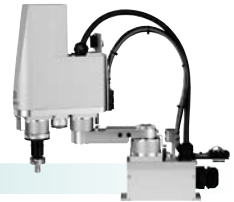


YK180XG

Standard type: Tiny type



- Arm length 180mm
- Maximum payload 1kg

Ordering method

YK180XG - 50

Model	Z axis stroke	Cable
	50: 50mm	2L: 2m
		3L: 3.5m
		5L: 5m
		10L: 10m

RCX340-4

Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
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Specify various controller setting items. RCX340 ▶ **P.502**

RCX240S

Controller	CE Marking	Expansion I/O	Network option	iVY System	Gripper	Battery
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Specify various controller setting items. RCX240/RCX240S ▶ **P.489**

Specifications

		X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length (mm)	105	75	50	-
	Rotation angle (°)	+/-125	+/-145	-	+/-360
AC servo motor output (W)		30	30	30	30
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Direct-coupled			
	Motor to speed reducer	Direct-coupled			
	Speed reducer to output	Direct-coupled			
Repeatability ^{Note 1} (XYZ: mm) (R: °)		+/-0.01		+/-0.01	+/-0.004
Maximum speed (XYZ: m/sec) (R: °/sec)		3.3		0.9	1700
Maximum payload (kg)		1.0			
Standard cycle time: with 0.1kg payload ^{Note 2} (sec)		0.33			
R-axis tolerable moment of inertia ^{Note 3} (kgm ²)		0.01			
User wiring (sq × wires)		0.1 × 8			
User tubing (Outer diameter)		φ4 × 2			
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length (m)		Standard: 2 Option: 3.5, 5, 10			
Weight (kg) (Excluding robot cable) ^{Note 4}		4.1			
Robot cable weight		0.9kg (2m) 1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
 Note 2. When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
 Note 3. There are limits to acceleration coefficient settings. See P.528.
 Note 4. The total robot weight is the sum of the robot body weight and the cable weight.

Controller

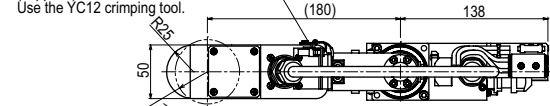
Controller	Power capacity (VA)	Operation method
RCX340 RCX240S	500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

Note. "Harmonic" and "Harmonic drive" are the registered trademarks of Harmonic Drive Systems Inc.
 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.

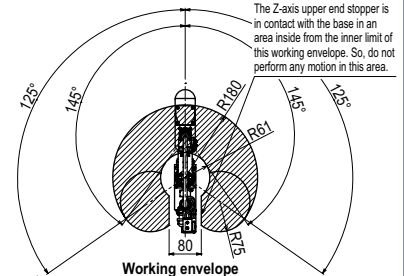
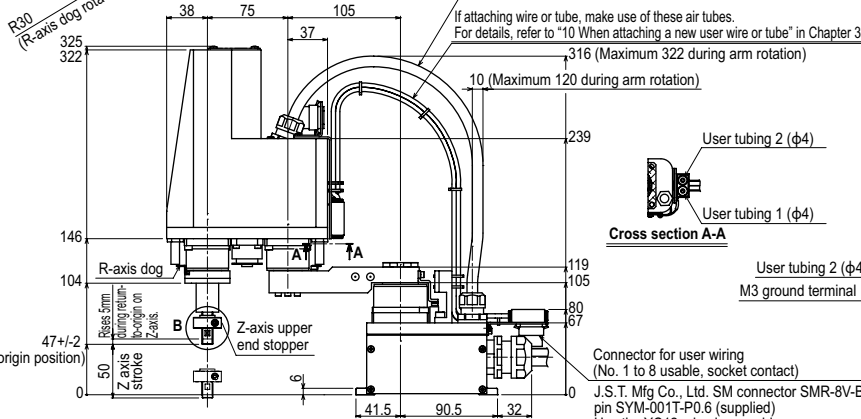
Our robot manuals (installation manuals) can be downloaded from our website at the address below:
<http://global.yamaha-motor.com/business/robot/>

YK180XG

Connector for user wiring (No. 1 to 8 usable, socket contact)
 J.S.T. Mfg Co., Ltd. SM connector SMR-8V-B, pin SYM-001T-P0.6 (supplied)
 Use the YC12 crimping tool.

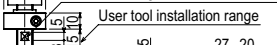


Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy.
 If attaching wire or tube, make use of these air tubes. For details, refer to "10 When attaching a new user wire or tube" in Chapter 3.

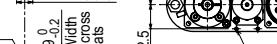


Working envelope
 X, Y-axis origin is at ±5° with respect to front of robot base
 When performing return-to-origin, move the axes counterclockwise in advance from the position shown above.

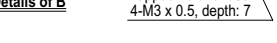
No phase relation between flat spot and R-axis origin
 User tool installation range



Hollow diameter: φ4
 Width across flats: 9.0 ± 0.2



Tapped hole for user 4-M3 × 0.5, depth: 7



2-φ5.5 through-hole (Use four M5 mounting bolts.)
 R27 (Min. cable bending radius)
 Do not move the cable.



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

