## Standard type: Small type

## **LOW COST HIGH PERFORMANCE MODEL**

Arm length 400mm
Maximum payload 4kg

Ordering method

YK400XE- 4

150

No entry: None S: With hollow shaft

RCX340-4

Specify various controller setting items. RCX340 ▶ P.566

■ Specifications								
			X-axis	Y-axis	Z-axis	R-axis		
Axis specifications	Arm length		225 mm	175 mm	150 mm	-		
	Rotation angle		+/-132 °	+/-150 °	-	+/-360 °		
AC servo motor output			200 W	100 W	100 W	100 W		
Deceleration mechanism	Transmission	Motor to speed reducer	Direct-coupled		Timing belt			
	method	Speed reducer to output	Direct-coupled		Timing belt			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.01 °		
Maximum speed			6 m	/sec	1.1 m/sec	2600 °/sec		
Maximum payload			4 kg (Standard specification), 3 kg (Option specifications Note 4)					
Standard cycle time: with 2kg payload Note 2			0.41 sec					
R-axis tolerable moment of inertia Note 3			0.05 kgm² (0.5 kgfcms²)					
User wiring			0.2 sq × 10 wires					
User tubing (Outer diameter)			ф 4 × 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			17 kg					

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 and performing the coarse positioning arch operation.

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

Note 4. Maximum payload of option specifications (with user wirring/tubing through spline type) is 3kg.

■ Controller Controller Power capacity (VA) Operation method Programming / Remote command / Operation RCX340 1000 using RS-232C communication

Note. The movement range can be restricted by adding the X- and Y-axis mechanical stoppers. (The maximum movement range was set at shipment.)
See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a standard coordinate with high accuracy.

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/

YK400XE-4		
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 attach a large load to it.		
φ27 ↓ B 7.8 View of B	φ6 H7 *0.012	polts are used.
4955	48 175 225 Maximum 350 dt.	Working envelope  X-axis mechanical stopper position : 134° Y-axis mechanical stopper position : 154°
Option User wiring and tubing routed through spline shaft.		User tubing 1 (\$\phi\$ black) User tubing 2 (\$\phi\$ 4 red) User tubing 3 (\$\phi\$ 4 blue)  User tubing 3 (\$\phi\$ 4 blue)  1.5.T. Mfg. Co., Lid. SM connector. SMR-11V-B Pin: SYM-001T-P0.6 is
187.8 Cross section A-A 174.8 174.3 124.7+/-2 (Z-axis origin position)	WAMAHA  S User tool installation range	181 144 139 134 User wiring connector (Numbers 1 to 10 are usable.)
Z-axis upper end mechanical stopper position of mise during return-to-origin	99 416 h7-0.018	SM connector: SMR-11V-B Pin: SYM-001T-P0.6 is attached. Use AP-K2N for the crimping machine.  User tubing 1 (64 black) User tubing 2 (64 red) / 20  19.5
Z-axis lower mechanical s position	Tapped hole for user wiring: 6.M4 × 0.7 Depth 8 The weight of the tool attached here should be added to the tip mass.  40 7 25  40 7 25  40 7 25  40 7 25	User tubing 3 (\$\phi \text{blue}\$) \( \frac{22}{2} \frac{1}{115.3} \)  Keep enough space for the maintenance work at the rear of the base.
XY-axis origin position (Stroke end specification) When performing return-to-origin, move the X-axis and Y-axis counterclockwise and dlockwise, respectively in advance from the position shown above.	51	

