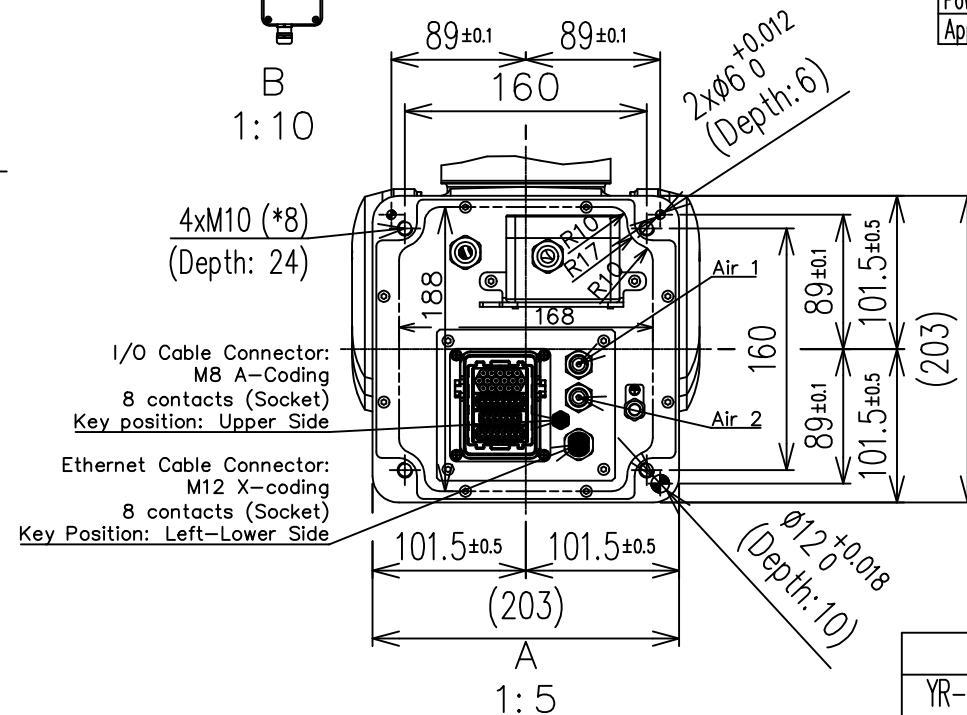
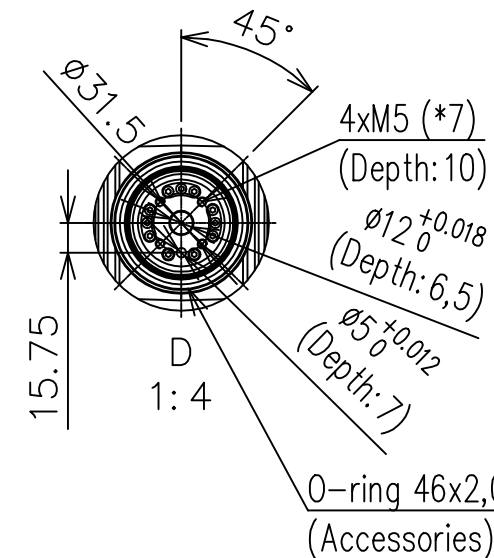
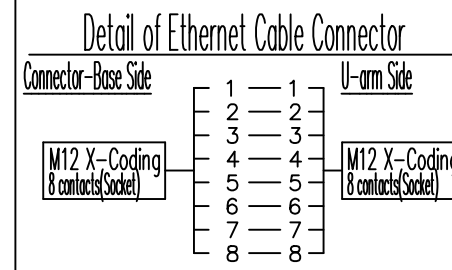
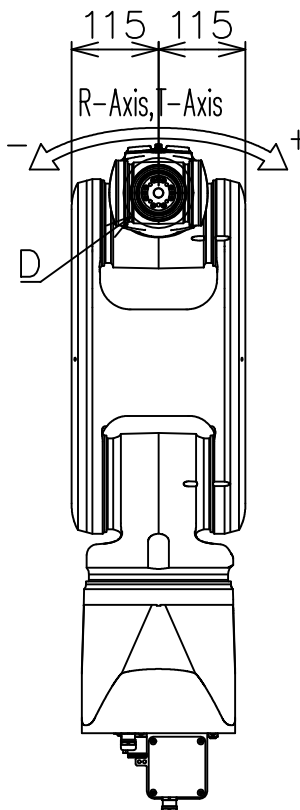
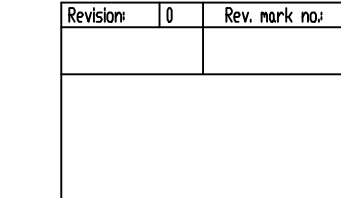




The reproduction, distribution and utilization of this document as well as the communication of its contents to others without express authorization is prohibited. Offenders will be held liable for the payment of damages. All rights reserved in the event of the grant of a patent, utility model or design.



- \*1 Repeatability conforms to ISO 9283.
- \*2 The maximum speed in this table is the available maximum value and will vary depending on the load, posture, or range of motion.
- \*3 The Cleanroom Class conforms to ISO 14644-1.
- \*4 When the manipulator is installed on a tilt or a wall, the motion of S-axis will be limited.
- \*5 The power requirement value is obtained using YASKAWA's in-house measurement conditions and will vary depending on the load, motion pattern, or cycle time.
- \*6 The posture in this drawing is in the home position.
- \*7 Maximum allowable torque equals to 8,5 Nm.
- \*8 Maximum allowable torque equals to 49,0 Nm.
- \*9 Use 4 x M10x35 screws to fix the robot to the baseplate (see detail E). In case of thicker baseplate, use longer screws accordingly (class 12.9).

Type		Controller	
YR-1-06VXM8-A00		YRC1000 / YRC1000 micro	
 www.eu.com	Dimension:		Weight [kg] 45 kg
	Created:	7-Dec-2023	Jevnikar M. 
	Reviewed:	7-Dec-2023	Jezeršek D. Sheet:
	Approved:	7-Dec-2023	Ichibangase A. A3
	Drawing-nr.: Y1100146		Scale: 1:10 Sheet: 1 / 1