**YK150XG** Standard type: Extra small type

- **Arm length**: 150mm
- **Maximum payload**: 1kg

### Ordering method

**YK150XG - 50 -**

<table>
<thead>
<tr>
<th>Model</th>
<th>YK150XG</th>
<th>50</th>
</tr>
</thead>
<tbody>
<tr>
<td>Cable</td>
<td>Controller / Safety standard</td>
<td>RCX340-4</td>
</tr>
</tbody>
</table>

Specify various controller setting items. RCX340 [566]

### 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>75</td>
<td>75</td>
<td>50</td>
<td></td>
</tr>
<tr>
<td>Rotation angle</td>
<td>+/-125°</td>
<td>+/-145°</td>
<td></td>
<td>+/-360°</td>
</tr>
<tr>
<td>AC servo motor output</td>
<td>30 W</td>
<td>30 W</td>
<td>30 W</td>
<td>30 W</td>
</tr>
</tbody>
</table>

- Deceleration mechanism
- Transmission method: Direct-coupled
- Speed reducer to output: Direct-coupled

**Controller**

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>300</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**: 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.

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**YK150XG**

- **Connector for user wiring (No. 1 to 8 usable, socket contact)**
- **J.S.T. Mfg Co., Ltd. SM connector (supplied)**
- **SYMA-057T-80.6 (supplied)**
- **Use the 1C12 crimping tool.**

- **Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy.**
- **If attaching wire or tube, make use of these air tubes.**
- **Doing so may degrade positioning accuracy.**
- **If the robot enters the inside of R12, the Z-axis upper end stopper may interfere with the base. Do not perform such motion.**
- **The Z-axis upper end stopper is in contact with the base in an area inside from the inner limit of this working envelope. So, do not perform any motion in this area.**

- **Working envelope**

- **X, Y-axis origin is at +0° with respect to front of robot base.**

- **When performing return-to-origin, move the axes counterclockwise in advance from the position shown above.**

---

**Controller**

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- **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:**