

YK400XEC-4

Clean type: Small type

LOW COST HIGH PERFORMANCE MODEL



- Arm length 400mm
- Maximum payload 4kg

Ordering method

YK400XEC	4	150			RCX340-4			
Model	Maximum payload	Z axis stroke	Brake release switch	Cable	Controller / Number of controllable axes	Safety standard	Option A to E (OP.A to E)	Absolute battery
			No entry: None BS: With brake release switch	3L: 3.5m 5L: 5m 10L: 10m				

Specify various controller setting items.

Basic specifications

		X axis	Y axis	Z axis	R axis
Axis specifications	Arm length	225 mm	175 mm	150 mm	-
	Rotation angle	+/-132 °	+/-145 °	-	+/-360 °
AC servo motor output		200 W	100 W	100 W	100 W
Deceleration mechanism	Transmission method	Direct-coupled		Timing belt	
	Motor to speed reducer Speed reducer to output	Direct-coupled		Timing belt	
Repeatability ^{Note 1}		+/-0.01 mm		+/-0.01 mm	+/-0.01 mm
Maximum speed		6 m/sec		1.1 m/sec	2600 °/sec
Maximum payload		4 kg			
Standard cycle time: with 2kg payload ^{Note 2}		0.45 sec			
R-axis tolerable moment of inertia ^{Note 3}		0.05 kgm ²			
User wiring		0.2 sq × 10 wires			
User tubing		φ 4 × 3			
Travel limit		1.Soft limit, 2.Mechanical stopper (X, Y, Z axes)			
Robot cable length		Standard: 3.5 m Option: 5 m, 10 m			
Weight		18 kg			
Degree of cleanliness		ISO CLASS 4 (ISO14644-1)			
Suction air flow		55 (Nl/min) ^{Note 4}			

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. Set within the range of ±1 Nl/min if the suction amount is not appropriate, the cleanliness may be adversely affected or the bellows may be deformed.

Controller

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

Note. User wiring and user tubing can be passed through from the top of the Z-axis shaft to the tip.

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.

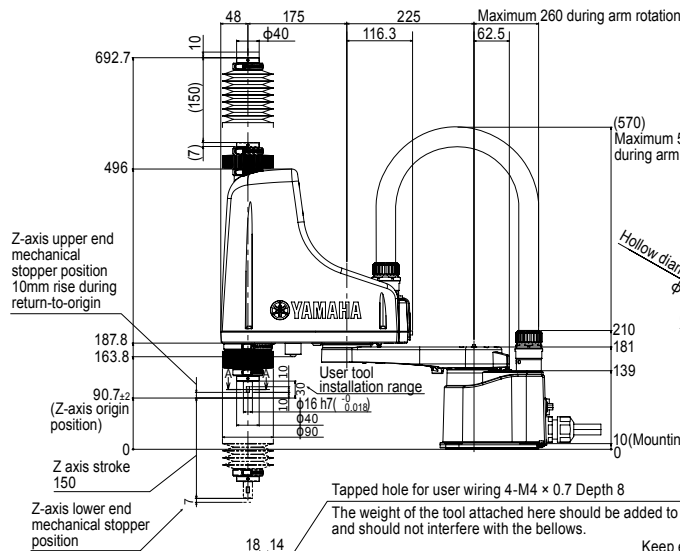
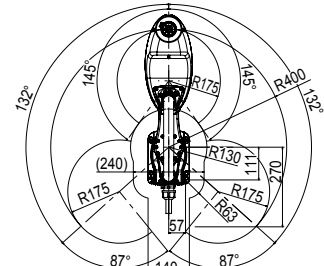
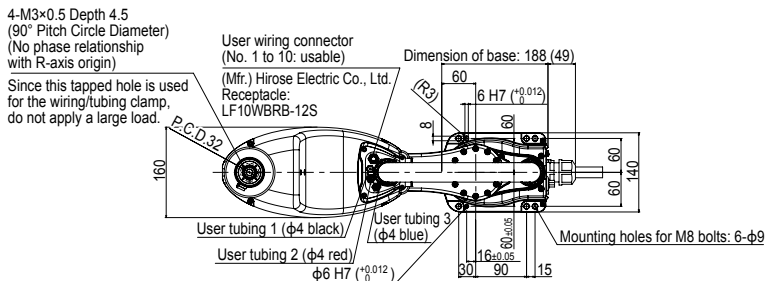
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

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4-M3×0.5 Depth 4.5
 (90° Pitch Circle Diameter)
 (No phase relationship
 with R-axis origin)

Since this tapped hole is used for the wiring/tubing clamp, do not apply a large load.



2-M4×0.7 Depth 5
 Since this tapped hole is used for the wiring/tubing clamp, do not apply a large load.

Hollow diameter φ11

Width across flat: 15
 No phase relationship with R-axis origin

Cross section A-A

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

4-φ9/R27 (Min. cable bending radius)
 Do not move the cable.

