

FASTECH

Ezi-SERVO II Plus-E

Ethernet Driver

Supported version TOP Design Studio

V1.4.11.23 or higher



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We want to thank our customers who use the Touch Operation Panel.

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Describes the devices required for connection, the setting of each device, cables, and configurable systems.

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Select a TOP model and an external device.

3. TOP communication setting [Page 4](#)

Describes how to set the TOP communication.

4. Supported addresses [Page 9](#)

Refer to this section to check the addresses which can communicate with an external device.

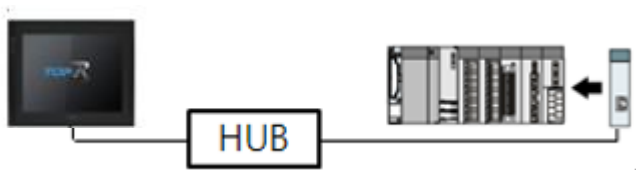
1. System configuration

The system configurations of TOP and "FASTECH – Ezi-SERVO Plus-E Series" are as follows:

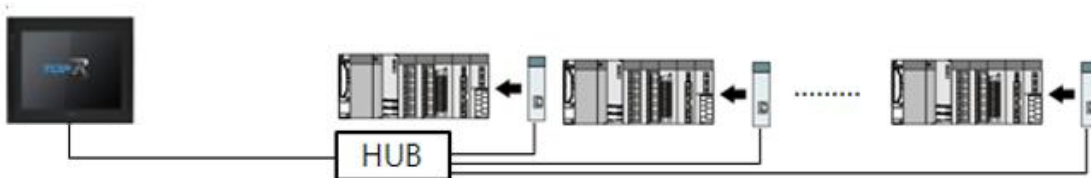
| Series | Communication method | Communication setting | Cable |
|---------------------|----------------------|--|------------------------------------|
| Ezi-Servo II Plus-E | Ethernet TCP | 3. TOP communication setting 4. TOP external device setting | 5.1. Cable table 1 |

■ Connection configuration

- 1:1 (one TOP and one external device) connection



- 1:N (one TOP and multiple external devices) connection



2. External device selection

- Select a TOP model and a port, and then select an external device.

| Settings | | Contents | | | | | |
|---------------------|--------------|---|-------|-----------|----------|---------------------|--------------|
| TOP | Model | Check the TOP display and process to select the touch model. | | | | | |
| External device | Vendor | Select the vendor of the external device to be connected to TOP. Select "FASTECH Co., Ltd." | | | | | |
| | PLC | Select an external device to connect to TOP. <table border="1" style="width: 100%; border-collapse: collapse;"> <thead> <tr> <th style="background-color: black; color: white;">Model</th> <th style="background-color: black; color: white;">Interface</th> <th style="background-color: black; color: white;">Protocol</th> </tr> </thead> <tbody> <tr> <td>FASTECH : Ezi-Servo</td> <td>Ethernet Tcp</td> <td>Ezi-Servo PlusE</td> </tr> </tbody> </table> <p>Please check the system configuration in Chapter 1 to see if the external device you want to connect is a model whose system can be configured.</p> | Model | Interface | Protocol | FASTECH : Ezi-Servo | Ethernet Tcp |
| Model | Interface | Protocol | | | | | |
| FASTECH : Ezi-Servo | Ethernet Tcp | Ezi-Servo PlusE | | | | | |

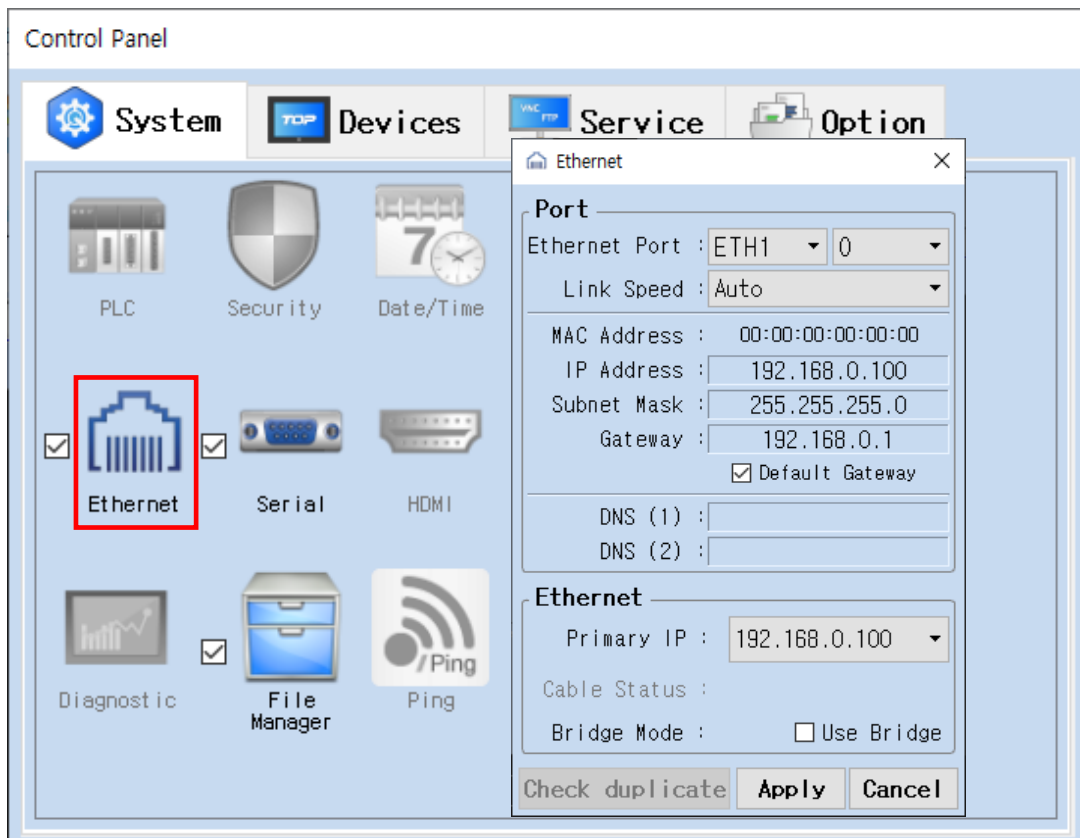
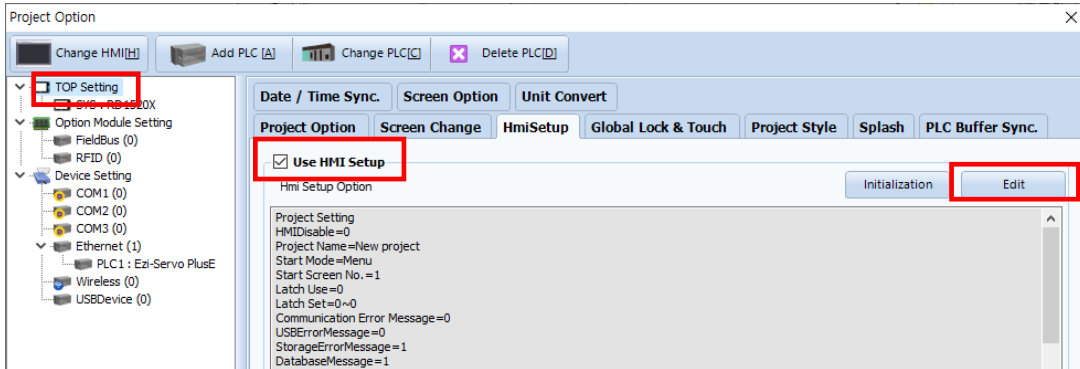
3. TOP communication setting

The communication can be set in TOP Design Studio or TOP main menu. The communication should be set in the same way as that of the external device.

3.1 Communication setting in TOP Design Studio

(1) Communication interface setting

- [Project > Project Property > TOP Setting] → [Project Option > "Use HMI Setup" Check > Edit > Ethernet]
- Set the TOP communication interface in TOP Design Studio.

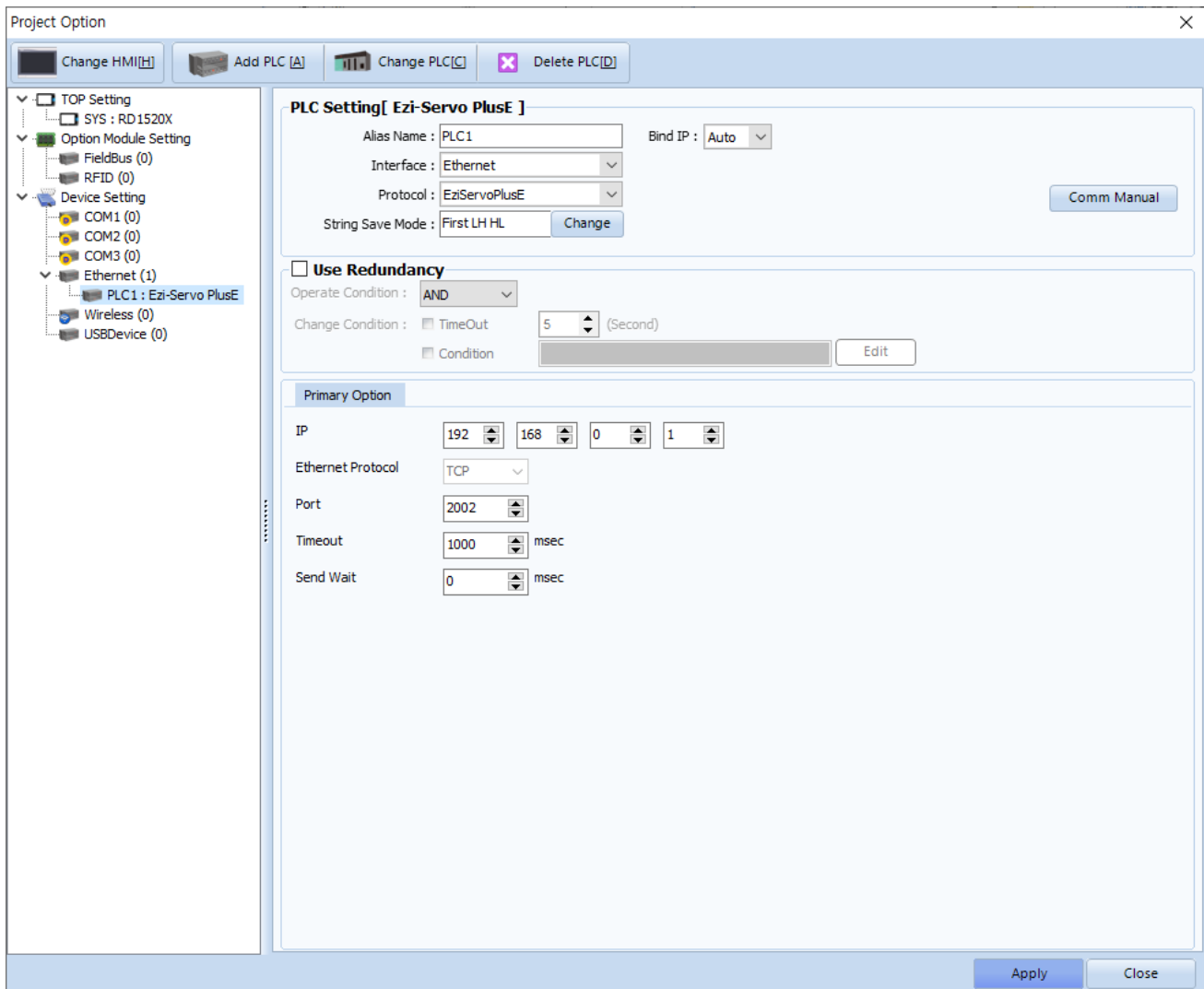


| Items | TOP | External device | Remarks |
|-------------|---------------|-----------------|---------|
| IP Address | 192.168.0.100 | 192.168.0.1 | |
| Subnet Mask | 255.255.255.0 | 255.255.255.0 | |
| Gateway | 192.168.0.1 | 192.168.0.1 | |

* The above settings are examples recommended by the company.

(2) Communication option setting

- [Project > Project Property > Device Setting > "FASTECH : Ezi-Servo"]
 - Set the options of the Computer Link communication driver in TOP Design Studio.

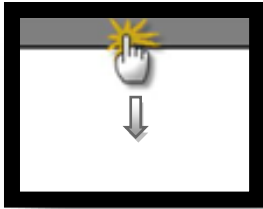


| Items | Settings | Remarks |
|---------------|---|---------|
| Interface | Select "Ethernet". | Fixed |
| Protocol | Select "EziServoPlusE". | |
| IP | Enter the IP address of the external device. | |
| TimeOut (ms) | Set the time for the TOP to wait for a response from an external device. | |
| SendWait (ms) | Set the waiting time between TOP's receiving a response from an external device and sending the next command request. | |

3.2. Communication setting in TOP

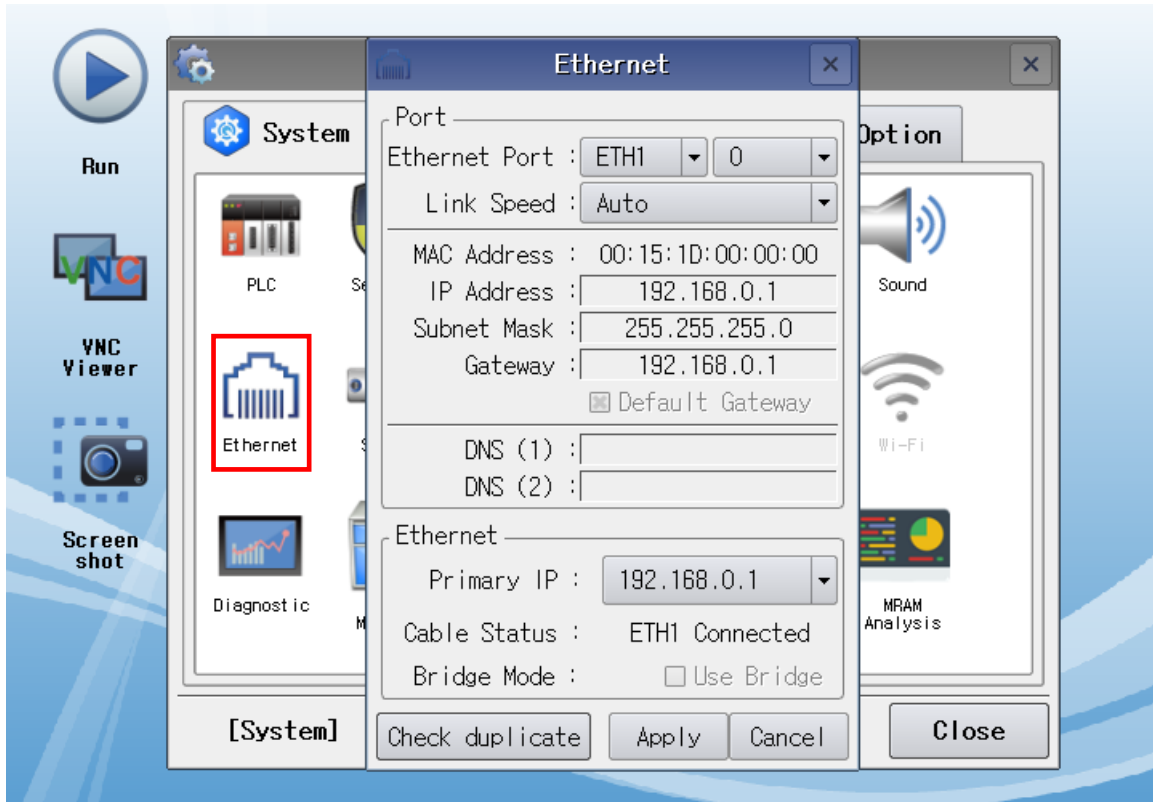
* This is a setting method when "Use HMI Setup" in the setting items in "3.1 TOP Design Studio" is not checked.

- Touch the top of the TOP screen and drag it down. Touch "EXIT" in the pop-up window to go to the main screen.



(1) Communication interface setting

- [Main Screen > Control Panel > Ethernet]



| Items | TOP | External device | Remarks |
|---|---------------|-----------------|---------|
| IP Address* Note 1) Note 2) | 192.168.0.100 | 192.168.0.1 | |
| Subnet Mask | 255.255.255.0 | 255.255.255.0 | |
| Gateway | 192.168.0.1 | 192.168.0.1 | |

*[Note 1](#)) The network addresses of the TOP and the external device (the first three digits of the IP, 192 . 168 . 0 . 0) should match.

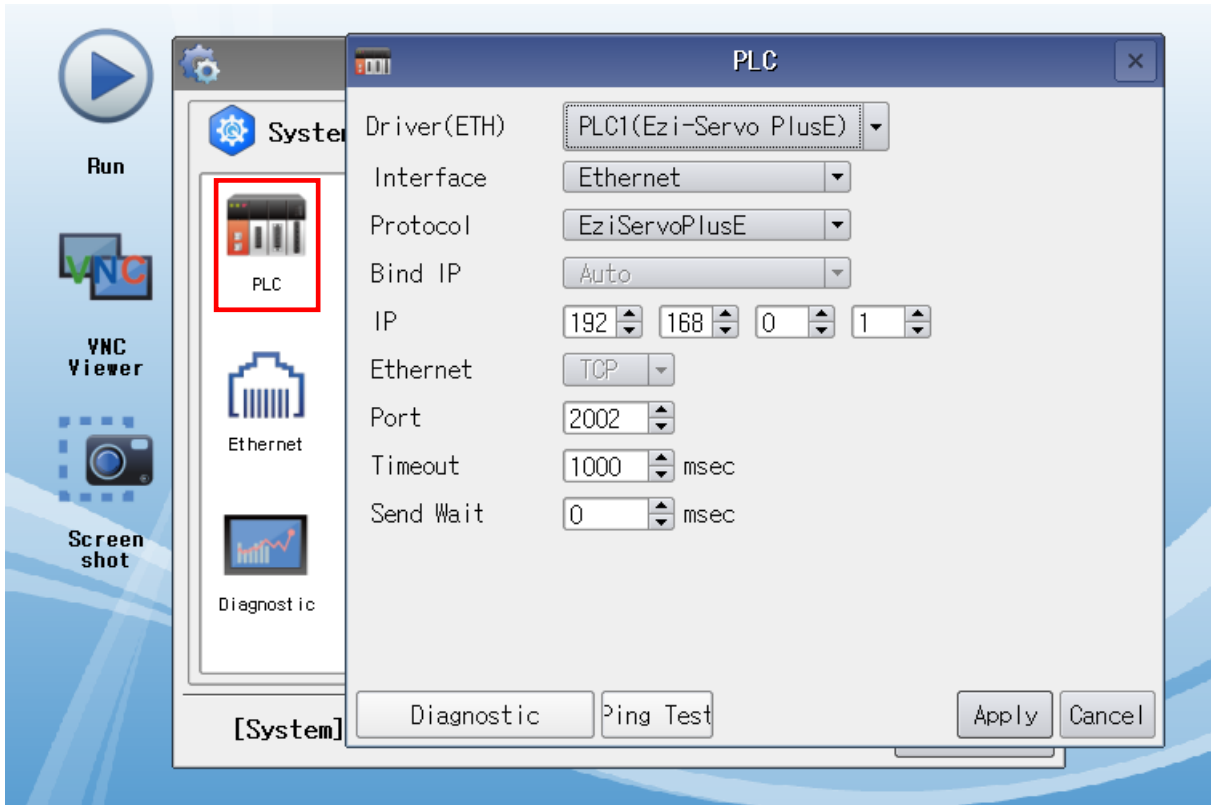
*[Note 2](#)) Do not use duplicate IP addresses over the same network.

* The above settings are examples recommended by the company.

| Items | Description |
|-------------|--|
| IP Address | Set an IP address to be used by the TOP to use over the network. |
| Subnet Mask | Enter the subnet mask of the network. |
| Gateway | Enter the gateway of the network. |

(2) Communication option setting

■ [Main Screen > Control Panel > PLC]



| Items | Settings | Remarks |
|---------------|---|---------|
| Interface | Select "Ethernet". | Fixed |
| Protocol | Select "EziServoPlusE". | |
| IP | Enter the IP address of the external device. | |
| TimeOut (ms) | Set the time for the TOP to wait for a response from an external device. | |
| SendWait (ms) | Set the waiting time between TOP's receiving a response from an external device and sending the next command request. | |

3.3 Communication diagnostics

- Check the interface setting status between the TOP and an external device.
 - Touch the top of the TOP screen and drag it down. Touch "EXIT" in the pop-up window to go to the main screen.
 - Check if the port (ETH1/ETH2) settings you want to use in [Control Panel > Ethernet] are the same as those of the external device.

- Diagnosis of whether the port communication is normal or not
 - Touch "Communication diagnostics" in [Control Panel > PLC].
 - The Diagnostics dialog box pops up on the screen and determines the diagnostic status.

| | |
|-----------------------|--|
| OK | Communication setting normal |
| Time Out Error | Communication setting abnormal - Check the cable, TOP, and external device setting status. (Reference: Communication diagnostics sheet) |

- Communication diagnostics sheet
 - If there is a problem with the communication connection with an external terminal, please check the settings in the sheet below.

| Items | Contents | Check | | Remarks | |
|----------------------|---------------------------------------|---------------------------|---|--|----|
| System configuration | How to connect the system | OK | NG | 1. System configuration | |
| | Connection cable name | OK | NG | | |
| TOP | Version information | OK | NG | 2. External device selection 3. Communication setting | |
| | Port in use | OK | NG | | |
| | Driver name | OK | NG | | |
| | Other detailed settings | OK | NG | | |
| | Relative prefix | Project setting | OK | | NG |
| | | Communication diagnostics | OK | | NG |
| | Ethernet port setting | IP Address | OK | | NG |
| | | Subnet Mask | OK | | NG |
| Gateway | | OK | NG | | |
| External device | CPU name | OK | NG | | |
| | Communication port name (module name) | OK | NG | | |
| | Protocol (mode) | OK | NG | | |
| | Setup Prefix | OK | NG | | |
| | Other detailed settings | OK | NG | | |
| | Ethernet port setting | IP Address | OK | | NG |
| | | Subnet Mask | OK | | NG |
| | | Gateway | OK | | NG |
| Check address range | OK | NG | 4. Supported addresses (For details, please refer to the PLC vendor's manual.) | | |

4. Supported addresses

■ The devices available in TOP are as follows:

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|------------------|-------------|-----------------------------|--|------------|-----|---------|
| INFO_DRIVER_VER | X | 0 – 0 | Read the version information on a connected external device. | 16 | R | |
| INFO_DRIVER_NAME | X | 0 – 0 | Read the name of a connected external device. | String | R | |
| INFO_MOTOR_NO | X | 0 – 0 | Read the number of a connected motor. | 16 | R | |
| SAVE_ROM_PARAM | 0.0 – 0.0 | X | Save the currently set parameter values and allocation values of I/O signals in the drive ROM memory. | 1 | W | |
| PARAM | 0.0 – 32.31 | 0–32 Parameter Number | Read operation (R): Read the parameter of a registered word address number from the RAM memory. Write operation (W): Save the parameter value of a registered word address number in the RAM memory. | 32 | R/W | |
| LOAD_ROM_DIOMAP | 0.0 – 0.0 | X | Read the setting status of the control IO signal and the level setting value of the signal from the ROM memory. | 1 | W | Note 1) |
| SERVO_ONOFF | 0.0 – 0.0 | X | Set Servo ON/OFF status. 0 : Servo OFF 1 : Servo ON | 1 | W | Note 1) |
| SERVO_ALMRST | 0.0 – 0.0 | X | Reset Servo Alarm status. | 1 | W | Note 1) |
| ALM_STATUS | X | 0 – 0 | Request current alarm status and information. ◆ Alarm Type 0 : No Alarm 1 : OverCurrent 2 : OverSpeed 3 : StepOut 4 : OverLoad 5 : OverTemperature 6 : BackEMP 7 : MotorConnect 8 : EncoderConnect 9 : MotorPower 10 : Inposition 11 : SystemHalt 12 : ROMdevice 15 : Position Overflow | 16 | R | |
| MOVE_STOP | 0.0 – 0.0 | X | Request to stop the motor which is currently running. | 1 | W | Note 1) |
| MOVE_ESTOP | 0.0 – 0.0 | X | Request to emergency stop the motor which is currently running. | 1 | W | Note 1) |
| MOVE_HOME | 0.0 – 0.0 | X | Request to start homing operation under the condition of the currently set parameter. | 1 | W | Note 1) |
| MOVE_PAUSE | 0.0 – 0.0 | X | Request to pause and unpaue the current operating status. 0: Unpause 1: Pause | 1 | W | Note 1) |
| STATUS_FLAG | 0.0 – 0.31 | 0 – 0 | Request a flag value which indicates operating status. For information on the operating status flag, refer to the Bit setting section of the Fastech manual status Flag. | 32 | R | |

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------------|-------------|--------------|---|------------|-----|---------|
| LOAD_ROM_PARAM | 0.0 – 0.0 | X | Read a specific parameter value of the ROM memory area. | 1 | W | |
| LOAD_ROM_PARAM_NO | X | 0 – 0 | ROM parameter number to be read | 16 | | Note 2) |
| ROM_PARAM | X | 0 – 0 | Parameter data value which has been read | 32 | | Note 2) |

Ex) Read the 2nd parameter value of the ROM area to be saved in the ROM_PARAM device when LOAD_ROM_PARAM device write operation is carried out if the data value of LOAD_ROM_PARAM_NO device is 2.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-----------|-------------|----------------------|--|------------|-----|---------|
| DIO_MASK | 0.0 – 22.31 | 0 – 22 Pin number | Read operation (R): Read the pin control IO setting status of a registered word address number. Write operation (W): Set the control IO signal to the pin of a registered word address number. | 32 | R/W | |
| DIO_LEVEL | 0.0 – 22.31 | 0 – 22 Pin number | Read operation (R): Read pin control IO signal level of a registered word address number. Write operation (W): Set the control IO signal level to the pin of a registered word address number. 0 : Active Low 1 : Active High | 32 | R/W | |

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-----------------|-------------|--------------|---|------------|-----|---------|
| COMP_OUT_TRIG | 0.0 – 0.0 | X | Create a control output signal (Compare Out) upon write operation. | 1 | W | Note 1) |
| COMP_OUT_POS | X | 0 – 0 | Compare Trigger start position | 32 | | Note 2) |
| COMP_OUT_PERIOD | X | 0 – 0 | Compare Trigger Pulse cycle | 32 | | Note 2) |
| COMP_OUT_WIDTH | X | 0 – 0 | Compare Trigger Pulse width | 32 | | Note 2) |
| COMP_OUT_STATUS | 0.0 – 0.0 | X | Current signal (Compare Out) output function reads the operating status. 0: Ended 1: Outputting | 1 | R | |

Ex) Upon COMP_OUT_TRIG operation, the operation is requested based on the data values of COMP_OUT_POS, COMP_OUT_PERIOD, and COMP_OUT_WIDTH devices.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|--------------|-------------|--------------|---|------------|-----|---------|
| DINPUT | 0.0 – 0.31 | 0 – 0 | <p>Read operation (R): Read the current input signal status of the control input terminal.</p> <p>Write operation (W): Set the input signal level of the control input terminal. If a specific bit value is 1, the corresponding input terminal signal becomes ON.</p> | 32 | R/W | |
| DINPUT_CLR | 0.0 – 0.31 | 0 – 0 | Set the input signal level of the control input terminal. If a specific bit value is 1, the corresponding input terminal signal becomes OFF. | 32 | W | |
| DOOUTPUT | 0.0 – 0.31 | 0 – 0 | <p>Read operation (R): Read the current output signal status of the control output terminal.</p> <p>Write operation (W): Set the output signal level of the control output terminal. If a specific bit value is 1, the corresponding output terminal signal becomes ON.</p> | 32 | R/W | |
| DOOUTPUT_CLR | 0.0 – 0.31 | 0 – 0 | Set the output signal level of the control output terminal. If a specific bit value is 1, the corresponding output terminal signal becomes OFF. | 32 | W | |

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------------|-------------|------------------------|---|------------|-----|---------|
| USER_OUT_STATUS | 0.0 – 8.16 | 0 – 8 PIN Number | Read the current PIN output status of a registered word address. 0 : STOP 2 : RUN | 16 | R | |
| USER_OUT_TIME | X | 0 – 8 | Output ON time set in the PIN of a registered word address | 16 | R | |
| USER_OUT_POS | X | 0:00 – 8:59 | Information on output location array set in the PIN of a registered word address | 32 | R | |
| USER_OUT_PCNT | X | 0 – 8 | Number of output location set in PIN of a registered word address | 16 | R | |
| SET_USER_OUT_TRIG | 0 – 8 | X | Create an output at a specific location on the set output. | 1 | W | Note 1) |
| SET_USER_OUT_TIME | X | 0 – 0 | Output On time (Unit: ms, 1 – 65535) | 16 | | Note 2) |
| SET_USER_OUT_POS | X | 0:00 – 8:59 | Output location array For word address 5:31 User Out number: 5 Output location array: 31 | 32 | | Note 2) |
| SET_USER_OUT_PCNT | X | 0 – 0 | Number of output positions (number of registered output location arrays) | 16 | | Note 2) |

Can be used after setting the output signal to User Out.

Ex) Upon SET_USER_OUT_TRIG operation, the operation is requested based on the data values of SET_USER_OUT_TIME, SET_USER_OUT_POS, SET_USER_OUT_PCNT devices.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|---------------|-------------|--------------|---|------------|-----|---------|
| MOVE_ABS_TRIG | 0.0 – 0.0 | X | Request to start movement operation as much as the absolute value [pulse] position. | 1 | W | Note 1) |
| MOVE_ABS_POS | X | 0 – 0 | Absolute position value for movement operation | 32 | | Note 2) |
| MOVE_POS_SPD | X | 0 – 0 | Speed value of position movement operation [pps] | 32 | | Note 2) |

Ex) Upon MOVE_ABS_TRIG operation, the device operates based on the data values of MOVE_ABS_POS and MOVE_POS_SPD devices.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|---------------|-------------|--------------|---|------------|-----|---------|
| MOVE_INC_TRIG | 0.0 – 0.0 | X | Request to start movement operation as much as the relative value [pulse] position. | 1 | W | Note 1) |
| MOVE_INC_POS | X | 0 – 0 | Relative position value for movement operation | 32 | | Note 2) |
| MOVE_POS_SPD | X | 0 – 0 | Speed value of position movement operation [pps] | 32 | | Note 2) |

Ex) Upon MOVE_INC_TRIG operation, the device operates based on the data values of MOVE_INC_POS and MOVE_POS_SPD devices.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------|-------------|--------------|---|------------|-----|---------|
| MOVE_LIMIT+ | 0.0 – 0.0 | X | Request to start LIMIT+ operation under the currently set parameter conditions. 0 : STOP 1 : LIMIT+ operation | 1 | W | Note 1) |
| MOVE_LIMIT- | 0.0 – 0.0 | X | Request to start LIMIT- operation under the currently set parameter conditions. 0 : STOP 1 : LIMIT- operation | 1 | | Note 1) |
| MOVE_SPD | X | 0 – 0 | Speed value of movement operation [pps] | 32 | | Note 2) |

Ex) Upon MOVE_LIMIT+,- operation, the device operates based on the data value of MOVE_SPD device.

*. When changing the direction during operation, the direction must be changed while in the STOP status.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-----------|-------------|--------------|---|------------|-----|---------|
| MOVE_JOG+ | 0.0 – 0.0 | X | Request to start JOG+ operation under the currently set parameter conditions. 0 : STOP 1 : JOG+ operation | 1 | W | Note 1) |
| MOVE_JOG- | 0.0 – 0.0 | X | Request to start JOG operation under the currently set parameter conditions. 0 : STOP 1 : JOG- operation | 1 | | Note 1) |
| MOVE_SPD | X | 0 – 0 | Speed value of movement operation [pps] | 32 | | Note 2) |

Ex) Upon MOVE_JOG+,- operation, the device operates based on the data value of MOVE_SPD device.

*. When changing the direction during operation, the direction must be changed while in the STOP status.



| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|------------------------|-------------|--------------|--|------------|-----|---------|
| MOVE_OVERRIDE_ABS_TRIG | 0.0 – 0.0 | X | Request to change the target absolute position value [pulse] value during operation. | 1 | W | Note 1) |
| MOVE_ABS_POS | X | 0 – 0 | Absolute position value for movement operation | 32 | | Note 2) |

Ex) Upon MOVE_OVERRIDE_ABS_TRIG operation, the device operates based on the data value of MOVE_ABS_POS device.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|------------------------|-------------|--------------|--|------------|-----|---------|
| MOVE_OVERRIDE_INC_TRIG | 0.0 – 0.0 | X | Request to change the target relative position value [pulse] value during operation. | 1 | W | Note 1) |
| MOVE_INC_POS | X | 0 – 0 | Relative position value for movement operation | 32 | | Note 2) |

Ex) Upon MOVE_OVERRIDE_INC_TRIG operation, the device operates based on the data value of MOVE_INC_POS device.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|------------------------|-------------|--------------|---|------------|-----|---------|
| MOVE_OVERRIDE_SPD_TRIG | 0.0 – 0.0 | X | Request to change the operating speed value [pps] during operation. | 1 | W | Note 1) |
| MOVE_SPD | X | 0 – 0 | Speed value of movement operation [pps] | 32 | | Note 2) |

Ex) Upon MOVE_OVERRIDE_SPD_TRIG operation, the device operates based on the data value of MOVE_SPD device.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------|-------------|--------------|---|------------|-----|---------|
| CMD_POS | X | 0 – 0 | Read operation (R): request the value [pulse] of the target position of that which is currently being followed (Command Position) Write operation (W): set a target position (Command Position) value [pulse]. | 32 | R/W | |
| ACT_POS | X | 0 – 0 | Read operation (R): request the current actual position (Actual Position) value [pulse]. Write operation (W): set the current actual position (Actual Position) value [pulse]. | 32 | R/W | |
| POS_ERR | X | 0 – 0 | Request the difference value [pulse] between the current target position (Command Position) and the actual position (Actual Position) value. | 32 | R | |
| CURRENT_SPD | X | 0 – 0 | Request the current operating speed value [pps]. | 32 | R | |
| CLEAR_POS | 0.0 – 0.0 | X | Set the target position (Command Position) and actual position (Actual Position) values to 0. | 1 | W | Note 1) |

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------|-------------|--------------|---|------------|-----|---------|
| LOAD_ROM_PT | 0.0 – 0.0 | X | Read all PT item values in the ROM memory area of the drive. | 1 | W | Note 1) |
| SAVE_ROM_PT | 0.0 – 0.0 | X | Store all PT item values in the ROM memory area of the drive. | 1 | W | Note 1) |

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------|-------------|--------------|---|------------|-----|---------|
| PT_RUN_TRIG | 0.0 – 0.0 | X | Start the operation of the position table starting from the designated PT number. | 1 | W | Note 1) |
| PT_NUMBER | x | 0 – 0 | PT number to start operation | 16 | | Note 2) |

Ex) Upon PT_RUN_TRIG operation, the device operates based on the data value of PT_NUMBER.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|---------|-------------|-----------------|--|---------------|-----|---------|
| PT_ITEM | X | 0–255 : 0–28 | <p>Read operation (R): read a specific value (Offset) from the PT items in the RAM memory of the drive.</p> <p>Write operation (W): store a specific value (Offset) among the PT items in the RAM memory of the drive.</p> <p>Word Address 0–255: PT number 0–28: Word Offset of an item</p> | 16 / 32 | R/W | |

Ex)

When PT_ITEM7:7 device is drawn to be registered, read the Decel Time value of the 7th PT upon read operation or save it upon write operation.

When PT_ITEM5:4 device is drawn to be registered, read the High Speed value of the 5th PT upon read operation or save it upon write operation.

Set the object Size to 32 for items of 32-bit size among the position table items.

*. Please refer to the position table items in the Fastech manual for specific item word offset value of PT.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------------|-------------|--------------|---|------------|-----|---------|
| PUSH_MOVE_TRIG | 0.0 – 0.0 | X | Request to start push motion operation to maintain a fixed force. | 1 | W | Note 1) |
| PUSH_START_SPD | X | 0 – 0 | Speed value of position movement starting [pps] | 32 | | Note 2) |
| PUSH_POS_SPD | X | 0 – 0 | Speed value of position movement operation [pps] | 32 | | Note 2) |
| PUSH_ABS_POS | X | 0 – 0 | Absolute position value of position movement | 32 | | Note 2) |
| PUSH_POS_ACC | X | 0 – 0 | Acceleration time of position movement [ms] | 16 | | Note 2) |
| PUSH_POS_DEC | X | 0 – 0 | Deceleration time of position movement [ms] | 16 | | Note 2) |
| PUSH_TORQUE_RATIO | X | 0 – 0 | Push motion torque ratio [%] | 16 | | Note 2) |
| PUSH_MOTION_SPD | X | 0 – 0 | Push motion operating speed value [pps] | 32 | | Note 2) |
| PUSH_END_POS | X | 0 – 0 | Push motion absolute position value | 32 | | Note 2) |
| PUSH_MODE | X | 0 – 0 | Push mode | 16 | | Note 2) |

Ex) Upon PUSH_MOVE_TRIG operation, the device operates based on the data values of PUSH_START_SPD, PUSH_POS_SPD, PUSH_ABS_POS, PUSH_POS_ACC, PUSH_POS_DEC, PUSH_TORQUE_RATIO, PUSH_MOTION_SPD, PUSH_END_POS, and PUSH_MODE.

For details, refer to the Push Motion function in the Fastech manual.

*. Be sure to execute MOVE STOP(ESTOP) command must be executed before the next motion command.

| Device | Bit Address | Word Address | Comment | Size (Bit) | R/W | Remarks |
|-------------|-------------|--------------|---|------------|-----|---------|
| PUSH_STATUS | X | 0 – 0 | <p>Read the current push motion operation status.</p> <p>*. Push motion status</p> <p>0 : Waiting status for general position movement</p> <p>1 : In push motion, the work is not in contact.</p> <p>2 : In contact with the work, and the force is maintained.</p> <p>3 : The push motion has been completed, but the work is not in contact.</p> <p>In this case, be sure to execute the STOP (ESTOP) command before the next motion command.</p> | 16 | R | |

Note 1) The action command address is not displayed in the general object address. *. [How to use action-only addresses](#)

Note 2) This is a device for parameter setting for a write-only device to use a specific function.

Appendix

1. Action command address

Unlike general addresses, operation-only addresses are not visible in the Address when registering objects. You can register an action-only address in the address editor which performs actions like the action function of Effect & Action in the Object Property.

The reverse action is not supported for action-only addresses.

* How to use action-only device

[Object Property Window] → [Effect & Action] → [Action] → [Bit or Select Word] → [Select Write-Only Device of External Device] → [Set Action Condition]

