

CONTROLLER



MECQ1 Series

User Manual

Communication Funtion

202103


Table of Content

1.	Communication Protocols.....	3
1 - 1.	Communication Functions.....	3
1 - 1 - 1.	Communication Specifications.....	3
1 - 1 - 2.	RS-485 Communication Protocols	4
1 - 1 - 3.	CRC Calculation Example	5
1 - 1 - 4.	Response Frame Structure and Communication Error	7
1 - 2.	Structure of Frame type	8
1 - 2 - 1.	Frame type and Data configuration	8
1 - 2 - 2.	Parameter List.....	22
1 - 2 - 3.	Bit set up of Output pin	23
1 - 2 - 4.	Bit set up of input pin.....	24
1 - 2 - 5.	Bit set up of status flag	25
1 - 2 - 6.	Contents of position table.....	26
1 - 2 - 7.	Information of Motors.....	27
1 - 3.	Program Method.....	27
2.	Library for PC program.....	28
2 - 1.	Library configuration	28
2 - 2.	Communication status window	29
2 - 3.	Drive Link Function.....	34
2 - 4.	Parameter Control Function	43
2 - 5.	Servo Control Function.....	49
2 - 6.	Control I/O Function	53
2 - 7.	Position control Function.....	66
2 - 8.	Drive Status Control Function	77
2 - 9.	Running Control Function.....	83
2 - 1 0.	Position Table Control Function.....	111
2 - 1 1.	Other Control Function.....	120
3.	Protocol for PLC Program	126

1 . Communication Protocols

1 - 1 . Communication Functions

MECQ1 can control up to 16axes by Daisy-Chain link at RS-485 (2- wire).

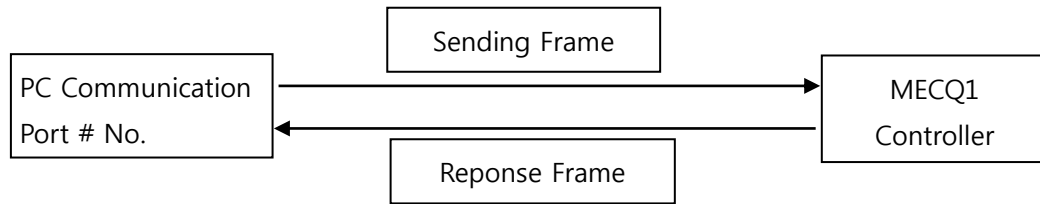
	<p>Pay attention that when Windows goes into standby or power-save mode, serial communication is basically disconnected. When the system is recovered from standby mode, it should be connected again with serial communication. This is also applicable to the library provided.</p>
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1 - 1 - 1 . Communication Specifications

Specification	RS-485
Communication Type	Asynchronous
	Half-duplex
baud rate [bps]	19200, 38400, 57600, 115200, 230400, 460800, 921600
Data Type	8bit ASCII code, HEX
Parity bit	No
stop bit	1bit
CRC Check	Yes
Max Cabling Length (Converter ↔ Drive)	30 m
Min Cable length between drive	More than 60 cm
Number of Connected Axes	16 axes (No. 0~F)

1 - 1 - 2 . RS-485 Communication Protocols

1) Overview of communication FRAME



2) Basic structure of FRAME

Header	Frame Data	Tail
0xAA 0xCC	4~252 bytes	0xAA 0xEE

- ① 0xAA : Delimited byte
- ② 0xAA 0xCC : Displays that the Frame locates in header.
- ③ 0xAA 0xEE : Displays that the Frame locates in tail.
- ④ If any of the Frame data is '0xAA', '0xAA' should be added right after it. (byte stuffing)
- ⑤ If any data following '0xAA' is not '0xAA', '0xCC' or '0xEE', it displays that an error has occurred.

Detailed **Frame Data** is configured as follows:

Slave ID	Frame type	Data	CRC	
1 byte	1 bytes	0 ~ 248 bytes.	2 bytes	
			Low byte	High byte

- ① Slave ID : Dive module number (0~15) connected to the PC communication port.
- ② Frame type : To designate command type of relevant frames. For the command type, refer to 「Frame Type and Data Configuration」section.
- ③ Data : Data structure and length is set according to Frame type. For more information, refer to 「Frame Type and Data Configuration」section.
- ④ CRC : To check that an error occurs during communication, '0xA001' of a polynomial factor in **CRC16(Cyclic Redundancy Check)** is used. Or 'X¹⁶+X¹⁵+X²+1' of a polynomial factor in CRC-16-IBM(Cyclic Redundancy Check) is used. CRC calculation is performed for all items (Slave ID, Frame type, Data) prior to CRC item.

1 - 1 - 3 . CRC Calculation Example

The following program source is included in a file (file name : CRC_Checksum.c) provided with the product.

1) The use of '0xA001' of CRC16

```

const unsigned short TABLE_CRCVALUE[] =
{
    0X0000, 0XC0C1, 0XC181, 0X0140, 0XC301, 0X03C0, 0X0280, 0XC241,
    0XC601, 0X06C0, 0X0780, 0XC741, 0X0500, 0XC5C1, 0XC481, 0X0440,
    0XCC01, 0X0CC0, 0X0D80, 0XCD41, 0X0F00, 0XCFC1, 0XCE81, 0X0E40,
    0X0A00, 0XCAC1, 0XCB81, 0X0B40, 0XC901, 0X09C0, 0X0880, 0XC841,
    0XD801, 0X18C0, 0X1980, 0XD941, 0X1B00, 0XDBC1, 0XDA81, 0X1A40,
    0X1E00, 0XDEC1, 0XDF81, 0X1F40, 0XDD01, 0X1DC0, 0X1C80, 0XDC41,
    0X1400, 0XD4C1, 0XD581, 0X1540, 0XD701, 0X17C0, 0X1680, 0XD641,
    0XD201, 0X12C0, 0X1380, 0XD341, 0X1100, 0XD1C1, 0XD081, 0X1040,
    0XF001, 0X30C0, 0X3180, 0XF141, 0X3300, 0XF3C1, 0XF281, 0X3240,
    0X3600, 0XF6C1, 0XF781, 0X3740, 0XF501, 0X35C0, 0X3480, 0XF441,
    0X3C00, 0XFCC1, 0XFD81, 0X3D40, 0XFF01, 0X3FC0, 0X3E80, 0XFE41,
    0XFA01, 0X3AC0, 0X3B80, 0XFB41, 0X3900, 0XF9C1, 0XF881, 0X3840,
    0X2800, 0XE8C1, 0XE981, 0X2940, 0XEB01, 0X2BC0, 0X2A80, 0XEA41,
    0XEE01, 0X2EC0, 0X2F80, 0XEF41, 0X2D00, 0XEDC1, 0XEC81, 0X2C40,
    0XE401, 0X24C0, 0X2580, 0XE541, 0X2700, 0XE7C1, 0XE681, 0X2640,
    0X2200, 0XE2C1, 0XE381, 0X2340, 0XE101, 0X21C0, 0X2080, 0XE041,
    0XA001, 0X60C0, 0X6180, 0XA141, 0X6300, 0XA3C1, 0XA281, 0X6240,
    0X6600, 0XA6C1, 0XA781, 0X6740, 0XA501, 0X65C0, 0X6480, 0XA441,
    0X6C00, 0XACC1, 0XAD81, 0X6D40, 0XAF01, 0X6FC0, 0X6E80, 0XAE41,
    0XAA01, 0X6AC0, 0X6B80, 0XAB41, 0X6900, 0XA9C1, 0XA881, 0X6840,
    0X7800, 0XB8C1, 0XB981, 0X7940, 0XBB01, 0X7BC0, 0X7A80, 0XBA41,
    0XBE01, 0X7EC0, 0X7F80, 0XBF41, 0X7D00, 0XBDC1, 0XBC81, 0X7C40,
    0XB401, 0X74C0, 0X7580, 0XB541, 0X7700, 0XB7C1, 0XB681, 0X7640,
    0X7200, 0XB2C1, 0XB381, 0X7340, 0XB101, 0X71C0, 0X7080, 0XB041,
    0X5000, 0X90C1, 0X9181, 0X5140, 0X9301, 0X53C0, 0X5280, 0X9241,
    0X9601, 0X56C0, 0X5780, 0X9741, 0X5500, 0X95C1, 0X9481, 0X5440,
    0X9C01, 0X5CC0, 0X5D80, 0X9D41, 0X5F00, 0X9FC1, 0X9E81, 0X5E40,
    0X5A00, 0X9AC1, 0X9B81, 0X5B40, 0X9901, 0X59C0, 0X5880, 0X9841,
    0X8801, 0X48C0, 0X4980, 0X8941, 0X4B00, 0X8BC1, 0X8A81, 0X4A40,
    0X4E00, 0X8EC1, 0X8F81, 0X4F40, 0X8D01, 0X4DC0, 0X4C80, 0X8C41,
    0X4400, 0X84C1, 0X8581, 0X4540, 0X8701, 0X47C0, 0X4680, 0X8641,
    0X8201, 0X42C0, 0X4380, 0X8341, 0X4100, 0X81C1, 0X8081, 0X4040
};

unsigned short CalcCRC(unsigned char* pDataBuffer, unsigned long usDataLen)
{
    unsigned char nTemp;
    unsigned short wCRCWord = 0xFFFF;

```

```

while (usDataLen--)
{
    nTemp = wCRCWord ^ *(pDataBuffer++);
    wCRCWord >>= 8;
    wCRCWord ^= TABLE_CRCVALUE[nTemp];
}
return wCRCWord;
}

```

2) Use of 'X16+X15+X2+1' of CRC-16-IBM

```

unsigned short CalcCRCbyAlgorithm(unsigned char* pDataBuffer, unsigned long usDataLen)
{
    const unsigned short POLYNOMIAL = 0xA001;
    unsigned short wCrc;
    int iByte, iBit;

    /* Initialize CRC */
    wCrc = 0xffff;

    for (iByte = 0; iByte < usDataLen; iByte++)
    {
        /* Exclusive-OR the byte with the CRC */
        wCrc ^= *(pDataBuffer + iByte);

        /* Loop through all 8 data bits */

        for (iBit = 0; iBit <= 7; iBit++)
        {
            /* If the LSB is 1, shift the CRC and XOR the polynomial mask with the CRC */

            // Note - the bit test is performed before the rotation, so can't move the << here
            if (wCrc & 0x0001)
            {
                wCrc >>= 1;
                wCrc ^= POLYNOMIAL;
            }
            else
            {
                // Just rotate it
                wCrc >>= 1;
            }
        }
    }
    return wCrc;
}

```

1 - 1 - 4 . Response Frame Structure and Communication Error

When any command is sent, the basic structure of Frame at the response side is same. However, there is a difference in case of **Frame Data**, which 'communication status' is added as shown below.

Slave ID	Frame type	Data		CRC	
1 byte	1 byte	1 byte	0 ~ 247bytes	2 bytes	
		Communication status	Response data	Low byte	High byte

- ① Slave ID : Same to sending Frame.
(When this is not same to sending data, it should be recognized as the error status.)
- ② Frame type : Same to sending Frame.
(When this is not same to sending data, it should be recognized as the error status.)
- ③ Data : When simple executive instructions are sent, this data cannot be read. However, in case of response, 1 byte is added to display the communication status (error / normal).

The code by **bytes means the 'Communication status'** as follows.

Hexa Code	Decimal Code	Description
0x00	0	Communication is normal.
0x80	128	Frame Type Error : Responded Frame type cannot be recognized.
0x81	129	Data error, ROM data read/write error : Data value responded is without the given range.
0x82	130	Received Frame Error : Frame data received is out of this specification.
0x85	133	Running Command Failure : The user has tried to execute new running commands in wrong condition as follows. 1) currently motor is running 2) currently motor is stopping 3) currently Servo is OFF status 4) try to Z-pulse Origin without encoder 5) other wrong motion command
0x86	134	RESET Failure : The user has tried to execute new running commands in wrong condition as follows. 1) While the servo is ON 2) Already RESET in ON by external input signal
0x87	135	Servo ON Failure ① : While an alarm occurs, the user has tried to execute Servo ON command.
0x88	136	Servo ON Failure ② : While Emergency Stop occurs, the user has tried to execute Servo ON command.
0x89	137	Servo ON Failure ③ : 'ServoON' signal is assigned to input pin already. Servo ON/OFF Can execute by external input signal only.
0xAA	170	CRC Error : Frame data received is out of CRC format. In this case, DLL Library of sending side automatically try to send 1 more time.

	1) If 'Header' and 'Slave ID' values in the sending Frame are abnormal, there is no response from the drive.
--	---



2) If the communication status is displayed to '130', the size of response data is '0' byte.

1 - 2 . Structure of Frame type

1 - 2 - 1 . Frame type and Data configuration

(1) The following table displays the content and configuration of data by Frame type.

Frame type	Library Name	Contents						
0x01 (1)	FAS_ GetSlaveInfo	<p>Connected slave type and program version information are required.</p> <p>Sending : 0 byte Response : 1~248 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>1 bytes</td> <td>0~246 bytes</td> </tr> <tr> <td>Communication status</td> <td>Slave type</td> <td>ACII string with NULL byte (strlen() + 1 bytes)</td> </tr> </table> <p>◆ Slave type : 102 : MECQ1</p>	1 byte	1 bytes	0~246 bytes	Communication status	Slave type	ACII string with NULL byte (strlen() + 1 bytes)
1 byte	1 bytes	0~246 bytes						
Communication status	Slave type	ACII string with NULL byte (strlen() + 1 bytes)						
0x05 (5)	FAS_ GetMotorInfo	<p>Connected motor type and maker information are required.</p> <p>Sending : 0 byte Response : 1~248 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>1 bytes</td> <td>0~246 bytes</td> </tr> <tr> <td>Communication status</td> <td>Motor type (1~255)</td> <td>ACII string with NULL byte (strlen() + 1 bytes)</td> </tr> </table> <p>◆ Motor type : refer to 「1-1-7.Information of Motors」</p>	1 byte	1 bytes	0~246 bytes	Communication status	Motor type (1~255)	ACII string with NULL byte (strlen() + 1 bytes)
1 byte	1 bytes	0~246 bytes						
Communication status	Motor type (1~255)	ACII string with NULL byte (strlen() + 1 bytes)						
0x10 (16)	FAS_ SaveAllParameters	<p>Current setting parameters & assign of IO signals are saved in the ROM of the drive. Even though the drive is powered off, saving these must be possible.</p> <p>Values set at 'FAS_SetParameter' & 'FAS_SetIOAssignMap' are saved together.</p> <p>Sending : 0 byte Response : 1 byte</p> <table border="1"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	Communication status				
1 byte								
Communication status								

<p>0x11 (17)</p>	<p>FAS_ GetRomParameter</p>	<p>Specific parameter values in the ROM are read.</p> <p>Sending : 1 byte</p> <table border="1" data-bbox="584 264 932 360"> <tr> <td>1 byte</td> </tr> <tr> <td>Parameter number (0~31)</td> </tr> </table> <p>Response : 5 bytes</p> <table border="1" data-bbox="584 434 1085 512"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Parameter value</td> </tr> </table> <p>Refer to 「1-2-2.Parameter List」</p>	1 byte	Parameter number (0~31)	1 byte	4 bytes	Communication status	Parameter value
1 byte								
Parameter number (0~31)								
1 byte	4 bytes							
Communication status	Parameter value							
<p>0x12 (18)</p>	<p>FAS_ SetParameter</p>	<p>Specific parameter values are saved to the RAM.</p> <p>Sending : 5 bytes</p> <table border="1" data-bbox="584 703 1208 808"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Parameter number (0~31)</td> <td>Parameter value</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 887 900 965"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table> <p>Refer to 「1-2-2.Parameter List」</p>	1 byte	4 bytes	Parameter number (0~31)	Parameter value	1 byte	Communication status
1 byte	4 bytes							
Parameter number (0~31)	Parameter value							
1 byte								
Communication status								
<p>0x13 (19)</p>	<p>FAS_ GetParameter</p>	<p>Specific parameter values in the RAM are read</p> <p>Sending : 1 byte</p> <table border="1" data-bbox="584 1155 868 1274"> <tr> <td>1 byte</td> </tr> <tr> <td>Parameter number (0~32)</td> </tr> </table> <p>Response : 5 bytes</p> <table border="1" data-bbox="584 1330 1085 1408"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Parameter value</td> </tr> </table> <p>Refer to 「1-2-2.Parameter List」</p>	1 byte	Parameter number (0~32)	1 byte	4 bytes	Communication status	Parameter value
1 byte								
Parameter number (0~32)								
1 byte	4 bytes							
Communication status	Parameter value							
<p>0x20 (32)</p>	<p>FAS_ SetIOOutput</p>	<p>Output signal level of the control output port is set.</p> <p>Sending : 8 bytes</p> <table border="1" data-bbox="584 1599 1106 1657"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>I/O set mask value</td> <td>I/O clear mask value</td> </tr> </table> <p>When specific bit of the set mask is '1', the relevant output port signal is set to [ON]. When specific bit of the clear mask is '1', the relevant output port signal is set to [OFF]. For more information, refer to 「1-2-3.Bit setup of Output Pin」.</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1924 876 1984"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	4 bytes	I/O set mask value	I/O clear mask value	1 byte	Communication status
4 bytes	4 bytes							
I/O set mask value	I/O clear mask value							
1 byte								
Communication status								

<p>0x21 (33)</p>	<p>FAS_ SetIOInput</p>	<p>Input signal level of the control input port is set.</p> <p>Sending : 8 bytes</p> <table border="1" data-bbox="584 264 1070 322"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>I/O set mask value</td> <td>I/O clear mask value</td> </tr> </table> <p>When specific bit of the set mask is '1', the relevant input port signal is set to [ON]. When specific bit of the clear mask is '1', the relevant input port signal is set to [OFF]. For more information, refer to 「1-2-4. Bit setup of Input Pin」.</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 593 865 651"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	4 bytes	I/O set mask value	I/O clear mask value	1 byte	Communication status		
4 bytes	4 bytes									
I/O set mask value	I/O clear mask value									
1 byte										
Communication status										
<p>0x22 (34)</p>	<p>FAS_ GetIOInput</p>	<p>Current input signal status of the control input port is read.</p> <p>Sending : 0 byte Response : 5 byte</p> <table border="1" data-bbox="584 786 1129 844"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Input status value</td> </tr> </table> <p>Relevant bit by each input signal, refer to 「1-2-4. Bit setup of Input Pin」</p>	1 byte	4 bytes	Communication status	Input status value				
1 byte	4 bytes									
Communication status	Input status value									
<p>0x23 (35)</p>	<p>FAS_ GetIOOutput</p>	<p>Current output signal status of the control output port is read.</p> <p>Sending : 0 byte Response : 5 byte</p> <table border="1" data-bbox="584 1048 1091 1128"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Output status value</td> </tr> </table> <p>Relevant bit by each output signal, refer to 「1-2-3.Bit setup of Output Pin」.</p>	1 byte	4 bytes	Communication status	Output status value				
1 byte	4 bytes									
Communication status	Output status value									
<p>0x24 (36)</p>	<p>FAS_ SetIOAssignMap</p>	<p>To assign control I/O signals to the pin of CN1 port and set the signal level. By running 'FAS_SaveAllParameters', you can save the setting value to the ROM.</p> <p>Sending : 6 bytes</p> <table border="1" data-bbox="584 1368 1259 1426"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>1 byte</td> </tr> <tr> <td>I/O number</td> <td>I/O pin masking data</td> <td>Setting level</td> </tr> </table> <ul style="list-style-type: none"> ◆I/O number: '0~11' corresponds to 'Limit+, Limit-, Org, IN1, ..., IN9' respectively, and '12~22' corresponds to 'COMP, OUT1, ..., OUT9' respectively. ◆I/O pin masking data: Refer to 「1-2-4. Bit setup of Input Pin」. ◆Level Setting: 0:Active Low, 1:Active High <p>Response : 1 byte</p> <table border="1" data-bbox="584 1666 865 1724"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	4 bytes	1 byte	I/O number	I/O pin masking data	Setting level	1 byte	Communication status
1 byte	4 bytes	1 byte								
I/O number	I/O pin masking data	Setting level								
1 byte										
Communication status										
<p>0x25 (37)</p>	<p>FAS_ GetIOAssignMap</p>	<p>Pin setting status of CN1 port is read from RAM area.</p> <p>Sending : 1 byte</p> <table border="1" data-bbox="584 1973 834 2054"> <tr> <td>1 byte</td> </tr> <tr> <td>I/O number</td> </tr> </table> <ul style="list-style-type: none"> ◆I/O number: '0~11' corresponds to 'Limit+, Limit-, Org, IN1, ..., IN9' 	1 byte	I/O number						
1 byte										
I/O number										

		<p>respectively, and '12~22' corresponds to 'COMP, OUT1, ..., OUT9' respectively.</p> <p>Response : 6 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>IO pin masking status</td> <td>Level status</td> </tr> </table> <p>For more information, refer to '0x24'Frame type.</p>	1 byte	4 bytes	1 byte	Communication status	IO pin masking status	Level status										
1 byte	4 bytes	1 byte																
Communication status	IO pin masking status	Level status																
0x26 (38)	FAS_ IOAssignMapReadR OM	<p>Pin setting status of CN1 port is loaded to RAM from ROM area.</p> <p>Sending : 0 byte</p> <p>Response : 2 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (0 : complete, values except 0: error)</td> </tr> </table>	1 byte	1 byte	Communication status	Command performing status (0 : complete, values except 0: error)												
1 byte	1 byte																	
Communication status	Command performing status (0 : complete, values except 0: error)																	
0x27 (39)	FAS_ TriggerOutput_Run A	<p>Start/Stop command for 'Compare Out' signal</p> <p>Sending : 18 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>4 byte</td> </tr> <tr> <td>Output start/stop (1:start 0:stop)</td> <td>Pulse start position [pulse]</td> <td>Pulse period [pulse]</td> </tr> </table> <table border="1"> <tr> <td>4 byte</td> <td>1 bytes</td> <td>4 byte</td> </tr> <tr> <td>Pulse width [msec]</td> <td>Output pin number (fix to 0)</td> <td>spare</td> </tr> </table> <ul style="list-style-type: none"> ◆ Pulse start position: Setting the start position of first pulse output. (-134,217,727 ~134,217,727) ◆ Pulse period: Setting the pulse period. (1 ~134,217,727) (0: pulse output only 1 time in pulse start position 1~ : pulse output repeatedly depends on setting) ◆ Pulse width: Setting the pulse width. (1~1000) <p>Response : 2 byte</p> <table border="1"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (0 : complete, values except 0: error)</td> </tr> </table>	1 byte	4 bytes	4 byte	Output start/stop (1:start 0:stop)	Pulse start position [pulse]	Pulse period [pulse]	4 byte	1 bytes	4 byte	Pulse width [msec]	Output pin number (fix to 0)	spare	1 byte	1 byte	Communication status	Command performing status (0 : complete, values except 0: error)
1 byte	4 bytes	4 byte																
Output start/stop (1:start 0:stop)	Pulse start position [pulse]	Pulse period [pulse]																
4 byte	1 bytes	4 byte																
Pulse width [msec]	Output pin number (fix to 0)	spare																
1 byte	1 byte																	
Communication status	Command performing status (0 : complete, values except 0: error)																	

0x28 (40)	FAS_ TriggerOutput_ Status	<p>Command to check if the trigger output pulse is working or not.</p> <p>Sending : 0 byte</p> <p>Response : 2 byte</p> <table border="1"> <tr> <td>1 byte</td> <td>1 bytes</td> </tr> <tr> <td>Communication status</td> <td>Status (1:output ON, 0 :output OFF)</td> </tr> </table>	1 byte	1 bytes	Communication status	Status (1:output ON, 0 :output OFF)
1 byte	1 bytes					
Communication status	Status (1:output ON, 0 :output OFF)					

<p>0x2A (42)</p>	<p>FAS_ ServoEnable</p>	<p>Servo ON/OFF status is set.</p> <p>Sending : 1 byte</p> <table border="1" data-bbox="584 271 836 349"> <tr><td>1 byte</td></tr> <tr><td>0:OFF, 1:ON</td></tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 416 858 495"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	1 byte	0:OFF, 1:ON	1 byte	Communication status
1 byte						
0:OFF, 1:ON						
1 byte						
Communication status						
<p>0x2B (43)</p>	<p>FAS_ ServoAlarmReset</p>	<p>Servo alarm status is reset.</p> <p>Sending : 0 byte</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 633 871 712"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	1 byte	Communication status		
1 byte						
Communication status						
<p>0x2E (46)</p>	<p>FAS_ GetAlarmType</p>	<p>To request the Alarm type</p> <p>Sending: 0 byte</p> <p>Response: 2 byte</p> <table border="1" data-bbox="584 842 1155 920"> <tr> <td>1 byte</td> <td>1 bytes</td> </tr> <tr> <td>Communication status</td> <td>Alarm type (1~)</td> </tr> </table> <p>◆ Alarm type: No alarm (0) OverCurrent(1) OverSpeed(2) StepOut(3) OverLoad(4) OverTemperature(5) BackEMF(6) MotorConnect(7) EncoderConnect(8) MotorPower(9) Inposition(10) SystemHalt(11) ROMdevice(12) OverInputVoltage(14) Position Overflow(15)</p>	1 byte	1 bytes	Communication status	Alarm type (1~)
1 byte	1 bytes					
Communication status	Alarm type (1~)					
<p>0x31 (49)</p>	<p>FAS_ MoveStop</p>	<p>To request to stop running the motor</p> <p>Sending : 0 byte</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1440 882 1518"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	1 byte	Communication status		
1 byte						
Communication status						
<p>0x32 (50)</p>	<p>FAS_ EmergencyStop</p>	<p>To request the running motor to stop emergently</p> <p>Sending : 0 byte</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1722 887 1800"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	1 byte	Communication status		
1 byte						
Communication status						

<p>0x33 (51)</p>	<p>FAS_ MoveOriginSingle Axis</p>	<p>To request the motor to return to the origin at the current setting parameter condition</p> <p>Sending : 0 byte Response : 1 byte</p> <table border="1" data-bbox="584 338 863 405"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	Communication status				
1 byte								
Communication status								
<p>0x34 (52)</p>	<p>FAS_ MoveSingleAxisAbs Pos</p>	<p>To request the motor to move its position as much as the absolute value[pulse]</p> <p>Sending : 8 bytes</p> <table border="1" data-bbox="584 555 1139 656"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Absolute position value</td> <td>Running speed [pps]</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 730 868 797"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	4 bytes	Absolute position value	Running speed [pps]	1 byte	Communication status
4 bytes	4 bytes							
Absolute position value	Running speed [pps]							
1 byte								
Communication status								
<p>0x35 (53)</p>	<p>FAS_ MoveSingleAxisIncPos</p>	<p>To request the motor to move its position as much as the incremental value[pulse]</p> <p>Sending : 8 bytes</p> <table border="1" data-bbox="584 931 1139 1032"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Incremental position value</td> <td>Running speed [pps]</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1106 868 1173"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	4 bytes	Incremental position value	Running speed [pps]	1 byte	Communication status
4 bytes	4 bytes							
Incremental position value	Running speed [pps]							
1 byte								
Communication status								
<p>0x36 (54)</p>	<p>FAS_ MoveToLimit</p>	<p>To request the motor to start limit motion at the current setting parameter condition</p> <p>Sending : 5 bytes</p> <table border="1" data-bbox="584 1350 1334 1451"> <tr> <td>4 bytes</td> <td>1 byte</td> </tr> <tr> <td>Running speed [pps]</td> <td>Running direction (0: -Limit 1: +Limit)</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1525 868 1592"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	1 byte	Running speed [pps]	Running direction (0: -Limit 1: +Limit)	1 byte	Communication status
4 bytes	1 byte							
Running speed [pps]	Running direction (0: -Limit 1: +Limit)							
1 byte								
Communication status								
<p>0x37 (55)</p>	<p>FAS_ MoveVelocity</p>	<p>To request the motor to start jog motion at the current setting parameter condition</p> <p>Sending : 5 bytes</p> <table border="1" data-bbox="584 1731 1342 1832"> <tr> <td>4 bytes</td> <td>1 byte</td> </tr> <tr> <td>Running speed [pps]</td> <td>Running direction (0: -Jog 1: +Jog)</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1906 890 1973"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	1 byte	Running speed [pps]	Running direction (0: -Jog 1: +Jog)	1 byte	Communication status
4 bytes	1 byte							
Running speed [pps]	Running direction (0: -Jog 1: +Jog)							
1 byte								
Communication status								

<p>0x38 (56)</p>	<p>FAS_ PositionAbsOverride</p>	<p>To request the motor to change the target absolute position value[pulse] while it is in running.</p> <p>Sending : 4 bytes</p> <table border="1" data-bbox="584 309 1074 376"> <tr><td>4 bytes</td></tr> <tr><td>Changed command position value [pulse]</td></tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 450 877 517"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	4 bytes	Changed command position value [pulse]	1 byte	Communication status
4 bytes						
Changed command position value [pulse]						
1 byte						
Communication status						
<p>0x39 (57)</p>	<p>FAS_ PositionIncOverride</p>	<p>To request the motor to change the target incremental position value[pulse] while it is in running.</p> <p>Sending : 4 bytes</p> <table border="1" data-bbox="584 730 1090 813"> <tr><td>4 bytes</td></tr> <tr><td>Changed command position value [pulse]</td></tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 887 884 965"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	4 bytes	Changed command position value [pulse]	1 byte	Communication status
4 bytes						
Changed command position value [pulse]						
1 byte						
Communication status						
<p>0x3A (58)</p>	<p>FAS_ VelocityOverride</p>	<p>To request the motor to change the running speed value[pps] while it is in running.</p> <p>Sending : 4 bytes</p> <table border="1" data-bbox="584 1077 979 1160"> <tr><td>4 bytes</td></tr> <tr><td>Changed running speed [pps]</td></tr> </table> <p>The accel/decel time is assigned to 'Axis Acc Time' and 'Axis Dec Time' value in parameter lists.</p> <p>Response : 1 byte</p> <table border="1" data-bbox="584 1301 896 1384"> <tr><td>1 byte</td></tr> <tr><td>Communication status</td></tr> </table>	4 bytes	Changed running speed [pps]	1 byte	Communication status
4 bytes						
Changed running speed [pps]						
1 byte						
Communication status						
<p>0x3B (59)</p>	<p>FAS_ AllMoveStop</p>	<p>To request stop for all motor that connected in same port.</p> <p>Sending : 0 byte (Slave number must be '99')</p> <p>Response : No response (It can not be receivedresponse from all Slave at the same time, So all Slaves are not sending the response)</p>				
<p>0x3C (60)</p>	<p>FAS_ AllEmergencyStop</p>	<p>To request emergency stop for all motor that connected in same port.</p> <p>Sending : 0 byte (Slave number must be '99')</p> <p>Response : No response (It can not be receivedresponse from all Slave at the same time, So all Slaves are not sending the response)</p>				

<p>0x3D (61)</p>	<p>FAS_All MoveOriginSingle Axis</p>	<p>To request return to the origin at the current setting parameter condition for all motors that connected in same port.</p> <p>Sending : 0 byte (Slave number must be '99')</p> <p>Response : no response (It can not be receivedresponse from all Slave at the same time, So all Slaves are not sending the response)</p>												
<p>0x3E (62)</p>	<p>FAS_All SingleAxisAbsPos</p>	<p>To request move its position as much as the absolute value[pulse] for all motors that connected in same port.</p> <p>Sending : 8 bytes (Slave number must be '99')</p> <table border="1" data-bbox="584 600 1139 701"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Absolute position value</td> <td>Running speed [pps]</td> </tr> </table> <p>Response : no response (It can not be received response from all Slave at the same time, so all slaves are not sending the response)</p>	4 bytes	4 bytes	Absolute position value	Running speed [pps]								
4 bytes	4 bytes													
Absolute position value	Running speed [pps]													
<p>0x3F (63)</p>	<p>FAS_All SingleAxisIncPos</p>	<p>To request move its position as much as the incremental value[pulse] for all motors that connected in same port.</p> <p>Sending : 8 bytes (Slave number must be '99')</p> <table border="1" data-bbox="584 1025 1209 1093"> <tr> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>incremental position value</td> <td>Running speed [pps]</td> </tr> </table> <p>Response : no response (It can not be receivedresponse from all Slave at the same time, so all slaves are not sending the response)</p>	4 bytes	4 bytes	incremental position value	Running speed [pps]								
4 bytes	4 bytes													
incremental position value	Running speed [pps]													
<p>0x80 (128)</p>	<p>FAS_ MoveSingleAxisAbs PosEx</p>	<p>Request the motor to move its position as much as the absolute value[pulse] with Custom Accel. / Decel. Time[msec]</p> <p>Sending: 40 bytes</p> <table border="1" data-bbox="584 1417 1382 1570"> <tr> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>2 bytes</td> </tr> <tr> <td>Absolute position value</td> <td>Running speed [pps]</td> <td>Flag option</td> <td>Custom Accel. Time (1~9999)</td> </tr> </table> <table border="1" data-bbox="584 1641 1002 1753"> <tr> <td>2 bytes</td> <td>24 bytes</td> </tr> <tr> <td>Custom Decel. Time (1~9999)</td> <td>Reserved</td> </tr> </table> <p>Flag option : 0x0001 : reserved 0x0002 : Custom Accel. Time is used. 0x0004 : Custom Decel. Time is used.</p> <p>If the Flag bit is OFF status(0), Accel./Decel. Time value is used that saved in controller.</p> <p>Response: 1 byte</p>	4 bytes	4 bytes	4 bytes	2 bytes	Absolute position value	Running speed [pps]	Flag option	Custom Accel. Time (1~9999)	2 bytes	24 bytes	Custom Decel. Time (1~9999)	Reserved
4 bytes	4 bytes	4 bytes	2 bytes											
Absolute position value	Running speed [pps]	Flag option	Custom Accel. Time (1~9999)											
2 bytes	24 bytes													
Custom Decel. Time (1~9999)	Reserved													

<p>0x81 (129)</p>	<p>FAS_ MoveSingle AxisIncPosEx</p>	<p>Request the motor to move its position as much as the absolute value [pulse] with Custom Accel. / Decel. Time[msec]</p> <p>Sending: 40 bytes</p> <table border="1" data-bbox="584 324 1382 443"> <tr> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>2 bytes</td> </tr> <tr> <td>incremental position value</td> <td>Running speed [pps]</td> <td>Flag option</td> <td>Custom Accel. Time (1~9999)</td> </tr> </table> <table border="1" data-bbox="584 510 1002 629"> <tr> <td>2 bytes</td> <td>24 bytes</td> </tr> <tr> <td>Custom Decel. Time (1~9999)</td> <td>Reserved</td> </tr> </table> <p>Flag option : 0x0001 : reserved 0x0002 : Custom Accel. Time is used. 0x0004 : Custom Decel. Time is used.</p> <p>If the Flag bit is OFF status (0), Accel./Decel. Time value is used that saved in controller.</p> <p>Response: 1 byte</p>	4 bytes	4 bytes	4 bytes	2 bytes	incremental position value	Running speed [pps]	Flag option	Custom Accel. Time (1~9999)	2 bytes	24 bytes	Custom Decel. Time (1~9999)	Reserved
4 bytes	4 bytes	4 bytes	2 bytes											
incremental position value	Running speed [pps]	Flag option	Custom Accel. Time (1~9999)											
2 bytes	24 bytes													
Custom Decel. Time (1~9999)	Reserved													
<p>0x82 (130)</p>	<p>FAS_ MoveVelocityEx</p>	<p>Request the motor to start jog motion at the current setting parameter condition with custom Accel/Decel time value[msec].</p> <p>Sending: 37 bytes</p> <table border="1" data-bbox="584 1167 1382 1285"> <tr> <td>4 bytes</td> <td>1 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Running speed [pps]</td> <td>Running direction (0: -Jog 1: +Jog)</td> <td>Flag option</td> </tr> </table> <table border="1" data-bbox="584 1335 1134 1453"> <tr> <td>2 bytes</td> <td>26 bytes</td> </tr> <tr> <td>Custom Accel./Decel. Time (1~9999)</td> <td>Reserved</td> </tr> </table> <p>Flag option : 0x0001 : reserved 0x0002 : Custom Accel./Decel. Time is used.</p> <p>If the Flag bit is OFF status(0), Accel./Decel. Time value is used that saved in controller.</p> <p>Response : 1 byte</p>	4 bytes	1 bytes	4 bytes	Running speed [pps]	Running direction (0: -Jog 1: +Jog)	Flag option	2 bytes	26 bytes	Custom Accel./Decel. Time (1~9999)	Reserved		
4 bytes	1 bytes	4 bytes												
Running speed [pps]	Running direction (0: -Jog 1: +Jog)	Flag option												
2 bytes	26 bytes													
Custom Accel./Decel. Time (1~9999)	Reserved													
	<p>FAS_MoveLinearAbs Pos</p>	<p>To request Linear Interpolation move its position as much as the absolute value[pulse] for more than 2 motors that connected in same port. Refer to 「2. Library for PC program」.</p>												
	<p>FAS_MoveLinearInc Pos</p>	<p>To request Linear Interpolation move its position as much as the incremental value[pulse] for more than 2 motors that connected in same port. Refer to 「2. Library for PC program」.</p>												

<p>0x40 (64)</p>	<p>FAS_ GetAxisStatus</p>	<p>To request the Flag value of displaying the running status</p> <p>Sending : 0 byte Response : 5 bytes</p> <table border="1" data-bbox="584 342 1056 461"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Status flag value</td> </tr> </table> <p>For bit related to each Flag, refer to 「1-2-5. Bit setup of Status Flag」.</p>	1 byte	4 bytes	Communication status	Status flag value														
1 byte	4 bytes																			
Communication status	Status flag value																			
<p>0x41 (65)</p>	<p>FAS_ GetIOAxisStatus</p>	<p>To request the I/O status and the running Flag status. (Frame type 0x22, 0x23, and 0x40 are packed.)</p> <p>Sending : 0 byte Response : 13 bytes</p> <table border="1" data-bbox="584 790 1382 909"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Input status value</td> <td>Output status value</td> <td>Status flag value</td> </tr> </table>	1 byte	4 bytes	4 bytes	4 bytes	Communication status	Input status value	Output status value	Status flag value										
1 byte	4 bytes	4 bytes	4 bytes																	
Communication status	Input status value	Output status value	Status flag value																	
<p>0x42 (66)</p>	<p>FAS_ GetMotionStatus</p>	<p>To request the current running progress status and its PT number (Frame type 0x51, 0x53, 0x54, and 0x55 are packed.)</p> <p>Sending : 0 byte Response : 21 bytes</p> <table border="1" data-bbox="584 1149 1445 1305"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Command position value</td> <td>Actual Position value</td> <td>Position Difference value</td> <td>Running speed value</td> <td>Current running PT number</td> </tr> </table>	1 byte	4 bytes	4 bytes	4 bytes	4 bytes	4 bytes	Communication status	Command position value	Actual Position value	Position Difference value	Running speed value	Current running PT number						
1 byte	4 bytes	4 bytes	4 bytes	4 bytes	4 bytes															
Communication status	Command position value	Actual Position value	Position Difference value	Running speed value	Current running PT number															
<p>0x43 (67)</p>	<p>FAS_ GetAllStatus</p>	<p>To request all data including the current running status (Frame type 0x41, and 0x42 are packed.)</p> <p>Sending : 0 byte</p> <p>Response : 33 bytes</p> <table border="1" data-bbox="584 1518 1345 1619"> <tr> <td>1 byte</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Input status value</td> <td>Output status value</td> <td>Status flag value</td> </tr> </table> <table border="1" data-bbox="584 1693 1386 1827"> <tr> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> <td>4 bytes</td> </tr> <tr> <td>Command position value</td> <td>Actual position value</td> <td>Position Difference value</td> <td>Running speed value</td> <td>Current running PT number</td> </tr> </table>	1 byte	4 bytes	4 bytes	4 bytes	Communication status	Input status value	Output status value	Status flag value	4 bytes	4 bytes	4 bytes	4 bytes	4 bytes	Command position value	Actual position value	Position Difference value	Running speed value	Current running PT number
1 byte	4 bytes	4 bytes	4 bytes																	
Communication status	Input status value	Output status value	Status flag value																	
4 bytes	4 bytes	4 bytes	4 bytes	4 bytes																
Command position value	Actual position value	Position Difference value	Running speed value	Current running PT number																
<p>0x50 (80)</p>	<p>FAS_ SetCommandPos</p>	<p>The user sets it to the command position value before starts to operate and then can check how the command position value is changed.</p> <p>Sending : 4 bytes</p> <table border="1" data-bbox="584 2018 1038 2094"> <tr> <td>4 bytes</td> </tr> <tr> <td>Command position setting count value</td> </tr> </table>	4 bytes	Command position setting count value																
4 bytes																				
Command position setting count value																				

		<p>Response : 1 byte</p> <table border="1"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	Communication status		
1 byte						
Communication status						
0x51 (81)	FAS_ GetCommandPos	<p>To request the command position value[pulse] being tracked.</p> <p>Sending : 0 byte</p> <p>Response : 5 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Command position value</td> </tr> </table>	1 byte	4 bytes	Communication status	Command position value
1 byte	4 bytes					
Communication status	Command position value					
0x52 (82)	FAS_ SetActualPos	<p>MECQ1 is the closed loop control drive and so the actual position value is continuously controlled while the motor is in running. The user sets it to the actual position value before it starts to operate and then can check how the actual position value is changed.</p> <p>Sending : 4 bytes</p> <table border="1"> <tr> <td>4 bytes</td> </tr> <tr> <td>Actual position count value</td> </tr> </table> <p>Response : 1 byte</p> <table border="1"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	4 bytes	Actual position count value	1 byte	Communication status
4 bytes						
Actual position count value						
1 byte						
Communication status						
0x53 (83)	FAS_ GetActualPos	<p>To request the current actual position value [pulse].</p> <p>Sending : 0 byte</p> <p>Response : 5 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Actual position value</td> </tr> </table>	1 byte	4 bytes	Communication status	Actual position value
1 byte	4 bytes					
Communication status	Actual position value					
0x54 (84)	FAS_ GetPosError	<p>To request the difference [pulse] between the command position value and the actual position value.</p> <p>Sending : 0 byte</p> <p>Response : 5 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Position difference value</td> </tr> </table> <p>By this value, the user can check the current running status (how much inposition is tracked).</p>	1 byte	4 bytes	Communication status	Position difference value
1 byte	4 bytes					
Communication status	Position difference value					
0x55 (85)	FAS_ GetActualVel	<p>To request the current running speed value [pps]</p> <p>Sending : 0 byte</p> <p>Response : 5 bytes</p> <table border="1"> <tr> <td>1 byte</td> <td>4 bytes</td> </tr> <tr> <td>Communication status</td> <td>Speed value</td> </tr> </table>	1 byte	4 bytes	Communication status	Speed value
1 byte	4 bytes					
Communication status	Speed value					

<p>0x56 (86)</p>	<p>FAS_ ClearPosition</p>	<p>The user sets the command position and actual position value to '0' before it starts to operate and then can check how the command position value is changed.</p> <p>Sending : 0 byte Response : 1 byte</p> <table border="1" data-bbox="584 394 898 472"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	Communication status						
1 byte										
Communication status										
<p>0x58 (88)</p>	<p>FAS_ MovePause</p>	<p>To request the pause start and pause end of motor motioning.</p> <p>Sending : 1 byte</p> <table border="1" data-bbox="584 645 963 723"> <tr> <td>1 byte</td> </tr> <tr> <td>0:pause release, 1:pause start</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 786 906 864"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	1 byte	0:pause release, 1:pause start	1 byte	Communication status				
1 byte										
0:pause release, 1:pause start										
1 byte										
Communication status										
<p>0x60 (96)</p>	<p>FAS_ PosTableReadItem</p>	<p>To read PT values in the RAM of the drive.</p> <p>Sending : 2 bytes</p> <table border="1" data-bbox="584 1021 963 1099"> <tr> <td>2 bytes</td> </tr> <tr> <td>Readable PT number (0~255)</td> </tr> </table> <p>Response : 65 bytes</p> <table border="1" data-bbox="584 1171 1153 1249"> <tr> <td>1 byte</td> <td>64 bytes</td> </tr> <tr> <td>Communication status</td> <td>Relevant PT values</td> </tr> </table> <p>For items by each PT, refer to 「1-2-6. Position Table Item」.</p>	2 bytes	Readable PT number (0~255)	1 byte	64 bytes	Communication status	Relevant PT values		
2 bytes										
Readable PT number (0~255)										
1 byte	64 bytes									
Communication status	Relevant PT values									
<p>0x61 (97)</p>	<p>FAS_ PosTableWriteItem</p>	<p>To save PT values to the RAM of the drive.</p> <p>Sending : 66 bytes</p> <table border="1" data-bbox="584 1413 1085 1491"> <tr> <td>2 bytes</td> <td>64 bytes</td> </tr> <tr> <td>PT number (0~255)</td> <td>Relevant PT value</td> </tr> </table> <p>For items by each PT, refer to 「1-2-6. Position Table Item」.</p> <p>Response : 2 bytes</p> <table border="1" data-bbox="584 1603 1361 1697"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (values except 0 : complete, 0: error)</td> </tr> </table>	2 bytes	64 bytes	PT number (0~255)	Relevant PT value	1 byte	1 byte	Communication status	Command performing status (values except 0 : complete, 0: error)
2 bytes	64 bytes									
PT number (0~255)	Relevant PT value									
1 byte	1 byte									
Communication status	Command performing status (values except 0 : complete, 0: error)									
<p>0x62 (98)</p>	<p>FAS_ PosTableReadROM</p>	<p>To read all PT values (256 ea) in the ROM of the drive</p> <p>Sending : 0 byte</p> <p>Response : 2 bytes</p> <table border="1" data-bbox="584 1883 1361 1984"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (0 : complete, values except 0: error)</td> </tr> </table>	1 byte	1 byte	Communication status	Command performing status (0 : complete, values except 0: error)				
1 byte	1 byte									
Communication status	Command performing status (0 : complete, values except 0: error)									

<p>0x63 (99)</p>	<p>FAS_ PosTableWriteROM</p>	<p>To save all PT value (256 ea) to the ROM of the drive.</p> <p>Sending : 0 byte</p> <p>Response : 2 bytes</p> <table border="1" data-bbox="584 353 1358 456"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (0 : complete, values except 0: error)</td> </tr> </table>	1 byte	1 byte	Communication status	Command performing status (0 : complete, values except 0: error)						
1 byte	1 byte											
Communication status	Command performing status (0 : complete, values except 0: error)											
<p>0x64 (100)</p>	<p>FAS_ PosTableRunItem</p>	<p>To start the position table operation from the designated PT number</p> <p>Sending : 2 bytes</p> <table border="1" data-bbox="584 584 836 663"> <tr> <td>2 bytes</td> </tr> <tr> <td>PT Number (0~255)</td> </tr> </table> <p>Response : 1 byte</p> <table border="1" data-bbox="584 734 874 813"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	2 bytes	PT Number (0~255)	1 byte	Communication status						
2 bytes												
PT Number (0~255)												
1 byte												
Communication status												
<p>0x6A (106)</p>	<p>FAS_ PosTableReadOneItem</p>	<p>To read one of PT values in the RAM of the drive.</p> <p>Sending: 4 byte</p> <table border="1" data-bbox="584 943 1369 1021"> <tr> <td>2 byte</td> <td>2 byte</td> </tr> <tr> <td>PT Number (0~255)</td> <td>Offset value(0~40)</td> </tr> </table> <p>Refer to 「1-2-6. Position Table Item」for Offset value</p> <p>Response: 5 byte</p> <table border="1" data-bbox="584 1133 1174 1211"> <tr> <td>1 byte</td> <td>4 byte</td> </tr> <tr> <td>Communication status</td> <td>Relevant one of PT value</td> </tr> </table>	2 byte	2 byte	PT Number (0~255)	Offset value(0~40)	1 byte	4 byte	Communication status	Relevant one of PT value		
2 byte	2 byte											
PT Number (0~255)	Offset value(0~40)											
1 byte	4 byte											
Communication status	Relevant one of PT value											
<p>0x6B (107)</p>	<p>FAS_ PosTableWriteOneItem</p>	<p>To save one of PT values to the RAM of the drive.</p> <p>Sending: 8 byte</p> <table border="1" data-bbox="584 1357 1402 1435"> <tr> <td>2 byte</td> <td>2 byte</td> <td>4 byte</td> </tr> <tr> <td>PT Number (0~255)</td> <td>Offset value (0~40)</td> <td>Relevant one of PT value</td> </tr> </table> <p>Refer to 「1-2-6. Position Table Item」for Offset value</p> <p>Response: 2 byte</p> <table border="1" data-bbox="584 1547 1385 1650"> <tr> <td>1 byte</td> <td>1 byte</td> </tr> <tr> <td>Communication status</td> <td>Command performing status (values except 0 : complete, 0: error)</td> </tr> </table>	2 byte	2 byte	4 byte	PT Number (0~255)	Offset value (0~40)	Relevant one of PT value	1 byte	1 byte	Communication status	Command performing status (values except 0 : complete, 0: error)
2 byte	2 byte	4 byte										
PT Number (0~255)	Offset value (0~40)	Relevant one of PT value										
1 byte	1 byte											
Communication status	Command performing status (values except 0 : complete, 0: error)											
<p>0x78 (120)</p>	<p>FAS_ MovePush</p>	<p>To request push motion(maintain specified motor torque) Command.</p> <p>Sending: 28 bytes</p> <table border="1" data-bbox="584 1906 1406 2058"> <tr> <td>4 byte</td> <td>4 bytes</td> <td>4 byte</td> <td>2 bytes</td> <td>2 bytes</td> </tr> <tr> <td>Normal Start speed</td> <td>Normal Move speed</td> <td>Normal Position</td> <td>Accel time</td> <td>Decel time</td> </tr> </table>	4 byte	4 bytes	4 byte	2 bytes	2 bytes	Normal Start speed	Normal Move speed	Normal Position	Accel time	Decel time
4 byte	4 bytes	4 byte	2 bytes	2 bytes								
Normal Start speed	Normal Move speed	Normal Position	Accel time	Decel time								

		<table border="1"> <tr> <td>2 byte</td> <td>4 bytes</td> <td>4 byte</td> <td>2 byte</td> </tr> <tr> <td>Push torque ratio</td> <td>Push Move speed</td> <td>Push Position</td> <td>Push mode</td> </tr> </table> <p>positioning start speed : 1~35000[pps] positioning operating speed : 1~500000[pps] positioning absolute position value : -134,217,728 ~134,217,727 Positioning Acceleration/Deceleration time : 1~9,999[ms] Push motion torque ration : 20~90[%] Push motion speec value : 1~33333[pps] (Max. 200[rpm]) (Resolution : 10,000) Push motion absolutr position value : -134,217,728 ~134,217,727 push mode : 0(stop mode), 1~10,000(non-stop mode)</p> <p>Refer to 「MECQ1_Manual_Text 8-6. Push Motion」.</p> <p>Response: 1 byte</p> <table border="1"> <tr> <td>1 byte</td> </tr> <tr> <td>Communication status</td> </tr> </table>	2 byte	4 bytes	4 byte	2 byte	Push torque ratio	Push Move speed	Push Position	Push mode	1 byte	Communication status
2 byte	4 bytes	4 byte	2 byte									
Push torque ratio	Push Move speed	Push Position	Push mode									
1 byte												
Communication status												
0x79 (121)	FAS_ GetPushStatus	<p>To request the current push motion status.</p> <p>Sending: 0 byte</p> <p>Response: 2 byte</p> <table border="1"> <tr> <td>1 byte</td> <td>1 bytes</td> </tr> <tr> <td>Communication status</td> <td> Push motion status (0: normal Servo ON 1: push motioning but the work is not detected 2: work detected and torque is maintained) </td> </tr> </table>	1 byte	1 bytes	Communication status	Push motion status (0: normal Servo ON 1: push motioning but the work is not detected 2: work detected and torque is maintained)						
1 byte	1 bytes											
Communication status	Push motion status (0: normal Servo ON 1: push motioning but the work is not detected 2: work detected and torque is maintained)											

* Frame Type '0x65 ~ 0x69', '0x90 ~ 0x92' are allocated for internal using purpose.

1 - 2 - 2 . Parameter List

No	Name	Unit	Lower	Upper	Default
0	Pulse Per Revolution		0	15	6
1	Axis Max Speed	[pps]	1	2,500,000	500,000
2	Axis Start Speed	[pps]	1	35,000	1
3	Axis Acc Time	[msec]	1	9,999	100
4	Axis Dec Time	[msec]	1	9,999	100
5	Speed Override	[%]	1	500	100
6	Jog Speed	[pps]	1	2,500,000	5,000
7	Jog Start Speed	[pps]	1	35,000	1
8	Jog Acc Dec Time	[msec]	1	9,999	100
9	S/W Limit Plus Value	[pulse]	-134,217,728	134,217,727	134,217,727
10	S/W Limit Minus Value	[pulse]	-134,217,728	134,217,727	-134,217,728
11	S/W Limit Stop Method		0	2	2
12	H/W Limit Stop Method		0	1	0
13	Limit Sensor Logic		0	1	0
14	Org Speed	[pps]	1	500,000	5,000
15	Org Search Speed	[pps]	1	50,000	1,000
16	Org Acc Dec Time	[msec]	1	9,999	50
17	Org Method		0	7	0
18	Org Dir		0	1	1
19	Org OffSet	[pulse]	-134,217,728	134,217,727	0
20	Org Position Set	[pulse]	-134,217,728	134,217,727	0
21	Org Sensor Logic		0	1	0
22	Position Loop Gain		0	63	4
23	Inpos Value		0	63	0
24	Pos Tracking Limit	[pulse]	1	134,217,727	1,000
25	Motion Dir		0	1	0
26	Limit Sensor Dir		0	1	0
27	Org Torque Ratio	[%]	20	90	50
28	Pos. Error Overflow Limit	[pulse]	1	134,217,727	1,000
29	Brake Delay Time	[msec]	10	5,000	200
30	Run Current	*10[%]	5	15	10
31	Boost Current	*50[%]	0	7	0
32	Stop Current	*10[%]	2	10	5

1 - 2 - 3 . Bit set up of Output pin

'This displays the detailed description for 0x20 Frame type.

This command is applicable only to 9 signals of 'User Output 0' ~ 'User Output 8' out of 24 signal types in the control output port. The rest (15 output signals) of them cannot be operated by the user's disposal. When any relevant situation occurs while the drive operates, they are displayed. The following table shows bit mask values by each signal.

Signal Name	Relevant Bit Position	Signal Name	Relevant Bit Position	Signal Name	Relevant Bit Position
Compare Out	0x00000001	Origin Search OK	0x00000100	User OUT 1	0x00010000
Inposition	0x00000002	ServoReady	0x00000200	User OUT 2	0x00020000
Alarm	0x00000004	reserved	0x00000400	User OUT 3	0x00040000
Moving	0x00000008	reserved	0x00000800	User OUT 4	0x00080000
Acc/Dec	0x00000010	PT Output0	0x00001000	User OUT 5	0x00100000
ACK	0x00000020	PT Output1	0x00002000	User OUT 6	0x00200000
END	0x00000040	PT Output2	0x00004000	User OUT 7	0x00400000
AlarmBlink	0x00000080	User OUT 0	0x00008000	User OUT 8	0x00800000

【Example 1】 Sending data to turn ON the User Output 5 port.

4 bytes (I/O set mask value)	4 bytes (I/O clear mask value)
0x00100000	0x00000000

【Example 2】 Sending data to turn OFF the User Output 5 port

4 bytes (I/O set mask value)	4 bytes (I/O clear mask value)
0x00000000	0x00100000

1 - 2 - 4 . Bit set up of input pin

This displays the detailed description for 0x21 Frame type.

This command is applicable to 32 signals in the control input port. The user can use signals for test as if they are inputted without actual input signal. The following table shows bit mask values by each signal.


Signal Name	Relevant Bit Position	Signal Name	Relevant Bit Position	Signal Name	Relevant Bit Position	Signal Name	Relevant Bit Position
Limit+	0x00000001	PT A4	0x00000100	Alarm Reset	0x00010000	JPT input2	0x01000000
Limit-	0x00000002	PT A5/ User IN 6	0x00000200	ServoON	0x00020000	JPT Start	0x02000000
Origin	0x00000004	PT A6/ User IN 7	0x00000400	Pause	0x00040000	User IN 0	0x04000000
Clear Position	0x00000008	PT A7/ User IN 8	0x00000800	Org Search	0x00080000	User IN 1	0x08000000
PT A0	0x00000010	PT Start	0x00001000	Teaching	0x00100000	User IN 2	0x10000000
PT A1	0x00000020	Stop	0x00002000	E-stop	0x00200000	User IN 3	0x20000000
PT A2	0x00000040	Jog+	0x00004000	JPT input0	0x00400000	User IN 4	0x40000000
PT A3	0x00000080	Jog-	0x00008000	JPT input1	0x00800000	User IN 5	0x80000000

【Example 1】 Sending data to turn ON the Pause port

4 bytes (I/O set mask value)	4 bytes (I/O clear mask value)
0x00040000	0x00000000

【Example 2】 Sending data to turn OFF the Pause port

4 bytes (I/O set mask value)	4 bytes (I/O clear mask value)
0x00000000	0x00040000

 Caution	Do not mix the bit setup of 'A5 ~ PT A7' and 'User IN 6 ~ IN8' together on your program.
--	--

1 - 2 - 5 . Bit set up of status flag

Refer to 'motion_define.h' of include files.

Name of Flag Define	Contents	Relevant Bit Position
FFLAG_ERRORALL	One or more error occurs.	0X00000001
FFLAG_HWPOSILMT	'+' direction limit sensor turns ON.	0X00000002
FFLAG_HWNEGALMT	'-' direction limit sensor turns ON.	0X00000004
FFLAG_SWPOGILMT	'+' direction program limit is exceeded.	0X00000008
FFLAG_SWNEGALMT	'-' direction program limit is exceeded.	0X00000010
FFLAG_ERRPOSOVERFLOW	Position error is bigger than 'Pos Error Overflow Limit' value after finished positioning command.	0X00000080
FFLAG_ERROVERCURRENT	The motor driving device is under over-current.	0X00000100
FFLAG_ERROVERSPEED	The motor speed exceeded 3000[rpm].	0X00000200
FFLAG_ERRPOSTRACKING	Position error is bigger thn 'Pos Tracking Limit' value during the positioning command.	0X00000400
FFLAG_ERROVERLOAD	Load exceeding the max torque of the motor is loaded more than 5 seconds.	0X00000800
FFLAG_ERROVERHEAT	The internal temperature of the drive exceeds 85°C.	0X00001000
FFLAG_ERRBACKEMF	A counter electromotive force of the motor exceeds 45V.	0X00002000
FFLAG_ERRMOTORPOWER	The power supplied to the motor is abnormal status.	0X00004000
FFLAG_ERRINPOSITION	After operation is finished, a position error occurs for more than 3 seconds.	0X00008000
FFLAG_EMGSTOP	The motor is under emergency stop.	0X00010000
FFLAG_SLOWSTOP	The motor is under general stop.	0X00020000
FFLAG_ORIGINRETURNING	The motor is returning to the origin.	0X00040000
FFLAG_INPOSITION	Inposition has been finished.	0X00080000
FFLAG_SERVOON	The motor is under Servo ON.	0X00100000
FFLAG_ALARMRESET	AlarmReset has run.	0X00200000
FFLAG_PTSTOPED	Position Table operation has been finished.	0X00400000
FFLAG_ORIGINSENSOR	The origin sensor is ON.	0X00800000
FFLAG_ZPULSE	The motor operates to z-pulse type of origin return operations.	0X01000000
FFLAG_ORIGINRETOK	Origin return operation has been finished.	0X02000000
FFLAG_MOTIONDIR	To display the motor operating direction (+: Off, -: On)	0X04000000
FFLAG_MOTIONING	The motor is running.	0X08000000
FFLAG_MOTIONPAUSE	The motor in running is stopped by Pause command.	0X10000000
FFLAG_MOTIONACCEL	The motor is operating to the acceleration section.	0X20000000
FFLAG_MOTIONDECEL	The motor is operating to the deceleration section.	0X40000000
FFLAG_MOTIONCONST	The motor is operating to the normal speed, not acceleration / deceleration sections.	0X80000000

1 - 2 - 6 . Contents of position table

Refer to 'motion_define.h' of include files.

Name	Name of Structure Parameter	Number of Bytes	Offset value	Unit	Low Limit *1	Upper Limit *1
Position	lPosition	4 (signed)	0	[pulse]	-134217728	+134217728
Low Speed	dwStartSpd	4 (unsigned)	4	[pps]	0	500000
High Speed	dwMoveSpd	4 (unsigned)	8	[pps]	0	500000
Accel. Time	wAccelRate	2 (unsigned)	12	[msec]	1	9999
Decel. Time	wDecelRate	2 (unsigned)	14	[msec]	1	9999
Command	wCommand	2 (unsigned)	16		0	10
Wait time	wWaitTime	2 (unsigned)	18	[msec]	0	600000
Continuous Action	wContinuous	2 (unsigned)	20		0	1
Jump Table No.	wBranch	2 (unsigned)	22		0 10000	255 10255
Jump PT 0	wCond_branch0	2 (unsigned)	24		0 10000	255 10255
Jump PT 1	wCond_branch1	2 (unsigned)	26		0 10000	255 10255
Jump PT 2	wCond_branch2	2 (unsigned)	28		0 10000	255 10255
Loop Count	wLoopCount	2 (unsigned)	30		0	100
Loop Jump Table No.	wBranchAfterLoop	2 (unsigned)	32		0 10000	255 10255
PT set	wPTSet	2 (unsigned)	34		0	15
Loop Counter Clear	wLoopCountCLR	2 (unsigned)	36		0	255
Check Inposition	bCheckInpos	2 (unsigned)	38		0	1
Compare Position	lTriggerPos	4 (signed)	40	[pulse]	-134217728	+134217728
Compare Width	wTriggerOnTime	2 (unsigned)	44	[msec]	1	9999
Push Ratio	wPushRatio	2 (unsigned)	46	[%]	20	90
Push Speed	dwPushSpeed	4 (unsigned)	48	[pps]	0	33333
Push Position	lPushPosition	4 (signed)	52	[pulse]	-134217728	+134217728
Push Mode	wPushMode	2 (unsigned)	56		0	10000
Blank		6 (unsigned)	58		0x00	

For the setting method by each item, refer to other manual 「[MECQ1_Manual_Position Table](#)」

1 - 2 - 7 . Information of Motors

Firstly the number and 2~3 characters are indicating the motor size and length.

【Example 1】 42L : Motor Flange size is 42mm and long size

1 - 3 . Program Method

There are 2 methods of programming for MECQ1.

The first is normally used method that using Visual C++ language under window system of PC.

Library that serviced together with MECQ1 have to be used. Refer to

[「2. Library for PC Program」](#)

The second method can be accomplished by sending command characters directly to MECQ1. The user have to prepare low level protocol programming like 'Protocol Test' program. This method is normally used for PLC system.

To excise the protocol programming, please refer to serviced [「3. Protocol for PLC Program」](#).with product, It can be also self tested by using of , 'ProtocolTest.exe' GUI program.

2 . Library for PC program

2 - 1 . Library configuration

To use this library, C++ header file(*.h) and library file(*.lib or *.dll) are required. These files are included in "MINDMAN\MEC Motor Editor V6 \include\". The following contents should be included in a source file for development.

```
#include "MINDMAN\MEC Motor Editor V6 \include\FAS_EziMotionPlusR.h"
#include "MINDMAN\MEC Motor Editor V6 \include\COMM_Define.h"
#include "MINDMAN\MEC Motor Editor V6 \include\MOTION_DEFINE.h"
#include "MINDMAN\MEC Motor Editor V6 \include\ReturnCodes_Define.h"
```

Also, library files are as follows:

```
"MINDMAN\MEC Motor Editor V6 \include\EziMotionPlusR.lib"
"MINDMAN\MEC Motor Editor V6 \include\EziMotionPlusR.dll"
```

A sample program source of using library is included in a

"MINDMAN\MEC Motor Editor V6 \Examples\" folder.

(1) The following table describes values returned when each library (DLL) function is used. The user can check **the values returned at the library (DLL) function**. In case of low-level programming, this service not provided.

Item	Definition	Returned value	Description
Normal	FMM_OK	0	The function has normally performed the command.
Input Error	FMM_NOT_OPEN	1	Wrong port number is inputted.
	FMM_INVALID_PORT_NUM	2	The port is not connected.
	FMM_INVALID_SLAVE_NUM	3	Wrong slave number is inputted.
Operation	FMM_POSTABLE_ERROR	9	An error occurs while the motor accesses to the position table.
Error	FMC_DISCONNECTED	5	The relevant drive is disconnected.
	FMC_TIMEOUT_ERROR	6	Response delay (100 msec) occurs.
	FMC_CRCFAILED_ERROR	7	Checksum error occurs.
	FMC_RECVPACKET_ERROR	8	Protocol level error occurs in packet that comes from Drive.

(2) The following table shows return values included commonly in all libraries. The user can check **the result (communication status, running status) judged by the drive**. When the user develops programs by using protocols without libraries (DLL), they are available as well.

Item	Definition	Returned value	Description
Normal	FMP_OK	0	Communication has been normally performed.
Input Error	FMP_FRAMETYPEERROR	128	The drive cannot recognize the command.
	FMP_DATAERROR	129	Input data is out of the range
Operation Error	FMP_RUNFAIL	133	The motor is already running or not prepared for running. Other wrong motion command.
	FMP_RESETFAIL	134	The user cannot execute AlarmReset command while the servo is ON.
	FMP_SERVOONFAIL1	135	An alarm has occurred.
	FMP_SERVOONFAIL2	136	The motor is under Emergency Stop.
	FMP_SERVOONFAIL3	137	'ServoON'signal is already assigned to input pin.
Connection Error	FMP_PACKETERROR	130	Protocol level error occurs in packet that Drive's received.
	FMP_PACKETCRCERROR	170	CRC value is not correct in packet that Drive's received.

2 - 2 . Communication status window

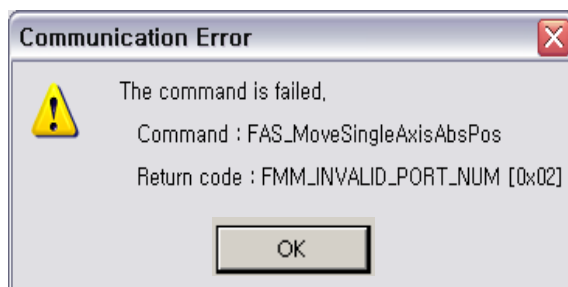
Above communication status is dividing by 3 groups.

(1) Communication Error



FMM_NOT_OPEN,

COM Port is not connected (This error mode can not be generated on GUI)



FMM_INVALID_PORT_NUM,

COM Port number does not exist (This error mode can not be generated on GUI)



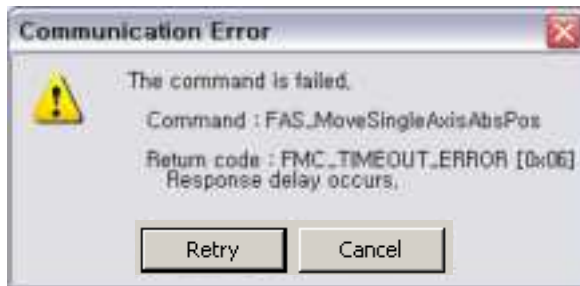
FMM_INVALID_SLAVE_NUM,

Slave number does not exist. Checking the ID value of the drive.



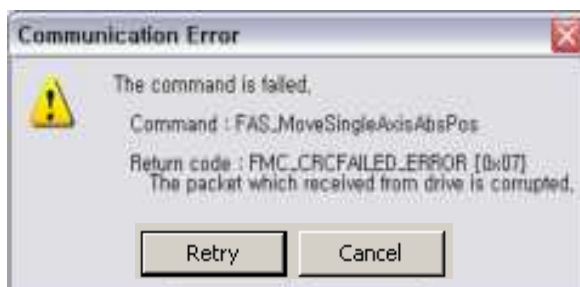
FMC_DISCONNECTED = 5,

COM Port is disconnecting during communication. Checking the communication cable Or Power of the drive.



FMC_TIMEOUT_ERROR,

There is no response from the drive.



FMC_CRCFAILED_ERROR,

CRC value of communication packet from the drive is not correct.

Check the possibility of noise on communication cable.



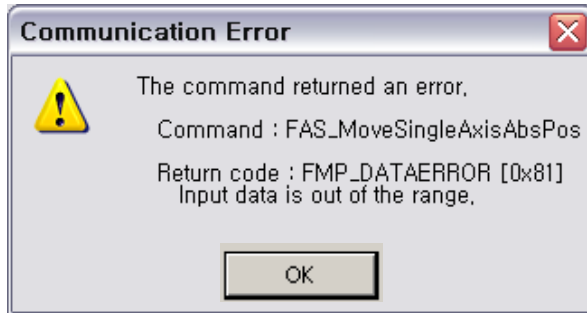
FMC_RECVPACKET_ERROR,

The length of received packet is not correct. Check the possibility of noise on communication cable.



FMP_FRAMETYPEERROR = 0x80,

Drive does not recognize the command or wrong command is sent
Check the command value sent you want to send to the drive.



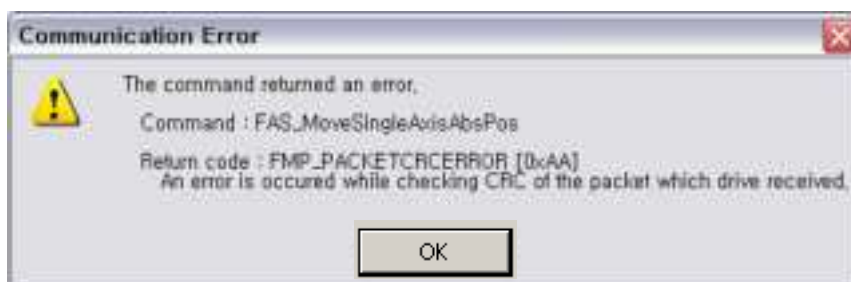
FMP_DATAERROR,

The value of the sended data is out of the proper range for drive.
Check the value that you want to send to the drive.



FMP_PACKETERROR,

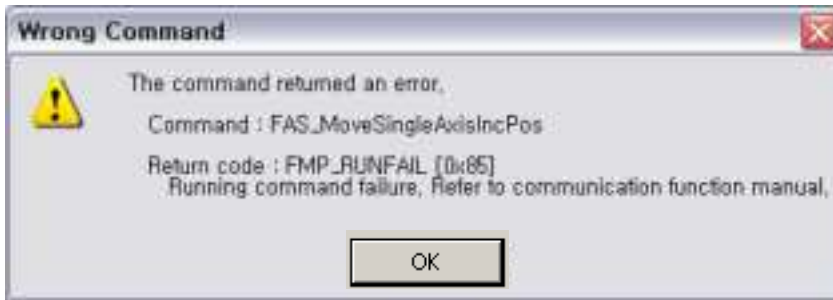
The length of received packet on drive is not correct. Check the possibility of
noise on communication cable.



FMP_PACKETCRCERROR = 0xAA,

The CRC value on drive is not correct. Check the possibility of noise on
communication cable.

(2) Wrong Command



FMP_RUNFAIL = 0x85,

Fail on motion command: The motor can not run on next status.

- The motor is already running
- The motor is under stop command
- Servo OFF status
- Other wrong motion command



FMP_RESETFAIL,

Fail on reset command: The motor can not reset on next status.

- Servo ON status
- Already 'Reset status by external input signal.



FMP_SERVOONFAIL1,

Wrong 'Servo ON' command during Alarm happens.



FMP_SERVOONFAIL2,

Wrong 'Servo ON' command during the emergency Stop



FMP_SERVOONFAIL3,

'Servo ON' Signal is assigned by external input pin. In this case Servo ON command by DLL library is not working.

(3) Command Execution Error



FMM_POSTABLE_ERROR,

The execution of DLL library for 'Position Table' is failed.

2 - 3 . Drive Link Function

Function Name	Description
FAS_Connect	The drive tries to connect communication with the drive module: The drive tries to connect communication with the drive module: When it is successfully connected, TRUE will return. Otherwise, FALSE will return.
FAS_Close	The drive tries to disconnect communication with the drive module.
FAS_GetSlaveInfo	The drive reads drive type and program version: Drive type and version information will return.
FAS_GetMotorInfo	The drive reads motor type and maker: Motor type and maker information will return.
FAS_IsSlaveExist	The drive checks whether there is the relevant drive: When it exists, TRUE will return. Otherwise, FALSE will return
FAS_EnableLog	To select the communication error log function ON/OFF : When it exists, TRUE will return. Otherwise, FALSE will return.
FAS_SetLogPath	To set the saved folder name of error log file : When folder exists, TRUE will return. Otherwise, FALSE will return.

FAS_Connect

FAS_Connect is the function of connecting MECQ1.

Syntax

```
BOOL FAS_Connect(
    BYTE nPortNo,
    DWORD dwBaud
);
```

Parameters

nPortNo

Select a serial port to be connected.

dwBaud

Input the Baudrate of the serial port

Return Value

When it is successfully connected, TRUE will returns. Otherwise, FALSE will return.

Remarks

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcInit()
{
    BYTE nPortNo = 1; // COMM Port number
    DWORD dwBaudrate = 115200; // Baudrate(Be variable by setting)
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    char lpBuff[256];
    int nBuffSize = 256;
    BYTE nType;
    int nRtn;

    // Try to connct
    if (FAS_Connect(nPortNo, dwBaudrate) == FALSE)
    {
        // Connection failed.
        // The port is not connected or the baudrate may be wrong.
        return; return;
    }

    if (FAS_IsSlaveExist(nPortNo, iSlaveNo) == FALSE)
    {
        // There is no relevant slave number.
```

```
        // Check the slave number of MECQ1.
        return;
    }

    nRtn = FAS_GetSlaveInfo(nPortNo, iSlaveNo, &nType, lpBuff, nBuffSize);
    if (nRtn != FMM_OK)
    {
        // Command has not been performed properly.
        // Refer to ReturnCodes_Define.h.
    }

    printf("Port : %d (Slave %d) \n", nPortNo, iSlaveNo);
    printf("\tType : %d \n", nType);
    printf("\tVersion : %d \n", lpBuff);

    // Disconnect.
    FAS_Close(nPortNo);
}
```

See Also

FAS_Close

FAS_Close

To disconnect the serial port being used

Syntax

```
void FAS_Close(  
    BYTE nPortNo  
);
```

Parameters

nPortNo

Port number to disconnect

Remarks

Example

Refer to 'FAS_Connect' library.

See Also

FAS_Connect

FAS_GetSlaveInfo

To get the version information string of the relevant drive

Syntax

```
int FAS_GetSlaveInfo(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BYTE pType,  
    LPSTR lpBuff,  
    int nBuffSize  
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive

pType

Relevant drive type number

lpBuff

Buffer pointer to get version information string

nBuffSize

lpBuff memory allocation size

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_Connect' library.

See Also

FAS_GetMotorInfo

To get the motor information string of the relevant drive

Syntax

```
int FAS_GetMotorInfo(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BYTE pType,  
    LPSTR lpBuff,  
    int nBuffSize  
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive

pType

Relevant motor type number

lpBuff

Buffer pointer to get version information string

nBuffSize

lpBuff memory allocation size

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_Connect' library.

See Also

FAS_IsSlaveExist

To check that the drive is connected.

Syntax

```
BOOL FAS_IsSlaveExist(  
    BYTE nPortNo,  
    BYTE iSlaveNo  
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive

Return Value

TRUE : The drive is connected.

FALSE : The drive is disconnected.

Remarks

This function is provided from the library only and it is inapplicable to the protocol program mode.

Example

Refer to 'FAS_Connect' library.

See Also

FAS_Connect

FAS_EnableLog

To select the save function of communication error log file.

Syntax

```
void FAS_EnableLog(BOOL bEnable);
```

Parameters

bEnable

Select output of Log.

Remarks

Select the Log output during Ezi-MOITON Plus-R DLL function used. This setup

Does not affect the other process or other program.

Log function start from 'FAS_Connect' function, the Log output is ended when the 'FAS_Close' is excuted..

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcDisableLog()
{
    BYTE nPortNo = 1; // COMM Port number

    FAS_EnableLog(FALSE);

    // Since the function of Log is not output..

    // Try to connect.
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // connection fail.
        // cab be different Port or different Baudrate.
        return;
    }

    // Connection close..
    FAS_Close(nPortNo);
}
```

See Also

FAS_SetLogPath

FAS_SetLogPath

Setup the folder path of Log output files.

Syntax

```
BOOL FAS_SetLogPath(LPCTSTR lpPath);
```

Parameters

lpPath

Folder path Character string of Log output file.

Return Value

If the folder name does not exist or can not access, return FALSE.

Remarks

This function has to be called before FAS_Connect library.

If the lpPath value is NULL or the length is 0, the Log path is selected to

Ezi-MOTION Plus-R Library folder. The default value for Log path is NULL that the current library and program exist folder.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcEnableLog()
{
    BYTE nPortNo = 1; // COMM Port number

    // Log output..
    FAS_EnableLog(TRUE); // Do not need to use

    if (!FAS_SetLogPath_T("C:\\Logs\\")) // C:\\Logs floder have to be exist
    {
        // Log path does not exist.
        Return;
    }

    // All Log output is stored in C:\\Logs folder.

    // Try to connect.
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection fail.
        // cab be different Port or different Baudrate.
        return;
    }

    // Close connect.
    FAS_Close(nPortNo);
}
}
```

See Also

FAS_EnableLog

2 - 4 . Parameter Control Function

Function Name	Description
FAS_SaveAllParameters	Current parameters are saved to the ROM: Even after the drive is powered OFF, parameters related to operating speed, acceleration/deceleration time, and origin return need to be preserved.
FAS_SetParameter	The designated parameter is saved to the RAM: Specific parameter is saved..
FAS_GetParameter	The designated parameter is read from the RAM: Specific parameter is read.
FAS_GetROMParameter	The designated parameter is read from the ROM: Specific parameter is read from the ROM.

FAS_SaveAllParameters

All parameters edited up to now & assign status of In/Out signals are saved in the ROM area.

Syntax

```
Int FAS_SaveAllParameters(
    BYTE nPortNo,
    BYTE iSlaveNo
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Parameter values set to 'FAS_SetIOAssignMap' library as well as current parameter values are saved to the ROM.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcModifyParameter()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    long lParamVal;
    int nRtn;

    // Try to connect
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection failed.
        // The port is not connected or the baudrate may be wrong.
        return;
    }

    // Check Axis Start Speed Parameter.
    nRtn = FAS_GetParameter(nPortNo, iSlaveNo, SERVO_AXISSTARTSPEED, &lParamVal);
    if (nRtn != FMM_OK)
    {
        // Command has not been performed properly.
        // Refer to ReturnCodes_Define.h.
        _ASSERT(FALSE);
    }
}
```

```

else
{
// Parameter value saved in MECQ1.
printf("Parameter [before] : Start Speed = %d \n", IParamVal);
}

// Change Axis Start Speed parameter as 200 then read it again.
nRtn = FAS_SetParameter(nPortNo, iSlaveNo, SERVO_AXISSTARTSPEED, 200);
_ASSERT(nRtn == FMM_OK); // To Stop if the command didn't execute correctly.
nRtn = FAS_GetParameter(nPortNo, iSlaveNo, SERVO_AXISSTARTSPEED, &IParamVal);
_ASSERT(nRtn == FMM_OK);
printf("Parameter [after] : Start Speed = %d \n", IParamVal);

// Check the value saved in the ROM.
nRtn = FAS_GetROMParameter(nPortNo, iSlaveNo, SERVO_AXISSTARTSPEED,
&IParamVal);
_ASSERT(nRtn == FMM_OK); // To Stop if the command didn't execute correctly..
printf("Parameter [ROM] : Start Speed = %d \n", IParamVal);

// Edit the parameter value then save it in the ROM.
nRtn = FAS_SetParameter(nPortNo, iSlaveNo, SERVO_AXISSTARTSPEED, 100);
_ASSERT(nRtn == FMM_OK); // To Stop if the command didn't execute correctly
nRtn = FAS_SaveAllParameters(nPortNo, iSlaveNo);
_ASSERT(nRtn == FMM_OK);

// Disconnect.
FAS_Close(nPortNo);
}

```

See Also

FAS_GetRomParameter

FAS_SetParameter

Edit the relevant parameter value and then save it to the RAM.

Syntax

```
int FAS_SetParameter(
    BYTE nPortNo,
    BYTE iSlaveNo,
    BYTE iParamNo,
    long lParamValue
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

iParamNo

Parameter number to be edited

lParamValue

Parameter value to be edited

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : There is no parameter of designated iParamNo. 않

Remarks

The function operates only for one parameter designated.

Parameters in the drive are saved to 2 memory areas. That is, when power is off, the ROM saves parameters permanently. When power is on, parameters in the ROM are copied to the DSP RAM and used. When the user changes parameters, it changes not parameters in the ROM but parameter in the RAM. This function is to set the parameter number designated from the RAM to the relevant value.

Example

Refer to 'FAS_SaveAllParameter' library.

See Also

FAS_GetParameter

FAS_GetParamater

To call specific parameter values of the drive

Syntax

```
int FAS_GetParameter(
    BYTE nPortNo,
    BYTE iSlaveNo,
    BYTE iParamNo,
    long* IParamValue
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

iParamNo

Parameter number to be imported.

IParamValue

Parameter values

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : There is no parameter of designated iParamNo.

Remarks

The function operates only for one parameter designated.

Parameters in the drive are saved to 2 memory areas. That is, when power is off, the ROM saves parameters permanently. When power is on, parameters in the ROM are copied to the DSP RAM and used. When the user changes parameters, it changes not parameters in the ROM but parameter in the RAM. This function reads the parameter number designated to the RAM..

Example

Refer to 'FAS_SaveAllParameter' library.

See Also

FAS_SetParameter

FAS_GetROMParameter

To call parameters saved in the ROM

Syntax

```
int FAS_GetROMParameter(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BYTE iParamNo,  
    long* IRomParam  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

iParamNo

Parameter number to be imported.

IRomParam

Parameter values saved in the ROM.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : There is no parameter of designated iParamNo

Remarks

To call parameter values saved in the ROM

Even though this function runs, the value in the RAM is not changed. For this, run FAS_SetParameter.

Example

Refer to 'FAS_SaveAllParameter' library.

See Also

FAS_SaveAllParameters

2 - 5 . Servo Control Function

Function Name	Description
FAS_ServoEnable	The Servo of the drive designated turns ON/OFF.
FAS_ServoAlarmReset	The drive which an alarm occurs is released: Troubleshoot the alarm cause and use this function.
FAS_GetAlarmType	Read the Alarm type of the drive.

FAS_ServoEnable

To turn ON/OFF the servo drive

Syntax

```
int FAS_ServoEnable(
    BYTE nPortNo,
    BYTE iSlaveNo,
    BOOL bOnOff
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant

bOnOff

Enable or Disable.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

The given time is required until Servo ON flag in the axis status turns on after enable.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcAxisStatus()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    EZISERVO_AXISSTATUS AxisStatus;
    int nRtn;

    // Try to connect
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection failed.
        // The port is not connected or the baudrate may be wrong.
        return;
    }
}
```

```
    }

    nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &(AxisStatus.dwValue));
    _ASSERT(nRtn == FMM_OK);

    // If SERVO_ON flag turns off, the servo turns on...
    if (AxisStatus.FFLAG_SERVOON == 0)
    {
        nRtn = FAS_ServoEnable(nPortNo, iSlaveNo, TRUE);
        _ASSERT(nRtn == FMM_OK);
    }

    // If there is an alarm, AlarmReset runs.
    if (AxisStatus.FFLAG_ERRORALL || AxisStatus.FFLAG_ERROVERCURRENT ||
AxisStatus.FFLAG_ERROVERLOAD)
    {
        nRtn = FAS_ServoAlarmReset(nPortNo, iSlaveNo);
        _ASSERT(nRtn == FMM_OK);
    }

    // Disconnect.
    FAS_Close(nPortNo);
}
}
```

See Also

FAS_ServoAlarmReset

FAS_ServoAlarmReset

To send AlarmReset command

Syntax

```
int FAS_ServoAlarmReset(  
    BYTE nPortNo,  
    BYTE iSlaveNo  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Before sending this command, troubleshoot the alarm cause.

For alarm cause, refer to 'MECQ1_Manual_Text'

Example

Refer to 'FAS_ServoEnable' library

See Also

FAS_ServoEnable

2 - 6 . Control I/O Function

Function Name	Description
FAS_SetIOInput	To set the input signal level of the control input port : Input signal is set to [ON] or [OFF].
FAS_GetIOInput	To read the current input signal status of the control input port : The signal status returns by bit for each input signal.
FAS_SetIOOutput	To set the output signal level of the control output port : Output signal is set to [ON] or [OFF].
FAS_GetIOOutput	To read the current output signal status of the control output port : The signal status returns by bit for each output signal..
FAS_GetIOAssignMap	To read the pin setting status of the CN1 port : The setting status for each 9 variable signals returns by bit to the Input and Output port.
FAS_SetIOAssignMap	To assign the control I/O signal to CN1 port pin and also set the signal level : Setting for each 9 variable signals is assigned to the Input and Output port.
FAS_IOAssignMapReadROM	To load the pin setting status of CN1 port from ROM area to RAM area.

FAS_SetIOInput

To set I/O input. For more information, refer to '1-2. Structure of Frame Type'

Syntax

```
int FAS_SetIOInput(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD dwIOSetMask,
    DWORD dwIOCLRMask
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

dwIOSetMask

Input bitmask value to be set.

dwIOCLRMask

Input bitmask value to be cleared.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Be careful that dwIOSetMask bit and dwIOCLRMask bit are not duplicated.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcIO()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    DWORD dwInput, dwOutput;
    int nRtn;

    // Try to connect
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
```

```

        // Connection failed.
        // The port is not connected or the baudrate may be wrong
        return;
    }

    // Check I/O input
    nRtn = FAS_GetIOInput(nPortNo, iSlaveNo, &dwInput);
    _ASSERT(nRtn == FMM_OK);
    if (dwInput & SERVO_IN_BITMASK_LIMITP)
    {
        // Limit + input is ON..
    }

    if (dwInput & SERVO_IN_BITMASK_USERIN0)
    {
        // User Input 0 is ON.
    }

    // Turning ON 'Clear Position' and 'User Input 1' inputs and turning off 'Jog +' input.
    nRtn = FAS_SetIOInput(nPortNo, iSlaveNo, SERVO_IN_BITMASK_CLEARPOSITION |
SERVO_IN_BITMASK_USERIN1, SERVO_IN_BITMASK_PJOG);
    _ASSERT(nRtn == FMM_OK);

    // Check I/O output.
    nRtn = FAS_GetIOOutput(nPortNo, iSlaveNo, &dwOutput);
    _ASSERT(nRtn == FMM_OK);
    if (dwOutput & SERVO_OUT_BITMASK_USEROUT0)
    {
        // User Output 0 is ON.
    }

    // Turn off User Output 1 and 2 signals.
    nRtn = FAS_SetIOOutput(nPortNo, iSlaveNo, 0, SERVO_OUT_BITMASK_USEROUT1 |
SERVO_OUT_BITMASK_USEROUT2);
    _ASSERT(nRtn == FMM_OK);

    // Disconnect.
    FAS_Close(nPortNo);
}

```

See Also

FAS_GetIOInput

FAS_GetIOInput

To read I/O input values. For more information, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_GetIOInput(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD* dwIOInput
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

dwIOInput

Parameter pointer which input values will be saved.

Return Value

FMM_OK : Command has been normally performed.

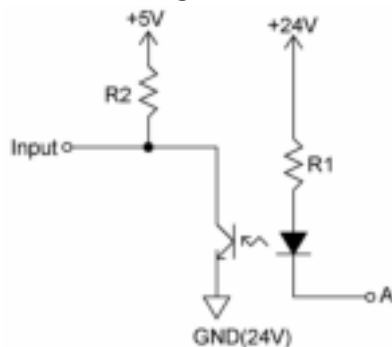
FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

There are 12 input pins in S-SERVO PlusR. The user can select and use 9 input pins of them. This function can read the input port status by 32bit. All of them are insulated by a photocoupler. (Refer to the figure.)



When Port A is supplied 24V from an external input port, the input is recognized to 5V(High)..

Example

Refer to 'FAS_SetIOInput' library.

See Also

FAS_SetIOInput

FAS_SetIOOutput

To read I/O output values. For more information, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_SetIOOutput(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD dwIOSetMask,
    DWORD dwIOCLRMask
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive..

dwIOSetMask

Output bitmask value to be set (On)

dwIOCLRMask

Output bitmask value be cleared (Off).

Return Value

FMM_OK : Command has been normally performed.

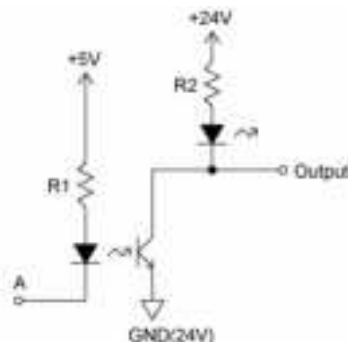
FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

There are 10 output pins in MECQ1. The user can select and use 9 output pins of them.



When output data is '1', Port A becomes 0V. When it is '0', Port A becomes +5V..

Be careful that dwIOSetMask bit and dwIOCLRMask bit are not duplicated.

Example

Refer to FAS_SetIOInput..

See Also

FAS_GetIOOutput

FAS_GetIOOutput

To read I/O output values. For more information, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_GetIOOutput(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD* dwIOOutput  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

dwIOInput

Parameter pointer which the output value will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_SetIOInput' library.

See Also

FAS_SetIOOutput

FAS_GetIOAssignMap

To read I/O Assign Map. For more information, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_GetIOAssignMap(
    BYTE nPortNo,
    BYTE iSlaveNo,
    BYTE iIOPinNo,
    BYTE* nIOLogic,
    BYTE* bLevel
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

iIOPinNo

I/O pin number to be read.

nIOLogic

Parameter pointer which the logic value assigned to a relevant pin will be saved

bLevel

Parameter pointer which the active level of relevant logic will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port..

Remarks

For nIOLogic, refer to 'Motion_define.h'.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcIOAssign()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    BYTE iPinNo;
    DWORD dwLogicMask;
    BYTE bLevel;
```

```

BYTE i;
int nRtn;

// Try to connect
if (FAS_Connect(nPortNo, 115200) == FALSE)
{
    // Connection failed
    // The port is not connected or the baudrate may be wrong.
    return;
}

// Check assigned information of input pin.
for (i=0; i</*Input Pin Count*/12; i++)
{
    nRtn = FAS_GetIOAssignMap(nPortNo, iSlaveNo, i, &dwLogicMask, &bLevel);
    _ASSERT(nRtn == FMM_OK);

    if (dwLogicMask != IN_LOGIC_NONE)
        printf("Input Pin %d : Logic Mask 0x%08X (%s)\n", i,
dwLogicMask, ((bLevel == LEVEL_LOW_ACTIVE) ? "Low Active" : "High Active"));
    else
        printf("Input Pin %d : Not assigned\n", i);
}

// Assign SERVOON Logic (Low Active) to input pin 3
iPinNo = 3;        // 0 ~ 11 value is available (Caution : 0 ~ 2 is fixed.).
nRtn      =      FAS_SetIOAssignMap(nPortNo,      iSlaveNo,      iPinNo,
SERVO_IN_BITMASK_SERVOON, LEVEL_LOW_ACTIVE);
_ASSERT(nRtn == FMM_OK);

// Check assign information of output pin
for (i=0; i<10/*Output Pin Count*/; i++)
{
    nRtn = FAS_GetIOAssignMap(nPortNo, iSlaveNo, 12/*Input Pin Count*/ + i,
&dwLogicMask, &bLevel);
    _ASSERT(nRtn == FMM_OK);

    if (dwLogicMask != OUT_LOGIC_NONE)
        printf("Output Pin %d : Logic Mask 0x%08X (%s)\n", i,
dwLogicMask, ((bLevel == LEVEL_LOW_ACTIVE) ? "Low Active" : "High Active"));
    else
        printf("Output Pin %d : Not assigned\n", i);
}

// Assign ALARM Logic (High Active) to output pin 9..
iPinNo = 9;        // 0 ~ 9 value is available (Caution : 0 is fixed to COMPOUT.).

```

```
        nRtn = FAS_SetIOAssignMap(nPortNo, iSlaveNo, 12/*Input Pin Count*/ + iPinNo,  
SERVO_OUT_BITMASK_ALARM, LEVEL_HIGH_ACTIVE);  
        _ASSERT(nRtn == FMM_OK);  
  
        // Disconnect.  
        FAS_Close(nPortNo);  
    }  
}
```

See Also

FAS_SetIOAssignMap

FAS_SetIOAssignMap

To set I/O Assign Map. For more information, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_SetIOAssignMap(
    BYTE nPortNo,
    BYTE iSlaveNo,
    BYTE iIOPinNo,
    BYTE nLogicNo,
    BYTE bLevel
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive..

iIOPinNo

I/O Pin number to be read.

nIOLogic

Logic value to be assigned to the relevant pin.

bLevel

Active Level value of the relevant logic.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : Designated iIOPinNo or nIOLogic value is out of range

Remarks

To save current setting values to the memory, 'FAS_SaveAllParameters' library should be run.

Example

Refer to 'FAS_GSetIOAssignMap' library.

See Also

FAS_GetIOAssignMap

FAS_IOAssignMapReadROM

To load the status of CN1 assignment being saved in ROM area.

Syntax

```
int FAS_PosTableReadROM(  
    BYTE nPortNo,  
    BYTE iSlaveNo  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMC_POSTABLE_ERROR : The error is generating during the reading Position Table.

Remarks

Example

See Also

FAS_GetIOAssignMap

2 - 7 . Position control Function

Function Name	Description
FAS_SetCommandPos	To set the command position value
FAS_SetActualPos	To set the current position to the actual position value
FAS_GetCommandPos	To read the current command position value
FAS_GetActualPos	To read the actual command position value
FAS_GetPosError	To read the difference between the actual position value and the command position value
FAS_GetActualVel	To read the actual running speed value while the motor is moving
FAS_ClearPosition	To set the command position and actual position value to '0'

FAS_SetCommandPos

To set the command position value of motor

Syntax

```
int FAS_SetCommandPos(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long lCmdPos
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lCmdPos

Command position value to be set.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port

Remarks

The user sets the position command (pulse output counter) value.

This function is generally used when the user sets the current position to coordinate that the user wants

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcClearPosition()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    int nRtn;

    // Try to connect.
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection failed
        // The port is not connected or the baudrate may be wrong.
        return;
    }
}
```

```
    }  
  
    // Initialize Command Position and Actual Position values to 0.  
    nRtn = FAS_SetCommandPos(nPortNo, iSlaveNo, 0);  
    _ASSERT(nRtn == FMM_OK);  
    nRtn = FAS_SetActualPos(nPortNo, iSlaveNo, 0);  
    _ASSERT(nRtn == FMM_OK);  
  
    // Disconnect.  
    FAS_Close(nPortNo);  
}
```

See Also

FAS_SetActualPos

FAS_SetActualPos

To set the actual position value of the motor

Syntax

```
int FAS_SetActualPos(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long lActPos  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lActPos

Actual position value to be set.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port..

Remarks

The user sets the encoder feedback counter value to the value that the user wants.

Example

Refer to 'FAS_GetActualPos' library.

See Also

FAS_SetCommandPos

FAS_GetCommandPos

To read the command position of the current motor.

Syntax

```
int FAS_GetCommandPos(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long* lCmdPos
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive.

lCmdPos

Parameter pointer that command position value will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port

Remarks

To read the position command (pulse output counter) value.

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcDisplayStatus()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    long lValue;
    int nRtn;

    // Try to connect
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection failed
        // The port is not connected or the baudrate may be wrong.
        return;
    }
}
```

```
// Check position information of MECQ1.
nRtn = FAS_GetCommandPos(nPortNo, iSlaveNo, &IValue);
_ASSERT(nRtn == FMM_OK);
printf("CMDPOS : %d \n", IValue);
nRtn = FAS_GetActualPos(nPortNo, iSlaveNo, &IValue);
_ASSERT(nRtn == FMM_OK);
printf("ACTPOS : %d \n", IValue);
nRtn = FAS_GetPosError(nPortNo, iSlaveNo, &IValue);
_ASSERT(nRtn == FMM_OK);
printf("POSERR : %d \n", IValue);
nRtn = FAS_GetActualVel(nPortNo, iSlaveNo, &IValue);
_ASSERT(nRtn == FMM_OK);
printf("ACTVEL : %d \n", IValue);

// Disconnect.
FAS_Close(nPortNo);
}
```

See Also

FAS_GetActualPos

FAS_GetActualPos

To read the actual position value of the motor.

Syntax

```
int FAS_GetActualPos(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long* lActPos  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lActPos

Parameter pointer which the actual position value will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

When the user decides the motor position and checks its actual position, this function is generally used.

Example

Refer to 'FAS_GetCommandPosition' library.

See Also

FAS_GetCommandPos

FAS_GetPosError

To read the actual position value of the motor

Syntax

```
int FAS_GetPosError(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long* lPosErr  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lPosErr

Parameter pointer which the position error value will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_GetCommandPosition' library.

See Also

FAS_GetCommandPos,

FAS_GetActualPos

FAS_GetActualVel

To read the actual velocity of the motor.

Syntax

```
int FAS_GetActualVel(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long* lActVel  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lActVel

Parameter pointer which the actual velocity value will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port

Remarks

Example

Refer to 'FAS_GetCOMmandPosition' library.

See Also

FAS_ClearPosition

To set the command position value and actual value to '0'.

Syntax

```
int FAS_SetCommandPos(
    BYTE nPortNo,
    BYTE iSlaveNo
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

The user sets the position command (pulse output counter) value.

This function is generally used when the user sets the current position to initial values..

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcClearPosition()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    int nRtn;

    // Try to connect.
    if (FAS_Connect(nPortNo, 115200) == FALSE)
    {
        // Connection failed.
        // The port is not connected or the baudrate may be wrong.
        return;
    }
}
```

```
        // Initialize Command Position and Actual Position values to 0.  
        nRtn = FAS_ClearPosition(nPortNo, iSlaveNo);  
        _ASSERT(nRtn == FMM_OK);  
  
        // Disconnect.  
        FAS_Close(nPortNo);  
    }  
}
```

See Also

FAS_SetActualPos, FAS_SetCommandPos

2 - 8 . Drive Status Control Function

Function Name	Description
FAS_GetIOAxisStatus	To read control I/O status, running status Flag value : The current input status value, the output setting status value, and the running status Flag value will be returned
FAS_GetMotionStatus	To read the current running progress status and its PT number : The command position value, the actual position value, the speed value will be returned
FAS_GetAllStatus	To read all status including the current I/O status at one time : This function is to combine 'FAS_GetIOAxisStatus' function and 'FAS_GetMotionStatus' function.:
FAS_GetAxisStatus	To read the running status Flag value of the relevant drive.

FAS_GetIOAxisStatus

To read I/O Input and Output values of the relevant drive, and the motor Axis Status.

Syntax

```
int FAS_GetIOAxisStatus(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD* dwInStatus,
    DWORD* dwOutStatus,
    DWORD* dwAxisStatus
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

dwInStatus

Parameter pointer which the I/O input value will be saved..

dwOutStatus

Parameter pointer which the I/O output value will be saved

dwAxisStatus

Parameter pointer which the axis status value of the relevant motor will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_GetMotionStatus

To read the motion status of current motor at one time.

Syntax

```
int FAS_GetMotionStatus(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long* ICmdPos,
    long* IActPos,
    long* IPosErr,
    long* IActVel,
    WORD* wPosItemNo
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

ICmdPos

Parameter pointer which the command position value will be saved.

IActPos

Parameter pointer which the actual position value will be saved.

IPosErr

Parameter pointer which the position error value will be saved.

IActVel

Parameter pointer which the actual velocity value will be saved.

wPosItemNo

Parameter pointer which current running item number in the Position Table will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port..

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_GetAllStatus

To read I/O Input and Output values of the relevant drive, the motor Axis Status, the motor motion status

Syntax

```
int FAS_GetAllStatus(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD* dwInStatus,
    DWORD* dwOutStatus,
    DWORD* dwAxisStatus,
    long* lCmdPos,
    long* lActPos,
    long* lPosErr,
    long* lActVel,
    WORD* wPosItemNo
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

dwInStatus

Parameter pointer which the I/O input value will be saved..

dwOutStatus

Parameter pointer which the I/O output value will be saved.

dwAxisStatus

Parameter pointer which the axis status value of the relevant motor will be

lCmdPos

Parameter pointer which the command position value will be saved.

lActPos

Parameter pointer which the actual position value will be saved.

lPosErr

Parameter pointer which the position error value will be saved.

lActVel

Parameter pointer which the actual velocity value will be saved.

wPosItemNo

Parameter pointer which current running item number in the Position Table will be saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library

See Also

FAS_GetAxisStatus

FAS_GetMotionStatus

FAS_GetAxisStatus

To read the motor Axis Status value. For status Flag, refer to '1-2. Structure of Frame Type'.

Syntax

```
int FAS_GetAxisStatus(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD* dwAxisStatus  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive

dwAxisStatus

Parameter pointer which the axis status value of the relevant motor.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library..

See Also

2 - 9 . Running Control Function

Function Name	Description
FAS_MoveStop	The motor in running is decelerated and stopped.
FAS_EmergencyStop	The motor in running stops immediately without deceleration
FAS_MoveOriginSingleAxis	The motor starts the origin return.
FAS_MoveSingleAxisAbsPos	The motor moves as much as the given absolute position value.
FAS_MoveSingleAxisIncPos	The motor moves as much as the given incremental position value.
FAS_MoveToLimit	The motor moves up to the position that the limit sensor is detected.
FAS_MoveVelocity	The motor moves to the given velocity and direction: This function is available to Jog motion.
FAS_PositionAbsOverride	While the motor is running, the target absolute position value [pulse] is changed.
FAS_PositionIncOverride	While the motor is running, the target incremental position value [pulse] is changed.
FAS_VelocityOverride	While the motor is running, the running velocity value [pulse] is changed.
FAS_AllMoveStop	All motors that connected in same port are decelerate and stopped.
FAS_AllEmergencyStop	All motors that connected in same port are directly stop without deceleration.
FAS_AllMoveOriginSingleAxis	All motors that connected in same port are starts the origin return.
FAS_AllMoveSingleAxisAbsPos	All motors that connected in same port moves as much as the given absolute position value.
FAS_AllMoveSingleAxisIncPos	All motors that connected in same port moves as much as the given incremental position value.
FAS_MoveLinearAbsPos	More than 2 motors that connected in same port Linear Interpolation moves as much as the given absolute position value.
FAS_MoveLinearIncPos	More than 2 motors that connected in same port Linear Interpolation moves as much as the given incremental position value.

FAS_MoveSingleAxisAbsPosEx	The motor moves as much as the given absolute position value with custom accel/decel time value.
FAS_MoveSingleAxisIncPosEx	The motor moves as much as the given incremental position value with custom accel/decel time value.
FAS_MoveVelocityEx	The motor moves to the given velocity and direction: This function is available to Jog motion with custom accel/decel time value.
FAS_MovePause	The motor starts pause in running or the motor starts again In pause status.

FAS_MoveStop

To stop the motor

Syntax

```
int FAS_MoveStop(
    BYTE nPortNo,
    BYTE iSlaveNo,
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library..

See Also

FAS_EmergencyStop

To stop the motor without deceleration

Syntax

```
int FAS_EmergencyStop(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

This function does not include deceleration phase. So, the user must be careful so that the machine cannot be impacted.

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_MoveOriginSingleAxis

To search the origin of system. For more information, refer to '[MECQ1_Manual_Text 8.3 Origin Return](#)'

Syntax

```
int FAS_MoveOriginSingleAxis(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_MoveSingleAxisAbsPos

To move the motor to the absolute coordinate

Syntax

```
int FAS_MoveSingleAxisAbsPos(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long lAbsPos,
    DWORD lVelocity,
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lAbsPos

Absolute coordinate of position to move.

lVelocity

Velocity when the motor moves

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

```
#include "FAS_ EziMOTIONPlusR.h"

void funcMove()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    DWORD dwAxisStatus, dwInput;
    EZISERVO_AXISSTATUS stAxisStatus;
    long lAbsPos, lIncPos, lVelocity;
    int nRtn;
```

```

// Try to connect.
if (FAS_Connect(nPortNo, 115200) == FALSE)
{
    // Connection failed.
    // The port is not connected or the baudrate may be wrong.
    return;
}

// Check error and Servo ON status.
nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &dwAxisStatus);
_ASSERT(nRtn == FMM_OK);
stAxisStatus.dwValue = dwAxisStatus;

//if (dwAxisStatus & 0x00000001)
if (stAxisStatus.FFLAG_ERRORALL)
    FAS_ServoAlarmReset(nPortNo, iSlaveNo);
//if ((dwAxisStatus & 0x00100000) == 0x00)
if (stAxisStatus.FFLAG_SERVOON == 0)
    FAS_ServoEnable(nPortNo, iSlaveNo, TRUE);

// Check input status.
nRtn = FAS_GetIOInput(nPortNo, iSlaveNo, &dwInput);
_ASSERT(nRtn == FMM_OK);

if (dwInput & (SERVO_IN_LOGIC_STOP | SERVO_IN_LOGIC_PAUSE |
SERVO_IN_LOGIC_ESTOP))
    FAS_SetIOInput(nPortNo, iSlaveNo, 0, SERVO_IN_LOGIC_STOP |
SERVO_IN_LOGIC_PAUSE | SERVO_IN_LOGIC_ESTOP);

// Increase the motor to 15000 pulse.
lIncPos = 15000;
lVelocity = 30000;
nRtn = FAS_MoveSingleAxisIncPos(nPortNo, iSlaveNo, lIncPos, lVelocity);
_ASSERT(nRtn == FMM_OK);

// Stand by until motion command is completely finished.
do
{
    Sleep(1);

    nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &dwAxisStatus);
    _ASSERT(nRtn == FMM_OK);
    stAxisStatus.dwValue = dwAxisStatus;
}
while (stAxisStatus.FFLAG_MOTIONING);

```

```
// Move the motor to '0'.
IAbsPos = 0;
IVelocity = 20000;
nRtn = FAS_MoveSingleAxisAbsPos(nPortNo, iSlaveNo, IAbsPos, IVelocity);
_ASSERT(nRtn == FMM_OK);

// Stand by until motion command is completely finished.
do
{
    Sleep(1);

    nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &dwAxisStatus);
    _ASSERT(nRtn == FMM_OK);
    stAxisStatus.dwValue = dwAxisStatus;
}
while (stAxisStatus.FFLAG_MOTIONING);

// Disconnect.
FAS_Close(nPortNo);
}
```

See Also

FAS_MoveSingleAxisIncPos

To move the motor to the incremental coordinate value.

Syntax

```
int FAS_MoveSingleAxisIncPos(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long lIncPos,  
    DWORD lVelocity  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lIncPos

Incremental coordinate of position to move.

lVelocity

Velocity when the motor moves.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_MoveToLimit

To give the motor a command to search the limit sensor.

Syntax

```
int FAS_MoveToLimit(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD IVelocity,  
    int iLimitDir,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

IVelocity

Velocity when the motor moves.

iLimitDir

Limit direction which the motor moves (0: -Limit, 1: +Limit)

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_MoveVelocity

To move the motor to the relevant direction and velocity. This function is also available for Jog motion.

Syntax

```
int FAS_MoveVelocity(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD lVelocity,  
    int iVelDir  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lVelocity

Velocity when the motor moves.

iVelDir

Direction which the motor moves (0: -Jog, 1: +Jog).

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_PositionAbsOverride

To change the incremental position value set while the motor moves to the incremental position.

Syntax

```
int FAS_PositionAbsOverride(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long IOverridePos
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive.

IOverridePos

Absolute coordinate position value to be changed.

Return Value

FMM_OK : Command has been normally performed.

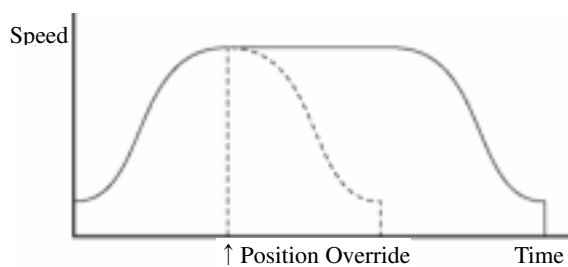
FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

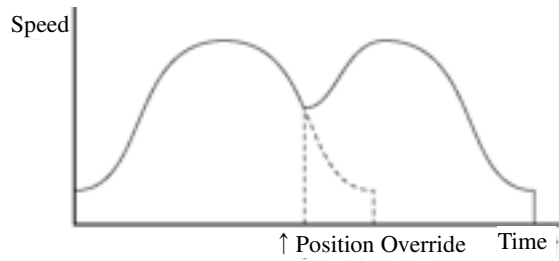
FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

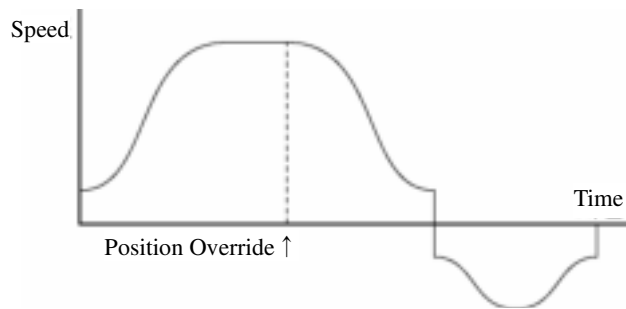
- 1) If the target position is set to the farther coordinate than the original target position while the motor moves to the accelerated or uniform velocity, the motor moves to the velocity pattern until then and stops the target position.



- 2) If the target position is changed while the motor is decelerated, it is again accelerated up to the uniform velocity and then stops to the target position..



- 3) . If the changed target position is set to the closer coordinate than the original target position, the motor move to the changed target position



- 3) It can not be used with 'FAS_PositionAbsOverride' library at the same time .
It can not be used with 'FAS_VelocityOverride' library at the same time.

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library..

See Also

FAS_PositionIncOverride

FAS_PositionIncOverride

To change the incremental position value set while the motor moves to the incremental position.

Syntax

```
int FAS_PositionIncOverride(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long IOverridePos  
);
```

Parameters

nPortNo

Port number of relevant drive..

iSlaveNo

Slave number of relevant drive.

IOverridePos

Incremental coordinate position value to be changed.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

- 1) Refer to 'FAS_PositionAbsOverride' library
- 2) It can not be used with 'FAS_PositionIncOverride' library at the same time.
It can not be used with 'FAS_VelocityOverride' library at the same time..

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_PositionAbsOverride

FAS_VelocityOverride

To change the set up velocity while the motor moving

Syntax

```
int FAS_VelocityOverride(
    BYTE nPortNo,
    BYTE iSlaveNo,
    DWORD IVelocity
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

IVelocity

Velocity to be changed in [pps].

Return Value

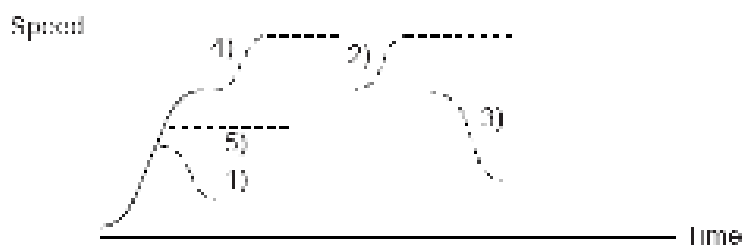
FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks



- 1) In case of $((\text{change speed}) < (\text{speed before change}))$, the motor reaches the change speed through acceleration/deceleration using a new velocity pattern.
- 5) In case of $((\text{change speed}) \geq (\text{speed before change}))$, the motor reaches the change speed through acceleration/deceleration without any new velocity pattern.
- 4) The motor reaches the 'speed before change' without a change of the velocity pattern and then it reaches the 'change speed' by a new velocity pattern.
- 2), 3) After acceleration/deceleration is finished, the motor reaches the change speed corresponding to the velocity pattern of the 'change speed'

- It can not be used with 'FAS_PositionIncOverride' library at the same time
It can not be used with 'FAS_PositionAbsOverride' library at the same time.

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library..

See Also

FAS_AllMoveStop

To stop the motor that connected in same port.

Syntax

```
int FAS_AllMoveStop(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive. (must be '99')

Return Value

No response.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_AllEmergencyStop

To stop the motor that connected in same port without deceleration.

Syntax

```
int FAS_AllEmergencyStop(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive. (must be '99').

Return Value

No response.

Remarks

This function does not include deceleration phase. So, the user must be careful so that the machine cannot be impacted.

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_AllMoveOriginSingleAxis

To search the origin of system for all motor that is connected in same port. For more information, refer to '[MECQ1_Manual_Text 8.3 Origin Return](#)'.

Syntax

```
int FAS_AllMoveOriginSingleAxis(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive. (must be '99').

Return Value

No response.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_AllMoveSingleAxisAbsPos

To move the motor that connected in same port to the absolute coordinate.

Syntax

```
int FAS_AllMoveSingleAxisAbsPos(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long lAbsPos,  
    DWORD lVelocity,  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive. (must be '99').

lAbsPos

Absolute coordinate of position to move

lVelocity

Velocity when the motor moves.

Return Value

No response.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_AllMoveSingleAxisIncPos

To move the motor that connected in same port to the incremental coordinate value.

Syntax

```
int FAS_AllMoveSingleAxisIncPos(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long lIncPos,  
    DWORD lVelocity  
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive. (must be '99').

lIncPos

Incremental coordinate of position to move.

lVelocity

Velocity when the motor moves.

Return Value

No response.

Remarks

Example

Refer to 'FAS_MoveSingleAxisAbsPos' library.

See Also

FAS_MoveLinearAbsPos

To move with Linear Interpolation function more than 2 motors that connected in same port to the absolute coordinate.

Syntax

```
int FAS_MoveLinearAbsPos(  
    BYTE nPortNo,  
    BYTE nNoOfslaves,  
    BYTE *iSlavesNo,  
    long *lAbsPos,  
    DWORD lFeedrate,  
    DWORD wAccelTime,  
);
```

Parameters

nPortNo

Port number of relevant drive.

nNoOfSlaves

Slave numbers for Linear motioning.

iSlavesNo

Array of Slave numbers.

lAbsPos

Array of position value for each slave.

lFeedrate

Speed value when moving

wAccelTime

Time value of Acceleration & deceleration section when moving

Return Value

FMM_OK : Command has been successfully performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

FAS_MoveLinearIncPos

To move with Linear Interpolation function more than 2 motors that connected in same port to the incremental coordinate.

Syntax

```
int FAS_MoveLinearIncPos(
    BYTE nPortNo,
    BYTE nNoOfslaves,
    BYTE *iSlavesNo,
    long *lIncPos,
    DWORD lFeedrate,
    DWORD wAccelTime,
);
```

Parameters

nPortNo

Port number of relevant drive.

nNoOfSlaves

Slave numbers for Linear motioning.

iSlavesNo

Array of Slave numbers.

lIncPos

Array of position value for each slave.

lFeedrate

Speed value when moving.

wAccelTime

Time value of Acceleration & deceleration section when moving.

Return Value

FMM_OK : Command has been successfully performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port

Remarks

FAS_MoveSingleAxisAbsPosEx

To move the motor to the absolute coordinate. (possible to appoint the running acc/deceleration time)

Syntax

```
int FAS_MoveSingleAxisAbsPosEx(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    long lAbsPos,  
    DWORD lVelocity,  
    MOTION_OPTION_EX* lpExOption  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

lAbsPos

Absolute coordinate of position to move

lVelocity

Velocity when the motor moves

lpExOption

Custom option.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Refer to MOTION_OPTION_EX struct.

Example

```
#include "FAS_ EziMOTIONPlusR.h"  
  
void funcMoveEx()  
{  
    BYTE nPortNo = 1; // COMM Port number  
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)  
    DWORD dwAxisStatus, dwInput;  
    EZISERVO_AXISSTATUS stAxisStatus;  
    long lAbsPos, lIncPos, lVelocity;
```

```

MOTION_OPTION_EX opt = {0};
int nRtn;

// Try to connect.
if (FAS_Connect(nPortNo, 115200) == FALSE)
{
    // Connection failed..
    // The port number may be wrong, or incorrect Baudrate.
    return;
}

// Moving motor with different acc/dec time. : FAS_MoveSingleAxisIncPosEx
lIncPos = 15000;
lVelocity = 30000;

opt.flagOption.BIT_USE_CUSTOMACCEL = 1;
opt.flagOption.BIT_USE_CUSTOMDECEL = 1;

opt.wCustomAccelTime = 50;
opt.wCustomDecelTime = 200;

nRtn = FAS_MoveSingleAxisIncPosEx(nPortNo, iSlaveNo, lIncPos, lVelocity, &opt);
_ASSERT(nRtn == FMM_OK);

// Waiting until Motion command has finished..
do
{
    Sleep(1);

    nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &dwAxisStatus);
    _ASSERT(nRtn == FMM_OK);
    stAxisStatus.dwValue = dwAxisStatus;
}
while (stAxisStatus.FFLAG_MOTIONING);

// Moving the motor to position 0
lAbsPos = 0;
lVelocity = 20000;
nRtn = FAS_MoveSingleAxisAbsPos(nPortNo, iSlaveNo, lAbsPos, lVelocity);
_ASSERT(nRtn == FMM_OK);

// Waiting until Motion command has finished
do
{
    Sleep(1);

```

```
        nRtn = FAS_GetAxisStatus(nPortNo, iSlaveNo, &dwAxisStatus);
        _ASSERT(nRtn == FMM_OK);
        stAxisStatus.dwValue = dwAxisStatus;
    }
    while (stAxisStatus.FFLAG_MOTIONING);

    // Disconnect.
    FAS_Close(nPortNo);
}
```

See Also

FAS_MoveSingleAxisIncPosEx

To move the motor to the specific Incremental coordinate (possible to appoint the running acc/decelerationtime)

Syntax

```
int FAS_MoveSingleAxisIncPosEx(
    BYTE nPortNo,
    BYTE iSlaveNo,
    long lIncPos,
    DWORD lVelocity,
    MOTION_OPTION_EX* lpExOption
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive.

lIncPos

Incremental coordinate of position to move.

lVelocity

Velocity when the motor moves.

lpExOption

Custom option.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

See Also

FAS_MoveVelocityEx

To move the motor to the relevant direction and velocity. This function is also available for Jog motion..

Syntax

```
int FAS_MoveVelocityEx (  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD lVelocity,  
    int iVelDir,  
    VELOCITY_OPTION_EX* lpExOption  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive

lVelocity

Velocity when the motor moves.

iVelDir

Direction which the motor moves (0: -Jog, 1: +Jog)

lpExOption

Custom option.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Refer to VELOCITY_OPTION_EX struct.

Example

```
#include "FAS_EziMOTIONPlusR.h"  
  
void funcMoveVelocityEx()  
{  
    BYTE nPortNo = 1;        // COMM Port number  
    BYTE iSlaveNo = 0;      // Slave No (0 ~ 15)  
    long lVelocity;  
    VELOCITY_OPTION_EX opt = {0};
```

```
int nRtn;

// Try to connect.
if (FAS_Connect(nPortNo, 115200) == FALSE)
{
    // Connection failed..
    // The port number may be wrong, or incorrect Baudrate.
    return;
}

// Moving motor with different acc/dec time. : FAS_MoveSingleAxisIncPosEx
lVelocity = 30000;

opt.flagOption.BIT_USE_CUSTOMACCDEC = 1;
opt.wCustomAccDecTime = 300;

nRtn = FAS_MoveVelocityEx(nPortNo, iSlaveNo, lVelocity, DIR_INC, &opt);
_ASSERT(nRtn == FMM_OK);

Sleep(5000);
FAS_MoveStop(nPortNo, iSlaveNo);
}
```

See Also

2 - 1 0 . Position Table Control Function

Function Name	Description
FAS_PosTableReadItem	To read items of RAM area in the specific all items of position table
FAS_PosTableWriteItem	To save specific all items of position table items to RAM area
FAS_PosTableWriteROM	To save all of position table values to ROM area : Total 256 PT values are saved.
FAS_PosTableReadROM	To read position table values in ROM area : Total 256 PT values are read.
FAS_PosTableRunItem	The motor starts to run from the designated position table in sequence:
FAS_PosTableReadOneItem	To read items of RAM area in the specific one item of position table
FAS_PosTableWriteOneItem	To save specific one item of position table items to RAM area

FAS_PosTableReadItem

To read a specific item in the position table

Syntax

```
int FAS_PosTableReadItem(
    BYTE nPortNo,
    BYTE iSlaveNo,
    WORD wItemNo,
    LPITEM_NODE lpItem
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive.

wItemNo

Item number to be read.

lpItem

Item structure pointer which item value is saved.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range

Remarks

Example

```
#include "FAS_EziMOTIONPlusR.h"

void funcPosTable()
{
    BYTE nPortNo = 1; // COMM Port number
    BYTE iSlaveNo = 0; // Slave No (0 ~ 15)
    WORD wItemNo;
    ITEM_NODE nodeItem;
    int nRtn;

    // Try to connect
    if (FAS_Connect(nPortNo, 115200) == FALSE)
```

```
{
    // Connection failed.
    // The port is not connected or the baudrate may be wrong.
    return;
}

// Read No.20 Position table value and edit the position value.
wItemNo = 20;
nRtn = FAS_PosTableReadItem(nPortNo, iSlaveNo, wItemNo, &nodeItem);
_ASSERT(nRtn == FMM_OK);

nodeItem.lPosition = 260000; // Change the position value to 260000..
nodeItem.wBranch = 23;           // Set next command as 23
nodeItem.wContinuous = 1;       // Next command should be connected
without deceleration..

nRtn = FAS_PosTableWriteItem(nPortNo, iSlaveNo, wItemNo, &nodeItem);
_ASSERT(nRtn == FMM_OK);

// Call the value in the ROM regardless of edited position table data
nRtn = FAS_PosTableReadROM(nPortNo, iSlaveNo);
_ASSERT(nRtn == FMM_OK);

// Save edited position table data in the ROM.
nRtn = FAS_PosTableWriteROM(nPortNo, iSlaveNo);
_ASSERT(nRtn == FMM_OK);

// Disconnect
FAS_Close(nPortNo);
}
```

See Also

FAS_PosTableWriteItem

FAS_PosTableWriteItem

To edit specific items in the position table

Syntax

```
int FAS_PosTableWriteItem(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    WORD wItemNo,  
    LPITEM_NODE lpItem  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

wItemNo

Item number to be edited.

lpItem

Item structure pointer to be edited.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMC_POSTABLE_ERROR : An error occurs while position table is being written.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range.

Remarks

Position Table data is saved to RAM / ROM area,

This function acts to save data to RAM area. When power is off, data is deleted.

Example

See Also

FAS_PosTableReadItem

FAS_PosTableWriteROM

To save all current position table items to ROM area

Syntax

```
int FAS_PosTableWriteROM(  
    BYTE nPortNo,  
    BYTE iSlaveNo  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMC_POSTABLE_ERROR : An error occurs while position table is being saved.

Remarks

Position table data is saved to RAM / ROM area,

This function acts to save data to ROM area. Even though power is off, data is preserved..

Example

See Also

FAS_PosTableReadROM

FAS_PosTableReadROM

To read position table items being saved in ROM area

Syntax

```
int FAS_PosTableReadROM(  
    BYTE nPortNo,  
    BYTE iSlaveNo  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive..

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMC_POSTABLE_ERROR : An error occurs while position table is being read.

Remarks

Example

See Also

FAS_PosTableWriteROM

FAS_PosTableRunItem

To perform command from a specific item in the position table.

Syntax

```
int FAS_PosTableRunItem(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    WORD wItemNo  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

wItemNo

Item number to start motion.

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range

Remarks

Example

See Also

FAS_GetAllStatus

FAS_MoveStop

FAS_EmergencyStop

FAS_PosTableReadOneItem

To read a one item in the specific position table

Syntax

```
int FAS_PosTableReadOneItem(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    WORD wItemNo,  
    WORD wOffset,  
    long* lPosItemVal  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

wItemNo

Item number to be read.

wOffset

offset value which will be read in PT items. (Refer to '[1-2-6. Position Table Item](#)')

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range.

Remarks

Example

See Also

FAS_PosTableReadItem

FAS_PosTableWriteOneItem

FAS_PosTableWriteOneItem

To edit one item in the specific position table.

Syntax

```
int FAS_PosTableWriteOneItem(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    WORD wItemNo,  
    WORD wOffset,  
    long lPosItemVal  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

wItemNo

Item number to be edited.

wOffset

offset value which will be save in PT items. (Refer to '[1-2-6. Position Table Item](#)')

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMC_POSTABLE_ERROR : An error occurs while position table is being written.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range.

Remarks

Example

See Also

FAS_PosTableWriteItem

FAS_PosTableReadOneItem

2 - 1 1 . Other Control Function

Function Name	Description
FAS_TriggerOutput_RunA	To Start/Stop command for 'Compare Out' signal
FAS_TriggerOutput_Status	To check if the trigger output pulse is working or not.
FAS_MovePush	To request push motion(maintain specified motor torque) command
FAS_GetPushStatus	To request the current push motion status

FAS_TriggerOutput_RunA

To start/stop the digital output signal(Compare Out pin) when reaching the specific Target position.

Syntax

```
int FAS_TriggerOutput_RunA(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BOOL bStartTrigger,  
    long lStartPos,  
    DWORD dwPeriod,  
    DWORD dwPulseTime,  
);
```

Parameters

nPortNo

Port number of relevant drive..

iSlaveNo

Slave number of relevant drive.

bStartTrigger

Output start/stop command (1:start, 0:stop)

long lStartPos

Output start position [pulse]

DWORD dwPeriod

Period of output signal [pulse]

DWORD dwPulseTime

Width of output signal [msec]

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

FMM_INVALID_PARAMETER_NUM : wItemNo is out of range.

Remarks

Example

See Also

FAS_TriggerOutput_Status

FAS_TriggerOutput_Status

To check if the trigger output is working or not..

Syntax

```
int FAS_TriggerOutput_Status(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BYTE* bTriggerStatus  
);
```

Parameters

nPortNo

Port number of relevant.

iSlaveNo

Slave number of relevant drive..

bTriggerStatus

Current status of signal output

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

See Also

FAS_TriggerOutput_RunA

FAS_MovePush

Movement while maintaining a predetermined strength from a specific location by moving the position command, and moving since in contact with the object (work) only to stop the move that power is the ability to continue (maintain specified motor torque)

Syntax

```
int FAS_MovePush(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    DWORD dwStartSpd,  
    DWORD dwMoveSpd,  
    long lPosition,  
    WORD wAccel, WORD wDecel,  
    WORD wPushRate,  
    DWORD dwPushSpd,  
    long lEndPosition,  
    WORD wPushMode  
);
```

Parameters

nPortNo

Port number of relevant drive

iSlaveNo

Slave number of relevant drive.

DWORD dwStartSpd

Start speed of position command.

DWORD dwMoveSpd

Move speed of position command.

long lPosition

Absolute target position of position command.

WORD wAccel

Accel time of position command

WORD wDecel

Deceleration time of position command.

WORD wPushRate

Torque ratio of Push motion..

DWORD dwPushSpd

Move speed of Push motion..

long lEndPosition

Absolute target position of push motion..

WORD wPushMode

Select the push mode (Stop or Non-stop)

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

See Also

FAS_GetPushStatus

FAS_GetPushStatus

The function to check progressing current push motion status..

Syntax

```
int FAS_MovePush(  
    BYTE nPortNo,  
    BYTE iSlaveNo,  
    BYTE* nPushStatus  
);
```

Parameters

nPortNo

Port number of relevant drive.

iSlaveNo

Slave number of relevant drive.

BYTE nPushStatus*

Status value of push motion. (refer to '1-2-1. FrameType and Data Configuration')

Return Value

FMM_OK : Command has been normally performed.

FMM_NOT_OPEN : The drive has not been connected yet.

FMM_INVALID_PORT_NUM : There is no nPort in the connected ports.

FMM_INVALID_SLAVE_NUM : There is no drive of iSlaveNo in the relevant port.

Remarks

Example

See Also

FAS_Move Push

3 . Protocol for PLC Program



Next window will be open when you click icon in User Program(GUI) installed folder.

Next test procedure will help you to understand the protocol programming.

(1) Servo ON/OFF command



The header and tail information is needed for protocol programming. Additionally Frame Data (Slave ID, Frame type, Data and CRC) is also needed in every protocol with header and tail.

- 1) Insert 'Comm Port' number and click 'Connect' button.
- 2) Header : Click 'Header' and you can see '[0XAA][0xCC]' on 'Send Buffer' window.
- 3) Slave ID : Insert your slave number(above example is '0') and click 'SlaveNo'.
- 4) Frame type : Insert 'Frame type'.

You can find next table information in '1-2-1. Frame Type and Data Configuration' on MECQ1_Manual_ Communication Function.

Frame type	DLL Library name	Data		
42 (0x2A)	FAS_ServoEnable	Setting the Servo ON/OFF status. Sending : 1 byte <table border="1" style="margin-left: 20px;"> <tr> <td>1 byte</td> </tr> <tr> <td>0:OFF, 1:ON</td> </tr> </table>	1 byte	0:OFF, 1:ON
1 byte				
0:OFF, 1:ON				

Insert '42' in area and click '1 byte' because the size of Frame Type is 1 byte..

- 5) Data : To make Servo ON status, the data is '1'. Insert '1' and click 1 byte'.
- 6) CRC : Click 'CRC' and the calculated result value(2 bytes) is displayed on

'Send Buffer' window.

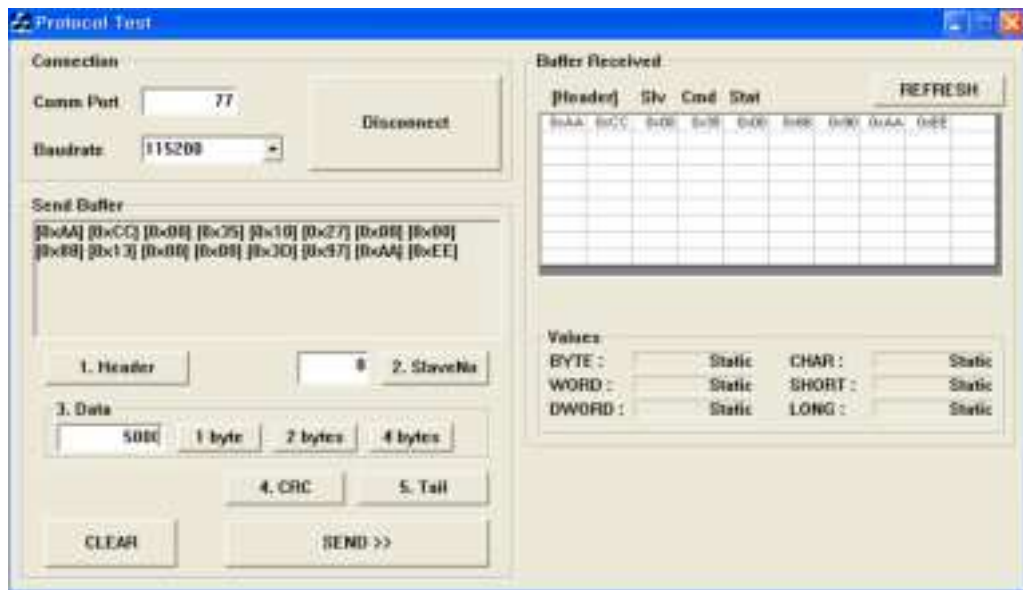
7) Tail : click 'Tail' and you can see '[0XAA][0xEE]' on 'Send Buffer' window.

8) Finally click 'Send' button to send command characters to MECQ1.

You can check the motor torque and LED flash for Servo ON status.

9) After sending command you can check the answering informations from MECQ1 on 'Buffer Received' window.

(2) Motion Command



- 1) Header
- 2) Slave No.
- 3) Frame type : insert '53' in 1 byte size for 'Incremental Move'command.
- 4) Data(Position value) : insert '10000' and click '4byte'
- 5) Data(Running speed) : insert '5000' and click '4 byte'
- 6) CRC
- 7) Tail
- 8) Send : In case of parameter is set to 'default' , motor has 1 revolution.
Command No '53' is incremental command, so re-click 'send' button, motor move again I more revolution.

(3) PLC Programming

There are some difference exist between real protocol and above example as below.

Above testing GUI excuates following fuctions automatically.

- 1) To use 'Byte stuffing' method to have clearly distinguish among the Header and Tail.
[Refer to 「1-1-2. RS-485 communication Protocol」](#)
- 2) To use CRC function to check communication error
- 3) [Refer to 「1-1-3. CRC calculation example」](#)