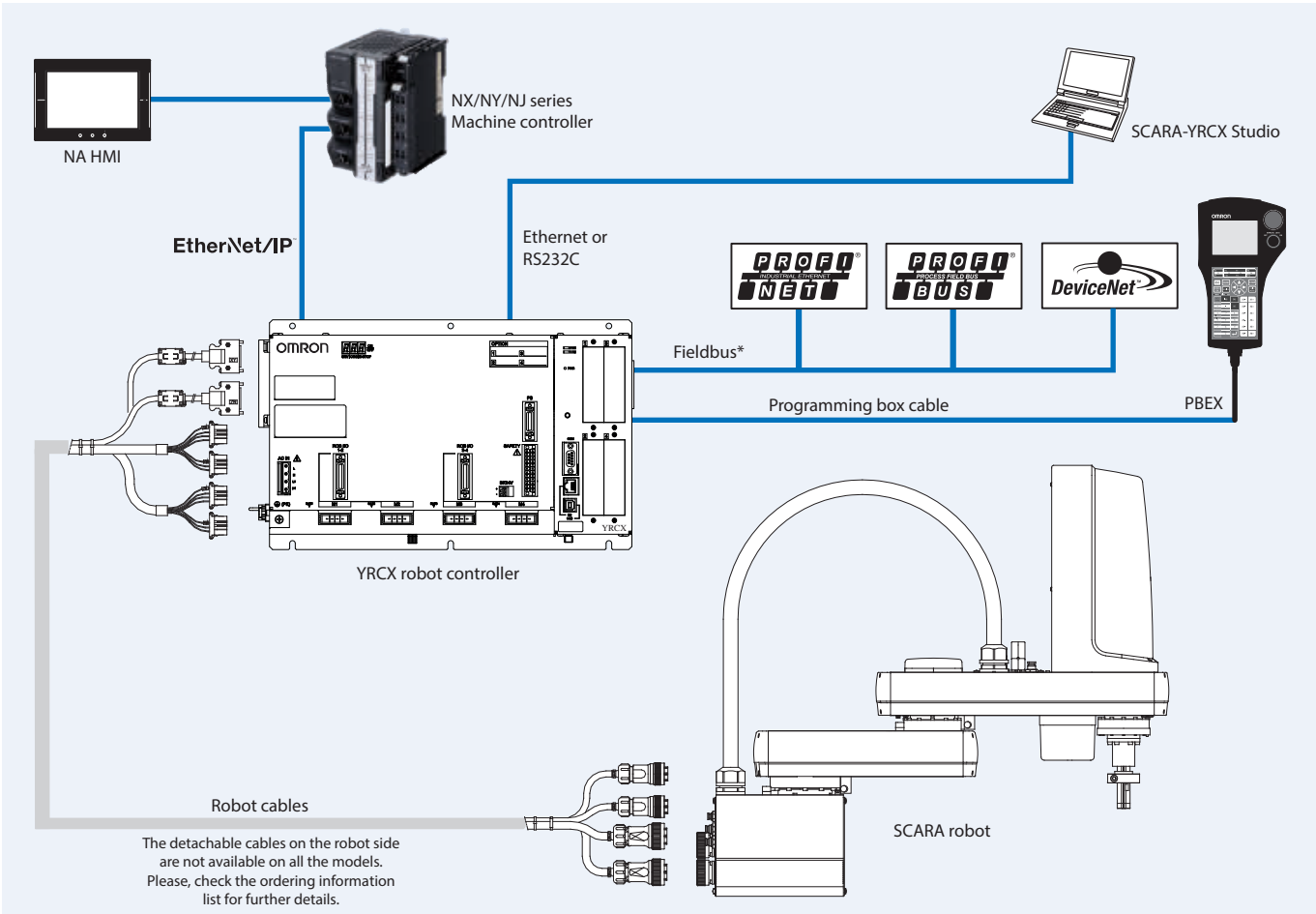# OMRON

SCARA robots

The flexible picking system

- Higher reliability (no belts in XG series, no electronic parts in movement)
- Higher precision and speed
- Minimum maintenance
- Easier to use
- Higher rigidity
- Very compact design
- Multiple connectivity options
- Integrated vision and conveyor tracking functions

System configuration

NA HMI

NX/NY/NJ series Machine controller

SCARA-YRCX Studio

EtherNet/IP™

Ethernet or RS232C

PROFINET

PROFIBUS PROCESS FIELD BUS

DeviceNet™

Fieldbus*

Programming box cable

PBEX

YRCX robot controller

Robot cables

The detachable cables on the robot side are not available on all the models. Please, check the ordering information list for further details.

SCARA robot

* Be careful not to mix field networks (EtherNet/IP, DeviceNet, PROFIBUS, PROFINET).

OMRON

Robot Controller

Specifications

Robot controller model			YRCX
Basic specifications	Number of controllable axes		4 axes maximum (Control simultaneously: 4 axes) Expandable up to 16 axes (4 robots) using YC-Link/E
	Controllable robots		SCARA robots
	Maximum power consumption		2500 VA
	Capacity of the connected motor		1600 W or less (in total for 4 axes)
	Dimensions (WxHxD)		355x195x130 mm
	Weight		6.2 kg
	Power supply voltage		Single phase 200 to 230 VAC, +/-10% maximum, 50/60 Hz
Axis control	Drive method		AC full-digital software servo
	Position detection method		Resolver or magnetic linear scale
	Control method		PTP motion (point to point), ARCH motion, linear interpolation, circular interpolation
	Coordinate system		Joint coordinates, Cartesian coordinates
	Position display units		Pulses, mm (millimeters), deg (degrees)
	Speed setting		1% to 100% (1% steps. This setting can be made even by programming)
	Acceleration setting		1. Automatic acceleration setting based on robot model type and type weight parameter 2. Setting based on acceleration and deceleration rate parameters (1% steps) * Can be changed by programming 3. Zone control
	Resolution		16384 P/rev, 1 micron
	Origin search method		Incremental, absolute, semi-absolute
Program	Program language		PSEUDO-BASIC (Conforming to JIS B8439 SLIM Language)
	Multitasks		16 tasks maximum
	Sequence program		1 program
	Point-data input method		Manual data input (coordinate data input), direct teaching, teaching playback, offline teaching (data input from external unit)
Memory	Memory capacity		2.1 MB (total capacity of program and points) (available program capacity during use of maximum number of points is 300 KB)
	Programs		100 programs (max. number of programs) 9999 lines (max. lines per program)
	Points		30000 points (max. number of points)
	Memory Backup battery		Lithium metallic battery (service life 4 years at a 0ºC to 40ºC)
	Internal flash memory		512 KB (ALL data only)
External input/output	SAFETY	Input	Emergency stop ready input, 2 systems Auto mode input, 2 systems (enabled only when the global specifications are used.)
		Output	Emergency stop contact output, 2 systems Enable contact output, 2 systems (enabled only when the PBEX is used.) Motor power ready output, 2 systems
	Brake output		Transistor output (PNP open collector)
	Origin sensor input		Connectable to 24 VDC normally-closed contact sensor

	External communications		RS-232C: 1CH D-SUB9 (female)
			RS-422: 1CH (Dedicated to PBEX)
			Ethernet: 1CH (IEEE802.3u/IEEE802.3)
			       100Mbps/10Mbps (100BASE-TX/10BASE-T)
			       Applicable to Auto Negotiation
			USB: 1CH (B type)

	Dedicated input/output board included with the YRCX controller		PNP Dedicated input 8 points, Dedicated output 9 points General input 16 points, General output 16 points
	Option boards	No. of slots	4
		General input/output	Optional input/output (NPN/PNP selectable) General input 24 points, General output 16 points
		Dedicated input/output	Optional input/output (NPN/PNP selectable) Dedicated input 8 points, Dedicated output 9 points General input 16 points, General output 16 points
		DeviceNet	DeviceNet slave Dedicated input 16 points, Dedicated output 16 points, General input 96 points, General output 96 points
		PROFIBUS	PROFIBUS slave Dedicated input 16 points, Dedicated output 16 points, General input 96 points, General output 96 points
		PROFINET	PROFINET, I/O device, 2 ports, conformance class B Dedicated input 16 points, Dedicated output 16 points, General input 96 points, General output 96 points
		EtherNet/IP	EtherNet/IP adapter, 2 ports Dedicated input 16 points, Dedicated output 16 points, General input 96 points, General output 96 points
		Ethernet	Built-in port
		Tracking	Tracking board AB phase input, up to 2 encoders
Options	Programming box		PBEX (with enable switch)
	Support software for PC		SCARA-YRCX Studio

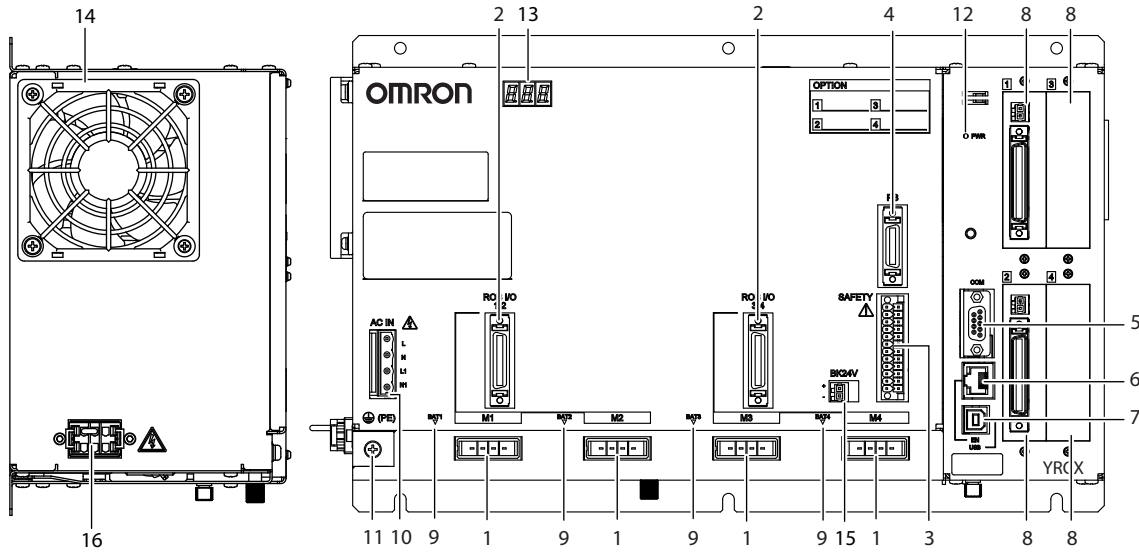| Robot controller model		YRCX
General specifications	**Operating temperature**	0ºC to 40ºC
	Storage temperature	-10ºC to 65ºC
	Operating humidity	35% to 85% RH (non-condensing)
	Absolute backup battery	Lithium metallic battery 3.6 V 2750 mAH / axis
	Absolute data backup period	1 year (in state with no power applied)
	Noise immunity	IEC61000-4-4 Level 3
	Protective structure	IP20

YC-Link/E connection

• Up to four robots can be managed with one master YRCX.
• Simultaneous start and arrival of each robot can be controlled freely.
• All programs and settings are managed using the master.
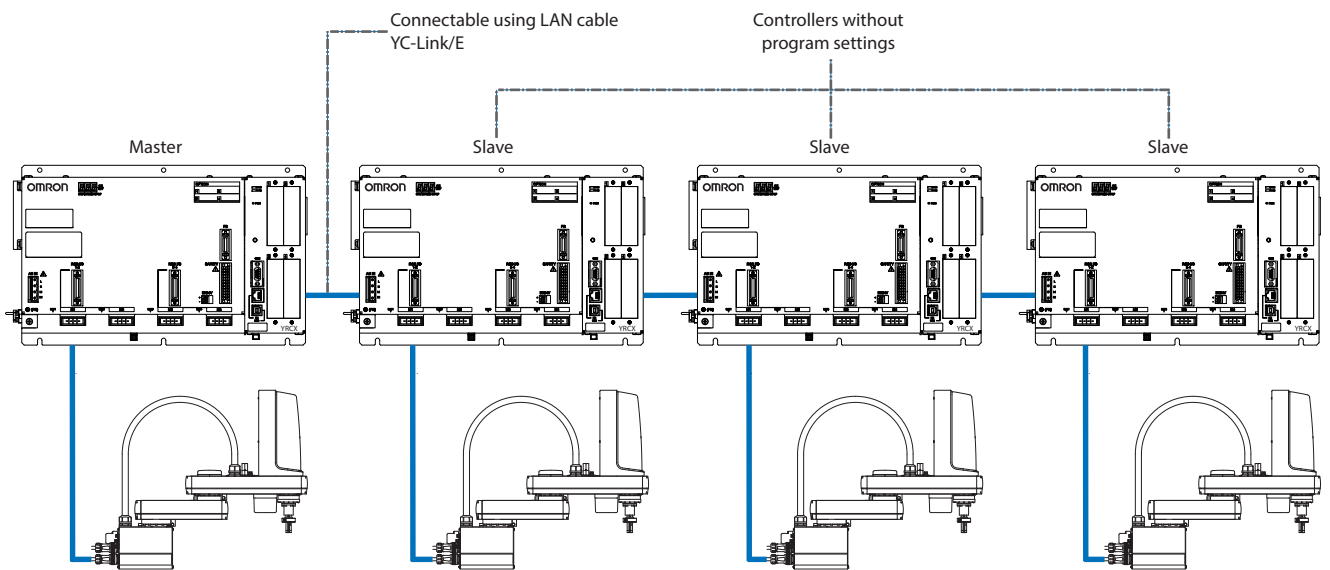
Nomenclature

YRCX controller

No.	Connector name	Function
1	M1/M2/M3/M4	Connectors used to drive the servo motor
2	ROB I/O [1-2/3-4]	Connectors used for servo motor feedback and sensor signals
3	SAFETY	Safety input/output connector for emergency stoppages, etc.
4	PB	Connector used to connect the programming box (PBEX)
5	COM	RS-232C interface connector
6	EN	Ethernet connection connector
7	USB	USB connection connector
8	OP [1/2/3/4]	Ports for option boards installation. Up to four option boards can be installed
9	BATT [1/2/3/4]	Battery connector for absolute backup
10	AC IN [L/N/L1/N1]	Control power supply and main power supply (motor drive power supply)
11	PE	Ground terminal (D class grounding work is required)
12	PWR LED	Lights up when the power is turned ON
13	7SEG LED	Indicates the controller or robot status
14	FAN	Ensures that the temperature inside the controller is kept at a fixed level. When installing the controller, keep a space of 50 mm or more from the left side panel so that the fan opening is not closed
15	BK24V	External 24V-input power connector for the brake[1]
16	RGEN	Regenerative unit connector for expansion. For the standard specifications, connect the thermal sensor shorting connector

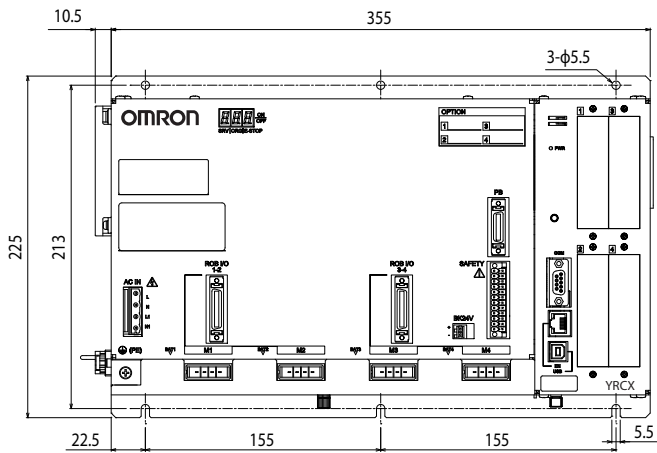*1 When two or more axes use the brake.
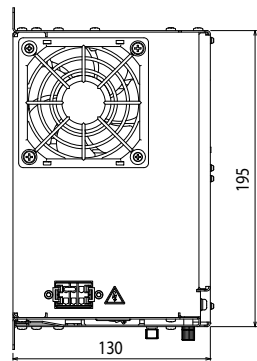
Dimensions

Programming box (PBEX)
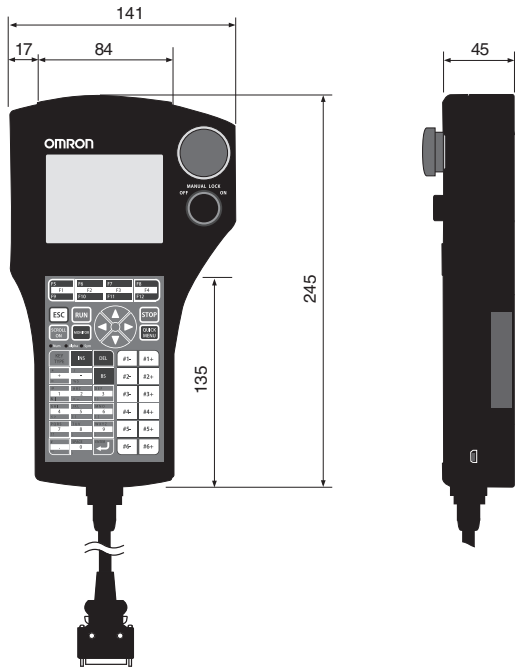
YRCX controller

Front view

Rear view

OMRON

R6YXE(T/S)400 XE SERIES - SMALL TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			400			
Maximum payload (kg)			4			
Repeatability[*1] (XYZ:mm) (R:º)			±0.01	±0.01	±0.01	±0.01
Axis specifications	**Arm length (mm)**		225	175	150	----
	Rotation range (º)		±132	±150	----	±360
Deceleration mechanism	**Speed reducer**		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission mechanism	**Motor to speed reducer**	Direct-coupled		Timing belt	
		Speed reducer to output	Direct-coupled			Timing belt
AC servo motor output (W)			200	100	100	100
Maximum speed (XYZ:m/sec) (R:º/sec)			6		1.1	2600
Standard cycle time: with 2 kg payload[*2] (sec)			0.41			
R axis allowable moment inertia[*3] (kgm²)			0.05			
User wiring (sq x pcs)			0.2 × 10			
User tubing (Outer diameter)			Ø4 × 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	**Open shaft**		R6YACXGLS			
	Brake release		R6YACXEBRAKEUNIT			
Weight (kg)			17			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When reciprocating 300 mm in horizontal and 25 mm in vertical directions and performing the coarse positioning arch operation.
*3   The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions
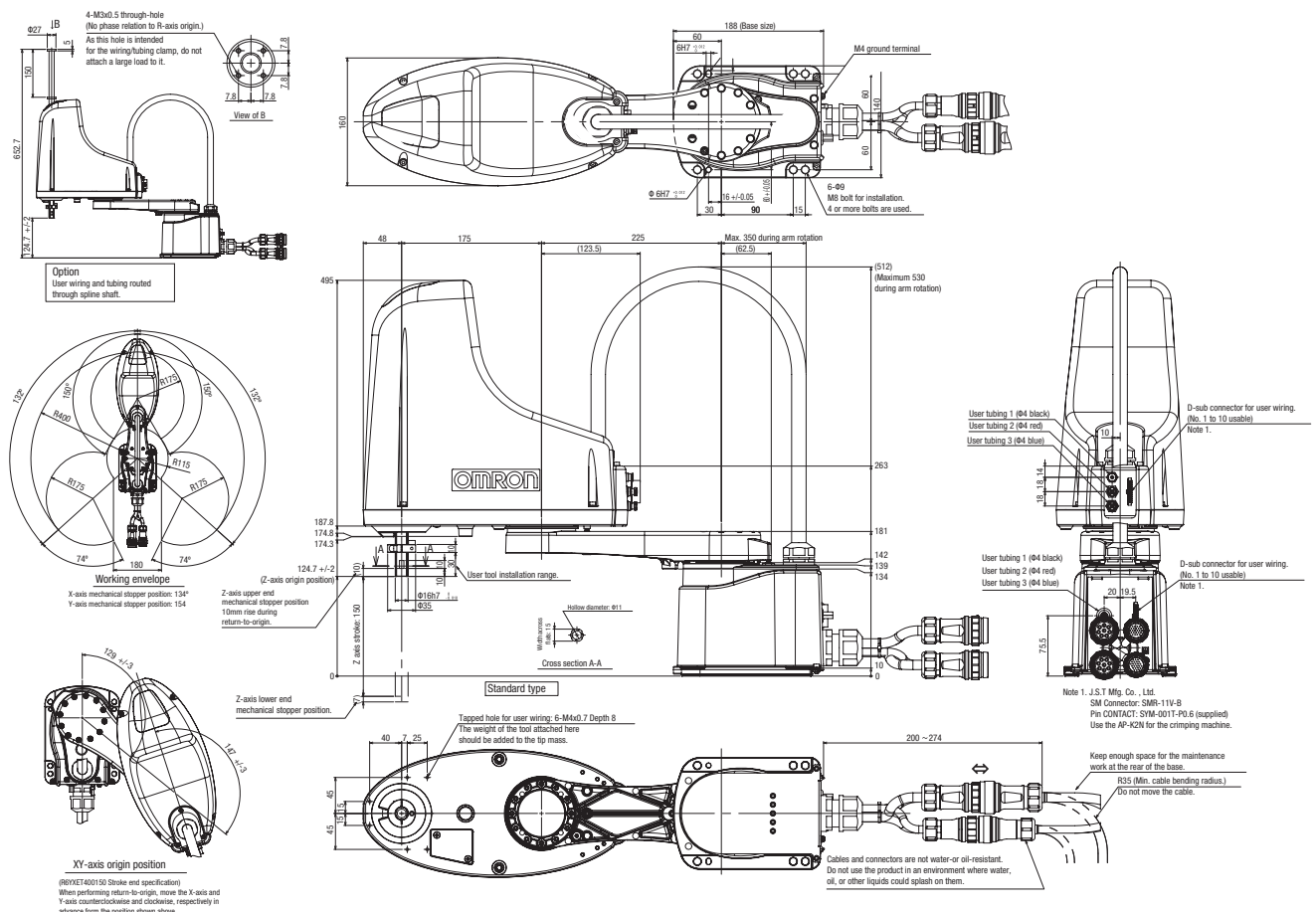
R6YXE510 XE SERIES - MEDIUM TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			510			
Maximum payload (kg)			10 (9)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)			±0.01	±0.01	±0.01	±0.01
Axis specifications	Arm length (mm)		235	275	200	----
	Rotation range (º)		±134	±152	----	±360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission mechanism	Motor to speed reducer	Direct-coupled		Timing belt	
		Speed reducer to output	Direct-coupled			Timing belt
AC servo motor output (W)			400	200	200	200
Maximum speed (XYZ:m/sec) (R:º/sec)			7.8		2	2600
Standard cycle time: with 2 kg payload[*3] (sec)			0.38			
R axis allowable moment inertia[*4] (kgm^2)			0.3			
User wiring (sq × pcs)			0.2 × 20			
User tubing (Outer diameter)			Ø6 × 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
	Hollow cap		R6YACXEHOLLOWCAP			
	Brake release		R6YACXEBRAKEUNIT			
Weight (kg)			25			

*1 Maximum payload is 9 kg when tool flange option is installed.
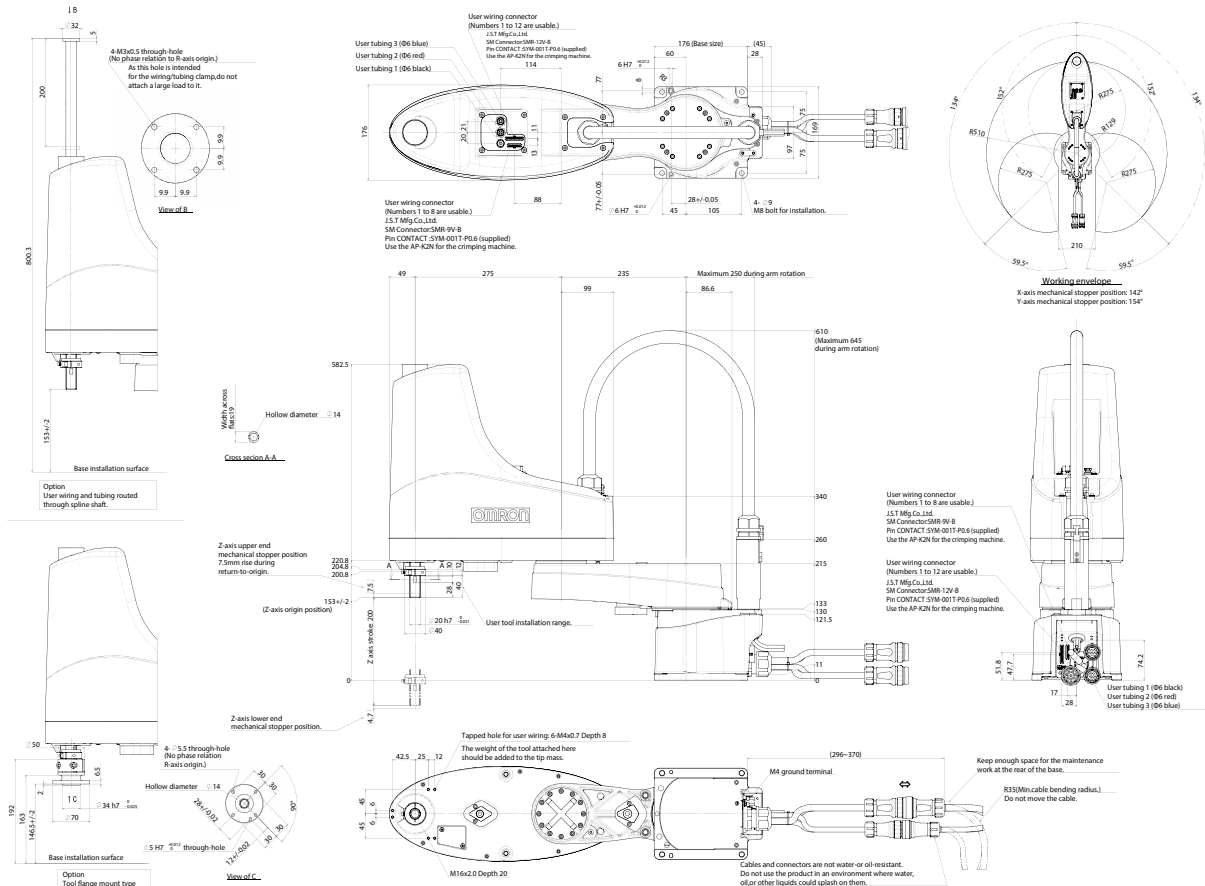*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When reciprocating 300 mm in horizontal and 25 mm in vertical directions and performing the coarse positioning arch operation.
*4 The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

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R6YXE610 XE SERIES - MEDIUM TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		610			
Maximum payload (kg)		10 (9) [*1]			
Repeatability [*2] (XYZ:mm) (R:º)		±0.01	±0.01	±0.01	±0.01
Axis specifications	Arm length (mm)	335	275	200	----
	Rotation range (º)	±134	±152	----	±360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission mechanism — Motor to speed reducer	Direct-coupled		Timing belt	
	Speed reducer to output	Direct-coupled			Timing belt
AC servo motor output (W)		400	200	200	200
Maximum speed (XYZ:m/sec) (R:º/sec)		8.6		2	2600
Standard cycle time: with 2 kg payload [*3] (sec)		0.39			
R axis allowable moment inertia [*4] (kgm^2)		0.3			
User wiring (sq x pcs)		0.2 × 20			
User tubing (Outer diameter)		Ø6 × 3			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
	Hollow cap	R6YACXEHOLLOWCAP			
	Brake release	R6YACXEBRAKEUNIT			
Weight (kg)		25			

*1   Maximum payload is 9 kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When reciprocating 300 mm in horizontal and 25 mm in vertical directions and performing the coarse positioning arch operation.
*4   The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

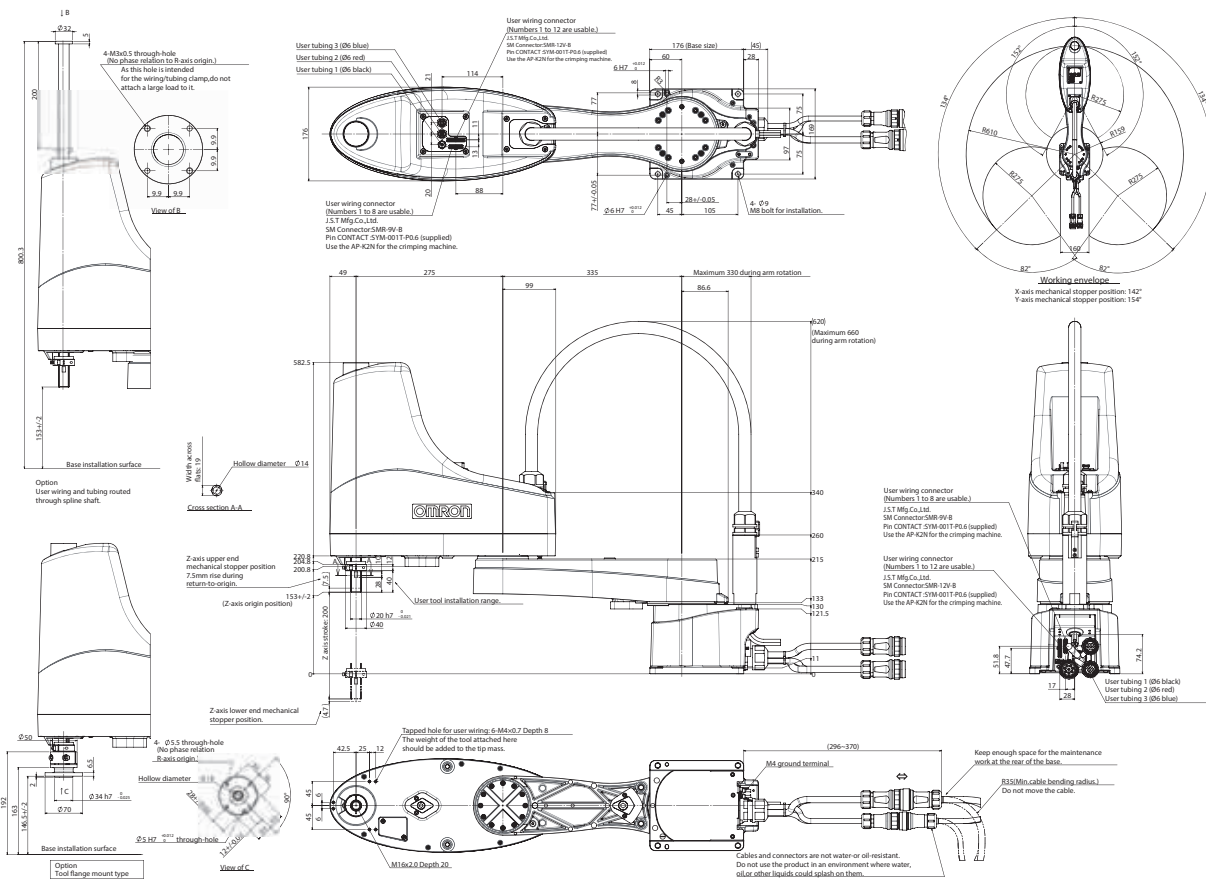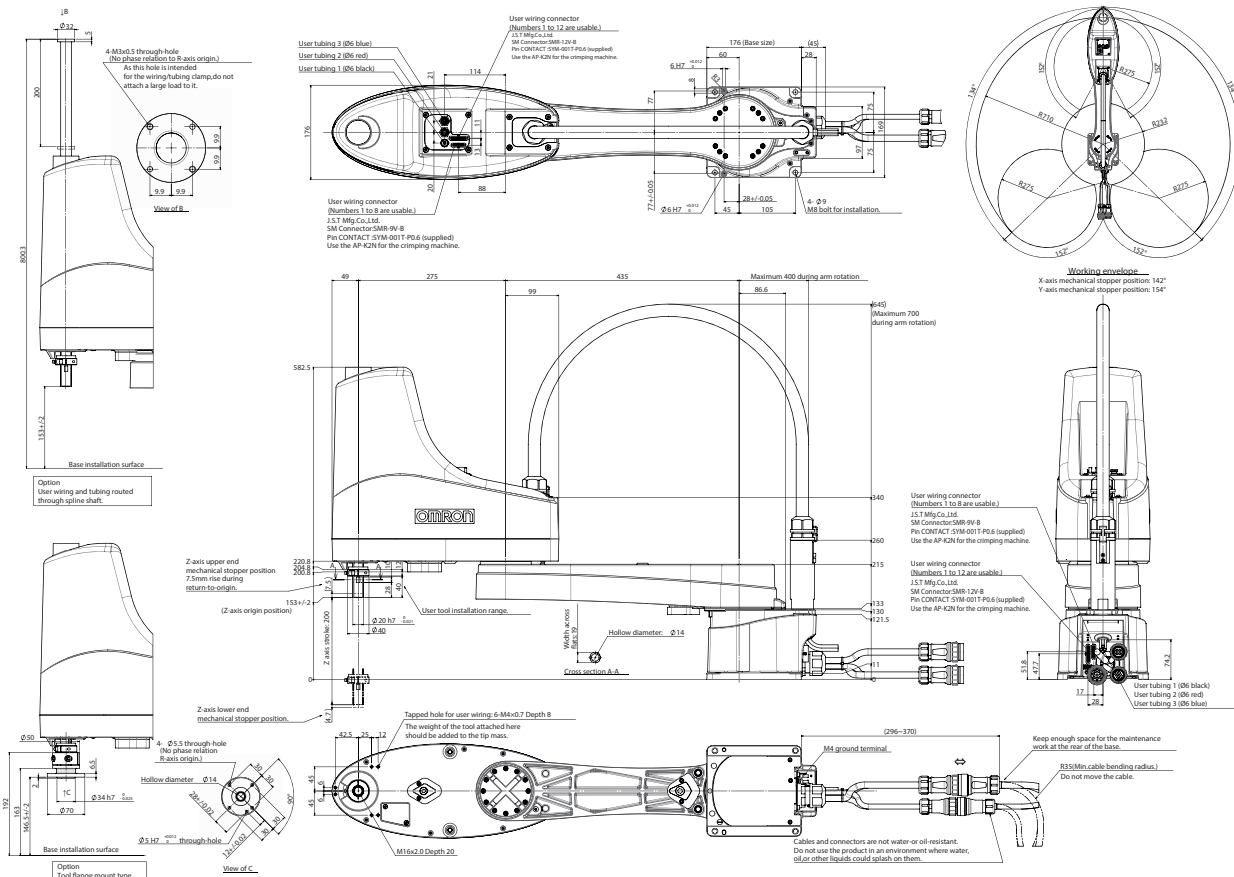# R6YXE710 XE SERIES - MEDIUM TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			710			
Maximum payload (kg)			10 (9)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)			±0.02	±0.02	±0.01	±0.01
Axis specifications	Arm length (mm)		435	275	200	----
	Rotation range (º)		±134	±152	----	±360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission mechanism	Motor to speed reducer	Direct-coupled		Timing belt	
		Speed reducer to output	Direct-coupled			Timing belt
AC servo motor output (W)			400	200	200	200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.5		2	2600
Standard cycle time: with 2 kg payload[*3] (sec)			0.42			
R axis allowable moment inertia[*4] (kgm^2)			0.3			
User wiring (sq x pcs)			0.2 × 20			
User tubing (Outer diameter)			Ø6 × 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
	Hollow cap		R6YACXEHOLLOWCAP			
	Brake release		R6YACXEBRAKEUNIT			
Weight (kg)			26			

*1 Maximum payload is 9 kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When reciprocating 300 mm in horizontal and 25 mm in vertical directions and performing the coarse positioning arch operation.
*4 The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

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R6YXG120 XG SERIES - TINY TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			120			
Maximum payload (kg)			1			
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.005		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		45	75	50	----
	Rotation range (º)		+/-125	+/-145	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			30	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)			3.3		0.9	1700
Standard cicle time: with 0.1kg payload[*2] (sec)			0.33			
R axis allowable moment inertia[*3] (kgm^2)			0.01			
User wiring (sq x pcs)			0.1 x 8			
User tubing (Outer diameter)			Ø4 x 2			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			2, 3.5, 5, 10			
Weight (kg) (Robot cable not included)[*4]			3.9			
Robot cable weight			0.9kg (2m) 1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Min. cable bending radius			R27			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   The overall weight of the robot is the total of the robot itself and the robot cable.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	300	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions
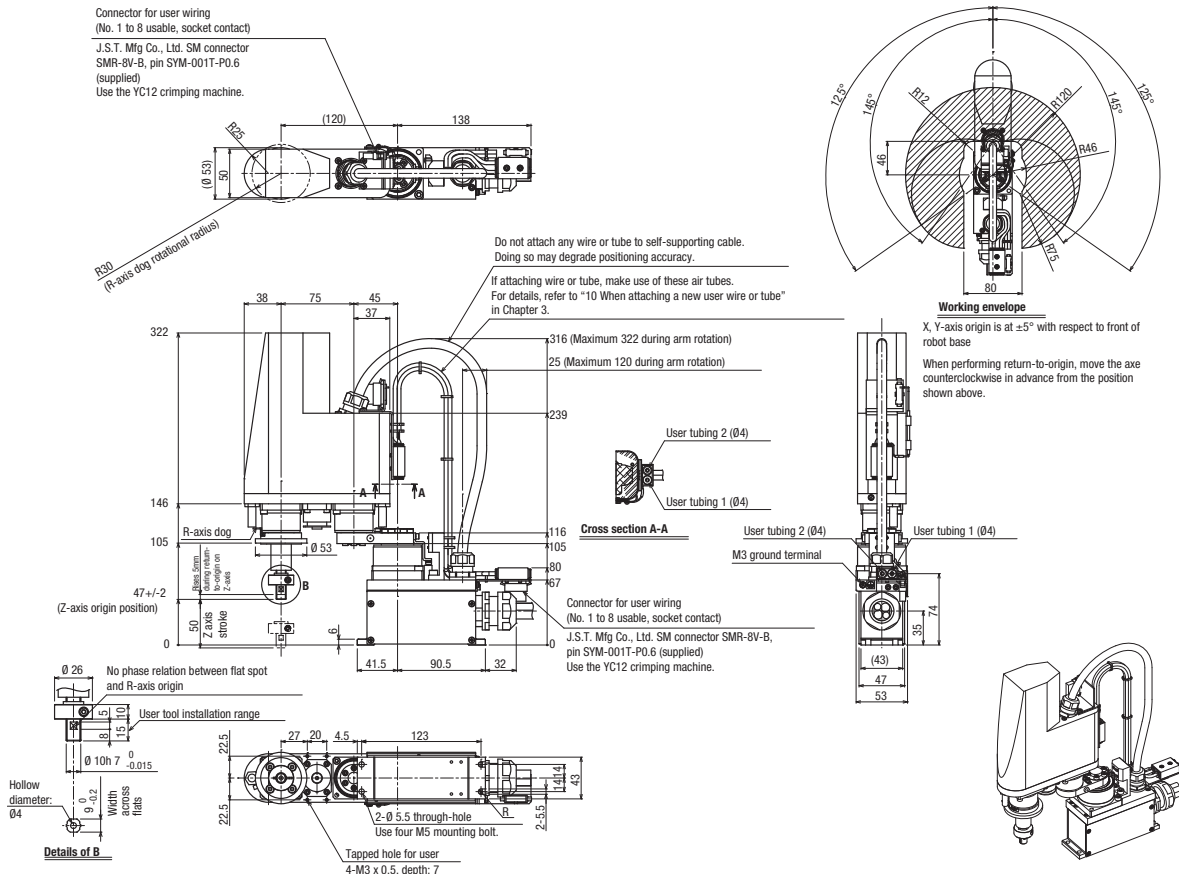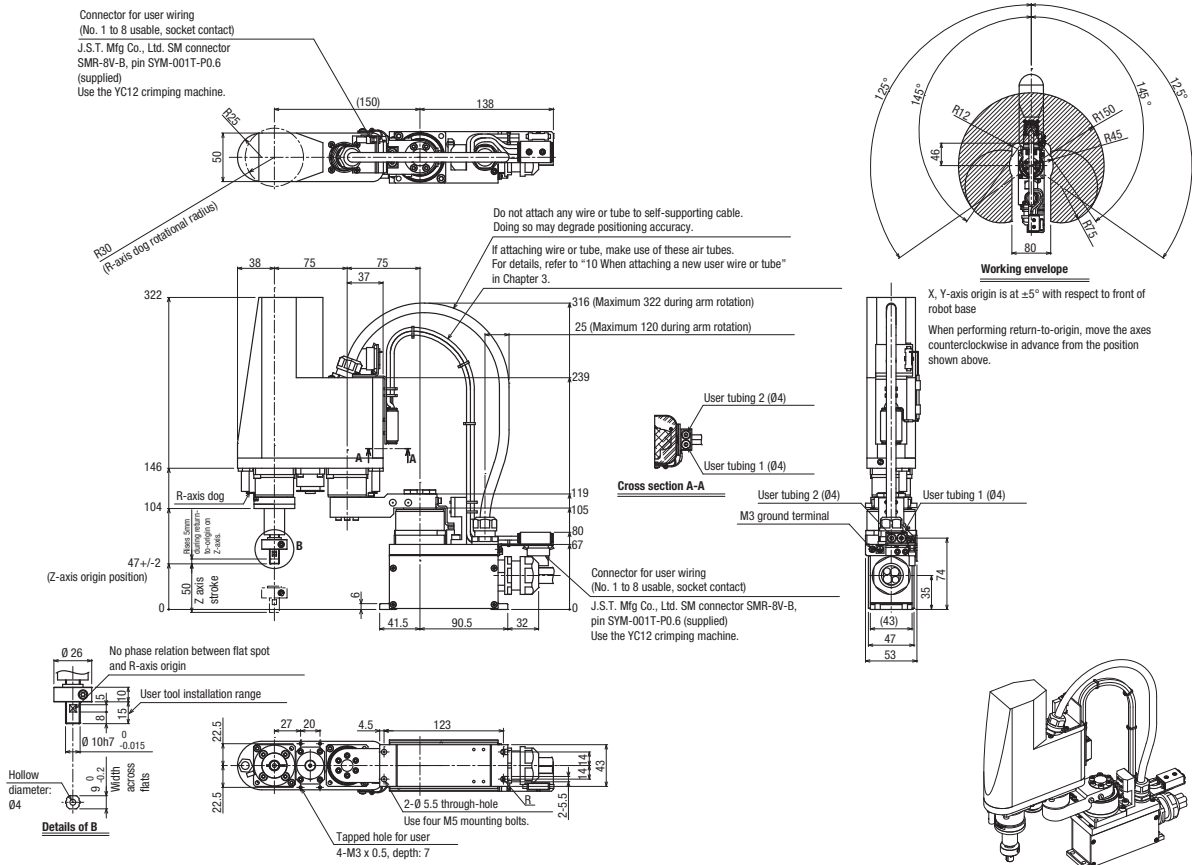
R6YXG150 XG SERIES - TINY TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			150			
Maximum payload (kg)			1			
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.005		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		75	75	50	----
	Rotation range (º)		+/-125	+/-145	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			30	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)			3.4		0.9	1700
Standard cicle time: with 0.1kg payload[*2] (sec)			0.33			
R axis allowable moment inertia[*3] (kgm^2)			0.01			
User wiring (sq x pcs)			0.1 x 8			
User tubing (Outer diameter)			Ø4 x 2			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			2, 3.5, 5, 10			
Weight (kg) (Robot cable not included)[*4]			4			
Robot cable weight			0.9kg (2m) 1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Min. cable bending radius			R27			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   The overall weight of the robot is the total of the robot itself and the robot cable.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	300	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXG180 XG SERIES - TINY TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		180			
Maximum payload (kg)		1			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.005		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	105	75	50	----
	Rotation range (º)	+/-125	+/-145	----	+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method — Motor to speed reducer	Direct-coupled			
	Transmission method — Speed reducer to output	Direct-coupled			
AC servo motor output (W)		30	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)		3.3		0.9	1700
Standard cicle time: with 0.1kg payload[*2] (sec)		0.33			
R axis allowable moment inertia[*3] (kgm^2)		0.01			
User wiring (sq x pcs)		0.1 x 8			
User tubing (Outer diameter)		Ø4 x 2			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		2, 3.5, 5, 10			
Weight (kg) (Robot cable not included)[*4]		4.1			
Robot cable weight		0.9kg (2m) 1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Min. cable bending radius		R27			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   The overall weight of the robot is the total of the robot itself and the robot cable.

Controller

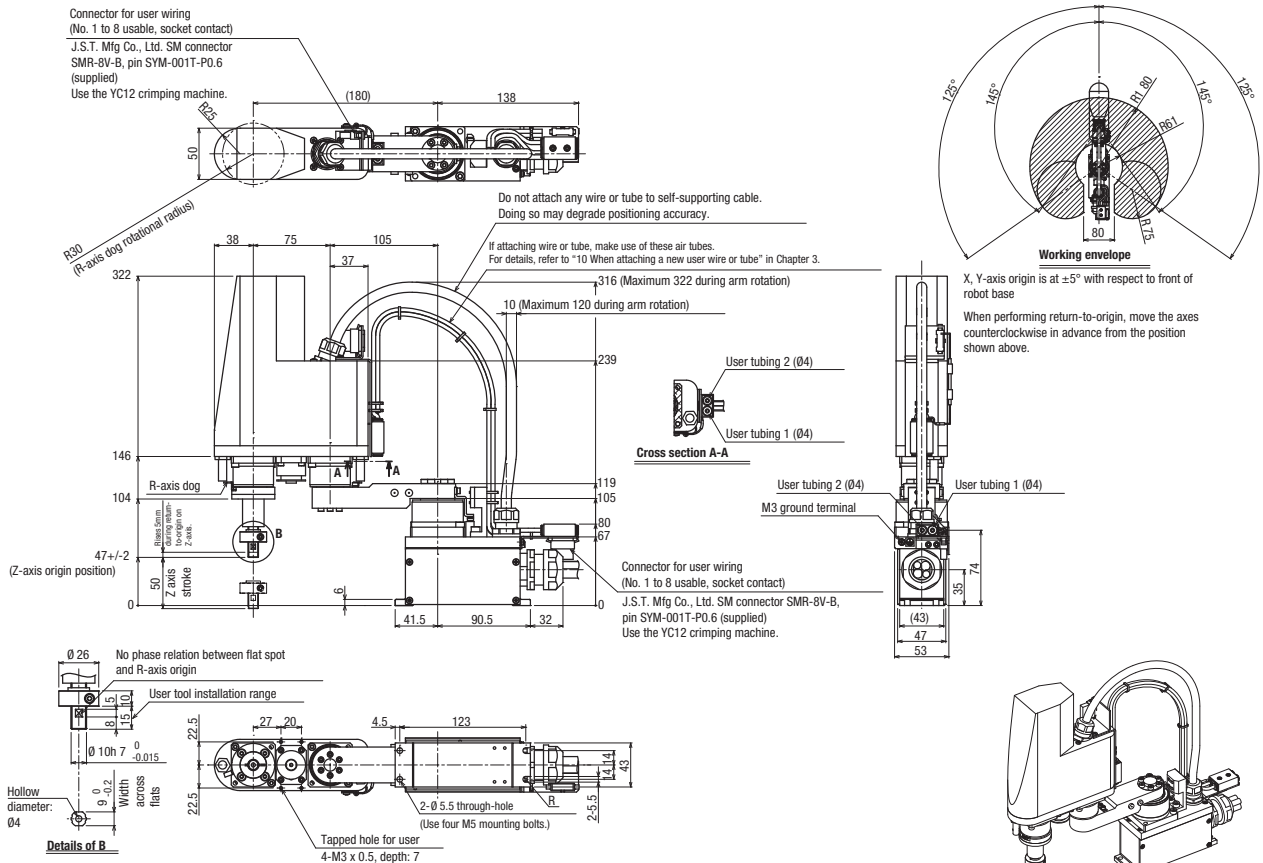| Controller	Power consumption (VA)	Operating method
YRCX	500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXG220 XG SERIES - TINY TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		220			
Maximum payload (kg)		1			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	111	109	100	----
	Rotation range (º)	+/-120	+/-140	----	+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method — Motor to speed reducer	Direct-coupled			
	Transmission method — Speed reducer to output	Direct-coupled			
AC servo motor output (W)		50	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)		3.4		0.7	1700
Standard cicle time: with 0.1kg payload[*2] (sec)		0.42			
R axis allowable moment inertia[*3] (kgm^2)		0.01			
User wiring (sq x pcs)		0.1 x 6			
User tubing (Outer diameter)		Ø3 x 2			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Weight (kg) (Robot cable not included)[*4]		5.5			
Robot cable weight		1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Min. cable bending radius		R27			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   The overall weight of the robot is the total of the robot itself and the robot cable.

Controller

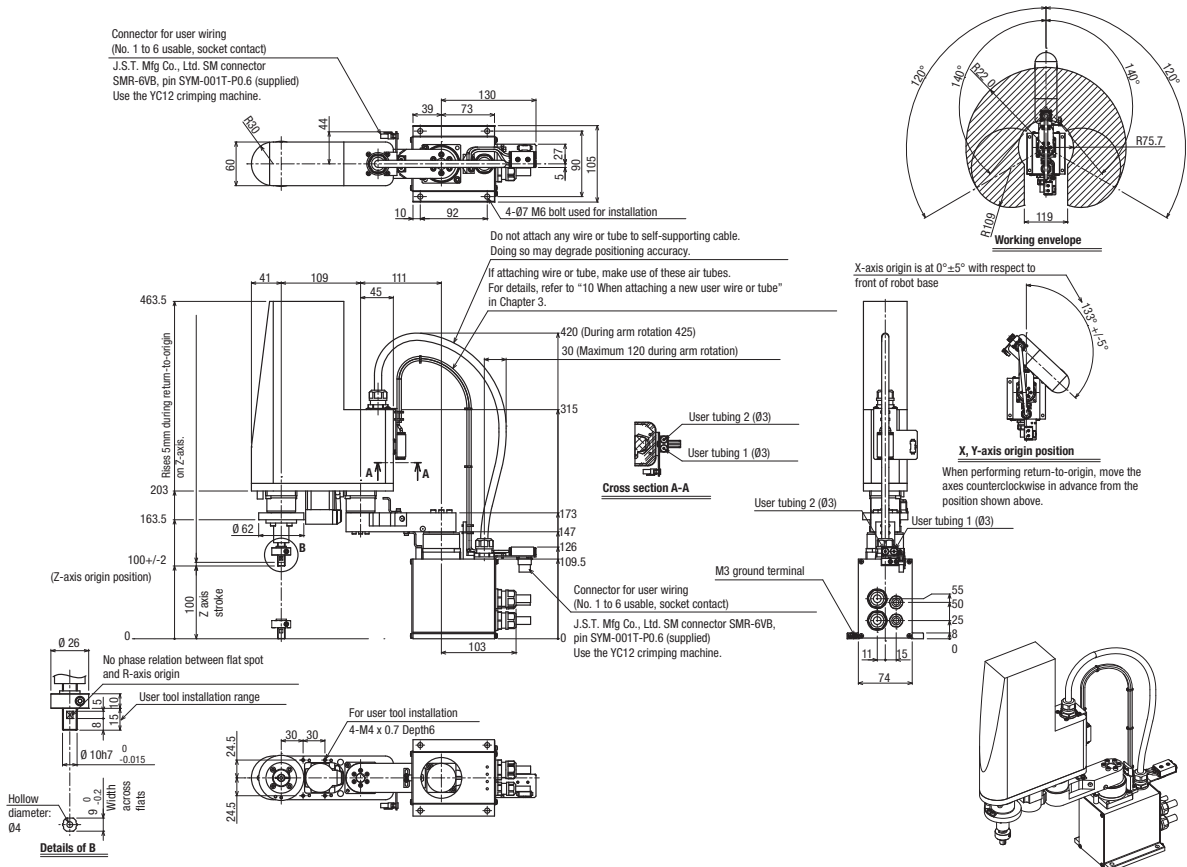| Controller	Power consumption (VA)	Operating method
YRCX	500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXGL250 XG SERIES - SMALL TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		250			
Maximum payload (kg)		5 (4)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	100	150	150	----
	Rotation range (º)	+/-140	+/-144	----	+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method — Motor to speed reducer	Direct-coupled			
	Transmission method — Speed reducer to output	Direct-coupled			
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		4.5		1.1	1020
Standard cicle time: with 2kg payload[*3] (sec)		0.49			
R axis allowable moment inertia[*4] (kgm²)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 3			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		14.5			

*1   Maximum payload is 4kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

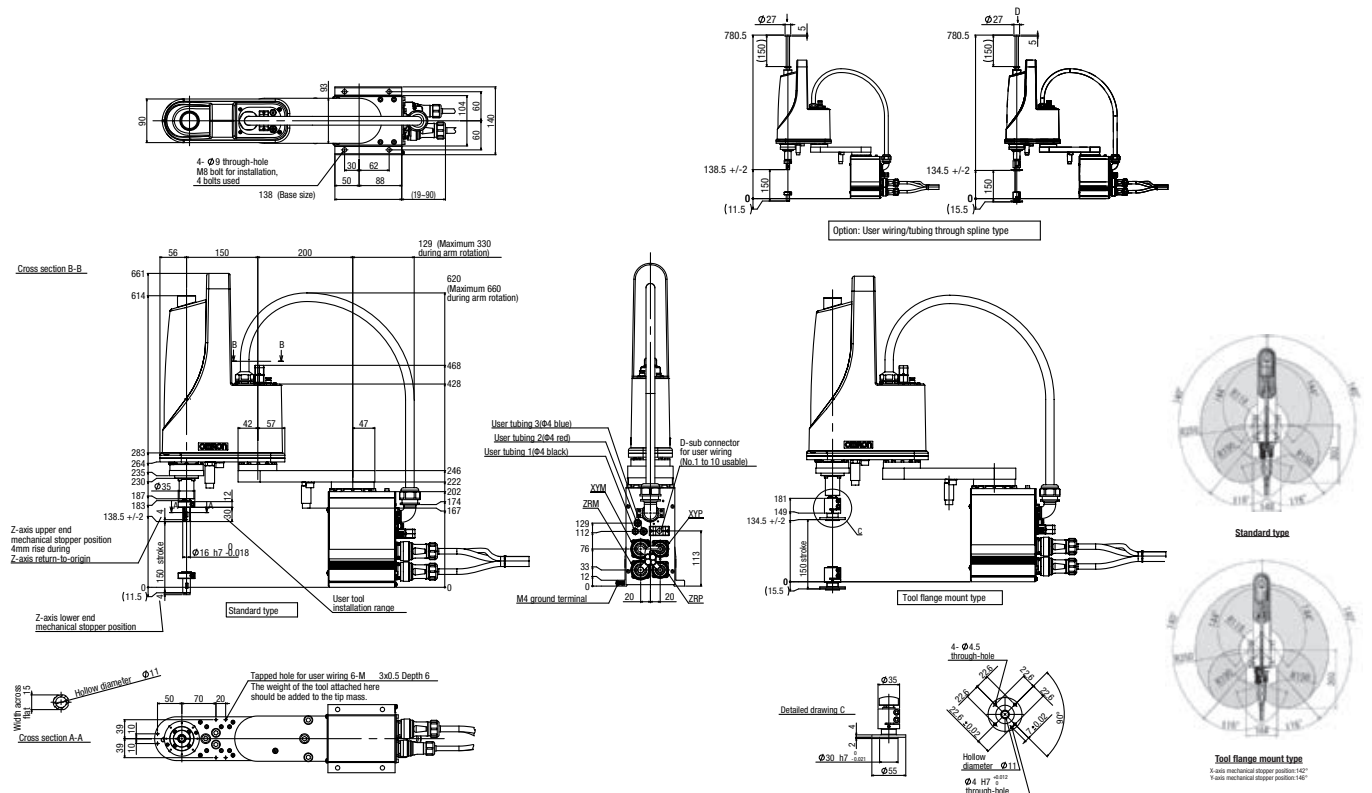## Dimensions

R6YXGL350 XG SERIES - SMALL TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			350			
Maximum payload (kg)			5 (4)[*1]			
Repeatability [*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		200	150	150	----
	Rotation range (º)		+/-140	+/-144	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			5.6		1.1	1020
Standard cicle time: with 2kg payload [*3] (sec)			0.49			
R axis allowable moment inertia [*4] (kgm²)			0.05			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			15			

*1   Maximum payload is 4kg when tool flange option is installed..
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

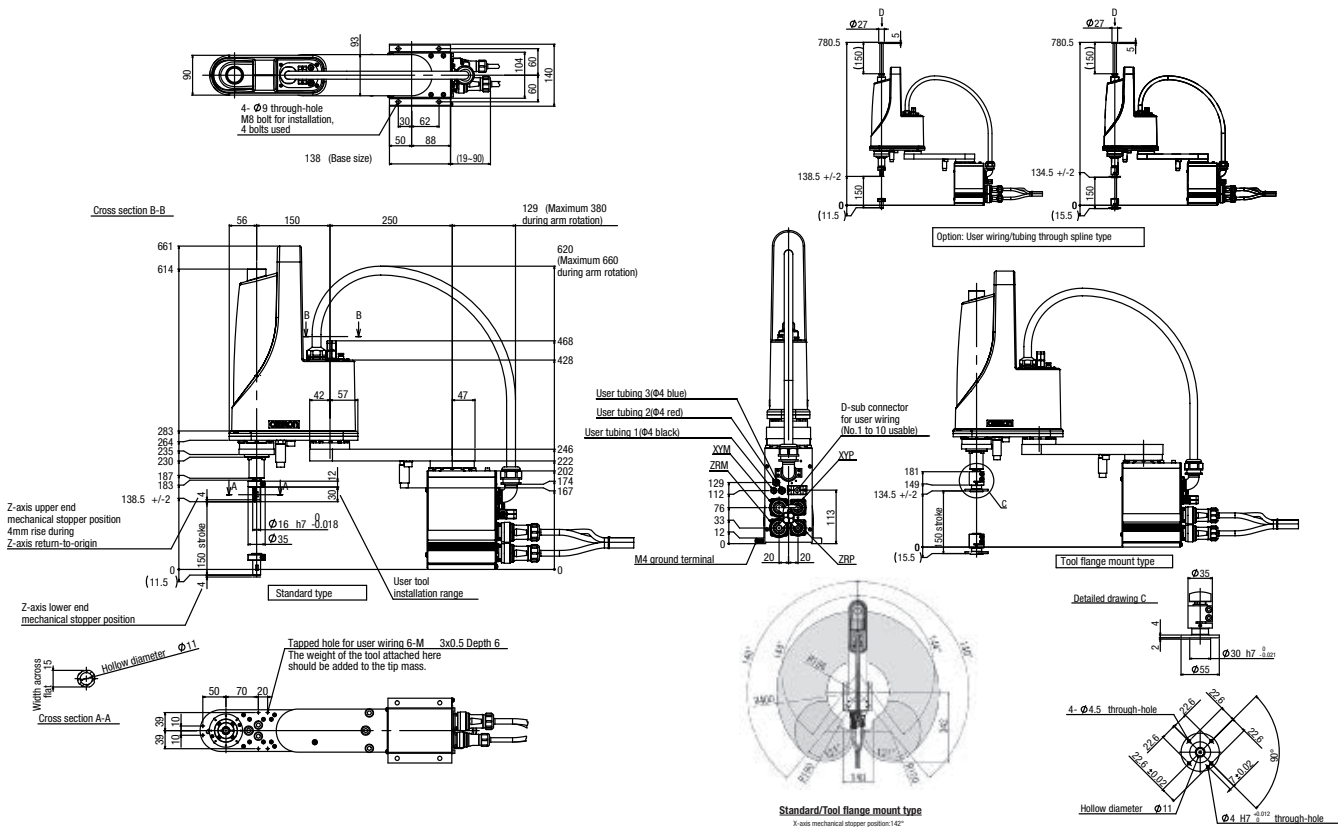## Dimensions

OMRON

R6YXGL400 XG SERIES - SMALL TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		400			
Maximum payload (kg)		5 (4)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	**Arm length (mm)**	250	150	150	----
	Rotation range (º)	+/-140	+/-144	----	+/-360
Deceleration mechanism	**Speed reducer**	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method — **Motor to speed reducer**	Direct-coupled			
	Speed reducer to output	Direct-coupled			
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		6.1		1.1	1020
Standard cicle time: with 2kg payload[*3] (sec)		0.49			
R axis allowable moment inertia[*4] (kgm^2)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 3			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	**Tool flange**	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		15.5			

*1 Maximum payload is 4kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

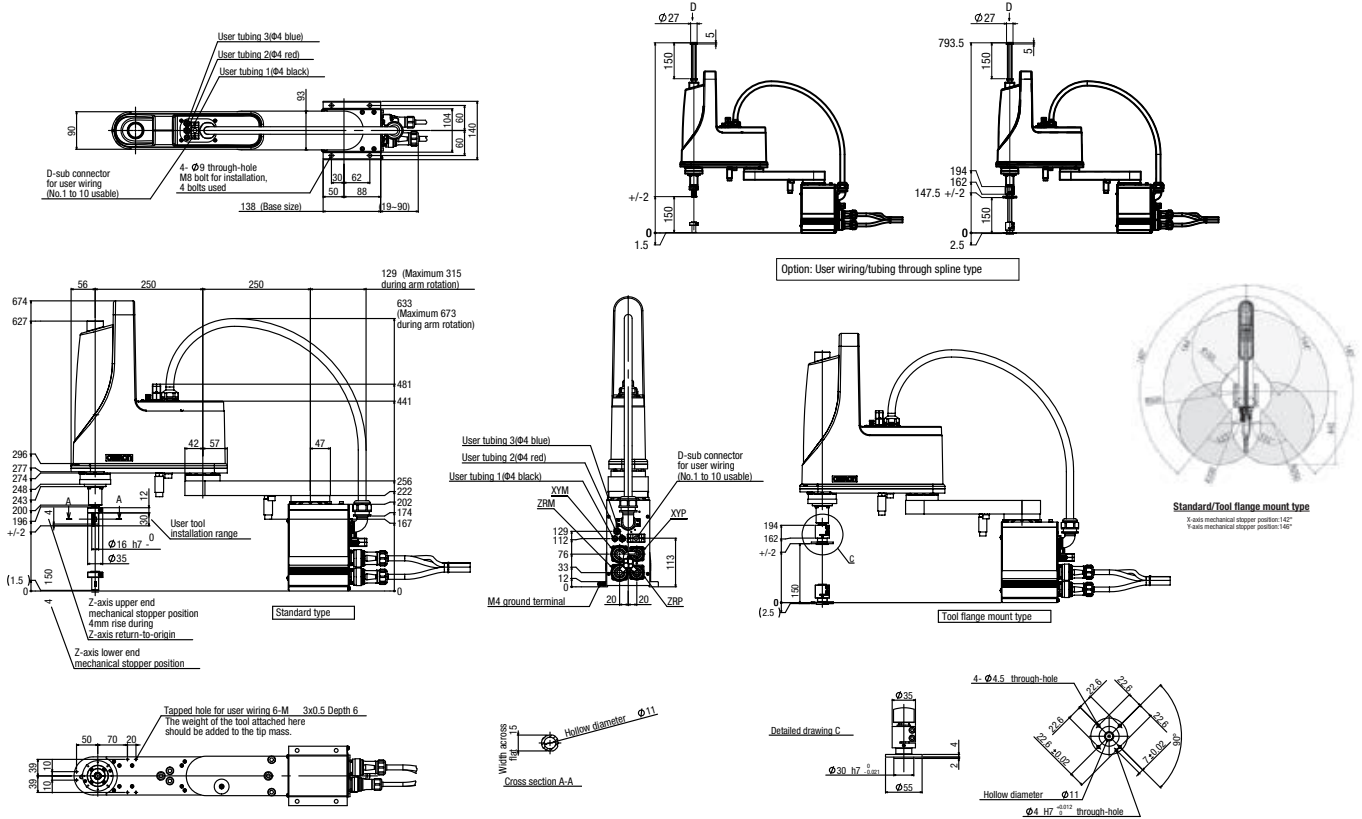## Dimensions

R6YXGL500 XG SERIES - MEDIUM TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			500			
Maximum payload (kg)			5 (4)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		250	250	150	----
	Rotation range (º)		+/-140	+/-144	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			5.1		1.1	1020
Standard cicle time: with 2kg payload[*3] (sec)			0.59			
R axis allowable moment inertia[*4] (kgm^2)			0.05			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			17			

*1 Maximum payload is 4kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Option: User wiring/tubing through spline type

Standard type

Tool flange mount type

Standard/Tool flange mount type
X-axis mechanical stopper position:142°
Y-axis mechanical stopper position:146°

OMRON

R6YXG500 XG SERIES - MEDIUM TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			500				
Maximum payload (kg)			10 (9)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		200	300	200	300	----
	Rotation range (º)		+/-130	+/-145	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			400	200	200		200
Maximum speed (XYZ:m/sec) (R:º/sec)			7.6		2.3	1.7	1700
Standard cicle time: with 2kg payload[*3] (sec)			0.45				
R axis allowable moment inertia[*4] (kgm^2)			0.30				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			30				

*1   Maximum payload is 9kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:147°

R6YXG500 Z200mm

R6YXG500 Z300mm

Z axis stroke	Model Name
200mm	R6YXG500200
300mm	R6YXG500300

Cross section A-A

R6YXGL600 XG SERIES - MEDIUM TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		600			
Maximum payload (kg)		5 (4)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	350	250	150	----
	Rotation range (º)	+/-140	+/-144	----	+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method — Motor to speed reducer	Direct-coupled			
	Speed reducer to output	Direct-coupled			
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		4.9		1.1	1020
Standard cicle time: with 2kg payload[*3] (sec)		0.63			
R axis allowable moment inertia[*4] (kgm^2)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 3			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		18			

*1 Maximum payload is 4kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

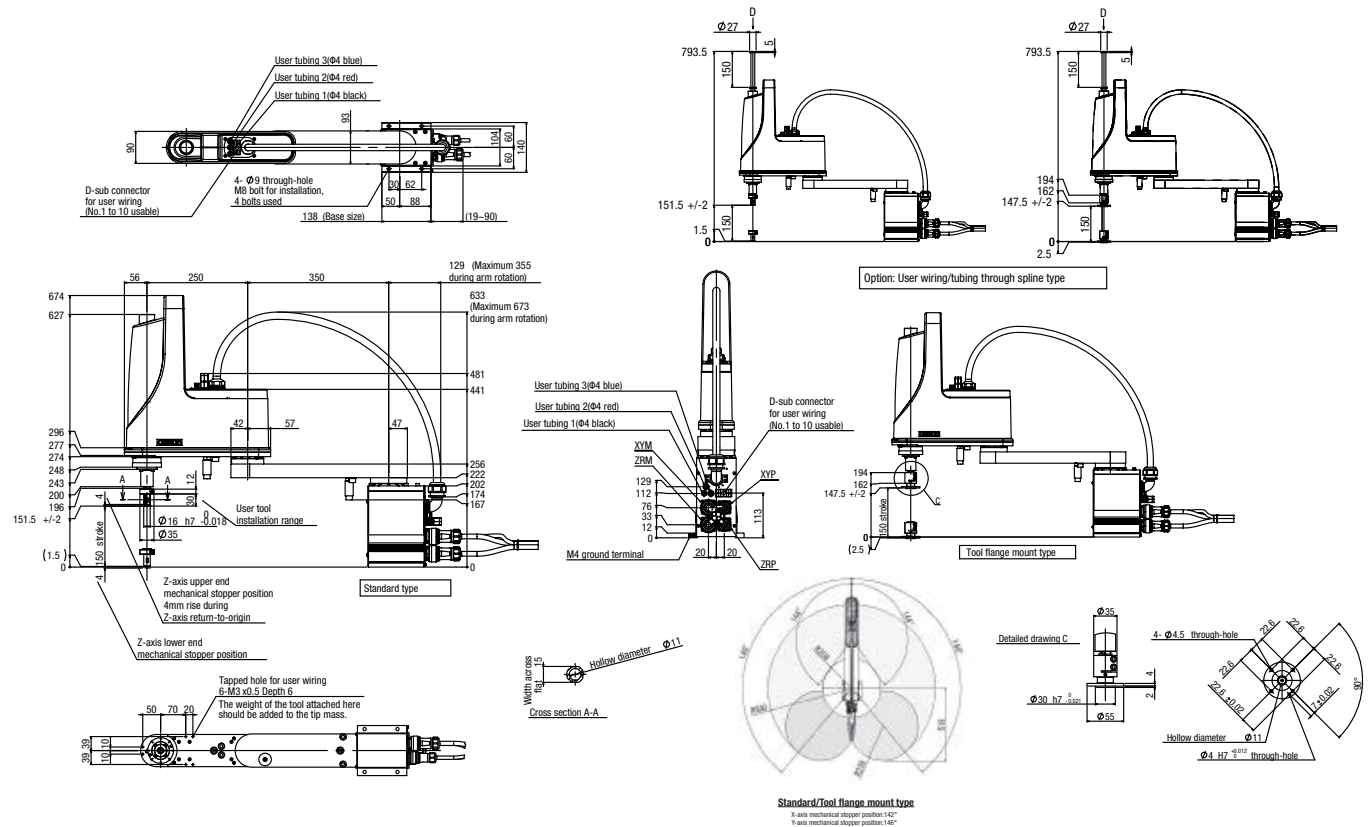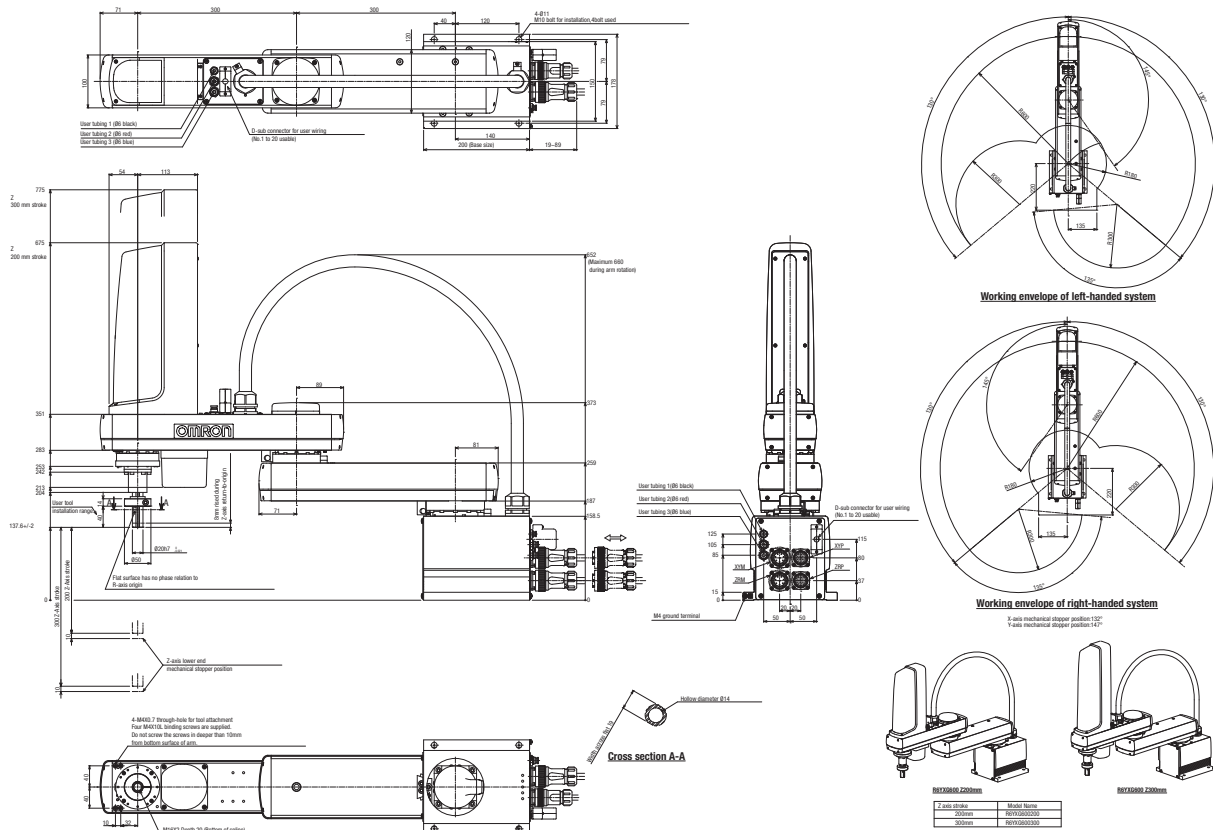## Dimensions

OMRON

R6YXG600 XG SERIES - MEDIUM TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		600				
Maximum payload (kg)		10 (9) [1]				
Repeatability [2] (XYZ:mm) (R:º)		+/-0.01		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)	300	300	200	300	----
	Rotation range (º)	+/-130	+/-145	----		+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method / Motor to speed reducer	Direct-coupled				
	Speed reducer to output	Direct-coupled				
AC servo motor output (W)		400	200	200		200
Maximum speed (XYZ:m/sec) (R:º/sec)		8.4		2.3	1.7	1700
Standard cicle time: with 2kg payload [3] (sec)		0.46				
R axis allowable moment inertia [4] (kgm^2)		0.30				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Option	Tool flange	R6YACXGLF				
Weight (kg) (Excluding robot cable)		31				

[1]   Maximum payload is 9kg when tool flange option is installed.
[2]   This is the value at a constant ambient temperature. (X,Y axes)
[3]   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
[4]   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system

Cross section A-A

R6YXGH600 XG SERIES - MEDIUM TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			600				
Maximum payload (kg)			20 (19)[*1]				
Repeatability [*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		200	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			7.7		2.3	1.7	920
Standard cicle time: with 2kg payload [*3] (sec)			0.47				
R axis allowable moment inertia [*4] (kgm^2)			1				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 48, Z axis 400mm: 50				

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position 132°
Y-axis mechanical stopper position 152°

Cross section A-A

R6YXGH600 Z200mm

R6YXGH600 Z400mm

Z axis stroke	Model Name
200mm	R6YXGH600200
400mm	R6YXGH600400

OMRON

R6YXGL700 XG SERIES - LARGE TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			700				
Maximum payload (kg)			10 (9)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)		400	300	200	300	----
	Rotation range (º)		+/-130	+/-145	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			400	200	200		200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.2		2.3	1.7	1700
Standard cicle time: with 2kg payload[*3] (sec)			0.50				
R axis allowable moment inertia[*4] (kgm^2)			0.30				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg)			32				

*1   Maximum payload is 9kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions
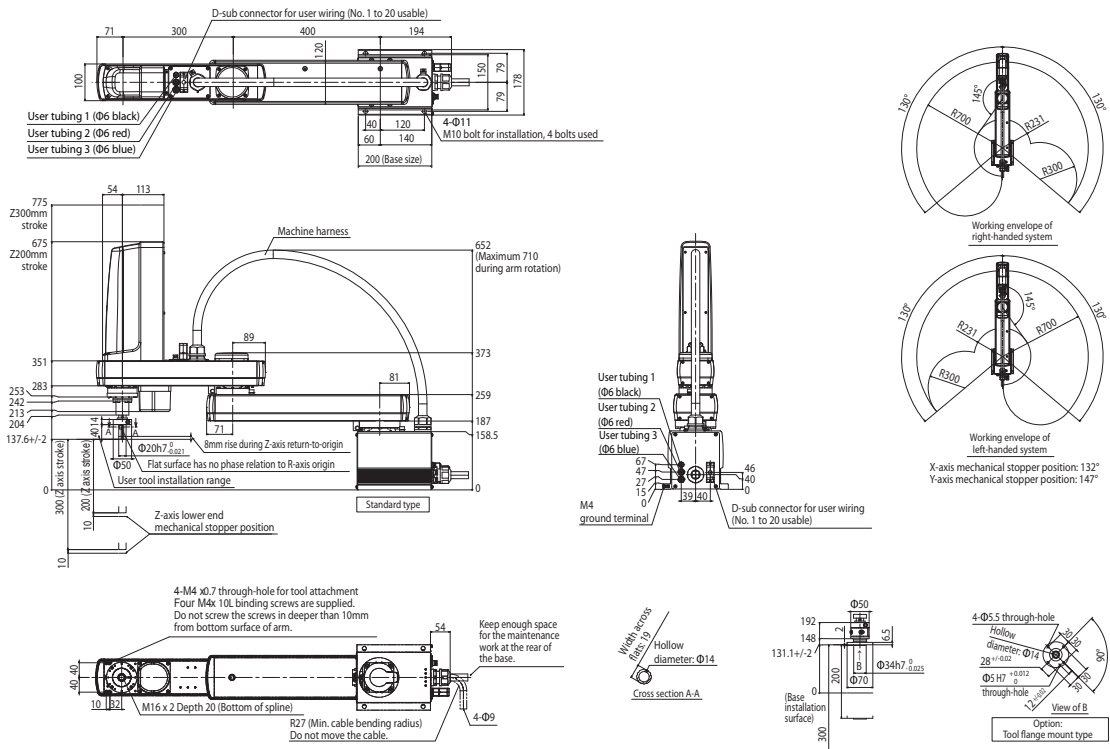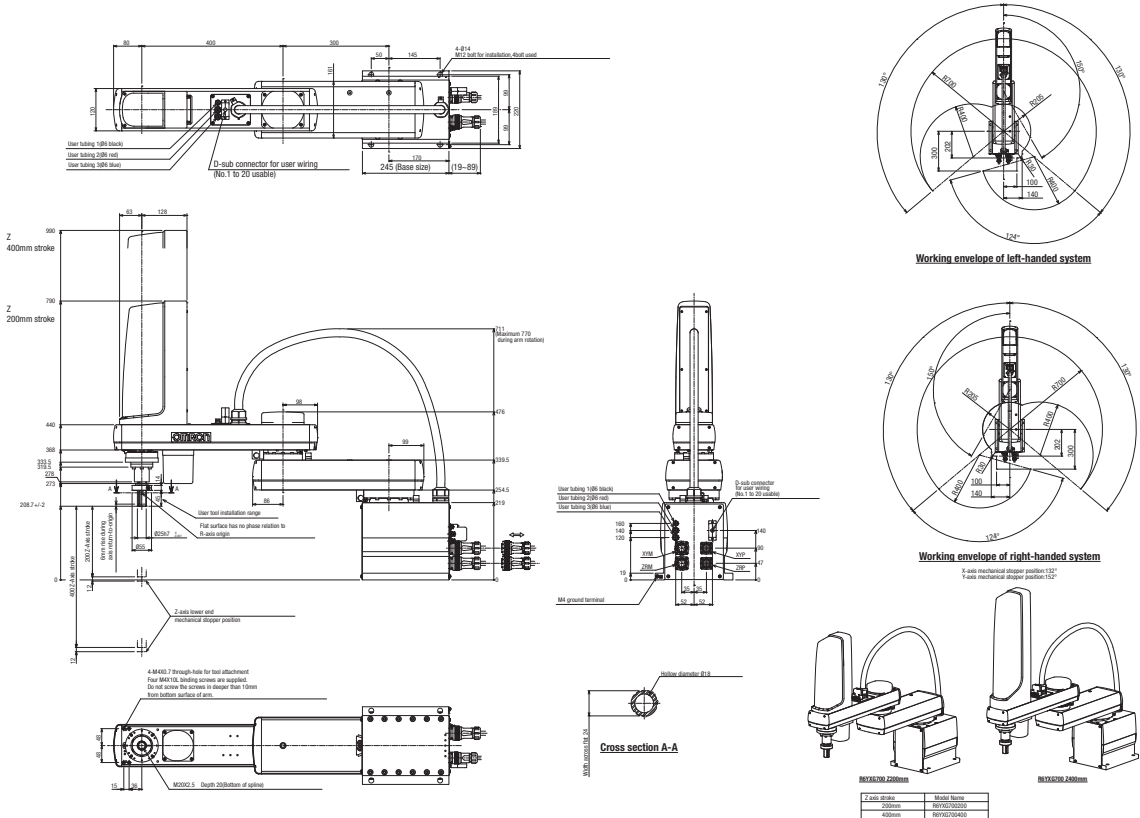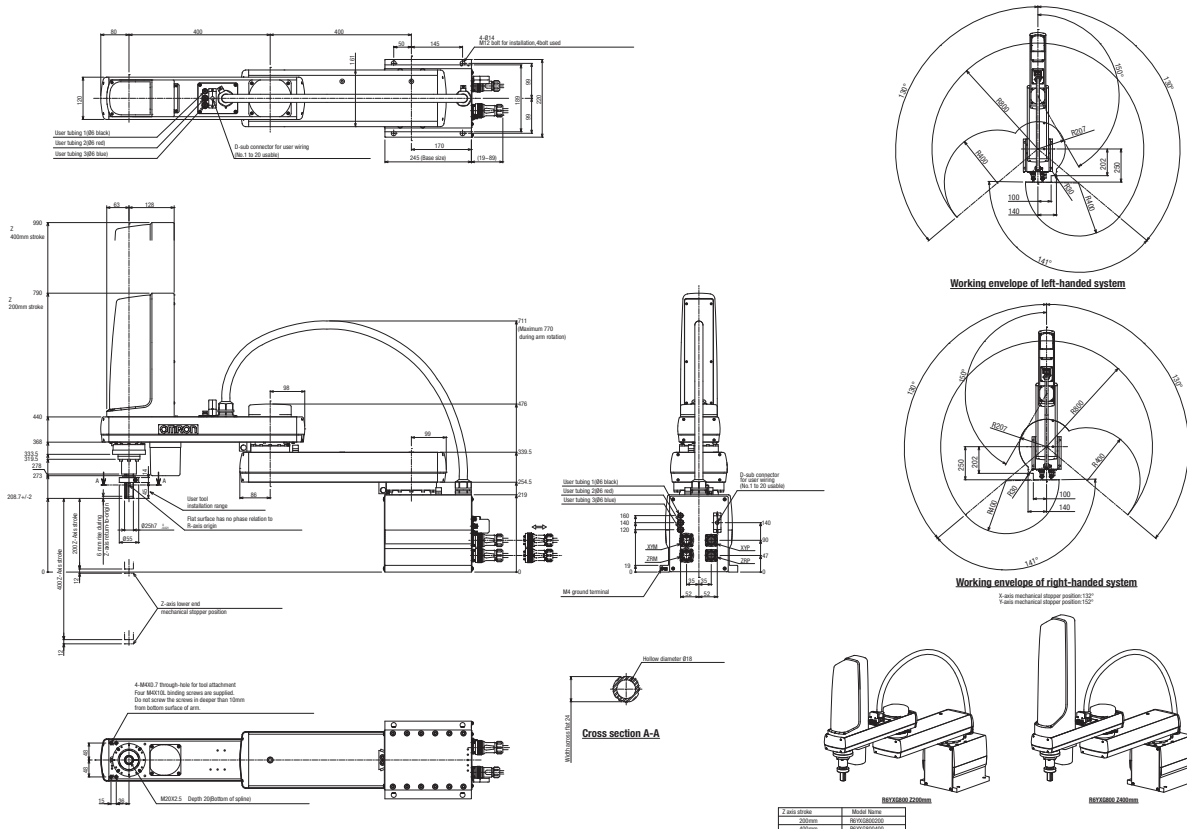

22

R6YXG700 XG SERIES - LARGE TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			700				
Maximum payload (kg)			20 (19)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		300	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			8.4		2.3	1.7	920
Standard cicle time: with 2kg payload[*3] (sec)			0.42				
R axis allowable moment inertia[*4] (kgm^2)			1				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 50, Z axis 400mm: 52				

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:152°

Cross section A-A

OMRON

R6YXG800 XG SERIES - LARGE TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			800				
Maximum payload (kg)			20 (19)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		400	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.2		2.3	1.7	920
Standard cicle time: with 2kg payload[*3] (sec)			0.48				
R axis allowable moment inertia[*4] (kgm^2)			1				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 52, Z axis 400mm: 54				

*1　Maximum payload is 19kg when tool flange option is installed.
*2　This is the value at a constant ambient temperature. (X,Y axes)
*3　When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4　There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system

Cross section A-A

R6YXG900 XG SERIES - LARGE TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			900				
Maximum payload (kg)			20 (19)[*1]				
Repeatability [*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		500	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.9		2.3	1.7	920
Standard cicle time: with 2kg payload [*3] (sec)			0.49				
R axis allowable moment inertia [*4] (kgm^2)			1				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 54, Z axis 400mm: 56				

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:152°

Cross section A-A

OMRON

R6YXG1000 XG SERIES - LARGE TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			1000				
Maximum payload (kg)			20 (19)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		600	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			10.6		2.3	1.7	920
Standard cicle time: with 2kg payload[*3] (sec)			0.49				
R axis allowable moment inertia[*4] (kgm^2)			1				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 56, Z axis 400mm: 58				

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:152°

R6YXGS(W/U)300 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE

Specifications

			X axis	Y axis	Z axis	R axis	
						W type	U type
Reach (mm)			300				
Maximum payload (kg)			5 (4)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004	
Axis specifications	Arm length (mm)		150	150	150	----	
	Rotation range (º)		+/-120	+/-130	----	+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			200	150	50	100	
Maximum speed (XYZ:m/sec) (R:º/sec)			4.4		1.0	1020	720
Standard cicle time: with 2kg payload[*3] (sec)			0.49				
R axis allowable moment inertia[*4] (kgm^2)			0.05				
User wiring (sq x pcs)			0.2 x 10				
User tubing (Outer diameter)			Ø4 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
	Open shaft		R6YACXGLS				
Weight (kg) (Excluding robot cable)			15.5				

*1   Maximum payload is 4kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

R6YXGS(W/U)400 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE
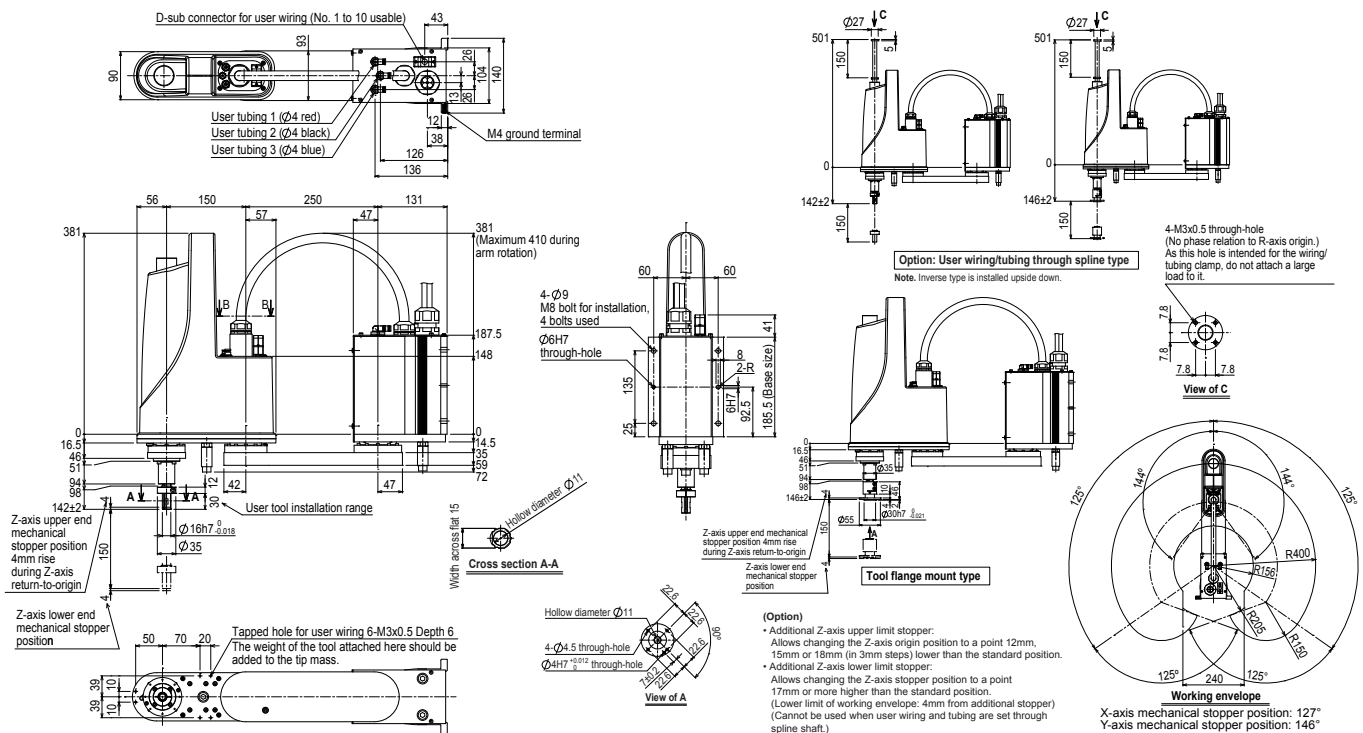
Specifications

			X axis	Y axis	Z axis	R axis	
						W type	U type
Reach (mm)			400				
Maximum payload (kg)			5 (4)[*1]				
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004	
Axis specifications	Arm length (mm)		250	150	150	----	
	Rotation range (º)		+/-125	+/-144	----	+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			200	150	50	100	
Maximum speed (XYZ:m/sec) (R:º/sec)			6.1		1.1	1020	720
Standard cicle time: with 2kg payload[*3] (sec)			0.49				
R axis allowable moment inertia[*4] (kgm²)			0.05				
User wiring (sq x pcs)			0.2 x 10				
User tubing (Outer diameter)			Ø4 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Option	Tool flange		R6YACXGLF				
	Open shaft		R6YACXGLS				
Weight (kg) (Excluding robot cable)			16				

*1   Maximum payload is 4kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

R6YXGS(W/U)500 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE
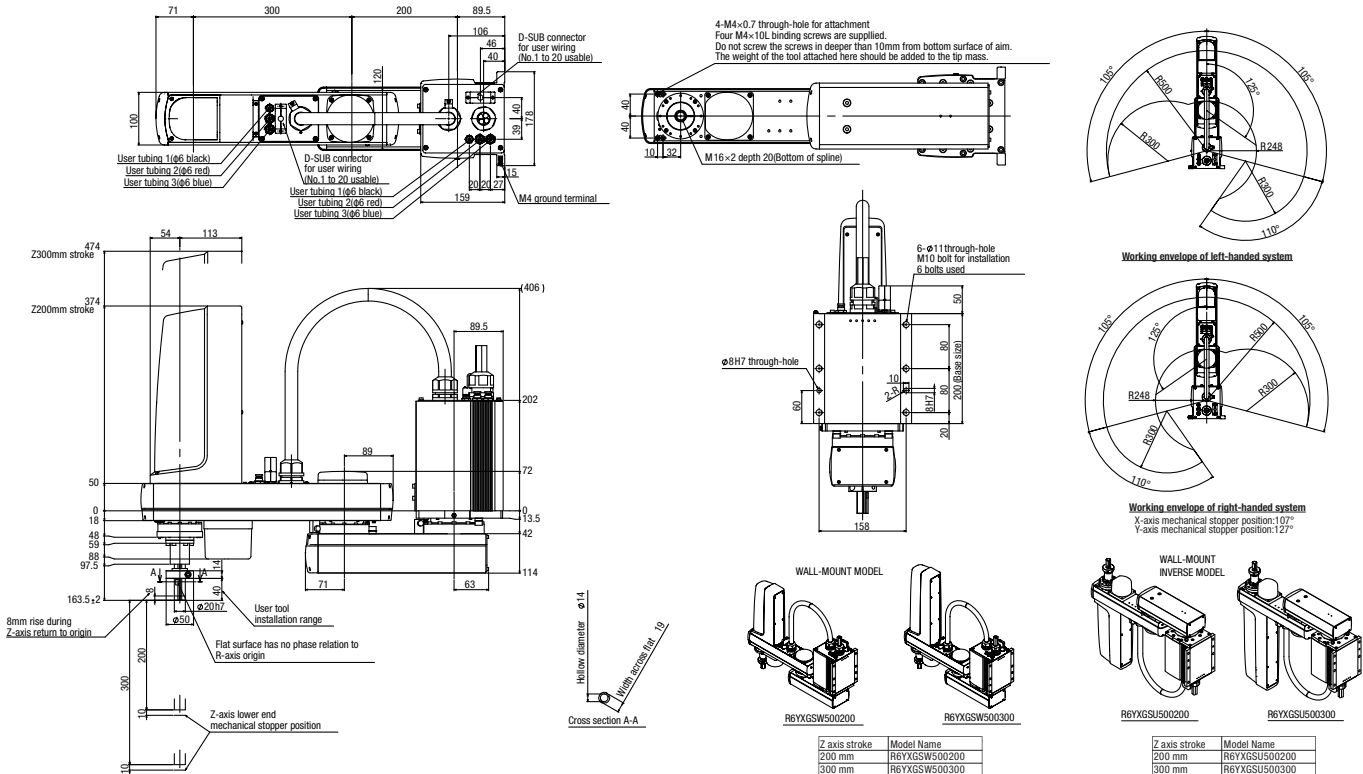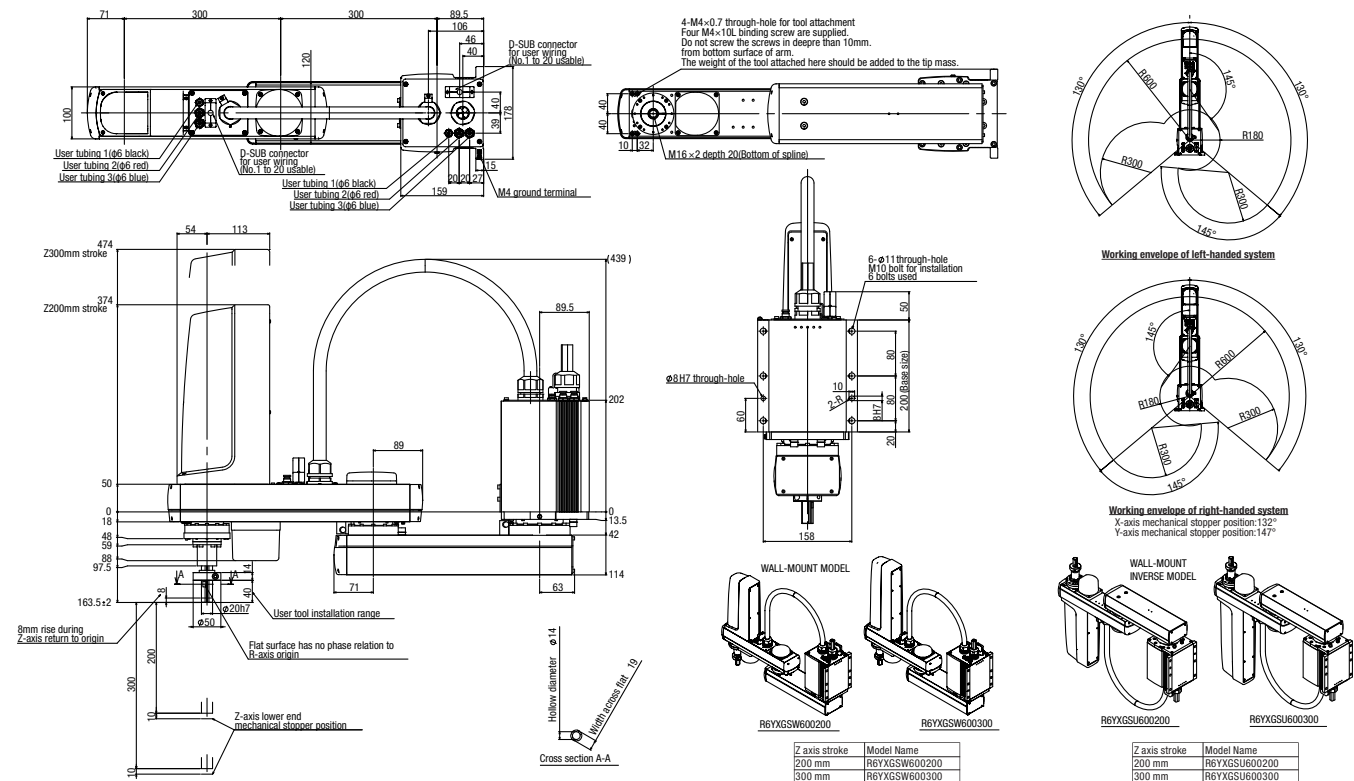
Specifications

			X axis	Y axis	Z axis		R axis	
							W type	U type
Reach (mm)			500					
Maximum payload (kg)			10 (9)[*1]					
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)		200	300	200	300	----	
	Rotation range (º)		+/-105	+/-125	----		+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled					
		Speed reducer to output	Direct-coupled					
AC servo motor output (W)			400	200	200		200	
Maximum speed (XYZ:m/sec) (R:º/sec)			7.6		2.3	1.7	1700	800
Standard cicle time: with 2kg payload[*3] (sec)			0.45					
R axis allowable moment inertia[*4] (kgm^2)			0.3					
User wiring (sq x pcs)			0.2 x 20					
User tubing (Outer diameter)			Ø6 x 3					
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)			3.5, 5, 10					
Min. cable bending radius			R27					
Option	Tool flange		R6YACXGLF					
Weight (kg) (Excluding robot cable)			26					

*1 Maximum payload is 9kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:107°
Y-axis mechanical stopper position:127°

WALL-MOUNT MODEL

R6YXGSW500200   R6YXGSW500300

Z axis stroke	Model Name
200 mm	R6YXGSW500200
300 mm	R6YXGSW500300

WALL-MOUNT INVERSE MODEL

R6YXGSU500200   R6YXGSU500300

Z axis stroke	Model Name
200 mm	R6YXGSU500200
300 mm	R6YXGSU500300

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R6YXGS(W/U)600 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE

Specifications

			X axis	Y axis	Z axis		R axis	
							W type	U type
Reach (mm)			600					
Maximum payload (kg)			10 (9)[*1]					
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.01		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)		300	300	200	300	----	
	Rotation range (º)		+/-130	+/-145	----		+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled					
		Speed reducer to output	Direct-coupled					
AC servo motor output (W)			400	200	200		200	
Maximum speed (XYZ:m/sec) (R:º/sec)			8.4		2.3	1.7	1700	800
Standard cicle time: with 2kg payload[*3] (sec)			0.46					
R axis allowable moment inertia[*4] (kgm^2)			0.3					
User wiring (sq x pcs)			0.2 x 20					
User tubing (Outer diameter)			Ø6 x 3					
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)			3.5, 5, 10					
Min. cable bending radius			R27					
Option	Tool flange		R6YACXGLF					
Weight (kg) (Excluding robot cable)			27					

*1   Maximum payload is 9kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:147°

WALL-MOUNT MODEL

R6YXGSW600200   R6YXGSW600300

Z axis stroke	Model Name
200 mm	R6YXGSW600200
300 mm	R6YXGSW600300

WALL-MOUNT INVERSE MODEL

R6YXGSU600200   R6YXGSU600300

Z axis stroke	Model Name
200 mm	R6YXGSU600200
300 mm	R6YXGSU600300

R6YXGS(W/U)700 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE

Specifications

		X axis	Y axis	Z axis		R axis	
						W type	U type
Reach (mm)		700					
Maximum payload (kg)		20 (19)[*1]					
Repeatability[*2] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)	300	400	200	400	----	
	Rotation range (º)	+/-130	+/-130	----		+/-360	
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)		750	400	400		200	
Maximum speed (XYZ:m/sec) (R:º/sec)		8.4		2.3	1.7	920	480
Standard cicle time: with 2kg payload[*3] (sec)		0.42					
R axis allowable moment inertia[*4] (kgm^2)		1.0					
User wiring (sq x pcs)		0.2 x 20					
User tubing (Outer diameter)		Ø6 x 3					
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)		3.5, 5, 10					
Min. cable bending radius		R27					
Option	Tool flange	R6YACXGLF					
Weight (kg) (Excluding robot cable)		51					

*1 Maximum payload is 19kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:132°

WALL-MOUNT MODEL

R6YXGSW700200   R6YXGSW700400

Z axis stroke	Model Name
200 mm	R6YXGSW700200
400 mm	R6YXGSW700400

WALL-MOUNT INVERSE MODEL

R6YXGSU700200   R6YXGSU700400

Z axis stroke	Model Name
200 mm	R6YXGSU700200
400 mm	R6YXGSU700400

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R6YXGS(W/U)800 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE

Specifications

			X axis	Y axis	Z axis		R axis	
							W type	U type
Reach (mm)			800					
Maximum payload (kg)			20 (19)[*1]					
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)		400	400	200	400	----	
	Rotation range (º)		+/-130	+/-145	----		+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled					
		Speed reducer to output	Direct-coupled					
AC servo motor output (W)			750	400	400		200	
Maximum speed (XYZ:m/sec) (R:º/sec)			9.2		2.3	1.7	920	480
Standard cicle time: with 2kg payload[*3] (sec)			0.48					
R axis allowable moment inertia[*4] (kgm^2)			1.0					
User wiring (sq x pcs)			0.2 x 20					
User tubing (Outer diameter)			Ø6 x 3					
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)			3.5, 5, 10					
Min. cable bending radius			R27					
Option	Tool flange		R6YACXGLF					
Weight (kg) (Excluding robot cable)			53					

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system
X-axis mechanical stopper position:132°
Y-axis mechanical stopper position:147°

WALL-MOUNT MODEL

R6YXGSW800200   R6YXGSW800400

Z axis stroke	Model Name
200 mm	R6YXGSW800200
400 mm	R6YXGSW800400

WALL-MOUNT INVERSE MODEL

R6YXGSU800200   R6YXGSU800400

Z axis stroke	Model Name
200 mm	R6YXGSU800200
400 mm	R6YXGSU800400

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R6YXGS(W/U)900 **XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE**

Specifications

Axis		X axis	Y axis	Z axis		R axis	
						W type	U type
Reach (mm)		900					
Maximum payload (kg)		20 (19)[*1]					
Repeatability[*2] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)	500	400	200	400	----	
	Rotation range (º)	+/-130	+/-150	----		+/-360	
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)		750	400	400		200	
Maximum speed (XYZ:m/sec) (R:º/sec)		9.9		2.3	1.7	920	480
Standard cicle time: with 2kg payload[*3] (sec)		0.49					
R axis allowable moment inertia[*4] (kgm^2)		1.0					
User wiring (sq x pcs)		0.2 x 20					
User tubing (Outer diameter)		Ø6 x 3					
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)		3.5, 5, 10					
Min. cable bending radius		R27					
Option	Tool flange	R6YACXGLF					
Weight (kg) (Excluding robot cable)		55					

*1 Maximum payload is 19kg when tool flange option is installed.
*2 This is the value at a constant ambient temperature. (X,Y axes)
*3 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4 There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Z axis stroke	Model Name
200 mm	R6YXGSW900200
400 mm	R6YXGSW900400

Z axis stroke	Model Name
200 mm	R6YXGSU900200
400 mm	R6YXGSU900400

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R6YXGS(W/U)1000 XG SERIES - WALL MOUNT/WALL MOUNT INVERSE TYPE

Specifications

			X axis	Y axis	Z axis		R axis	
							W type	U type
Reach (mm)			1000					
Maximum payload (kg)			20 (19)[1]					
Repeatability[2] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004	
Axis specifications	Arm length (mm)		600	400	200	400	----	
	Rotation range (º)		+/-130	+/-150	----		+/-360	
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive	
	Transmission method	Motor to speed reducer	Direct-coupled					
		Speed reducer to output	Direct-coupled					
AC servo motor output (W)			750	400	400		200	
Maximum speed (XYZ:m/sec) (R:º/sec)			10.6		2.3	1.7	920	480
Standard cicle time: with 2kg payload[3] (sec)			0.49					
R axis allowable moment inertia[4] (kgm²)			1.0					
User wiring (sq x pcs)			0.2 x 20					
User tubing (Outer diameter)			Ø6 x 3					
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)					
Robot cable length (m)			3.5, 5, 10					
Min. cable bending radius			R27					
Option	Tool flange		R6YACXGLF					
Weight (kg) (Excluding robot cable)			57					

*1   Maximum payload is 19kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

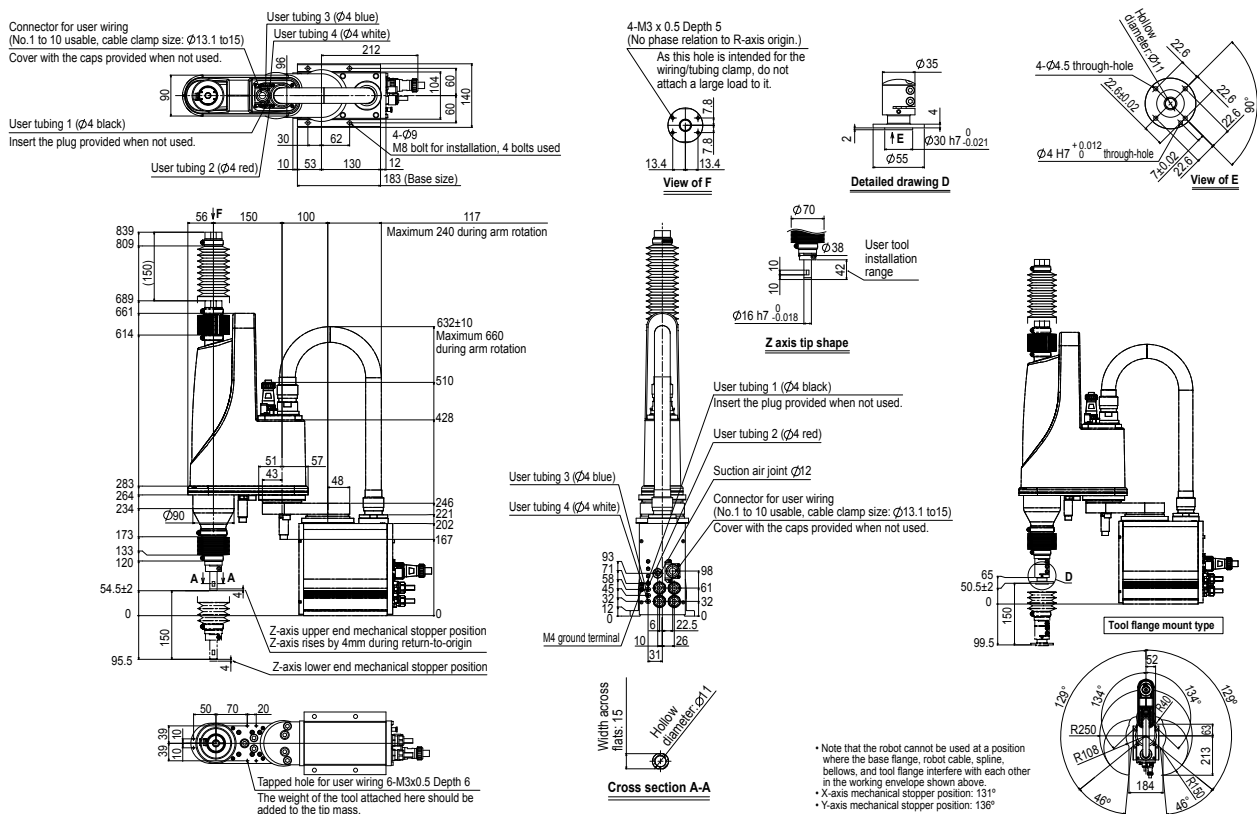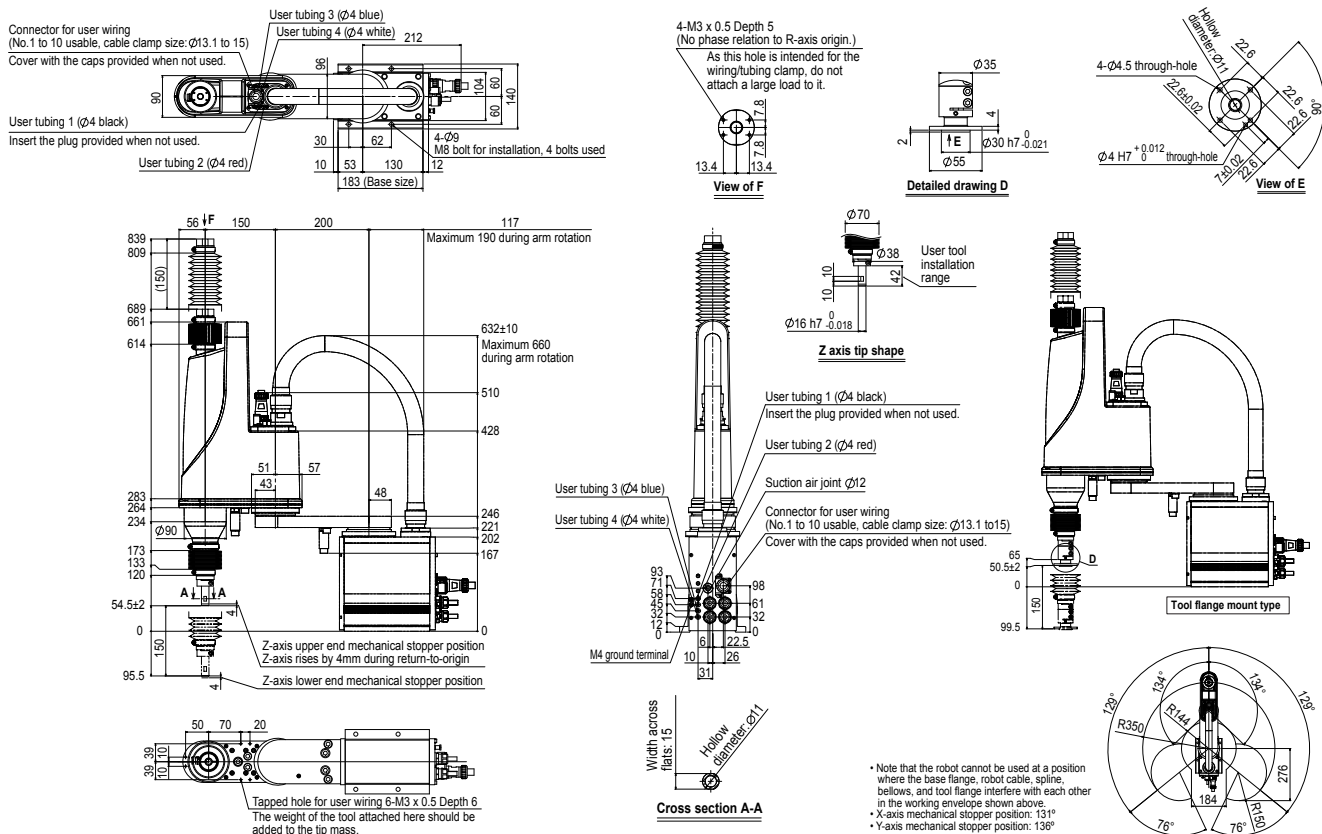# R6YXGLC250 XG SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		250			
Maximum payload (kg)		4			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	100	150	150	----
	Rotation range (º)	+/-129	+/-134	----	+/-360
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		4.5		1.1	1020
Standard cicle time: with 2kg payload[*2] (sec)		0.57			
R axis allowable moment inertia[*3] (kgm^2)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 4			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		17.5			
Degree of cleanliness		Class ISO 3 (ISO 14644-1)[*4] + ESD[*5]			
Intake air (N l/min)		30[*6]			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Class 10 (0.1 μm) equivalent to FED-STD-209D.
*5   ESD (ElectroStatic Discharge) prevention is an option. Please, contact your OMRON representative for more details.
*6   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

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R6YXGLC350 XG SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		350			
Maximum payload (kg)		4			
Repeatability[*1] **(XYZ:mm) (R:º)**		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	200	150	150	----
	Rotation range (º)	+/-129	+/-134	----	+/-360
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		5.6		1.1	1020
Standard cicle time: with 2kg payload[*2] **(sec)**		0.57			
R axis allowable moment inertia[*3] **(kgm^2)**		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 4			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		18			
Degree of cleanliness		Class ISO 3 (ISO 14644-1)[*4] + ESD[*5]			
Intake air (N l/min)		30[*6]			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Class 10 (0.1 µm) equivalent to FED-STD-209D.
*5   ESD (ElectroStatic Discharge) prevention is an option. Please, contact your OMRON representative for more details.
*6   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

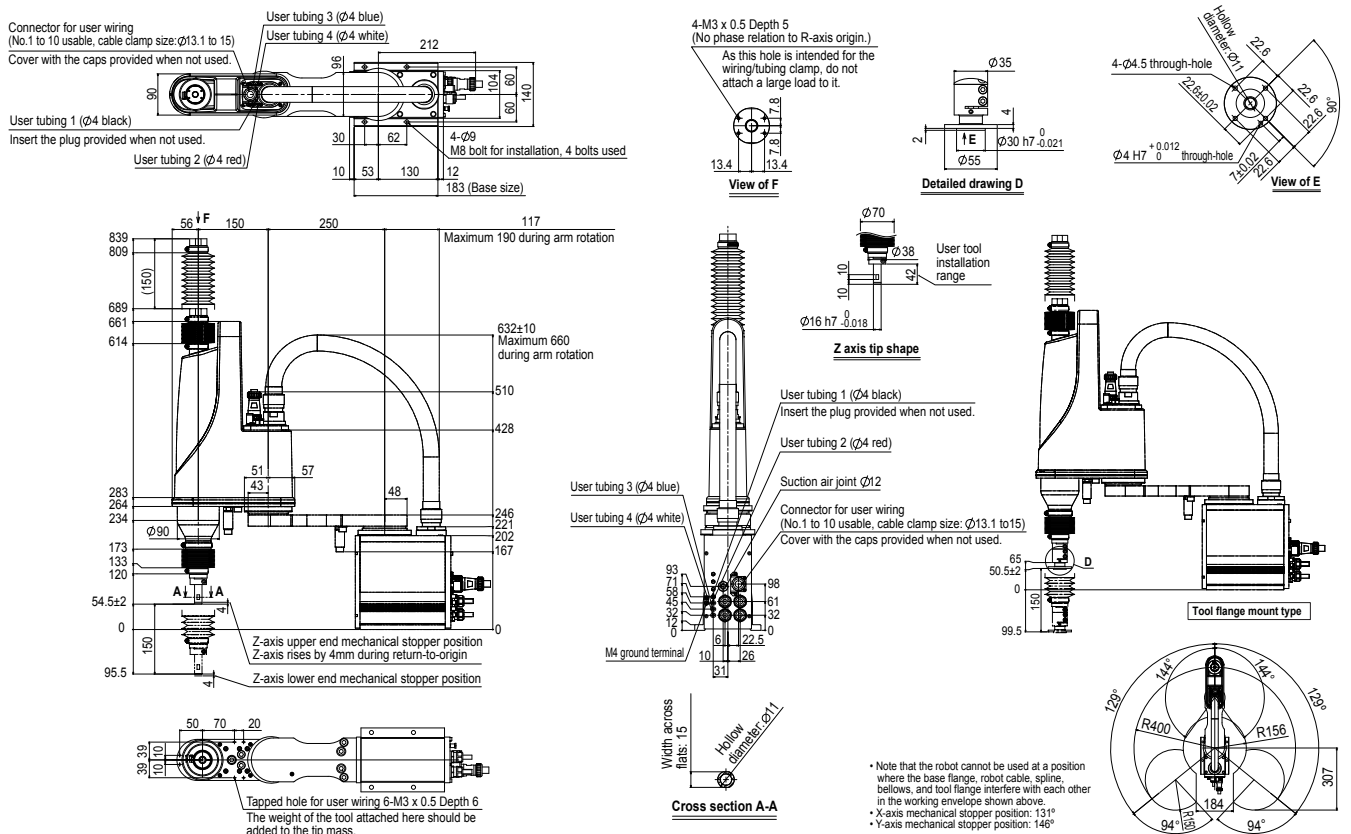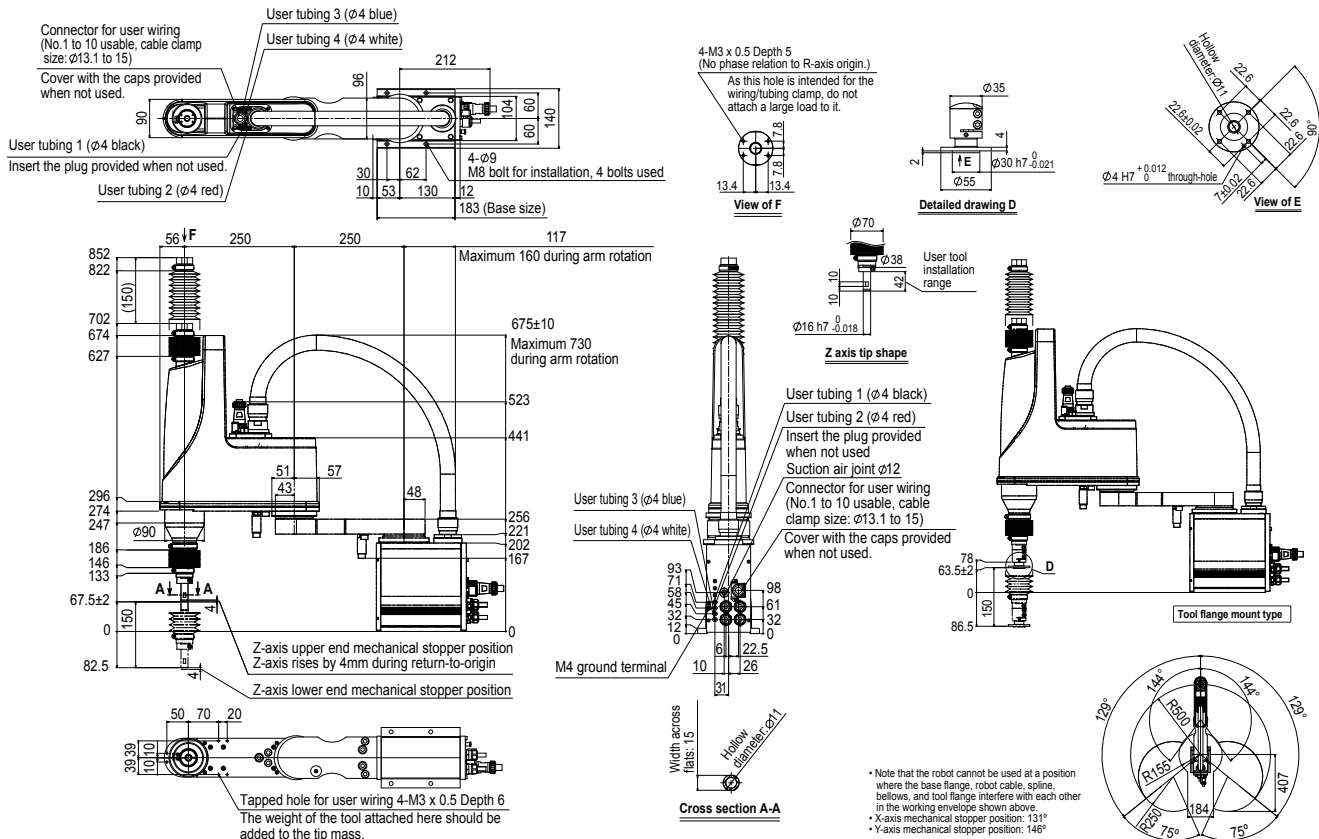# R6YXGLC400 XG SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		400			
Maximum payload (kg)		4			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	250	150	150	----
	Rotation range (º)	+/-129	+/-144	----	+/-360
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		6.1		1.1	1020
Standard cicle time: with 2kg payload [*2] (sec)		0.57			
R axis allowable moment inertia[*3] (kgm^2)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 4			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		18.5			
Degree of cleanliness		Class ISO 3 (ISO 14644-1)[*4] + ESD[*5]			
Intake air (N l/min)		30[*6]			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Class 10 (0.1 μm) equivalent to FED-STD-209D.
*5   ESD (ElectroStatic Discharge) prevention is an option. Please, contact your OMRON representative for more details.
*6   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

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R6YXGLC500 XG SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		500			
Maximum payload (kg)		4			
Repeatability*1 (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	250	250	150	----
	Rotation range (º)	+/-129	+/-144	----	+/-360
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		5.1		1.1	1020
Standard cicle time: with 2kg payload*2 (sec)		0.74			
R axis allowable moment inertia*3 (kgm²)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 4			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		21			
Degree of cleanliness		Class ISO 3 (ISO 14644-1)*4 + ESD*5			
Intake air (N l/min)		30*6			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Class 10 (0.1 μm) equivalent to FED-STD-209D.
*5   ESD (ElectroStatic Discharge) prevention is an option. Please, contact your OMRON representative for more details.
*6   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

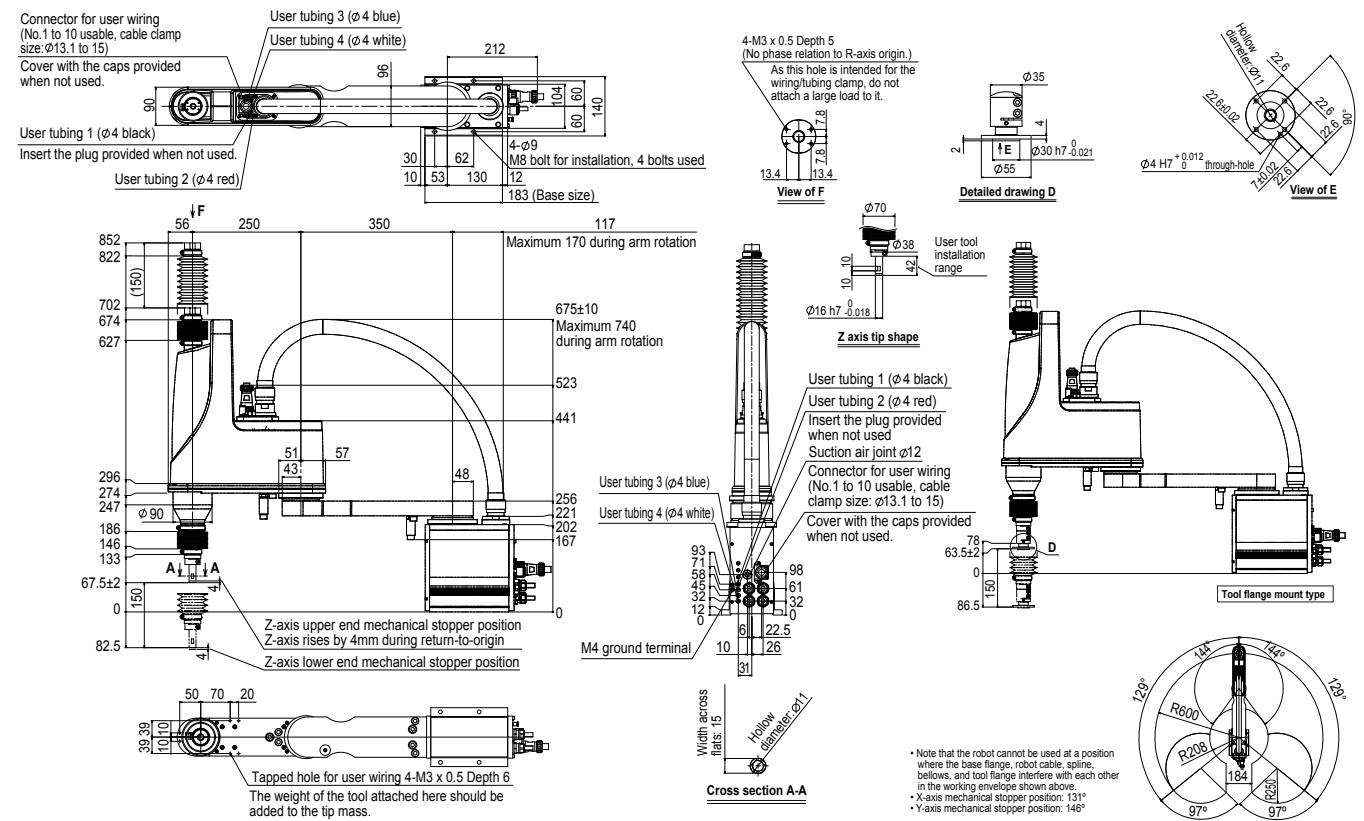# R6YXGLC600 XG SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		600			
Maximum payload (kg)		4			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	350	250	150	----
	Rotation range (º)	+/-129	+/-144	----	+/-360
AC servo motor output (W)		200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)		4.9		1.1	1020
Standard cicle time: with 2kg payload[*2] (sec)		0.74			
R axis allowable moment inertia[*3] (kgm^2)		0.05			
User wiring (sq x pcs)		0.2 x 10			
User tubing (Outer diameter)		Ø4 x 4			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Min. cable bending radius		R27			
Option	Tool flange	R6YACXGLF			
	Open shaft	R6YACXGLS			
Weight (kg) (Excluding robot cable)		22			
Degree of cleanliness		Class ISO 3 (ISO 14644-1)[*4] + ESD[*5]			
Intake air (N l/min)		30[*6]			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Class 10 (0.1 μm) equivalent to FED-STD-209D.
*5   ESD (ElectroStatic Discharge) prevention is an option. Please, contact your OMRON representative for more details.
*6   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXGLP250 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			250			
Maximum payload (kg)			4			
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		100	150	150	----
	Rotation range (º)		+/-129	+/-134	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			4.5		1.1	1020
Standard cicle time: with 2kg payload[*2] (sec)			0.57			
R axis allowable moment inertia[*3] (kgm^2)			0.05			
Protection class[*4]			Equivalent to IP65 (IEC 60529)			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 4			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			17.5			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
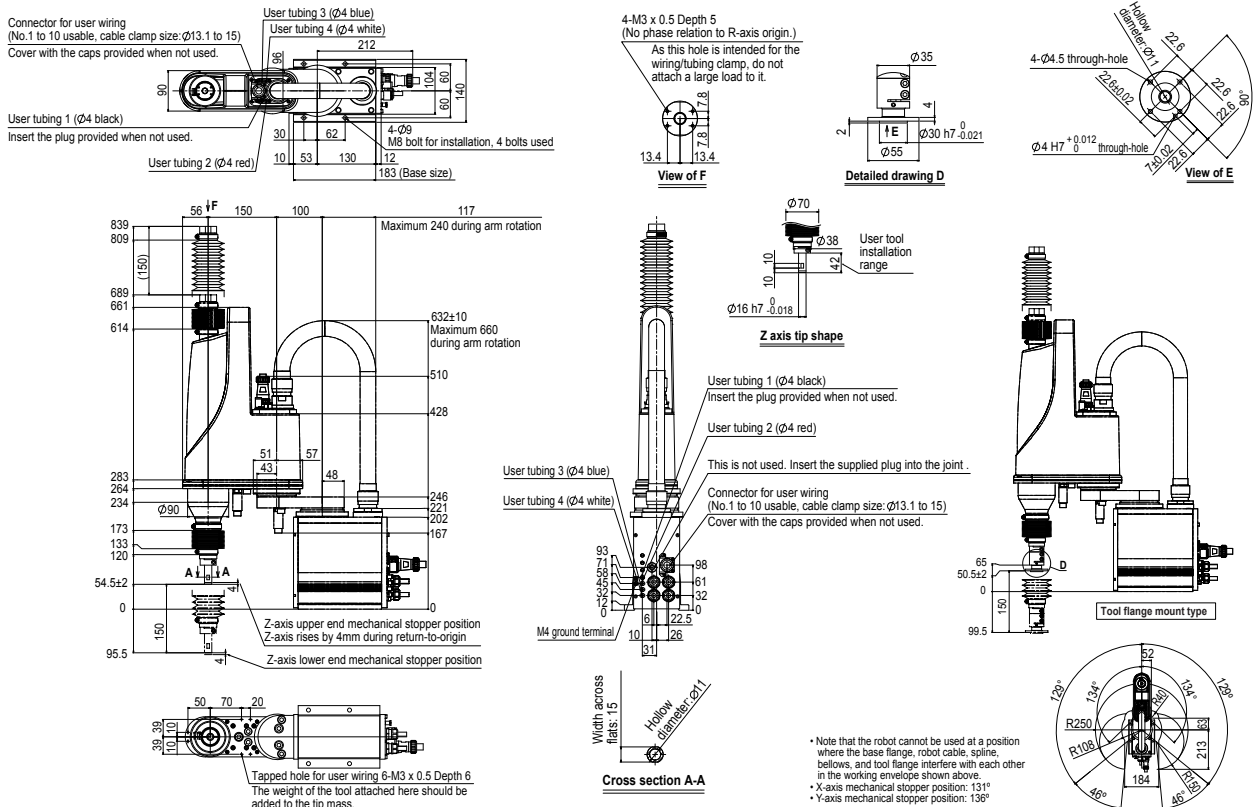*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

R6YXGLP350 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			350			
Maximum payload (kg)			4			
Repeatability*1 (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		200	150	150	----
	Rotation range (º)		+/-129	+/-134	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			5.6		1.1	1020
Standard cicle time: with 2kg payload*2 (sec)			0.57			
R axis allowable moment inertia*3 (kgm2)			0.05			
Protection class*4			Equivalent to IP65 (IEC 60529)			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 4			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			18			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
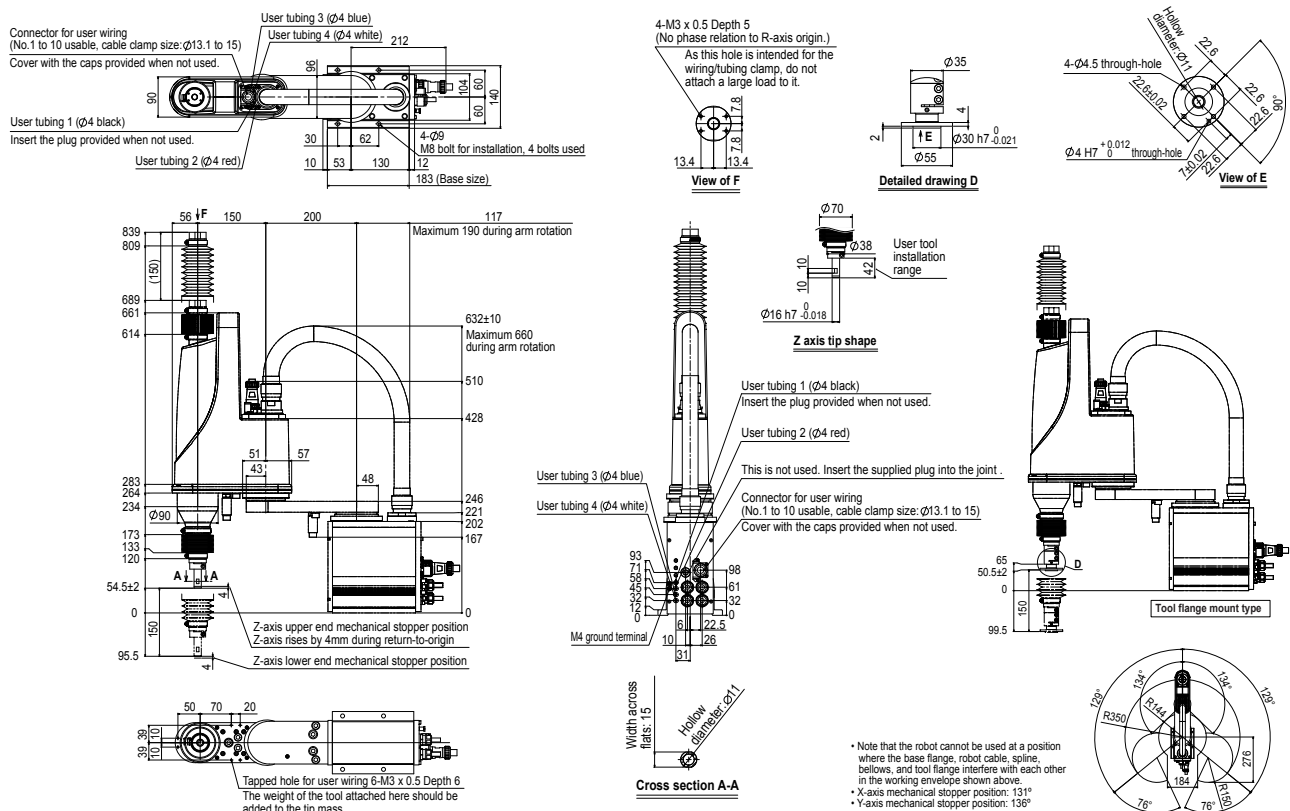*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXGLP400 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			400			
Maximum payload (kg)			4			
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		250	150	150	----
	Rotation range (º)		+/-129	+/-144	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			6.1		1.1	1020
Standard cicle time: with 2kg payload[*2] (sec)			0.57			
R axis allowable moment inertia[*3] (kgm^2)			0.05			
Protection class[*4]			Equivalent to IP65 (IEC 60529)			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 4			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			18.5			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
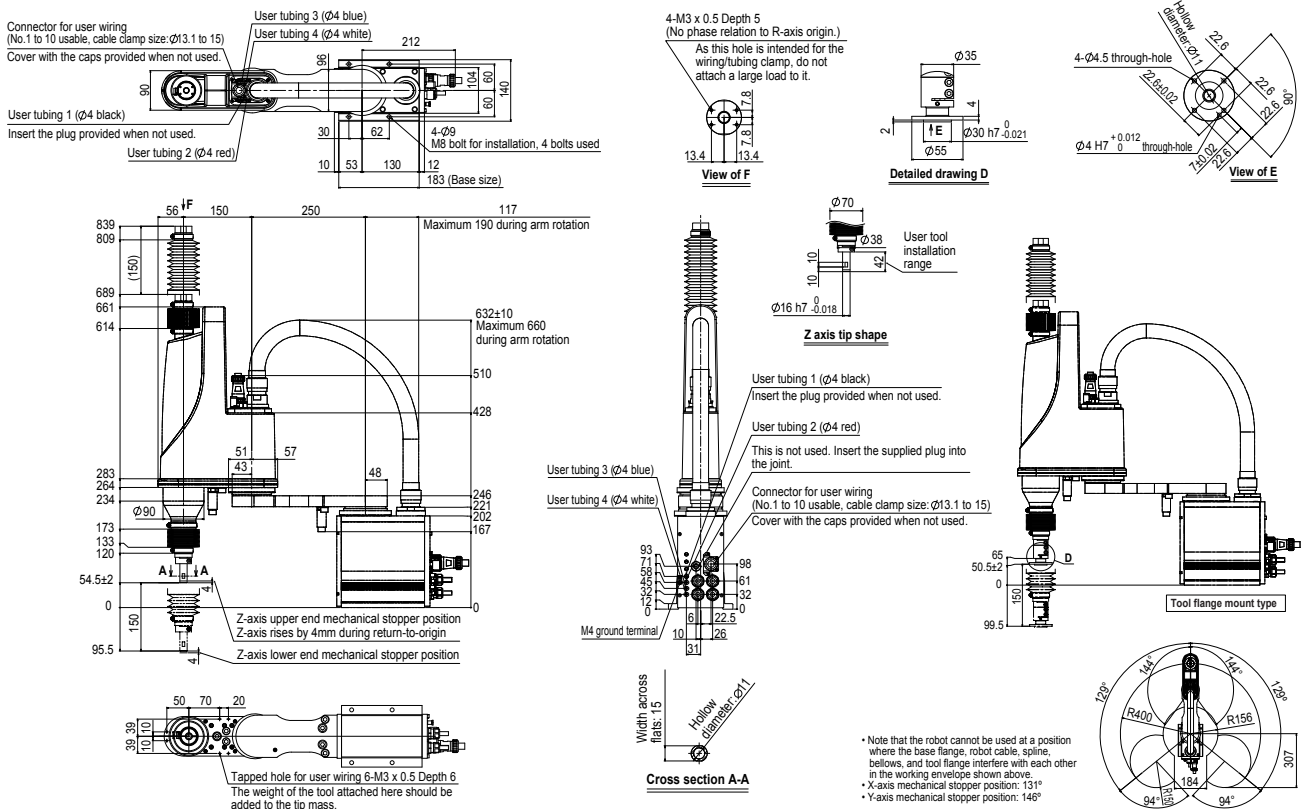*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

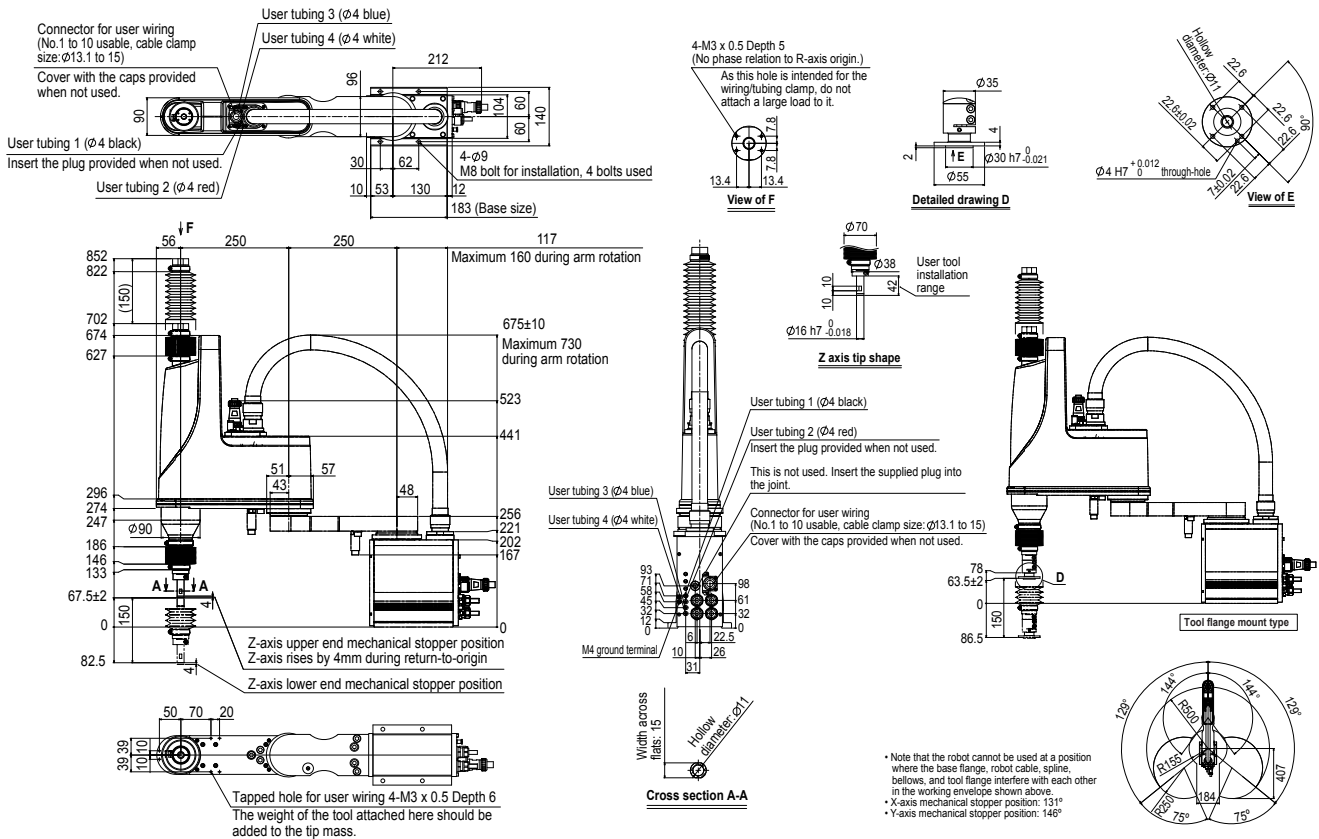# R6YXGLP500 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			500			
Maximum payload (kg)			4			
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		250	250	150	----
	Rotation range (º)		+/-129	+/-144	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			5.1		1.1	1020
Standard cicle time: with 2kg payload[*2] (sec)			0.74			
R axis allowable moment inertia[*3] (kgm^2)			0.05			
Protection class[*4]			Equivalent to IP65 (IEC 60529)			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 4			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			21			

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3 There are limits to the setting of the acceleration coefficient.
*4 Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXGP500 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			500				
Maximum payload (kg)			8				
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.01		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		200	300	200	300	----
	Rotation range (º)		+/-130	+/-145	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			400	200	200		200
Maximum speed (XYZ:m/sec) (R:º/sec)			7.6		2.3	1.7	1700
Standard cicle time: with 2kg payload[*2] (sec)			0.55				
R axis allowable moment inertia[*3] (kgm^2)			0.3				
Protection class[*4]			Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 28, Z axis 300mm: 29				

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
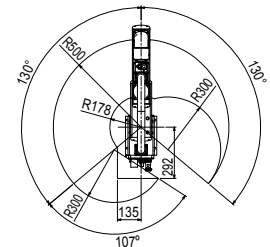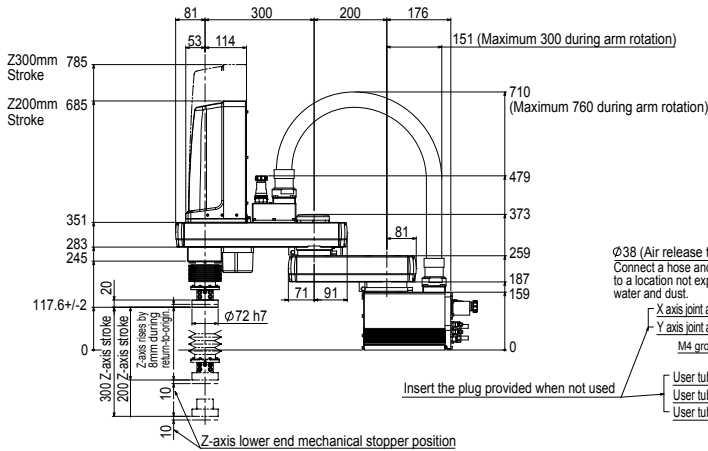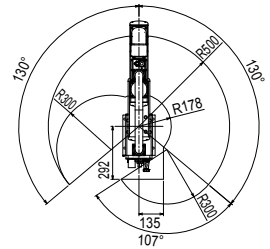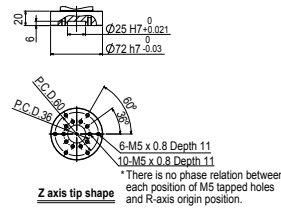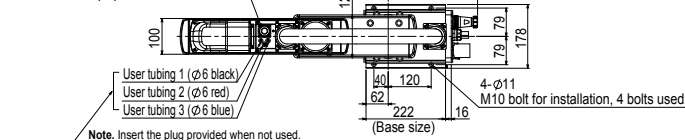*3 There are limits to the setting of the acceleration coefficient.
*4 Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system

• Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above.
• X-axis mechanical stopper position : 132º
• Y-axis mechanical stopper position : 147º

R6YXGLP600 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			600			
Maximum payload (kg)			4			
Repeatability*1 (XYZ:mm) (R:º)			+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)		350	250	150	----
	Rotation range (º)		+/-129	+/-144	----	+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw	Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			200	150	50	100
Maximum speed (XYZ:m/sec) (R:º/sec)			4.9		1.1	1020
Standard cicle time: with 2kg payload*2 (sec)			0.74			
R axis allowable moment inertia*3 (kgm²)			0.05			
Protection class*4			Equivalent to IP65 (IEC 60529)			
User wiring (sq x pcs)			0.2 x 10			
User tubing (Outer diameter)			Ø4 x 4			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	Tool flange		R6YACXGLF			
	Open shaft		R6YACXGLS			
Weight (kg) (Excluding robot cable)			22			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
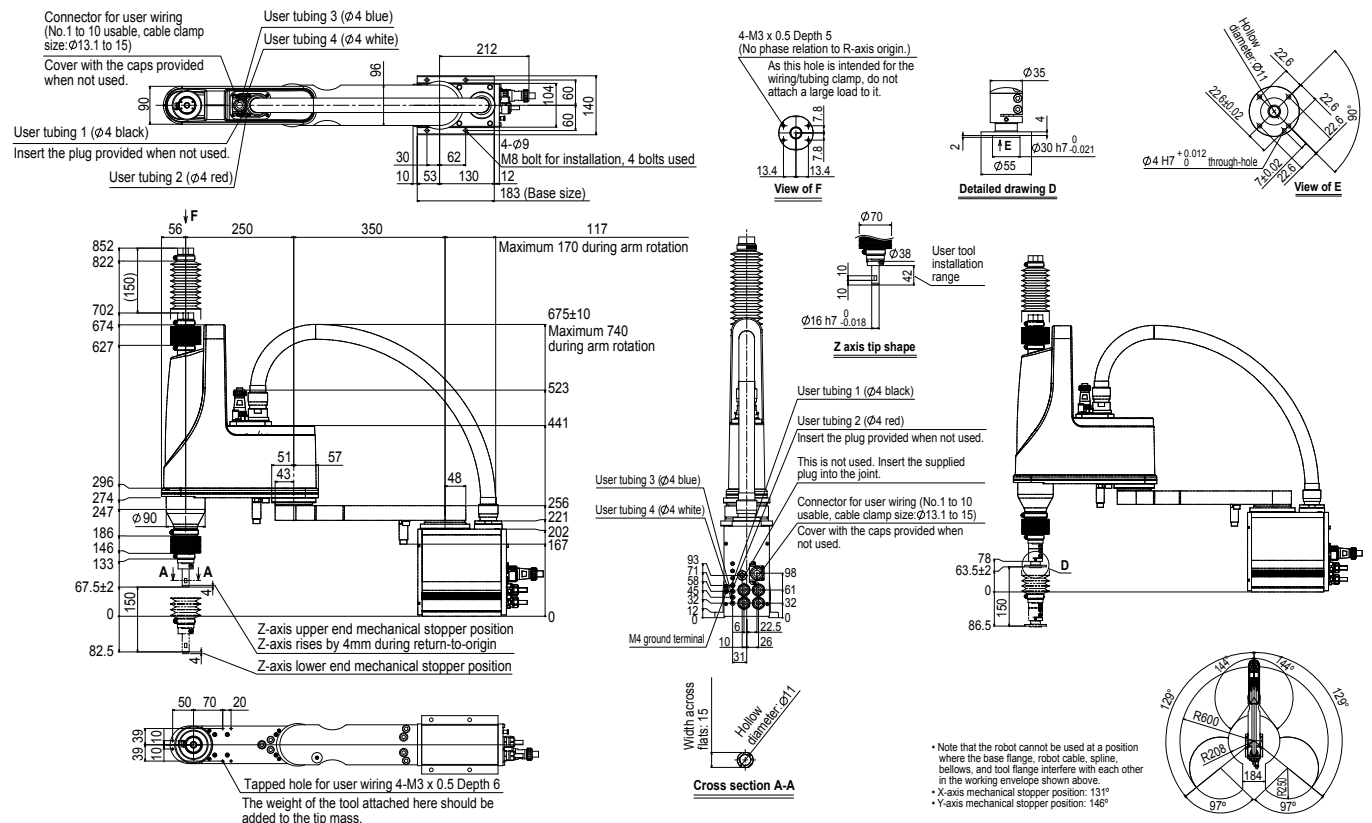*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXGP600 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		600				
Maximum payload (kg)		8				
Repeatability[*1] **(XYZ:mm) (R:º)**		+/-0.01		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)	300	300	200	300	----
	Rotation range (º)	+/-130	+/-145	----		+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)		400	200	200		200
Maximum speed (XYZ:m/sec) (R:º/sec)		8.4		2.3	1.7	1700
Standard cicle time: with 2kg payload[*2] **(sec)**		0.56				
R axis allowable moment inertia[*3] **(kgm²)**		0.3				
Protection class[*4]		Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg) (Excluding robot cable)		Z axis 200mm: 29, Z axis 300mm: 30				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
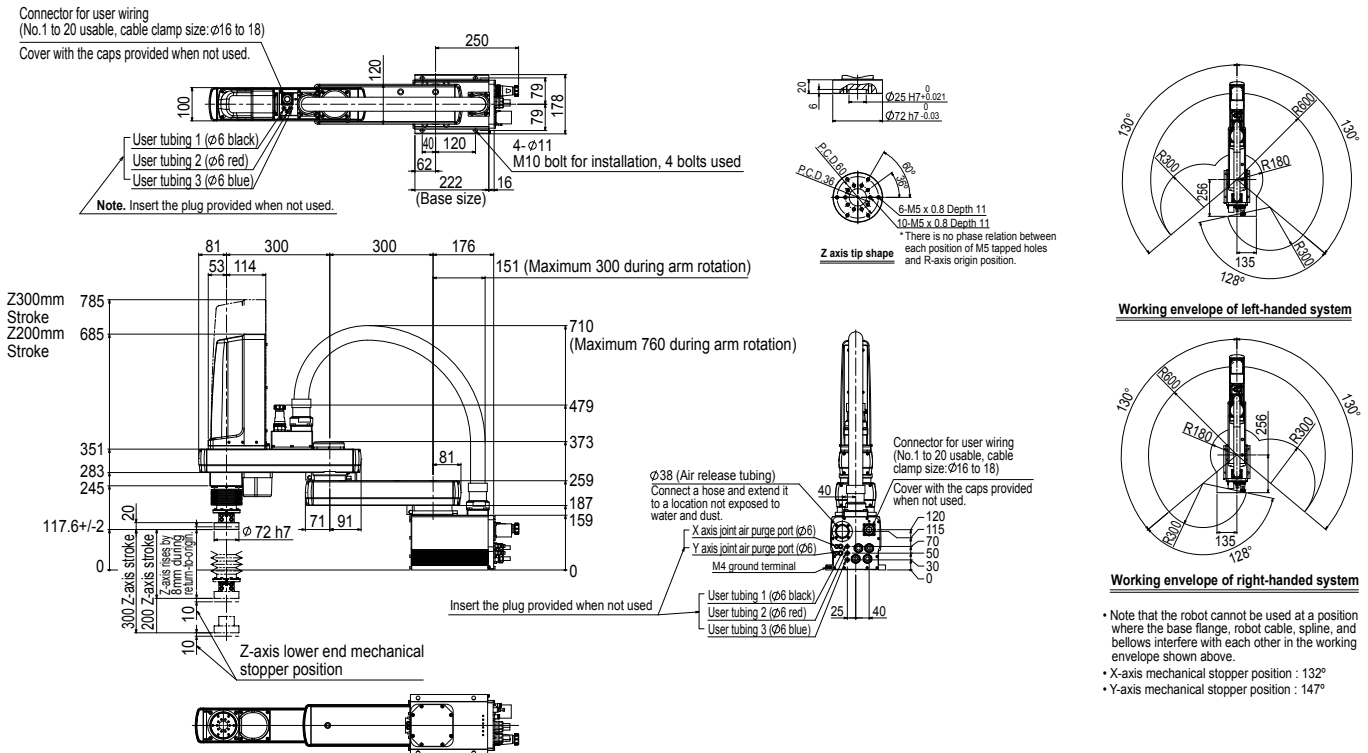*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1700	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system

• Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above.
• X-axis mechanical stopper position : 132º
• Y-axis mechanical stopper position : 147º

R6YXGHP600 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

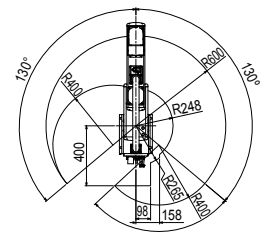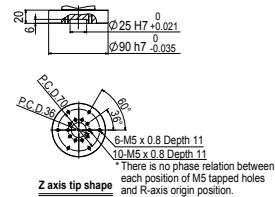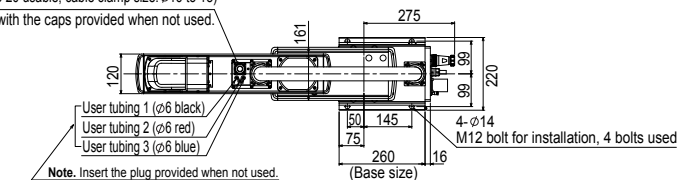|			X axis	Y axis	Z axis		R axis
Reach (mm)			600				
Maximum payload (kg)			18				
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		200	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			7.7		2.3	1.7	920
Standard cicle time: with 2kg payload[*2] (sec)			0.57				
R axis allowable moment inertia[*3] (kgm^2)			1.0				
Protection class[*4]			Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 48, Z axis 400mm: 50				

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3 There are limits to the setting of the acceleration coefficient.
*4 Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope of left-handed system

Working envelope of right-handed system

• Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above.
• X-axis mechanical stopper position : 132º
• Y-axis mechanical stopper position : 152º

OMRON

R6YXGP700 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		700				
Maximum payload (kg)		18				
Repeatability*1 (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)	300	400	200	400	----
	Rotation range (º)	+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer	Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)		750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)		8.4		2.3	1.7	920
Standard cicle time: with 2kg payload*2 (sec)		0.52				
R axis allowable moment inertia*3 (kgm2)		1.0				
Protection class*4		Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg) (Excluding robot cable)		Z axis 200mm: 50, Z axis 400mm: 52				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.
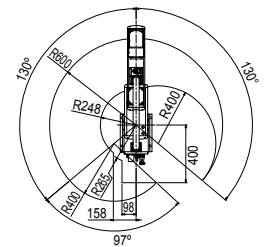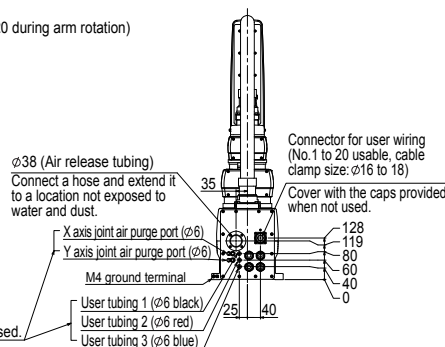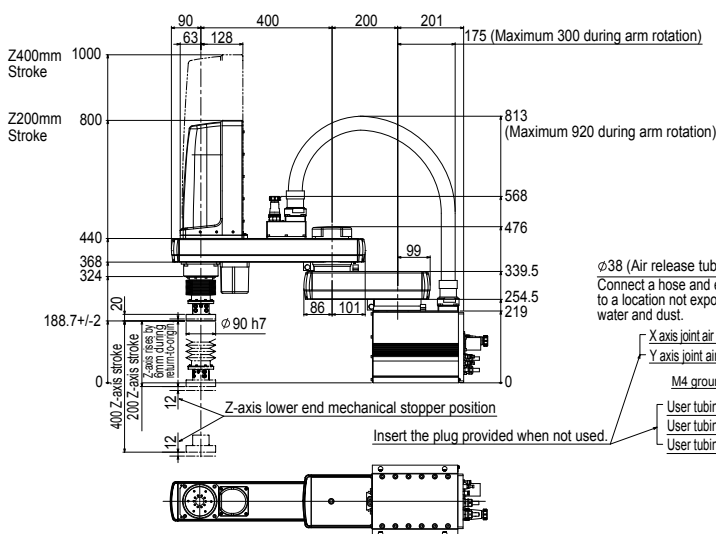
Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

R6YXGP800 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			800				
Maximum payload (kg)			18				
Repeatability[*1] (XYZ:mm) (R:º)			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		400	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.2		2.3	1.7	920
Standard cicle time: with 2kg payload[*2] (sec)			0.58				
R axis allowable moment inertia[*3] (kgm^2)			1.0				
Protection class[*4]			Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 52, Z axis 400mm: 54				

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
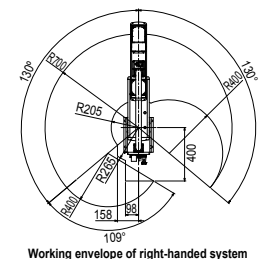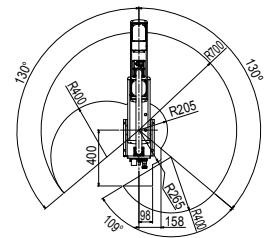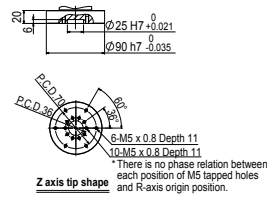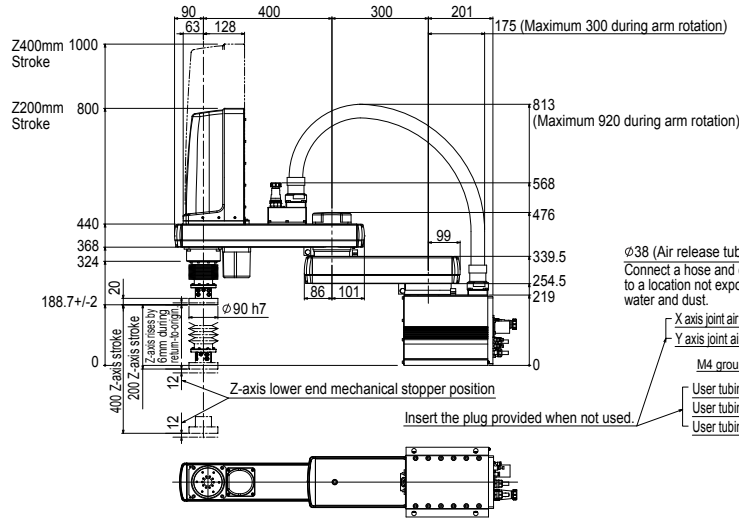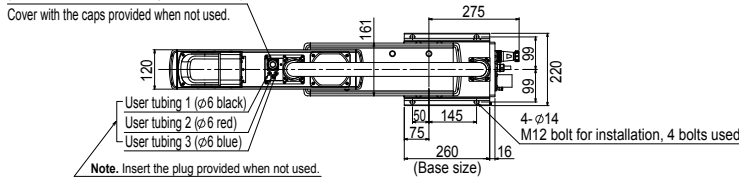*3 There are limits to the setting of the acceleration coefficient.
*4 Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Connector for user wiring
(No.1 to 20 usable, cable clamp size: ∅16 to 18)
Cover with the caps provided when not used.

User tubing 1 (∅6 black)
User tubing 2 (∅6 red)
User tubing 3 (∅6 blue)

Note. Insert the plug provided when not used.

4-∅14
M12 bolt for installation, 4 bolts used
(Base size)

Z400mm 1000 Stroke
Z200mm 800 Stroke

175 (Maximum 300 during arm rotation)
813 (Maximum 920 during arm rotation)

Z-axis lower end mechanical stopper position
Insert the plug provided when not used.

∅38 (Air release tubing)
Connect a hose and extend it to a location not exposed to water dust.

X axis joint air purge port (∅6)
Y axis joint air purge port (∅6)
M4 ground terminal
User tubing 1 (∅6 black)
User tubing 2 (∅6 red)
User tubing 3 (∅6 blue)

Connector for user wiring
(No.1 to 20 usable, cable clamp size: ∅16 to 18)
Cover with the caps provided when not used.

Ø25 H7
Ø90 h7

6-M5 x 0.8 Depth 11
10-M5 x 0.8 Depth 11
* There is no phase relation between each position of M5 tapped holes and R-axis origin position.
Z axis tip shape

Working envelope of left-handed system

Working envelope of right-handed system

• Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above.
• X-axis mechanical stopper position : 132º
• Y-axis mechanical stopper position : 152º

OMRON

R6YXGP900 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

			X axis	Y axis	Z axis		R axis
Reach (mm)			900				
Maximum payload (kg)			18				
Repeatability[*1] **(XYZ:mm) (R:º)**			+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)		500	400	200	400	----
	Rotation range (º)		+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer		Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer	Direct-coupled				
		Speed reducer to output	Direct-coupled				
AC servo motor output (W)			750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)			9.9		2.3	1.7	920
Standard cicle time: with 2kg payload[*2] **(sec)**			0.59				
R axis allowable moment inertia[*3] **(kgm²)**			1.0				
Protection class[*4]			Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)			0.2 x 20				
User tubing (Outer diameter)			Ø6 x 3				
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)			3.5, 5, 10				
Min. cable bending radius			R27				
Weight (kg) (Excluding robot cable)			Z axis 200mm: 54, Z axis 400mm: 56				

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3 There are limits to the setting of the acceleration coefficient.
*4 Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.
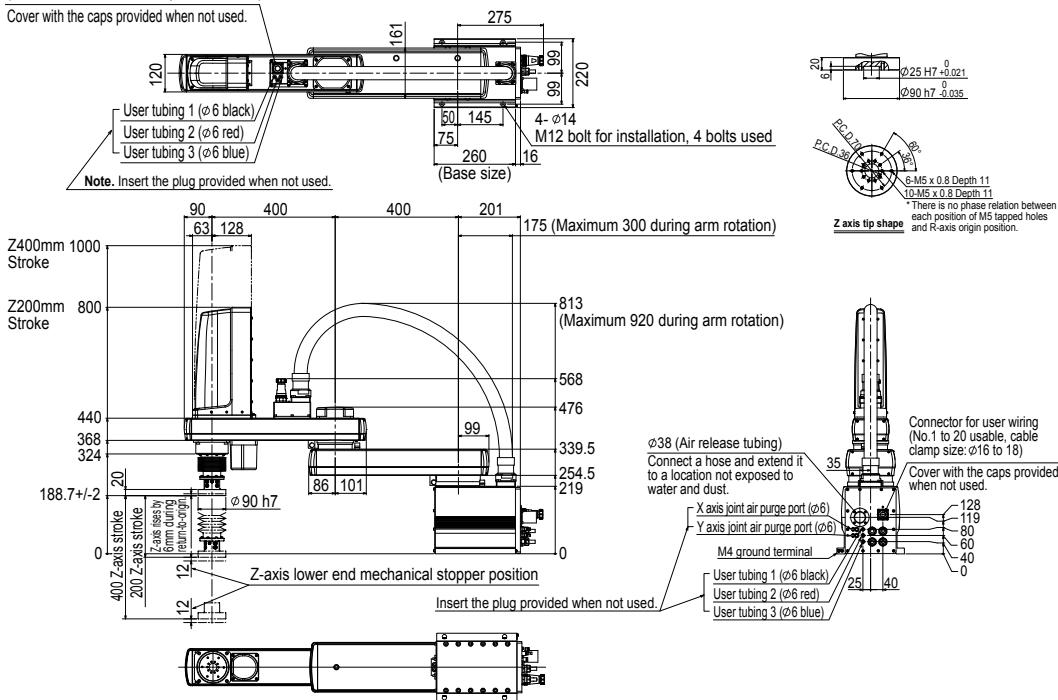
Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

R6YXGP1000 XG SERIES - DUST-PROOF & DRIP-PROOF TYPE

Specifications

				X axis	Y axis	Z axis		R axis
Reach (mm)				1000				
Maximum payload (kg)				18				
Repeatability[*1] (XYZ:mm) (R:º)				+/-0.02		+/-0.01		+/-0.004
Axis specifications	Arm length (mm)			600	400	200	400	----
	Rotation range (º)			+/-130	+/-150	----		+/-360
Deceleration mechanism	Speed reducer			Harmonic drive	Harmonic drive	Ball screw		Harmonic drive
	Transmission method	Motor to speed reducer		Direct-coupled				
		Speed reducer to output		Direct-coupled				
AC servo motor output (W)				750	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)				10.6		2.3	1.7	920
Standard cicle time: with 2kg payload[*2] (sec)				0.59				
R axis allowable moment inertia[*3] (kgm^2)				1.0				
Protection class[*4]				Equivalent to IP65 (IEC 60529)				
User wiring (sq x pcs)				0.2 x 20				
User tubing (Outer diameter)				Ø6 x 3				
Movement limit setting				1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)				3.5, 5, 10				
Min. cable bending radius				R27				
Weight (kg) (Excluding robot cable)				Z axis 200mm: 56, Z axis 400mm: 58				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
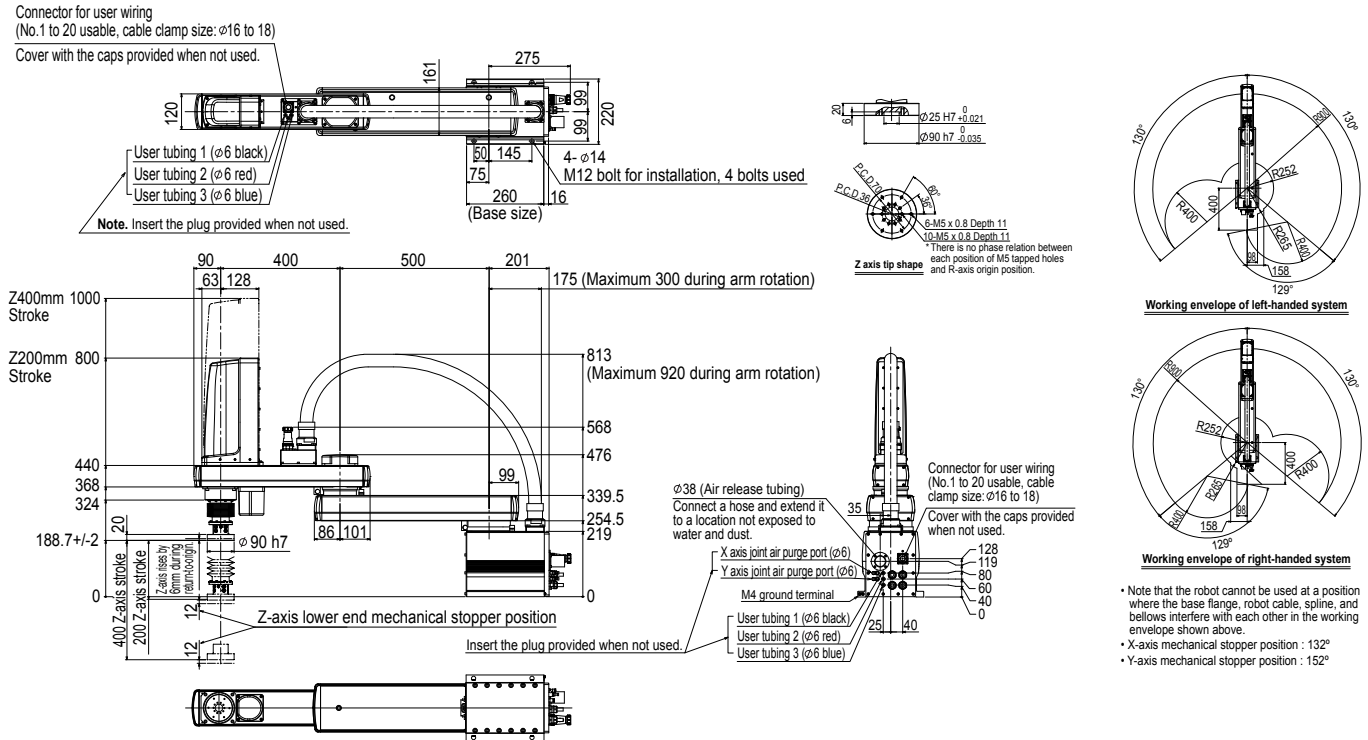*3   There are limits to the setting of the acceleration coefficient.
*4   Do not use robots where the bellows section is directly exposed to water jet. Contact your OMRON representative for information on drip-proof structure preventing liquid other than water.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

R6YXX1200 X SERIES - HIGH PAYLOAD TYPE

Specifications

			X axis	Y axis	Z axis	R axis
Reach (mm)			1200			
Maximum payload (kg)			50 (49)[*1]			
Repeatability[*2] (XYZ:mm) (R:º)			+/-0.05		+/-0.02	+/-0.005
Axis specifications	**Arm length (mm)**		600	600	400	----
	Rotation range (º)		+/-125	+/-150	----	+/-360
Deceleration mechanism	**Speed reducer**		Planetary gear	Planetary gear	Ball screw	Harmonic drive
	Transmission method	**Motor to speed reducer**	Direct-coupled		Timing belt transmission	Timing belt transmission
		Speed reducer to output	Direct-coupled			
AC servo motor output (W)			900	800	600	400
Maximum speed (XYZ:m/sec) (R:º/sec)			7.4		0.75	600
Standard cicle time: with 2kg payload[*3] (sec)			0.91			
R axis allowable moment inertia[*4] (kgm^2)			2.45			
User wiring (sq x pcs)			0.2 x 20			
User tubing (Outer diameter)			Ø6 x 3			
Movement limit setting			1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)			3.5, 5, 10			
Min. cable bending radius			R27			
Option	**Tool flange**		R6YACXGLF			
Weight (kg) (Excluding robot cable)			124			

*1   Maximum payload is 49kg when tool flange option is installed.
*2   This is the value at a constant ambient temperature. (X,Y axes)
*3   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
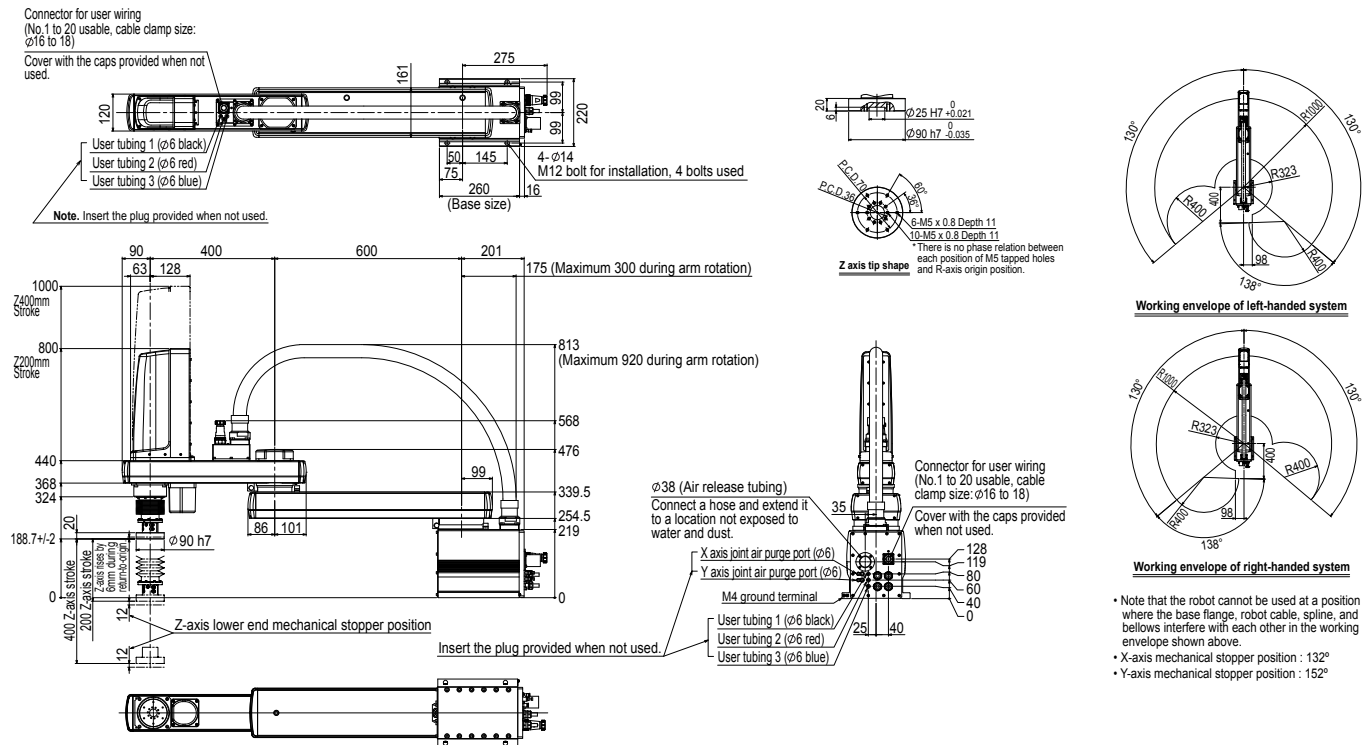*4   There are limits to the setting of the acceleration coefficient.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope

R6YXC180 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		180			
Maximum payload (kg)		1			
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	71	109	100	----
	Rotation range (º)	+/-120	+/-140	----	+/-360
AC servo motor output (W)		50	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)		3.3		0.7	1700
Standard cicle time: with 0.1kg payload[*2] (sec)		0.42			
R axis allowable moment inertia[*3] (kgm²)		0.01			
User wiring (sq x pcs)		0.1 x 8			
User tubing (Outer diameter)		Ø3 x 2			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Weight (kg) (Excluding robot cable)[*4]		6.5			
Robot cable weight		1.5kg (3.5m), 2.1kg (5m), 4.2kg (10m)			
Min. cable bending radius		R27			
Degree of cleanliness		CLASS 10 (0.1 micron base)			
Intake air (N l/min)		30			

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   The total robot weight is the sum of the robot body weight and the cable weight.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Left-hand side system operation range

Right-hand side system operation range

D-sub connector for user cables 9 pin
(Adapted to #1 to 8)

4-Ø7
4 M6 bolts used for installation

User tubes 1 (Barb fitting Ø3)
User tubes 2 (Barb fitting Ø3)

500
(When the arm turns 510)

12:User tool installation area

Cover

D-sub connector for user cables 9 pin
(Adapted to #1 to 8)
Cover internal intake pipe (bulkhead union Ø8)
X, Y, R axis joint section intake pipe (bulkhead union Ø6)
User tubes 2 (bulkhead union Ø3)
User tubes 1 (bulkhead union Ø3)

M3 grounding terminal

X axis origin point is 0°+/-5° from the base front surface

4-M3 x 0.5   Depth 6
User tool installation tap

Ø 10H7 +0.015/0 Depth 2
4-M3 x 0.5 Depth 6

The user tool installation flange center line is offset within +/-5° relative to the R axis origin point.

Z axis mechanical stopper

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

OMRON

R6YXC220 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis	R axis
Reach (mm)		220			
Maximum payload (kg)		1			
Repeatability[*1] **(XYZ:mm) (R:º)**		+/-0.01		+/-0.01	+/-0.004
Axis specifications	Arm length (mm)	111	109	100	----
	Rotation range (º)	+/-120	+/-140	----	+/-360
AC servo motor output (W)		50	30	30	30
Maximum speed (XYZ:m/sec) (R:º/sec)		3.4		0.7	1700
Standard cicle time: with 0.1kg payload[*2] **(sec)**		0.45			
R axis allowable moment inertia[*3] **(kgm^2)**		0.01			
User wiring (sq x pcs)		0.1 x 8			
User tubing (Outer diameter)		Ø3 x 2			
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)			
Robot cable length (m)		3.5, 5, 10			
Weight (kg) (Excluding robot cable)[*4]		6.5			
Robot cable weight		1.5kg (3.5m), 2.1kg (5m), 4.2kg (10m)			
Min. cable bending radius		R27			
Degree of cleanliness		CLASS 10 (0.1 micron base)			
Intake air (N l/min)		30			

*1　This is the value at a constant ambient temperature. (X,Y axes)
*2　When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.
*3　There are limits to the setting of the acceleration coefficient.
*4　The total robot weight is the sum of the robot body weight and the cable weight.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Left-hand side system operation range

Right-hand side system operation range

Z axis mechanical stopper

The user tool installation flange center line is offset within +/-5° relative to the R axis origin point.

X axis origin point is 0°+/-5° from the base front surface

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

R6YXC500 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		500				
Maximum payload (kg)		10				
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)	250	250	200	300	----
	Rotation range (º)	+/-120	+/-142	----		+/-360
AC servo motor output (W)		400	200	200		100
Maximum speed (XYZ:m/sec) (R:º/sec)		4.9		1.7		876
Standard cicle time: with 2kg payload[*2] (sec)		0.53				
R axis allowable moment inertia[*3] (kgm^2)		0.12				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg)		31				
Degree of cleanliness		CLASS 10[*4]				
Intake air (N l/min)		60[*5]				

*1   This is the value at a constant ambient temperature. (X,Y axes)
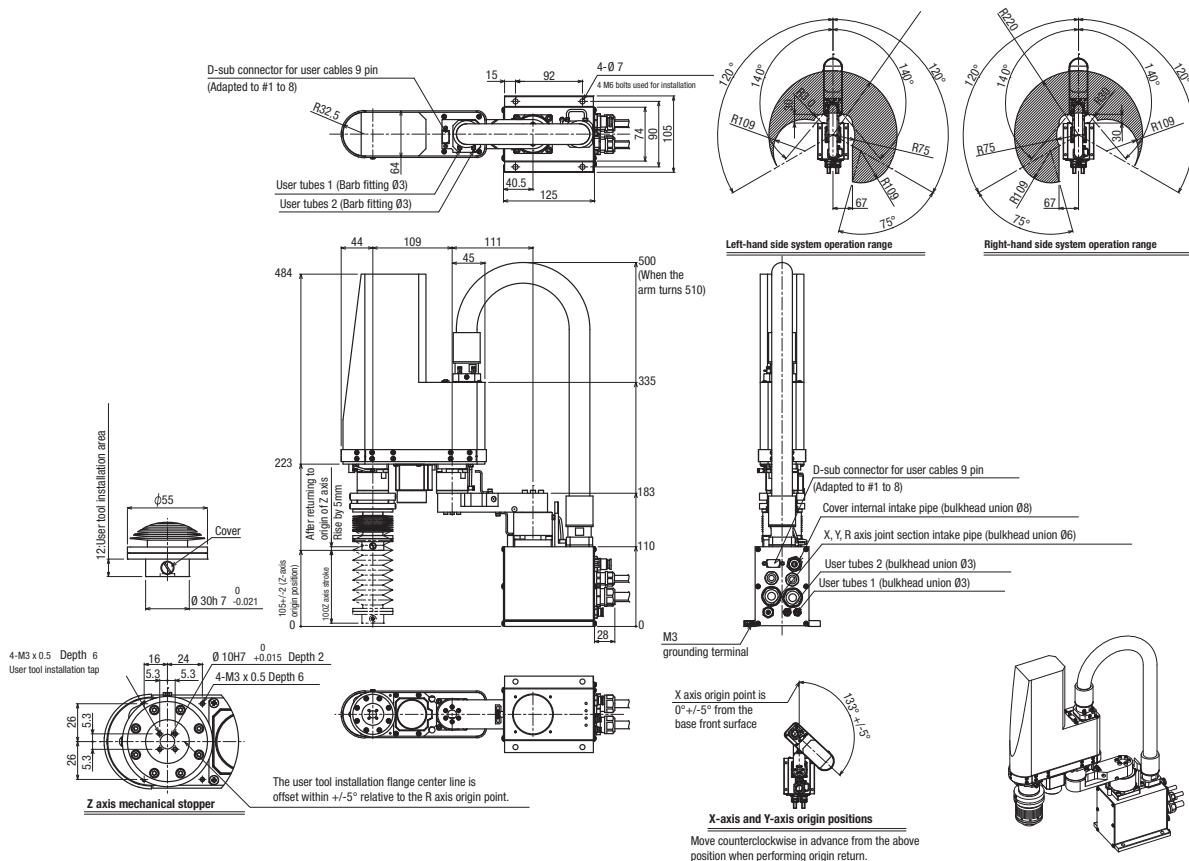*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Per 1 cf (0.1micron base), when suction blower is used.
*5   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope

X,Y axis mechanical stopper position

OMRON

R6YXC600 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		600				
Maximum payload (kg)		10				
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)	350	250	200	300	----
	Rotation range (º)	+/-120	+/-145	----		+/-360
AC servo motor output (W)		400	200	200		100
Maximum speed (XYZ:m/sec) (R:º/sec)		5.6		1.7		876
Standard cicle time: with 2kg payload[*2] (sec)		0.56				
R axis allowable moment inertia[*3] (kgm^2)		0.12				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg)		33				
Degree of cleanliness		CLASS 10[*4]				
Intake air (N l/min)		60[*5]				

*1 This is the value at a constant ambient temperature. (X,Y axes)
*2 When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3 There are limits to the setting of the acceleration coefficient.
*4 Per 1 cf (0.1micron base), when suction blower is used.
*5 The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	1500	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope

X,Y axis mechanical stopper position

R6YXC700 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		700				
Maximum payload (kg)		20				
Repeatability [1] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)	350	350	200	400	----
	Rotation range (º)	+/-120	+/-145	----		+/-360
AC servo motor output (W)		800	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)		6.7		1.7		600
Standard cicle time: with 2kg payload [2] (sec)		0.57				
R axis allowable moment inertia [3] (kgm^2)		0.32				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg)		57				
Degree of cleanliness		CLASS 10 [4]				
Intake air (N l/min)		60 [5]				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Per 1 cf (0.1micron base), when suction blower is used.
*5   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope

X,Y axis mechanical stopper position

OMRON

R6YXC800 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		800				
Maximum payload (kg)		20				
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)	450	350	200	400	----
	Rotation range (º)	+/-120	+/-145	----		+/-360
AC servo motor output (W)		800	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)		7.3		1.7		600
Standard cicle time: with 2kg payload[*2] (sec)		0.57				
R axis allowable moment inertia[*3] (kgm^2)		0.32				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg)		58				
Degree of cleanliness		CLASS 10[*4]				
Intake air (N l/min)		60[*5]				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Per 1 cf (0.1micron base), when suction blower is used.
*5   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

Working envelope

X,Y axis mechanical stopper position

OMRON

R6YXC1000 XC SERIES - CLEAN TYPE

Specifications

		X axis	Y axis	Z axis		R axis
Reach (mm)		1000				
Maximum payload (kg)		20				
Repeatability[*1] (XYZ:mm) (R:º)		+/-0.02		+/-0.01		+/-0.005
Axis specifications	Arm length (mm)	550	450	200	400	----
	Rotation range (º)	+/-120	+/-145	----		+/-360
AC servo motor output (W)		800	400	400		200
Maximum speed (XYZ:m/sec) (R:º/sec)		8		1.7		600
Standard cicle time: with 2kg payload[*2] (sec)		0.6				
R axis allowable moment inertia[*3] (kgm²)		0.32				
User wiring (sq x pcs)		0.2 x 20				
User tubing (Outer diameter)		Ø6 x 3				
Movement limit setting		1.Soft limit 2.Mechanical stopper (X, Y, Z axis)				
Robot cable length (m)		3.5, 5, 10				
Min. cable bending radius		R27				
Weight (kg)		59				
Degree of cleanliness		CLASS 10[*4]				
Intake air (N l/min)		60[*5]				

*1   This is the value at a constant ambient temperature. (X,Y axes)
*2   When moving 25mm in vertical direction and 300mm in horizontal direction reciprocally.
*3   There are limits to the setting of the acceleration coefficient.
*4   Per 1 cf (0.1micron base), when suction blower is used.
*5   The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller	Power consumption (VA)	Operating method
YRCX	2000	Programming / I/O point trace / Remote command / Operation using RS-232C or Ethernet communications

Dimensions

OMRON

SCARA Robots

Ordering information

SCARA Robots

XE series - Standard type

Robot				Robot controller	Arm 1/2 Return-to-origin	Robot + controller item code	Accessories			
Series	Reach (mm)	Z-axis stroke (mm)	Payload (kg)				Tool flange	Open shaft	Hollow cap	Brake release
R6Y XE	400	150	4	YRCX	Stroke end method	R6YXET400150YRCX	Not applicable	R6YACXGLS	Not applicable	R6YACXE BRAKEUNIT
					Sensor method	R6YXES400150YRCX	Not applicable	R6YACXGLS		
	510	200	10		Sensor method	R6YXE510200YRCX	R6YACXGLF	R6YACXGLS	R6YACXE HOLLOWCAP	
	610	200	10		Sensor method	R6YXE610200YRCX	R6YACXGLF	R6YACXGLS		
	710	200	10		Sensor method	R6YXE710200YRCX	R6YACXGLF	R6YACXGLS		

XG series - Standard type

Robot				Robot controller	Robot + controller item code	Accessories	
Series	Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y XG	120	50	1	YRCX	R6YXG12050YRCX	Not applicable	Not applicable
	150	50	1		R6YXG15050YRCX	Not applicable	Not applicable
	180	50	1		R6YXG18050YRCX	Not applicable	Not applicable
	220	100	1		R6YXG220100YRCX	Not applicable	Not applicable
XGL	250	150	5		R6YXGL250150YRCX	R6YACXGLF	R6YACXGLS
	350	150	5		R6YXGL350150YRCX	R6YACXGLF	R6YACXGLS
	400	150	5		R6YXGL400150YRCX	R6YACXGLF	R6YACXGLS
	500	150	5		R6YXGL500150YRCX	R6YACXGLF	R6YACXGLS
XG	500	200	10		R6YXG500200YRCX	R6YACXGLF	Not applicable
		300			R6YXG500300YRCX		
XGL	600	150	5		R6YXGL600150YRCX	R6YACXGLF	R6YACXGLS
XG	600	200	10		R6YXG600200YRCX	R6YACXGLF	Not applicable
		300			R6YXG600300YRCX		
XGH	600	200	20		R6YXGH600200YRCX	R6YACXGLF	Not applicable
		400			R6YXGH600400YRCX		
XGL	700	200	10		R6YXGL700200YRCX	R6YACXGLF	Not applicable
		300			R6YXGL700300YRCX		
XG	700	200	20		R6YXG700200YRCX	R6YACXGLF	Not applicable
		400			R6YXG700400YRCX		
	800	200	20		R6YXG800200YRCX	R6YACXGLF	Not applicable
		400			R6YXG800400YRCX		
	900	200	20		R6YXG900200YRCX	R6YACXGLF	Not applicable
		400			R6YXG900400YRCX		
	1000	200	20		R6YXG1000200YRCX	R6YACXGLF	Not applicable
		400			R6YXG1000400YRCX		

XG series - Wall-mount type

Robot				Robot controller	Robot + controller item code	Accessories	
Series	Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y XGSW	300	150	5	YRCX	R6YXGSW300150YRCX	R6YACXGLF	R6YACXGLS
	400	150	5		R6YXGSW400150YRCX	R6YACXGLF	R6YACXGLS
	500	200	10		R6YXGSW500200YRCX	R6YACXGLF	Not applicable
		300			R6YXGSW500300YRCX		
	600	200	10		R6YXGSW600200YRCX	R6YACXGLF	Not applicable
		300			R6YXGSW600300YRCX		
	700	200	20		R6YXGSW700200YRCX	R6YACXGLF	Not applicable
		400			R6YXGSW700400YRCX		
	800	200	20		R6YXGSW800200YRCX	R6YACXGLF	Not applicable
		400			R6YXGSW800400YRCX		
	900	200	20		R6YXGSW900200YRCX	R6YACXGLF	Not applicable
		400			R6YXGSW900400YRCX		
	1000	200	20		R6YXGSW1000200YRCX	R6YACXGLF	Not applicable
		400			R6YXGSW1000400YRCX		

XG series - Wall-mount inverse type

Robot					Robot controller	Robot + controller item code	Accessories	
Series		Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y	XGSU	300	150	5	YRCX	R6YXGSU300150YRCX	R6YACXGLF	R6YACXGLS
		400	150	5		R6YXGSU400150YRCX	R6YACXGLF	R6YACXGLS
		500	200	10		R6YXGSU500200YRCX	R6YACXGLF	Not applicable
			300			R6YXGSU500300YRCX		
		600	200	10		R6YXGSU600200YRCX	R6YACXGLF	Not applicable
			300			R6YXGSU600300YRCX		
		700	200	20		R6YXGSU700200YRCX	R6YACXGLF	Not applicable
			400			R6YXGSU700400YRCX		
		800	200	20		R6YXGSU800200YRCX	R6YACXGLF	Not applicable
			400			R6YXGSU800400YRCX		
		900	200	20		R6YXGSU900200YRCX	R6YACXGLF	Not applicable
			400			R6YXGSU900400YRCX		
		1000	200	20		R6YXGSU1000200YRCX	R6YACXGLF	Not applicable
			400			R6YXGSU1000400YRCX		

XG series - Clean type

Robot					Robot controller	Robot + controller item code	Accessories	
Series		Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y	XGLC	250	150	4	YRCX	R6YXGLC250150YRCX	R6YACXGLF	R6YACXGLS
		350	150	4		R6YXGLC350150YRCX	R6YACXGLF	R6YACXGLS
		400	150	4		R6YXGLC400150YRCX	R6YACXGLF	R6YACXGLS
		500	150	4		R6YXGLC500150YRCX	R6YACXGLF	R6YACXGLS
		600	150	4		R6YXGLC600150YRCX	R6YACXGLF	R6YACXGLS

XG series - Dust-proof & drip-proof type

Robot					Robot controller	Robot + controller item code	Accessories	
Series		Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y	XGLP	250	150	4	YRCX	R6YXGLP250150YRCX	R6YACXGLF	R6YACXGLS
		350	150	4		R6YXGLP350150YRCX	R6YACXGLF	R6YACXGLS
		400	150	4		R6YXGLP400150YRCX	R6YACXGLF	R6YACXGLS
		500	150	4		R6YXGLP500150YRCX	R6YACXGLF	R6YACXGLS
	XGP	500	200	8		R6YXGP500200YRCX	Equipped by default	Equipped by default
			300			R6YXGP500300YRCX		
	XGLP	600	150	4		R6YXGLP600150YRCX	R6YACXGLF	R6YACXGLS
	XGP	600	200	8		R6YXGP600200YRCX	Equipped by default	Equipped by default
			300			R6YXGP600300YRCX		
	XGHP	600	200	18		R6YXGHP600200YRCX	Equipped by default	Equipped by default
			400			R6YXGHP600400YRCX		
	XGP	700	200	18		R6YXGP700200YRCX	Equipped by default	Equipped by default
			400			R6YXGP700400YRCX		
		800	200	18		R6YXGP800200YRCX	Equipped by default	Equipped by default
			400			R6YXGP800400YRCX		
		900	200	18		R6YXGP900200YRCX	Equipped by default	Equipped by default
			400			R6YXGP900400YRCX		
		1000	200	18		R6YXGP1000200YRCX	Equipped by default	Equipped by default
			400			R6YXGP1000400YRCX		

X series - High payload type

Robot					Robot controller	Robot + controller item code	Accessories	
Series		Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y	XX	1200	400	50	YRCX	R6YXX1200400YRCX	R6YACXGLF	Not applicable

XC series - Clean type

Robot					Robot controller	Robot + controller item code	Accessories	
Series		Reach (mm)	Z-axis stroke (mm)	Payload (kg)			Tool flange	Open shaft
R6Y	XC	180	100	1	YRCX	R6YXC180100YRCX	Not applicable	Not applicable
		220	100	1		R6YXC220100YRCX	Not applicable	Not applicable
		500	200	10		R6YXC500200YRCX	Not applicable	Not applicable
			300			R6YXC500300YRCX		
		600	200	10		R6YXC600200YRCX	Not applicable	Not applicable
			300			R6YXC600300YRCX		
		700	200	20		R6YXC700200YRCX	Not applicable	Not applicable
			400			R6YXC700400YRCX		
		800	200	20		R6YXC800200YRCX	Not applicable	Not applicable
			400			R6YXC800400YRCX		
		1000	200	20		R6YXC1000200YRCX	Not applicable	Not applicable
			400			R6YXC1000400YRCX		

SCARA robot cables

SCARA robot series	Applicable robots	Robot cable		
		Length (m)	Item code	Detachable
XG series - Standard type	R6YXG120/150/180	2.0	R6YACCX002T1	Not applicable
		3.5	R6YACCX003T1	Not applicable
		5.0	R6YACCX005T1	Not applicable
		10.0	R6YACCX010T1	Not applicable
XG series - Standard type	R6YXG220	3.5	R6YACCX003T2	●
		5.0	R6YACCX005T2	●
		10.0	R6YACCX010T2	●
XE series - Standard type XG series - Standard type X series - High payload type	R6YXE400/510/610/710 R6YXGL250/350/400/500/600 R6YXG500/600/700/800/900/1000 R6YXGH600 R6YXX1200	3.5	R6YACCX003XGX	●
		5.0	R6YACCX005XGX	●
		10.0	R6YACCX010XGX	●
XG series - Standard type XG series - Wall mount type XG series - Wall-mount inverse type	R6YXGL700 R6YXGSW300/400/500/600/700/800/900/1000 R6YXGSU300/400/500/600/700/800/900/1000	3.5	R6YACCX003XGS	Not applicable
		5.0	R6YACCX005XGS	Not applicable
		10.0	R6YACCX010XGS	Not applicable
XG series - Clean type XG series - Dust-proof & dip-proof type	R6YXGLC250/350/400/500/600 R6YXGLP250/350/400/500/600 R6YXGP500/600/700/800/900/1000 R6YXGHP600	3.5	R6YACCX003XGCXGP	●
		5.0	R6YACCX005XGCXGP	●
		10.0	R6YACCX010XGCXGP	●
XC series - Clean type	R6YXC180/220/500/600/700/800/1000	3.5	R6YACCX003XSXC	Not applicable
		5.0	R6YACCX005XSXC	Not applicable
		10.0	R6YACCX010XSXC	Not applicable

YRCX Robot Controller options

Type	Specifications		Model
Optional input/output	8 dedicated input, 9 dedicated output 16 general purpose input, 16 general purpose output	NPN	R6YACSD241X[1]
		PNP	R6YACSD242X[1][2]
	24 general purpose input, 16 general purpose output	NPN	R6YACMD241X
		PNP	R6YACMD242X
Communications[3]	EtherNet/IP		R6YACEIP01X
	DeviceNet slave		R6YACDRT01X
	PROFIBUS slave		R6YACPRT01X
	PROFINET slave		R6YACPNT01X
	YC-Link/E master		R6YACYCM01X[4]
	YC-Link/E slave		R6YACYCS01X[4]
Conveyor tracking	Tracking board		R6YACTR01X[5]
	Encoder cable for tracking	10 m	R6YACCR005
Programming box	PBEX	5 m	R6YACPB005EX
		12 m	R6YACPB012EX
Communications cable	Communications cable 9-9 pin	5 m	R6YACCC005
	USB communications cable	5 m	R6YACUSB005
Drive boards	X axis	Max. current: 5 A	R6YACDBX05X
		Max. current: 10 A	R6YACDBX10X
		Max. current: 20 A	R6YACDBX20X
	Y axis	Max. current: 5 A	R6YACDBY05X
		Max. current: 10 A	R6YACDBY10X
		Max. current: 20 A	R6YACDBY20X

*1 Only one option board can be selected. This board should be inserted on slot 1.
*2 Provided by default with the YRCX Robot Controller.
*3 Be careful not to mix field networks (EtherNet/IP, DeviceNet, PROFIBUS, PROFINET).
*4 Select only one master or slave board for YC-Link/E.
*5 Only one tracking board can be selected.

Software

Specifications		Model
SCARA-YRCX Studio	Software	Please download it from following URL: https://industrial.omron.eu/en/products/x-series#downloads
	License dongle	R6YACSSC1X[1]

*1 One license per computer.

ALL DIMENSIONS SHOWN ARE IN MILLIMETERS.

To convert millimeters into inches, multiply by 0.03937. To convert grams into ounces, multiply by 0.03527.