YK350TW

Orbit type

- Arm length 350mm
- Maximum payload 5kg

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Model	Z axis stroke	Tool flange	Hollow shaft	Cable	Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
	130: 130mm	No entry: None F: With tool flange	No entry: None S: With hollow shaft	3L: 3.5m 5L: 5m 10L: 10m								

Specify various controller setting items. RCX340 ▶ P.566

Specifications

			X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length		175 mm	175 mm	130 mm	-
	Rotation angle		+/-225 °	+/-225 °	-	+/-720 °
AC servo motor output			750 W	400 W	200 W	105 W
Deceleration mechanism	Transmission method	Motor to speed reducer	Timing belt	Direct-coupled	Timing belt	Timing belt
		Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.01 °
Maximum speed			5.6 m/sec		1.5 m/sec	3000 °/sec
Maximum payload Note 2			5 kg			
Standard cycle time: with 1kg payload Note 3			0.32 sec			
R-axis tolerable moment of inertia Note 4		Rated	0.005 kgm²			
		Maximum	0.05 kgm²			
User wiring			0.15 sq × 8 wires			
User tubing (Outer diameter)			ϕ 6 × 2			
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			26 kg			

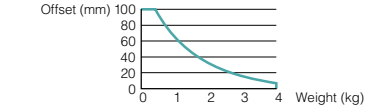
Note 1. This is the value at a constant ambient temperature.
Note 2. Tool flange specifications (option) are 4 kg.
Note 3. When moving a 1 kg load back and forth 300mm horizontally and 25mm vertically (rough positioning arch motion).
Note 4. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

Controller

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

R-axis moment of inertia (load inertia)

Recommended positional relationship between the load weight and the offset amount from the center of the R-axis (center of gravity position)

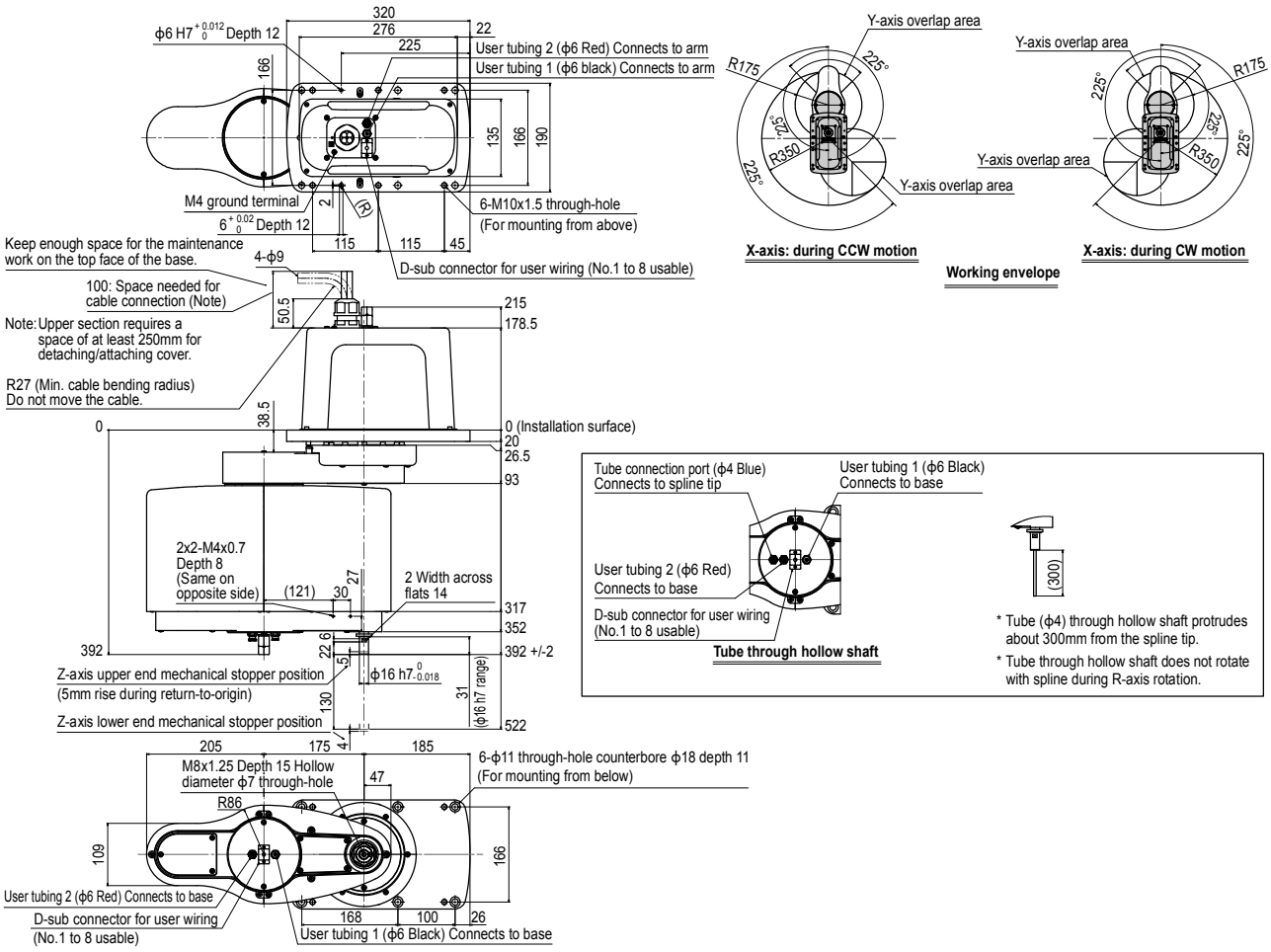


Note. When the payload exceeds 4kg, it is predicted that the R-axis moment of inertia may exceed the rated value. So, make proper parameter setting.

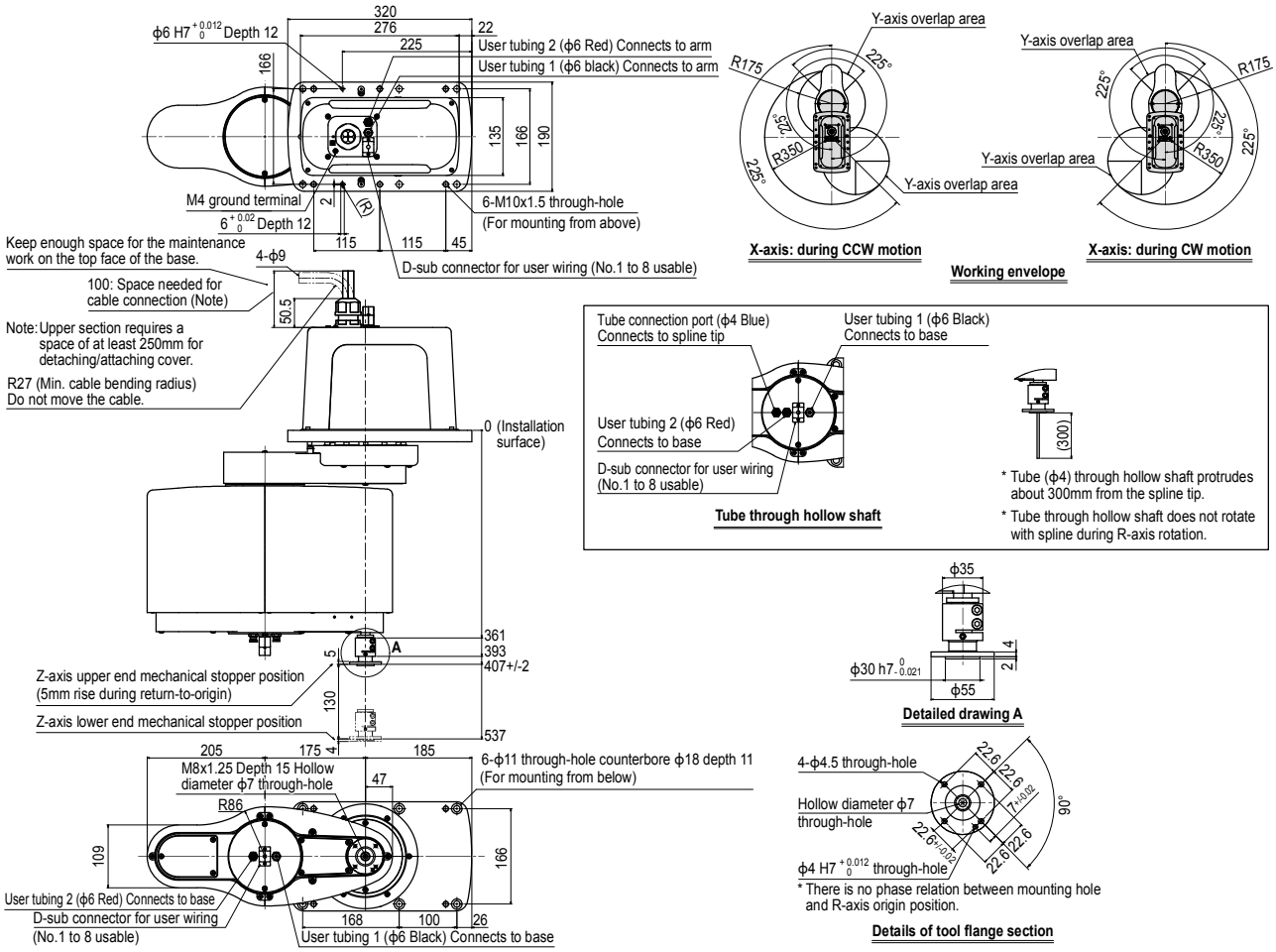
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

YK350TW



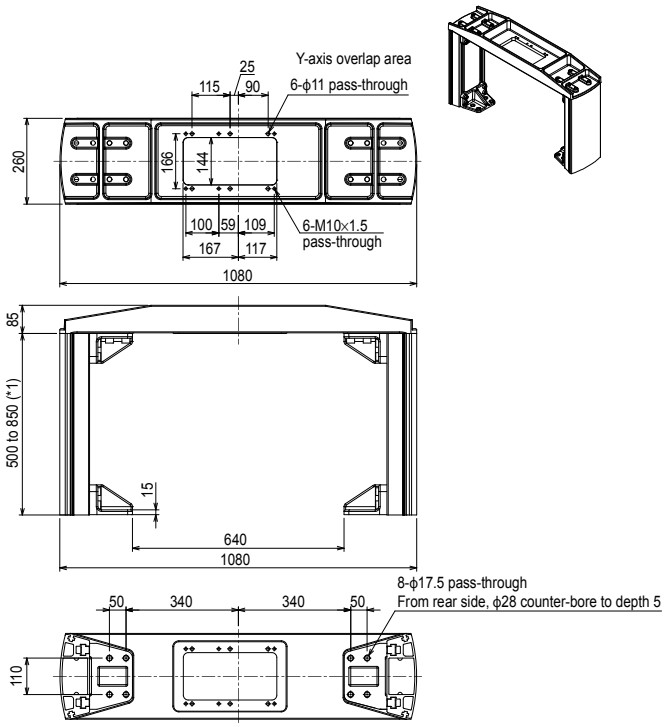
YK350TW Tool flange mount type



Dedicated mounting bracket for the YK-TW <BASE POST ASSY.>

The YK-TW can be easily installed on top of a customer-provided stand.

External diagram for the YK350TW



The mounting bracket is assembled by the customer. Refer to the included assembly diagram for assembly.

*1. Identical to the height of the robot mounting surface. The height of the stand can be selected at a 50 mm pitch.

Height (mm)	Model	Unit weight (kg)
500	KDU-M6100-P0	46
550	KDU-M6100-50	48
600	KDU-M6100-R0	50
650	KDU-M6100-60	51
700	KDU-M6100-S0	54
750	KDU-M6100-70	55
800	KDU-M6100-T0	57
850	KDU-M6100-80	59

* YK350TW and YK500TW are parts in common.
* The top plate by itself weighs 19 kg.

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