

# EtherCAT CiA402 Profile Interface

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Manual



Documentation of the EtherCAT CiA402 Interface of the  
following Drives:

- C1150-DS-XC-0S/1S
- C1250-DS-XC-0S/1S
- C1450-DS-VS-0S/1S
- E1450-DS-QN-0S/1S
- E1250-DS-UC

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## Table of Contents

<b>1 System overview</b>	<b>6</b>
1.1 References	6
1.2 Connecting In and Out	6
<b>2 Setup in the PLC</b>	<b>7</b>
2.1 Copy Device Description File	7
2.2 Scan the EtherCAT slave devices	8
<b>3 Operation Modes</b>	<b>11</b>
3.1 Profile Position Mode (OpMode 1)	11
3.2 Homing Mode (OpMode 6)	12
3.3 Cyclic Sync Position Mode (OpMode 8)	13
3.4 Cyclic Sync Torque Mode (OpMode 10)	14
<b>4 Process Data Object (PDO) Configuration</b>	<b>14</b>
4.1 Input PDO Modules	15
4.1.1 Cyclic Mode Inputs 0x1A02	15
4.1.2 Cyclic Mode Inputs 2 0x1A03	15
4.1.3 Cyclic Inputs 0x1A12	16
4.1.4 User Defined Inputs 0x1A20	16
4.1.5 Config Module 0x1B08	16
4.1.6 Input Demvel 0x1B10	17
4.1.7 Input DemCurrFilt 0x1B16	17
4.1.8 Input ActVelFilt 0x1B11	17
4.1.9 Input ActVelFilt 0x1B12	18
4.1.10 Mon Channel 1 0x1B28	18
4.1.11 Mon Channel 2 0x1B29	18
4.1.12 Mon Channel 3 0x1B2A	18
4.1.13 Mon Channel 4 0x1B2B	18
4.2 Output PDO Modules	19
4.2.1 Cyclic Position Mode 0x1602	19
4.2.2 Cyclic Position Velocity Mode 0x1603	19
4.2.3 Cyclic Position Velocity Torque Mode 0x1604	20
4.2.4 Cyclic Torque Mode 0x1606	20
4.2.5 Cyclic Position Velocity 0x1613	21
4.2.6 Cyclic Position Velocity Torque 0x1614	21
4.2.7 User Defined Outputs 0x1620	21
4.2.8 Config Module 0x1708	21
4.2.9 Max Current Set A 0x1710	22
4.2.10 Torque/force limits 0x1711	22
4.2.11 Par Channel 1 0x1728	22
4.2.12 Par Channel 2 0x1729	22
4.2.13 Par Channel 3 0x172A	22
4.2.14 Par Channel 4 0x172B	23
4.3 Typical Startup Telegrams	23
<b>5 Asynchronous Configuration Protocol CoE</b>	<b>24</b>
5.1 Communication CiA402 Profile Area(1000h-1FFFh)	24
5.1.1 Homing method Object 6098	25
5.1.2 Homing speeds Object 6099	25
5.2 Manufacturer specific Profile Area(2000h-5FFFh)	25

5.2.1	Parameter UPID read RAM value .....	28
5.2.2	Parameter UPID write RAM value .....	28
5.2.3	Parameter UPID read ROM value .....	29
5.2.4	Parameter UPID write ROM value .....	29
5.2.5	Parameter UPID read minimal value .....	30
5.2.6	Parameter UPID read maximal value .....	30
5.2.7	Parameter UPID read default value .....	31
5.2.8	Parameter UPID write RAM & ROM value .....	31
5.2.9	Parameter default OS SW instance .....	32
5.2.10	Parameter default MC SW instance .....	32
5.2.11	Parameter default Intf SW instance .....	33
5.2.12	Parameter default Appl SW instance .....	33
5.2.13	Reset device .....	34
5.2.14	Parameter default MC SW instance with immediate response .....	34
5.2.15	Start read UPID List .....	35
5.2.16	Read next UPID List entry .....	36
5.2.17	Start read modified UPID List .....	36
5.2.18	Read next modified UPID List entry .....	37
5.2.19	Stop MC and Application SW instances .....	38
5.2.20	Start MC and Application SW instances .....	38
5.2.21	Curves copy curves from RAM to FLASH .....	39
5.2.22	Curves delete all curves in RAM .....	39
5.2.23	Curves start write curve in RAM .....	40
5.2.24	Curves write curve info block data in RAM .....	40
5.2.25	Curves write curve set point data in RAM .....	41
5.2.26	Curves read info and setpoint data block size in RAM .....	41
5.2.27	Curves read info block data in RAM .....	42
5.2.28	Curves read set point data in RAM .....	42
5.2.29	Read error counters .....	43
5.2.30	Read logged error item Code and instance .....	43
5.2.31	Read logged error item time low .....	44
5.2.32	Read logged error item time high .....	44
5.2.33	Read error short text .....	45
5.2.34	Command Table copy entries from RAM to FLASH .....	45
5.2.35	Command Table delete all entries in RAM .....	46
5.2.36	Command Table delete entry in RAM .....	46
5.2.37	Command Table start write entry in RAM .....	47
5.2.38	Command Table write entry data in RAM .....	47
5.2.39	Command Table entry data size in RAM .....	48
5.2.40	Command Table read entry data in RAM .....	48
5.2.41	Command Table read presence list .....	49
<b>6</b>	<b>EtherCAT CiA402 Parameters .....</b>	<b>50</b>
6.1	<i>Parameters .....</i>	<i>50</i>
6.1.1	EtherCAT CiA402/Dis-/Enable .....	50
6.1.2	EtherCAT CiA402/Station Alias/Alias Address Source .....	50
6.1.3	EtherCAT CiA402/Station Alias/Alias Address Parameter .....	50
6.1.4	EtherCAT CiA402/Station Alias/Alias Address Parameter Mask .....	51
6.1.5	EtherCAT CiA402/NC Configuration/Velocity Scale Numerator /Denominator .....	51
6.1.6	EtherCAT CiA402/NC Configuration/Operation Mode 10 Config .....	51

6.1.7 EtherCAT CiA402/Connection Timeout/Timeout Behavior .....	51
<b>7 Connecting to the EtherCAT Network .....</b>	<b>51</b>
7.1 Pin Assignment of the Connectors X17-X18 .....	51

## 1 System overview

EtherCAT is the open real-time Ethernet network originally developed by Beckhoff. The LinMot act as Slave in this network and is implemented with the standard ASIC ET1100 from Beckhoff. With the CiA402 Protocol it is possible to use the drive profile functionality over the EtherCAT bus.

For further information on the EtherCAT fieldbus please visit:

<http://www.ethercat.org/>

### 1.1 References

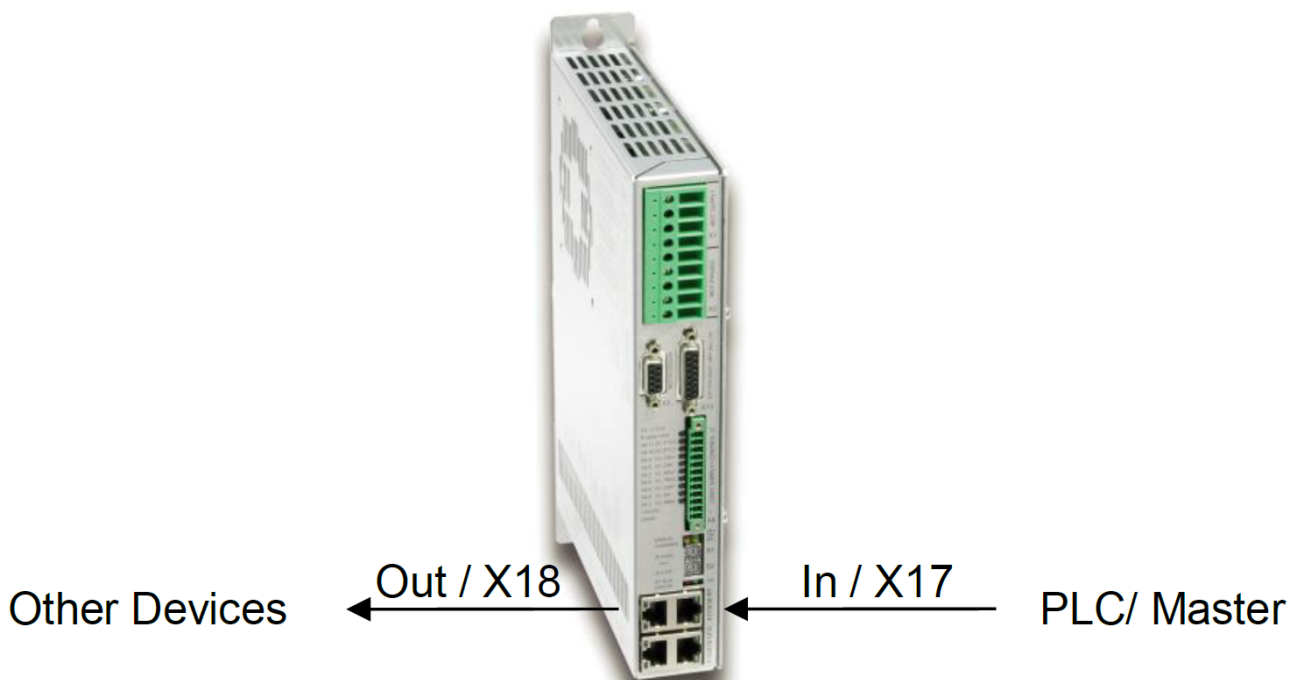
All user manuals are distributed with the LinMot-Talk software the newest versions can be downloaded from the LinMot homepage in the download section.

Ref	Title	Source
1	User Manual Motion Control SW	<a href="http://www.linmot.com">www.linmot.com</a>
2	LinMot Drive Configuration over Fieldbus Interfaces SG5	<a href="http://www.linmot.com">www.linmot.com</a>

### 1.2 Connecting In and Out



**Attention:** In the EtherCAT the cabling is directed due topology support, so In and Out is different! The real time Ethernet RJ45 connector X17 is the input and the real time RJ45 connector X18 is the output.



## 2 Setup in the PLC

In the following steps the integration of a LinMot EtherCAT Sercos Servo Drive in the PLC is described. In the example a Beckhoff master PLC is used. The easiest way is the online configuration when the device is connected to the EtherCAT network.

### 2.1 Copy Device Description File

The LinMot Servo Drive is described with \*.xml device description file distributed with the LinMot-Talk software. This file is only used when offline configuration is desired.

Copy this file to PLC so it can access it.

Example Source path of EtherCAT Device description file:

```
C:\Programme\LinMot\LinMot-Talk 6.5 Build  
20160205\Firmware\Interfaces\EtherCAT\XML\NTIL_CiA402_Servos_V1_8r2.xml
```

Example Destination path of EtherCAT Device description file:

**TwinCAT 2:**

```
C:\TwinCAT\Io\EtherCAT\ NTIL_CiA402_Servos_V1_8r2.xml
```

**TwinCAT 3:**

```
C:\TwinCAT\3.1\Config\Io\EtherCAT\ NTIL_CiA402_Servos_V1_8r2.xml
```

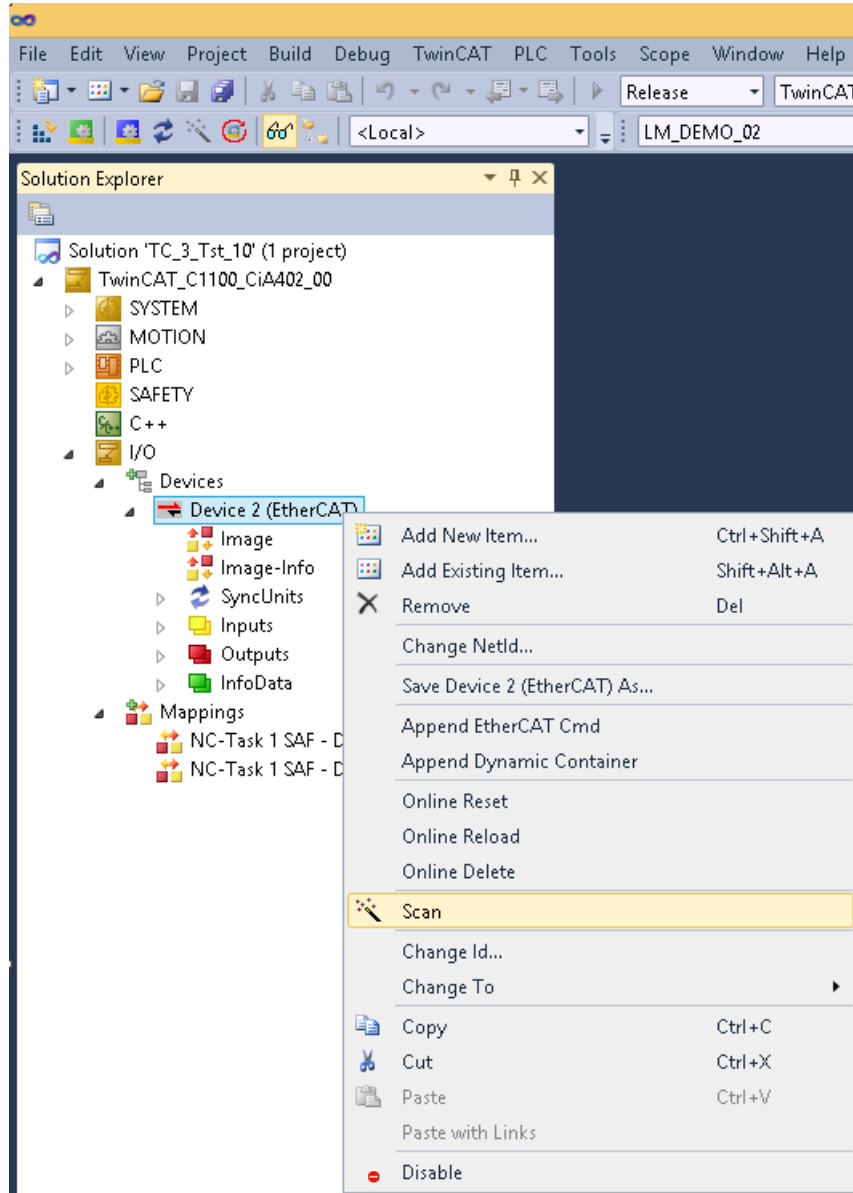
**Omron:**

```
C:\OMRON\Sysmac Studio\IODeviceProfiles\EsiFiles\UserEsiFiles\ NTIL_CiA402_Servos_V1_8r2.xml
```

If this is done the PLC should recognize the corresponding LinMot drives on the EtherCAT fieldbus automatically.

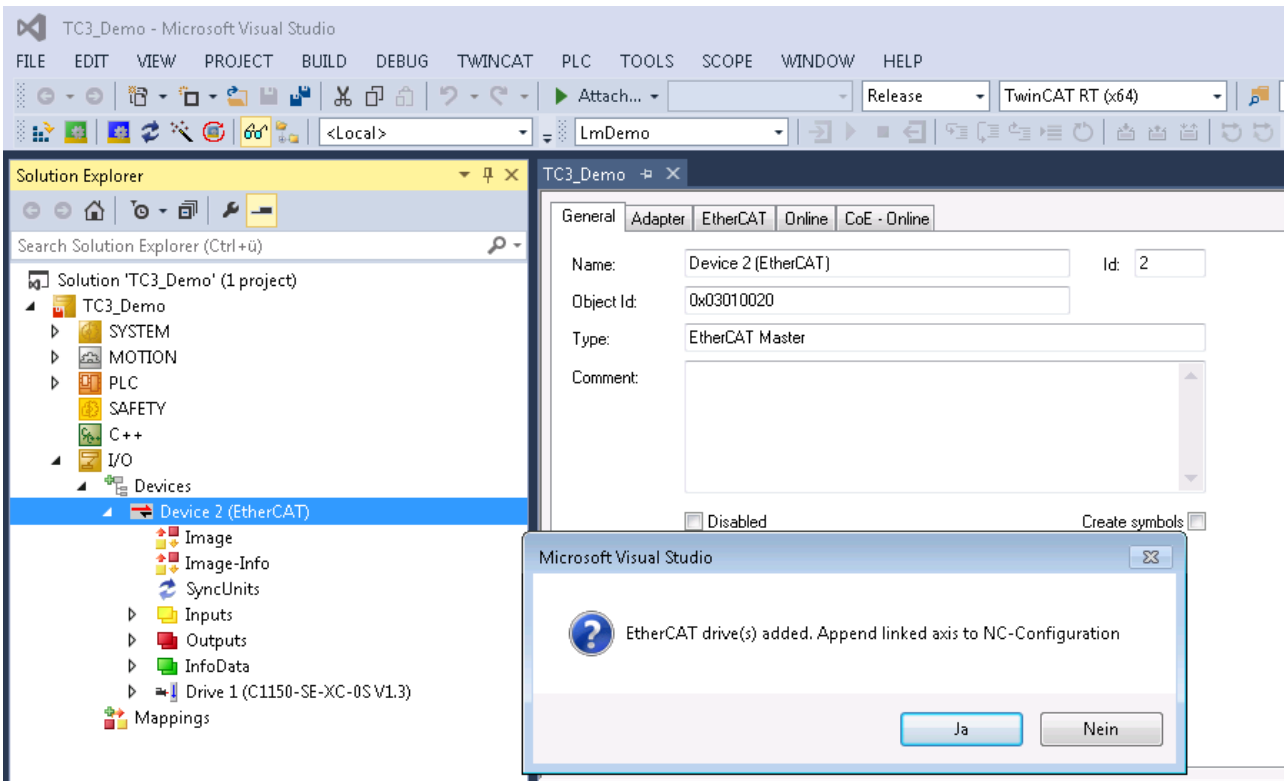
## 2.2 Scan the EtherCAT slave devices

Connect the EtherCAT LinMot SoE Servo Drive to the EtherCAT-Master and power on the signal supply. Then scan for the connected devices in the System Manager:

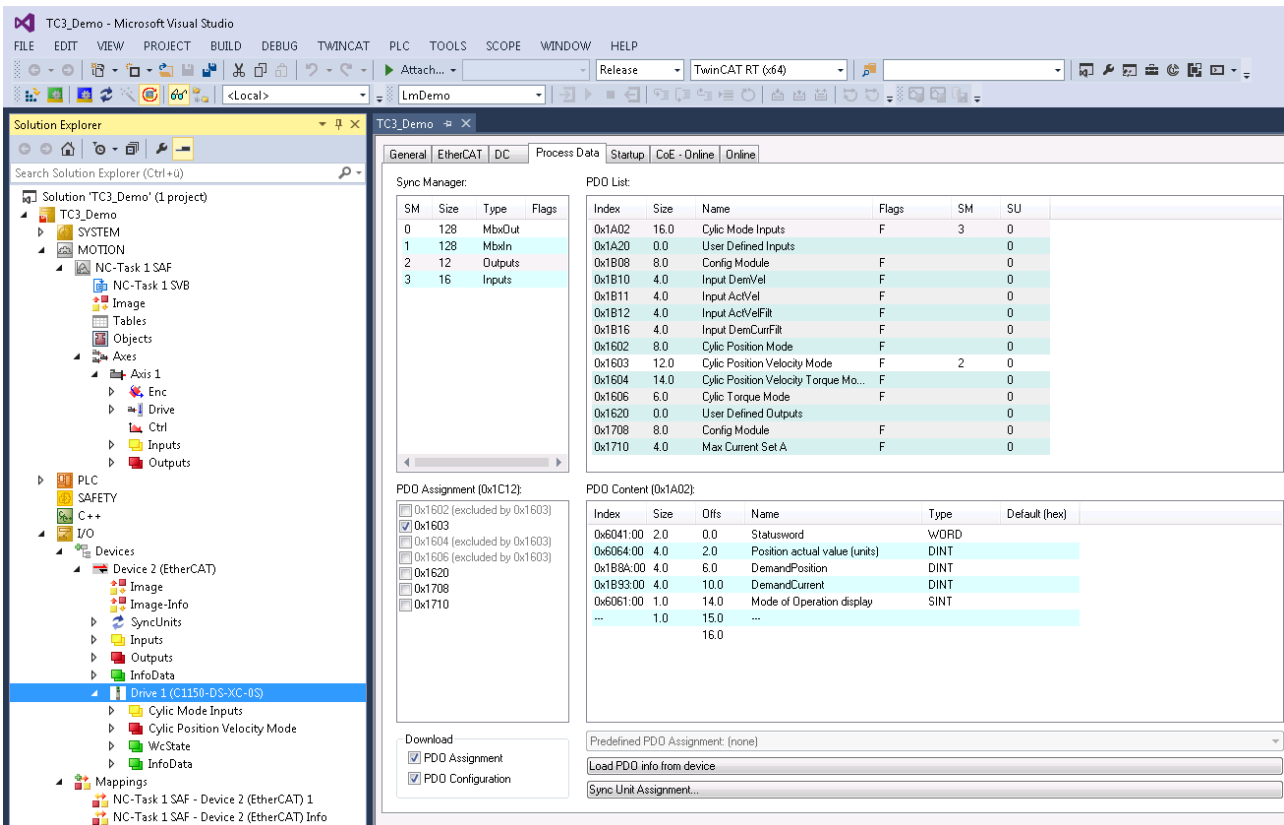


Scan for EtherCAT slave devices

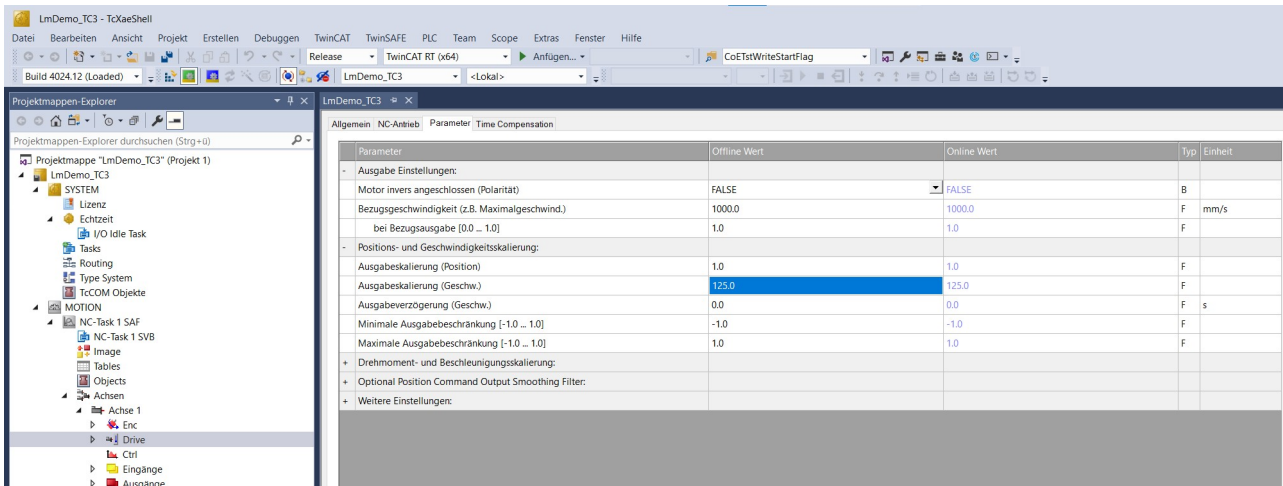




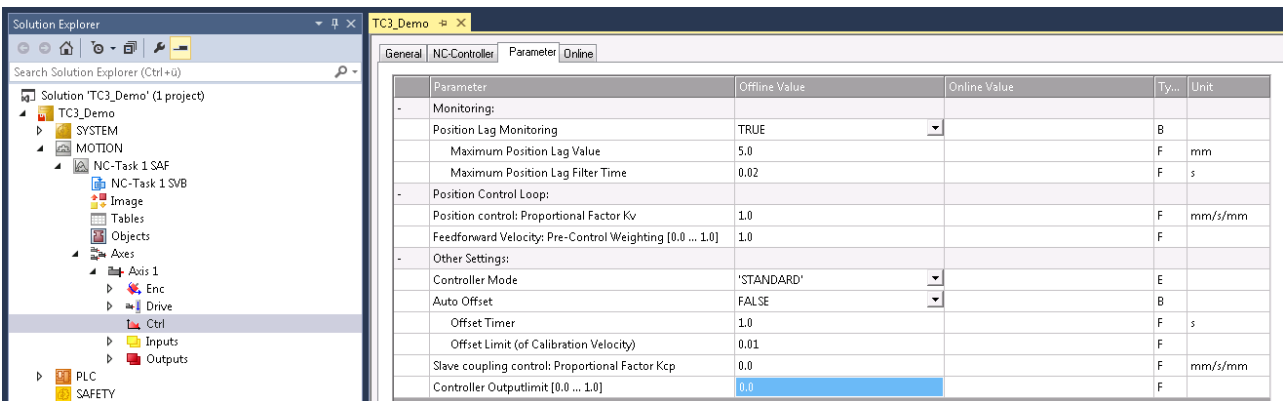
With the question Add drives to NC-configuration select yes.



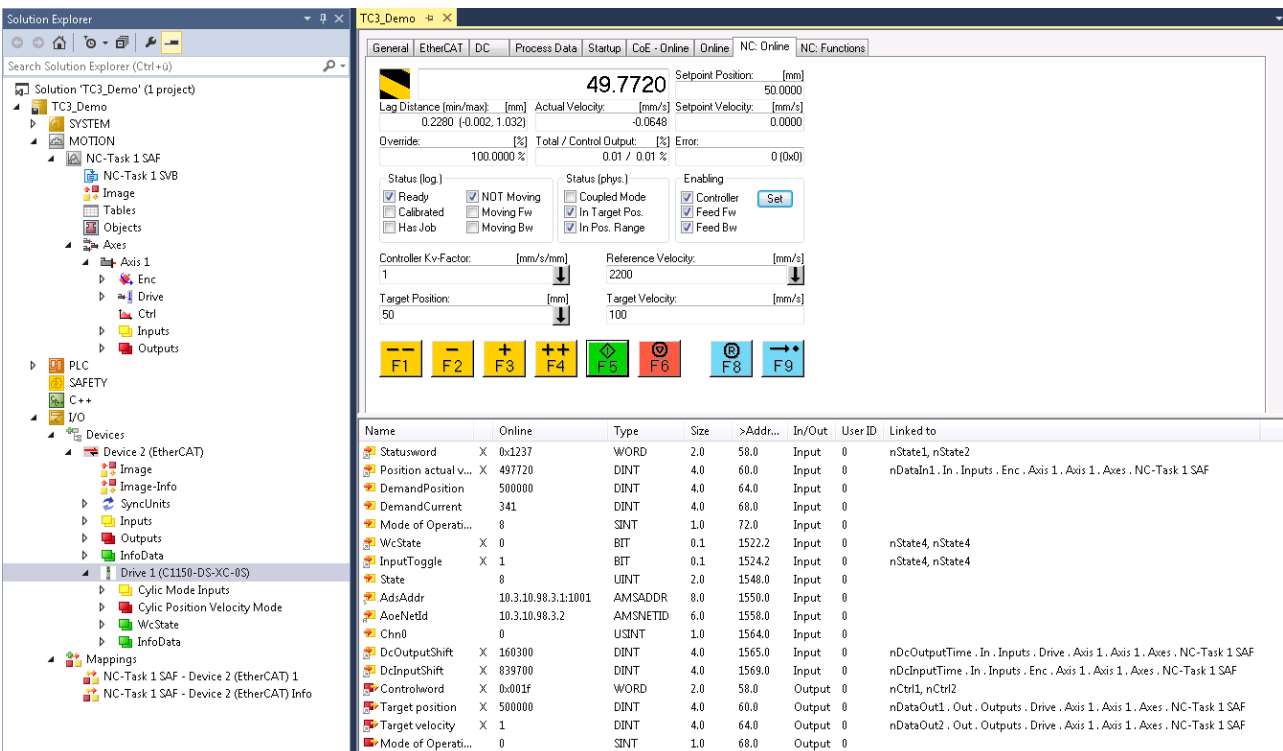
These steps add the servo drive and its NC-axis to the project.



Then the velocity output scale factor has to be set to 125.0 for correct operation



Though the position controlling is done in the drive the controller output has to be set to 0. If this is forgotten, the behaviour could be noisy. To set these NC parameters they have to be downloaded.

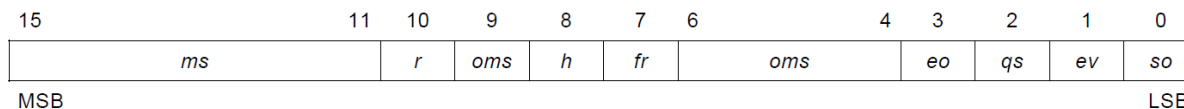


Now the servo drive can be used with system manager NC functionality when started.

### 3 Operation Modes

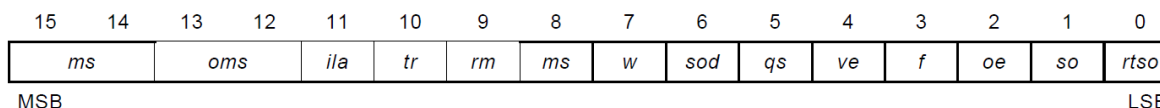
The device profile defines several modes of operation. The user will be able to activate the required function by selecting the mode of operation. They include profile position mode, homing mode, interpolated position mode, profile velocity mode, profile torque mode, velocity mode, cyclic synchronous position mode, cyclic synchronous velocity mode, and cyclic synchronous torque mode. The control word, status word and the setpoints are used mode-specific.

#### Object 6040h : Control Word



LEGEND: ms = manufacturer-specific; r = reserved; oms = operation mode specific; h = halt; fr = fault reset; eo = enable operation; qs = quick stop; ev = enable voltage; so = switch on

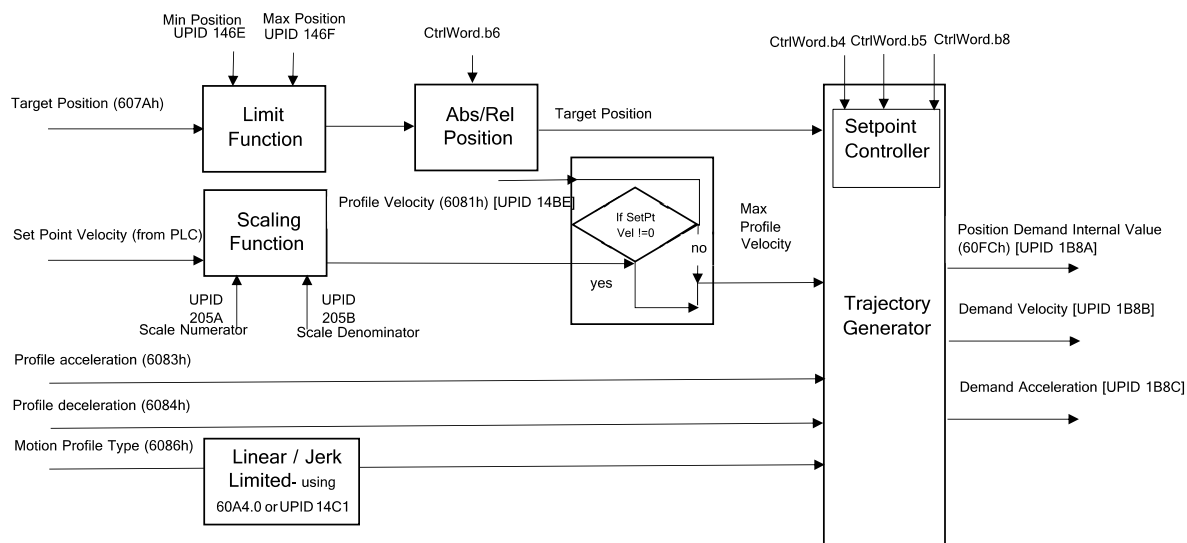
#### Object 6041h: Status Word



LEGEND: ms = manufacturer-specific; oms = operation mode specific; ila = internal limit active; tr = target reached; rm = remote; w = warning; sod = switch on disabled; qs = quick stop; ve = voltage enabled; f = fault; oe = operation enabled; so = switched on; rtso = ready to switch on

#### 3.1 Profile Position Mode (OpMode 1)

A target position is applied to the trajectory generator. It is generating a position demand value for the position control loop. Please check the below figure for the details of the scales/ limits applied for position, velocity and the other inputs like acceleration, deceleration and the selection of motion profile type.



#### Use of Control Word

15	10	9	8	7	6	5	4	3	0
See operation modes chapter	Change on set point	Halt	See operation modes chapter	Abs/rel	Change set immediately	New setpoint	See operation modes chapter		
MSB					LSB				

The setting of the setpoints is controlled by the control word bit 4 - *new setpoint* and control word bit 5 - *change set immediately*. When the bit 4 is 1, the new setpoint is buffered in the set point list as long as the free setpoints are available in the drive device. If there is no setpoint in progress, then the new setpoint shall become active immediately. If a setpoint is in progress the new setpoint will be stored in the buffer that is free. When the *change set immediately* bit of the controlword is set to 1, a single set-point is expected. All previously loaded set-points shall be discarded.

When the control word bit 6 is 0, the absolute value is taken for target position calculation. If the control word bit 6 is 1, the relative position is taken.

When the control word bit 8 - *halt* is 1 the axis will freeze . The *not freeze* bit of the control word (UPID 1D5B) will be thereby 0. When the *halt* bit is 0, the positioning shall be executed or continued and the *not freeze* bit of the control word will be 1.

The control word bit 9 - *change on set point* is fixed to 0. A change to 1 is currently not supported.

## Use of Status Word

15	14	13	12	11	10	9	0
See operation modes chapter	Following error	Set-point ack	See operation modes chapter	Target reached	See operation modes chapter		
MSB					LSB		

Status word bit 10 - *target reached* is implemented as the invert bit of *motion active*- MC SW status word bit 13. This bit can also be watched in UPID 1D77h. The bit 12 *set point ack* is 1 when the new setpoint is in process. *Set point ack* will be 0 when the previous setpoint is already processed.

Status word bit 13 is currently not supported.

## 3.2 Homing Mode (OpMode 6)

This mode describes the method by which the drive goes to home position. The different modes of homing are listed in UPID 13C4h. The homing method has to be selected using the LinMot Tool. The UPID 13C4h gives different UPID selection as seen below.

Name	Value	Raw Data	Value...	UPID	Type	Scale	Offset	Min	Max	Def...	Att.
<input type="radio"/> Actual Position	Off	0000h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Mechanical Stop Negative Search	Off	0001h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Mechanical Stop Positive Search	Off	0002h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Limit Switch Negative	Off	000Eh	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Limit Switch Positive	Off	000Fh	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch Negative	Off	0003h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch Positive	Off	0010h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch And Mechanical Stop Negative	Off	0004h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch And Mechanical Stop Positive	Off	0005h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch And Limit Switch Negative	Off	0006h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Home Switch And Limit Switch Positive	Off	0007h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 And Mechanical Stop Negative	Off	0008h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 And Mechanical Stop Positive	Off	0009h	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 And Limit Switch Negative	Off	000Ah	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 And Limit Switch Positive	Off	000Bh	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 Negative Search	Off	000Ch	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> Index Dn.X13 Positive Search	Off	000Dh	0f	13C4h	Ulnr16						Rw (GRUW)
<input type="radio"/> No Drive Homing	On	0011h	0n	13C4h	Ulnr16					X	Rw (GRUW)

## Control Word

15	9	8	7	6	5	4	3	0
See operation modes chapter	Halt		See operation modes chapter	Reserved (0)		Homing Operation Start	See operation modes chapter	

MSB

LSB

The bit 4 of control word - Homing operation start is linked to the UPID 1D61h. The bit 8 halt is not supported in this version.

**Status Word**

15	14	13	12	11	10	9	0
See operation modes chapter	Homingerror		Homing Attained	See operation modes chapter	Target reached	See operation modes chapter	

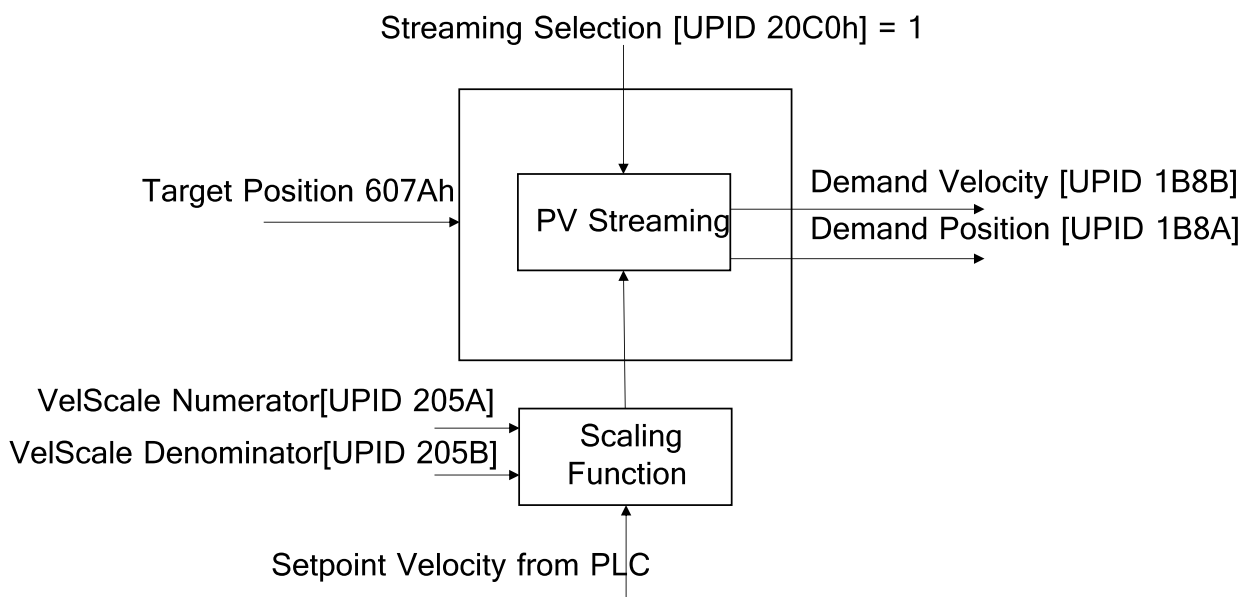
MSB

LSB

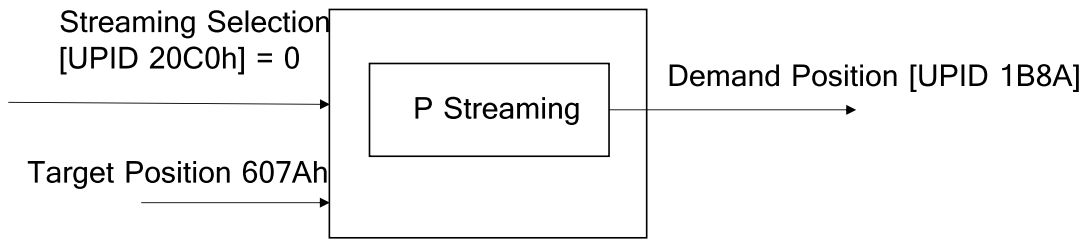
The bit 10 of status word is 1 when the homing is interrupted or not started. When the homing is finished the bit 10 and bit 12 are high.

**3.3 Cyclic Sync Position Mode (OpMode 8)**

In this operation mode, it provides a target position to the drive device, which performs position control and velocity control depends on the user input to the UPID 20C0h. The behavior of the control function is influenced by the control parameters like the limit functions. The default selection of OpMode 8 in Streaming Selection - UPID 20C0h is 1 which is PV streaming.

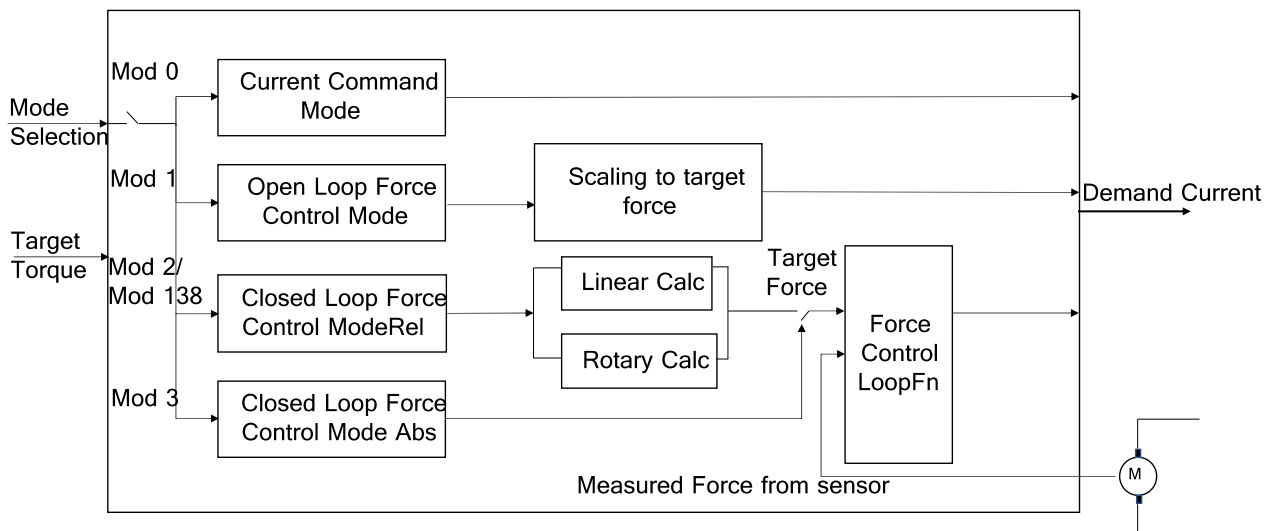


The legacy mode is P streaming which is selected by Streaming Selection - UPID 20C0h as 0. This is also supported.



### 3.4 Cyclic Sync Torque Mode (OpMode 10)

In this mode, the trajectory generator will provide the target force/torque to the drive. There are 4 modes of selection based on the user input on UPID 2070h. They are current command mode, openloop force/torque control mode, closed loop force/torque control mode relative, closed loop force/torque Ctrl Mode Abs. This mode is used by the PDO 0x1604 and 0x1614.



## 4 Process Data Object (PDO) Configuration

The cyclic process data is configured in the master and transmitted to the slave during startup. The default mapping is documented in the tables below. The inputs and outputs correspond to the PLC point of view. For a detailed description of the exchanged data and its meaning refer to [1]. For a detailed description of the PDO data refer to [1] or have a look at the TwinCAT demo program, which is included with the LinMot-Talk software.

**4.1 Input PDO Modules**

The screenshot displays the configuration interface for Input PDO Modules. It includes several panels:

- General Tab:** Shows navigation options like General, EtherCAT, DC, Process Data, Startup, CoE - Online, Online, NC: Online, and NC: Functions.
- Sync Manager:** A table listing synchronization managers (SM) with their sizes and types.
 

SM	Size	Type	Flags
0	128	MbxOut	
1	128	MbxIn	
2	12	Outputs	
3	16	Inputs	
- PDO List:** A table listing predefined PDO objects.
 

Index	Size	Name	Flags	SM	SU
0x1A02	16.0	Cyclic Mode Inputs	F	3	0
0x1A20	0.0	User Defined Inputs			0
0x1B08	8.0	Config Module	F		0
0x1B10	4.0	Input DemVel	F		0
0x1B11	4.0	Input ActVel	F		0
0x1B12	4.0	Input ActVelFilt	F		0
0x1B16	4.0	Input DemCurrFilt	F		0
0x1602	8.0	Cyclic Position Mode	F		0
0x1603	12.0	Cyclic Position Velocity Mode	F	2	0
0x1604	14.0	Cyclic Position Velocity Torque Mo...	F		0
0x1606	6.0	Cyclic Torque Mode	F		0
0x1620	0.0	User Defined Outputs			0
0x1708	8.0	Config Module	F		0
0x1710	4.0	Max Current Set A	F		0
- PDO Assignment (0x1C13):** A list of checkboxes for assigning PDOs to SMs. 0x1A02 is checked.
- PDO Content (0x1A02):** A table showing the content of the selected PDO.
 

Index	Size	Offs	Name	Type	Default (hex)
0x6041:00	2.0	0.0	Statusword	WORD	
0x6064:00	4.0	2.0	Position actual value (units)	DINT	
0x1B8A:00	4.0	6.0	DemandPosition	DINT	
0x1B93:00	4.0	10.0	DemandCurrent	DINT	
0x6061:00	1.0	14.0	Mode of Operation display	SINT	
---	1.0	15.0	---		
		16.0			

Overview of the predefined Input Process data objects

**4.1.1 Cyclic Mode Inputs 0x1A02**

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1A02	16	-	Variables	RECORD
0x6041:00	2	0	Statusword	Uint16
0x6064:00	4	2	Position actual value	Int32
0x1B8A:00	4	6	DemandPosition	Int32
0x1B93:00	4	10	DemandCurrent	Int32
0x6061:00	1	14	Mode of Operation display	Byte
	1	15	Byte Padding	Byte

This module could be used to map the inputs of an CiA402 NC axis.

**4.1.2 Cyclic Mode Inputs 2 0x1A03**

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1A03	14	-	Variables	RECORD
0x6041:00	2	0	Statusword	Uint16

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1A03	14	-	Variables	RECORD
0x6064:00	4	2	Position actual value	Int32
0x6062:00	4	6	DemandPosition	Int32
0x6077:00	2	10	Torque actual value	Int16
0x6061:00	1	12	Mode of Operation display	Byte
	1	13	Byte Padding	Byte

This module could be used to map the inputs of an CiA402 NC axis.

The "Torque actual value" is calculated out of the "Actual Torque/Force" (UPID: 1BBFh/1BFFh) multiplied with 5000 divided with the "Maximal Torque/Force" (UPID: 1BBEh/1BB0h).

If the Closed Loop Force Control Mode is active the measured torque/force (UPID: 1EA1h) is taken to calculate the " Actual Torque/Force".

#### 4.1.3 Cyclic Inputs 0x1A12

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1A12	16	-	Variables	RECORD
0x6041:00	2	0	Statusword	Uint16
0x6064:00	4	2	Position actual value	Int32
0x1B8A:00	4	6	DemandPosition	Int32
0x1B93:00	4	10	DemandCurrent	Int32

This module could be used to map the inputs of an CiA402 NC axis.

#### 4.1.4 User Defined Inputs 0x1A20

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1A20	2..32	-	Variables	RECORD
1..8			User defined Parameter/Variables accessed by UPID	

The PDO 0x1620 could be used, to read Variables/Parameters for which no predefined PDO exists. It is possible to map 1 to 8 entries defined by its UPID in this PDO. Allowed are only 16 or 32 bit entries. The defined Size of the data has to match with the size, defined by the UPID.

#### 4.1.5 Config Module 0x1B08

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B08	8	-	Variables	RECORD
0x1B09:00	2	0	Config Status Word	Uint16
0x1B0A:00	2	2	Config Index/..	Uint16
0x1B0B:00	4	4	Config Value	Word32

This module is the feedback data module of the module 1708 "Configuration Module Output".



#### 4.1.6 Input Demvel 0x1B10

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B10	4	-	Variables	
0x1B8B:00	4	0	DemandVelocity	Int32

The Demand Velocity is backscaled with the parameters “Velocity Scale Denominator” and “Velocity Scale Numerator”.

#### 4.1.7 Input DemCurrFilt 0x1B16

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B16	4	-	Variables	
0x1B98:00	4	0	Demand Current Filtered	Int32

The Demand Current filtered (UPID 1B98).

#### 4.1.8 Input ActVelFilt 0x1B11

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B11	4	-	Variables	
0x1B8E:00	4	0	ActualVelocity	Int32

The “ActualVelocity” is backscaled with the parameters “Velocity Scale Denominator” and “Velocity Scale Numerator”.

#### 4.1.9 Input ActVelFilt 0x1B12

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B12	4	-	Variables	
0x1BAF:00	4	0	ActualVelocityFilt	Int32

The "ActualVelocityFilt" is backscaled with the parameters "Velocity Scale Denominator" and "Velocity Scale Numerator".

#### 4.1.10 Mon Channel 1 0x1B28

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B28	4	-	Variables	
0x20A8:00	4	0	Mon Channel 1	Int32

The data of the variable which is defined by the parameter Channel 1 UPID.

#### 4.1.11 Mon Channel 2 0x1B29

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B29	4	-	Variables	
0x20A8:00	4	0	Mon Channel 2	Int32

The data of the variable which is defined by the parameter Channel 2 UPID.

#### 4.1.12 Mon Channel 3 0x1B2A

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B2A	4	-	Variables	
0x20A8:00	4	0	Mon Channel 3	Int32

The data of the variable which is defined by the parameter Channel 3 UPID.

#### 4.1.13 Mon Channel 4 0x1B2B

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1B2B	4	-	Variables	
0x20A8:00	4	0	Mon Channel 4	Int32

The data of the variable which is defined by the parameter Channel 4 UPID.

## 4.2 Output PDO Modules

General | EtherCAT | DC | **Process Data** | Startup | CoE - Online | Online | NC: Online | NC: Functions

Sync Manager:

SM	Size	Type	Flags
0	128	MbxOut	
1	128	MbxIn	
2	12	Outputs	
3	16	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A02	16.0	Cyclic Mode Inputs	F	3	0
0x1A20	0.0	User Defined Inputs			0
0x1B08	8.0	Config Module	F		0
0x1B10	4.0	Input DemVel	F		0
0x1B11	4.0	Input ActVel	F		0
0x1B12	4.0	Input ActVelFilt	F		0
0x1B16	4.0	Input DemCurrFilt	F		0
0x1602	8.0	Cyclic Position Mode	F		0
0x1603	12.0	Cyclic Position Velocity Mode	F	2	0
0x1604	14.0	Cyclic Position Velocity Torque Mo...	F		0
0x1606	6.0	Cyclic Torque Mode	F		0
0x1620	0.0	User Defined Outputs			0
0x1708	8.0	Config Module	F		0
0x1710	4.0	Max Current Set A	F		0

PDO Assignment (0x1C12):

- 0x1602 (excluded by 0x1603)
- 0x1603
- 0x1604 (excluded by 0x1603)
- 0x1606 (excluded by 0x1603)
- 0x1620
- 0x1708
- 0x1710

PDO Content (0x1603):

Index	Size	Offs	Name	Type	Default (hex)
0x6040:00	2.0	0.0	Controlword	WORD	
0x607A:00	4.0	2.0	Target position	DINT	
0x60FF:00	4.0	6.0	Target velocity	DINT	
0x6060:00	1.0	10.0	Mode of Operation	SINT	
---	1.0	11.0	---		
		12.0			

Overview of the predefined Output Process data objects

### 4.2.1 Cyclic Position Mode 0x1602

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1602	8	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x607A:00	4	2	Target position	Int32
0x6060:00	1	6	Mode of Operation	Byte
	1	7	Byte Padding	Byte

### 4.2.2 Cyclic Position Velocity Mode 0x1603

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1603	12	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x607A:00	4	2	Target position	Int32
0x60FF:00	4	6	Target velocity	Int32

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1603	12	-	Variables	RECORD
0x6060:00	1	10	Mode of Operation	Byte
	1	11	Byte Padding	Byte

Default input PDO mapping of 12 Bytes

#### 4.2.3 Cyclic Position Velocity Torque Mode 0x1604

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1604	14	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x607A:00	4	2	Target position	Int32
0x60FF:00	4	6	Target velocity	Int32
0x6071:00	2	10	Target torque	Int16
0x6060:00	1	12	Mode of Operation	Byte
	1	13	Byte Padding	Byte

This module can be used, if the operation mode has to be changed during run time. At the moment the cyclic position mode (0x08), the cyclic torque mode (0xA) and the cyclic closed loop torque mode (0x8A) are supported. To change the operation mode simply change the value of "Mode of Operation" variable.

#### 4.2.4 Cyclic Torque Mode 0x1606

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1606	6	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x6071:00	2	2	Target torque	Int32
0x6060:00	1	4	Mode of Operation	Byte
	1	5	Byte Padding	Byte

#### 4.2.5 Cyclic Position Velocity 0x1613

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1613	10	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x607A:00	4	2	Target position	Int32
0x60FF:00	4	6	Target velocity	Int32

Default input PDO mapping of 10 Bytes

#### 4.2.6 Cyclic Position Velocity Torque 0x1614

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1614	12	-	Variables	RECORD
0x6040:00	2	0	Controlword	Word16
0x607A:00	4	2	Target position	Int32
0x60FF:00	4	6	Target velocity	Int32
0x6071:00	2	10	Target torque	Int16

At the moment the cyclic position/velocity mode (0x08), the cyclic torque mode (0xA) and the cyclic closed loop torque mode (0x8A) are supported. To select if cyclic position/velocity (default value) mode or position mode is used, use change parameter "Cyclic position mode" (UPID 20C0h).

#### 4.2.7 User Defined Outputs 0x1620

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1620	2..32	-	Variables	RECORD
1..8			User defined Parameter/Variables accessed by UPID	

The PDO 0x1620 could be used to set Variables/Parameters for which no predefined PDO exists. It is possible to map 1 to 8 entries defined by its UPID in this PDO. Allowed are only 16 or 32 bit entries. The defined Size of the data has to match with the size defined with the UPID.

#### 4.2.8 Config Module 0x1708

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1708	8	-	Variables	RECORD
0x1709:00	2	0	Config Control Word	Uint16
0x170A:00	2	2	Config Index/..	Uint16
0x170B:00	4	4	Config Value	Word32

With this module the LinMot drive can be completely configured. So it gives access over parameters curves command table entries and the error log. The detail functionality is described in the document [2] "Configuration over fieldbus SG5". As response module "Configuration Module Input" (0x1B08) has to be configured.

#### 4.2.9 Max Current Set A 0x1710

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1710	4	-	Variables	
0x13A6:00	4	0	Max Current Set A	Uint32

Could be used to change the maximal current of the position controller set A, during runtime.

#### 4.2.10 Torque/force limits 0x1711

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1711	4	-	Variables	RECORD
0x60E0:00	2	0	Positive torque/force limit 5000 = maximal torque value positive	Uint16
0x60E1:00	2	2	Negative torque/force limit 5000 = maximal torque value negative	Uint16

With this module the positive and negative torque/force value could be individually set cyclic.

#### 4.2.11 Par Channel 1 0x1728

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1728	4	-	Variables	RECORD
0x20B0:00	4	0	Value written to parameter/variable.	Int32

With this module a parameter/variable could be directly written from the PLC the parameter/variable is defined by the parameter "Channel 1 UPID".

#### 4.2.12 Par Channel 2 0x1729

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1729	4	-	Variables	RECORD
0x20B0:00	4	0	Value written to parameter/variable.	Int32

With this module a parameter/variable could be directly written from the PLC the parameter/variable is defined by the parameter "Channel 2 UPID".

#### 4.2.13 Par Channel 3 0x172A

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1728	4	-	Variables	RECORD
0x20B0:00	4	0	Value written to parameter/variable.	Int32

With this module a parameter/variable could be directly written from the PLC the parameter/variable is defined by the parameter "Channel 3 UPID".

#### 4.2.14 Par Channel 4 0x172B

Index	Size [Byte]	Byte Offset	Name	Data Type
0x1728	4	-	Variables	RECORD
0x20B0:00	4	0	Value written to parameter/variable.	Int32

With this module a parameter/variable could be directly written from the PLC the parameter/variable is defined by the parameter "Channel 4 UPID".

### 4.3 Typical Startup Telegrams

<span>General</span> <span>EtherCAT</span> <span>DC</span> <span>Process Data</span> <span>Startup</span> <span>CoE - Online</span> <span>Online</span> <span>NC: Online</span> <span>NC: Functions</span>							
Transition	Protocol	Index	Data	Comment			
<b>C</b> <PS>	CoE	0x1C12:00	0x00 (0)	clear sm pdos (0x1C12)			
<b>C</b> <PS>	CoE	0x1C13:00	0x00 (0)	clear sm pdos (0x1C13)			
<b>C</b> <PS>	CoE	0x1A20:00	0x00 (0)	clear pdo 0x1A20 entries			
<b>C</b> <PS>	CoE	0x1620:00	0x00 (0)	clear pdo 0x1620 entries			
<b>C</b> <PS>	CoE	0x1C12:01	0x1603 (5635)	download pdo 0x1C12:01 i...			
<b>C</b> <PS>	CoE	0x1C12:00	0x01 (1)	download pdo 0x1C12 count			
<b>C</b> <PS>	CoE	0x1C13:01	0x1A02 (6658)	download pdo 0x1C13:01 i...			
<b>C</b> <PS>	CoE	0x1C13:00	0x01 (1)	download pdo 0x1C13 count			
<b>A</b> <IP, PS>	AoE	1/3	0A 03 0A 62 03 02	AoE Init Cmd (download N...			

This figure shows the startup telegram list of LinMot CiA402 servo drive

## 5 Asynchronous Configuration Protocol CoE

For configuration purpose (Parameter Handling) the standard Sercos over EtherCAT CoE-Protocol is used.

### 5.1 Communication CiA402 Profile Area(1000h-1FFFh)

General | EtherCAT | DC | Process Data | Startup | **CoE - Online** | Online

Update List     Auto Update     Single Update     Show Offline Data

Advanced...   

Add to Startup...        Module OD (AoE Port):

Index	Name	Flags	Value
1000	Device type	M RO	0x00020192 (131474)
1008	Device name	M RO	C1250DSXC0S
1009	Hardware version	RO	V1RG
100A	Software version	RO	6.6 Build 20160928
+ 1018:0	Identity	RO	> 4 <
+ 1602:0	Cyclic Position Mode	RO	> 4 <
+ 1603:0	Cyclic Position Velocity Mode	RO	> 5 <
+ 1604:0	Cyclic Position Velocity Torque Mode	RO	> 6 <
+ 1606:0	Cyclic Torque Mode	RO	> 4 <
+ 1620:0	User Defined Outputs	RW	> 0 <
+ 1708:0	Config Module	RO	> 3 <
+ 1A02:0	Cyclic Mode Inputs	RO	> 6 <
+ 1A20:0	User Defined Inputs	RW	> 0 <
+ 1B08:0	Config Module	RO	> 3 <
+ 1B10:0	Input DemVel	RO	> 1 <
+ 1B11:0	Input ActVel	RO	> 1 <
+ 1B12:0	Input ActVelFilt	RO	> 1 <
+ 1C00:0	Sync Man Communication type	RO	> 4 <
+ 1C12:0	Sync Manager 2 PDO Assignment	RW	> 1 <
+ 1C13:0	Sync Manager 3 PDO Assignment	RW	> 1 <
6007	Abort connection option code	RW	0
603F	Error code	RO	100
6040	Controlword	RW P	0x0000 (0)
6041	Statusword	RO P	0x0288 (648)
6060	Mode of Operation	RW P	8
6061	Mode of Operation display	RO P	8
6062	Position demand value	RW P	0
6064	Position actual value ( units )	RO P	0
607A	Target position	RW P	0
607C	Home offset	RW P	-100000
6098	Homing method	RW P	-111
+ 6099:0	Homing speeds	RO	> 2 <
609A	Homing acceleration	RW P	0x00002710 (10000)
60FC	Position demand internal value	RW P	0
60FF	Target velocity	RW P	0

LinMot CiA402 Object Dictionary



### 5.1.1 Homing method Object 6098

As homing method only the Device specific values -128..-111 are supported, the object 6098 value is calculated out of the UPID 13C4 (Homing mode) value added with -128.

UPID 0x13C4 value	Object 0x6098 value	Description
0	-128	Actual Position
1	-127	Mechanical Stop Negative Search
.	.	.
17	-111	No drive Homing

### 5.1.2 Homing speeds Object 6099

In the Linmot-drive only one homing speeds exist, therefore writing to subindex 1 or 2 of the object 6099 both changes the value of the UPID 13C8 (Homing Max Speed).

## 5.2 Manufacturer specific Profile Area(2000h-5FFFh)

Parameters can be modified via their UPIDs (Unique Parameter ID) via CoE. To use a UPID command, an SDO read (FB\_EcCoeSdoReadEx) or write (FB\_EcCoeSdoWriteEx) has to be performed on the index "2000h + UPID". The sub-index specifies the command which is performed

Sdo Service	Index	Sub-Index	Description
Read	2000h+UPID	01h	Parameter UPID read RAM value
Write	2000h+UPID	01h	Parameter UPID write RAM value
Read	2000h+UPID	02h	Parameter UPID read ROM value
Write	2000h+UPID	02h	Parameter UPID write ROM value
Read	2000h+UPID	03h	Parameter UPID read minimal value
Read	2000h+UPID	04h	Parameter UPID read maximal value
Read	2000h+UPID	05h	Parameter UPID read default value
Write	2000h+UPID	06h	Parameter UPID write RAM and ROM value
Write	2000h	07h	Parameter Default OS SW instance
Write	2000h	08h	Parameter Default MC SW instance
Write	2000h	09h	Parameter Default Intf SW instance
Write	2000h	0Ah	Parameter Default Appl SW instance
Write	2000h	0Bh	Reset device
Write	2000h	18h	Parameter Default MC SW instance with immediate response
Write	2000h	24h	Parameter Start Read UPID List
Read	2000h	25h	Parameter Read next UPID List entry
Write	2000h	26h	Parameter Start Read modified UPID List
Read	2000h	27h	Parameter Read next modified UPID List entry
Write	2000h	35h	Stop MC and Appl SW instances

Sdo Service	Index	Sub-Index	Description
Write	2000h	36h	Start MC and Appl SW instances
Write	2000h	40h	Curves copy curves from RAM to FLASH
Write	2000h	41h	Curves delete all in RAM
Write	2000h+ID	50h	Curves start write curve in RAM
Write	2000h+ID	54h	Curves write curve info block data in RAM
Write	2000h+ID	53h	Curves write curve set point data in RAM
Read	2000h+ID	60h	Curves read info and data size
Read	2000h+ID	61h	Curves read info block data
Read	2000h+ID	62h	Curves read setpoint data
Read	2000h	70h	Read error counters
Read	2000h+ID	71h	Read error code of logged entry
Read	2000h+ID	72h	Read error time low of logged entry
Read	2000h+ID	73h	Read error time high of logged entry
Read	2000h+ID	74h	Read error text stringlet 0 of error code
Read	2000h+ID	75h	Read error text stringlet 1 of error code
Read	2000h+ID	76h	Read error text stringlet 2 of error code
Read	2000h+ID	77h	Read error text stringlet 3 of error code
Read	2000h+ID	78h	Read error text stringlet 4 of error code
Read	2000h+ID	79h	Read error text stringlet 5 of error code
Read	2000h+ID	7Ah	Read error text stringlet 6 of error code
Read	2000h+ID	7Bh	Read error text stringlet 7 of error code
Write	2000h	80h	Command Table copy entries from RAM to FLASH
Write	2000h	81h	Command Table delete all entries in RAM
Write	2000h+ID	82h	Command Table delete single entry in RAM
Write	2000h+ID	83h	Command Table start write entry in RAM
Write	2000h+ID	84h	Command Table write entry data in RAM
Read	2000h+ID	85h	Command Table read entry data size
Read	2000h+ID	86h	Command Table read entry data
Read	2000h	87h	Command Table read presence list entries 0..31
Read	2000h	88h	Command Table read presence list entries 32..63
Read	2000h	89h	Command Table read presence list entries 64..95
Read	2000h	8Ah	Command Table read presence list entries 96..127
Read	2000h	8Bh	Command Table read presence list entries 128..159
Read	2000h	8Ch	Command Table read presence list entries 160..191
Read	2000h	8Dh	Command Table read presence list entries 192..223
Read	2000h	8Eh	Command Table read presence list entries 224..255

---

Sdo Service	Index	Sub-Index	Description

### 5.2.1 Parameter UPID read RAM value

Read the RAM value of the parameter specified by its UPID, and stores the result in the 4 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	01h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.2 Parameter UPID write RAM value

Write the content of the write\_buffer to the RAM value of the parameter specified by its UPID. The write\_buffer can have a unique size of 4 bytes.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	01h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pSrcBuf	DWORD	ADR(write_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.3 Parameter UPID read ROM value

Read the ROM value of the parameter specified by its UPID, and stores the result in the 4 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	02h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.4 Parameter UPID write ROM value

Write the content of the write\_buffer to the ROM value of the parameter specified by its UPID. The write\_buffer can have a unique size of 4 bytes.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	02h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pSrcBuf	DWORD	ADR(write_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.5 Parameter UPID read minimal value

Read the minimal value of the parameter specified by its UPID, and stores the result in the 4 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	03h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.6 Parameter UPID read maximal value

Read the maximal value of the parameter specified by its UPID, and stores the result in the 4 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	04h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.7 Parameter UPID read default value

Read the default value of the parameter specified by its UPID, and stores the result in the 4 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	05h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.8 Parameter UPID write RAM & ROM value

Write the content of the write\_buffer to the RAM and ROM value of the parameter specified by its UPID. The write\_buffer can have a unique size of 4 bytes.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	06h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + UPID
Input	pSrcBuf	DWORD	ADR(write_buffer (4bytes))
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.9 Parameter default OS SW instance

All parameters of the OS SW instance are set to their default value. The SDO response is given when the defaulting process is finished, this can last several seconds.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	07h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.10 Parameter default MC SW instance

All parameters of the MC SW instance are set to their default value. The SDO response is given when the defaulting process is finished, this can last several seconds.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	08h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID



### 5.2.11 Parameter default Intf SW instance

All parameters of the interface SW instance are set to their default value. The SDO response is given when the defaulting process is finished, this can last several seconds.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	09h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.12 Parameter default Appl SW instance

All parameters of the application SW instance are set to their default value. The SDO response is given when the defaulting process is finished, this can last several seconds.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	0Ah (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.13 Reset device

This service resets the device.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	0Bh (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.14 Parameter default MC SW instance with immediate response

All parameters of the MC SW instance are set to their default value, the SDO response is given immediate. Take into account that the defaulting process last up to 10 seconds don't take other actions before this time is elapsed.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	18h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.15 Start read UPID List

Specify the SW layer by its start UPID of which the UPID list will be read out. The list contains all parameters and variables of the SW layer.

FUNCTION_BLOCK FB_EcCoESdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AoE NetID
Input	nSlaveAddr	T_AmsPort	ADS Port
Input	nSubIndex	UDINT	0024h (LinMot Service ID)
Input	nIndex	UDINT	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (4bytes)) Start UPID: 0000h: OS SW layer 1000h: MC SW layer 2000h: Intf SW layer 3000h: Appl SW layer
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bCompleteAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.16 Read next UPID List entry

Read the response state, UPID, address usage and ROM value of the parameter and the RAM value of the variables. The reading of the list doesn't stop at the end of a SW instance, only at the end of all instances.

FUNCTION_BLOCK FB_EcCoESdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AMS NetID
Input	nSlaveAddr	T_AmsPort	ADS Port
Input	nSubIndex	UDINT	0025h (LinMot Service ID)
Input	nIndex	UDINT	2000h
Input	pDstBuf	Struct	ADR(read_buffer (10bytes))
Input	cbBufLen	UDINT	Always 10 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bCompleteAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

Response Data Structure

Offset	Name	Type	Description
0	Res State	UINT	0x0000: No error 0x00C5: Reading not initialized 0x00C6: No UPID found (finished)
2	UPID	UINT	UPID of Parameter Or Variable
4	Value	UDINT	Value of Parameter
8	Address usage	UINT	

### 5.2.17 Start read modified UPID List

Specify the SW layer by its start UPID of which the UPID list will be read out. The list contains all parameters and variables of the SW layer.

FUNCTION_BLOCK FB_EcCoESdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AoE NetID
Input	nSlaveAddr	T_AmsPort	ADS Port
Input	nSubIndex	UDINT	0026h (LinMot Service ID)
Input	nIndex	UDINT	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (4bytes)) Start UPID: 0000h: OS SW layer 1000h: MC SW layer 2000h: Intf SW layer

FUNCTION_BLOCK FB_EcCoESdoWriteEx			
Direction	Name	Type	Description
			3000h: Appl SW layer
Input	cbBufLen	UDINT	Always 4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bCompleteAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.18 Read next modified UPID List entry

Read the response state, UPID, address usage and ROM value of the next modified parameter. The reading of the list doesn't stop at the end of a SW instance, only at the end of all instances.

FUNCTION_BLOCK FB_EcCoESdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AMS NetID
Input	nSlaveAddr	T_AmsPort	ADS Port
Input	nSubIndex	UDINT	0027h (LinMot Service ID)
Input	nIndex	UDINT	2000h
Input	pDstBuf	Struct	ADR(read_buffer (10bytes))
Input	cbBufLen	UDINT	Always 10 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bCompleteAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### Response Data Structure

Offset	Name	Type	Description
0	Res State	UINT	0x0000: No error 0x00C5: Reading not initialized 0x00C6: No UPID found (finished)
2	UPID	UINT	UPID of Parameter Or Variable
4	Value	UDINT	Value of Parameter
8	Address usage	UINT	

### 5.2.19 Stop MC and Application SW instances

This service stops the execution of the MC and application SW layers. This command should be used before configuring (writing to ROM values) of these instances.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	35h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.20 Start MC and Application SW instances

This service starts the execution of the MC and application SW layers. This command should be used after configuring (writing to ROM values) of these instances are finished.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	36h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.21 Curves copy curves from RAM to FLASH

This service copies the actual in the RAM defined curves to the FLASH memory, so they are available after power up. Use this command only with stopped MC SW!

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	40h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.22 Curves delete all curves in RAM

This service deletes all curves in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	41h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.23 Curves start write curve in RAM

This service initiates the writing of a new curve in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	50h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer)
Input	cbBufLen	UDINT	4 bytes: <ul style="list-style-type: none"> <li>• UINT: Info Data Size</li> <li>• UINT: Set Point Data Size</li> </ul>
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.24 Curves write curve info block data in RAM

This service writes the curve info data block in the RAM, it has to be repeated until the whole info data block is written.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	53h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer)
Input	cbBufLen	UDINT	4 bytes data of curve info block
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID



### 5.2.25 Curves write curve set point data in RAM

This service writes the curve setpoint data block in the RAM, it has to be repeated until all setpoints are written.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	53h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer)
Input	cbBufLen	UDINT	4 bytes of setpoint data
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.26 Curves read info and setpoint data block size in RAM

Read the status and size of the data blocks of the curve defined by its ID the data is stored in the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	60h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (6bytes)) <ul style="list-style-type: none"> <li>• UINT: Status</li> <li>• UINT: Info block size</li> <li>• UINT: Set point data block size</li> </ul>
Input	cbBufLen	UDINT	6 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.27 Curves read info block data in RAM

Read the info data block of the curve defined by its ID the 4 byte result is stored together with the read status in the 6 bytes of the read\_buffer. This command has to be repeated until the whole info data block is read (status = 0).

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	61h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (6bytes)) • UINT: Status • DWORD: data
Input	cbBufLen	UDINT	6 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.28 Curves read set point data in RAM

Read the set point data block of the curve defined by its ID the 4 byte result is stored together with the read status in the 6 bytes of the read\_buffer. This command has to be repeated until the whole set point data block is read (status = 0).

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	62h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (6bytes)) • UINT: Status • DWORD: data
Input	cbBufLen	UDINT	6 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.29 Read error counters

Read the number of logged errors and total occurred errors and stores them in the read buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	70h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) <ul style="list-style-type: none"> <li>• UINT: Number of logged errors</li> <li>• UINT: Number of total errors</li> </ul>
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.30 Read logged error item Code and instance

Read the error code of the specified (ID) logged error item..

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	71h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) <ul style="list-style-type: none"> <li>• UINT: Error code</li> <li>• UINT: Error instance</li> </ul>
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.31 Read logged error item time low

Read the error time millisecond part of the specified (ID) logged error item.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	72h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) • DINT: Error time [ms]
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.32 Read logged error item time high

Read the error time hours part of the specified (ID) logged error item..

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	73h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) • DINT: Error time [h]
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.33 Read error short text

Read the short text of an error defined by its error code, for each stringlet (4 characters) a service number 74h..7Bh is defined.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	74h (LinMot Sdo Service ID) + stringlet Count 0..7)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) • 4 characters of error short text
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.34 Command Table copy entries from RAM to FLASH

This service copies the actual in the RAM defined Command Table entries to the FLASH memory so they are available after power up. Use this command only with stopped MC SW!

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	80h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.35 Command Table delete all entries in RAM

This service deletes all Command table entries in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	81h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.36 Command Table delete entry in RAM

This service delete a single Command Table entry defined by its ID in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	82h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer (0 bytes))
Input	cbBufLen	UDINT	0 bytes (4 bytes also accepted)
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.37 Command Table start write entry in RAM

This service initiate the writing of a new Command Table entry in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	83h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer)
Input	cbBufLen	UDINT	4 bytes: • UDINT: Entry Data Size
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.38 Command Table write entry data in RAM

This service writes the Command Table data block in the RAM.

FUNCTION_BLOCK: FB_EcCoeSdoWriteEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	84h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pSrcBuf	DWORD	ADR(write_buffer)
Input	cbBufLen	UDINT	4 bytes of entry data
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.39 Command Table entry data size in RAM

Read the the entry size of the Command Table entry specified by its ID, and stores the result in the 6 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	85h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (6bytes)) • UINT: Status • UDINT: entry size
Input	cbBufLen	UDINT	6 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

### 5.2.40 Command Table read entry data in RAM

Read the entry size of the Command Table entry specified by its ID, and stores the result in the 6 bytes of the read\_buffer.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	85h (LinMot Sdo Service ID)
Input	nIndex	WORD	2000h + ID
Input	pDstBuf	DWORD	ADR(read_buffer (6bytes)) • UINT: Status • UDINT: entry size
Input	cbBufLen	UDINT	6 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID



### 5.2.41 Command Table read presence list

Read the Command Table entry list defined by its subindex-ID, and stores the result in the 4 bytes of the read\_buffer. A zero of the corresponding bit means command table entry is present, a one means the corresponding entry doesn't exist.

FUNCTION_BLOCK: FB_EcCoeSdoReadEx			
Direction	Name	Type	Description
Input	sNetId	T_AmsNetId	AmsNetId of master
Input	nSlaveAddr	UINT	Address of slave
Input	nSubIndex	Byte	87h + ID (LinMot Sdo Service ID) ID = 0: entries 0..31 ID = 1: entries 32..63 ID = 2: entries 64..95 ID = 3: entries 96..127 ID = 4: entries 128..159 ID = 5: entries 160..191 ID = 6: entries 192..223 ID = 7: entries 224..225
Input	nIndex	WORD	2000h
Input	pDstBuf	DWORD	ADR(read_buffer (4bytes)) - DWORD: presence list, 0 means entry exists
Input	cbBufLen	UDINT	4 bytes
Input	bExecute	BOOL	Rising edge starts writing
Input	tTimeout	TIME	Timeout value
Input	bComplAccess	BOOL	FALSE
Output	bBusy	BOOL	Indicates reading active/finished
Output	bError	BOOL	Indicates reading error
Output	nErrId	UDINT	Error ID

## 6 EtherCAT CiA402 Parameters

### 6.1 Parameters



**Attention:** The EtherCAT CiA402 Interface has an additional parameter tree branch (Parameters → EtherCAT CiA402), which can be configured with the distributed LinMot-Talk software.

With these parameters, the EtherCAT interface can be enabled or disabled. The LinMot-Talk software can be downloaded from <http://www.linmot.com> under the section Download, Software, LinMot Talk.

#### 6.1.1 EtherCAT CiA402/Dis-/Enable

With the Dis-/Enable parameter the LinMot Servo Drive can be run without the Ethernet EtherCAT Interface going online. So in a first step the system can be configured and run without any bus connection.

##### ETHERCAT/Dis-/Enable

Disable	Servo Drive runs without ETHERCAT.
Enable	Servo Drive runs with ETHERCAT connection.



**Attention:** If the ETHERCAT Interface is disabled, the integrated ETHERCAT-ASIC rests in reset state! No messages will be sent to other devices connected to the ETHERCAT-Network via the servo drive.

#### 6.1.2 EtherCAT CiA402/Station Alias/Alias Address Source

With this parameter the station alias address source is defined.



**Attention:** If a station alias address is defined in the ET1100 Eeprom (could be programmed from the master over the Network), this alias address is taken.

##### ETHERCAT/Station Alias/Alias Address Source

None	No station alias address is generated
ID Switches	The ID switches defines the station alias address
ID Switches + Parameter	The station alias address is build out of the ID-Switch value added with the parameter value (typ. Offset)
RT MAC	The lowest 2 bytes of the device MAC address are used as station alias address
Parameter	The Station alias address parameter value defines the Alias Address
<b>Masked RT MAC and Parameter</b>	The station alias address is defined by the masked parameter ored with the RT MAC masked with the inverse mask

#### 6.1.3 EtherCAT CiA402/Station Alias/Alias Address Parameter

This is the parameter value of the station alias address.

### 6.1.4 EtherCAT CiA402/Station Alias/Alias Address Parameter Mask

Mask value for the parameter value of the station alias address.

### 6.1.5 EtherCAT CiA402/NC Configuration/Velocity Scale Numerator /Denominator

This two parameters are taken to Scale the PDO Value of “Target velocity” (Index 0x60FF) to the Drive Resolution which is [1um/s]. The Scaling factor is Velocity Scale Numerator divided by Velocity Scale Denominator.

For the Beckhoff this factor could be set to 1 (as the default value is 1/1), if adapted as described chapter 2.2 in the master.

For Omron PLC’s this factor is typically 0.1 → Velocity Scale Numerator = 1 and Velocity Scale Denominator = 10.

### 6.1.6 EtherCAT CiA402/NC Configuration/Operation Mode 10 Config

ETHERCAT/NC Configuration/Operation Mode 10 Config	
Current Command Mode	In Operation Mode 10 the current command mode is activated, the setpoint is given directly as current [mA].
Force/Torque Control Mode	In Operation Mode 10 the current command mode is activated, the setpoint is given relative, 5000 corresponds to the maximal force/torque.
Closed Loop Force/Torque Control Mode	In Operation Mode 10 the closed loop force/torque control mode is activated, the setpoint is given relative, 5000 corresponds to the maximal force/torque.
Closed Loop Force/Torque Control Mode Abs	In Operation Mode 10 the closed loop force/torque control mode is activated, the setpoint is given absolute with 0.1N resolution as Target Force (UPID 1EA0h) and 1E-6Nm resolution as target torque.

This parameter is used for the when Output PDO modules 0x1604 or 0x1614 are used.

### 6.1.7 EtherCAT CiA402/Connection Timeout/Timeout Behavior

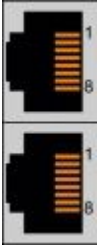
With this parameter the drive behavior on an Connection timeout could be set. This parameter is also represented in the profile parameter with index 0x6007.

ETHERCAT/Conection Timeout/Timeout Behavior	
Ignore	Nothing happens if an IO timeout occurs.
Error with Disable Voltage	Drive goes to Error State and the Voltage is disabled immediately when the IO timeout occurs.
Error with Quick Stop	Drive goes to Error State before the Voltage is disabled a Quick Stop is performed, when the IO timeout occurs.
Error with Go To Pos	Drive goes to Error State before the Voltage is disabled a Go To Position is performed, when the IO timeout occurs.

## 7 Connecting to the EtherCAT Network

### 7.1 Pin Assignment of the Connectors X17-X18

The ETHERCAT connector is a standard RJ45 female connector with a pin assignment as defined by EIA/TIA T568B:

X17 – X18	ETHERCAT Connector		
	Pin	Wire color code	Assignment 100BASE-TX
	1	WHT/ORG	Rx+
	2	ORG	Rx-
	3	WHT/GRN	Tx+
	4	BLU	-
	5	WHT/BLU	-
	6	GRN	Tx-
	7	WHT/BRN	-
	8	BRN	-
	case	-	-
RJ-45	Use standard patch cables (twisted pair, S/UTP, AWG26) for wiring. This type of cable is usually referred to as a “Cat5e-Cable”.		

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