YK220XC

Arm length 220mm Maximum payload 1kg

Ordering method

YK220XC - 100 - [ ] - RCX240 - [ ] - [ ] - [ ] - BB

Model	Z axis stroke	Cable length	Controller	Usable for CE	Expansion I/O Note 1	Network optuon	Battery
	100: 100mm	3L: 3.5m (Standard) 5L: 5m 10L: 10m		No entry: Standard E: CE marking	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 YC: YC-Link Note 2	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.

Basic specifications

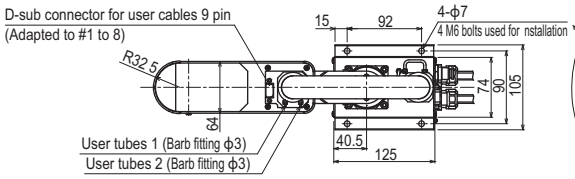
		X axis	Y axis	Z axis	R axis
Axis specifications	Arm length (mm)	111	109	100	–
	Rotation angle ( )	+/-120	+/-140	–	+/-360
AC servo motor output (W)		50	30	30	30
Repeatability Note 1 (XYZ mm) (R)		+/-0 01		+/-0 01	+/-0.004
Maximum speed (XYZ m/sec) (R /sec)		3.4		0.7	1700
Maximum payload (kg)		1.0			
Standard cycle time: with 0.1kg payload Note 2 (sec)		0.45			
R-axis tolerable moment of inertia Note 3 (kgm²)		0 01			
User wiring (sq × wires)		0.1 × 8			
User tubing (Outer diameter)		ϕ3 × 2			
Travel limit		1.Soft limit, 2.Mechanical stopper (X, Y, Z axes)			
Robot cable length (m)		Standard: 3.5 Option: 5, 10			
Weight (kg) (Excluding robot cable) Note 4		6.5			
Robot cable weight		1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Degree of cleanliness		CLASS 10 (0.1μm base)			
Intake air (Nℓ/min)		30			

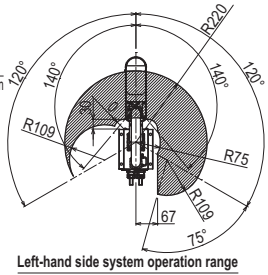
Note 1. This is the value at a constant ambient temperature.
Note 2. When reciprocating 100mm in horizontal and 25mm in vertical directions.
Note 3. There are limits to acceleration coefficient settings.
Note 4. The total robot weight is the sum of the robot body weight and the cable weight.

Controller

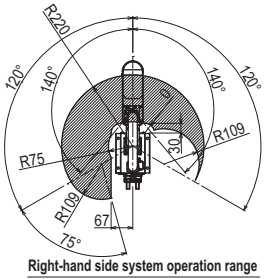
Controller	Power capacity (VA)	Operation method
RCX240	500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YK220XC

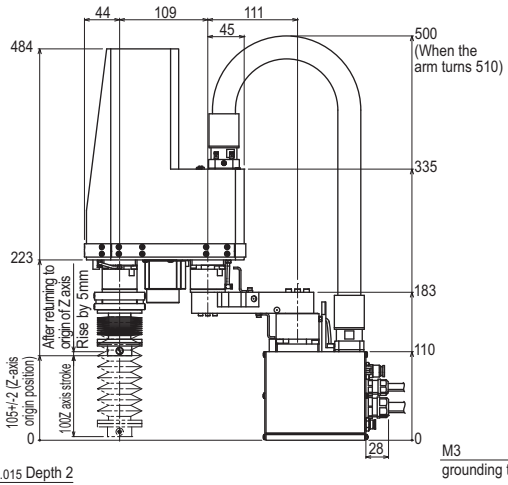


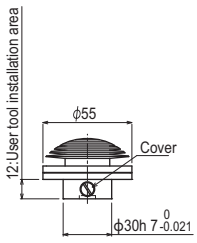


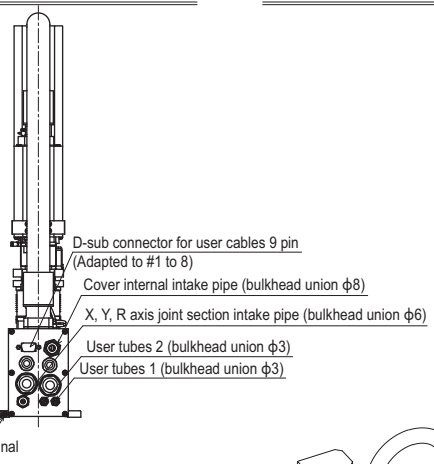
Left-hand side system operation range

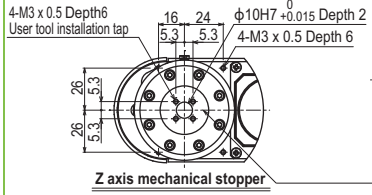


Right-hand side system operation range

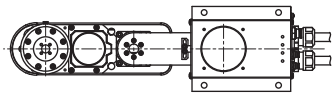


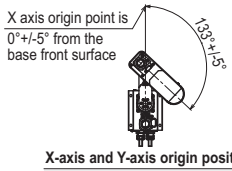






Z axis mechanical stopper





X-axis and Y-axis origin positions
Move counterclockwise in advance from the above position when performing origin return.