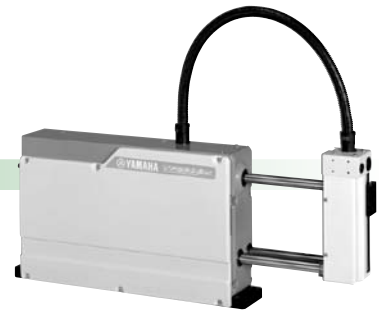


YP220BX 2 axes



Ordering method

YP220BX		RCX222			
Model	Cable length	Controller	Usable for CE	Inputs/Outputs selection 1	Inputs/Outputs selection 2
	3L: 3.5m 5L: 5m 10L: 10m	RCX222	No entry: Standard E: CE marking	N: NPN ^{Note 2} P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS EN: Ethernet YC: YC-Link ^{Note 1}	No entry: None N1: OP.DIO24/16 (NPN) ^{Note 2} P1: OP.DIO24/17 (PNP) EN: Ethernet ^{Note 3}

Note 1. Available only for the master.
 Note 2. NPN cannot be selected if using CE marking.
 Note 3. Only when you have selected CC, DN or PB for Input/Output selection 1, you can select EN for Input/Output selection 2.

Specifications

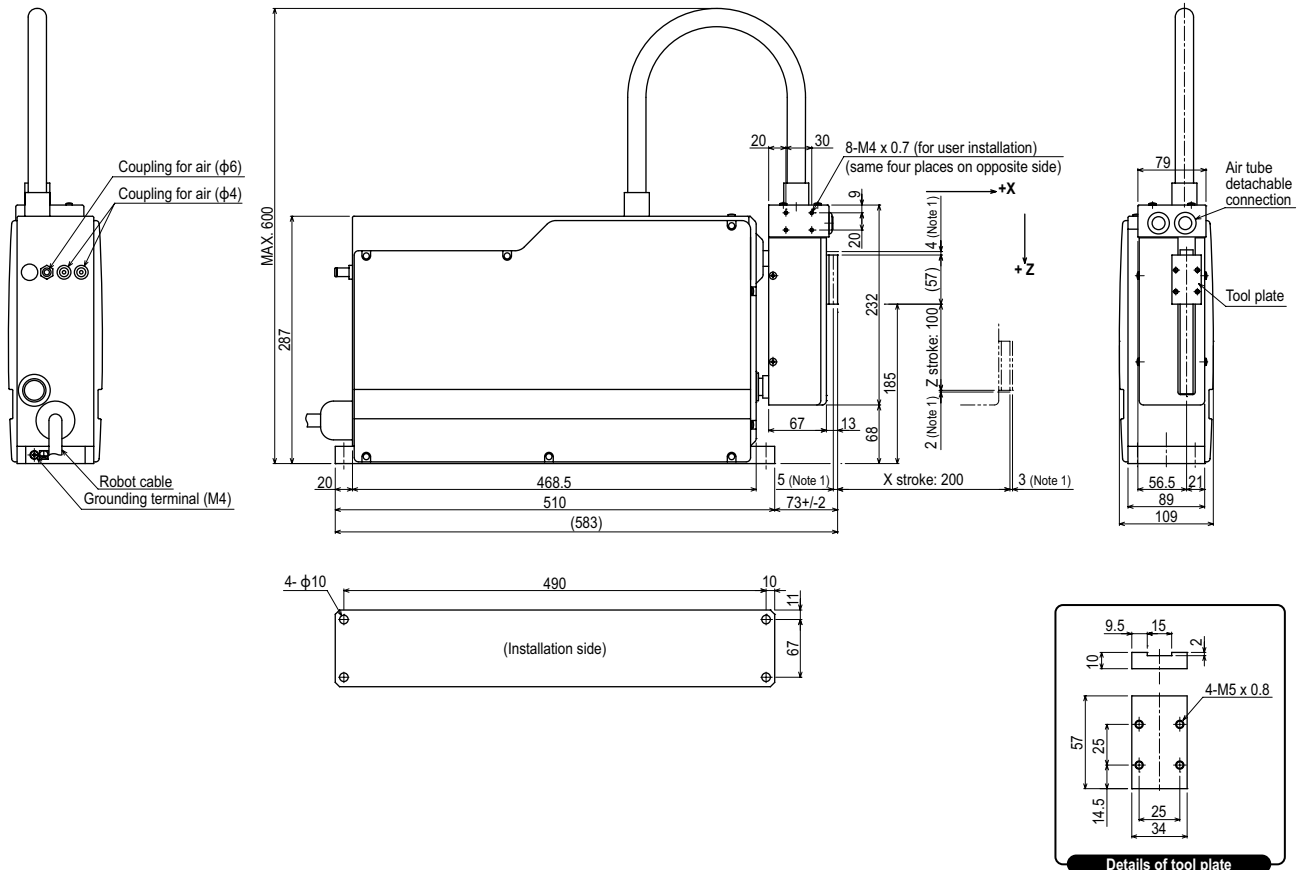
	X axis	Z axis
AC servo motor output (W)	200	200
Repeatability ^{Note 1} (mm)	+/-0.05	+/-0.05
Drive system	Timing belt	Timing belt
Deceleration ratio (mm)	Equivalent to lead 24	Equivalent to lead 20
Maximum speed ^{Note 2} (mm/sec)	1440	1200
Moving range (mm)	200	100
Cycle time (sec)	0.45 ^{Note 3}	
Maximum payload (kg)	3	
Robot cable length (m)	Standard: 3.5 Option: 5,10	
Weight (kg)	17	

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX222	500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

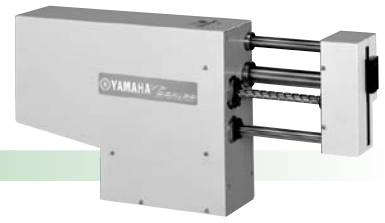
YP220BX



Note 1. Distance to mechanical stopper.
 Note 2. Return-to-origin on the YP220BX is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.

- APPLICATION
- Linear conveyor modules
- LCM100
- TRANSEURO
- Compact single-axis robots
- FLIP-X
- Single-axis robots
- PHASER
- Linear motor single-axis robots
- XY-X
- Cartesian robots
- YK-X
- SCARA robots
- YP-X
- Pick & place robots
- CLEAN
- CONTROLLER INFORMATION
- 2-axes
- 3-axes
- 4-axes

YP320X 2 axes



Ordering method

YP320X		RCX222			
Model	Cable length	Controller	Usable for CE	Inputs/Outputs selection 1	Inputs/Outputs selection 2
	3L: 3.5m 5L: 5m 10L: 10m	RCX222	No entry: Standard E: CE marking	N: NPN ^{Note 2} P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS EN: Ethernet YC: YC-Link ^{Note 1}	No entry: None N1: OP.DIO24/16 (NPN) ^{Note 2} P1: OP.DIO24/17 (PNP) EN: Ethernet ^{Note 3}

Note1. Available only for the master.
 Note2. NPN cannot be selected if using CE marking.
 Note3. Only when you have selected CC, DN or PB for Input/Output selection 1, you can select EN for Input/Output selection 2.

Specifications

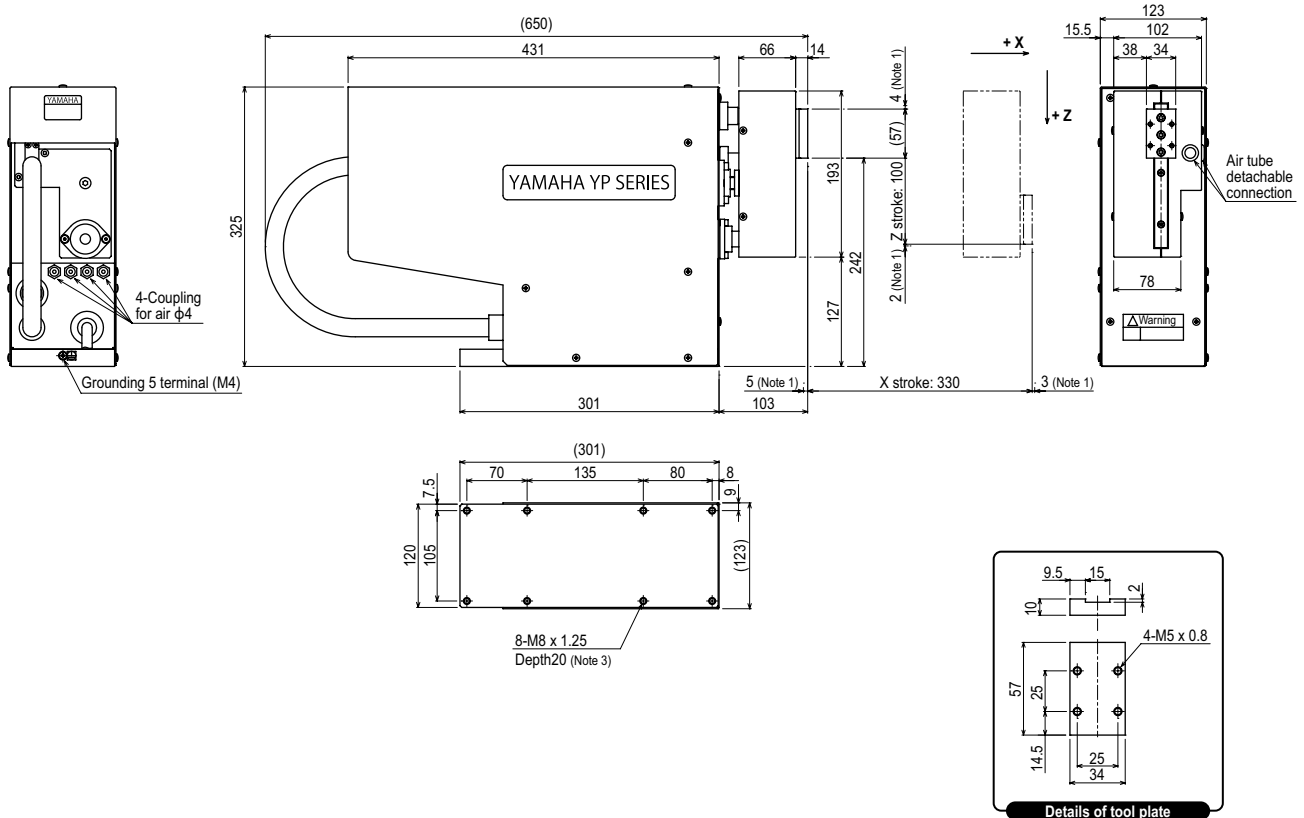
	X axis	Z axis
AC servo motor output (W)	200	200
Repeatability^{Note 1} (mm)	+/-0.02	+/-0.05
Drive system	Ball screw (C7 class)	Timing belt
Deceleration ratio (mm)	Equivalent to lead 20	Equivalent to lead 25
Maximum speed^{Note 2} (mm/sec)	1500	1500
Moving range (mm)	330	100
Cycle time (sec)	0.57 ^{Note 3} , 0.78 ^{Note 4}	
Maximum payload (kg)	3	
Robot cable length (m)	Standard: 3.5 Option: 5,10	
Weight (kg)	21	

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).
 Note 4. Reciprocating time in vertical direction (25mm) and longitudinal direction (300mm) with the arch amount of 25 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX222	500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YP320X



Note 1. Distance to mechanical stopper.
 Note 2. Return-to-origin on the YP320X is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.
 Note 3. Do not use bolts longer than 20mm (robot bottom plate thickness).

YP220BXR 3 axes



Ordering method

YP220BXR

Model	Cable length
	3L: 3.5m
	5L: 5m
	10L: 10m

RCX340-3

Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
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Specify various controller setting items. RCX340 ▶ **P.508**

RCX240S

Controller	CE Marking	Expansion I/O	Network option	iVY System	Gripper	Battery
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Specify various controller setting items. RCX240/RCX240S ▶ **P.495**

Specifications

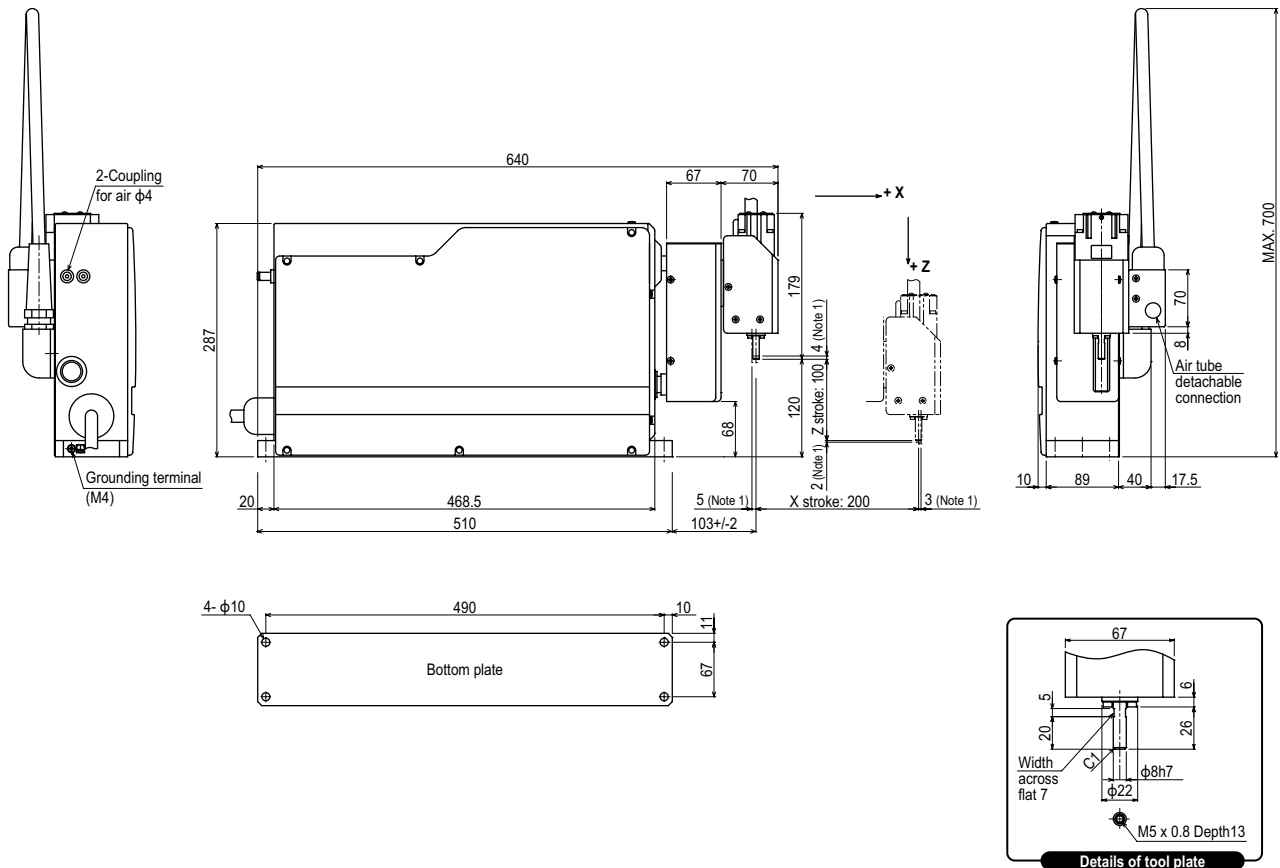
	X axis	Z axis	R axis
AC servo motor output (W)	200	200	60
Repeatability ^{Note 1} (mm)	+/-0.05	+/-0.05	+/-0.1
Drive system	Timing belt	Timing belt	Ball Reducer
Deceleration ratio (mm)	Equivalent to lead 24	Equivalent to lead 20	1/18
Maximum speed ^{Note 2} (XZ: mm/sec) (R: °/sec)	1440	1200	1000
Moving range (XZ: mm) (R: °)	200	100	+/-180
Cycle time (sec)	0.62 ^{Note 3}		
Maximum payload (kg)	1		
R-axis allowable moment inertia (kgm ² [kgfcm ²])	0.00098 [0.01]		
Robot cable length (m)	Standard: 3.5 Option: 5,10		
Weight (kg)	19		

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX340 RCX240S	700	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YP220BXR



Note1. Distance to mechanical stopper.
 Note2. Return-to-origin on the YP220BXR is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.

APPLICATION

Linear conveyor modules
LCM100

Compact single-axis robots
TRANSERVO

Single-axis robots
FLIP-X

Linear motor single-axis robots
PHASER

Cartesian robots
XX-X

SCARA robots
YK-X

Pick & place robots
YP-X

CLEAN

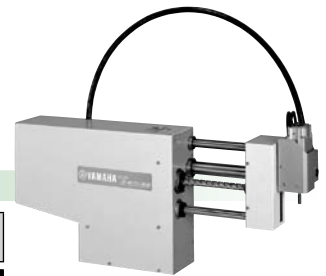
CONTROLLER INFORMATION

2-axes

3-axes

4-axes

YP320XR 3 axes



Ordering method

YP320XR **RCX340-3**

Model **Cable length** **Controller / Number of controllable axes** **Safety standard** **Option A (OP.A)** **Option B (OP.B)** **Option C (OP.C)** **Option D (OP.D)** **Option E (OP.E)** **Absolute battery**

3L: 3.5m
5L: 5m
10L: 10m

Specify various controller setting items. RCX340 ▶ P.508

RCX240S **BB**

Controller **CE Marking** **Expansion I/O** **Network option** **iVY System** **Gripper** **Battery**

Specify various controller setting items. RCX240/RCX240S ▶ P.495

Specifications

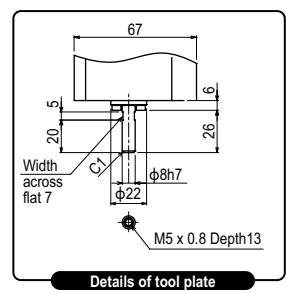
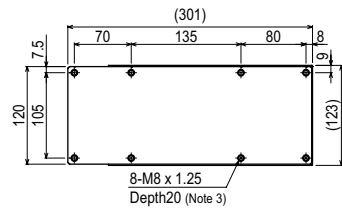
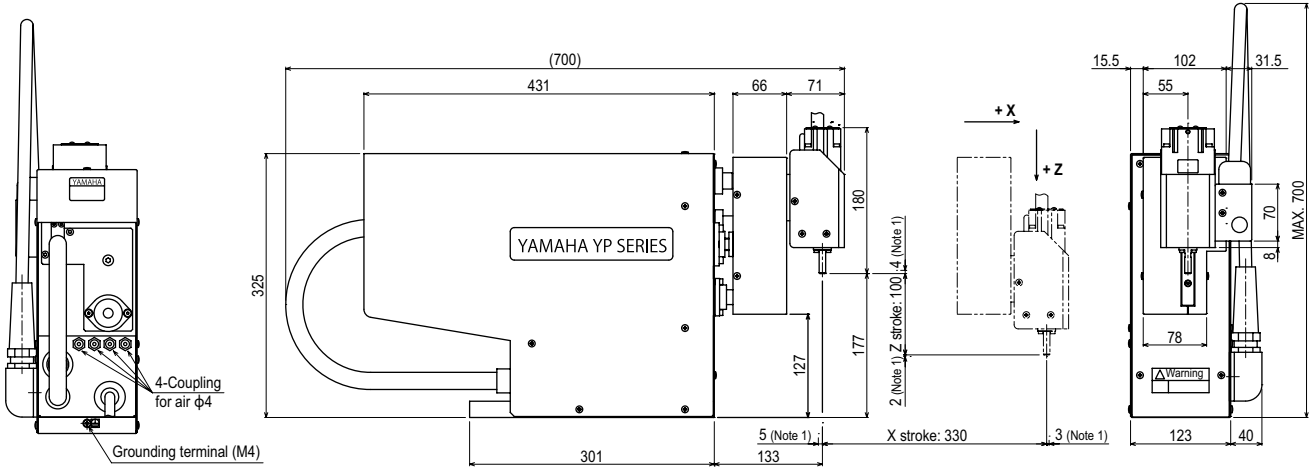
	X axis	Z axis	R axis
AC servo motor output (W)	200	200	60
Repeatability ^{Note 1} (XZ: mm) (R: °)	+/-0.02	+/-0.05	+/-0.1
Drive system	Ball screw (C7 class)	Timing belt	Ball Reducer
Deceleration ratio (mm)	Equivalent to lead 20	Equivalent to lead 25	1/18
Maximum speed ^{Note 2} (XZ: mm/sec) (R: °/sec)	1500	1500	1000
Moving range (XZ: mm) (R: °)	330	100	+/-180
Cycle time (sec)	0.67 ^{Note 3} , 0.87 ^{Note 4}		
Maximum payload (kg)	1		
R-axis allowable moment inertia (kgm ² [kgfcm ²])	0.00098 [0.01]		
Robot cable length (m)	Standard: 3.5 Option: 5,10		
Weight (kg)	23		

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).
 Note 4. Reciprocating time in vertical direction (25mm) and longitudinal direction (300mm) with the arch amount of 25 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX340 RCX240S	700	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YP320XR



Note1. Distance to mechanical stopper.
 Note2. Return-to-origin on the YP320XR is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.
 Note3. Do not use bolts longer than 20mm (robot bottom plate thickness).

YP330X 3 axes



Ordering method

YP330X

Model	Cable length
	3L: 3.5m
	5L: 5m
	10L: 10m

RCX340-3

Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
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Specify various controller setting items. RCX340 ▶ **P.508**

RCX240S

Controller	CE Marking	Expansion I/O	Network option	iVY System	Gripper	Battery
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Specify various controller setting items. RCX240/RCX240S ▶ **P.495**

Specifications

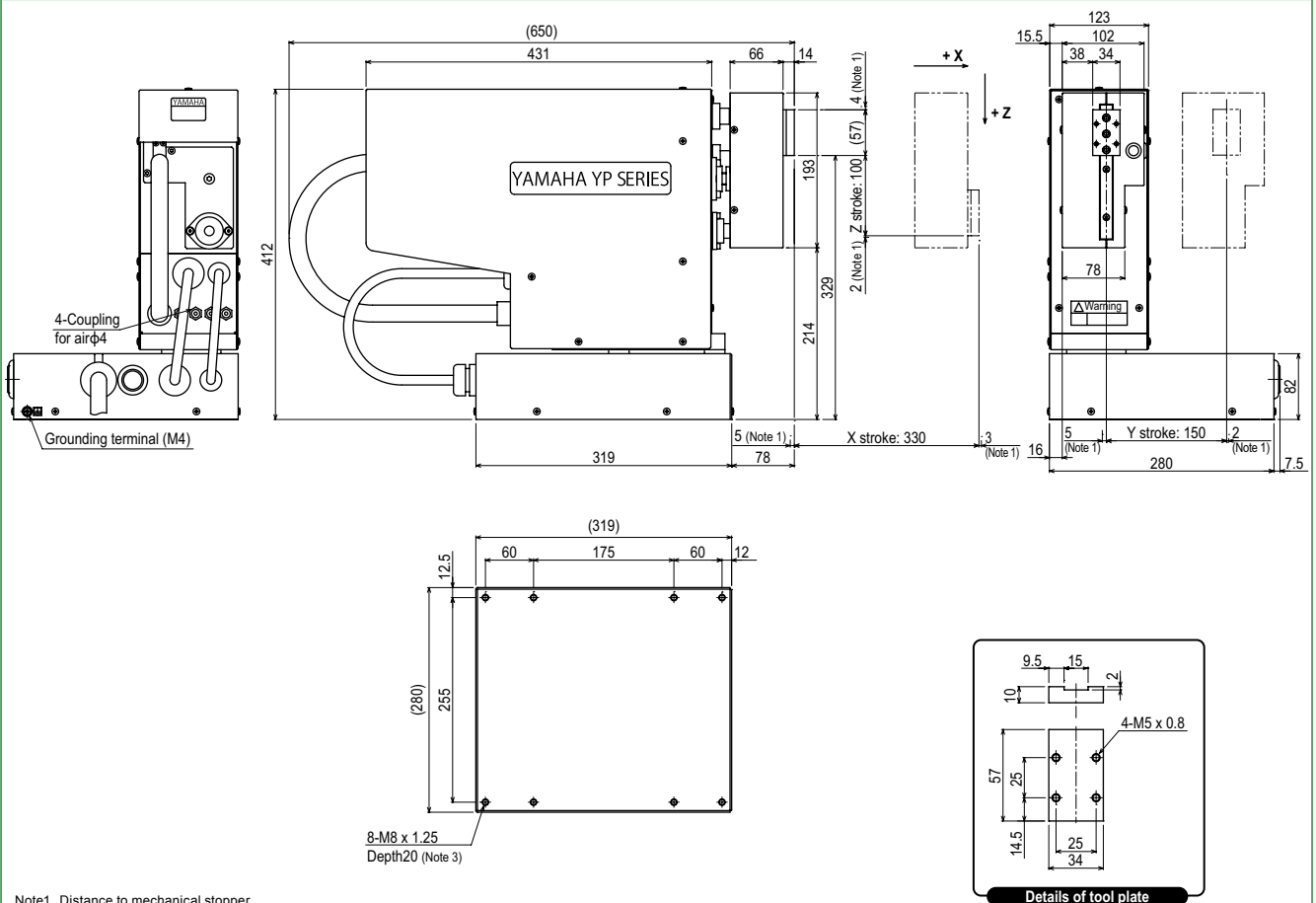
	X axis	Y axis	Z axis
AC servo motor output (W)	200	200	200
Repeatability ^{Note 1} (mm)	+/-0.02	+/-0.02	+/-0.05
Drive system	Ball screw (C7 class)	Ball screw (C7 class)	Timing belt
Deceleration ratio (mm)	Equivalent to lead 20	Equivalent to lead 20	Equivalent to lead 25
Maximum speed ^{Note 2} (mm/sec)	1500	1000	1500
Moving range (mm)	330	150	100
Cycle time (sec)	0.57 ^{Note 3} , 0.78 ^{Note 4}		
Maximum payload (kg)	3		
Robot cable length (m)	Standard: 3.5 Option: 5,10		
Weight (kg)	32		

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).
 Note 4. Reciprocating time in vertical direction (25mm) and longitudinal direction (300mm) with the arch amount of 25 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX340 RCX240S	700	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YP330X



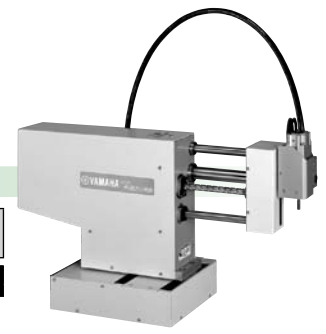
Note1. Distance to mechanical stopper.
 Note2. Return-to-origin on the YP330X is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.
 Note3. Do not use bolts longer than 20mm (robot bottom plate thickness).

Controller

RCX340 ▶ 508 RCX240S ▶ 495

APPLICATION
 Linear conveyor modules
 LCMT100
 TRANSEURO
 Compact single-axis robots
 FLIP-X
 Single-axis robots
 PHASER
 Linear motor single-axis robots
 XY-X
 Cartesian robots
 YK-X
 SCARA robots
 YP-X
 Pick & place robots
 CLEAN
 CONTROLLER INFORMATION
 2-axes
 3-axes
 4-axes

YP340X 4 axes



APPLICATION
Linear conveyor modules LCM100
Compact single-axis robots TRANSERVO
Single-axis robots FLIP-X
Linear motor single-axis robots PHASER
Cartesian robots XY-X
SCARA robots YK-X
Pick & place robots YP-X
CLEAN
CONTROLLER INFORMATION
2-axes
3-axes
4-axes

Ordering method

YP340X

Model

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

RCX340-4

Controller / Number of controllable axes

Safety standard

Option A (OP.A)

Option B (OP.B)

Option C (OP.C)

Option D (OP.D)

Option E (OP.E)

Absolute battery

Specify various controller setting items. RCX340 ▶ **P.508**

RCX240S

Controller

CE Marking

Expansion I/O

Network option

iVY System

Gripper

Battery

Specify various controller setting items. RCX240/RCX240S ▶ **P.495**

Specifications

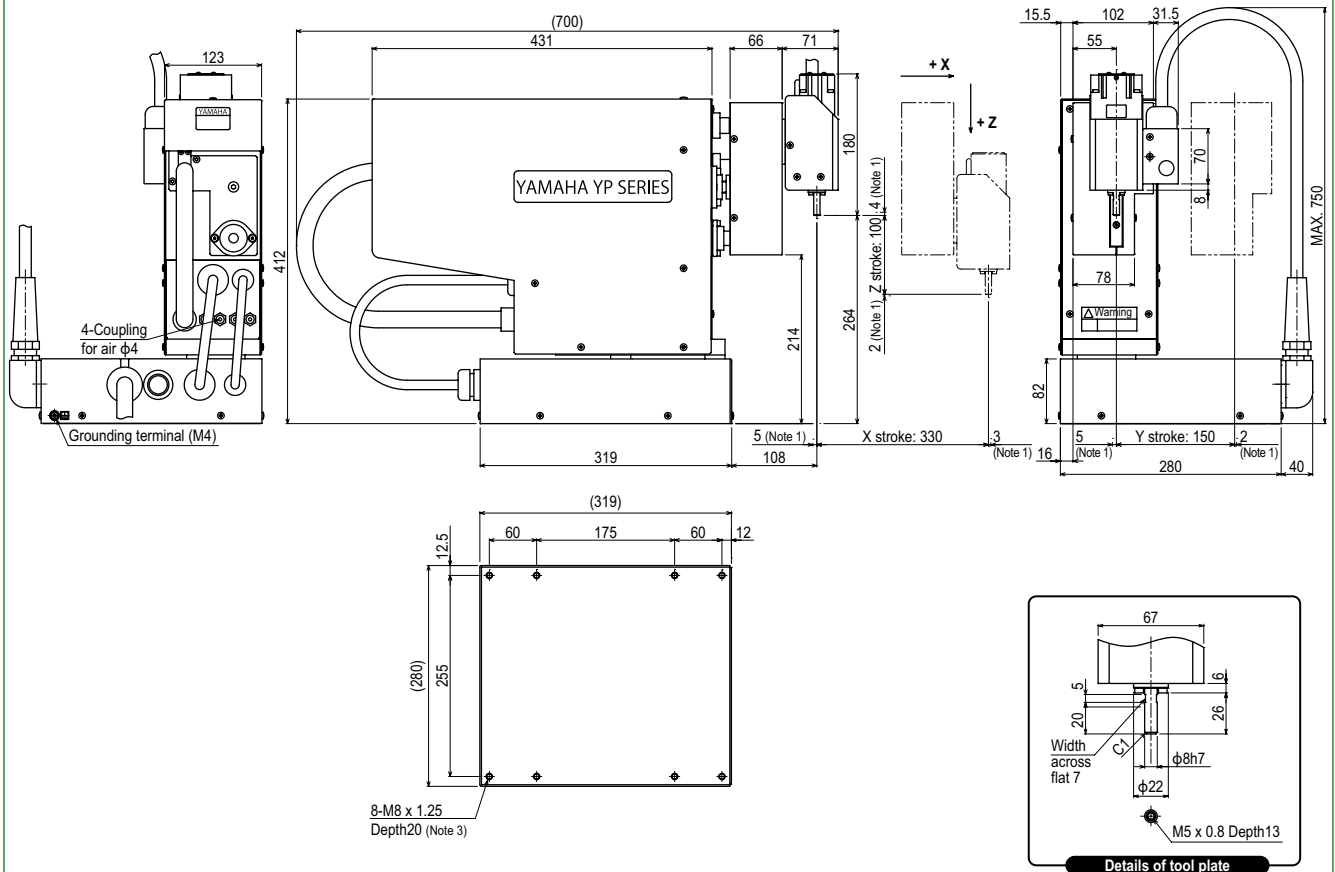
	X axis	Y axis	Z axis	R axis
AC servo motor output (W)	200	200	200	60
Repeatability ^{Note 1} (XYZ: mm)(R: °)	+/-0.02	+/-0.02	+/-0.05	+/-0.1
Drive system	Ball screw (C7 class)	Ball screw (C7 class)	Timing belt	Ball Reducer
Deceleration ratio (mm)	Equivalent to lead 20	Equivalent to lead 20	Equivalent to lead 25	1/18
Maximum speed ^{Note 2} (XYZ: mm/sec) (R: °/sec)	1500	1000	1500	1000
Moving range (XYZ: mm) (R: °)	330	150	100	+/-180
Cycle time (sec)	0.67 ^{Note 3} , 0.87 ^{Note 4}			
Maximum payload (kg)	1			
R-axis allowable moment inertia (kgm ² [kgfcm ²])	0.00098 [0.01]			
Robot cable length (m)	Standard: 3.5 Option: 5,10			
Weight (kg)	34			

Note 1. Positioning repeatability precision in a single swing when residual vibration is stabilized (variable depending on the load and stroke).
 Note 2. When the moving stroke is short, the maximum speed may not be reached.
 Note 3. Reciprocating time in vertical direction (50mm) and longitudinal direction (150mm) with the arch amount of 50 (when executing rough-positioning arch motion with 1kg load).
 Note 4. Reciprocating time in vertical direction (25mm) and longitudinal direction (300mm) with the arch amount of 25 (when executing rough-positioning arch motion with 1kg load).

Controller

Controller	Power consumption (VA)	Operating method
RCX340 RCX240S	800	Programming / I/O point trace / Remote command / Operation using RS-232C communication

YP340X



Note 1. Distance to mechanical stopper.
 Note 2. Return-to-origin on the YP340X is by absolute reset. So the origin position must be set the first time (making initial settings) but after that is not required.
 Note 3. Do not use bolts longer than 20mm (robot bottom plate thickness).