■ Ordering method

RCX340-4 YK800XGP Controller / Safety Option A Option B Option C Option D Option E Absolute er of controllable axes standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) Absolute Cable 3L: 3.5m 5L: 5m 10L: 10m 200: 200mm 400: 400mm

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

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		400 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 +/-0.0		+/-0.004 °		
Maximum speed		9.2 m	n/sec	2.3 m/sec 1.7 m/sec	920 °/sec		
Maximum payload			20 kg				
Standard cycle time: with 2kg payload Note 2			0.58 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: 56 kg Z axis 400 mm: 58 kg				

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

Controller Power capacity (VA) Operation method

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Programming / I/O point trace / Remote command /

Operation using RS-232C communication

■ Controller

RCX340

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,Y 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.

Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi16 \text{ to 18}\)  Cover with the caps provided when not used.  User tubing 1 (\$\phi6 \text{ black}\)  User tubing 2 (\$\phi6 \text{ red}\)  User tubing 3 (\$\phi6 \text{ told}\)  User tubing 3 (\$\phi6 \text{ told}\)  Note. Insert the plug provided when not used.  (Base size)  175 (Maximum 300 during arm rotation)  Working envelope of left-handed system		
No. 1s 20 usable, cashe camps provided when not used.    See   16   16   16   16   16   16   16	YK800XGP	
Working envelope of left-handed system  ### Working envelope of left-handed system  #### Working envelope of left-handed system  ##### Working envelope of left-handed system  ##### Working envelope of left-handed system  ##### Working envelope of left-handed system  ########## Working envelope of left-handed system  ###################################	(No.1 to 20 usable, cable clamp size: \$\phi 16\$ to 18)  Cover with the caps provided when not used.  User tubing 2 (\$\phi 6\$ red)  User tubing 3 (\$\phi 6\$ blue)  Note. Insert the plug provided when not used.  90  400  400  201  175 (Maximum 300 during arm rotation)	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 base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the base or the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the same of the arm may be in contact with the arm may be in contact w
(Maximum 920 during arm rotation)  568  476  338 (Air release tubing) 339.5 Cornect a hose and extend it associated and exposed to a docation not exposed to 254.5 water and dust.  219  228  238 (Air release tubing) 339.5 Cornect a hose and extend it associated exposed to 254.5 water and dust.  249  250  251  252  253  250  250  250  250  250  250	Stroke	
R32 (Min. cable bending radius) Do not move the cable.  R32 (Min cable bending radius)  Do not move the cable.  R34 (Min cable bending radius)  Do not move the cable.  R35 (Min cable bending radius)  A (Min cable ben	Maximum 920 during arm rotation)  (Maximum 920 during arm rotation)	Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi\$ 16 to 18)  Cover with the caps provided when not used.  128 80 60 40 0  If the robot enters the inside of R265 and comer of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the am may be in contact with
Z axis tip snape	R32 (Min. cable bending radius)  R30 not move the cable.	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 envelope shown above.  X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 152°  6-M5×0.8 Depth 11 There is no phase relation between each position of M5 tapped holes and R-axis pricing nosition.
	Z axis_	tip snape

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