Arm length 700mm
Maximum payload 20kg

■ Ordering method



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

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		300 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			8.4 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			0.52 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: 54 kg Z axis 400 mm: 56 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

Controller Power capacity (VA) Operation method

2500

Programming / I/O point trace / Remote command /

Operation using RS-232C communication

■ Controller

RCX340

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 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.

VIZZONOD	
YK700XGP	
Connector for user wiring (No.1 to 20 usable, cable clamp size: \$416 to18) Cover with the caps provided when not used. User tubing 1 (\$46 black) User tubing 2 (\$66 red) User tubing 3 (\$66 blue) Note. Insert the plug provided when not used. (Base size)	\$ R205
90 400 300 201 Z400mm 1000 63 128 Stroke 175 (Maximum 300 during arm rotation)	If the robot enters the inside of R266 and corner of dimensions 98 and 400, the Zawist 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.
7200mm 800	Working envelope of left-handed system
Stroke 800 Stroke 800 440 440 368 324 188.7+/-2 999 339.5 \$\phi_{38}\$ (Air release tubing) 254.5 \$\frac{5}{5}\$ Connect a hose and extend it to a location not exposed to to a location not exposed to water and dust. X axis joint air purge port (\$\phi_{6}\$) Y axis joint air purge port (\$\phi_{6}\$) W4 ground terminal User tubing 1 (\$\phi_{6}\$ black) User tubing 2 (\$\phi_{6}\$ ed) 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.
miser the plug provided when not used.	Working envelope of right-handed system φ25 H7 ^{+0.021} 0 Note that the robot cannot be used at a position where the base flange, robot cable, soline, and
Keep enough space for the maintenance work at the rear of the base.	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° 6-M5×0.8 Depth 11 10-M5×0.8 Depth 11 1 There is no phase relation between each position of M5 tapped holes
R32 (Min. cable bending radius) Do not move the cable. Z axis till Z axis till	and R-axis origin position