YK350XGP

Dust-proof & drip-proof type

Arm length 350mm
Maximum payload 4kg

Ordering method

YK350XGP-150

No entry: None F: With tool flange

RCX340-4

Safety Option A Option B Option C Option D Option E Absolute Standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) battery

Specify various controller setting items. RCX340 ▶ P.678

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		200 mm	150 mm	150 mm	-
specifications	Rotation angle		+/-129 °	+/-134 °	-	+/-360 °
AC servo motor output			200 W	150 W	50 W	100 W
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			5.6 m	n/sec	1.1 m/sec	1020 °/sec
Maximum payload			4 kg			
Standard cycle time: with 2kg payload Note 2			0.52 sec			
R-axis tolerable moment of inertia Note 3			0.05 kgm²			
Protection class Note 4			Equivalent to IP65 (IEC 60529)			
User wiring			0.2 sq × 10 wires			
User tubing (Outer diameter)			ф 4 × 4			
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			22 kg			
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Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1000 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/

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.

YK350XGP If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such metics. User tubing 3 (\$4 blue) 4-M3 × 0.5 Depth 5 (No phase relation to R-axis origin.) Connector for user wiring (No.1 to 10 usable, cable clamp size: φ13.1 to15) User tubing 4 (\$4 white) As this hole is intended for the wiring/tubing clamp, do not attach a large load to it. Cover with the caps provided when not used Hollow diameter: φ1 such motion. ((©)) User tubing 1 (φ4 black) Φ 62 4-ф9 M8 bolt for installation, 4 bolts used Insert the plug provided when not used. 30 R350 User tubing 2 (\$\phi4\$ red)/ 10 53 130 183 (Base size) View of F 56↓**F** 200 117 Maximum 190 during arm rotation 839 809 76° 15 (120) Machine Harness Note that the robot cannot be used at a position where the base flange, robot cable, spline, bellows, and tool flange interfere with each other in the working envelope shown above.
X-axis mechanical stopper position: 131°
Y-axis mechanical stopper position: 136° 689 661 614 Maximum 660 during arm rotation User tubing 1 (φ4 black) 510 Insert the plug provided when not used. 428 User tubing 2 (\$4 red) 57 Since this port is not used, cover it with the cap supplied with the joint. 43 User tubing 3 (\$\phi4\$ blue) 48 283 264 Connector for user wiring (No.1 to 10 usable, cable clamp size: ϕ 13.1 to15) 234 User tubing 4 (\$4 white ф90 Cover with the caps provided when not used. 167 Z-axis bellows A TA 54.5+/-2 across flats: 0 150 ф70 Z-axis upper end mechanical stopper position M4 ground terminal Z-axis rises 4mm during return-to-origin. 10 26 95.5 31 Z-axis lower end mechanical stopper position 50 70 20 Keep enough space for the maintenance User tool installation range work at the rear of the base. Cross section A-A ((()) ф16 h7 _{-0.018} Z axis tip shape Tapped hole for user wiring 6-M3 \times 0.5 Depth 6 / The weight of the tool attached here should be R32 (Min. cable bending radius) / Do not move the cable. added to the tip mass.

