## YK500XC

Standard type: Medium type

Arm length 500mm
Maximum payload 10kg

■ Ordering method

YK500XG

Z axis stroke - Tool flange 200: 200mm No entry: None S: With tool flange

Cable 3L: 3.5m

**RCX340-4** 

Option B — Option C(OP.B) (OP.C)

Controller

RCX340

Controller | Power capacity (VA) | Operation method

1700

Programming / I/O point trace Remote command /

Operation using RS-232C communication

Specify various controller setting items. RCX340 ▶ P.566

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		200 mm	300 mm	200 mm 300 mm	-
specifications	Rotation angle		+/-130 °	+/-145 °	-	+/-360 °
AC servo motor output			400 W	200 W	200 W	200 W
Deceleration mechanism	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			7.6 m/sec		2.3 m/sec 1.7 m/sec	1700 °/sec
Maximum payload			10 kg (Standard type), 9 kg (Tool flange mount type)			
Standard cycle time: with 2kg payload Note 2			0.42 sec			
R-axis tolerable moment of inertia Note 3			0.30 kgm²			
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			30 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. Note. To set the standard coordinates with high accuracy, use a

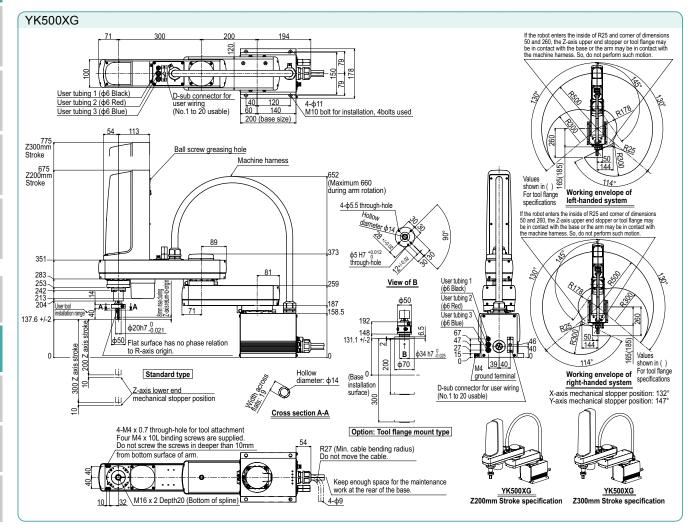
standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 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



Controller