

YK250XGP

Dust-proof & drip-proof type



- Arm length 250mm
- Maximum payload 4kg

Ordering method

YK250XGP - 150 **S** **RCX340-4**

Model	Z axis stroke	Tool flange	Hollow shaft	Cable	Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
	150: 150mm	No entry: None F: With tool flange	S: With hollow shaft	3L: 3.5m 5L: 5m 10L: 10m								

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

Specifications

		X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length	100 mm	150 mm	150 mm	-
	Rotation angle	+/-129 °	+/-134 °	-	+/-360 °
AC servo motor output		200 W	150 W	50 W	100 W
Deceleration mechanism	Transmission method	Direct-coupled			
	Motor to speed reducer Speed reducer to output	Direct-coupled			
Repeatability ^{Note 1}		+/-0.01 mm	+/-0.01 mm	+/-0.004 °	
Maximum speed		4.5 m/sec	1.1 m/sec	1020 °/sec	
Maximum payload		4 kg			
Standard cycle time: with 2kg payload ^{Note 2}		0.50 sec			
R-axis tolerable moment of inertia ^{Note 3}		0.05 kgm ²			
Protection class ^{Note 4}		Equivalent to IP65 (IEC 60529)			
User wiring		0.2 sq x 10 wires			
User tubing (Outer diameter)		φ 4 x 4			
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length		Standard: 3.5 m Option: 5 m, 10 m			
Weight		21.5 kg			

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

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

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

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

Controller

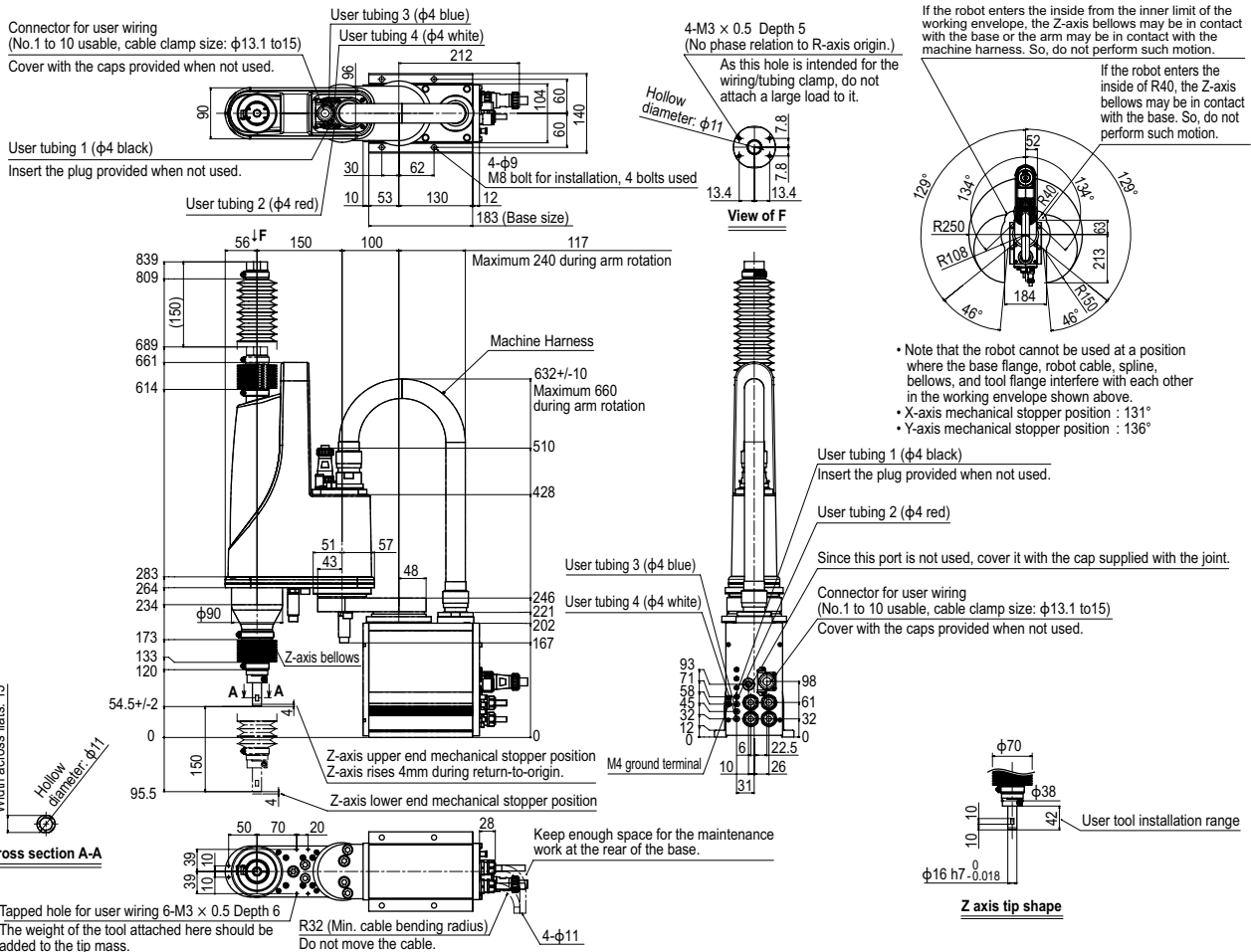
Controller	Power capacity (VA)	Operation method
RCX340	1000	Programming / I/O point trace / Remote command / Operation using RS-232C communication

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

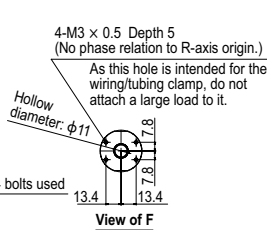
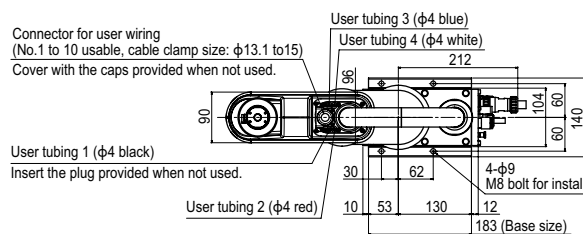
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

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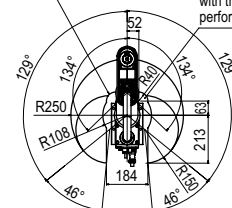


YK250XGP Tool flange mount type

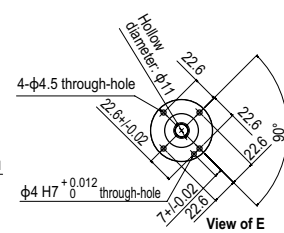
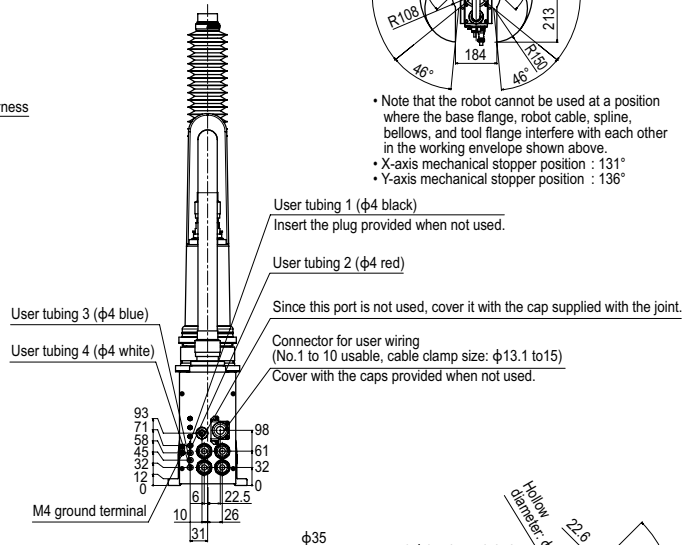
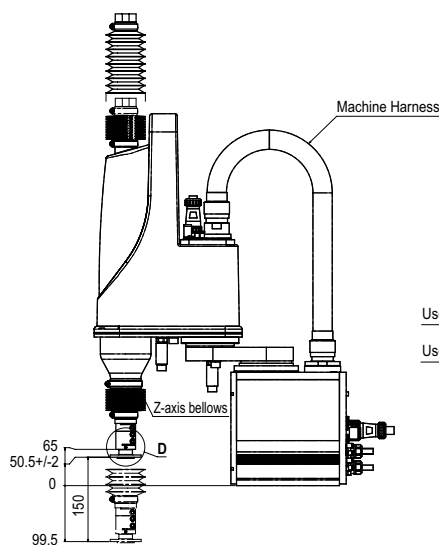


If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion.

If the robot enters the inside of R40, the Z-axis bellows may be in contact with the base. 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°



Tapped hole for user wiring 6-M3 \times 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.

4- $\phi 11$

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