

YK220X

Standard type: Extra small type



- Arm length 220mm
- Maximum payload 1kg

Ordering method

YK220X - 100		RCX340-4								
Model	Z axis stroke 100: 100mm	Cable 3L: 3.5m 5L: 5m 10L: 10m	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

Specify various controller setting items. RCX340 ▶ **P.678**

Specifications

		X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length	111 mm	109 mm	100 mm	—
	Rotation angle	+/-120 °	+/-140 °	—	+/-360 °
AC servo motor output		50 W	30 W	30 W	30 W
Deceleration mechanism	Transmission method	Direct-coupled			
	Motor to speed reducer	Direct-coupled			
Speed reducer to output		Direct-coupled			
Repeatability ^{Note 1}		+/-0.01 mm	+/-0.01 mm	+/-0.004 °	
Maximum speed		3.4 m/sec	0.7 m/sec	1700 °/sec	
Maximum payload		1.0 kg			
Standard cycle time: with 0.1kg payload ^{Note 2}		0.42 sec			
R-axis tolerable moment of inertia ^{Note 3}		0.01 kgm ²			
User wiring		0.1 sq × 6 wires			
User tubing (Outer diameter)		φ 3 × 2			
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 (Excluding robot cable) ^{Note 4}		5.5 kg			
Robot cable weight		1.5 kg (3.5 m)	2.1 kg (5 m)	4.2 kg (10 m)	

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. 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

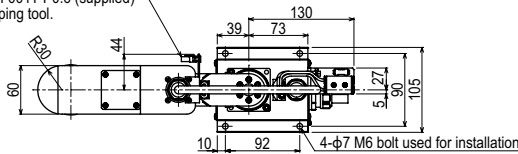
Controller	Power capacity (VA)	Operation method
RCX340	500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

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:
<https://global.yamaha-motor.com/business/robot/>

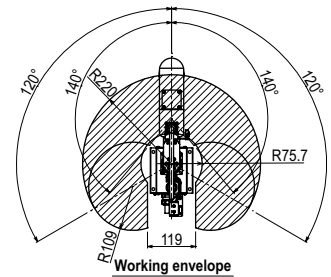
YK220X

Connector for user wiring
 (No. 1 to 6 usable, socket contact)
 J.S.T. Mfg Co., Ltd. SM connector
 SMR-6VB, pin SYM-001T-P0.6 (supplied)
 Use the YC12 crimping tool.

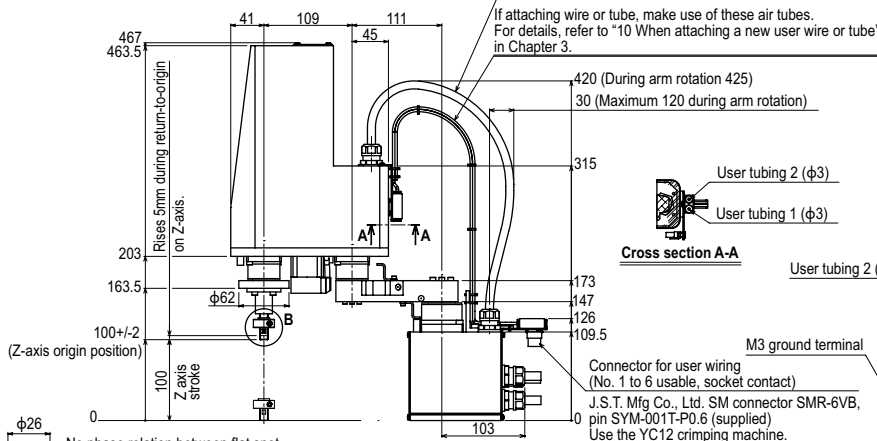


Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy.

If attaching wire or tube, make use of these air tubes. For details, refer to "10 When attaching a new user wire or tube" in Chapter 3.

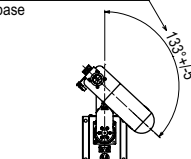


Working envelope



Cross section A-A

X-axis origin is at 0°/+5° with respect to front of robot base

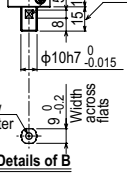


X, Y-axis origin position

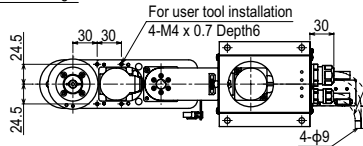
When performing return-to-origin, move the axes counterclockwise in advance from the position shown above.

No phase relation between flat spot and R-axis origin

User tool installation range



Details of B



R27 (Min. cable bending radius) Do not move the cable.

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

