

YK150XG

Standard type: Extra small type

- Arm length 150mm
- Maximum payload 1kg

Ordering method

YK150XG - 50

Model	Z axis stroke
	50: 50mm

Cable
2L: 2m
3L: 3.5m
5L: 5m
10L: 10m

RCX340-4

Controller / Number of controllable axes
RCX340-4

Safety standard

Option A (OP.A)

Option B (OP.B)

Option C (OP.C)

Option D (OP.D)

Option E (OP.E)

Absolute battery

Specify various controller setting items. RCX340 ▶ **P.636**

Specifications

		X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length	75 mm	75 mm	50 mm	-
	Rotation angle	+/-125 °	+/-145 °	-	+/-360 °
AC servo motor output		30 W	30 W	30 W	30 W
Deceleration mechanism	Transmission method	Direct-coupled			
	Motor to speed reducer Speed reducer to output	Direct-coupled			
Repeatability ^{Note 1}		+/-0.01 mm	+/-0.01 mm	+/-0.004 °	
Maximum speed		3.4 m/sec	0.9 m/sec	1700 °/sec	
Maximum payload		1.0 kg			
Standard cycle time: with 0.1kg payload ^{Note 2}		0.33 sec			
R-axis tolerable moment of inertia ^{Note 3}		0.01 kgm ²			
User wiring		0.1 sq × 8 wires			
User tubing (Outer diameter)		φ 4 × 2			
Travel limit		1. Soft limit 2. Mechanical stopper (X,Y,Z axis)			
Robot cable length		Standard: 2 m Option: 3.5 m, 5 m, 10 m			
Weight (Excluding robot cable) ^{Note 4}		4.0 kg			
Robot cable weight		0.9 kg (2 m)	1.5 kg (3.5 m)	2.1 kg (5 m)	4.2 kg (10 m)

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

Note 4. The total robot weight is the sum of the robot body weight and the cable weight.

Controller

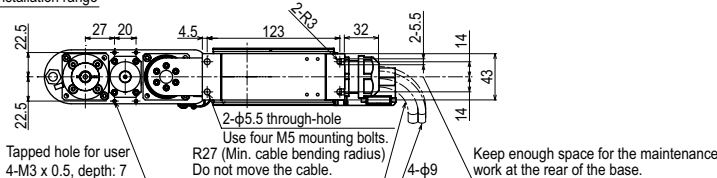
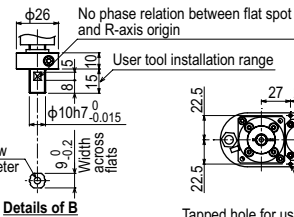
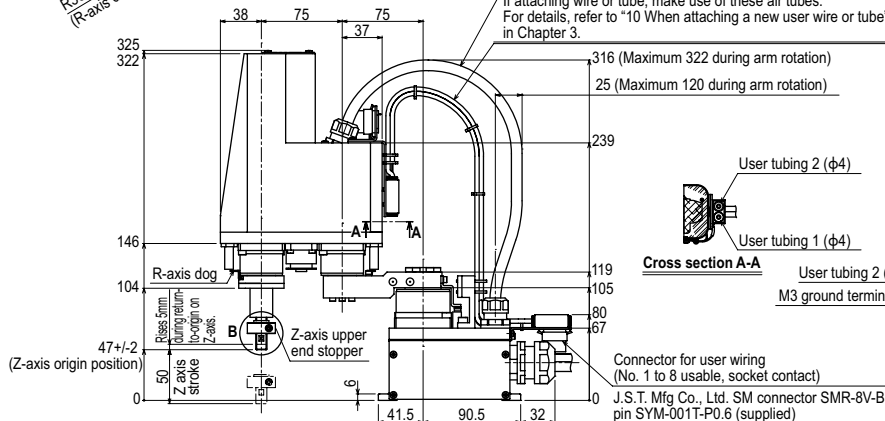
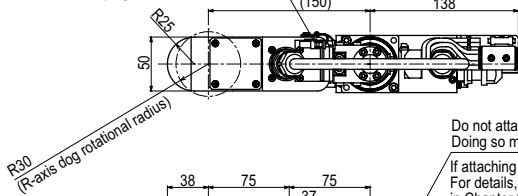
Controller	Power capacity (VA)	Operation method
RCX340	300	Programming / I/O point trace / Remote command / Operation using RS-232C communication

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.

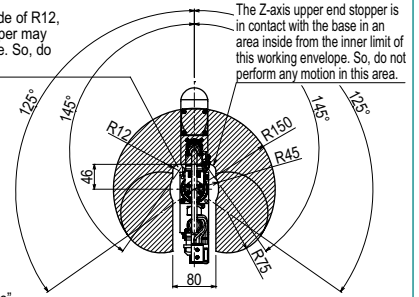
Our robot manuals (installation manuals) can be downloaded from our website at the address below:
<https://global.yamaha-motor.com/business/robot/>

YK150XG

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.



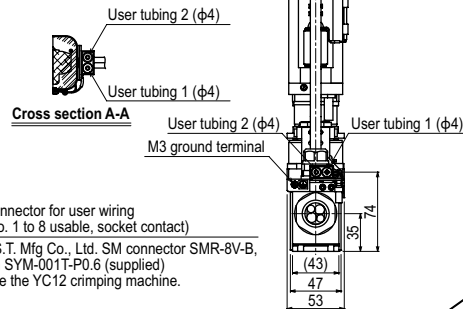
If the robot enters the inside of R12, the Z-axis upper end stopper may be in contact with the base. So, do not perform such motion.



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.



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 machine.

