

**XYC4-D Series
Specifications**

Item		XYC4-D
Model name of robot set (Note 1)(Note 2)		XYC-40*a*b*cD-L(R)[L : Left arm type R : Right arm type]
Model name of robot unit		XYC-40*a*b*cDM-L(R)[L : Left arm type R : Right arm type]
X-axis stroke(*a)		(*a=) 2: 250mm, 3: 350mm, 4: 450mm, 5: 550mm
Y-axis stroke(*b)		(*b=) 3: 300mm, 4: 400mm, 5: 500mm, 6: 600mm, 7: 700mm, 9: 900mm
Vertical stroke(*c)		(*c=) 2: 200mm, 3: 300mm
Wrist rotation angle		±270°
Axis combination		X(1st axis) + Y(2nd axis) + Z(3rd axis) + T(4th axis)
Maximum payload		10kg
Composite speed		X(1st axis), Y(2nd axis) : 1000mm/s Z(3rd axis) : 2000mm/s T(4th axis) : 610°/s
Position repeatability(Note 2)		X(1st axis), Y(2nd axis), Z(3rd axis) : ±0.025mm T(4th axis) : ±0.02°
Maximum force-fit		98N(one second or less)
Maximum allowable inertia moment around T-axis		0.078 kgm ²
Position detection		Simplified absolute encoder
Drive motor		AC servomotors for all joints, + Air balance cylinder + Brake for 3rd axis
Air source(for gravity balancing)	Operating pressure	0.05 to 0.35MPa
	Maximum allowable pressure	0.59MPa
Weight		approx. 66kg (XYC-40593DM-L(R), the heaviest model)

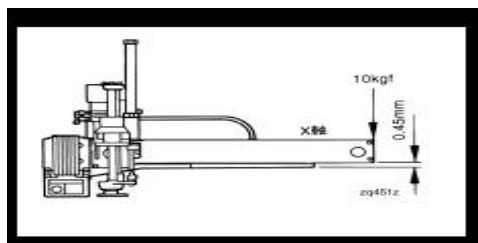
Note 1 : The model name of robot set refers to the model name of a complete set including a robot unit, controller.

Note 2 : Position repeatability is the value at constant ambient temperature.

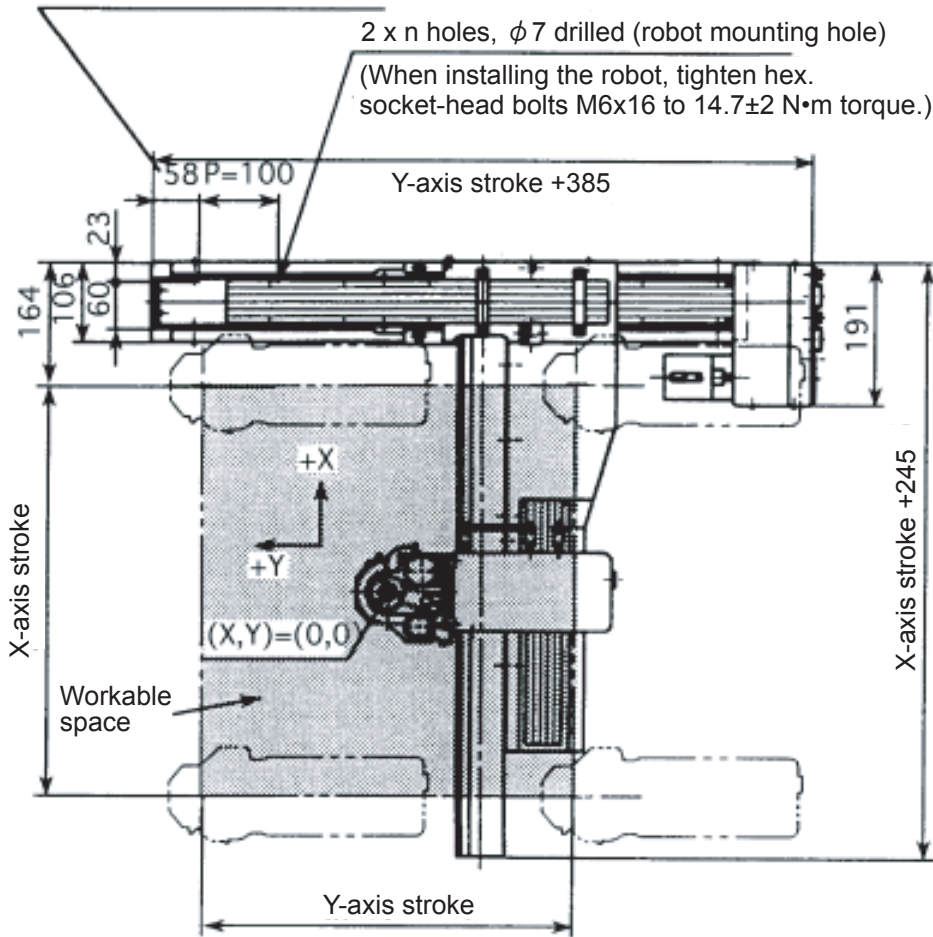
<Rigidity of the X-axis>

The X-axis is cantilever-structured, so its rigidity is lower than that of other axes.

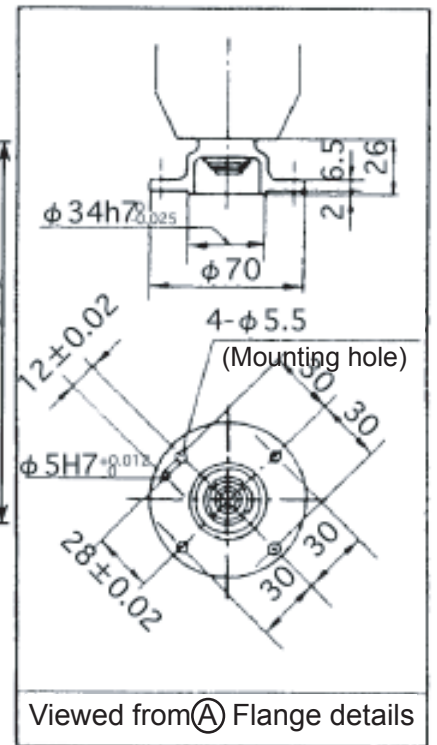
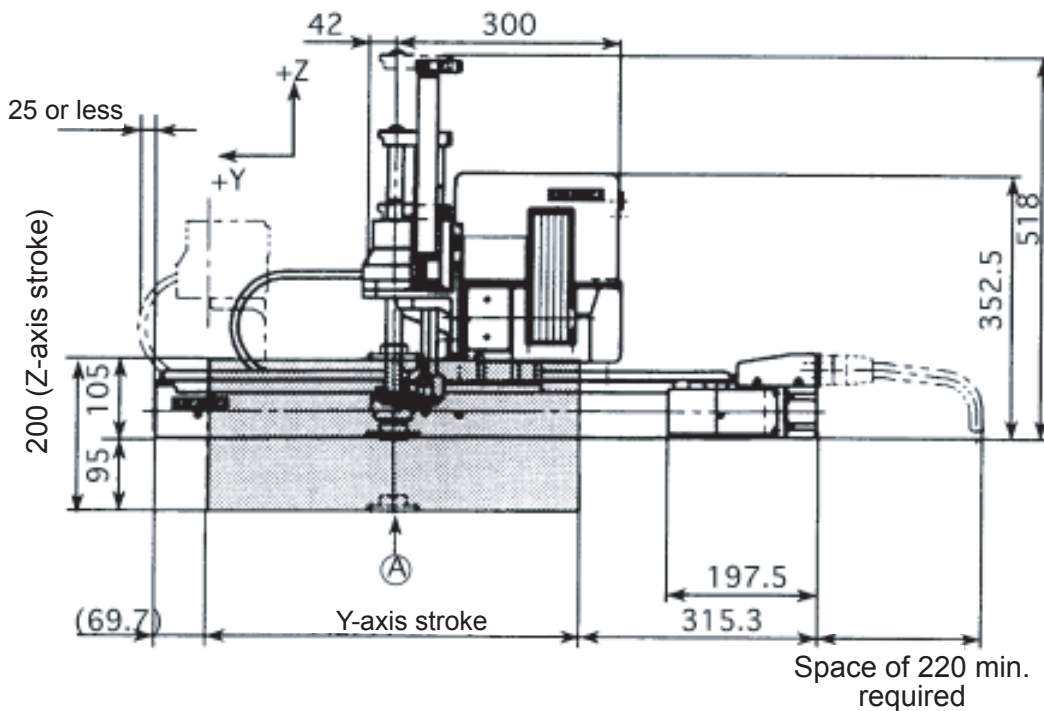
In the case of the XYC-40592DM-L), the deflection at the end of the X-axis frame is 0.45 mm a load of 10 kg is applied.



108 when Y-axis stroke is 900



Y-axis stroke (mm)	n ↕
300↕	6↕
400↕	7↕
500↕	8↕
600↕	9↕
700↕	10↕
900↕	11↕



Note: The origin (X, Y, Z, T = 0, 0, 0, 0) is at the center of the X- and Y-axis strokes, at the underside of the mounting base, and at the center of the robot flange shown in "Flange details" figure.