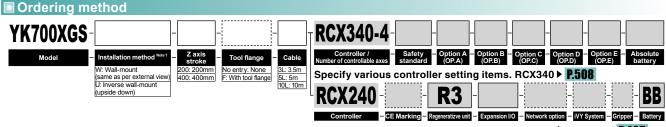
Arm length 700mm
Maximum payload 20kg



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

■ Controller

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	-
specifications	Rotation angle		+/-130 °	+/-130 °	-	+/-360 °
AC servo motor output			750 W	400 W	400 W	200 W
5	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
Deceleration mechanism	Transmission	Motor to speed reducer	Direct-coupled			
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.0	12 mm	+/-0.01 mm	+/-0.004 °
Maximum speed			8.4 m/sec 2.3 1.7 920 ° m/sec m/sec 480 °/s		920 °/sec (wall-mount) 480 °/sec (inverse wall-mount	
Maximum payload			20 kg (Standard specification), 19 kg (Option specifications)			
Standard cycle time: with 2kg payload Note 2			0.42 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm ²			
User wiring			0.2 sq × 20 wires			
User tubing (Outer diameter)			ф 6 × 3			
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			Z axis 200 mm: 50 kg Z axis 400 mm: 52 kg			

Controller | Power capacity (VA) | Operation method Programming / I/O point trace / RCX340 Remote command / 2500 RCX240-R3 Operation using RS-232C communication

Note. "Harmonic" and "Harmonic drive" are the registered trademarks of Harmonic Drive Systems Inc.

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

Note. Please consult YAMAHA when connecting other tubes and cables to the self-self-self-self-self-self-self-self-	upporting machine namess.	
User tubing 1 (\$\phi 6\$ Black) User tubing 2 (\$\phi 6\$ Red) User tubing 3 (\$\phi 6\$ Black) User tubing 5 (\$\phi 6\$ Black) User tubing 6 (\$\phi 6\$ Black) User tubing 6 (\$\phi 6\$ Black) User tubing 7 (\$\phi 6\$ Black) User tubing 8 (\$\phi 6\$ Black) User tubing 9 (\$\phi 6\$ Black) Us	D-sub connector for user wiring (No.1 to 20 usable) 119 R27 (Min. cable bending radius) Do not move the cable. Keep enough spart the maintenance with the prace of the top face of the top	work on
Z200mm 385 Stroke 35 71.5 85.5 127.3 196.3±2 Z-axis upper end mechanical stopper position 6mm rise during Z-axis return-to-origin Z-axis return-to-origin 8 Flat surface has no phase relation to R-axis origin. Z-axis lower end mechanical stopper position	247 0 (Base 0 10 10 10 10 10 10 10 10 10 10 10 10 1	Working envelope of left-handed system Working envelope of right-handed system Working envelope of right-handed system X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 132°
4-M4 x 0.7 through-hole for tool attact Four M4 x 10L binding screws are sujunt to not screw the screws in deeper the from bottom surface of arm. The weight of the tool attached here added to the tip mass. M20 x 2.5 Depth20 (Bottom of spline)	hment Cross section A-A hment polied. an 10mm Option: Tool flange mount type	YK700XGS Z200mm Stroke specification Stroke specification