YK600XGLC

Clean type: Medium type

Arm length 600mm  Maximum payload 4kg

Ordering method

YK600XGLC - 150

Model  Z axis stroke  Type

AXIS 350  250  150  100

Options: Hollow shaft  R32 (Min. cable bending radius)

Controller / Number of controllable axis

Controller: RCX340  Number: 4

Safety standard

OP. A

Dim. (OP. B)

OP. F2

OP. F3

OP. F4

Specify various controller setting items. RCX340

Controller

RCX340

Power capacity (VA)  Operation method

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

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

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

YK600XGLC

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)

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

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

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

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

Note 4: Class 10 (5㎛) equivalent to FED-STD-200D

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.
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)
4-M3 × 0.5 Depth 6
Tapped hole for user wiring 6-M3 × 0.5 Depth 6

4.450 × 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.

Hollow diameter: Φ11

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

Machine Harness

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

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

Connector for user wiring (No. 1 to 10 usable, cable clamp size: Φ13.1 to 15)
Cover with the caps provided when not used.

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

User tubing 1 (Φ4 black)
User tubing 2 (Φ4 red)
Insert the plug provided when not used.
User tubing 3 (Φ4 blue)
User tubing 4 (Φ4 white)

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

Hollow diameter: Φ11

The arm may be in contact with the machine harness in an area inside from the inner limit of this working envelope. So, do not operate the arm in this area.

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°

Do not move the cable.

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

Controller RCX340 ➤ 566