YK500TW

Orbit type

Arm length 500mm **Maximum payload 4kg**

Ordering method

YK500TW - 130 - [ ] - [ ] - [ ] - RCX240 - [ ] - R3 - [ ] - [ ] - [ ] - [ ] - BB

Model	Z axis stroke	Tool flange	Hollow shaft	Cable	Controller	Usable for CE	Regenerative unit	Expansion I/O Note 1	Network option	iVY System	Gripper	Battery
YK500TW	130: 130mm	No entry: None F: With tool flange	No entry: None S: With hollow shaft	3L: 3.5m 5L: 5m 10L: 10m	RCX240	No entry: Standard E: CE marking	R3: RGU-3	N, P: Standard I/O 16/8 N1, P1: 40/24 N2, P2: 64/40 N3, P3: 88/56 N4, P4: 112/72	No entry: None CC: CC-Link DN: DeviceNet PB: Profibus EN: Ethernet EP: EtherNet/IP YC: YC-Link Note 2	No entry: None VY: iVY (Vision) TR: iVY+Light +Tracking LC: iVY+Light	No entry: None GR: Gripper	BB: 4 pcs

Note 1. Use N to N4 when NPN is selected on the I/O board, and P to P4 when PNP is selected.
Note 2. Available only for the master. See P.39 for details on YC-Link system.

Specifications

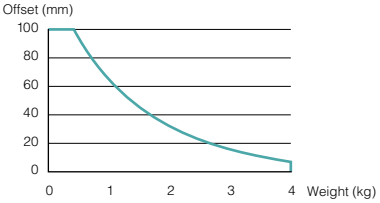
			X-axis	Y-axis	Z-axis	R-axis
Axis specifications	Arm length (mm)		250	250	130	-
	Rotation angle (°)		+/-225	+/-225	-	+/-720
AC servo motor output (W)			750	400	200	105
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Belt speed reduction
	Transmission method	Motor to speed reducer	Timing belt	Direct-coupled	Timing belt	Timing belt
		Speed reducer to output	Direct-coupled			
Repeatability Note 1 (XYZ: mm) (R: °)			+/-0.015		+/-0.01	+/-0.01
Maximum speed (XYZ: m/sec) (R: °/sec)			6.8		1.5	3000
Maximum payload Note 2 (kg)			4			
Standard cycle time: with 1kg payload Note 3 (sec)			0.29			
R-axis tolerable moment of inertia Note 4 (kgm²)		Rated	0.005			
		Maximum	0.05			
User wiring (sq × wires)			0.15 × 8			
User tubing (Outer diameter)			φ4 × 2			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length (m)			Standard: 3.5 Option: 5,10			
Weight (kg)			27			

Note 1. This is the value at a constant ambient temperature.
Note 2. Tool flange specifications (option) are 3 kg.
Note 3. When moving a 1 kg load back and forth 300mm horizontally and 25mm vertically (rough positioning arch motion).
Note 4. Limits must be placed on parameters such as acceleration according to the moment of inertia being used. See P.476.

Controller

Controller	Power capacity (VA)	Operation method
RCX240-R3	1000	Programming / I/O point trace / Remote command / Operation using RS-232C communication

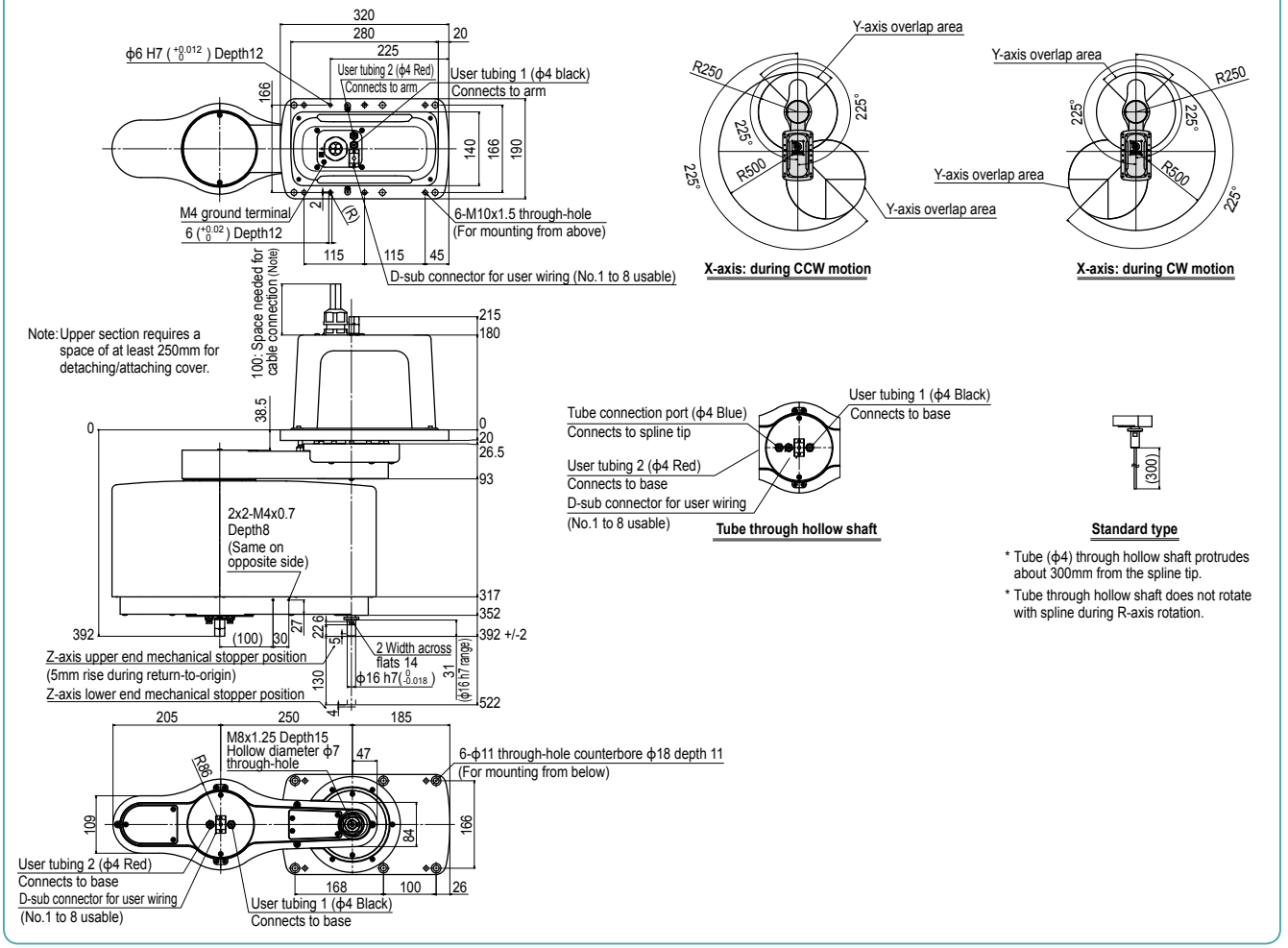
Note. The graph below shows recommended positional relation between the payload and the offset distance (center of gravity) from the R-axis center.



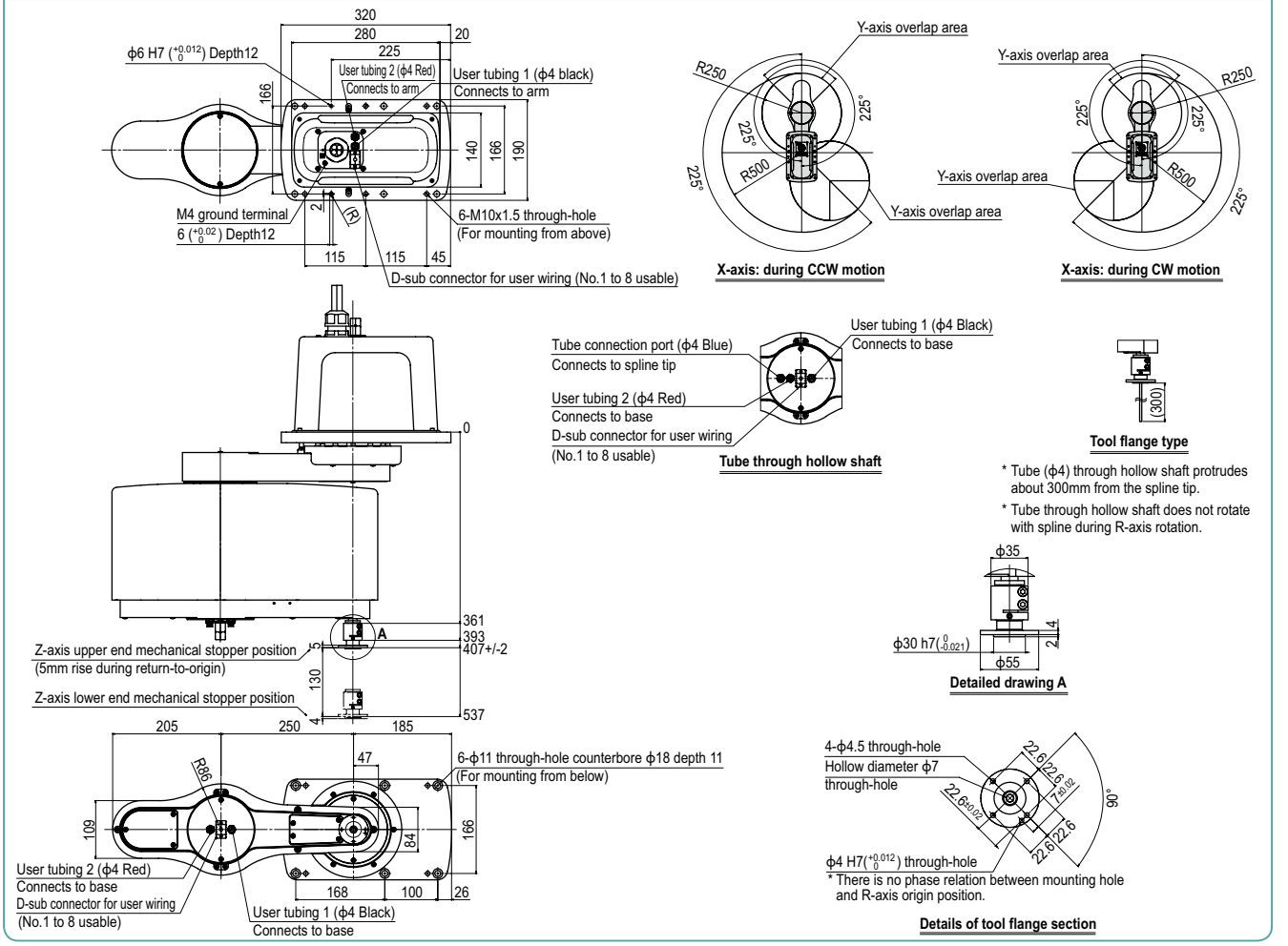
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

Our robot manuals (installation manuals) can be downloaded from our website at the address below:
http://www.yamaha-motor.co.jp/global/industrial/robot/

YK500TW



YK500TW Tool flange mount type



Controller RCX240 ▶ 438