YK800XG

Dust-proof & drip-proof type

Arm length 800mm
Maximum payload 20kg

■ Ordering method

YK800XGP RCX340-4 Safety Option A Option B Option C Option D Option E Absorption Standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt

Specify various controller setting items. RCX340 ▶ P.678

			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	+/-0.004 °
Maximum speed			9.2 n	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			

I/O point trace Remote command / RCX340 2500 Operation using RS-232C communication

Controller | Power capacity (VA) | Operation method

Programming /

■ 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

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.

YK800XGP Connector for user wiring (No.1 to 20 usable, cable clamp size: ϕ 16 to18) Cover with the caps provided when not used. R205 User tubing 1 (\$\phi6\$ black)/ 145 4-φ14 M12 bolt for installation, 4 bolts used User tubing 2 (\phi 6 red) / User tubing 3 (\phi 6 blue) / 260 (Base size) Note. Insert the plug provided when not used. If the robot enters the inside of R265 and of 158 400 400 201 dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with 175(Maximum 300 during arm rotation) 63 128 Z400mm 1000 Stroke the machine harness. So, do not perform such motion. Working envelope of left-handed system Z200mm 800 (Maximum 920 during arm rotation) 568 Connector for user wiring 476 ψυσ (Air release tubing)
339.5 Connect a hose and extend it to a location not exposed to 254.5 water and dust. 440 (No 1 to 20 usable able clamp size: \$\dightarrow\$16 to 18) Cover with the caps provided when not used. Ħ 188.7+/-2 ф90 h7 X axis joint air purge port (φ6) Z-axis stroke Y axis joint air purge port (φ6) M4 ground terminal 2 Z-axis lower end mechanical stopper position User tubing 1 (φ6 black)/ 119 If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be User tubing 2 (\$\phi6\$ red) User tubing 3 (\$\phi 6 blue) contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. Insert the plug provided when not used Working envelope of right-handed system eep enough space for the ф25 Н7 maintenance work at the real 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. ф90 h7 -0.035 of the base. P.C.D.36 X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 152° R32 (Min. cable bending radius) Do not move the cable. 4-φ11 112 6-M5×0.8 Depth 11
10-M5×0.8 Depth 11
10-M5×0.8 Depth 11
*There is no phase relation between each position of M5 tapped holes and R-axis origin position.