Arm length 400mm
Maximum payload 4kg

■ Ordering method

YK400XE- 4

150

RCX340-4

■ Controller

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		225 mm	175 mm	150 mm	-	
specifications	Rotation angle		+/-132 °	+/-150 °	-	+/-360 °	
AC servo motor output			200 W	100 W	100 W	100 W	
Deceleration mechanism	Transmission method	Motor to speed reducer	Direct-coupled		Timing belt		
		Speed reducer to output	Direct-coupled			Timing belt	
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.01 °	
Maximum speed			6 m	/sec	1.1 m/sec	2600 °/sec	
Maximum payload			4 kg (Standard specification), 3 kg (Option specifications Note 4)				
Standard cycle time: with 2kg payload Note 2			0.41 sec				
R-axis tolerable moment of inertia Note 3			0.05 kgm² (0.5 kgfcms²)				
User wiring			0.2 sq × 10 wires				
User tubing (Outer diameter)			ф 4 × 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			17 kg				

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions and performing the coarse positioning arch operation.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.
Note 4. Maximum payload of option specifications (with user wiring/tubing through spline type) is 3kg.

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

Note. The movement range can be restricted by adding the X- and Y-axis mechanical stoppers. (The maximum movement range was set at shipment.)
See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a standard coordinate with high accuracy.

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

YK400XE-4		
4-M3 × 0.5 through-hole (No phase relation to R-axis origin.) As this hole is intended for the wiring/tubing clamp, do not attach a large load to it.	188 (Base size) 6 H7 + 0.012	09 150 150
φ27 + B 7.8 7.8 View of B	ф6 H7 ^{0.012} S 6-ф9 M8 bolt 4 or mor	for installation, re bolts are used.
495	48 175 225 Maximum 350 (123.5) 62.5	(512) Maximum 530 during arm rotation Working envelope X-axis mechanical stopper position : 134° Y-axis mechanical
Option User wiring and tubing routed through spline shaft.		User tubing 1 (\(\phi\)4 black) User tubing 2 (\(\phi\)4 red) User tubing 3 \[\begin{array}{c} \text{ST Win Co Lift} \\ \text{ST Win Co Lift} \end{array}
M (10th across 51) Hollow damages 611	O YAMAHA	User tubing 3 (\$\phi 4\$ blue) J.S.T. Mfg. Co.,Ltd. SM connector: SMR-11V-B Pin: SYM-001T-P0.6 is attached. Use AP-K2N for the crimping machine.
Cross section A-A 174.8 174.3 124.7+1-2 (Z-axis origin position) Z-axis upper end mechanical stopper position 10mm rise during return-to-origin	User tool installation range Value Value	144 139 134 User wiring connector (Numbers 1 to 10 are usable.) J.S.T. Mfg. Co.,Ltd. SM connector: SMR-11V-B Pin: SYM-001T-Pl.6 is attached. User wiring connector (Numbers 1 to 10 are usable.) User wiring connector (Numbers 1 to 10 are usable.) User wiring connector (Numbers 1 to 10 are usable.) User wiring connector (Numbers 1 to 10 are usable.)
Z-axis lower mechanical sposition	Standard type Tapped hole for user wiring: 6-M4 x 0.7 Depth 8 The weight of the tool attached here should be added to the tip mass. 40 7,25 Standard type 4-\$9 Min. cable bending radius R27(*) *Do not move the cable.	User tubing 1 (\$4\$ black) User tubing 2 (\$4\$ red) User tubing 3 (\$4\$ blue) Ti Keep enough space for the maintenance
		work at the rear of the base.

S: Sensor T: Stroke end

No entry: None S: With hollow shaft

Specify various controller setting items. RCX340 ▶ P.566

Our robot manuals (installation manuals) can be