YK700XG

Arm length 700mm
Maximum payload 20kg

Dust-proof & drip-proof type

■ Ordering method

YK700XGP

RCX340-4

Safety Option A Option B Option C Option D Option E standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E)

Controller

Programming / I/O point trace Remote command /

Specify various controller setting items. RCX340 ▶ **P.566**

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	_
specifications	Rotation angle		+/-130 °	+/-150 °	_	+/-360 °
AC servo motor output			750 W	400 W	400 W	200 W
Deceleration mechanism	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			8.4 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec
Maximum payload			20 kg			
Standard cycle time: with 2kg payload Note 2			0.52 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm²			
Protection class Note 4			Equivalent to IP65 (IEC 60529)			
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: 54 kg Z axis 400 mm: 56 kg			

RCX340 2500 Operation using RS-232C communication

Controller | Power capacity (VA) | Operation method

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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

Note 1. This is the value at a constant ambient temperature. (X/x axes)
Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

YK700XGP Connector for user wiring (No.1 to 20 usable, cable clamp size: ϕ 16 to18) Cover with the caps provided when not used. R205 ⊐ ജ -User tubing 1 (φ6 black) 4-ф14 M12 bolt for installation, 4 bolts used User tubing 2 (\$\phi6\$ red) 75 User tubing 3 (\$6 blue) 16 Note. Insert the plug provided when not used. 98 158 If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. 100 300 201 175(Maximum 300 during arm rotation) 63 128 Z400mm 1000 Stroke Working envelope of left-handed system Z200mm 800 (Maximum 920 during arm rotation) Stroke 568 476 440 Connector for user wiring 99 368 324 (No.1 to 20 usable 339.5 \$438 (Air release tubing) cable clamp size: φ16 to18) 254.5 Connect a hose and extend to a location not exposed to Cover with the caps provided 86 101 171 when not used 188.7+/-2 ф90 h7 -128 -119 -80 -60 -40 X axis joint air purge port (φ6) Stroke Y axis joint air purge port (φ6) M4 ground terminal If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with User tubing 1 (φ6 black)/ Z-axis lower end mechanical stopper position 25 | 40 User tubing 2 (\$\phi6\$ red) the machine harness. So, do not perform such motion. User tubing 3 (\$\phi6\$ blue) Insert the plug provided when not used Working envelope of right-handed system φ25 H7 0 0 · Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working ф90 h7 -0.035 envelope shown above X-axis mechanical stopper position: 132° P.C.D.364 Keep enough space for the Y-axis mechanical stopper position: 152° maintenance work at the rear of the base. 6-M5×0.8 Depth 11 10-M5x0.8 Depth 11
* There is no phase relation between each position of M5 tapped holes and R-axis origin position. R32 (Min. cable bending radius) Do not move the cable.

4-ф11