YK1000XGP

Dust-proof & drip-proof type

Arm length 1000mm
Maximum payload 20kg

■ Ordering method

YK1000XGP RCX340-4 200: 200mm 400: 400mm

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specific	cations					
			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
	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			10.6 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec
Maximum payload			20 kg			
Standard cycle time: with 2kg payload Note 2			0.59 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm ²			
Protection class Note 4			Equivalent to IP65 (IEC 60529)			
User wiring (sq × wires)			0.2 × 20			
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: 60 kg Z axis 400 mm: 62 kg			
Note 1. This is the v	alue at a constar	nt ambient temperature. (X.Y	axes)			

■ 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

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/

where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above.

X-axis mechanical stopper position: 132°

Y-axis mechanical stopper position: 152°

10-M5×0.8 Depth 11
* There is no phase relation between each position of M5 tapped holes

ф90 h7 -0.035

Z axis tip shape and R-axis origin position.

6-M5×0.8 Depth 11

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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.

Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi\$16 to 18) Cover with the caps provided when not used. 66 User tubing 1 (\phi 6 black)/ 4-ф14 M12 bolt for installation, 4 bolts used PROD 145 User tubing 2 (\phi 6 red)
User tubing 3 (\phi 6 blue) 9 260 (Base size) 16 Note. Insert the plug provided when not used. 600 If the robot enters the inside of the corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. 201 63 128 175(Maximum 300 during arm rotation) 1000 Z400mm Stroke Working envelope of left-handed system (Maximum 920 during arm rotation) 568 476 (No.1 to 20 usable, cable clamp size: \$\phi16\$ to18) 440 339.5 ¢38 (Air release tubing) 99 239.5 Connect a hose and extend 254.5 to a location not exposed to water and dust. Cover with the caps provided R400 φ90 h7 86 101 219 135 188.7+/-2 S Stroke

Xis Stroke

Z-aus ries

Gmm during

Refurn-borigin X axis joint air purge port (φ6) Y axis joint air purge port (φ6) 138° M4 ground terminal If the robot enters the inside of the corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the machine harmess. So, do not perform such motion. User tubing 1 (φ6 black) Z-axis lower end mechanical stopper position User tubing 2 (\$6 red) User tubing 3 (\$\phi6\$ blue) Insert the plug provided when not used Working envelope of right-handed system φ25 H7 ^{+0.021} · Note that the robot cannot be used at a position

Keep enough space for the maintenance work at the rear of the base.

4-ф11

P.C.D.36

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R32 (Min. cable bending radius) Do not move the cable