YK150XG

Arm length 150mm
Maximum payload 1kg

■ Ordering method



Cable

RCX340-4

Specify various controller setting items. RCX340 ▶ P.508

Standard type: Tiny type

RCX240S - CE Marking - Expansion I/O - Network option - iVY System - Gripper - Battery

Specify various controller setting items. RCX240/RCX240S ▶ P.495

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		75 mm	75 mm	50 mm	-
specifications	Rotation angle		+/-125 °	+/-145 °	_	+/-360 °
AC servo motor output		30 W	30 W	30 W	30 W	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1		+/-0.0)1 mm	+/-0.01 mm	+/-0.004 °	
Maximum speed		3.4 n	n/sec	0.9 m/sec	1700 °/sec	
Maximum payload		1.0 kg				
Standard cycle time: with 0.1kg payload Note 2			0.33 sec			
R-axis tolerable moment of inertia Note 3			0.01 kgm²			
User wiring			0.1 sq × 8 wires			
User tubing (Outer diameter)			φ 4 × 2			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 2 m Option: 3.5 m, 5 m, 10 m			
Weight (Excluding robot cable) Note 4			4.0 kg			
Robot cable weight			0.9 kg (2 m) 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)			

	Controller							
ĺ	Controller	Power capacity (VA)	Operation method					
	RCX340 RCX240S	300	Programming / I/O point trace / Remote command / Operation using RS-232C communication					

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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 http://global.yamaha-motor.com/business/robot/

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. There are limits to acceleration coefficient settings. See P.536

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

