## YK700XGS

Wall mount / inverse type

Arm length 700mm
Maximum payload 20kg

Ordering method

YK700XGS

W: Wall mount (same as per external view) U: Inverse wall mount (upside down)

200: 200mm No entry: None F: With tool flange

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	-
specifications	Rotation angle		+/-130 °	+/-130 °	_	+/-360 °
AC servo motor output			750 W	400 W	400 W	200 W
Deceleration mechanism	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1		+/-0.02 mm +/-0.01 mm +/-0.004 °		+/-0.004 °		
Maximum speed			8.4 m/sec 2.3 1.7 920 °/sec (wall moun m/sec 480 °/sec (inverse wall moun		920 °/sec (wall mount) 480 °/sec (inverse wall mount)	
Maximum payload			20 kg (Standard type), 19 kg (Tool flange mount type)			
Standard cycle time: with 2kg payload Note 2			0.42 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm <sup>2</sup>			
User wiring			0.2 sq × 20 wires			
User tubing (Outer diameter)			ф 6 × 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			Z axis 200 mm: 50 kg Z axis 400 mm: 52 kg			

■ Controller							
Controller	Power capacity (VA)	Operation method					
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication					

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

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

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.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

YK700XGS 300 D-sub connector for User tubing 3 (φ6 Blue) user wiring (No.1 to 20 usable) User tubing 2 (φ6 Red) User tubing 1 (φ6 Black ● R310 User tubing 1 (\$\phi6\$ Black)
User tubing 2 (\$\phi6\$ Red) 19 D-sub connector for M4 ground terminal User tubing 3 (\$\phi6\$ Blue) user wiring (No.1 to 20 usable) R27 (Min. cable bending Keep enough space for radius)
Do not move the cable. the maintenan ce work on Z400mm 585 Stroke the top face of the base. 130 Ball screw greasing hole (520)Working envelope of left-handed system 6-φ14 M12 bolt for installation, Z200mm Stroke **4-φ9** 6bolts used R700 97.5 e size) ф8Н7 through-hole 10 28 245 R310 0 (Base 0 30 installation 65.5 surface) R400 137.3 150.5 186.3 202.8+/-2 132 -196.3+/-2 φ25h7 86 (114) Hollow diameter: 418
Width across User tool installation range 198 Z-axis upper end Standard type mechanical stopper position 6mm rise during Z-axis return-to-origin ф50 h7 -0.025 ф55 Flat surface has no phase Working envelope of right-handed system ф95 relation to R-axis origin. 8 X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 132° Z-axis lower end mechanical stopper position 4-M4 x 0.7 through-hole for tool attachment Four M4 x 10L binding screws are supplied.
Do not screw the screws in deeper than 10mm from bottom surface of arm. Option: Tool flange mount type The weight of the tool attached here should be added to the tip mass. 4-φ6.6 through-hole \$ **(KO**) φ6 H7 +0.012 through-hole M20 x 2.5 Depth20 (Bottom of spline) View of B

Controller