

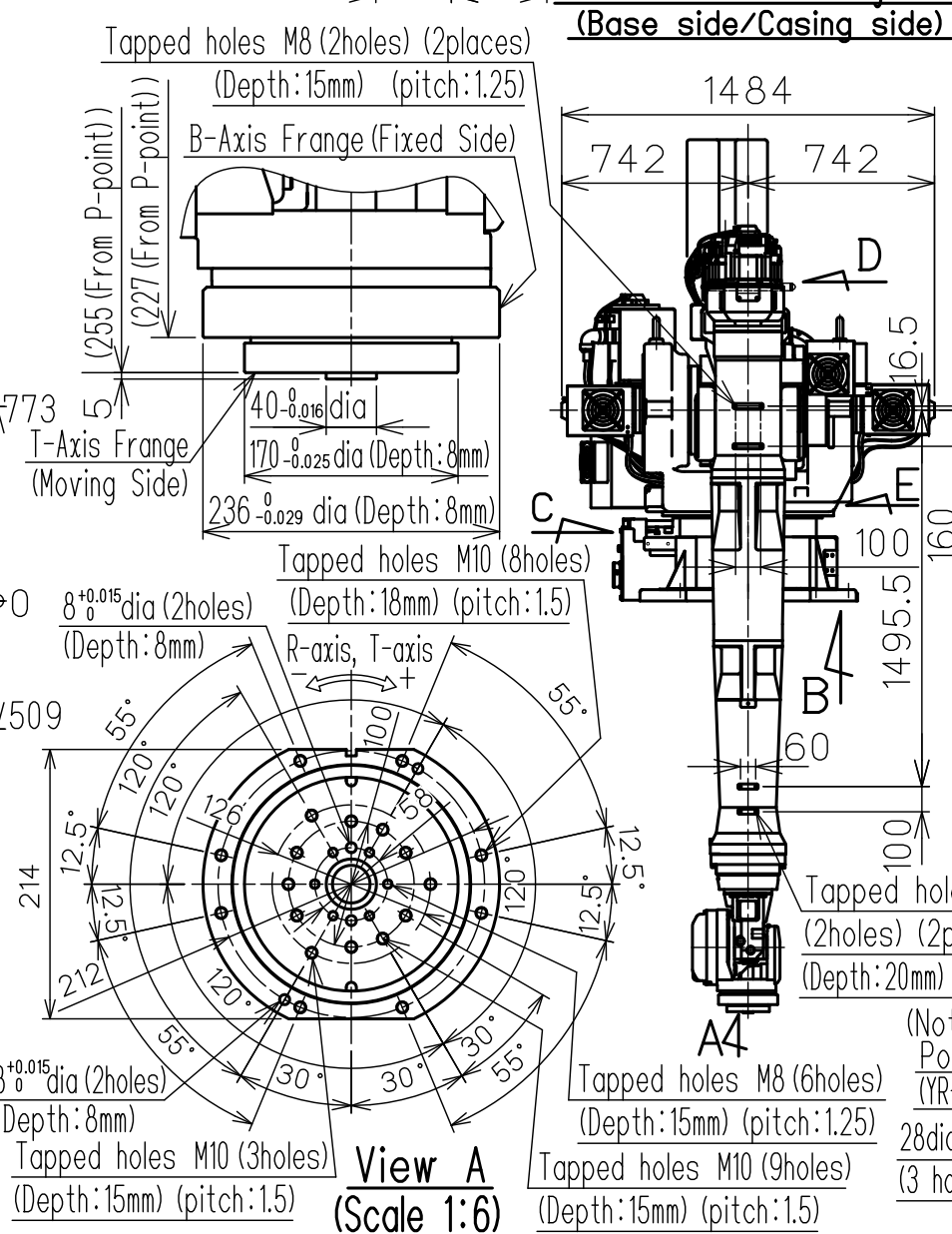
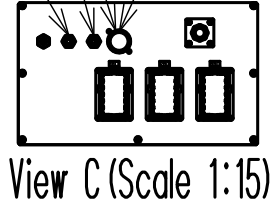
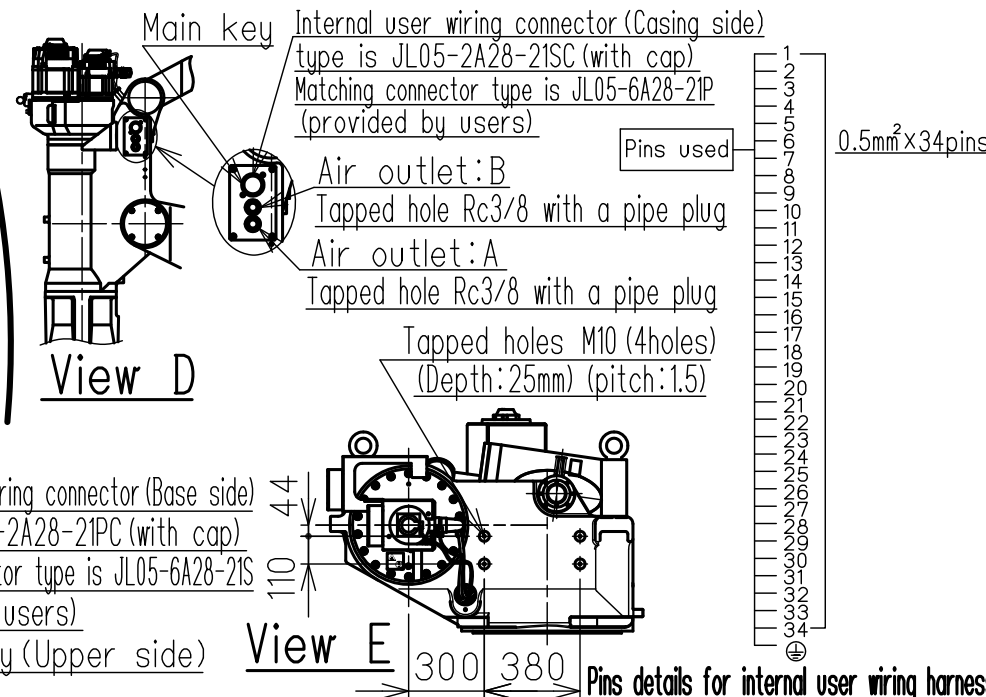
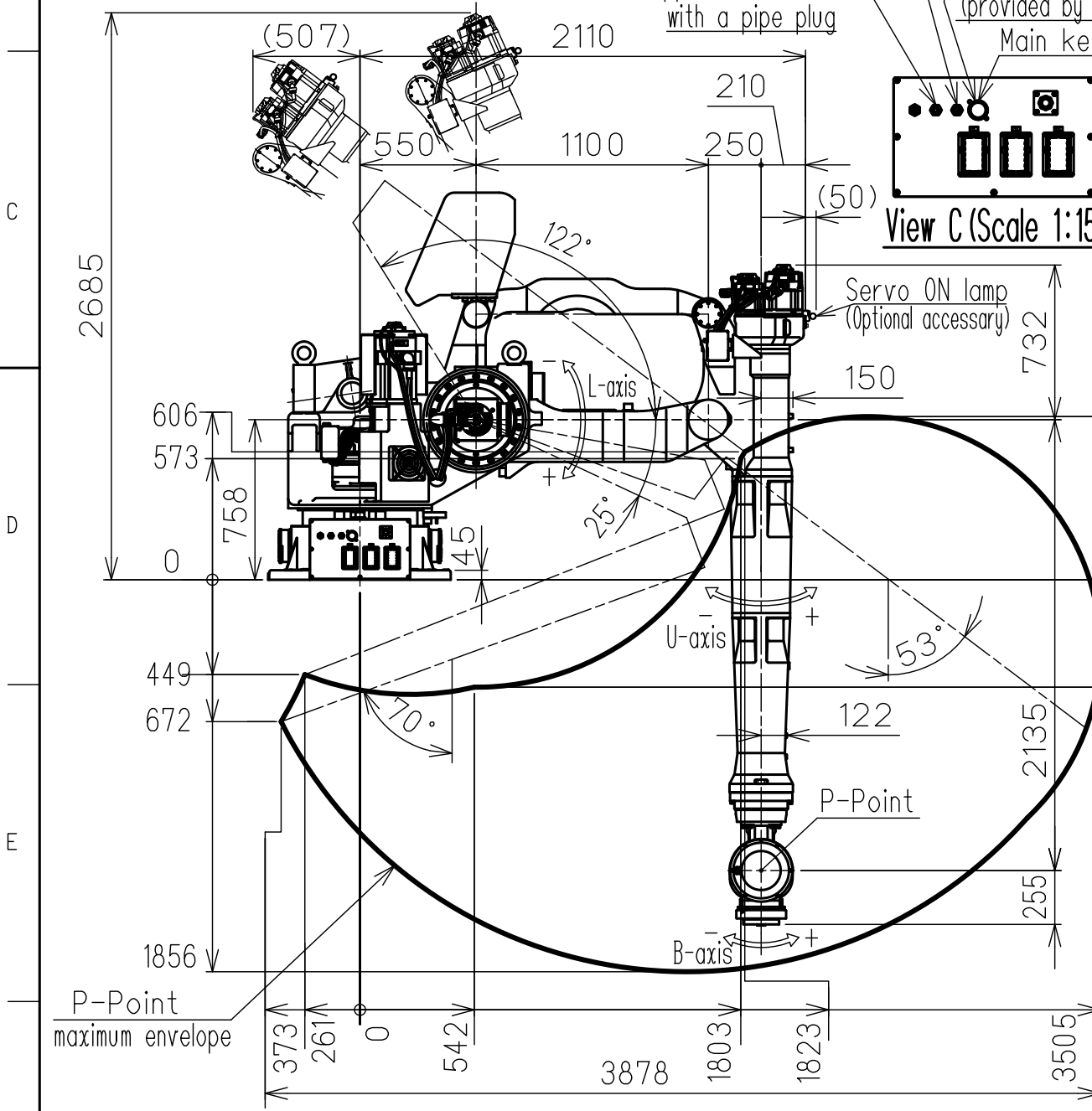
DWG.NO. HW1385440

Type	Note
YR-1-06VRF200-*00	Standard Specification
YR-1-06VRF200-*10	Parallel Link Hand Specification(※8)

(Note6)  
Power Cables  
(YR-1-06VRF200-L\*\*)

(Note6)  
Power Cables  
(YR-1-06VRF200-K\*\*)

(Note6)  
Power Cables  
(YR-1-06VRF200-J\*\*)



Item	Model	MOTOMAN-PH200RF
Type	YR-1-06VRF200-*00	YR-1-06VRF200-*10
Configuration	Vertically articulated	
Degree of Freedom	6	
Payload	Wrist	200kg
	On U-arm	100kg(※3)
Repeatability (※1)	0.5 mm	
Range of Motion	S-Axis (Turning)	-150° - +150°
	L-Axis (Lower Arm)	-122° - +25°
	U-Axis (Upper Arm)	-70° - +53°
	R-Axis (Roll)	-360° - +360°
	B-Axis (Pitch/Yaw)	-120° - +120° -120° - +85°
	T-Axis (Twist)	-360° - +360° -70° - +70°
Max Speed	S-Axis	1.57rad/s, 90°/s
	L-Axis	1.57rad/s, 90°/s
	U-Axis	1.57rad/s, 90°/s
	R-Axis	1.40rad/s, 80°/s 0.62rad/s, 35.5°/s
	B-Axis	1.40rad/s, 80°/s
	T-Axis	2.79rad/s, 160°/s
Allowable Moment	R-Axis	1274N·m (130kgf·m)
	B-Axis	2156N·m (220kgf·m)
	T-Axis	0N·m (0kgf·m)
Allowable Inertia (GD <sup>2</sup> /4)	R-Axis	84.5kg·m <sup>2</sup>
	B-Axis	330kg·m <sup>2</sup>
	T-Axis	80kg·m <sup>2</sup>
Approx. Robot mass	2940kg	
Protected structure	Body: IP30, Wrist: IP67	
Mounting method	Shelf-mounted	
Allowable Conditions	Temperature	0 to +45°C
	Humidity	20 to 80%RH (Non-condensing)
	Vibration	9.8m/s <sup>2</sup> (1.0G) or less
	Altitude	1000m or less
	Others	<ul style="list-style-type: none"> <li>Free from explosive or corrosive gas and liquid.</li> <li>Free from dust, soot, oil, or water.</li> <li>Free from electrical noise.</li> <li>Free from strong magnetic fields.</li> </ul>
Power Requirements	22KVA	
Controller	YRC1000	

Units: mm

※1 Repeatability is conformed to ISO 9283.

※2 The manipulator is in the home position.

※3 It is the payload of the flange of the parallel link hand.

※4 Allowable moment/inertia are the acceptable values at the time of combining with a parallel link hand or a fixed hand. (Values include the weights of parallel link hand and the workpiece)

※5 Allowable wrist load is based on an assumption that the robot is handling a workpiece horizontally by keeping its wrist flange downwards.

※6 Power cable will be located on different positions depending on models (J\*\*, K\*\*, L\*\*).

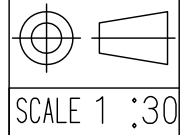
※7 Adjustable S axis mechanical stoppers are the standard equipment.

※8 Parallel link hand parts is option. It is necessary to add separately.

Note:

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FOR STUDY PURPOSE ONLY



**YASKAWA**  
株式会社 安川電機

Reference Drawing

TITLE MOTOMAN-PH200RF  
DIMENSION DIAGRAM

DRWN DATE Nov.02.'17  
DWG.NO. HW1385440

SIZE A3