YK1000XGS

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Wall mount / inverse type

Arm length 1000mm
Maximum payload 20kg

■ Ordering method

RCX340-4 YK1000XGS Tool flange

W: Wall mount (same as per external view) U: Inverse wall mount (upside down)

200: 200mm No entry: None 400: 400mm F: With tool flange

Specify various controller setting items. RCX340 ▶ P.566

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		600 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
mechanism	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.02 mm +/-0.01		+/-0.01 mm	+/-0.004 °
Maximum speed			10.6 m/sec 2.3 n/sec 920 °/sec (wall mount) 10.6 m/sec 2.3 n/sec 1.7 n/sec 480 °/sec (inverse wall mount) 10.6 m/sec 10.6			
Maximum payload			20 kg (Standard type), 19 kg (Tool flange mount type)			
Standard cycle time: with 2kg payload Note 2			0.49 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: 56 kg Z axis 400 mm: 58 kg			
Note 1. This is the value at a constant embient temperature. (V.V. even)						

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

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: 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 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

D-sub connector for User tubing 3 (\$6 Blue) user wiring (No.1 to 20 usable) User tubing 2 (\$\phi6 \text{ Red}) User tubing 1 (φ6 Black 111. **(** 25 User tubing 1 (φ6 Black), 160 R324 47 User tubing 2 (φ6 Red) D-sub connector for user wiring (No.1 to 20 usable) M4 ground terminal User tubing 3 (\$\phi6\$ Blue) R400 Keep enough space for the maintenance work on the top face of the base. 2400 R27 (Min. cable bending 128 radius)

Do not move the cable Z400mm Ball screw greasing hole Working envelope of left-handed system Stroke (520) 6-φ14 M12 bolt for installation, 6bolts used Z200mm Stroke 72 ф8Н7 97.5 97.5 245 (base size) through-hole R1000 (Base installation surface) R324 25 71.5 \ 85.5 -127.3 -132 -196.3+/-2 -137.3 150.5 R400 A I 186.3 (114) 202.8+/-2φ25h7 Z-axis upper end mechanical stopper position 6mm rise during Z-axis User tool installation range 198 B 200 ф50 h7-0.025 ф55 Standard type Hollow diameter: ϕ 18 Working envelope of right-handed system across Flat surface has no phase relation to R-axis origin. ф95 return-to-origin X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 152° Width 400 mechanical stopper position 4-M4 x 0.7 through-hole for tool attachment 0 4-M4 X 0.7 inrough-hole for too altachment. Four M4 x 10.b inding screws are supplied. Do not screw the screws in deeper than 10mm from bottom surface of arm. The weight of the tool attached here should be added to the tip mass. Cross section A-A Option: Tool flange mount type

4-φ6.6 through-hole

3 / 100

View of B

φ6 H7 +0.012 through-hole

15 36 M20 x 2.5 Depth20 (Bottom of spline)

Controller