

# **Ezi-SERVO<sup>®</sup> II** **Plus-E MINI**

## **Closed Loop Stepping System**

User Manual

User Program(GUI) Function

( Rev.02)



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**This manual describes how to operate User Program(GUI).**

**For more information, refer to related manuals as following.**

- (1) [User Manual\\_Text](#)
- (2) [User Manual\\_Communication Function](#)
- (3) [User Manual\\_Position Table Function](#)

## 1 . Installation and Connection of the Program

There are two operation modes as follows in Ezi-SERVOII Plus-E MINI.

- 1) Using Motion Library (DLL) which is provided for the program for Windows 7/ 8/ 10.
- 2) Using Position Table (PT) and external signals input by the user.

For the operation modes above, refer to each related manual.

This chapter describes the user program(GUI) used for the installation and running test of the controller.

### 1 - 1 . Installable PC Specifications

Type : Compatible with PC/AT

Ethernet 10/100base-T/TX Lan Card

Hard disk capacity more than 10MB

Screen SVGA(1024×768 or more)

CPU Pentium4 2.0GHz or more

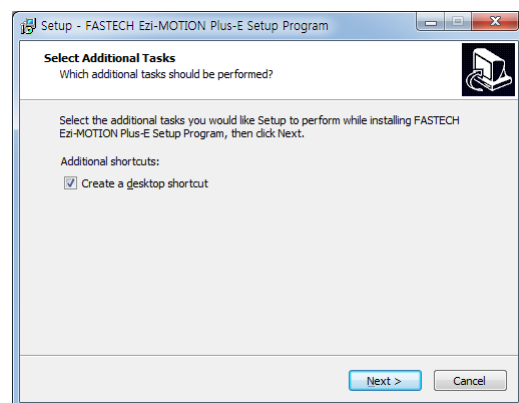
OS : Windows 7/ 8/ 10(32/64Bit)

### 1 - 2 . How to Install User Program(GUI)

Download [Ezi-MOTION\_Plus-E\_SETUP] program on FASTECH website and Install as shown below.

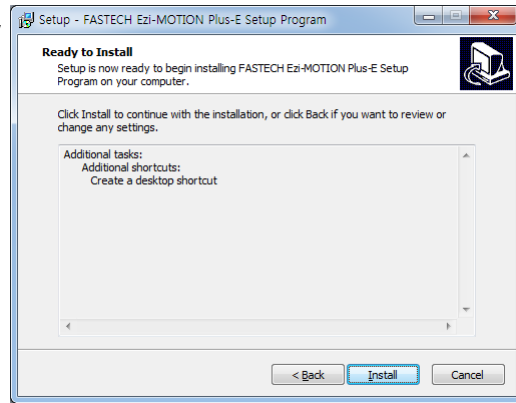
Installation Start window.

Click Next.

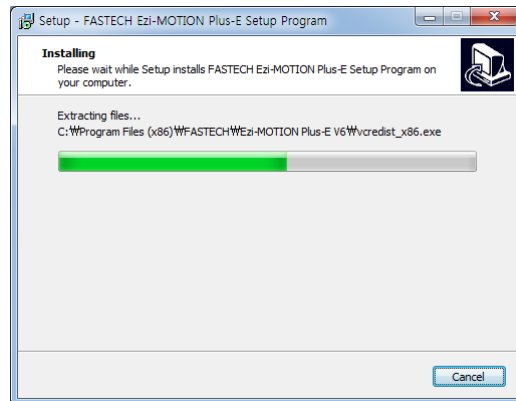


## Installation and Connection of the Program

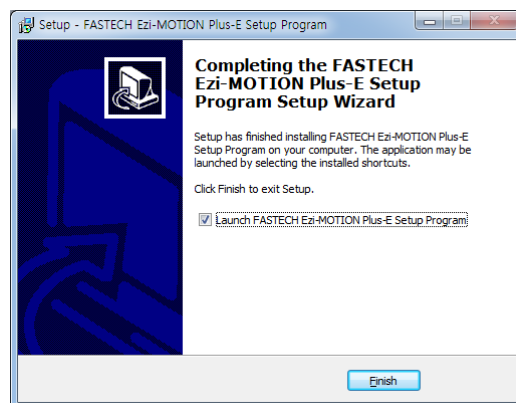
Select a folder where the program is installed,  
And click 'Install'.



Installing

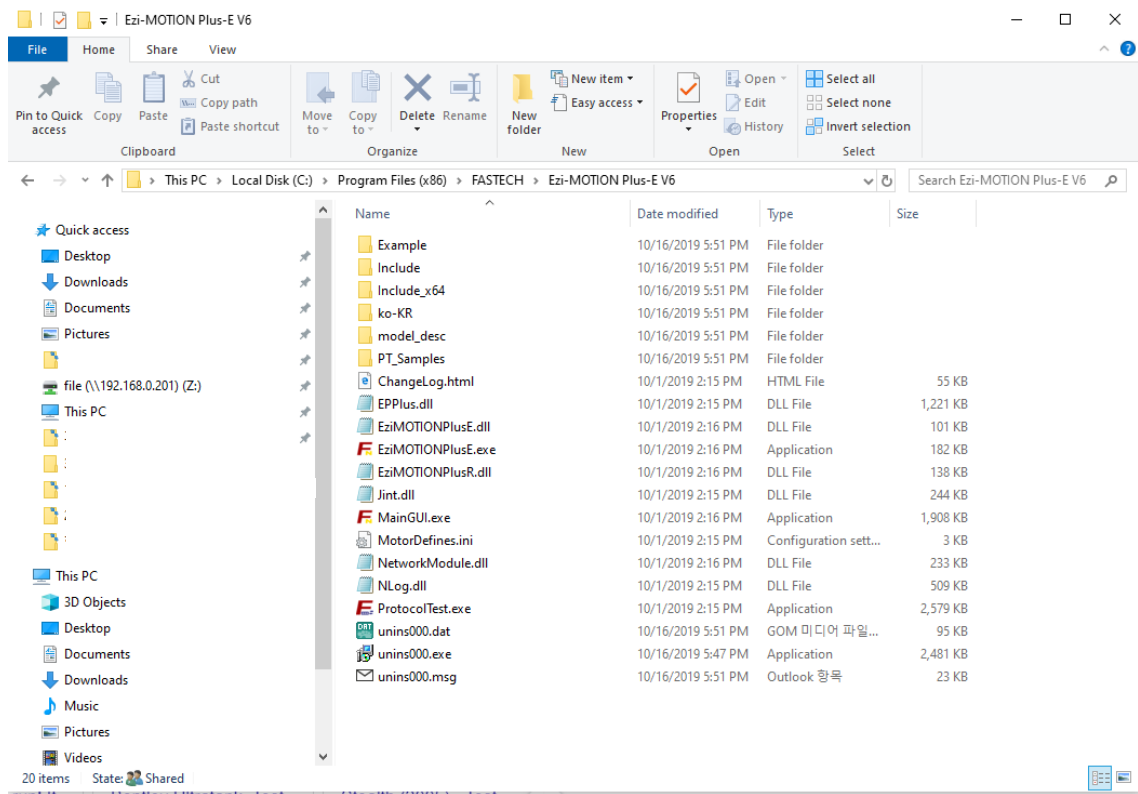


Installation is completed.



## Installation and Connection of the Program

When installation is completed, you can find the below files in the selected folder.



- 1) Include folder : \*.dll, \*.lib, \*.h, \*.cs files (for 32bit, including files for C#)
- 2) Include\_x64 folder : \*.dll, \*.lib, \*.h, \*.cs files(for 64bit, including files for C#)
- 3) Example folder : source code for sample
- 4) PT\_Samples folder : sample data files for position table

## 1 - 3 . Connecting PC with Drive Module


- (1) To communicate with controller module, the user should prepare Ethernet cable and connect it with the PC. For more information, refer to 「[User Manual\\_Text](#)」.

Execute User program(GUI) icon(Ezi-MOTION PlusE V6) and click 「Connect」. Then the following window will be displayed.



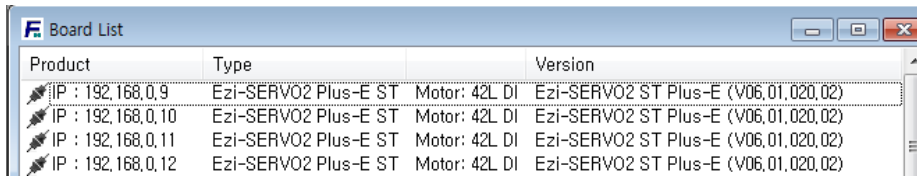
Button	Description
Add	Enter IP Address and add on List. If the item does not exist with added IP Address, List will not be added.
Broadcast Search	Search every item that can be connected to GUI and then add it to the list.
Refresh Status	Check the connection status of listed item.
Connect	Connect the listed item and execute GUI.

- After setting the IP address of each product differently, if you press the Broadcast Search button, all products are displayed in the list. At this time, if you press the Connect button, all products are connected to the GUI.

 <b>Caution</b>	<ol style="list-style-type: none"> <li><b>1. Please assign different IP Addresses of connected drives to a single network (segment).</b></li> <li><b>2. If the connection fails, please check IP conflict and IP Address of PC.</b></li> </ol>
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(2) When the connection is completed, the window will appear as shown below.

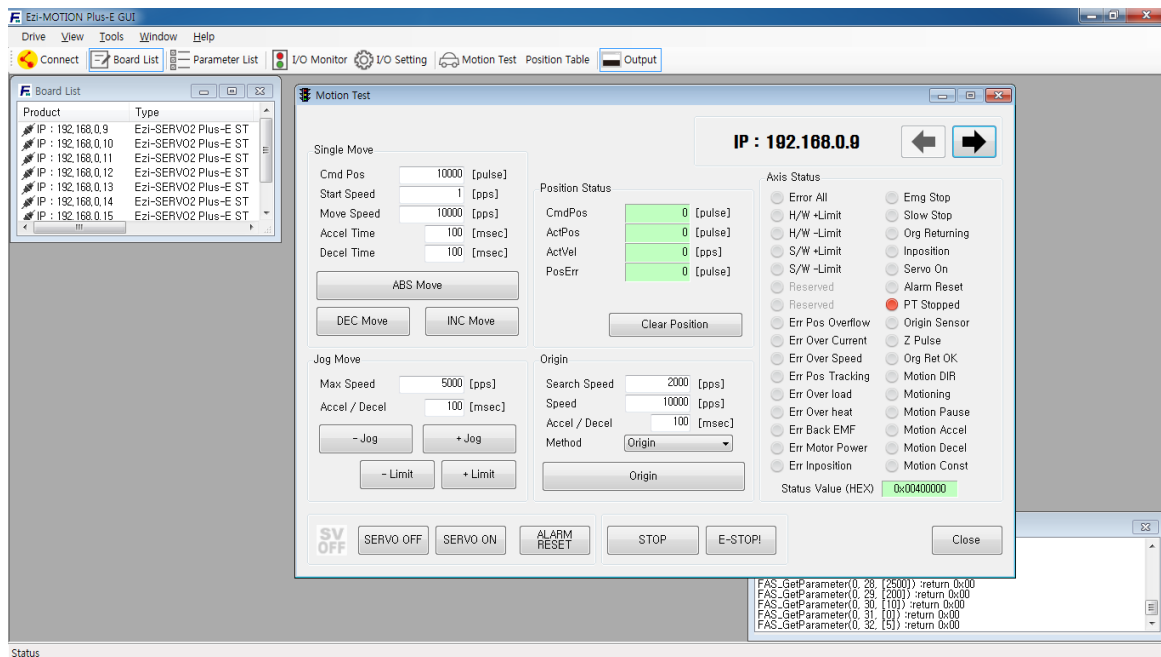
- 1) IP Address of Connected drives
- 2) Type of all connected motors and drives
- 3) Firmware Version



The screenshot shows a window titled 'Board List' with a table containing four columns: Product, Type, Motor, and Version. There are four rows of data, each representing a connected drive. Each row starts with a small icon and an IP address.

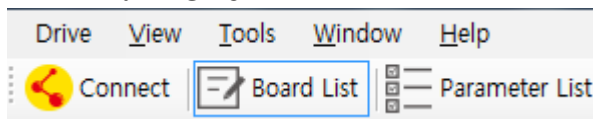
Product	Type	Motor	Version
IP : 192.168.0.9	Ezi-SERVO2 Plus-E ST	Motor: 42L DI	Ezi-SERVO2 ST Plus-E (V06.01.020.02)
IP : 192.168.0.10	Ezi-SERVO2 Plus-E ST	Motor: 42L DI	Ezi-SERVO2 ST Plus-E (V06.01.020.02)
IP : 192.168.0.11	Ezi-SERVO2 Plus-E ST	Motor: 42L DI	Ezi-SERVO2 ST Plus-E (V06.01.020.02)
IP : 192.168.0.12	Ezi-SERVO2 Plus-E ST	Motor: 42L DI	Ezi-SERVO2 ST Plus-E (V06.01.020.02)

## 2 . Main Window



This is the basic window when the program is running. Each window is displayed in this window. The user can open each window with a toolbar.

### 2 - 1 . Menu



Menu	Description
Drive	To connect or disconnect with the drive
View	To open each window
Tool	To select a language of GUI
Window	To change window's array

### 2 - 2 . Toolbar



It provides various buttons to go to different screens.

(The button of the Toolbar is enabled or disabled depending on the connected product.)

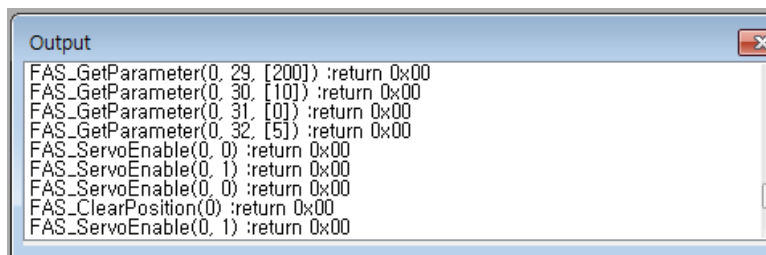
Clicking each button executes the following functions.

Button	Description
Connect	To connect or disconnect with the drive
Board List	To display connected module information and communication status



Parameter list	To set parameter values related to operation control like a position command
I/O Monitor	To monitor digital input and output signal of Drive CN1 connector.
I/O Setting	To set digital input and output signal of Drive CN1 connector
Motion Test	To execute motion commands such as Jog operation, Position operation, Origin return operation
Position Table	To input, modify, save, execute the data for position table
Output	To display DLL function corresponding to the command being executed

## 2 - 3 . Output

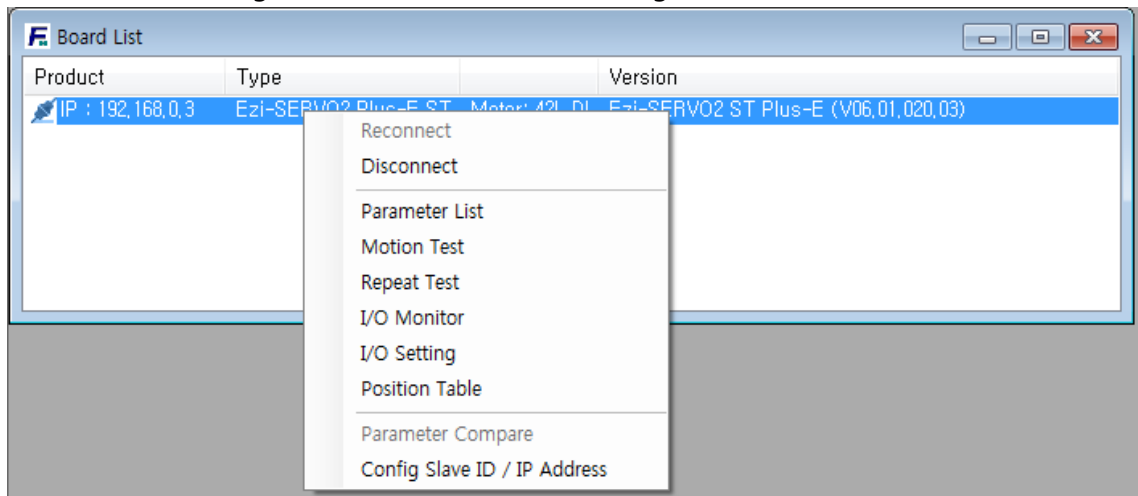


Click 'Output' at the Toolbar or check [Menu] – [View] – [Output], and the above window will be displayed.

This screen shows the command used for the drive. You can check which function was used, how the parameter value was entered, and check whether it was processed normally. The window displays the function entered by the user or the function used when the button is clicked. For more information of commands, please refer to [「User Manual-Communication Function」](#)

## 2 - 4 . Board List

It is a screen to check the list of connected drives. You can check the information for each drive. To configure or test the drive function, right-click the drive.



Displayed Information :

- 1) Drive IP Address
- 2) Drive Type
- 3) Motor Type
- 4) Drive **Firmware Version**

- Disconnect / Reconnect

Disconnect : Disconnect the drive.

Reconnect : Reconnect the drive.

- Parameter List

It shows the screen to check, modify, and manage the parameters of the drive.

- Motion Test

In this window, motion commands such as jog operation, position operation, and origin return are executed.

- Repeat Test

This screen allows you to test one axis of the motor with repeating motion.

- I/O Monitor

This window monitors the digital input and output signals of the CN1 connector.

- I/O Setting

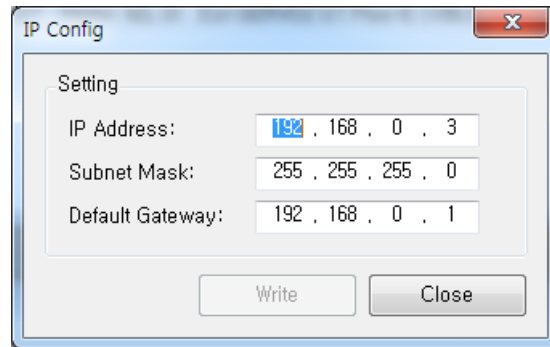
In this window, you set the digital input and output signals for the CN1 connector.

- Position Table

This is a window where you can enter and execute data for the position table.

- Config Slave ID / IP Address

This window allows you to change the default IP Address / Subnet Mask / Gateway settings.



After clicking "Write" and resetting power, configuration is applied.

The last number of IP Address is not applied even if it is changed in this window.

The last number is **set by the switch**.

Ex) IP Address : If you change the IP address 192.168.0.3 → 192.169.10.100, it still remains same, 192.168.10.3.

## 2 - 5 . Repeat Test

① You can set up to 3 absolute position values and travel speeds and perform repeat operation tests.

② You can specify the delay time and number to repeat for each repetition.

\* Delay Time : Wait time until each motion ends and the next motion starts. The unit is [msec].

\* Repeat : Set the number of repetitions for motion loop. If this value is '0', it repeats infinitely.

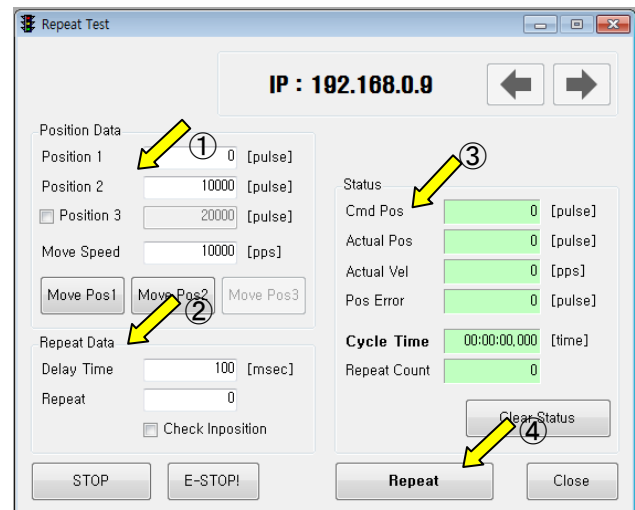
(Motion Loop is operated as Position1 -> Position2 -> Position1, and in this case it is counted as one cycle.)

③ Operation status and repeat count are displayed.

\* Cycle Time : Displays the time until repeat test is completely finished.

\* Repeat Count : Increases whenever one motion loop is finished.

④ Click the 'Repeat' button to start repeat operation according to the settings. If you click the 'Repeat' button while driving, it stops after completing the cycle in progress. To stop regardless of the cycle, use the 'Stop' or 'E-Stop!' button. '



### 3 . Parameter List

Parameter List

IP : 192.168.0.9

Parameters

No.	Name	Unit	Field	Default	Value	Comment
0	Pulse Per Revolution		0 ~ 8	8	8	10000
1	Axis Max Speed	pps	1 ~ 2500000	500000	2500000	
2	Axis Start Speed	pps	1 ~ 35000	1	1	
3	Axis Acc Time	msec	1 ~ 9999	100	100	
4	Axis Dec Time	msec	1 ~ 9999	100	100	
5	Speed Override	%	1 ~ 500	100	100	
6	Jog Speed	pps	1 ~ 2500000	5000	5000	
7	Jog Start Speed	pps	1 ~ 35000	1	1	
8	Jog Acc Dec Time	msec	1 ~ 9999	100	100	
9	S/W Limit Plus Value	pulse	-134217728 ~ 134217727	134217727	134217727	
10	S/W Limit Minus Value	pulse	-134217728 ~ 134217727	-134217728	-134217728	
11	S/W Limit Stop Method		0 ~ 2	2	2	No Stop
12	H/W Limit Stop Method		0 ~ 1	0	0	E-Stop
13	Limit Sensor Logic		0 ~ 1	0	0	Low Active
14	Org Speed	pps	1 ~ 500000	5000	10000	
15	Org Search Speed	pps	1 ~ 50000	1000	2000	
16	Org Acc Dec Time	msec	1 ~ 9999	50	100	
17	Org Method		0 ~ 7	0	0	Origin
18	Org Dir		0 ~ 1	0	1	CCW
19	Org Offset	pulse	-134217728 ~ 134217727	0	0	
20	Org Position Set	pulse	-134217728 ~ 134217727	0	0	
21	Org Sensor Logic		0 ~ 1	0	0	Low Active

Set to Default Load ROM Save to ROM Load File Save to File Close

Item	Description
No.	Parameter number
Name	Parameter name
Unit	Parameter unit
Field	Range that can input Parameter field
Default	Parameter default value
Value	Current parameter value
Comment	Current parameter description

The user can set and save parameter values related to motion control by each drive module. 'Value' column displays the value applied to current motion control and can be edited

#### 3 - 1 . IP Address

IP : 192.168.0.2

To display drive's umber for the current parameter list window. By using right/left arrow key, the user can select other drive.

Buttons at the bottom bar including 'Save to ROM' is available only for the current drive.

To control several drive parameters, the user should execute related each one of slave

independently.

### 3 - 2 . Parameter Input

No.	Name	Unit	Field	Default	Value	Comment
0	Pulse Per Revolution		0 ~ 8	8	8	10000
1	Axis Max Speed	pps	1 ~ 2500000	500000	2500000	
2	Axis Start Speed	pps	1 ~ 35000	1	1	
3	Axis Acc Time	msec	1 ~ 9999	100	100	
4	Axis Dec Time	msec	1 ~ 9999	100	100	

Select parameters as shown at the table, and the input box will be displayed and then the user can edit parameter values. When the user inputs the parameter value, it is saved to RAM area of the drive. The machine operates as the parameter is edited. However, when the drive is powered off, the value is deleted. To continuously operate the machine as the parameter value is set, the user must click 'SAVE to ROM' button and save the edited value to ROM.

When the input value is out of right range, it is displayed in red color.

The value cannot be inputted in RAM of the drive.

### 3 - 3 . Parameter List Window Buttons

Click each button, and the following functions will be executed.

Button	Description
Set to Default	Converts all parameter values into 'Default Value'
Load ROM	Converts 'Value' items into values saved to the ROM area.
Save to ROM	Saves 'Value' items to the ROM area. (Even though the drive is powered off, they are not deleted. )
Load File	Set 'Value' items to the values saved to an external file.
Save to File	Saves the current values to an external file. (The user defines folder position and file name. The extension is *.fpt. )

For more information of parameter types and their functions, refer to 「[User Manual\\_Text 10.Parameter](#)」.

### 3 - 4 . Save/Read to Files

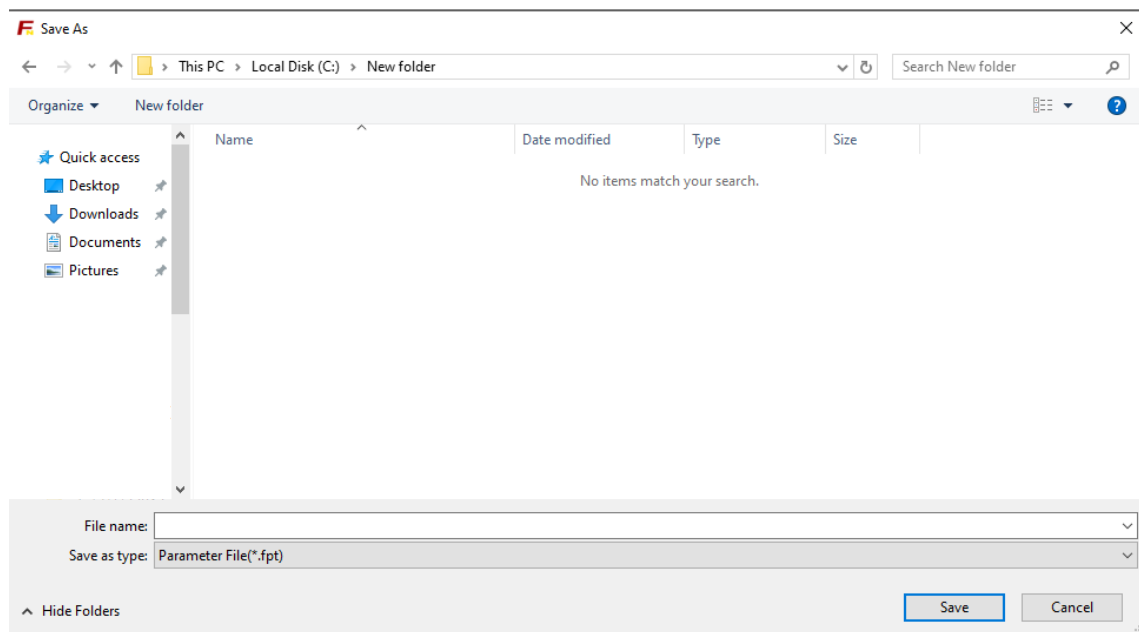
Ezi-SERVOII Plus-E MINI can save parameters, Input/output and position table data to an external file folder and can read them if necessary.

The user can edit a name of file, click 'Save' button, and save data. Then can select a file, click 'Open' button and read data.

File extension for parameter: \*.fpt

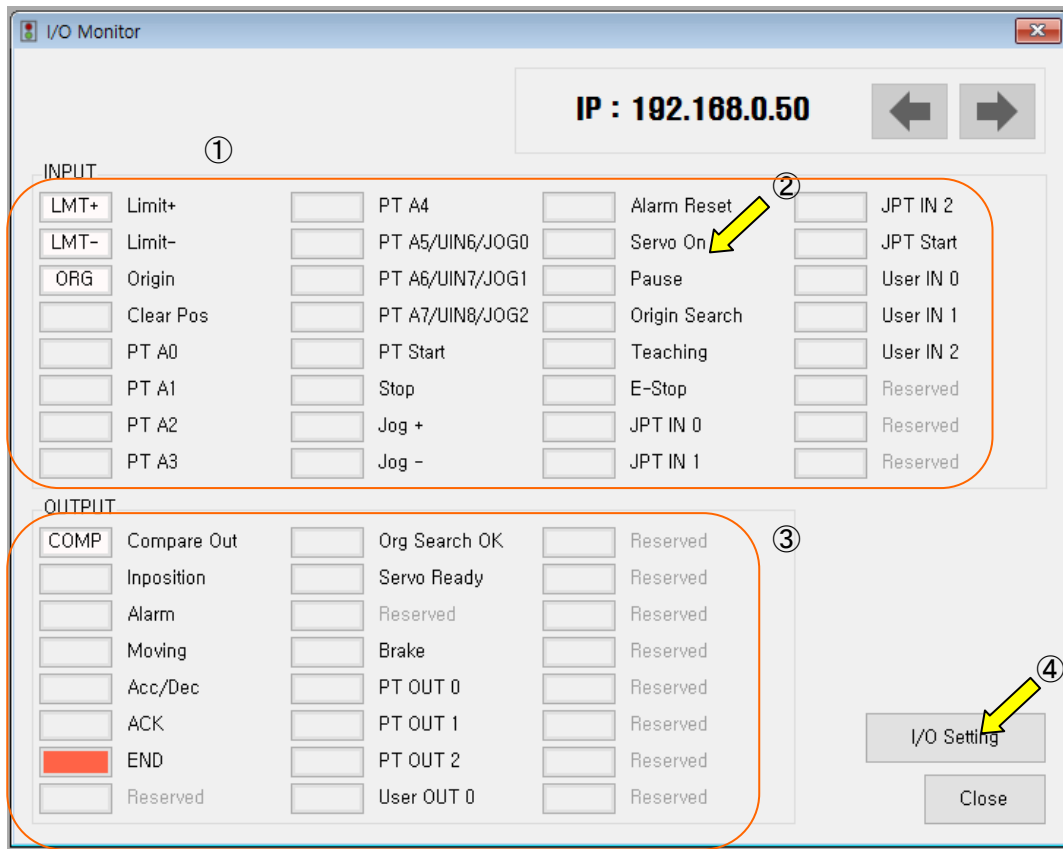
File extension for Input/output: \*.fit

File extension for position table data: \*.txt



## 4 . I/O Monitoring

The user can set and check control I/O signals related to operation control through CN1 connector. The next window is the sample setting of I/O Monitoring status.



### 1) Input Signal : ①

There are 29 definable input signals. However, just 6 signals of them can be connected with CN1 connector physically at once.

The first three signals are fixed to 'LIMIT+' , 'LIMIT-' and 'ORIGIN' sensors. Therefore other signals cannot be connected and used with these pins. The user can set up to 3 signals to Input 3 pins at one time. 'IN1'~'IN3' indicators are displayed to current setting signals.

When each signal for set as 'IN1'~'IN3' is [ON] through CN1 connector, icon is changed into 'green'. When the signal is [OFF], it returns to 'white' to the original state.

### 2) Virtual Input Function : ②

Even though the input pin is not assigned to 'IN1' ~ 'IN3' at all, the user can click each button and virtually change the signal into [ON]/[OFF]. For instance, click 'Pause' button, and the stop function will be operated temporarily. However, 'PT Start' signal is exceptional.



### 3) Output Signal : ③

There are 14 definable output signals. However, just 2 signals of them can be connected with CN1 connector physically at one time.

The first signal '**COMP**' is used to specific purpose only. Therefore, other signals cannot be connected and used with this pin. The user can set up to 1 signal to Output 1 pin at one time. '**OUT1**' indicator is displayed to current setting signal.

When each signal is [ON] through CN1 connector, icon is changed into 'green'. When the signal is [OFF], it returns to 'white' to the original state.

### 4) Virtual Output Function :

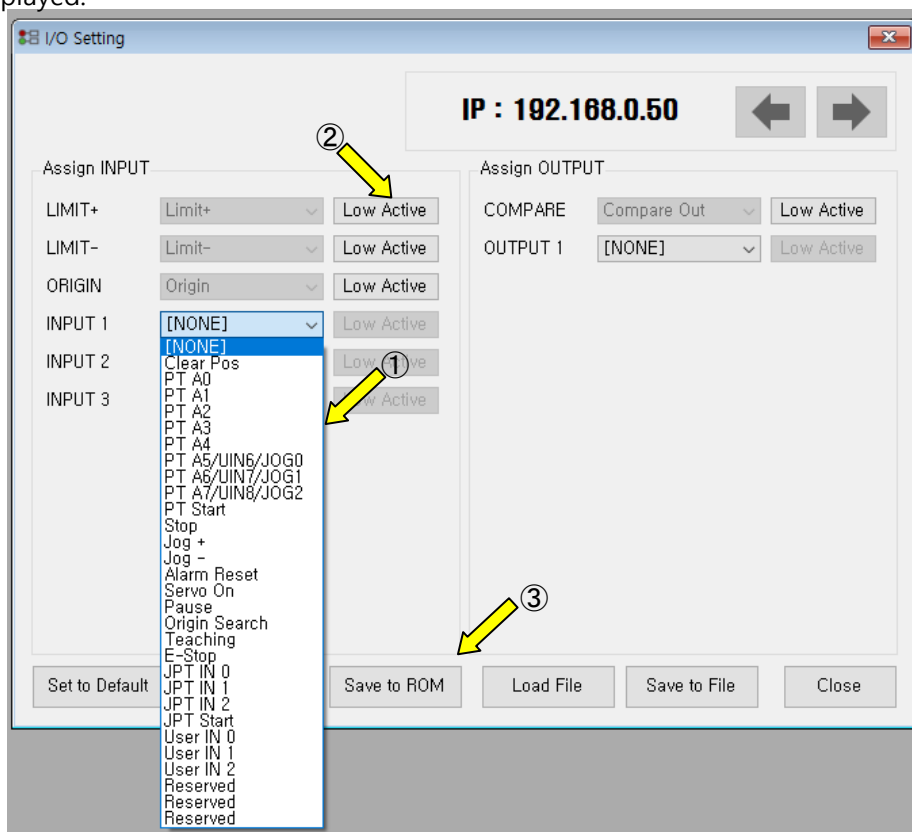
After assigning the 'User OUT 0' signal to 'OUT1', if you click the button, the signal changes ([ON]/[OFF]) through the pin.

### 5) I/O Logic Setting Button : ④

Assign the signal that the user wants to physical pin of CN1 connector, and display which defines 'Active Level' of that signal is executed.


## 4 - 1 . I/O Logic Setting

Click 'I/O Logic Setting' icon at the I/O Monitor window, and the following window will be displayed.



The assignment method of input and output is same and using as following.

### 1) Signal Assignment : ①

To change pin assignment of CN1 connector, click  button to the right of the corresponding signal name as showed above, and select signals will be displayed at the drop-down menu.

### 2) Signal Level Assignment : ②

These buttons provide the user with functions that user can select the active level of signal for the signal to be recognized to [ON]. User can click the button to the right of the signal name and set the signal.

- \* Low Active : When the signal is set[ON] to 0 volt.
- \* High Active : When the signal is set[ON] to 24 volt.

### 3) Save : ③



Output pin of CN1 can be set described same as input. All changed signals are temporarily saved to the RAM area. To save them to the ROM area, the user must click 'Save to ROM' button. At this time, **current parameter values are saved to the ROM** area as well.

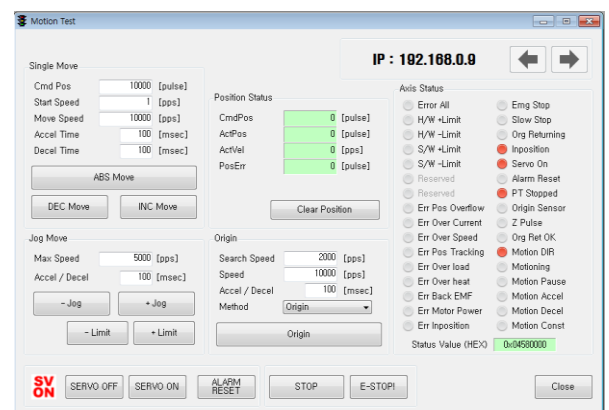
For more information of 'I/O Monitoring' and 'I/O Logic Setting' windows, refer to [「User Manual-Text 6. Control I/O Signal」](#).

## 5 . Motion Test


To test the motor connected with the controller drive. The user can test motion for one axis. User can test that the motor moves to the given position, and also simply transfer the motor to one direction. The user can move the motor to the origin or the limit and then test its sensor. At the position status and the axis status, the user can check the position, speed, and status of the current axis.

### 5 - 1 . Initial Movement

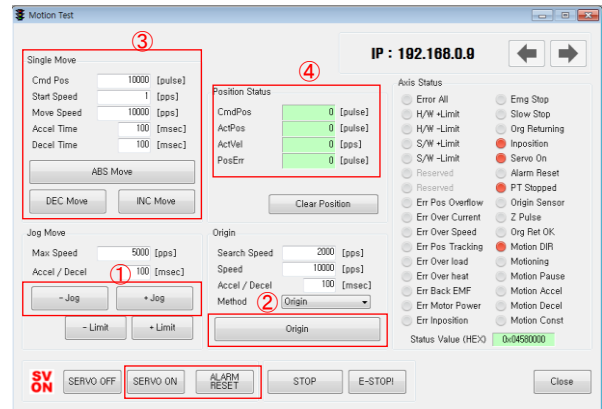
- 1) Click 「Motion Test」 at the main menu.
- 2) The window as shown to the right is displayed.
- 3) Select drive for test.
- 4) Click  and the motor will be Servo ON and the icon will be changed into  .  
At this time, the motor starts to be electrified and the motor becomes 'lock' status.




5) **Jog operation(①)**

After setting jog related parameters, click  and press it for a while, and the motor will be operated to the setting direction.

- 6) According to the motion of motor, the user can check its position and Refer to 「[User Manual-Text 8. Other Operation Functions](#)」.

7) **Origin Return operation(②)**

Click 「Origin」, origin return motion will be operated. The motion type may be different subject to how origin return type(parameter) is selected.

- 8) When origin return is finished, the red LED is displayed to ON like  Origin Search OK at the 'Axis Status' window. Refer to 「[User Manual-Text 8. Other Operation Functions](#)」.

9) **Single Move operation(③)**

The user can test straight-line move command for one axis. 'Abs Move' button moves to the absolute position, and 'DEC Move' and 'INC Move' move to the relative position.

\* Cmd Pos : Indicates target position value.

The unit is [pulse]. When 'Abs Move' is executed, this displays the absolute position. When 'DEC Move' or 'INC Move' is executed, this displays the relative position.

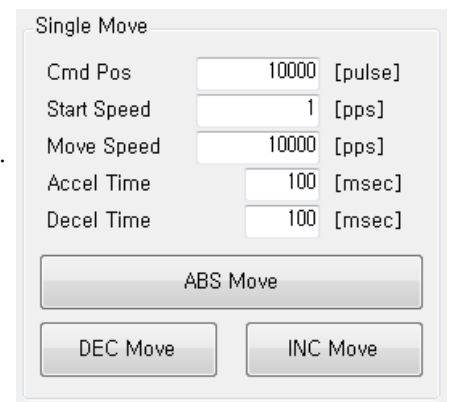
\* Start Speed : It is linked with parameter 2 Axis Start Speed.

If it is changed, the parameter value is also changed.

'Start Speed' should be smaller than 'Move Speed'.

\* Move Speed : It is for setting the movement speed when executing Abs Move, DEC Move, INC Move. 'Move Speed' should be larger than 'Start Speed'.

\* Accel Time, Decel Time : Parameter 3 and 4 Axis Accel and Axis Decel Time are linked with each other, If it is changed, the parameter value changes as well.



### 10) Position Status(④)

To displays the current position of axis. Click to Clear Position button, and Cmd Pos value and Actual Pos value will be initialized to '0'.

- \* Cmd Pos : It is the target position value during operation.
- \* Actual Pos : It is the current position value during operation.
- \* Actual Vel : The actual running speed of the current motor.
- \* Pos Error : The difference between the Cmd Pos value and the Actual Pos value.

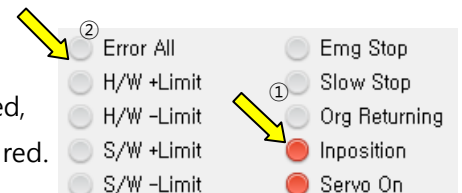
This value allows you to see how much you are following the current target position.

### 11) Axis Status and Alarm

To display the current axis status. Each status is displayed to ON/OFF.

'ON' indicates in red and 'OFF' indicates in gray.

- ① When the motor stops operation and Inposition is finished, the corresponding LED at the right figure is displayed in red.



- ② When an alarm occurs during operation, the corresponding LED is in red.

For more information of alarm types, refer to 「[User Manual-Text 6.4 Output signal](#)」.

- ③ After removing the alarm cause, click 'ALARM RESET' to check that the alarm is released. Then Servo ON again.



### 12) Stop operation

There are Pause, Stop, E-Stop commands for Stop operating.

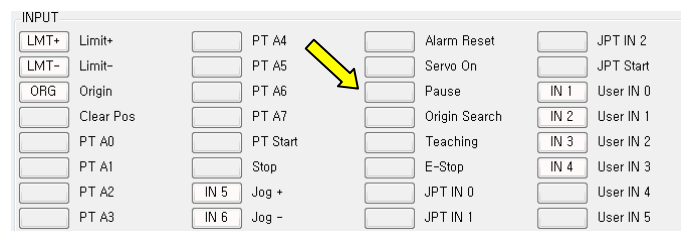
- ① Temporary stop (Pause)

Click 'Pause' button at the I/O Monitoring window to stop the motion temporarily.

When clicking the button again, the motor restarts to operate.

If 'Pause' signal is set to 'IN1~IN9',

the actual external signal must be supplied to [ON] status.



- ② Deceleration stop(Stop), Emergency stop(E-Stop)

When the motor needs to stop during operation, use the button as shown to the right on Motion Test window.



'STOP' button includes deceleration function and 'E-STOP' button does not include deceleration function.

## 5 - 2 . Multi Axes Motion Test

In one window, it is possible to monitor some of the Axis Status, Command Position, Actual Position, etc. of several axes connected, and Jog operation and position operation commands can be executed.

### 1) Available Axis Status

: Error, Servo On, Inposition, Motionning,  $\pm$ Limit Sensor, Origin Sensor

### 2) Move Command

:  $\pm$ Jog, Abs Move, Inc Move

The screenshot displays the 'Multi Axes Motion Test' software window. It features two side-by-side control panels for two different axes. The left panel is for axis '192,168,0,2' and the right panel is for axis '192,168,0,3'. Each panel includes a table of status indicators and a set of control buttons.

Parameter	Axis 1 (192,168,0,2)	Axis 2 (192,168,0,3)
ID / Name	192,168,0,2	192,168,0,3
Cmd Pos	0	0
Actual Pos	1	0
Error	<input type="checkbox"/>	<input type="checkbox"/>
Servo On	<input type="checkbox"/>	<input type="checkbox"/>
Inposition	<input type="checkbox"/>	<input type="checkbox"/>
Motioning	<input type="checkbox"/>	<input type="checkbox"/>
-L / ORG / +L	<input type="checkbox"/> <input type="checkbox"/> <input type="checkbox"/>	<input type="checkbox"/> <input type="checkbox"/> <input type="checkbox"/>
Jog Speed	5000	5000
	- Jog + Jog	- Jog + Jog
Position	10000	10000
Move Speed	10000	10000
Accel / Decel	100 100	100 2000
	DEC INC	DEC INC
	ABS	ABS
	STOP	STOP

## 5 - 3 . Function Test

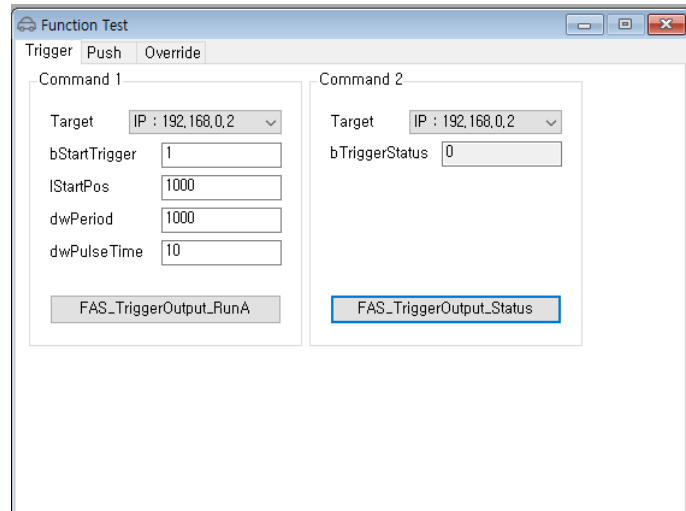
Trigger Pulse Output, Push Motion, Position Override, Velocity Override functions are executed.

### 1) Trigger

You can set the factor value of FAS\_TriggerOutput\_RunA() function and check the Trigger Status.

After setting the factor value of FAS\_TriggerOutput\_RunA() function, if you operate the motor with the position movement command (Abs Move or Inc Move) in Motion Test or Multi Axes Motion Test, Trigger Output is executed according to the setting.

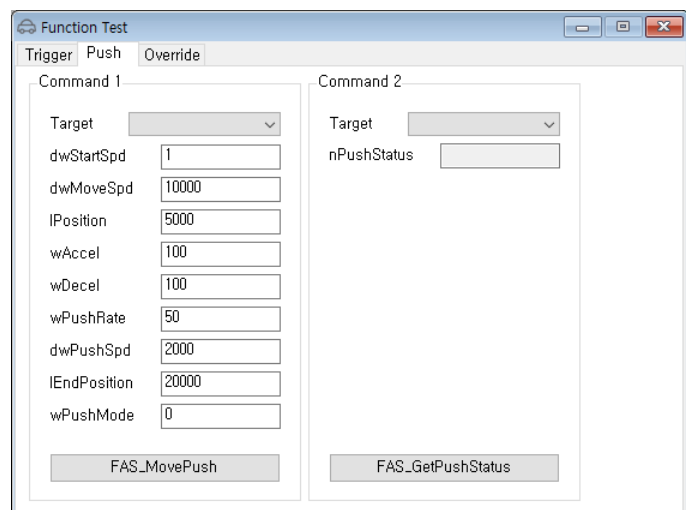
- A) Select Target.
- B) Enter each Item.
- C) Click FAS\_TriggerOutput\_RunA.
- D) Run move command  
in Motion Test or Multi Axes  
Motion Test.
- E) Click FAS\_TriggerOutput\_Status  
to check the status.



### 2) Push

FAS\_MovePush() function parameter value setting and function execution is possible, and push status can be checked.

- A) Select Target.
- B) Enter each Item.
- C) Click FAS\_MovePush.
- D) Click FAS\_GetPushStatus  
to check Push Move status.



### 3) Override

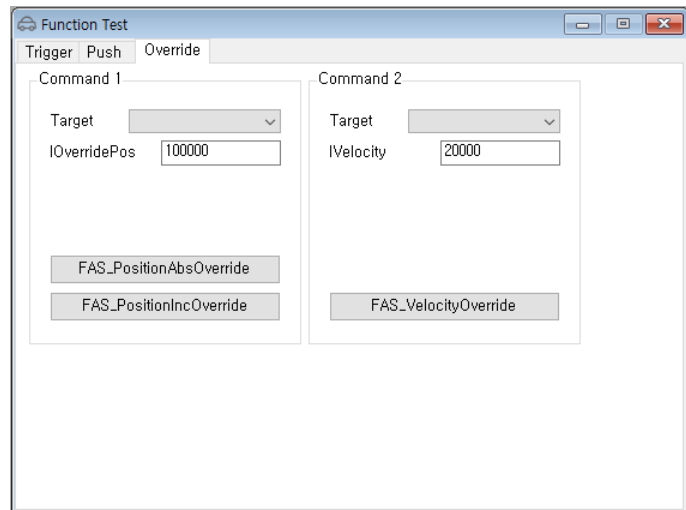
Position Override, Velocity Override can be executed.

### A) Position Override

- ① Select Target.
- ② Run Abs(Inc) Move at Motion Test.
- ③ Before motion is finished, click FAS\_PositionAbs(Inc)Override in Function Test – Override.

### B) Velocity Override

- ① Select Target.
- ② Run Abs(Inc) Move at Motion Test.
- ③ Before motion is finished, click FAS\_VelocityOverride in Function Test – Override.



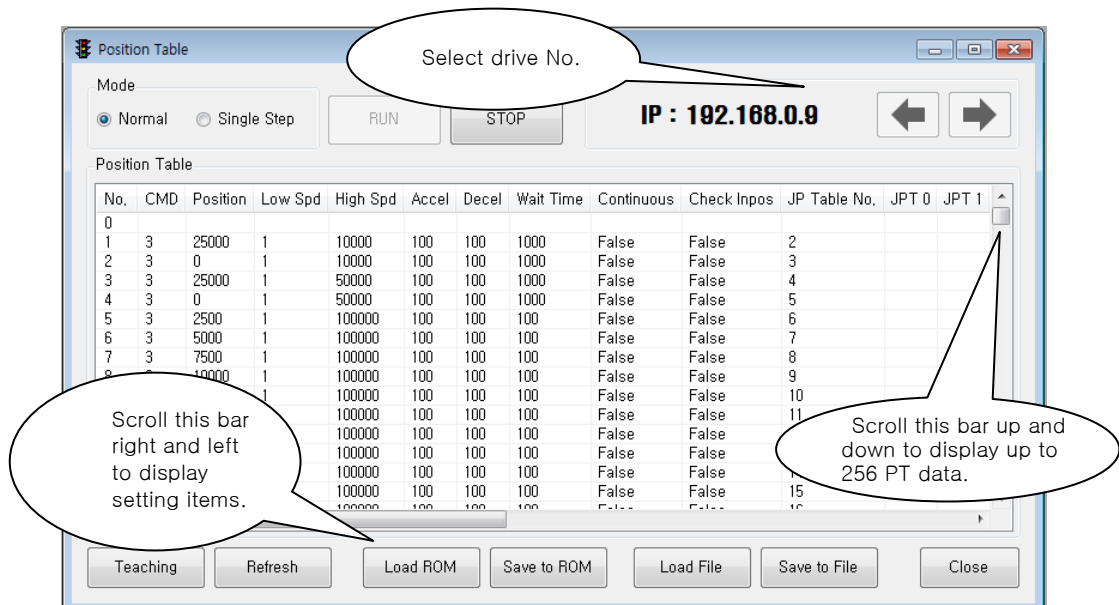
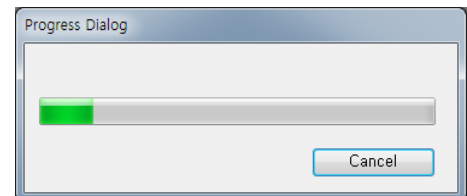
## 6 . Position Table (PT)

For more information of position table, refer to 「[User Manual-Position Table Function](#)」.

This chapter introduces its basic usage.

### 1) Reading position table data

Click 'Pos Table' icon at the main menu, and  
Data saved to the RAM area will be loaded  
and then the following window will be displayed.



Position table data can be changed at any time.

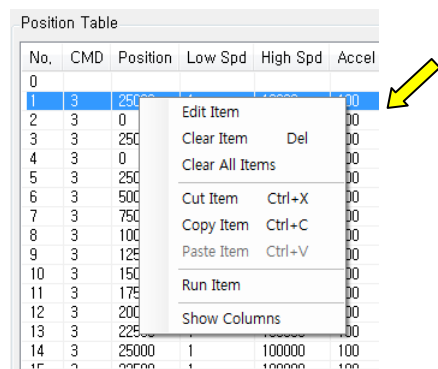
The position table can save up to 256 step data. If the position table is used to the program area, it can be used for all point numbers without restriction. In other words, it is possible to start at a random point number and jump to other point number.

### 2) Put the mouse on a specific PT data line,

click its right button, and the pop-up menu will be displayed as shown to the right.

All of the functions can be implemented.

Click 'Edit Item', and the user can edit data at the window like 3) below.





3) Put the mouse on a specific PT data line, double click its left key, and the right window will be displayed.

- \* Input the value in order from 'Command' related items according to operation modes.
- \* When all data of the positing table is completely input, click 'Save' button to save the data on RAM area.
- \* To edit the next position table, the user should use direction button.
- \* Refer to [「User Manual-Position Table Function」](#) for more detail information.

PT Item Editor

Command: ABS - Normal Motion

Motion: Jump PT Output

Position: 0 [pulse]

Low Speed: 1 [pps]

High Speed: 10000 [pps]

Accel Time: 100 [msec]

Decel Time: 100 [msec]

☐ Continuous

☐ Check Inposition

Waiting time after command: 1000 [msec]

Write Cancel

This data is saved to the RAM area. So, when power is off, data is deleted. Click 'Save to ROM' button for saving the data to the ROM area.

4) Set the motor to 'Servo ON' and select the mode 'Normal', click PT No to start motion, and then execute 'Run'.

Position Table

Mode: ☒ Normal ☐ Single Step

RUN STOP

IP : 192.168.0.9

No.	CMD	Position	Low Spd	High Spd	Accel	Decel	Wait Time	Continuous	Check Inpos	JP Table No.	JPT 0	JPT 1
0												
1	3	25000	1	10000	100	100	1000	False	False	2		
2	3	0	1	10000	100	100	1000	False	False	3		
3	3	25000	1	50000	100	100	1000	False	False	4		
4	3	0	1	50000	100	100	1000	False	False	5		
5	3	2500	1	100000	100	100	100	False	False	6		
6	3	5000	1	100000	100	100	100	False	False	7		
7	3	7500	1	100000	100	100	100	False	False	8		
8	3	10000	1	100000	100	100	100	False	False	9		
9	3	12500	1	100000	100	100	100	False	False	10		

Teaching Refresh Load ROM Save to ROM Load File Save to File Close

While PT No is operated in sequence, PT lines in service are changed in grey.



## **FASTECH Co., Ltd.**

Rm#1202, 401-dong, Bucheon Techno-Park,  
655, Pyeongcheon-ro, Bucheon-si Gyeonggi-do,  
Republic of Korea (Zip:14502)  
TEL : +82-32-234-6300 FAX : +82-32-234-6302  
E-mail : [fastech@fastech.co.kr](mailto:fastech@fastech.co.kr)  
Homepage : [www.fastech.co.kr](http://www.fastech.co.kr)

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