YK250XG

Arm length 250mm
Maximum payload 5kg

Specifications

specifications Rotation angle

Deceleration Transmission

User tubing (Outer diameter)

method

Standard cycle time: with 2kg payload Note

Note 1. This is the value at a constant ambient temperature. (X,Y axes) Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

User tubing 1 (\$\phi4\$ black)

User tubing 2 (\$\phi4\$ red)

User tubing 3 (\$4 blue)

AV.

Z-axis lower end

mechanical stopper position

70

ф16 h7-0.018 ф35

R-axis tolerable moment of inertia Note 3

AC servo motor output

mechanism

Repeatability

User wiring

Travel limit

Weight

Maximum speed

Maximum payload

Robot cable length

YK250XG

Ø

Cross section B-B

661

614

183

120

Tapped hole for user wiring 6-M3 × 0.5 Depth 6

138 5+/-2

User tool installation

range

across flat 15

W Ø

Cross section A-A

The weight of the tool attack added to the tip mass.

Axis

YK250XG - 150

Cable

RCX340-4

Controller | Power capacity (VA) | Operation method

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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting iid (ontion). Pafer to the user's

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

downloaded from our website at the address below

https://global.yamaha-motor.com/business/robot/

The arm may be in contact with the machine harness in an area inside from the inner limit of this working envelope.

Note that the robot cannot be used at a position where the base flange or robot cable interferes with the spline in the working envelope shown above.
X-axis mechanical stopper position: 142°

**The content of the co

ф27

Y-axis mechanical stopper position : 146°

4-M3 × 0.5 through-hole (No phase relation to R-axis origin.) As this hole is intended for the wiring/tubing clamp, do not

780.5

138.5 +/-2

20

Option: User wiring/tubing through spline type

attach a large load to it.

D-sub connector for user wiring (No. 1 to 10 usable)

So, do not operate the arm in this area.

Our robot manuals (installation manuals) can be

1000

Programming /

I/O point trace /

Remote command /

Operation using RS-232C

communication

■ Ordering method

Z-axis

150 mm

50 W

+/-0.01 mm

1.1 m/sec

Direct-coupled

Direct-coupled

5 kg (Standard specification), 4 kg (Option specifications Note 4

0.43 sec

0.05 kgm2 (0.5 kgfcms2)

0.2 sq × 10 wires

ф 4 × 3

1.Soft limit 2.Mechanical stopper (X.Y.Z axis)

Standard: 3.5 m Option: 5 m, 10 m

18.5 ka

R-axis

+/-360°

100 W

+/-0.004 °

1020 °/sec

■ Controller

7.8

7.8

View of F

7.8



Motor to speed reduce

Speed reducer to output

Arm length

Tool flange - Hollow shaft No entry: None
F: With tool flange

No entry: None
S: With hollow shaft

X-axis

100 mm

+/-140°

200 W

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg

me?

142

62

Machine

50 88

D-sub connector for user wiring (No. 1 to 10 usable)

100

57

Y-axis

150 mm

+/-144

150 W

+/-0.01 mm

4.5 m/sec

8 8

lg

138 (Base size)

M8 bolt for installation, 4 bolts used

129 Maximum 280 during arm rotation

Maximum 660 during arm rotation

User tubing 1 (φ4 black)

User tubing 2 (ф4 red) User tubing 3 (\$4 blue)

M4 ground terminal /

468

428

Z-axis upper end mechanical stopper position 4mm rise during Z-axis return-to-origin

4-φ9/

R27 (Min. cable bending radius)

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

Do not move the cable

Specify various controller setting items. RCX340 ▶ P.678

Standard type: Small type

RCX340



