YK800XGS

Wall mount / inverse type

Arm length 800mm
Maximum payload 20kg

Ordering method

Druering method		
YK800XGS-	- RCX340-4	
Model Installation method Notes W: Wall mount (same as per external view U: Inverse wall mount (upside down)	Stude 200: 200mm No entry: None BL: 3.5m	

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 specifications Rotation angle			400 mm	400 mm	200 mm 400 mm	-		
		+/-130 °	+/-145 °	_	+/-360 °			
AC servo motor output		750 W	400 W	400 W	200 W			
	Transmission	Motor to speed reducer	Direct-coupled					
	method	Speed reducer to output	Direct-coupled					
Repeatability Note 1		+/-0.0	+/-0.02 mm		+/-0.004 °			
Maximum speed		9.2 m/sec 2.3 1.7 920 °/sec (wall more m/sec m/sec 480 °/sec (inverse wall n		920 °/sec (wall mount) 480 °/sec (inverse wall mount)				
Maximum payload			20 kg (Standard type), 19 kg (Tool flange mount type)					
Standard cycle time: with 2kg payload Note 2			0.48 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: 52 kg Z axis 400 mm: 54 kg					
Note 1 This is the	value at a constar	at ambient temperature (XX	/ avaa\					

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

Controller

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.

YK800XGS User tubing 3 (\$\phi6\$ Blue)
User tubing 2 (\$\phi6\$ Red)
User tubing 1 (\$\phi6\$ Black) D-sub connector for user wiring (No.1 to 20 usable) 41 R241 User tubing 1 (ф6 Black) D-sub connector for User tubing 2 (\$\phi6\$ Red) R400 Keep enough space for the maintenance work on the top user wiring \(No.1 to 20 usable) M4 ground terminal User tubing 3 (\$\phi6\$ Blue) 128 R27 (Min. cable bending radius) Z400mm Stroke 585 Do not move the cable face of the base Ball screw greasing hole (520) 6-φ14 M12 bolt for installation, Working envelope of left-handed system 4-ф9 Z200mm 385 Stroke 6bolts used 247 847 5 97.5 97.5 245 (base size) ф8Н7 through-hole 0 (Base 0 30 installation 65.5 surface) R24 85.5 127.3 R400 150.5 186.3 202.8+/-2 132 196.3+/-2 79 P.400 φ25h7 (114) User tool installation range Z-axis upper end mechanical stopper position 6mm rise B Hollow diameter: ϕ 18 ф55 Standard type 200 φ50 h7 -0.025 Flat surface has no phase Width across flats: 24 relation to R-axis origin. Working envelope of right-handed system ф95 during Z-axis 145 return-to-origin Z-axis lower end X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 147° 9 mechanical stopper position 4-M4 x 0.7 through-hole for tool attachment Four M4 x 10L binding screws are supplied. Do not screw the screws in deeper than 10mm Cross section A-A Option: Tool flange mount type from bottom surface of arm 4-φ6.6 through-hole The weight of the tool attached here should be added to the tip mass. (0) φ6 H7 +0.012 through-hole M20 x 2.5 Depth20 (Bottom of spline) V, View of B