FASTECH

Fast, Accurate, Smooth Motion Control

Ezi-SERVOII-EC Operation Manual
< Parker 'PAC' Controller>

Parker

Ezi-SERVO®

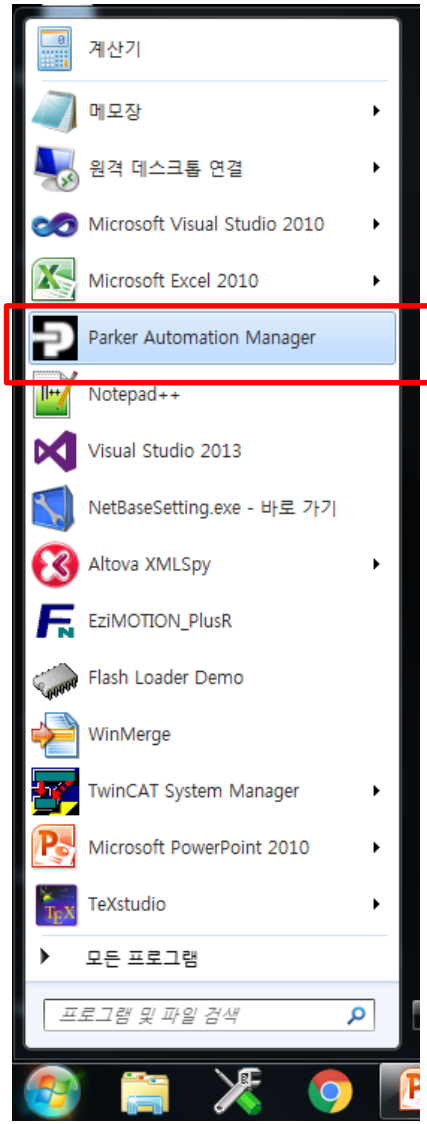
Closed Loop Stepping System

▣ Ezi-SERVOII-EC Data Download [Manual]

❑ **Manual** : Download the EtherCAT manual on FASTECH website (www.fastech.co.kr)

SERVO®
Closed Loop Stepping System

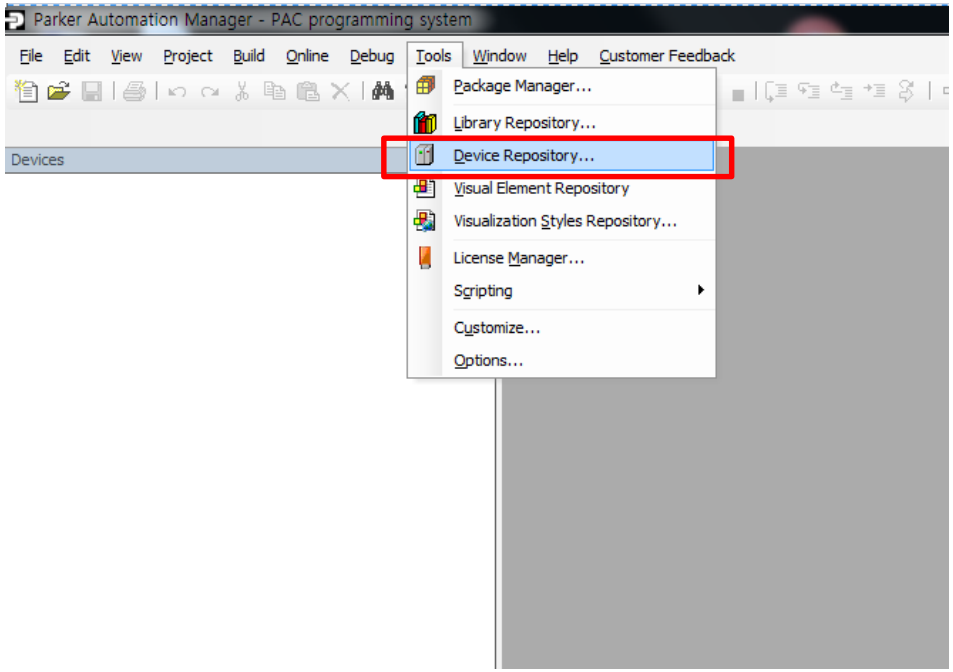
Save ESI(XML) file

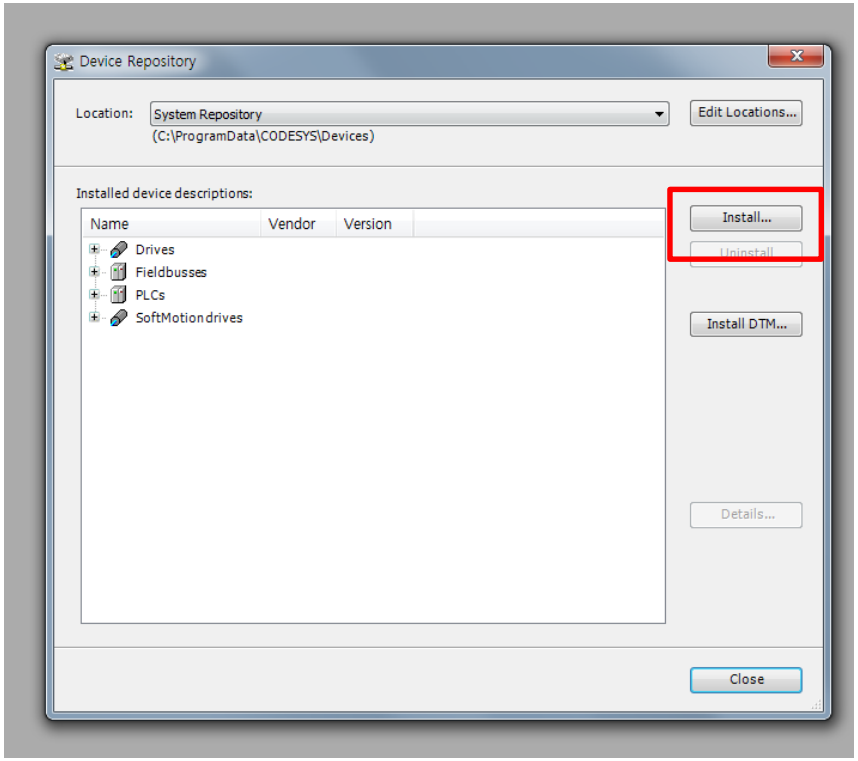


Launch the Parker Automation Manager Software

Save ESI(XML) file

Click “Tools” and “Device Repository” and click Install

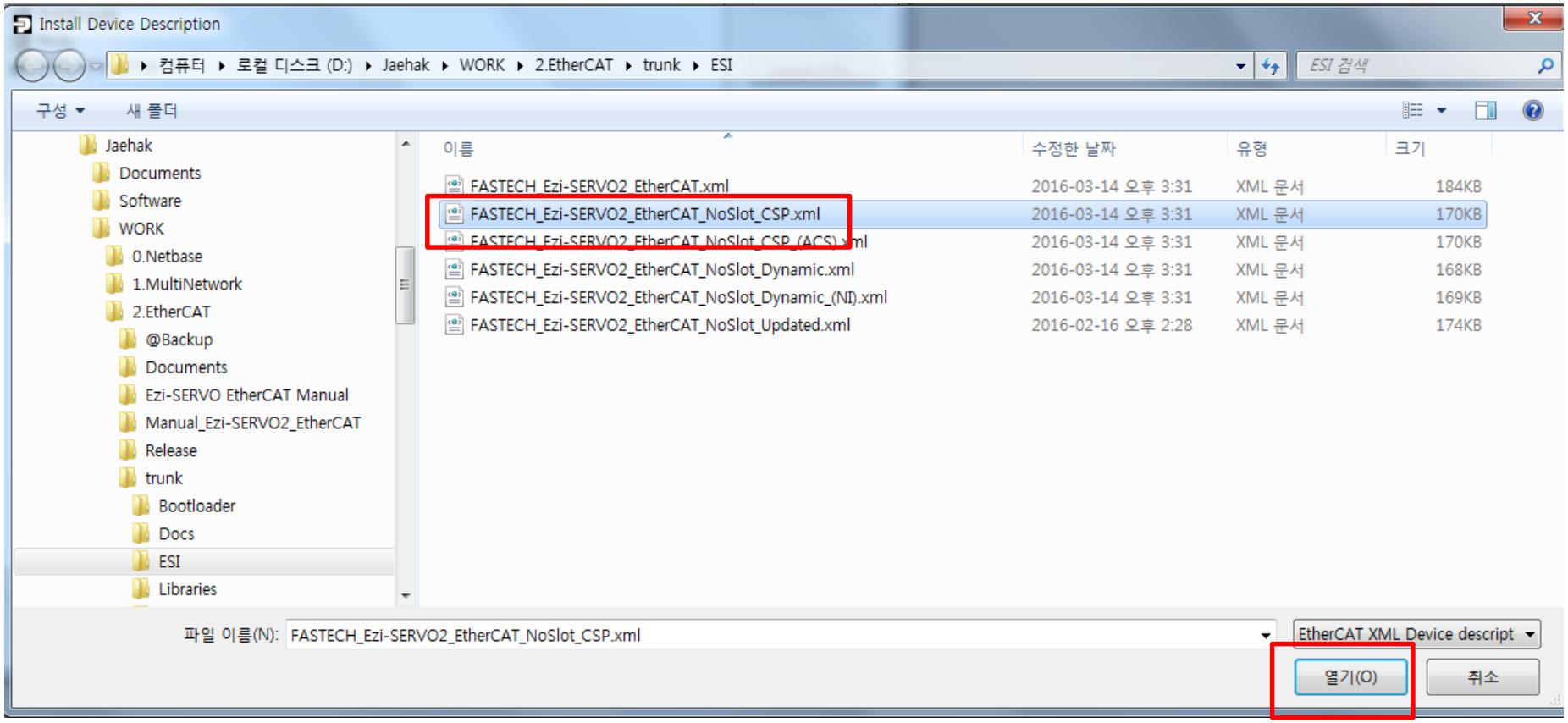




Ezi-SERVO®
Closed Loop Stepping System

Save ESI(XML) file

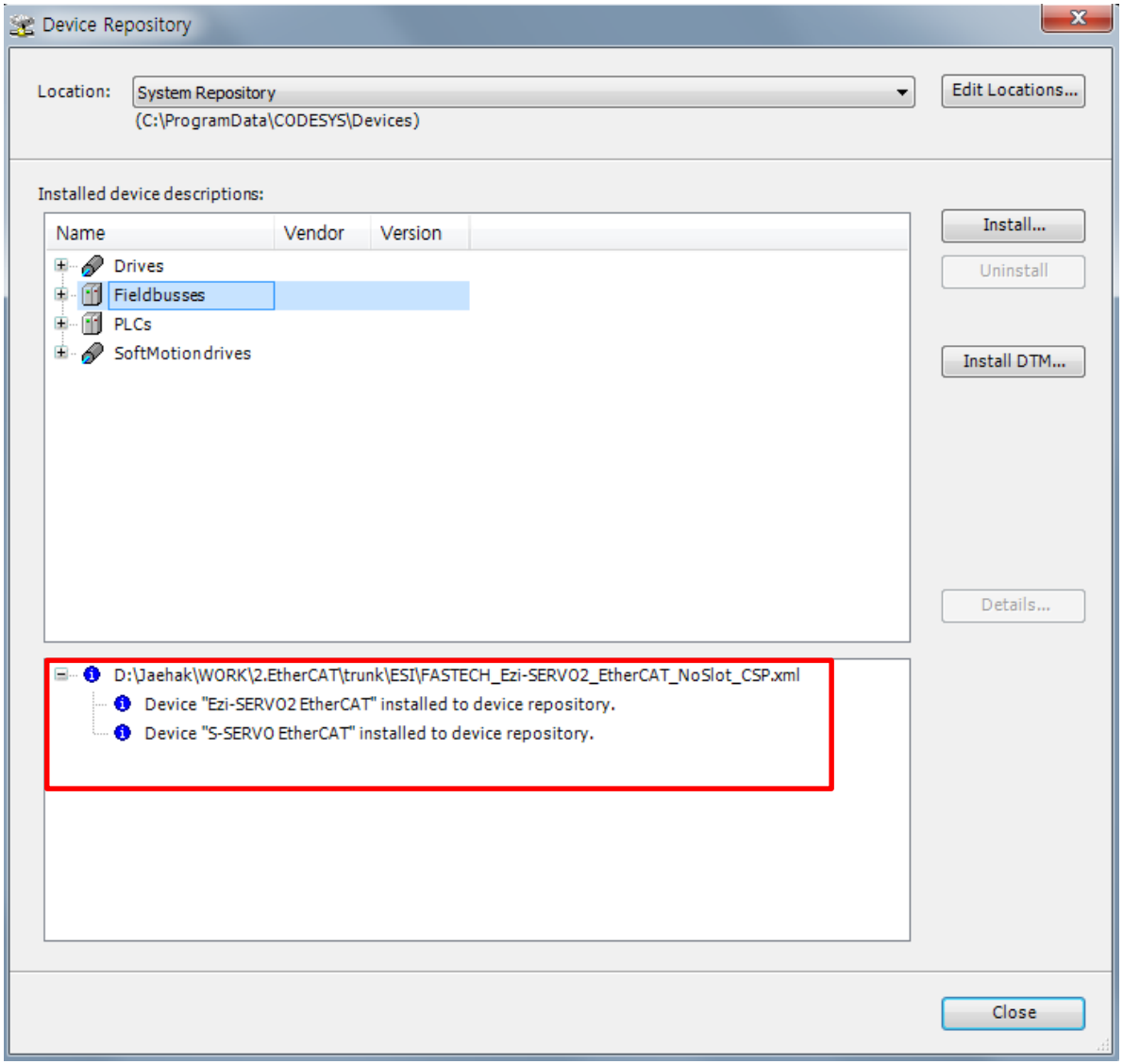
Click “FASTECH_Ezi-SERVO2_EtherCAT_NoSlot_CSP.xml” and click “열기”



Ezi-SERVO®
Closed Loop Stepping System

Save ESI(XML) file

- Then you can see XML file is saved as below

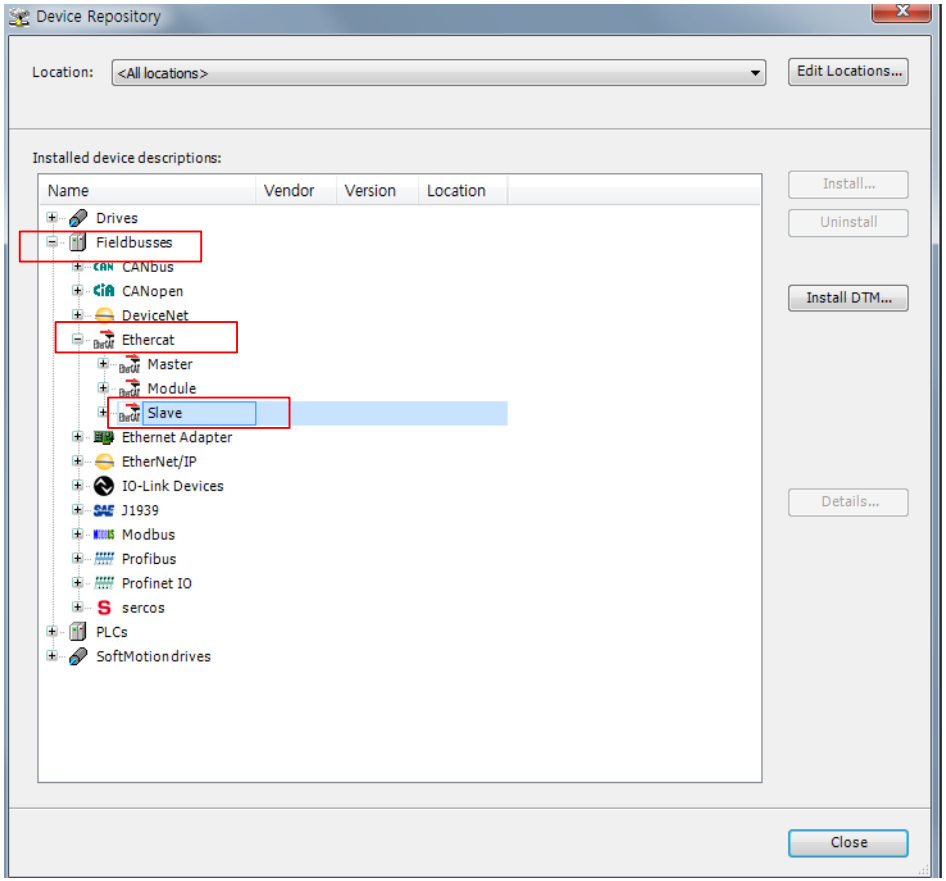


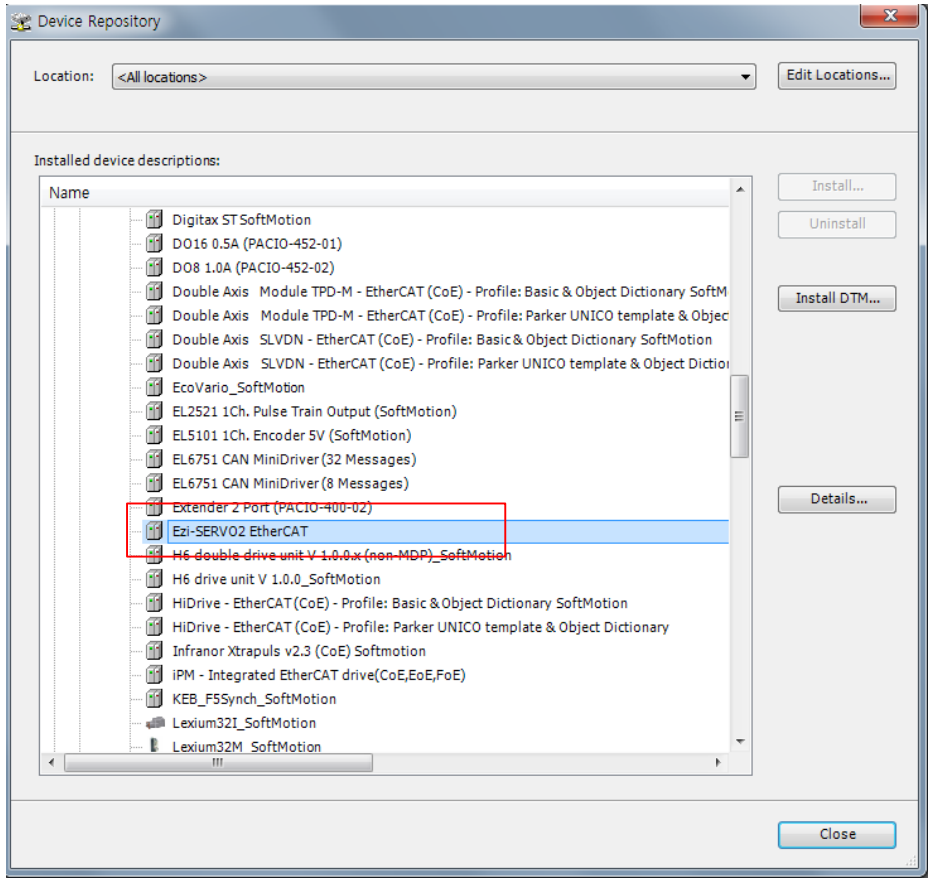
Ezi-SERVO®
Closed Loop Stepping System

Save ESI(XML) file

- You can check XML file path as below

  Fieldbusses – EtherCAT – Slave – Ezi-SERVO II EtherCAT

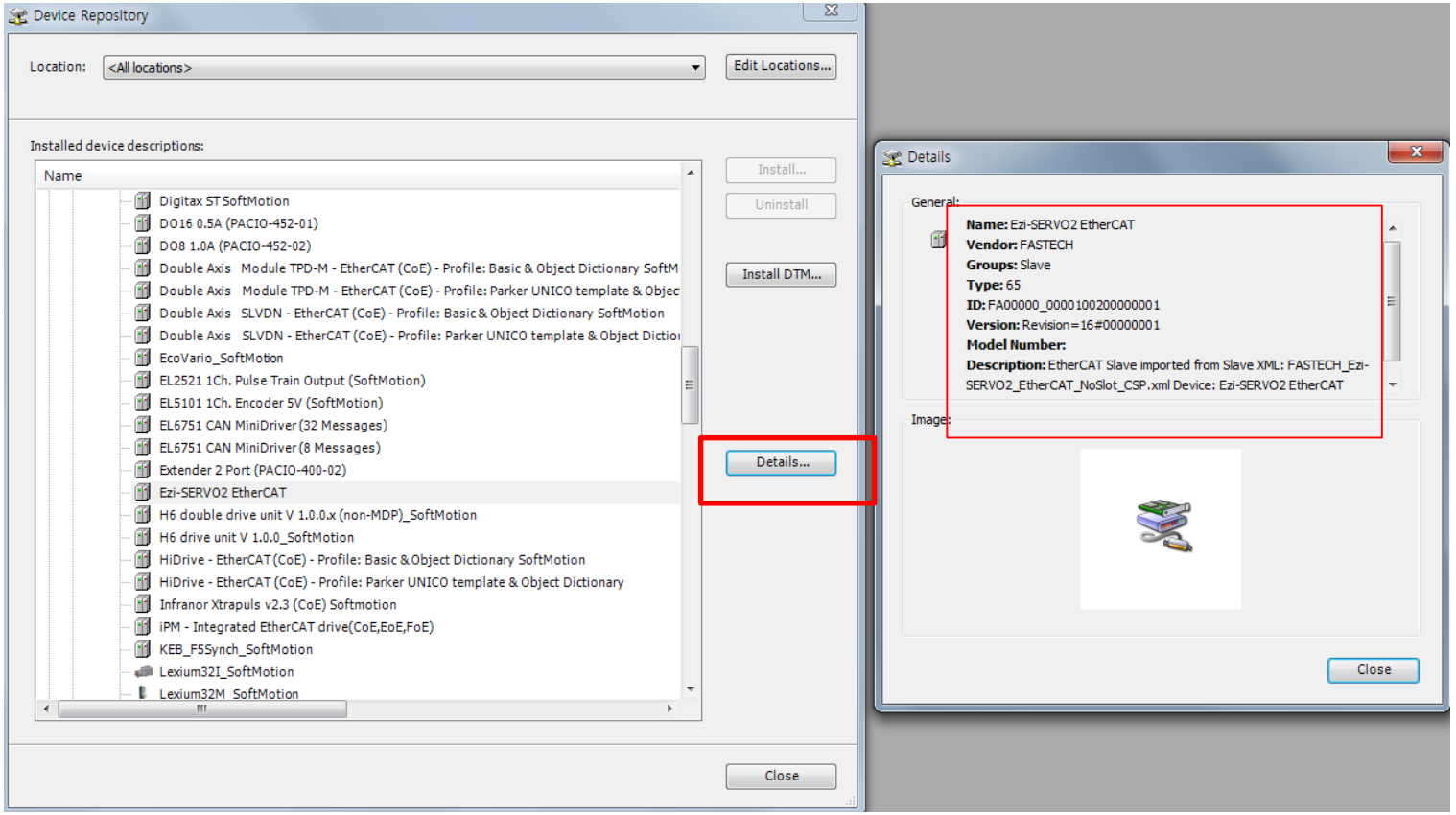




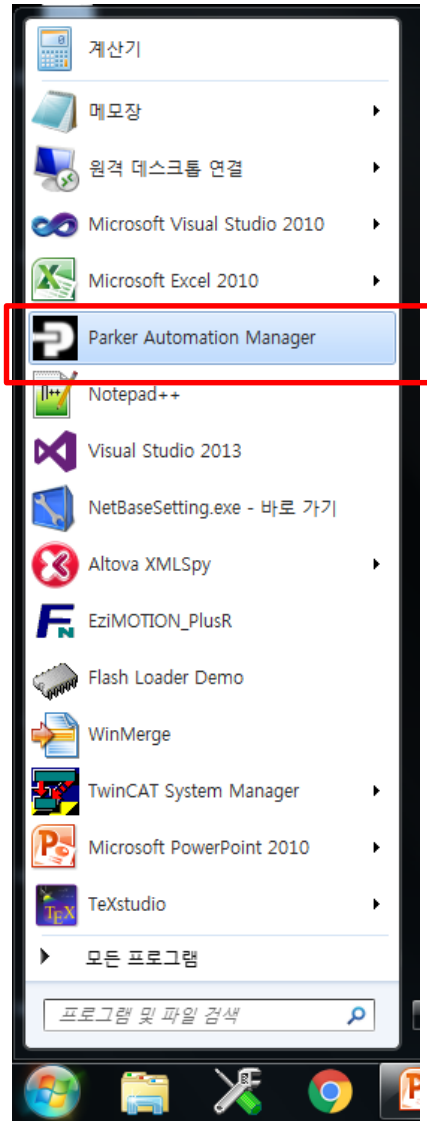
Ezi-SERVO®
Closed Loop Stepping System

Save ESI(XML) file

- You can see the detailed information of file when click “Details” as below



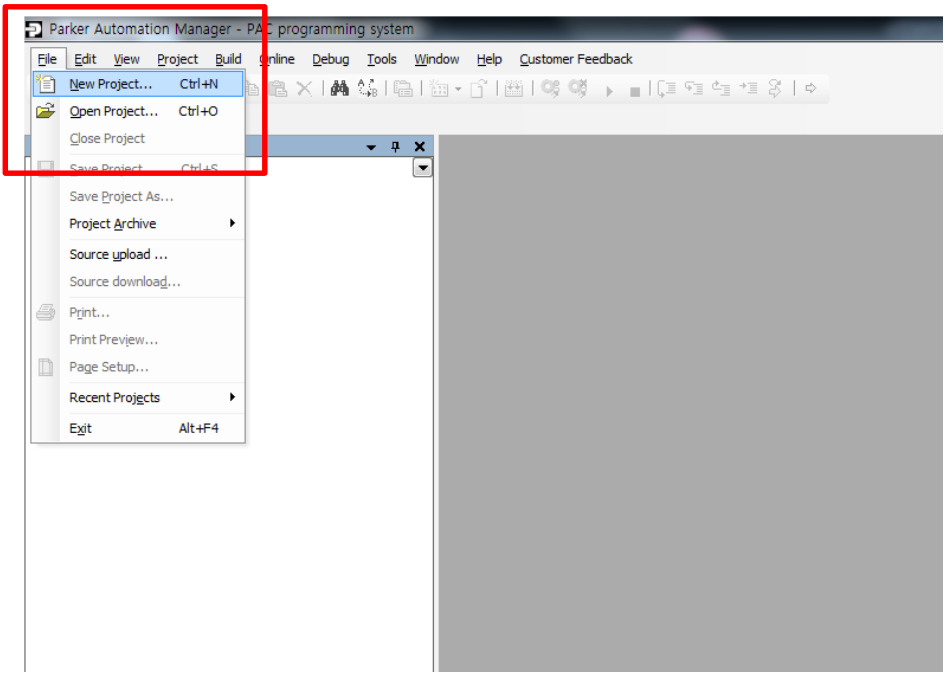
Creating a new PAC project



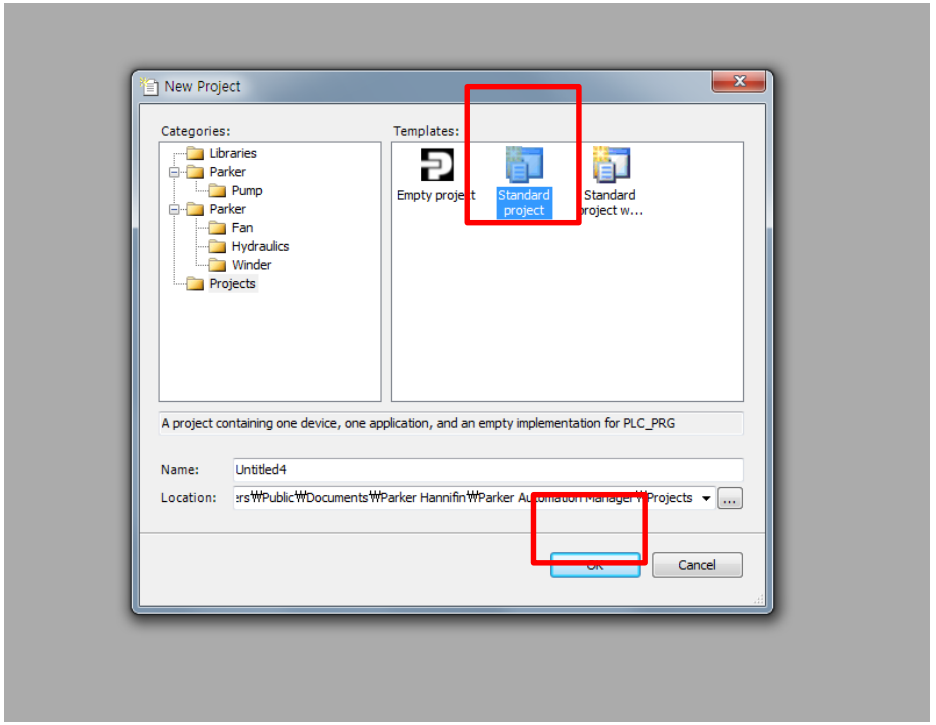
Launch the Parker Automation Manager Software

Creating a new PAC project

Choose File – "New Project"



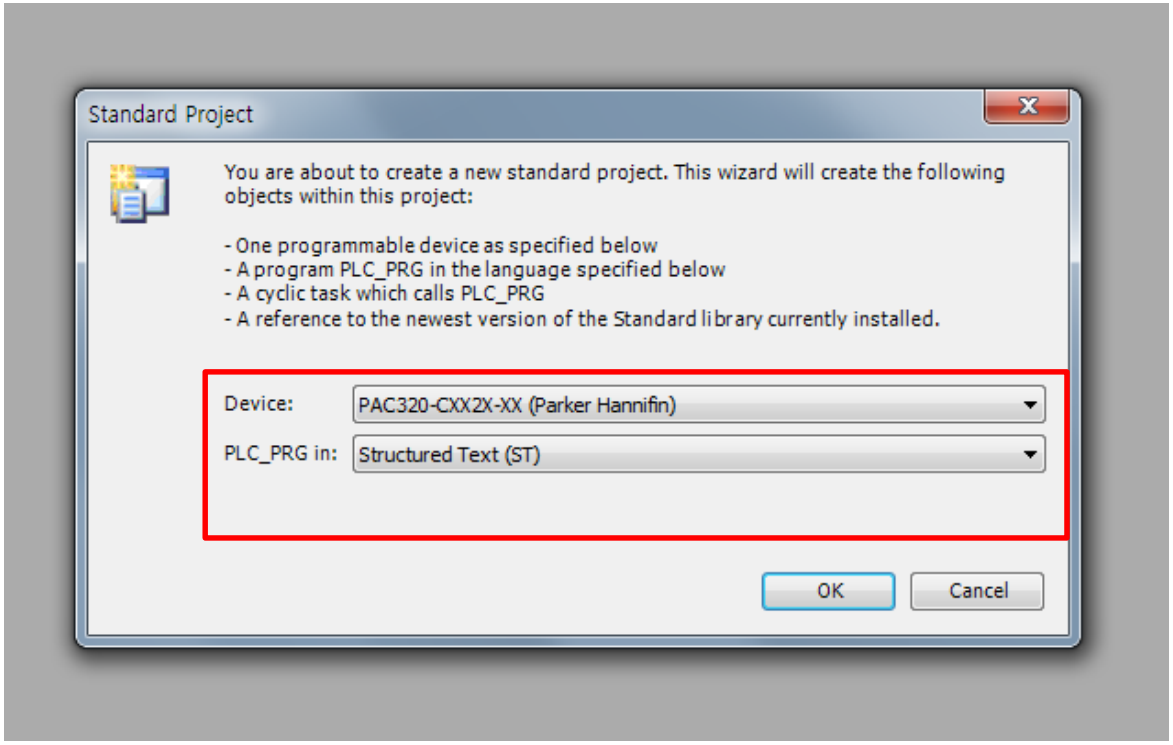
Choose "Standard project" and name your project. Click OK.



Ezi-SERVO®
Closed Loop Stepping System

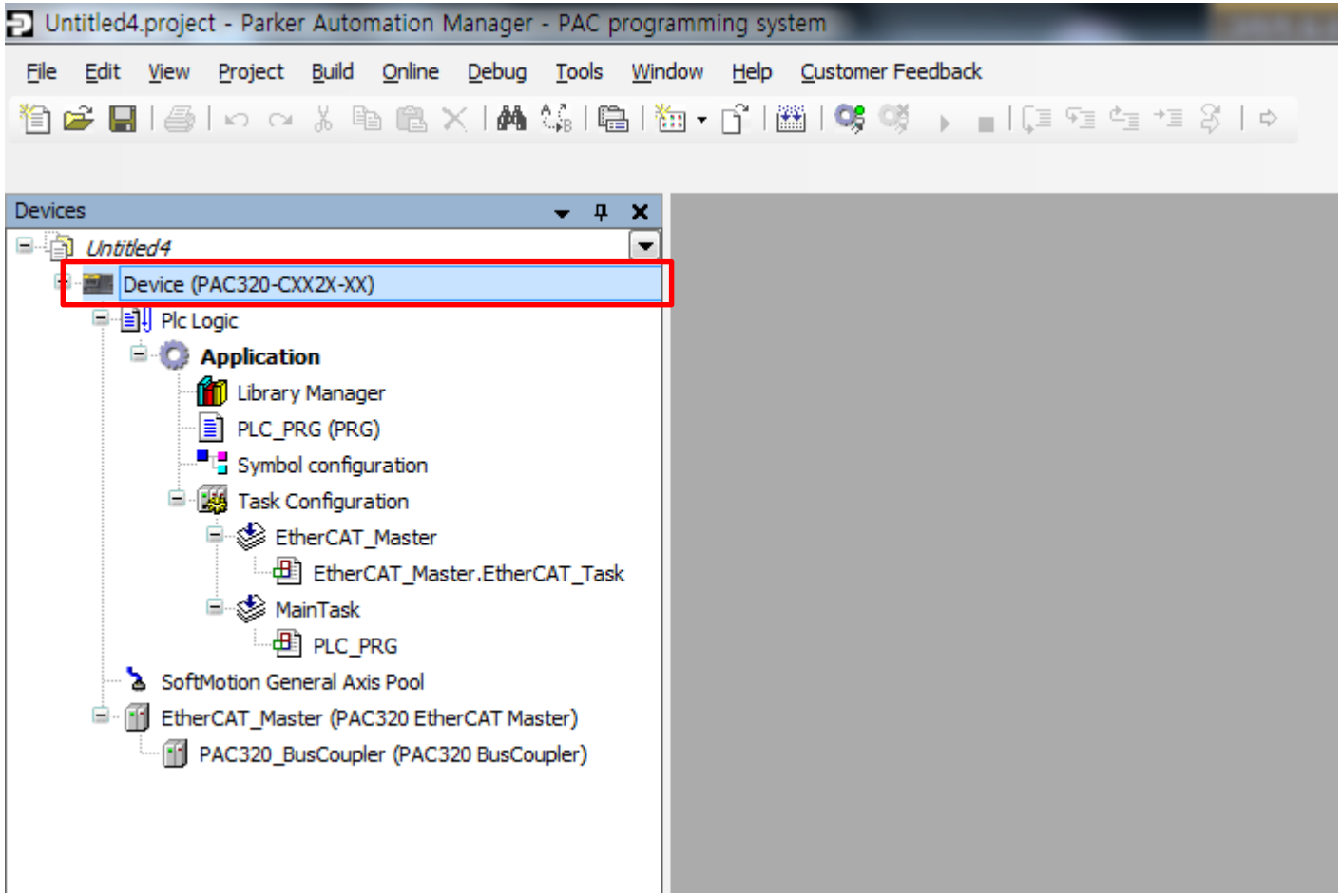
Creating a new PAC project

Choose the appropriate PAC320 device as below. Choose OK.



Connection to the PAC

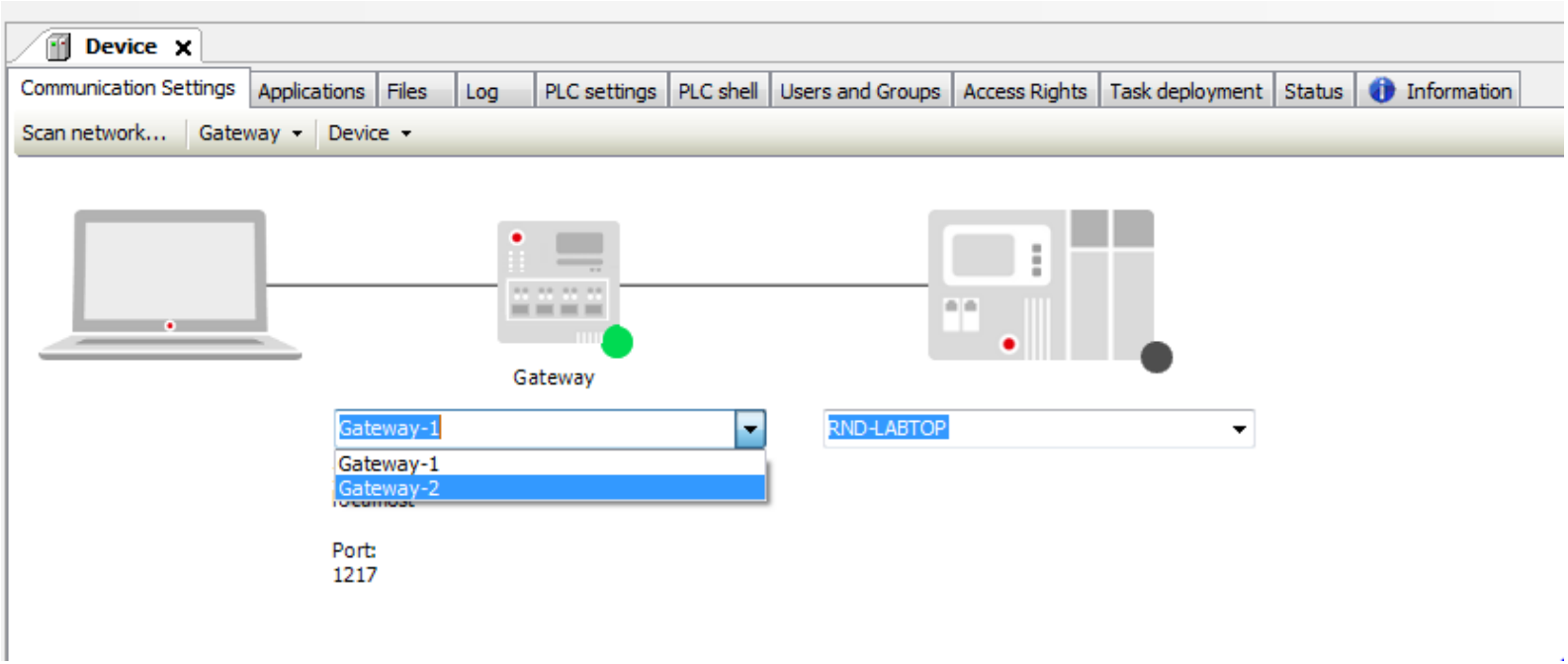
Double click on “Device (PAC320-CXX2X-XX). ”



Connection to the PAC

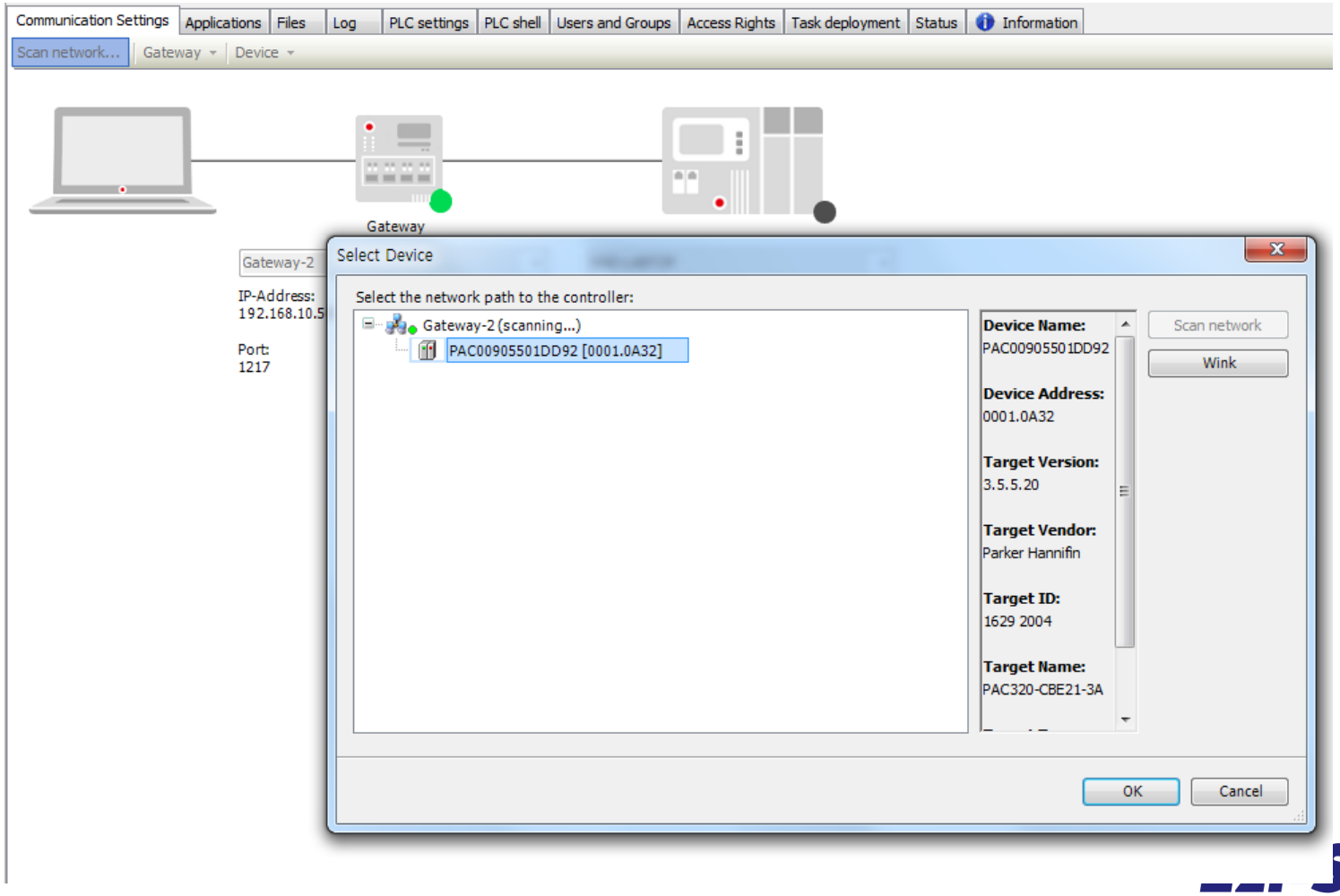
Choose Gateway-2 as below

(You can see the green dot if connection is OK. If not, please check the cable is connected well.)



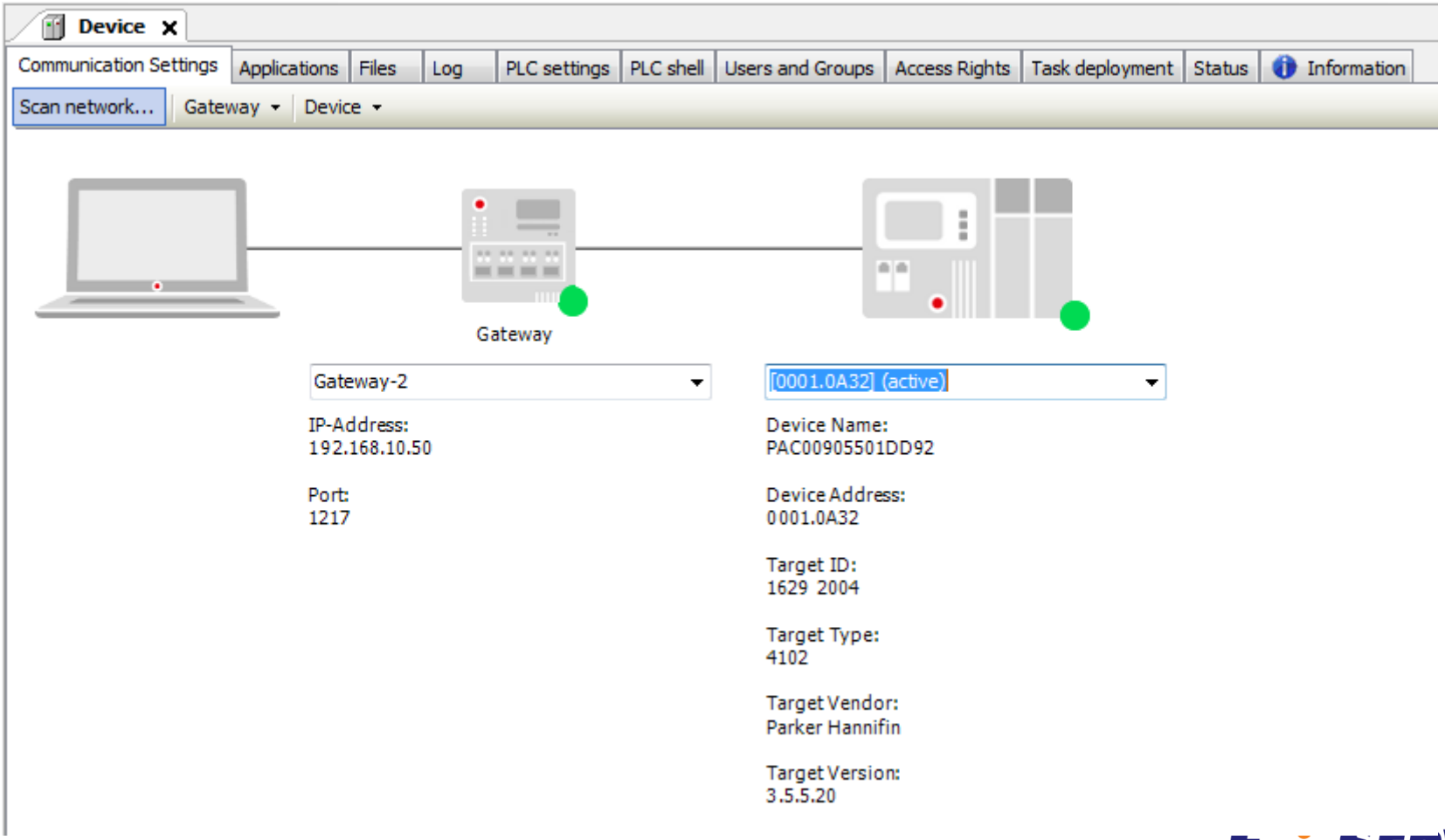
Connection to the PAC

Select “Scan network”. After scanning process finds the PAC, select the PAC and click OK.



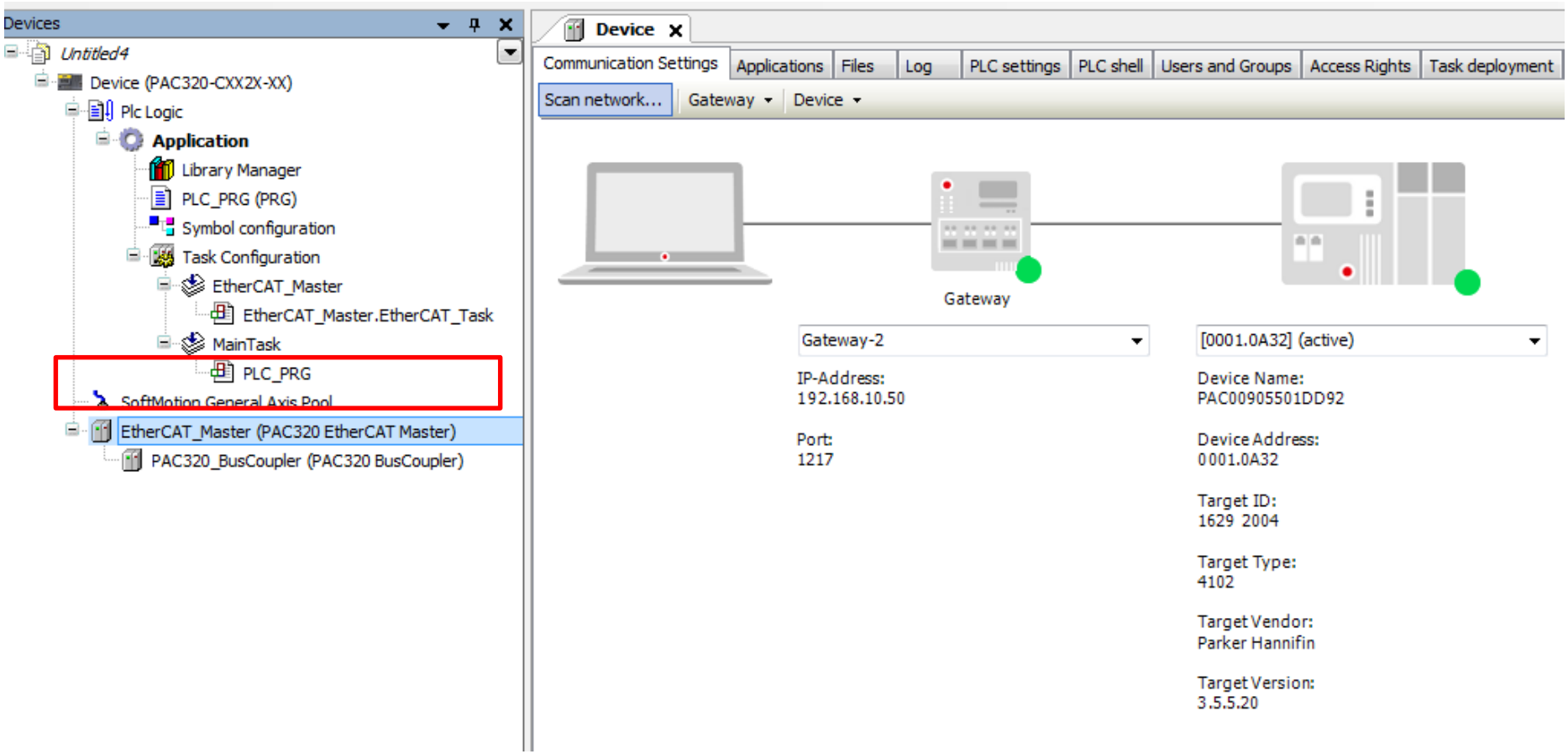
Connection to the PAC

- **The Green dot on the device indicates that the device was found and you are now connected to the PAC.**



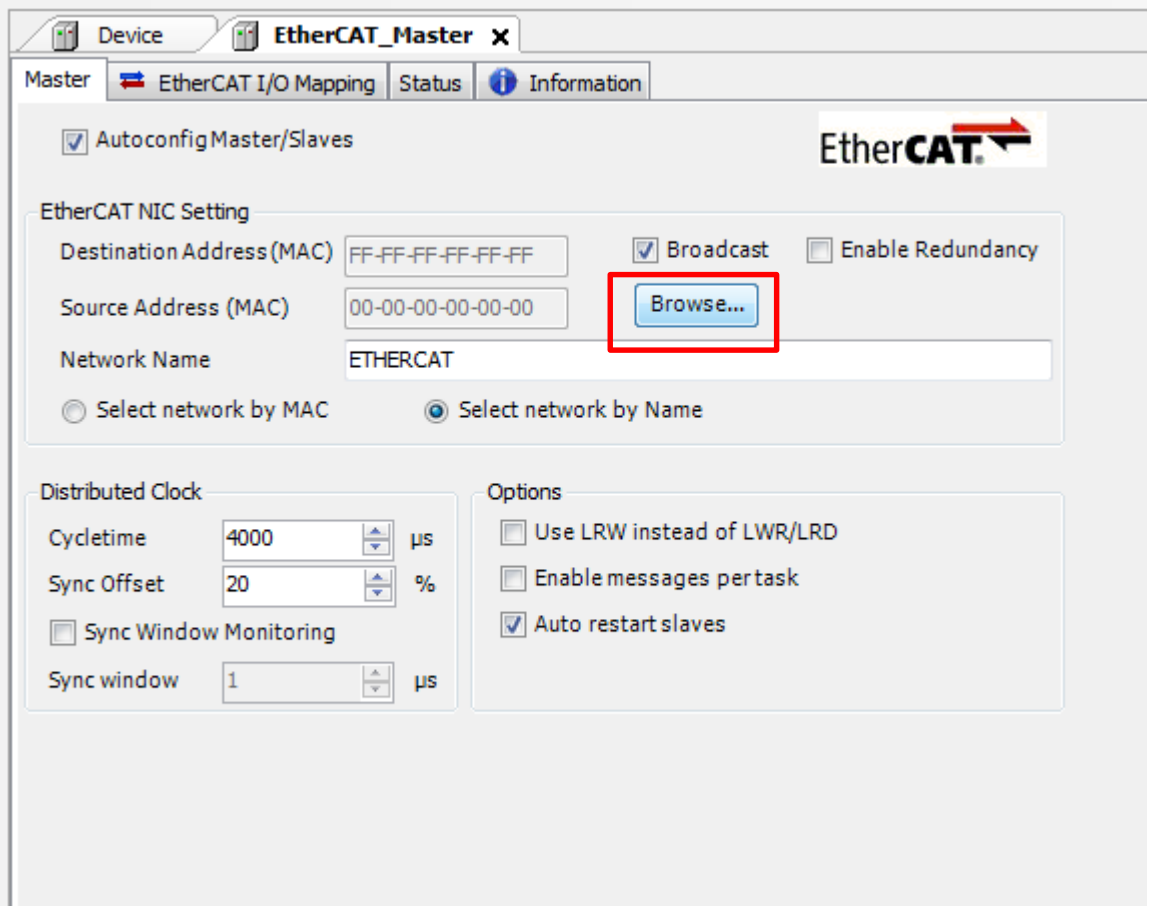
Configure EtherCAT_Master Node

Double click the EtherCAT_Master node (PAC320 EtherCAT Master)



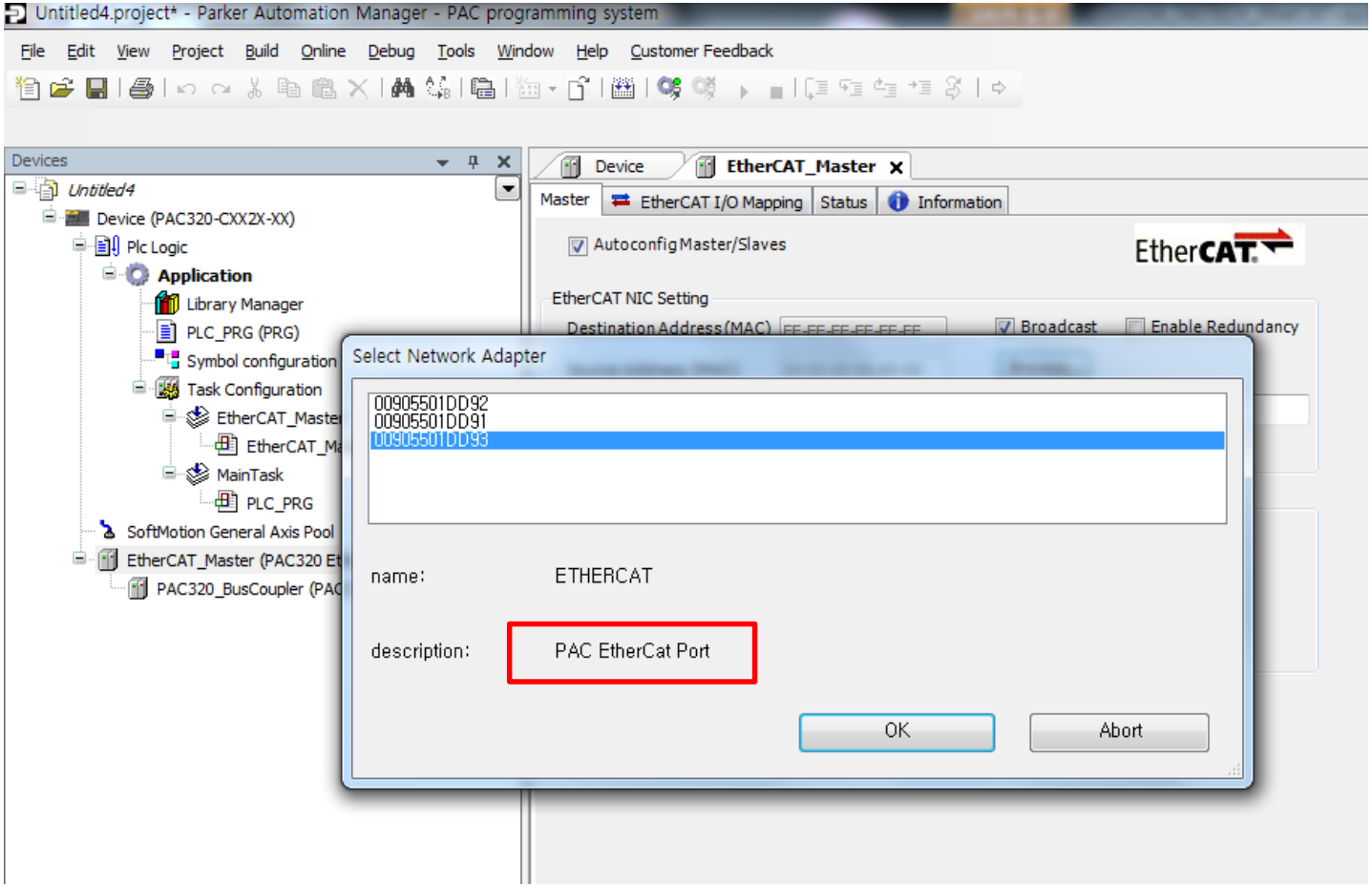
Configure EtherCAT_Master Node

Choose “Browser”



Configure EtherCAT_Master Node

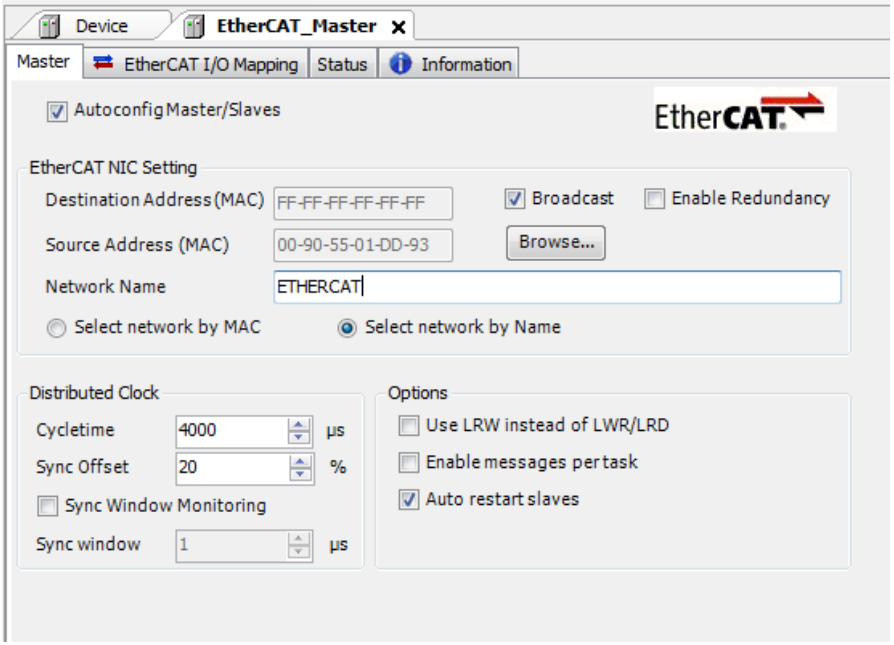
Choose 00905501DD93 (PAC EtherCAT Port). Click OK

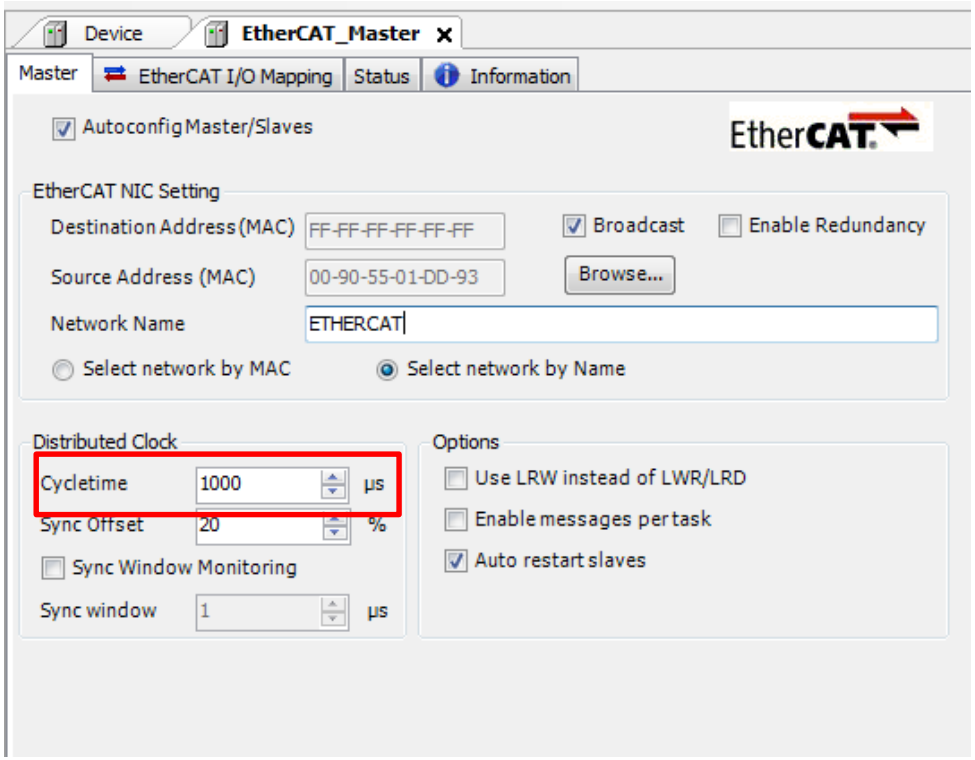


Ezi-SERVO®
Closed Loop Stepping System

Configure EtherCAT_Master Node

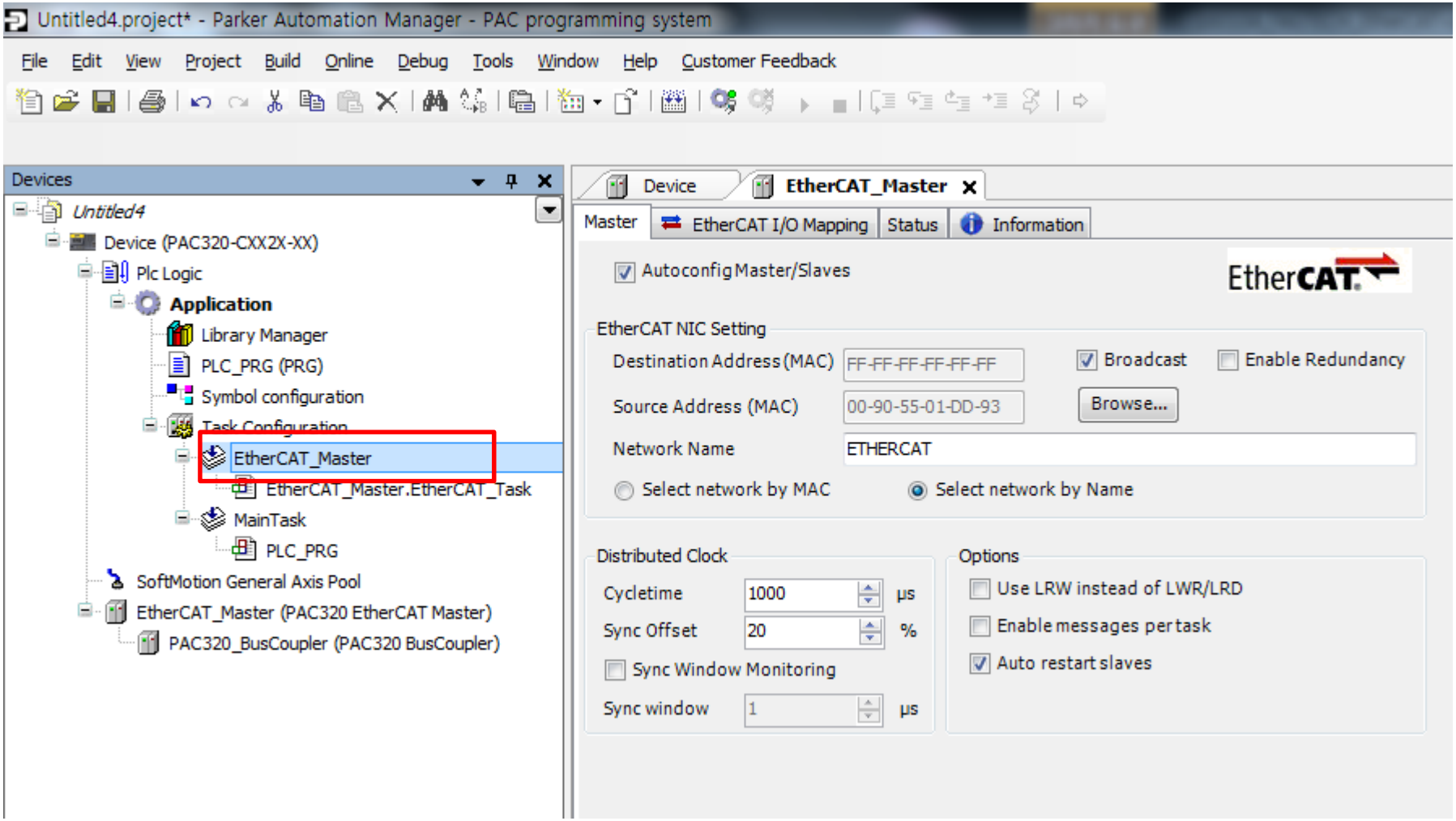
- Change the Distributted Clock Cycle time to 1000 (1000 usec is a reasonable starting point.)





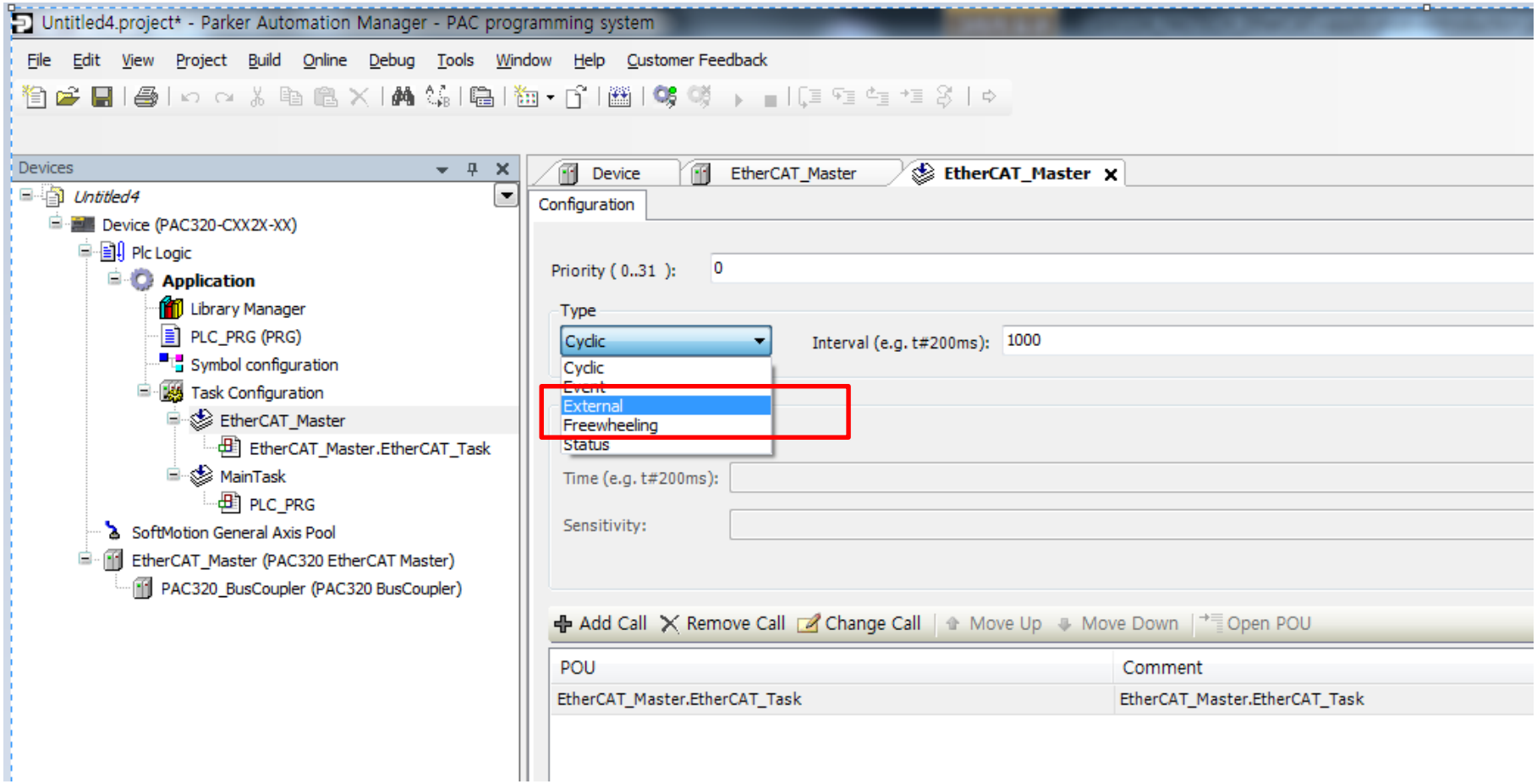
Configure the EtherCAT_Master Task

Double click on “EtherCAT_Master”



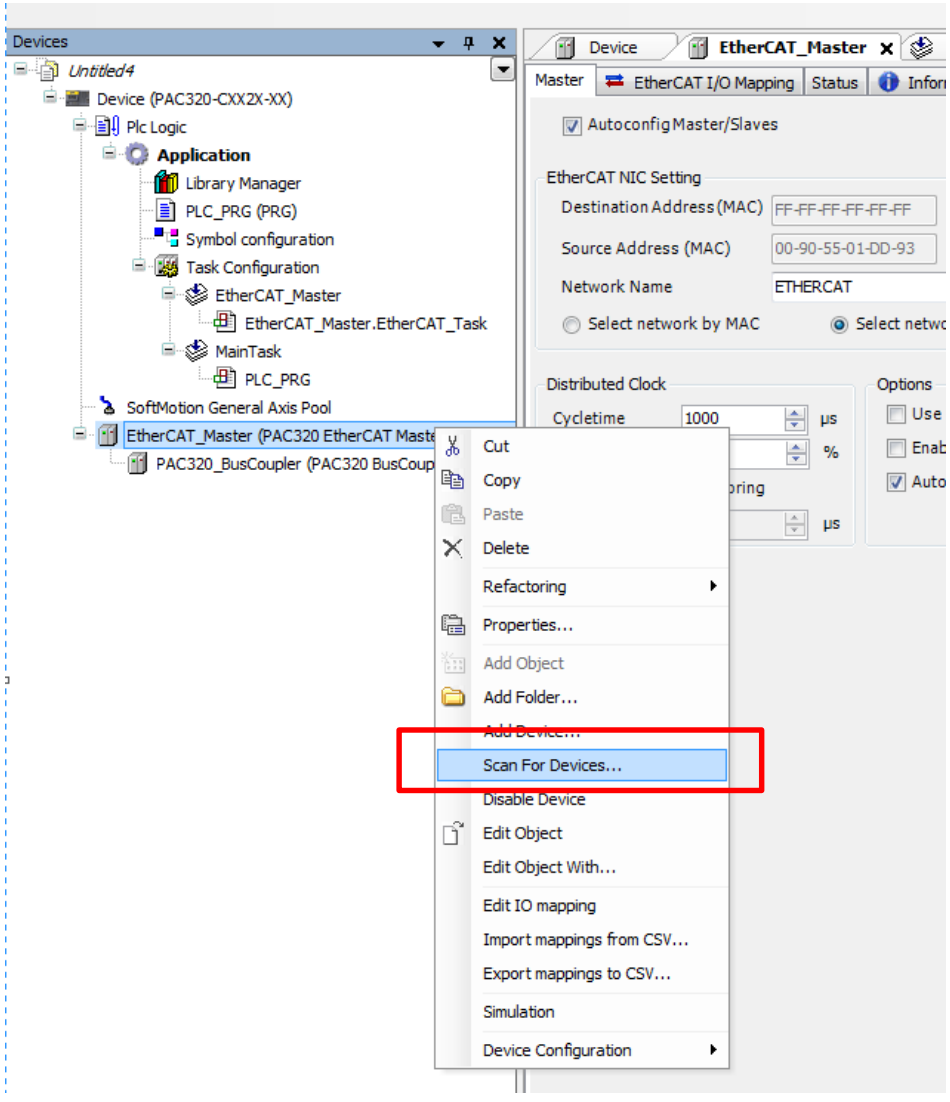
Configure the EtherCAT_Master Task

Set the Type to External



Scan for Devices

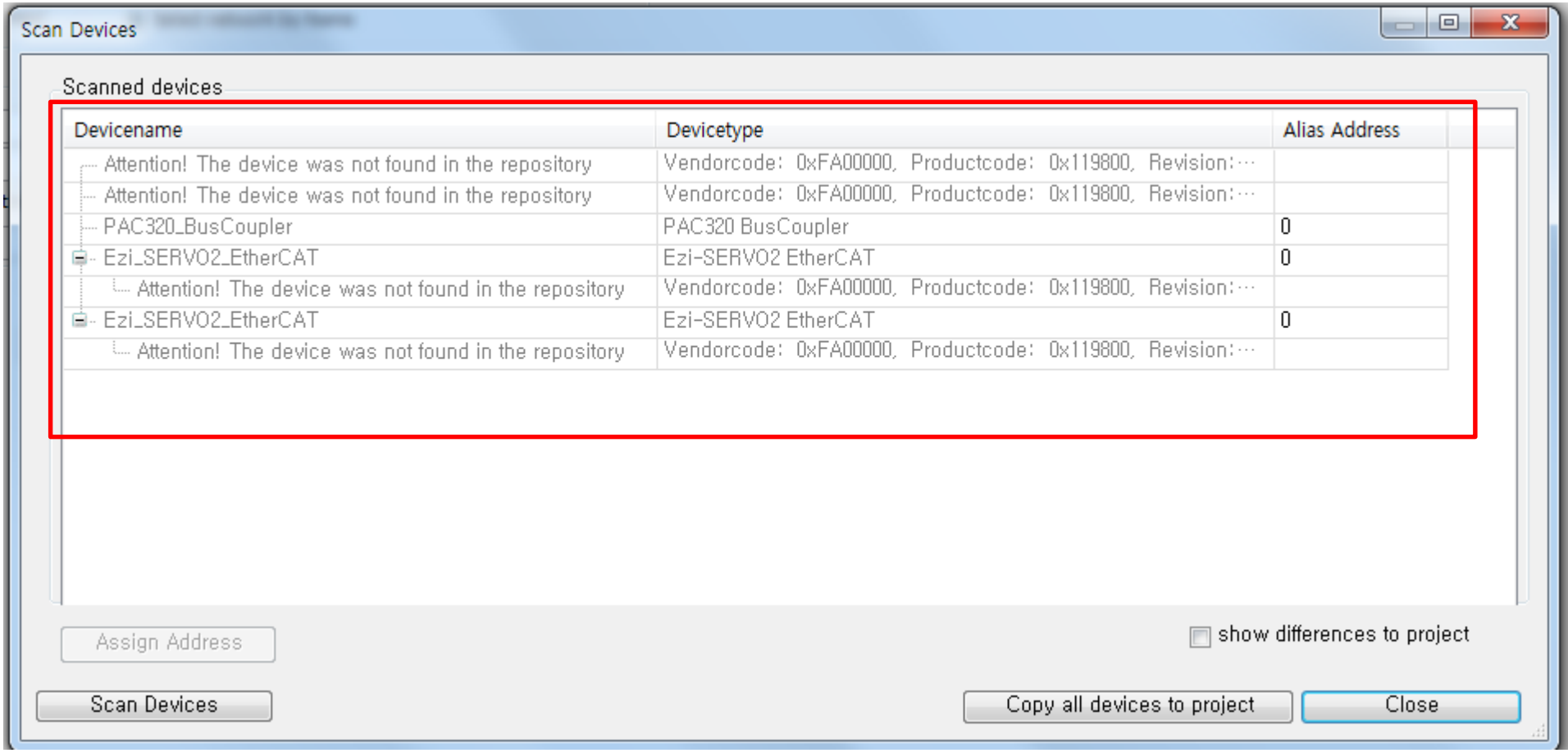
- Right-click on “EtherCAT_Master [PAC320 EtherCAT Master] and select “Scan for Devices…”



Ezi-SERVO®
Closed Loop Stepping System

Scan for Devices

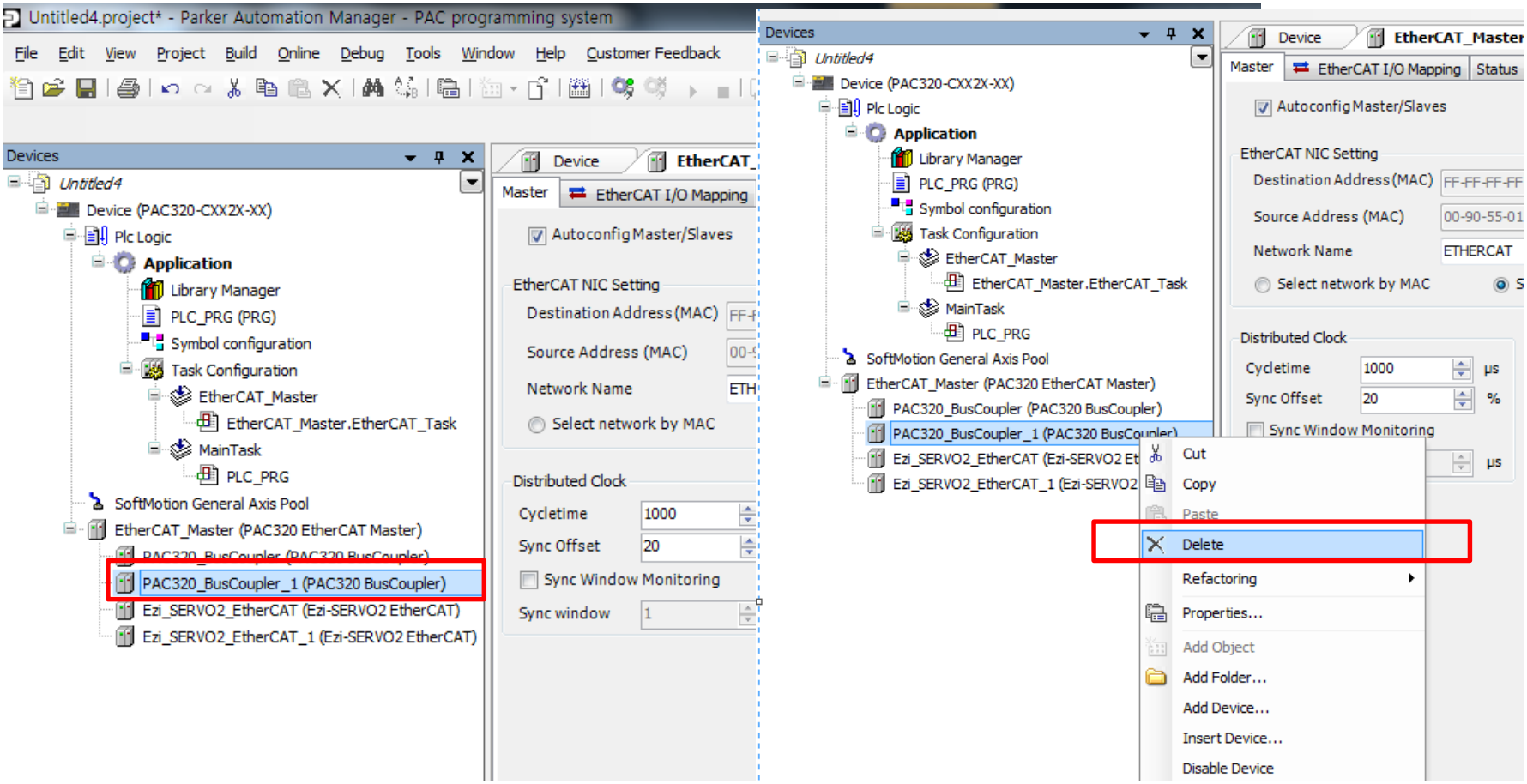
A list of connected EtherCAT slaves will be displayed and then click the “Copy all devices to project”



Ezi-SERVO®
Closed Loop Stepping System

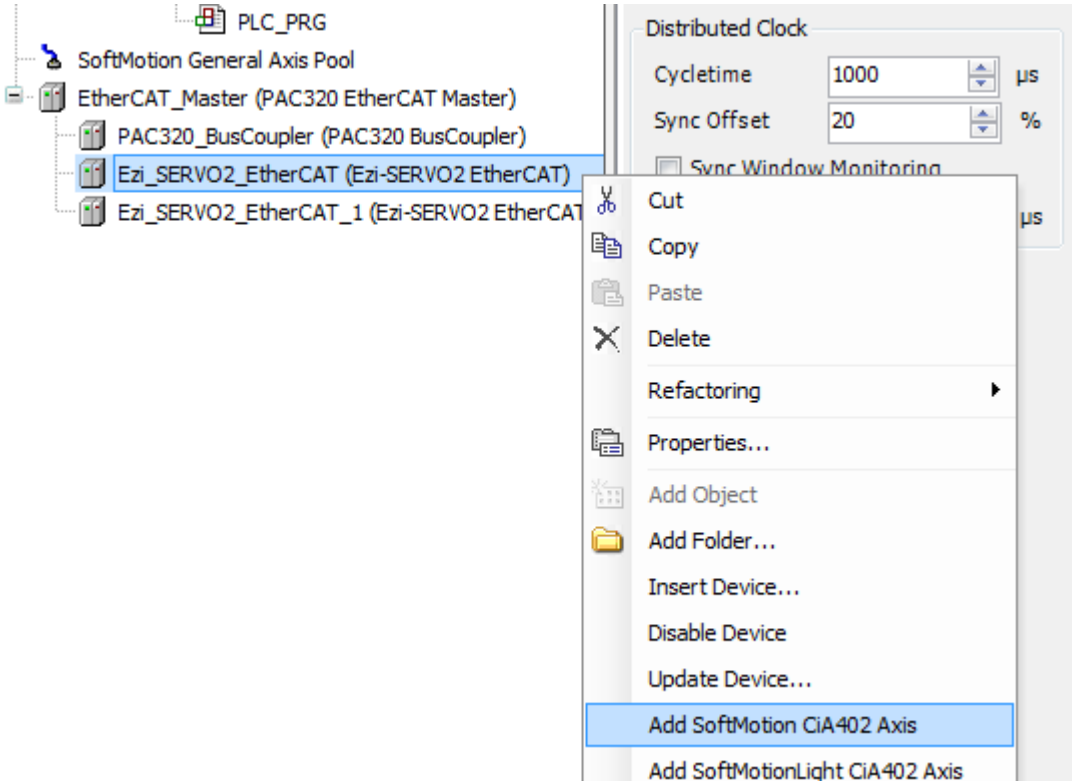
Scan for Devices

Right click on the PAC320_BusCoupler_1(PAC320 BusCoupluer) and choose the Delete



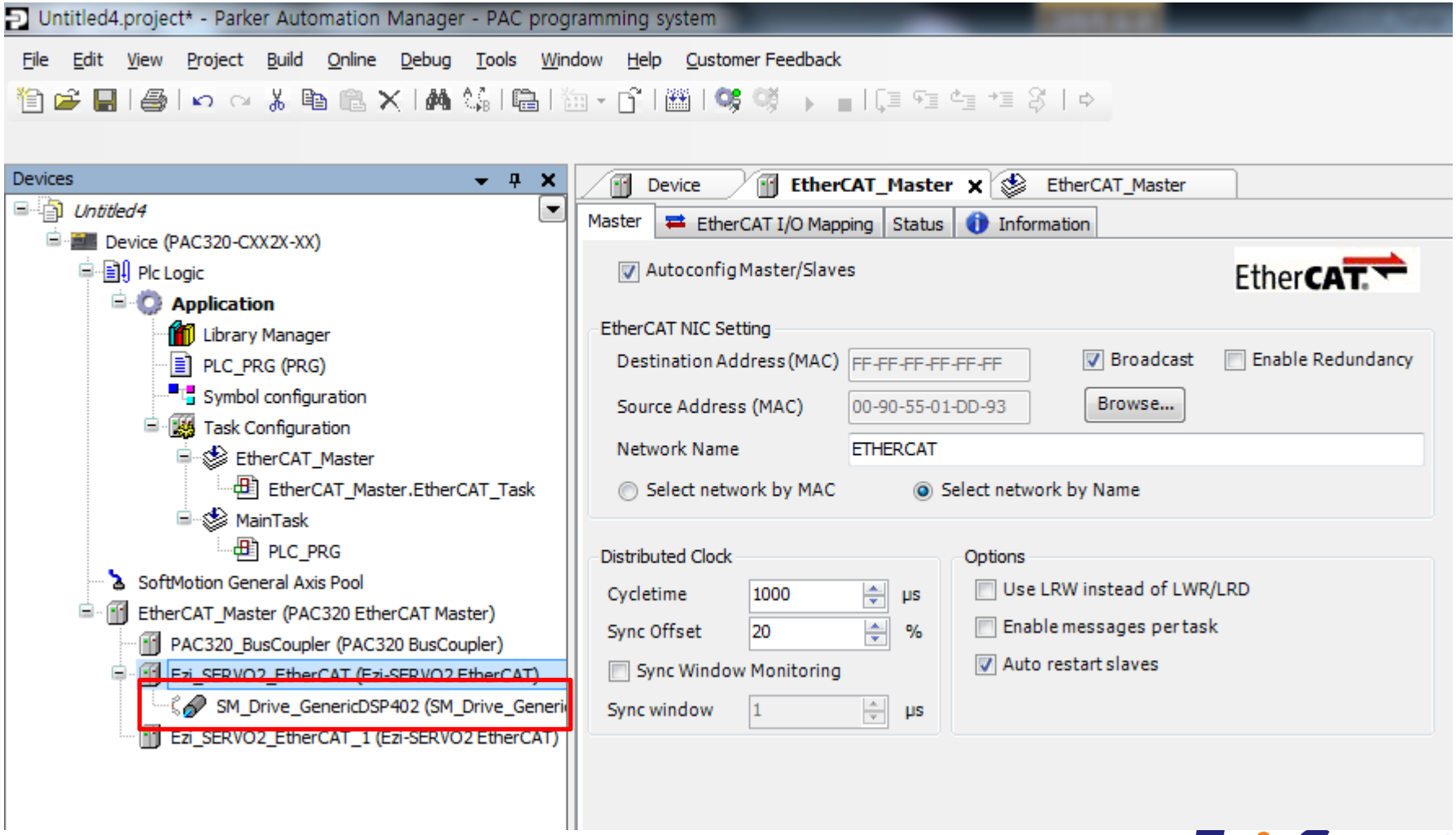
Add device

Right-click on the Ezi_SERVO2_EtherCAT and choose Add Softmotion CiA 402 Axis



Add device

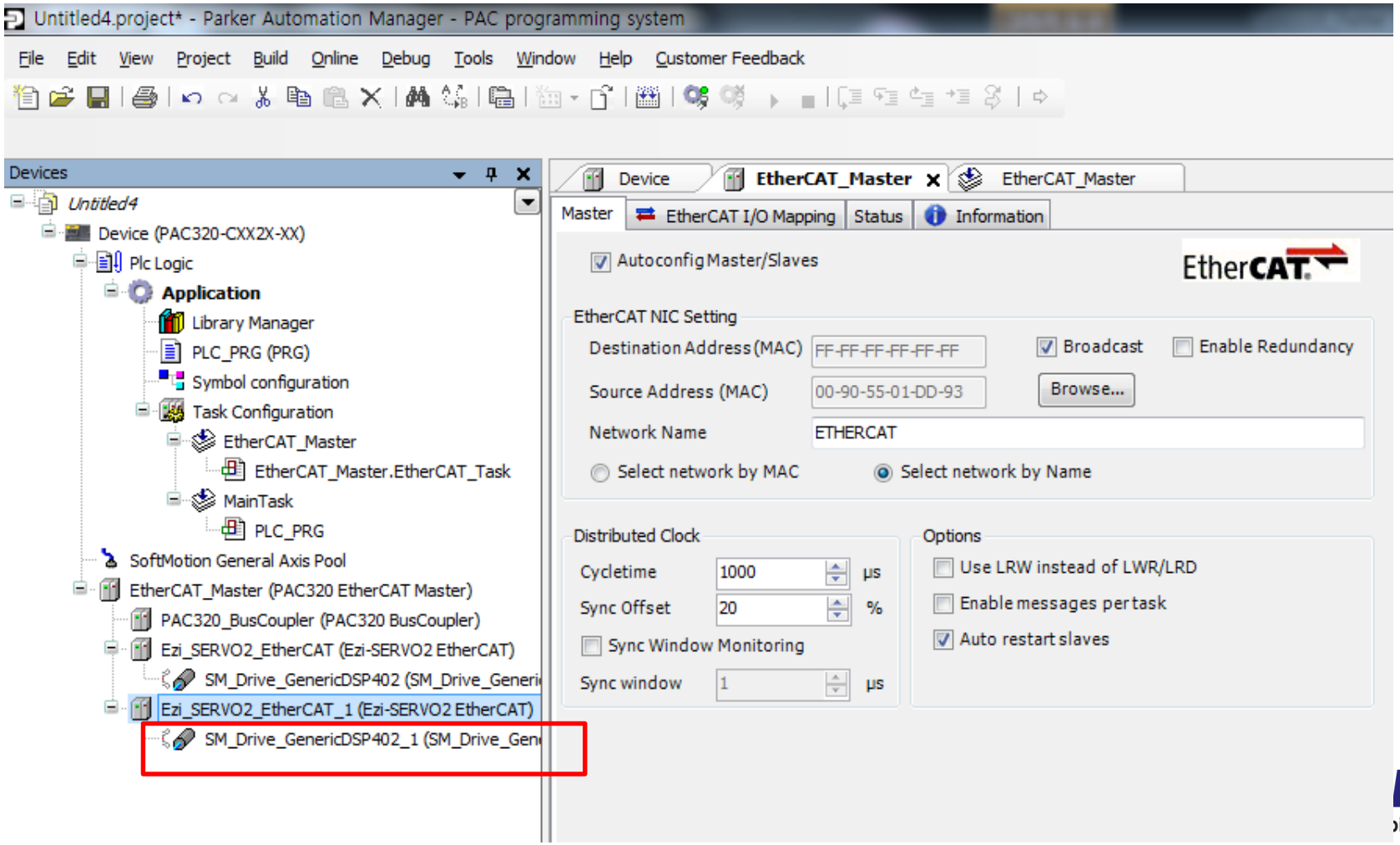
Then SM_Drive_Generic axis is created.



Ezi-SERVO®
Closed Loop Stepping System

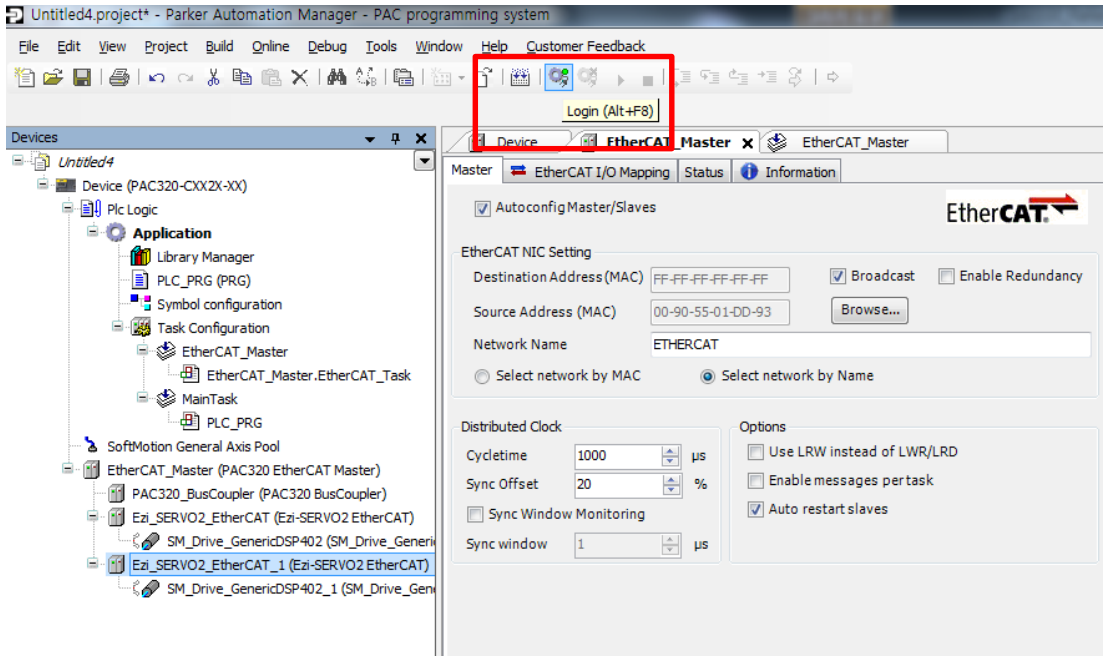
Add device

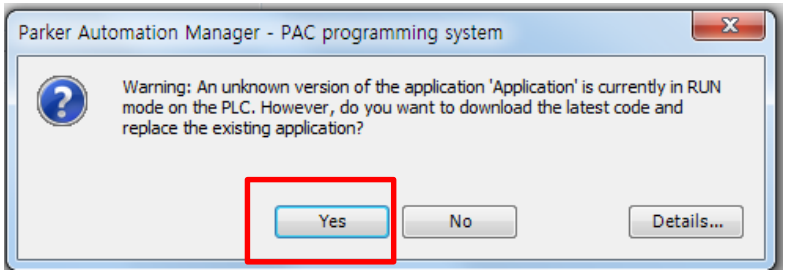
Right-click on Ezi-SERVO2_EtherCAT_1 and choose Add Softmotion CiA 402 Axis then SM_Drive_Generic axis is created same as before.



Login

Select the Login Icon on the Toolbar and click Yes

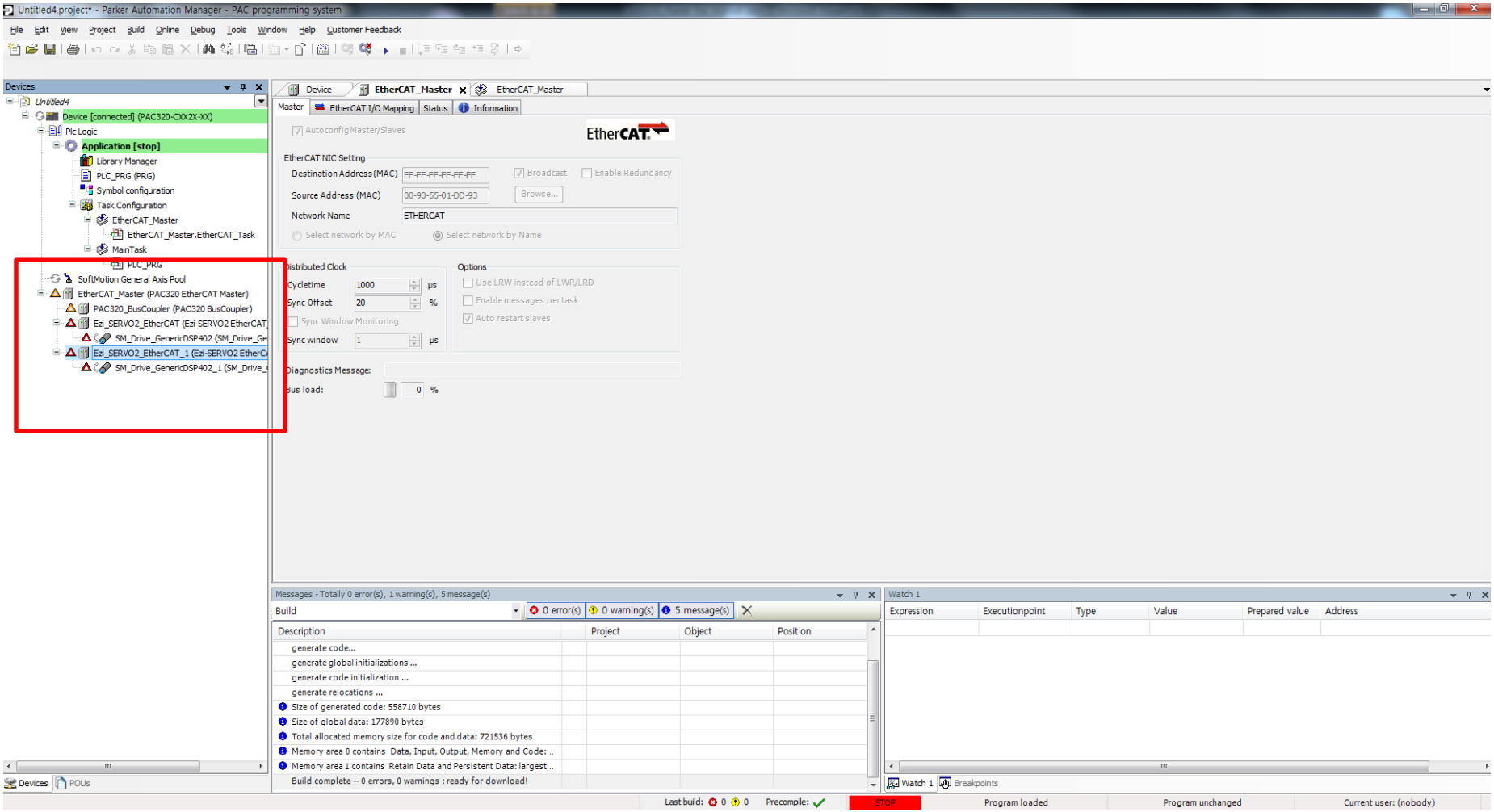




Ezi-SERVO®
Closed Loop Stepping System

Login

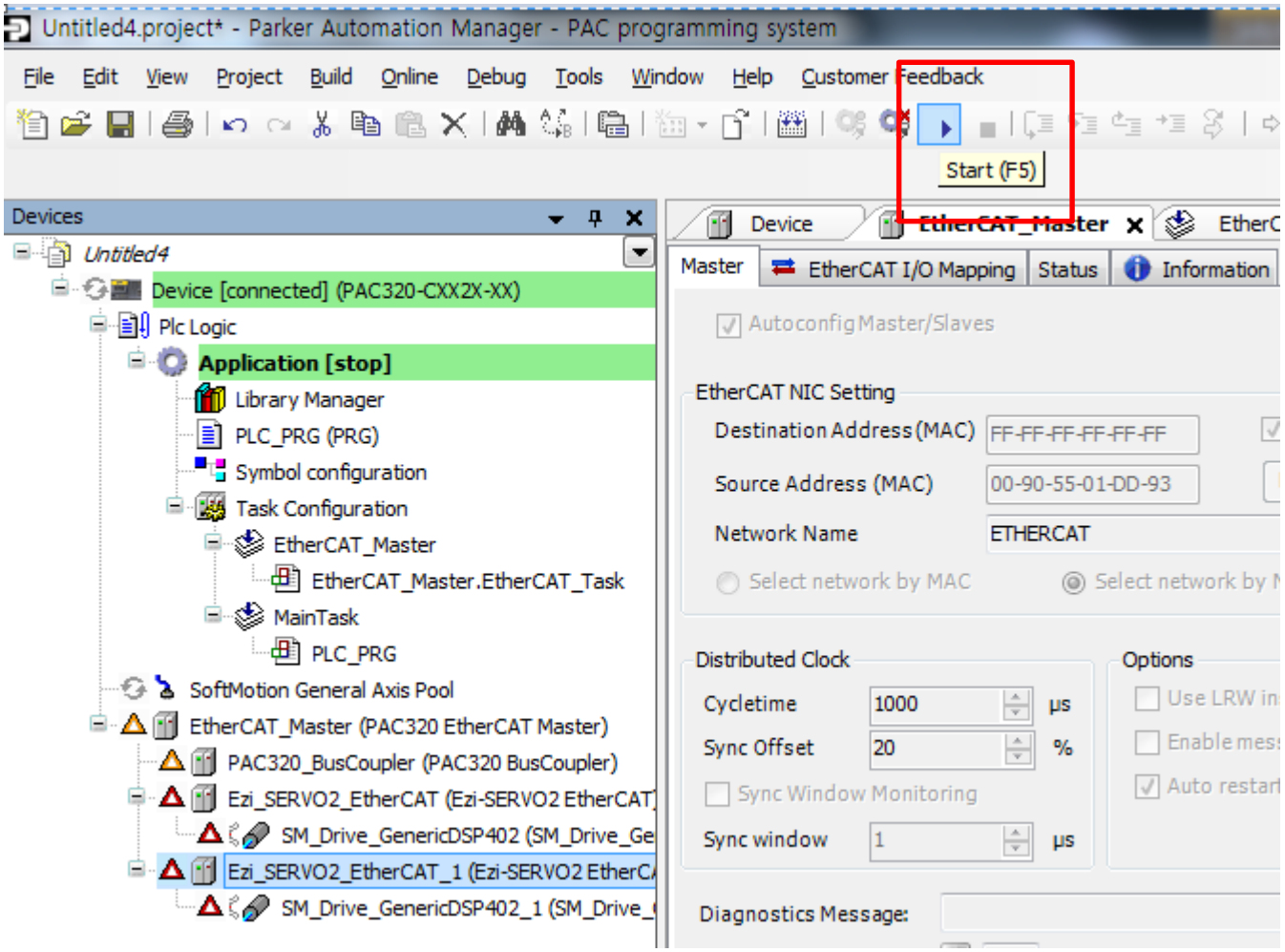
You can see the below will show up on your device tree



Ezi-SERVO®
Closed Loop Stepping System

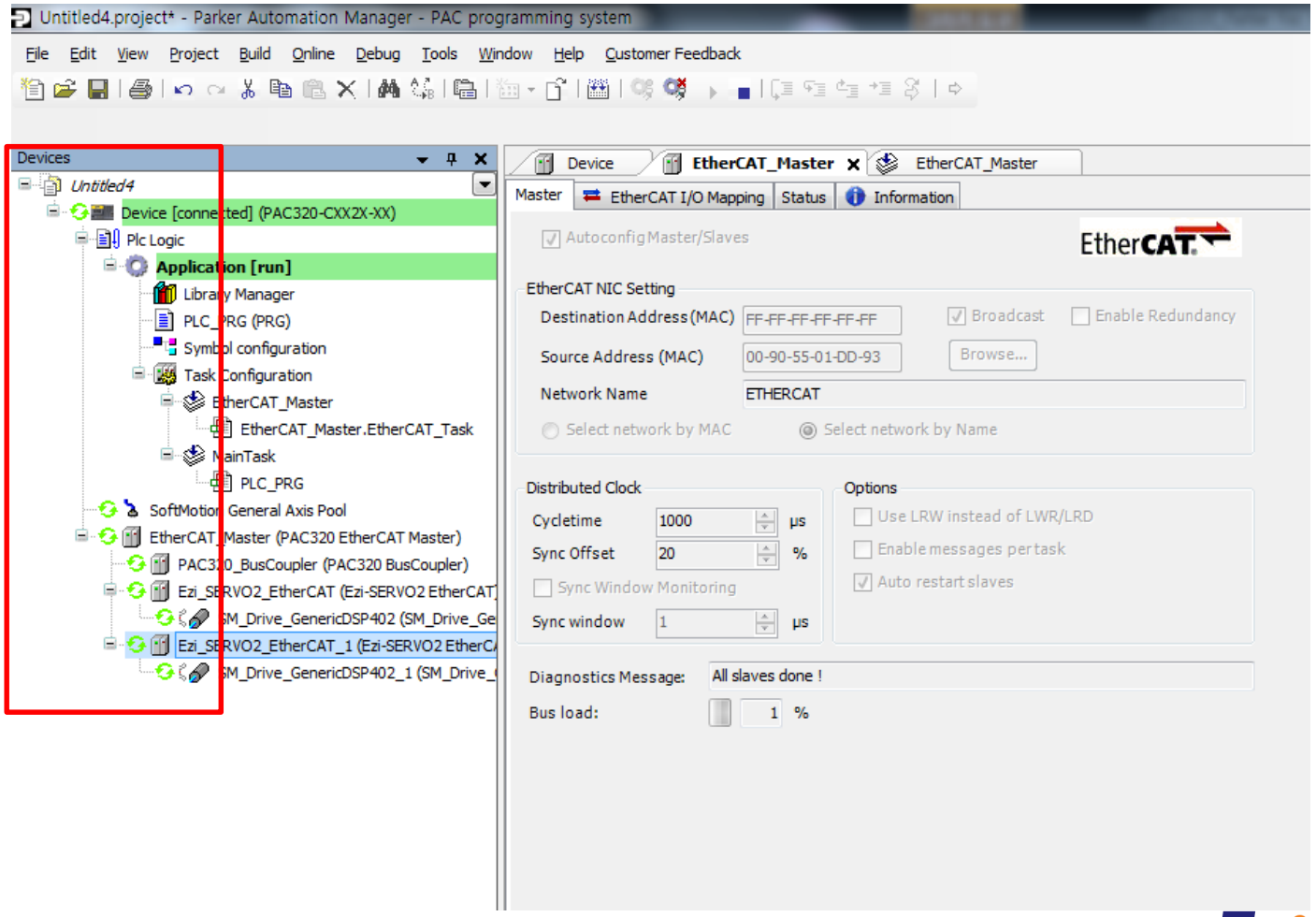
Start

- Select the Start Icon on the Toolbar



Start

The Green dot on the device indicates that you are now ready to run EtherCAT slave.



We are a pioneer changing the history of step motor !!

FASTECH
Fast, Accurate, Smooth Motion Control