

Documentation | EN

# EP1518-0002

EtherCAT Box with 8 digital inputs and 2 counters





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# 1 Foreword

## 1.1 Notes on the documentation

### Intended audience

This description is only intended for the use of trained specialists in control and automation engineering who are familiar with the applicable national standards.

It is essential that the documentation and the following notes and explanations are followed when installing and commissioning these components.

It is the duty of the technical personnel to use the documentation published at the respective time of each installation and commissioning.

The responsible staff must ensure that the application or use of the products described satisfy all the requirements for safety, including all the relevant laws, regulations, guidelines and standards.

### Disclaimer

The documentation has been prepared with care. The products described are, however, constantly under development.

We reserve the right to revise and change the documentation at any time and without prior announcement.

No claims for the modification of products that have already been supplied may be made on the basis of the data, diagrams and descriptions in this documentation.

### Trademarks

Beckhoff®, TwinCAT®, TwinCAT/BSD®, TC/BSD®, EtherCAT®, EtherCAT G®, EtherCAT G10®, EtherCAT P®, Safety over EtherCAT®, TwinSAFE®, XFC®, XTS® and XPlanar® are registered trademarks of and licensed by Beckhoff Automation GmbH. Other designations used in this publication may be trademarks whose use by third parties for their own purposes could violate the rights of the owners.

### Patent Pending

The EtherCAT Technology is covered, including but not limited to the following patent applications and patents: EP1590927, EP1789857, EP1456722, EP2137893, DE102015105702 with corresponding applications or registrations in various other countries.

The logo for EtherCAT, featuring the word "EtherCAT" in a bold, black, sans-serif font. A red arrow points from the top of the "A" to the top of the "T".

EtherCAT® is registered trademark and patented technology, licensed by Beckhoff Automation GmbH, Germany.

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## 1.2 Safety instructions

### Safety regulations

Please note the following safety instructions and explanations!  
Product-specific safety instructions can be found on following pages or in the areas mounting, wiring, commissioning etc.

### Exclusion of liability

All the components are supplied in particular hardware and software configurations appropriate for the application. Modifications to hardware or software configurations other than those described in the documentation are not permitted, and nullify the liability of Beckhoff Automation GmbH & Co. KG.

### Personnel qualification

This description is only intended for trained specialists in control, automation and drive engineering who are familiar with the applicable national standards.

### Description of instructions

In this documentation the following instructions are used.  
These instructions must be read carefully and followed without fail!

#### **DANGER**

##### **Serious risk of injury!**

Failure to follow this safety instruction directly endangers the life and health of persons.

#### **WARNING**

##### **Risk of injury!**

Failure to follow this safety instruction endangers the life and health of persons.

#### **CAUTION**

##### **Personal injuries!**

Failure to follow this safety instruction can lead to injuries to persons.

#### **NOTE**

##### **Damage to environment/equipment or data loss**

Failure to follow this instruction can lead to environmental damage, equipment damage or data loss.



##### **Tip or pointer**

This symbol indicates information that contributes to better understanding.

## 1.3 Documentation Issue Status

Version	Comment
2.4	<ul style="list-style-type: none"> <li>Chapter "Supply voltages" updated</li> </ul>
2.3	<ul style="list-style-type: none"> <li>Technical data updated</li> <li>UL requirements updated</li> <li>Dimensions updated</li> </ul>
2.2	<ul style="list-style-type: none"> <li>Front page updated</li> <li>Scope of delivery added</li> <li>Structure update</li> </ul>
2.1.0	<ul style="list-style-type: none"> <li>Safety instructions new layout</li> <li>Chapter <i>Mounting</i> updated</li> </ul>
2.0.0	<ul style="list-style-type: none"> <li>Migration</li> <li>Basic function principles chapter corrected</li> </ul>
1.1.0	<ul style="list-style-type: none"> <li>Power Connection updated</li> </ul>
1.0.0	<ul style="list-style-type: none"> <li>First release</li> </ul>

### Firmware and hardware versions

This documentation refers to the firmware and hardware version that was applicable at the time the documentation was written.

The module features are continuously improved and developed further. Modules having earlier production statuses cannot have the same properties as modules with the latest status. However, existing properties are retained and are not changed, so that older modules can always be replaced with new ones.

Documentation Version	Firmware	Hardware
2.4	04	11
2.3	04	09
2.2	04	08
2.1	04	06
2.0.0	04	05
1.0.0	02	00

The firmware and hardware version (delivery state) can be found in the batch number (D-number) printed on the side of the EtherCAT Box.

### Syntax of the batch number (D-number)

WW YY FF HH

WW - week of production (calendar week)

YY - year of production

FF - firmware version

HH - hardware version

Example with D no.: 55 09 01 00:

55 - week of production 55

09 - year of production 2009

01 - firmware version 01

00 - hardware version 001

Further information on this topic: [Version identification of EtherCAT devices \[► 58\]](#).

## 2 EtherCAT Box - Introduction

The EtherCAT system has been extended with EtherCAT Box modules with protection class IP67. Through the integrated EtherCAT interface the modules can be connected directly to an EtherCAT network without an additional Coupler Box. The high-performance of EtherCAT is thus maintained into each module.

The extremely low dimensions of only 126 x 30 x 26.5 mm (h x w x d) are identical to those of the Fieldbus Box extension modules. They are thus particularly suitable for use where space is at a premium. The small mass of the EtherCAT modules facilitates applications with mobile I/O interface (e.g. on a robot arm). The EtherCAT connection is established via screened M8 connectors.

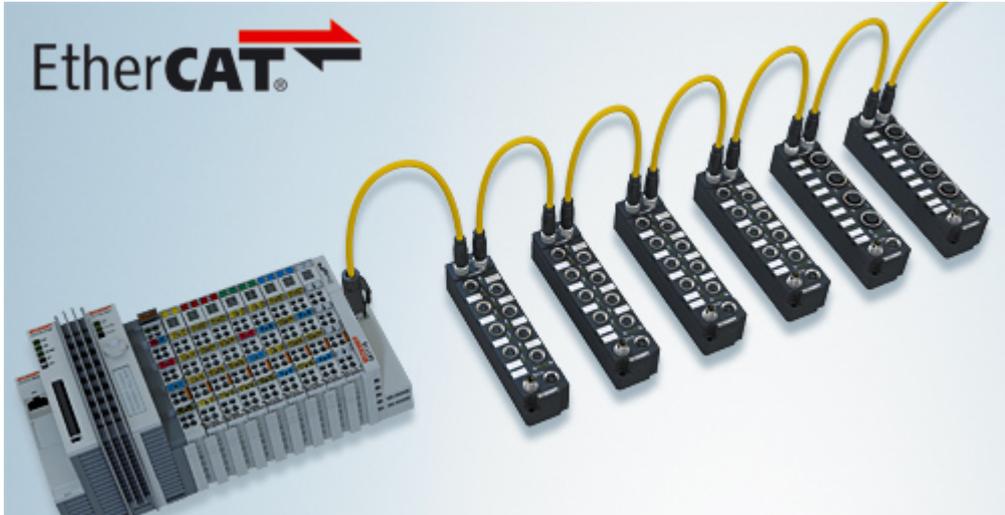


Fig. 1: EtherCAT Box Modules within an EtherCAT network

The robust design of the EtherCAT Box modules enables them to be used directly at the machine. Control cabinets and terminal boxes are now no longer required. The modules are fully sealed and therefore ideally prepared for wet, dirty or dusty conditions.

Pre-assembled cables significantly simplify EtherCAT and signal wiring. Very few wiring errors are made, so that commissioning is optimized. In addition to pre-assembled EtherCAT, power and sensor cables, field-configurable connectors and cables are available for maximum flexibility. Depending on the application, the sensors and actuators are connected through M8 or M12 connectors.

The EtherCAT modules cover the typical range of requirements for I/O signals with protection class IP67:

- digital inputs with different filters (3.0 ms or 10  $\mu$ s)
- digital outputs with 0.5 or 2 A output current
- analog inputs and outputs with 16 bit resolution
- Thermocouple and RTD inputs
- Stepper motor modules

XFC (eXtreme Fast Control Technology) modules, including inputs with time stamp, are also available.



Fig. 2: EtherCAT Box with M8 connections for sensors/actuators



Fig. 3: EtherCAT Box with M12 connections for sensors/actuators

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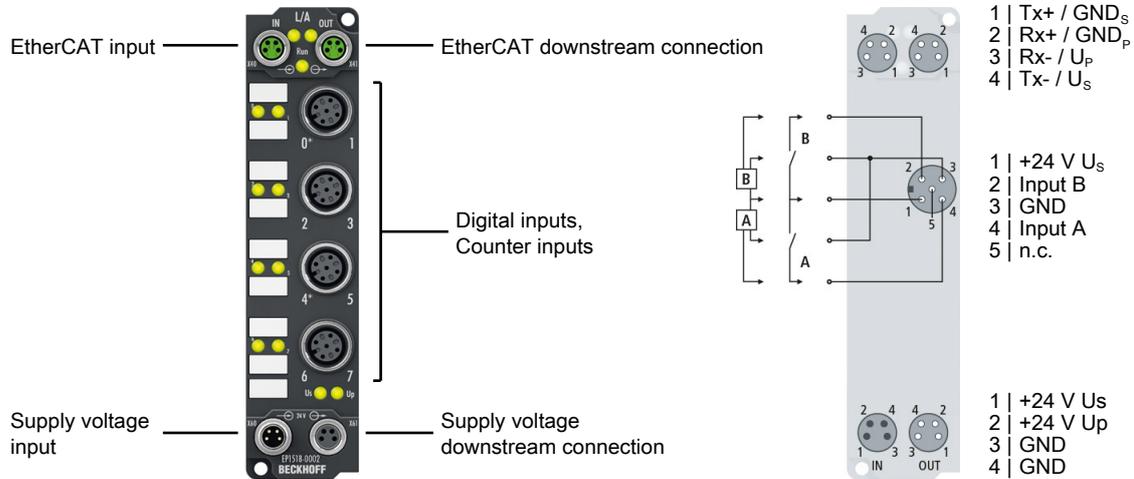
**● Basic EtherCAT documentation**

**i** You will find a detailed description of the EtherCAT system in the Basic System Documentation for EtherCAT, which is available for download from our website ([www.beckhoff.com](http://www.beckhoff.com)) under Downloads.

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## 3 Product overview

### 3.1 Introduction



#### 8 digital inputs (24 V<sub>DC</sub>), 2 counters

The EP1518-0002 EtherCAT Box with digital inputs acquires binary control signals from the process level and transfers them, with electrical isolation, to the controller.

The signal state is indicated by means of light emitting diodes. Connection is via M12 connectors. The input filters can be set between 0 and 100 ms via EtherCAT.

Inputs 0 and 4 can be used as up/down counters (32-bit). Inputs 1 and 5 operate as GATES and inputs 2 and 6 control Up/Down.

The EP1518 has three modes of operation that can be selected via the PDOs using the Sync-Manager:

- 2 digital inputs and 2 counters (delivery state)
- 5 digital inputs and 1 counter
- 8 digital inputs

All inputs continue to be shown in the process image even in the counter operation modes. Signal acquisition takes place with the filter times set via CoE.

Irrespective of that, the counter pulses are always counted with a filter of 150 μs. Further parameters can be set via the CoE objects.

The sensors are supplied via the control voltage U<sub>S</sub> in two groups of four sensors each. Any short circuits on the sensor side are detected and reported to the controller.

The load voltage U<sub>P</sub> is not used in the input module, but may optionally be connected in order to be relayed downstream.

#### Quick links

[Technical data](#) [► 11]

[Process image](#) [► 14]

[Dimensions](#) [► 16]

[Signal connection](#) [► 23]

## 3.2 Technical data

All values are typical values over the entire temperature range, unless stated otherwise.

EtherCAT	
Connection	2 x M8 socket, 4-pin, green
Electrical isolation	500 V
Distributed Clocks	yes

Supply voltages	
Connection	Input: M8 connector, 4-pin Downstream connection: M8 socket, 4-pin, black
U <sub>S</sub> nominal voltage	24 V <sub>DC</sub> (-15 % / +20 %)
U <sub>S</sub> sum current: I <sub>S,sum</sub>	max. 4 A
Current consumption from U <sub>S</sub>	120 mA + sensor supply
Rated voltage U <sub>P</sub>	24 V <sub>DC</sub> (-15 % / +20 %)
U <sub>P</sub> sum current: I <sub>P,sum</sub>	max. 4 A
Current consumption from U <sub>P</sub>	None. U <sub>P</sub> is only forwarded.
Electrical isolation GND <sub>S</sub> / GND <sub>P</sub>	no

Digital inputs	
Number	8
Connection	4 x M12 socket
Characteristics	Type 3 according to EN61131-2, compatible with type 1
Input filter	adjustable: 10 μs ... 100 ms Counter inputs: 150 μs
Signal voltage "0"	-3 ... +5 V
Signal voltage "1"	+11 ... +30 V
Input current	3 mA
Sensor supply	from the control voltage U <sub>S</sub> , short-circuit proof <ul style="list-style-type: none"> <li>• max. 0.5 A for channels 0 ... 3 in total</li> <li>• max. 0.5 A for channels 4 ... 7 in total</li> </ul>

Housing data	
Dimensions W x H x D	30 mm x 126 mm x 26.5 mm (without connectors)
Weight	approx. 165 g
Installation position	variable
Material	PA6 (polyamide)

Environmental conditions	
Ambient temperature during operation	-25 ... +60 °C -25 ... +55 °C according to cURus
Ambient temperature during storage	-40 ... +85 °C
Vibration resistance, shock resistance	conforms to EN 60068-2-6 / EN 60068-2-27 Additional checks <a href="#">▶ 13</a>
EMC immunity / emission	conforms to EN 61000-6-2 / EN 61000-6-4
Protection class	IP65, IP66, IP67 (conforms to EN 60529)

Approvals / markings	
Approvals / markings <sup>*)</sup>	ATEX, CE, cURus <a href="#">▶ 24</a>

\*) Real applicable approvals/markings see type plate on the side (product marking).

**Additional checks**

The boxes have been subjected to the following checks:

Verification	Explanation
Vibration	10 frequency sweeps in 3 axes
	5 Hz < f < 60 Hz displacement 0.35 mm, constant amplitude
	60.1 Hz < f < 500 Hz acceleration 5 g, constant amplitude
Shocks	1000 shocks in each direction, in 3 axes
	35 g, 11 ms

**3.3 Scope of supply**

Make sure that the following components are included in the scope of delivery:

- 1x EtherCAT Box EP1518-0002
- 2x protective cap for EtherCAT socket, M8, green (pre-assembled)
- 1x protective cap for supply voltage input, M8, transparent (pre-assembled)
- 1x protective cap for supply voltage output, M8, black (pre-assembled)
- 10x labels, blank (1 strip of 10)

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**● Pre-assembled protective caps do not ensure IP67 protection**

**i** Protective caps are pre-assembled at the factory to protect connectors during transport. They may not be tight enough to ensure IP67 protection.

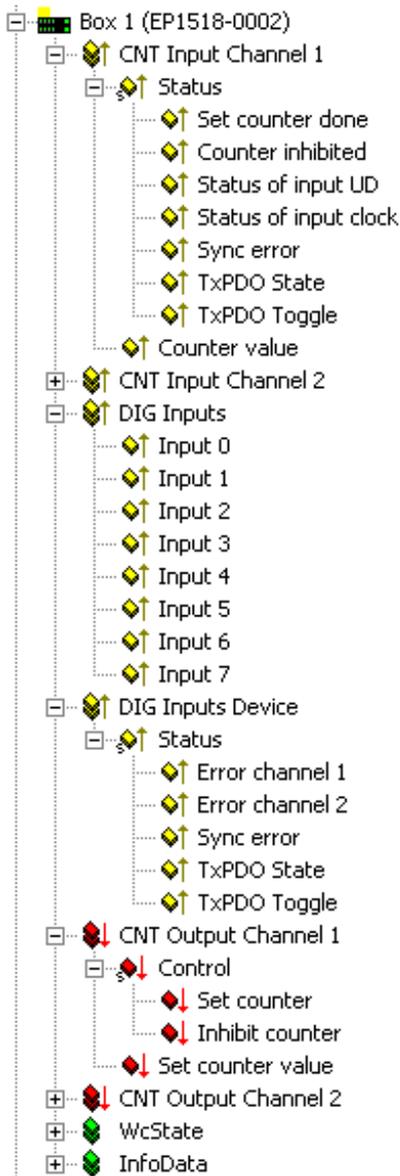
Ensure that the protective caps are correctly seated to ensure IP67 protection.

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### 3.4 Process image

The process image depends on the selected [operation mode](#) [▶ 36].

#### Operation mode: 2 counters and 2 digital inputs (delivery state)



The adoption of the **Set counter** bit from **CNT Output Channel 1** is displayed with **Set counter done**.

The adoption of the **Inhibit counter** bit from **CNT Output Channel 1** is displayed with **Counter inhibited**.

**Status of input UD** shows the status of the Up/Down counter input of the 1st counter.

**Status of input clock** shows the status of the input clock input of the 1st counter.

Sync Error, TxPDO State and TxPDO Toggle are standard EtherCAT process data.

The input data of the 2nd counter can be found under **CNT Input Channel 2**. Their structure corresponds to that of the 1st counter.

**DIG Inputs** shows the states of the individual inputs irrespective of the selected operation mode.

**Error channel 1** displays a short circuit of the supply voltage Us to digital inputs 0 to 3.

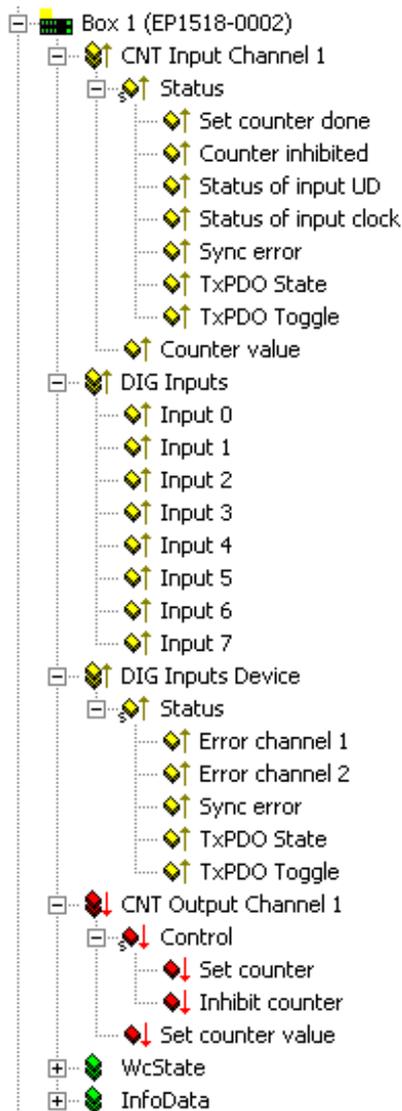
**Error channel 2** displays a short circuit of the supply voltage Us to digital inputs 4 to 7.

The output data of the 1st counter can be found under **CNT Output Channel 1**.

The setting of **Set counter** activates the adoption of the **Set Counter Value** into the **Counter Value** of the 1st counter. The setting of **Inhibit Counter** disables the 1st counter. Alternatively the counter can be disabled or enabled by the physical GATE input. The two values are XORed.

The output data of the 2nd counter can be found under **CNT Output Channel 1**. Their structure corresponds to that of the 1st counter.

**Operation mode: 1 counter and 5 digital inputs**



The input data of the 1st counter can be found under **CNT Input Channel 1**.

The adoption of the **Set counter** bit from **CNT Output Channel 1** is displayed with **Set counter done**.

The adoption of the **Inhibit counter** bit from **CNT Output Channel 1** is displayed with **Counter inhibited**.

**Status of input UD** shows the status of the Up/Down counter input of the 1st counter.

**Status of input clock** shows the status of the input clock input of the 1st counter.

Sync Error, TxPDO State and TxPDO Toggle are standard EtherCAT process data.

**DIG Inputs** shows the states of the individual inputs irrespective of the selected operation mode.

**Error channel 1** displays a short circuit of the supply voltage Us to digital inputs 0 to 3.

**Error channel 2** displays a short circuit of the supply voltage Us to digital inputs 4 to 7.

The output data of the 1st counter can be found under **CNT Output Channel 1**.

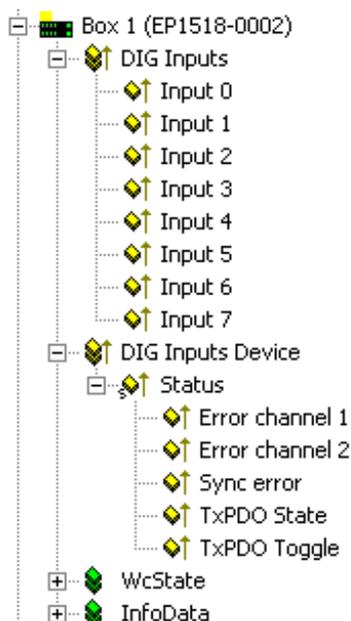
The setting of **Set counter** activates the adoption of the **Set Counter Value** into the **Counter Value** of the 1st counter.

The setting of **Inhibit Counter** disables the 1st counter.

Alternatively the counter can be disabled or enabled by the physical GATE input.

The two values are XORed.

**Operation mode: 8 digital inputs**



**DIG Inputs** shows the states of the individual inputs irrespective of the selected mode.

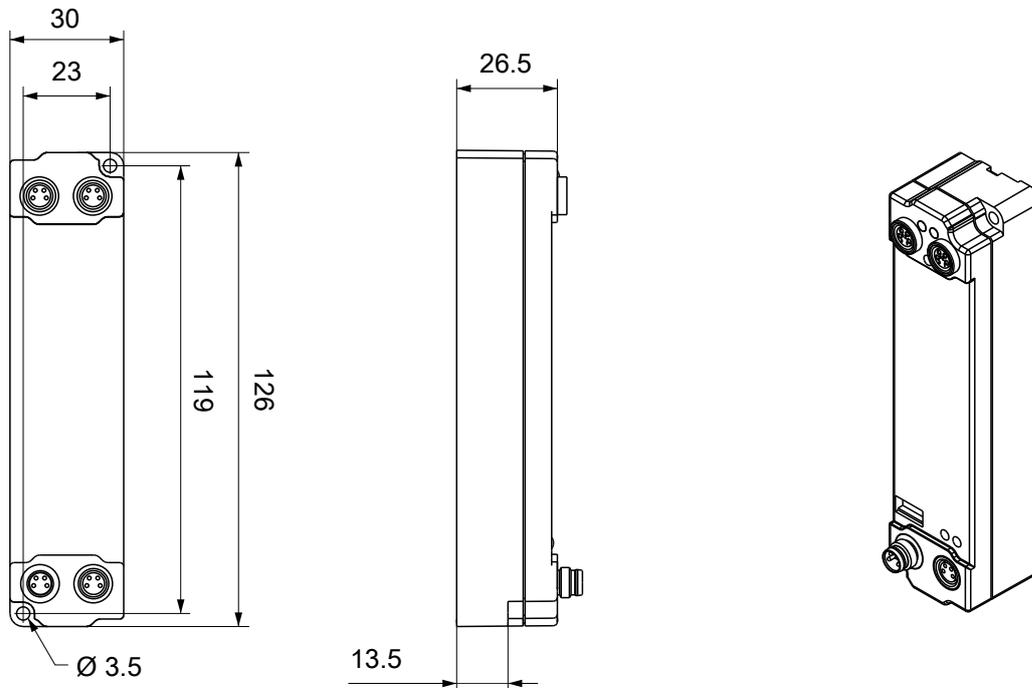
**Error channel 1** displays a short circuit of the supply voltage Us to digital inputs 0 to 3.

**Error channel 2** displays a short circuit of the supply voltage Us to digital inputs 4 to 7.

## 4 Installation

### 4.1 Mounting

#### 4.1.1 Dimensions



All dimensions are given in millimeters.  
The drawing is not true to scale.

#### Housing features

Housing material	PA6 (polyamide)
Sealing compound	polyurethane
Mounting	two mounting holes $\varnothing 3.5$ mm for M3
Metal parts	brass, nickel-plated
Contacts	CuZn, gold-plated
Power feed through	max. 4 A
Installation position	variable
Protection class	IP65, IP66, IP67 (conforms to EN 60529) when screwed together
Dimensions (H x W x D)	approx. 126 x 30 x 26.5 mm (without connectors)

## 4.1.2 Fixing

### NOTE

#### Dirt during assembly

Dirty connectors can lead to malfunctions. Protection class IP67 can only be guaranteed if all cables and connectors are connected.

- Protect the plug connectors against dirt during the assembly.

Mount the module with two M3 screws on the mounting holes in the corners of the module. The mounting holes have no thread.

## 4.1.3 Tightening torques for plug connectors

Screw connectors tight with a torque wrench. (e.g. ZB8801 from Beckhoff)

Connector diameter	Tightening torque
M8	0.4 Nm
M12	0.6 Nm

## 4.2 Connection

### 4.2.1 EtherCAT

#### 4.2.1.1 Connectors

**NOTE**

**Risk of confusion: supply voltages and EtherCAT**

Defect possible through incorrect insertion.

- Observe the color coding of the connectors:  
 black: Supply voltages  
 green: EtherCAT

EtherCAT Box Modules have two green M8 sockets for the incoming and downstream EtherCAT connections.



#### Connection

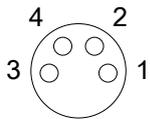


Fig. 4: M8 socket

EtherCAT	M8 connector	Core colors		
Signal	Contact	ZB9010, ZB9020, ZB9030, ZB9032, ZK1090-6292, ZK1090-3xxx-xxxx	ZB9031 and old versions of ZB9030, ZB9032, ZK1090-3xxx-xxxx	TIA-568B
Tx +	1	yellow <sup>1)</sup>	orange/white	white/orange
Tx -	4	orange <sup>1)</sup>	orange	orange
Rx +	2	white <sup>1)</sup>	blue/white	white/green
Rx -	3	blue <sup>1)</sup>	blue	green
Shield	Housing	Shield	Shield	Shield

<sup>1)</sup> Core colors according to EN 61918

**i Adaptation of core colors for cables ZB9030, ZB9032 and ZK1090-3xxxx-xxxx**

For standardization, the core colors of the ZB9030, ZB9032 and ZK1090-3xxx-xxxx cables have been changed to the EN61918 core colors: yellow, orange, white, blue. So there are different color codes in circulation. The electrical properties of the cables have been retained when the core colors were changed.

**4.2.1.2 Status LEDs**



**L/A (Link/Act)**

A green LED labelled "L/A" is located next to each EtherCAT socket. The LED indicates the communication state of the respective socket:

LED	Meaning
off	no connection to the connected EtherCAT device
lit	LINK: connection to the connected EtherCAT device
flashes	ACT: communication with the connected EtherCAT device

**Run**

Each EtherCAT slave has a green LED labelled "Run". The LED signals the status of the slave in the EtherCAT network:

LED	Meaning
off	Slave is in "Init" state
flashes uniformly	Slave is in "Pre-Operational" state
flashes sporadically	Slave is in "Safe-Operational" state
lit	Slave is in "Operational" state

Description of the EtherCAT slave states

**4.2.1.3 Cables**

For connecting EtherCAT devices only shielded Ethernet cables that meet the requirements of at least category 5 (CAT5) according to EN 50173 or ISO/IEC 11801 should be used.

EtherCAT uses four wires for signal transmission. Thanks to automatic line detection ("Auto MDI-X"), both symmetrical (1:1) or cross-over cables can be used between Beckhoff EtherCAT.

Detailed recommendations for the cabling of EtherCAT devices

## 4.2.2 Supply voltages

### ⚠ WARNING

#### Power supply from SELV/PELV power supply unit!

SELV/PELV circuits (Safety Extra Low Voltage, Protective Extra Low Voltage) according to IEC 61010-2-201 must be used to supply this device.

Notes:

- SELV/PELV circuits may give rise to further requirements from standards such as IEC 60204-1 et al, for example with regard to cable spacing and insulation.
- A SELV (Safety Extra Low Voltage) supply provides safe electrical isolation and limitation of the voltage without a connection to the protective conductor, a PELV (Protective Extra Low Voltage) supply also requires a safe connection to the protective conductor.

### ⚠ CAUTION

#### Observe the UL requirements

- When operating under UL conditions, observe the warnings in the chapter [UL Requirements \[▶ 24\]](#).

The EtherCAT Box has one input for two supply voltages:

- **Control voltage  $U_s$**   
The following sub-functions are supplied from the control voltage  $U_s$ :
  - the fieldbus
  - the processor logic
  - typically the inputs and the sensors if the EtherCAT Box has inputs.
- **Peripheral voltage  $U_p$**   
For EtherCAT Box modules with digital outputs the digital outputs are typically supplied from the peripheral voltage  $U_p$ .  $U_p$  can be supplied separately. If  $U_p$  is switched off, the fieldbus function, the function of the inputs and the supply of the sensors are maintained.

The exact assignment of  $U_s$  and  $U_p$  can be found in the pin assignment of the I/O connections.

#### Redirection of the supply voltages

The power IN and OUT connections are bridged in the module. Hence, the supply voltages  $U_s$  and  $U_p$  can be passed from EtherCAT Box to EtherCAT Box in a simple manner.

### NOTE

#### Note the maximum current!

Ensure that the permitted current for the connectors is not exceeded when routing the supply voltages  $U_s$  and  $U_p$ :

M8 connector: max. 4 A  
7/8" connector: max 16 A

### NOTE

#### Unintentional cancellation of the electrical isolation of $GND_s$ and $GND_p$ possible.

In some types of EtherCAT Box modules the ground potentials  $GND_s$  and  $GND_p$  are connected.

- If several EtherCAT Box modules are supplied with the same electrically isolated voltages, check whether there is an EtherCAT Box among them in which the ground potentials are connected.

4.2.2.1 Connectors

**NOTE**

**Risk of confusion: supply voltages and EtherCAT**

Defect possible through incorrect insertion.

- Observe the color coding of the connectors:  
 black: Supply voltages  
 green: EtherCAT

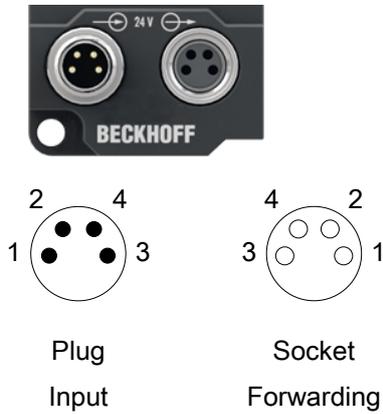


Fig. 5: M8 connector

Contact	Function	Description	Core color <sup>1)</sup>
1	U <sub>S</sub>	Control voltage	Brown
2	U <sub>P</sub>	Peripheral voltage	White
3	GND	GND	Blue
4	GND	GND	Black

<sup>1)</sup> The core colors apply to cables of the type: Beckhoff ZK2020-3xxx-xxxx

4.2.2.2 Status LEDs

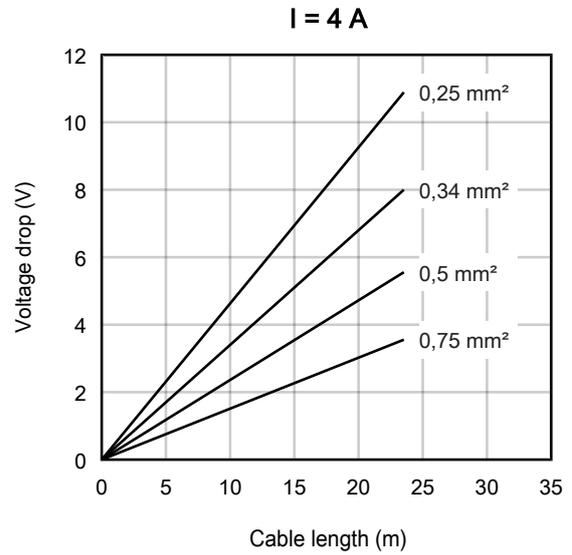
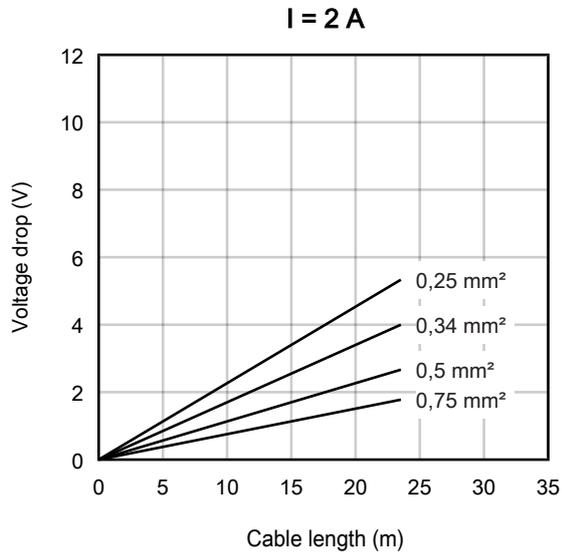


LED	Display	Meaning
U <sub>S</sub> (control voltage)	off	The supply voltage U <sub>S</sub> is not available.
	green illuminated	The supply voltage U <sub>S</sub> is available.
U <sub>P</sub> (peripheral voltage)	off	The supply voltage U <sub>P</sub> is not available.
	green illuminated	The supply voltage U <sub>P</sub> is available.

### 4.2.2.3 Conductor losses

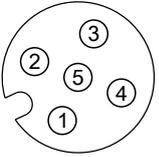
Take into account the voltage drop on the supply line when planning a system. Avoid the voltage drop being so high that the supply voltage at the box lies below the minimum nominal voltage. Variations in the voltage of the power supply unit must also be taken into account.

#### Voltage drop on the supply line



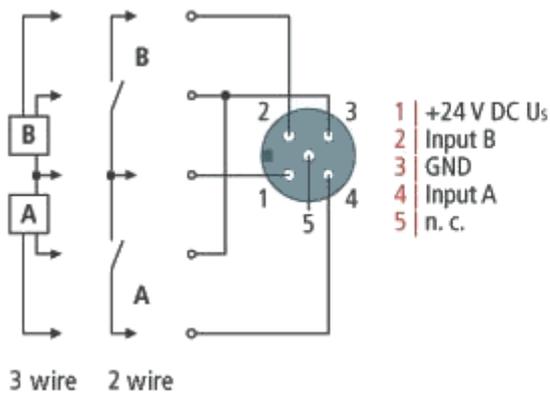
### 4.2.3 Signal connection

#### Pin assignment

M12 socket	Pin	Symbol	Function
	1	+24 V Us	Sensor supply
	2	Input B	Digital input
	3	GND	Ground
	4	Input A	Digital input
	5	n.c.	-

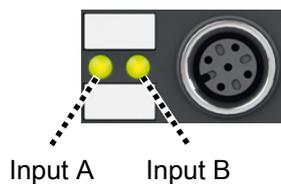
Use the sensor supply at pin 1 as supply voltage for connected sensors. [Specifications \[►\\_11\]](#).

#### Connection examples



#### Status LEDs

Each M12 socket has two green LEDs. An LED lights up when a high level is detected at the respective input.



## 4.3 UL Requirements

The installation of the EtherCAT Box Modules certified by UL has to meet the following requirements.

### Supply voltage

#### ⚠ CAUTION

##### CAUTION!

This UL requirements are valid for all supply voltages of all marked EtherCAT Box Modules!  
For the compliance of the UL requirements the EtherCAT Box Modules should only be supplied

- by a 24 V<sub>DC</sub> supply voltage, supplied by an isolating source and protected by means of a fuse (in accordance with UL248), rated maximum 4 Amp, or
- by a 24 V<sub>DC</sub> power source, that has to satisfy *NEC class 2*.  
A *NEC class 2* power supply shall not be connected in series or parallel with another (class 2) power source!

#### ⚠ CAUTION

##### CAUTION!

To meet the UL requirements, the EtherCAT Box Modules must not be connected to unlimited power sources!

### Networks

#### ⚠ CAUTION

##### CAUTION!

To meet the UL requirements, EtherCAT Box Modules must not be connected to telecommunication networks!

### Ambient temperature range

#### ⚠ CAUTION

##### CAUTION!

To meet the UL requirements, EtherCAT Box Modules has to be operated only at an ambient temperature range of -25 °C to +55 °C!

### Marking for UL

All EtherCAT Box Modules certified by UL (Underwriters Laboratories) are marked with the following label.



Fig. 6: UL label

## 4.4 ATEX notes

### 4.4.1 ATEX - Special conditions

#### ⚠ WARNING

**Observe the special conditions for the intended use of EtherCAT Box modules in potentially explosive areas – directive 94/9/EU.**

- The certified components are to be installed with a BG2000-0000 or BG2000-0010 protection enclosure [► 26] that guarantees a protection against mechanical hazards!
- If the temperatures during rated operation are higher than 70°C at the feed-in points of cables, lines or pipes, or higher than 80°C at the wire branching points, then cables must be selected whose temperature data correspond to the actual measured temperature values!
- Observe the permissible ambient temperature range of 0 to 55°C for the use of EtherCAT Box modules in potentially explosive areas!
- Measures must be taken to protect against the rated operating voltage being exceeded by more than 40% due to short-term interference voltages!
- The connections of the certified components may only be connected or disconnected if the supply voltage has been switched off or if a non-explosive atmosphere is ensured!

#### Standards

The fundamental health and safety requirements are fulfilled by compliance with the following standards:

- EN 60079-0: 2006
- EN 60079-15: 2005

#### Marking

The EtherCAT Box modules certified for potentially explosive areas bear the following marking:



II 3 G Ex nA II T4 DEKRA 11ATEX0080 X Ta: 0 - 55°C

or



II 3 G Ex nA nC IIC T4 DEKRA 11ATEX0080 X Ta: 0 - 55°C

#### Batch number (D number)

The EtherCAT Box modules bear a batch number (D number) that is structured as follows:

D: WW YY FF HH

WW - week of production (calendar week)

YY - year of production

FF - firmware version

HH - hardware version

Example with batch number 29 10 02 01:

29 - week of production 29

10 - year of production 2010

02 - firmware version 02

01 - hardware version 01

## 4.4.2 BG2000 - EtherCAT Box protection enclosures

### ⚠ WARNING

#### Risk of electric shock and damage of device!

Bring the EtherCAT system into a safe, powered down state before starting installation, disassembly or wiring of the modules!

### ATEX

### ⚠ WARNING

#### Mount a protection enclosure!

To fulfill the special conditions according to ATEX [▶ 25], a BG2000-0000 or BG2000-0010 protection enclosure has to be mounted over the EtherCAT Box.

### Installation

Put the cables for EtherCAT, power supply and sensors/actuators through the hole of the protection enclosure.

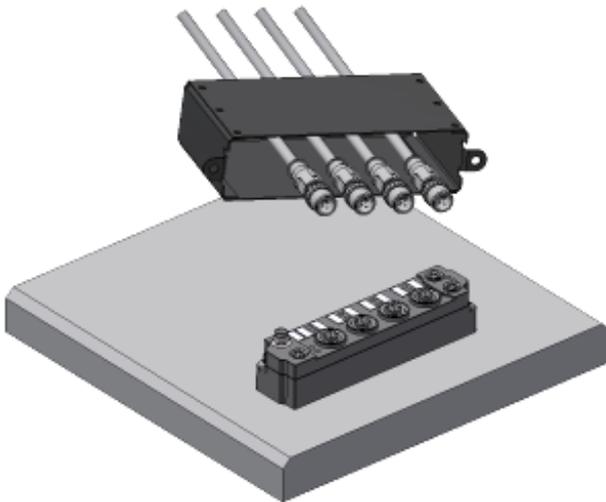


Fig. 7: BG2000 - putting the cables

Fix the wires for EtherCAT, power supply and sensors/actuators to the EtherCAT Box.

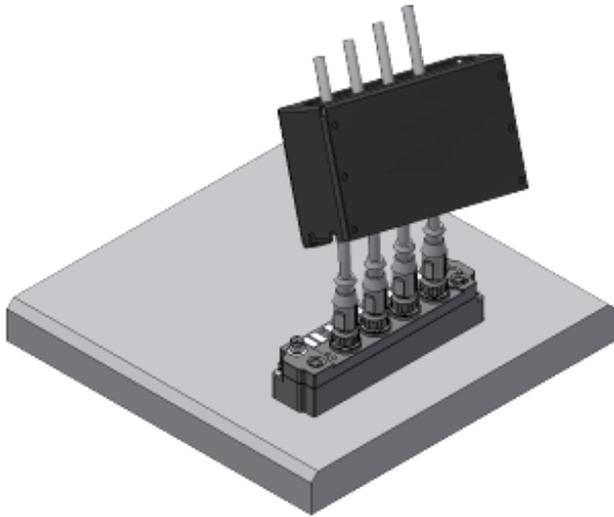


Fig. 8: BG2000 - fixing the cables

Mount the protection enclosure over the EtherCAT Box.

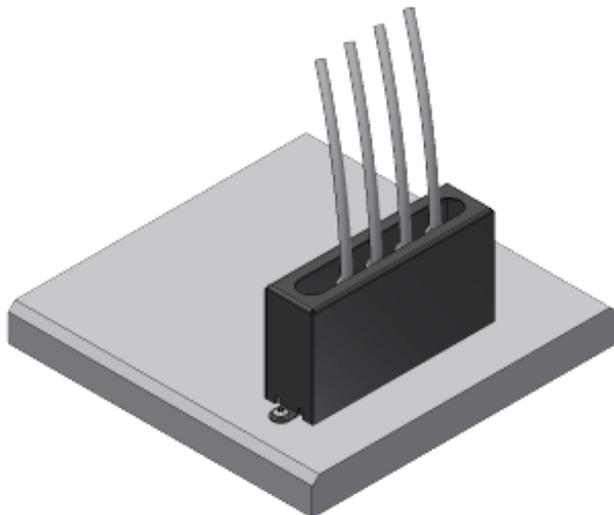


Fig. 9: BG2000 - mounting the protection enclosure

### 4.4.3 ATEX Documentation



#### Notes about operation of EtherCAT Box Modules (EPxxxx-xxxx) in potentially explosive areas (ATEX)

Pay also attention to the continuative documentation Notes about operation of EtherCAT Box Modules (EPxxxx-xxxx) in potentially explosive areas (ATEX) that is available in the download area of the Beckhoff homepage <http://www.beckhoff.com>!

## 4.5 Disposal



Products marked with a crossed-out wheeled bin shall not be discarded with the normal waste stream. The device is considered as waste electrical and electronic equipment. The national regulations for the disposal of waste electrical and electronic equipment must be observed.

## **5 Commissioning and configuration**

### **5.1 Integrating into a TwinCAT project**

The procedure for integration in a TwinCAT project is described in these [Quick start guide](#).

## 5.2 Distributed Clocks (DC)

### ● EtherCAT System Documentation



A basic introduction to the topic of EtherCAT and Distributed Clocks is available in the [Download](#) area on the Beckhoff homepage: [EtherCAT System Documentation](#).

The Box supports the distributed clocks functionality. In order for the Box to provide the current counter reading before the arrival of the querying EtherCAT datagram in the specified process data, a corresponding signal must be generated cyclically in the Box. This signal can be triggered in the Box by two events: the SyncManager (SM) and the distributed clock (DC). Under operation mode selection the following options are available (see Fig. "DC" (*Disributed Clocks*) tab)

- **SM-synchron**

The SyncManager event occurs when an EtherCAT frame successfully exchanges process data with the Box. Frame-triggered, the current counter value is thus cyclically determined, but with the low temporal jitter of the Ethernet frame.

- **DC-synchron**

In DC operation mode determination of the counter value is triggered cyclically at constant intervals through the integrated DC unit, synchronous with the bus cycle as standard. More uniform polling offers higher-quality position data for a higher-level control algorithm, for example.

The trigger for the counter reading is the SYNC0 signal.

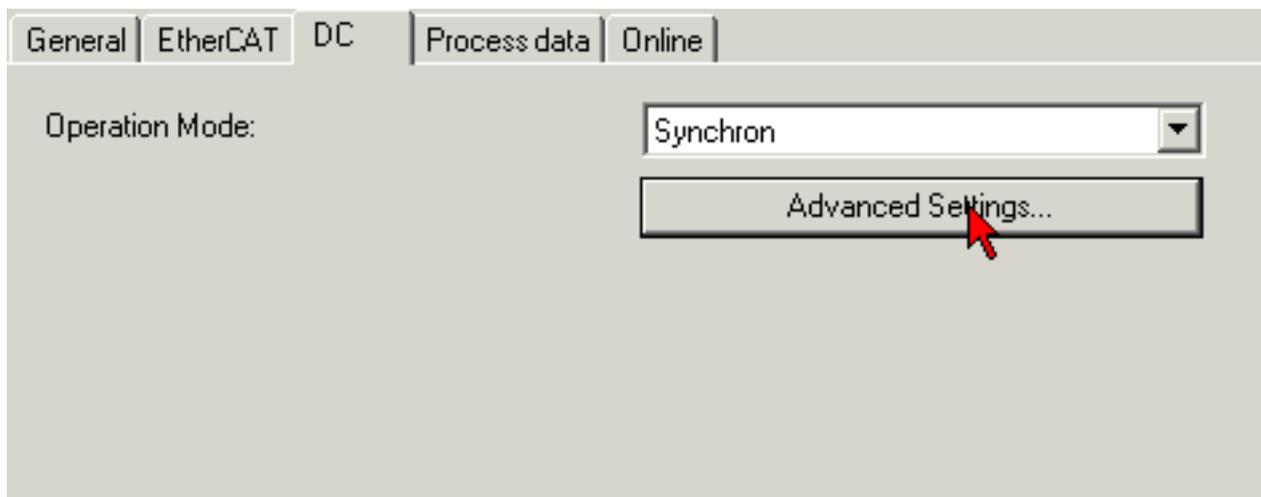


Fig. 10: DC tab (Distributed Clocks)

When *DC-Synchron* operation mode is activated TwinCAT selects settings that ensure reliable operation of the Box with current position data. This means that determination of the current counter value is triggered by the SYNC0 signal at highly constant intervals and in good time (i.e. with an adequate safety buffer) before retrieving EtherCAT datagram is started.

If necessary, the SYNC0 signal can be shifted along the time axis to the right/later or left/earlier in associated dialogs by specifying a user-defined shift time, see Fig. *Advanced Distributed Clock (DC) settings*.

- A right-shift (positive shift value) will delay the counter value query, which means the position value becomes more current from the PLC perspective. However, this increases the risk that the position determination may not be finished in time before the arrival of EtherCAT frame, so that no current position value is available in this cycle.
- A left-shift (negative shift value) means the counter value will be queried earlier, resulting in older position values, with an associated increase in the safety buffer before the arrival of the EtherCAT datagram. This setting may be useful in systems with high real-time jitter, if no Industrial PCs from Beckhoff are used for control purposes, for example.

**NOTE**

**Risk of device damage**

The mentioned notes and information should be used advisedly.  
 The EtherCAT master automatically allocates SYNC0 and SYNC1 settings that support reliable and timely process data acquisition.  
 User intervention at this point may lead to undesired behavior.  
 If these settings are changed in the System Manager, no plausibility checks are carried out on the software side. Correct function cannot be guaranteed for all conceivable setting options.

**Default setting**

The cyclic reading of the inputs is triggered by the SYNC0 pulse (interrupt) of the DC in the EtherCAT Box. The EtherCAT master sets the *Sync Unit Cycle* time value to the PLC cycle time and therefore the EtherCAT cycle time as standard. See Fig. *Advanced Distributed Clock (DC) settings: 4000 μs = 4 ms*, as TwinCAT is in configuration mode.

**DC settings**

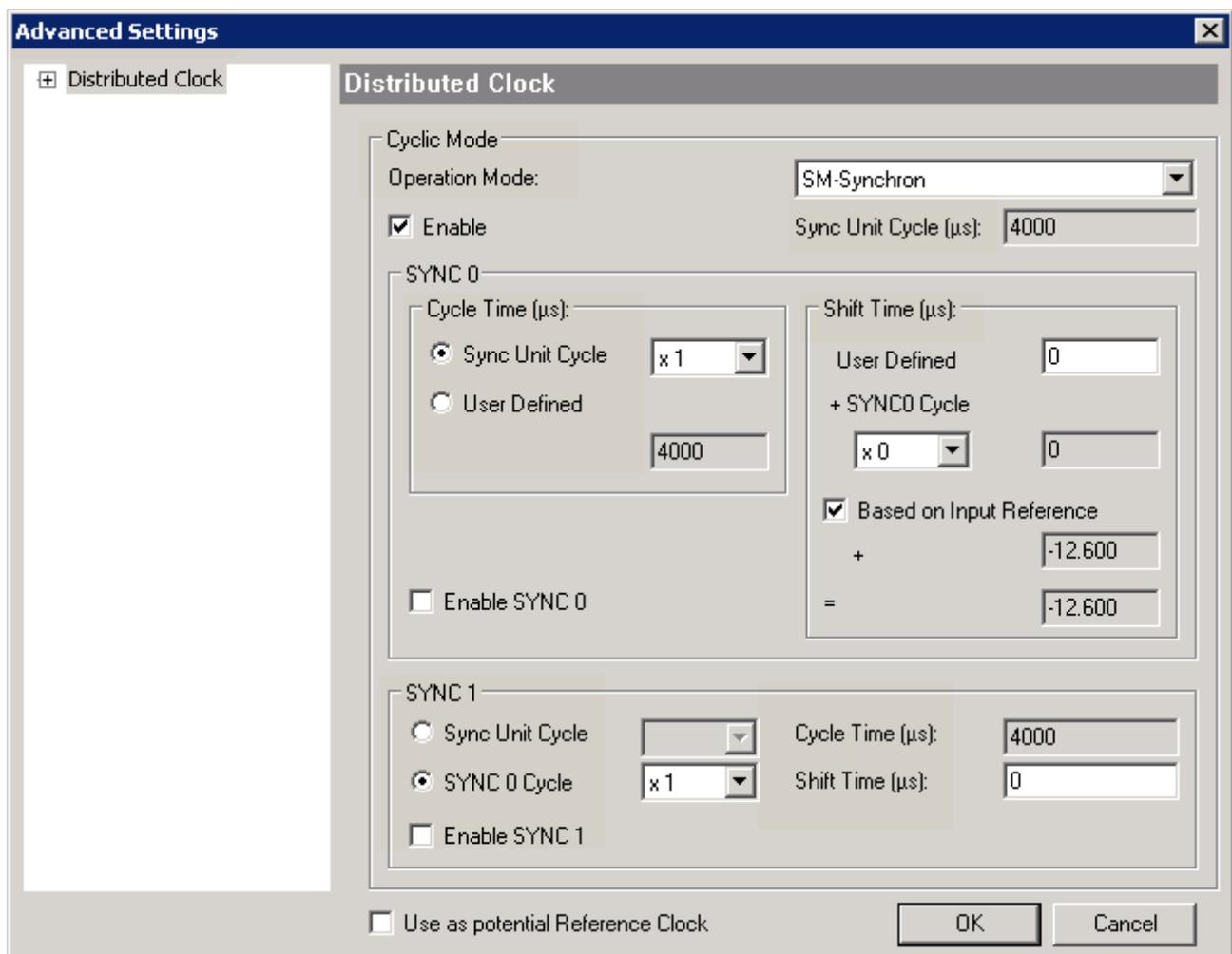


Fig. 11: Advanced settings for Distributed Clocks (DC)

**SYNC0**

Sync Unit cycle: a multiple of the bus cycle time. The counter value is periodically determined at this interval (in μs).

**User defined**

Any number up to 2<sup>32</sup> ns, or about 4.3 seconds. Use of decimal points is allowed.

## Shift Time

The Shift Time can be used to shift the SYNC0 pulse for this EtherCAT Box relative to other EtherCAT devices and the global SYNC pulse in nanosecond steps. If the inputs of several Boxes are read simultaneously, the same value must be entered here.

## Based on input reference

If this option is activated an additional Input Shift is added to the configurable terminal-specific SYNC0 shift (user defined). This value is calculated and made available by the EtherCAT master (SysMan/Device EtherCAT/Tab EtherCAT/Advanced Settings/Distributed Clocks/Input Shift Time). As a result, *all* input terminals in the system (EL1xxx, EL3xxx, EP1xxx, EP3xxx, EPP1xxx, EPP3xxx) read in their inputs as shortly as possible before the EtherCAT frame is fetched, so that controller can be supplied with input data that is as current as possible.

## Enable SYNC0

Automatically activated in *DC-synchron* operation mode.

## SYNC1

Additional SYNC pulse, derived from SYNC0 or from the DC itself.

## DC settings for EtherCAT master

Higher-level distributed clock parameters can be modified under advanced settings for the EtherCAT master. Refer also to the basic introduction to the topic of EtherCAT and Distributed Clocks; download: the [Distributed Clocks system description](#).

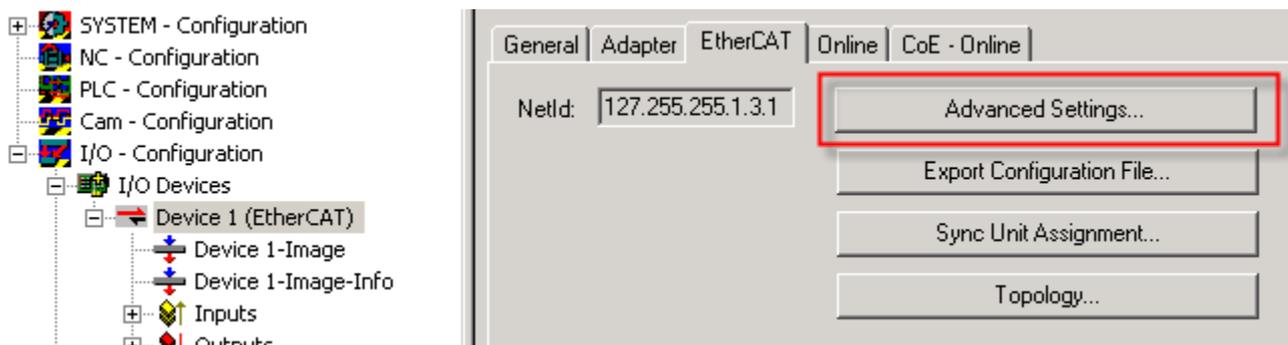


Fig. 12: EtherCAT Master, EtherCAT tab, Advanced Settings

## 5.3 Distributed Clocks and EP1518

### ● Digital inputs and Distributed Clocks

**i** If the Distributed Clock of the EP1518 is activated, the digital inputs are read in without the set filter promptly before the arrival of the querying EtherCAT datagram.

## 5.4 Configuration

### 5.4.1 Basic Function Principles

The EP1518-0002 has 8 digital inputs. Of these, inputs 0, 1 and 2 as well as 4, 5 and 6 can each be used for one counter. The states of the individual inputs are always illustrated in the process image, irrespective of their use.

Input	M12	Properties
0	Socket 1, Pin 4	Digital input or counter input 1
1	Socket 1, Pin 2	Digital input or Gate 1
2	Socket 2, Pin 4	Digital input or Up/Down 1
3	Socket 2, Pin 2	Digital input
4	Socket 3, Pin 4	Digital input or counter input 2
5	Socket 3, Pin 2	Digital input or Gate 2
6	Socket 4, Pin 4	Digital input or Up/Down 2
7	Socket 4, Pin 2	Digital input

#### Operation modes

Three operation modes [► 36] are available. The setting takes place by selecting the PDOs in the Sync-Manager:

Operation mode	Number of counter channels	Number of "free" digital inputs	Properties
2 up/down counters (32-bit)	2	2	Single pulses are counted at the counter inputs.
2 up/down counters (32-bit)	1	5	The gate input or the software gate enables the counter. The count direction is specified via CoE.
8 digital inputs, no counter	-	8	digital inputs: Filter for inputs 0 and 4 permanently set to 150 µs. The filter setting for the other inputs is configurable by software.

The GATE and Up/Down inputs can be converted to standard inputs.

#### Counting mode

The following settings for GATE and Up/Down can be combined and apply independently to each counter.

#### Counting mode with standard setting (up counter)

In the delivery state the Counter Value is incremented on each rising edge. The count direction is up.

The counter is disabled by applying a high level to the GATE input or by setting the *Inhibit Counters* bit.

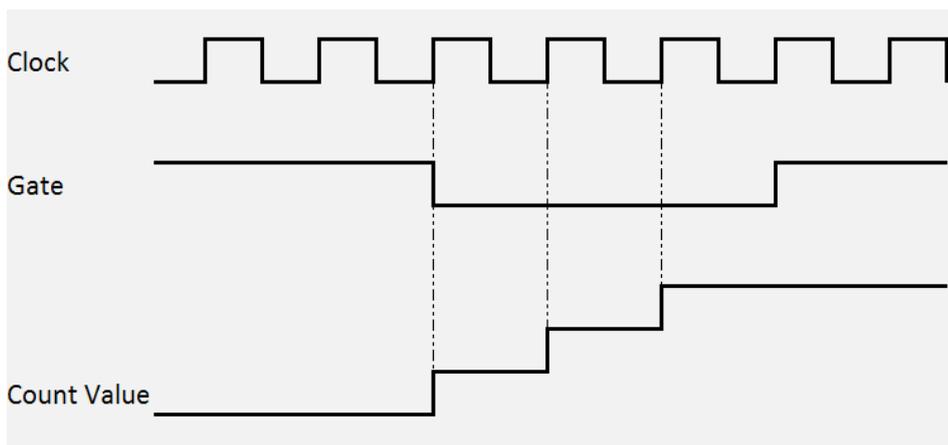


Fig. 13: Counting mode with standard setting

**Counting mode with reversed count direction (down counter)**

The count direction is changed by applying a high level to the Up/Down input or by setting the CoE object 0x80x0:04 *Count down*. The count direction is down.

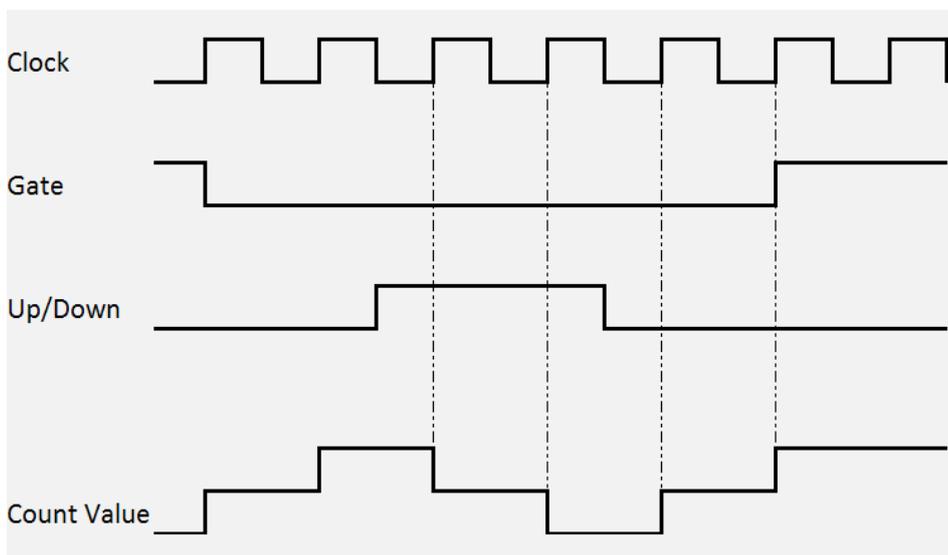


Fig. 14: Counting mode with reversed counting direction

**Counting mode with inverted (negated) GATE input**

In the default setting the counter is disabled by applying a high level to the GATE input or by setting the *Inhibit Counters* bit

Setting the CoE object 0x80x0:05 *Enable input gate* activates the counter if GATE is set and deactivates it if GATE is not set.

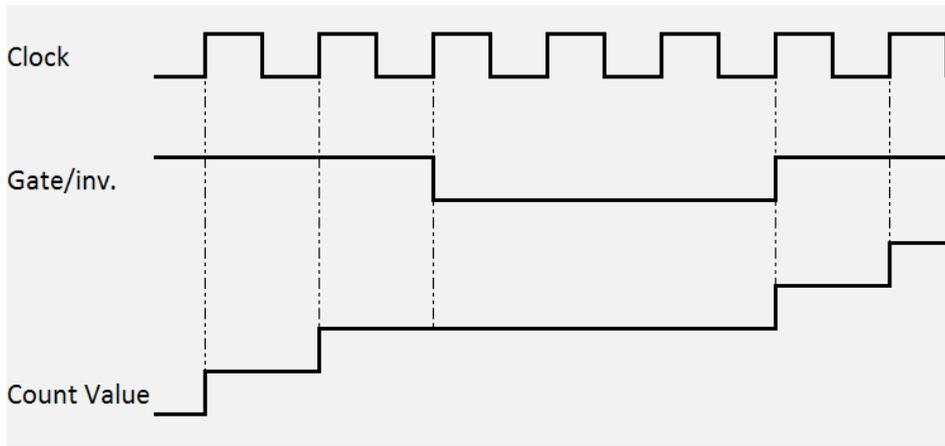


Fig. 15: Counting mode with inverted GATE input

Index	Name	Flags	Value
8000:0	CNT Settings	RW	> 19 <
8000:03	Enable reload	RW	TRUE
8000:04	Count down	RW	FALSE
8000:05	Operating mode	RW	Enable pos. gate (Gate sperrt mit ...)
8000:07	Enable input gate	RW	FALSE
8000:08	Enable input UD		
8000:13	Counter reload value		
8010:0	CNT Settings		
8022:0	DIG Filter Settings		

**Set Value Dialog**

Dec:

Hex:

Enum: 

- Enable pos. gate (Gate sperrt mit positivem
- Enable neg. gate (Gate sperrt mit negativem

Boot:

Binary:

Bit Size:  1  8  16  32  64  ?

Fig. 16: CoE for inverting the GATE input

## 5.4.2 Operation modes

### Operation mode selection

There are three operation modes to choose from:

- [Two up/down counters \[▶ 37\]](#)(delivery state)
- [One up/down counter \[▶ 38\]](#)
- [8 digital inputs \[▶ 39\]](#)

The setting takes place by selecting the PDOs in the Sync-Manager:

Operation mode	Number of 32-bit counters	Number of "free" digital inputs	Properties
2 up/down counters	2	2	Single pulses at the counter inputs are counted; the Gate input or the software gate enables the counter; count direction via CoE
1 up/down counters	1	5	
8 digital inputs, no counter	-	8	digital inputs: Filter for inputs 0 and 4 permanently set to 150 µs. The filter setting for the other inputs is configurable by software.

Operation mode settings of the PDOs	0x1600	0x1601	0x1A00	0x1A01	0x1A02	0x1A03	Comments
2 up/down counters (32-bit)	1	1	1	1	0/1	0/1	2 counters, digital inputs, diagnosis of Us
1 up/down counters (32-bit)	1	0	1	0	0/1	0/1	
8 digital inputs, no counter	0	0	0	0	0/1	0/1	digital inputs: Filter for inputs 0 and 4 permanently set to 150 µs. The filter setting for the other inputs is configurable by software.

The module parameters are set in the CoE objects 0x8000:0 for counter 1, 0x8010:0 for counter 2 and 0x8022:0 for the digital inputs. (integrate links)

#### **i** The second counter is always active internally

Internally the second counter is always active, so that when switching from one 32-bit counter to two 32-bit counters the previous incoming pulses were counted in the second counter and saved in the Counter Value.

## Two up/down counters

This is the operation mode in the factory setting.

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

Sync Manager:

SM	Size	Type	Flags
0	256	MbxOut	
1	256	MbxIn	
2	12	Outputs	
3	16	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	CNT Input Channel 1	F	3	0
0x1A01	6.0	CNT Input Channel 2	F	3	0
0x1A02	2.0	DIG Inputs	F	3	0
0x1A03	2.0	DIG Inputs Device	F	3	0
0x1600	6.0	CNT Output Channel 1	F	2	0
0x1601	6.0	CNT Output Channel 2	F	2	0

PDO Assignment (0x1C12):

- 0x1600
- 0x1601

PDO Content (0x1A00):

Index	Size	Offs	Name	Type	Default (hex)
---	0.2	0.0	---		
0x6000:03	0.1	0.2	Status__Set counter done	BOOL	
0x6000:04	0.1	0.3	Status__Counter inhibited	BOOL	
0x6000:05	0.1	0.4	Status__Status of input UD	BOOL	
0x6000:06	0.1	0.5	Status__Status of input clock	BOOL	
---	0.7	0.6	---		
0x6000:0E	0.1	1.5	Status__Sync error	BOOL	
0x6000:0F	0.1	1.6	Status__TxPDO State	BOOL	
0x6000:10	0.1	1.7	Status__TxPDO Toggle	BOOL	
0x6000:11	4.0	2.0	Counter value	UDINT	
		6.0			

Download

- PDO Assignment
- PDO Configuration

Predefined PDO Assignment: (none)

Load PDO info from device

Sync Unit Assignment...

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

Sync Manager:

SM	Size	Type	Flags
0	256	MbxOut	
1	256	MbxIn	
2	12	Outputs	
3	16	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	CNT Input Channel 1	F	3	0
0x1A01	6.0	CNT Input Channel 2	F	3	0
0x1A02	2.0	DIG Inputs	F	3	0
0x1A03	2.0	DIG Inputs Device	F	3	0
0x1600	6.0	CNT Output Channel 1	F	2	0
0x1601	6.0	CNT Output Channel 2	F	2	0

PDO Assignment (0x1C12):

- 0x1A00
- 0x1A01
- 0x1A02
- 0x1A03

PDO Content (0x1A00):

Index	Size	Offs	Name	Type	Default (hex)
---	0.2	0.0	---		
0x6000:03	0.1	0.2	Status__Set counter done	BOOL	
0x6000:04	0.1	0.3	Status__Counter inhibited	BOOL	
0x6000:05	0.1	0.4	Status__Status of input UD	BOOL	
0x6000:06	0.1	0.5	Status__Status of input clock	BOOL	
---	0.7	0.6	---		
0x6000:0E	0.1	1.5	Status__Sync error	BOOL	
0x6000:0F	0.1	1.6	Status__TxPDO State	BOOL	
0x6000:10	0.1	1.7	Status__TxPDO Toggle	BOOL	
0x6000:11	4.0	2.0	Counter value	UDINT	
		6.0			

Download

- PDO Assignment
- PDO Configuration

Predefined PDO Assignment: (none)

Load PDO info from device

Sync Unit Assignment...

The PDOs 0x1600 [▶ 49], 0x1601 [▶ 50] as well as 0x1A00 [▶ 50], 0x1A01 [▶ 50], 0x1A02 [▶ 51] and 0x1A03 [▶ 51] are activated. The meaning of the individual objects is explained in the object description.

**One up/down counter**

This mode can be set as follows:

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

Sync Manager:

SM	Size	Type	Flags
0	256	MbxOut	
1	256	MbxIn	
2	6	Outputs	
3	10	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	CNT Input Channel 1	F	3	0
0x1A01	6.0	CNT Input Channel 2	F		0
0x1A02	2.0	DIG Inputs	F	3	0
0x1A03	2.0	DIG Inputs Device	F	3	0
0x1600	6.0	CNT Output Channel 1	F	2	0
0x1601	6.0	CNT Output Channel 2	F		0

PDO Assignment (0x1C12):

0x1600  
 0x1601

PDO Content (0x1A00):

Index	Size	Offs	Name	Type	Default (hex)
---	0.2	0.0	---		
0x6000:03	0.1	0.2	Status__Set counter done	BOOL	
0x6000:04	0.1	0.3	Status__Counter inhibited	BOOL	
0x6000:05	0.1	0.4	Status__Status of input UD	BOOL	
0x6000:06	0.1	0.5	Status__Status of input clock	BOOL	
---	0.7	0.6	---		
0x6000:0E	0.1	1.5	Status__Sync error	BOOL	
0x6000:0F	0.1	1.6	Status__TxPDO State	BOOL	
0x6000:10	0.1	1.7	Status__TxPDO State	BOOL	

Download

PDO Assignment  
 PDO Configuration

Predefined PDO Assignment: (none)

Load PDO info from device

Sync Unit Assignment...

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

Sync Manager:

SM	Size	Type	Flags
0	256	MbxOut	
1	256	MbxIn	
2	6	Outputs	
3	10	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	CNT Input Channel 1	F	3	0
0x1A01	6.0	CNT Input Channel 2	F		0
0x1A02	2.0	DIG Inputs	F	3	0
0x1A03	2.0	DIG Inputs Device	F	3	0
0x1600	6.0	CNT Output Channel 1	F	2	0
0x1601	6.0	CNT Output Channel 2	F		0

PDO Assignment (0x1C12):

0x1A00  
 0x1A01  
 0x1A02  
 0x1A03

PDO Content (0x1A00):

Index	Size	Offs	Name	Type	Default (hex)
---	0.2	0.0	---		
0x6000:03	0.1	0.2	Status__Set counter done	BOOL	
0x6000:04	0.1	0.3	Status__Counter inhibited	BOOL	
0x6000:05	0.1	0.4	Status__Status of input UD	BOOL	
0x6000:06	0.1	0.5	Status__Status of input clock	BOOL	
---	0.7	0.6	---		
0x6000:0E	0.1	1.5	Status__Sync error	BOOL	
0x6000:0F	0.1	1.6	Status__TxPDO State	BOOL	
0x6000:10	0.1	1.7	Status__TxPDO State	BOOL	

Download

PDO Assignment  
 PDO Configuration

Predefined PDO Assignment: (none)

Load PDO info from device

Sync Unit Assignment...

The PDOs 0x1600 [▶ 49] as well as 0x1A00 [▶ 50], 0x1A02 [▶ 51] and 0x1A03 [▶ 51] are activated. The CoE objects are identical to the 2 x 32-bit counter operation mode.

**8 digital inputs, no counter**

This mode can be set as follows:

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

Sync Manager:

SM	Size	Type	Flags
0	256	MbxOut	
1	256	MbxIn	
2	0	Outputs	
3	4	Inputs	

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	CNT Input Channel 1	F		0
0x1A01	6.0	CNT Input Channel 2	F		0
0x1A02	2.0	DIG Inputs	F	3	0
0x1A03	2.0	DIG Inputs Device	F	3	0
0x1600	6.0	CNT Output Channel 1	F		0
0x1601	6.0	CNT Output Channel 2	F		0

PDO Assignment (0x1C12):

- 0x1A00
- 0x1A01
- 0x1A02
- 0x1A03

PDO Content (0x1A00):

Index	Size	Offs	Name	Type	Default (hex)
---	0.2	0.0	---		
0x6000:03	0.1	0.2	Status__Set counter done	BOOL	
0x6000:04	0.1	0.3	Status__Counter inhibited	BOOL	
0x6000:05	0.1	0.4	Status__Status of input UD	BOOL	
0x6000:06	0.1	0.5	Status__Status of input clock	BOOL	
---	0.7	0.6	---		
0x6000:0E	0.1	1.5	Status__Sync error	BOOL	
0x6000:0F	0.1	1.6	Status__TxPDO State	BOOL	
0x6000:10	0.1	1.7	Status__TxPDO Toggle	BOOL	
0x6000:11	4.0	2.0	Counter value	UDINT	
		6.0			

Download

- PDO Assignment
- PDO Configuration

Predefined PDO Assignment: (none)

Load PDO info from device

Sync Unit Assignment...

The PDOs 0x1A02 [▶ 51] and 0x1A03 [▶ 51] are activated. The meaning of the individual objects is explained in the object description.

### 5.4.3 Counter settings

#### Enabling the GATE and Up/Down inputs as standard inputs

By setting the CoE objects *Enable Input gate* and *Enable input UD*, the inputs are no longer allocated to the counters, but are used as standard inputs.

Index	Name	Flags	Value
[-] 8000:0	CNT Settings	RW	> 19 <
[-] 8000:03	Enable reload	RW	TRUE
[-] 8000:04	Count down	RW	FALSE
[-] 8000:05	Operating mode	RW	Enable pos. gate (Gate sperrt mit ...
[-] 8000:07	Enable input gate	RW	FALSE
[-] 8000:08	Enable input UD	RW	FALSE
[-] 8000:13	Counter reload value	RW	0x0000C350 (50000)
[+] 8010:0	CNT Settings	RW	> 19 <
[+] 8022:0	DIG Filter Settings	RW	> 8 <

Fig. 17: Enabling the inputs

#### Setting the counter to a value specified by the process data

The counter (counter value) can be set to any desired value by the controller.

To do this, set the desired value in *Set counter value*. The value is then adopted by *Counter value* on a rising edge of the *Set counter* control bit.

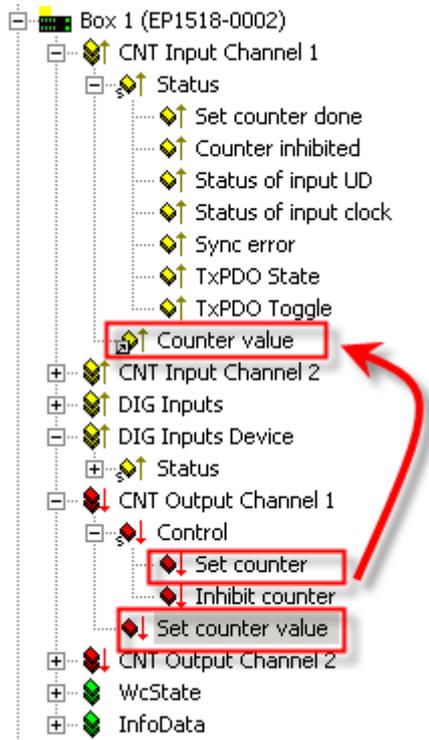


Fig. 18: Setting the counter

#### Automatic setting/resetting of the counter to a defined value

If a desired value is set in *Counter reload value* and the *Enable reload* bit is activated, the counter is set to 0 or to the set value if the specified value is exceeded or fallen below (depending on the counting direction).

Index	Name	Flags	Value
8000:0	CNT Settings	RW	> 19 <
8000:03	Enable reload	RW	TRUE
8000:04	Count down	RW	FALSE
8000:05	Operating mode	RW	Enable pos. gate (Gate sperrt mit ...
8000:07	Enable input gate	RW	FALSE
8000:08	Enable input UD	RW	FALSE
8000:13	Counter reload value	RW	0x0000C350 (50000)
8010:0	CNT Settings	RW	> 19 <
8022:0	DIG Filter Settings	RW	> 8 <

**Set Value Dialog**

Dec:

Hex:

Float:

Boot:

Binary:

Bit Size:  1  8  16  32  64  ?

Fig. 19: Automatic setting of the counter

## 5.4.4 Restoring the delivery state

To restore the delivery state for backup objects in ELxxxx terminals / EPxxxx- and EPPxxxx box modules, the CoE object *Restore default parameters, SubIndex 001* can be selected in the TwinCAT System Manager (Config mode).

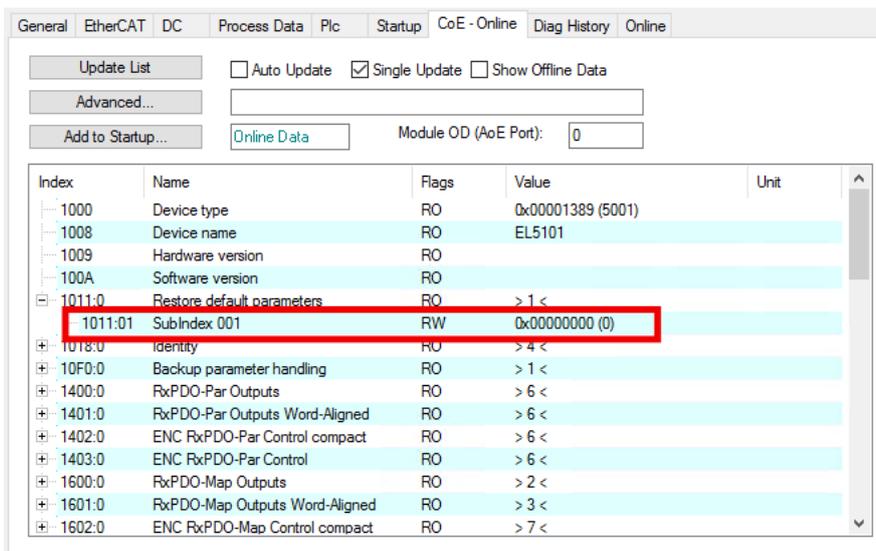


Fig. 20: Selecting the Restore default parameters PDO

Double-click on *SubIndex 001* to enter the Set Value dialog. Enter the value **1684107116** in field *Dec* or the value **0x64616F6C** in field *Hex* and confirm with OK.

All backup objects are reset to the delivery state.

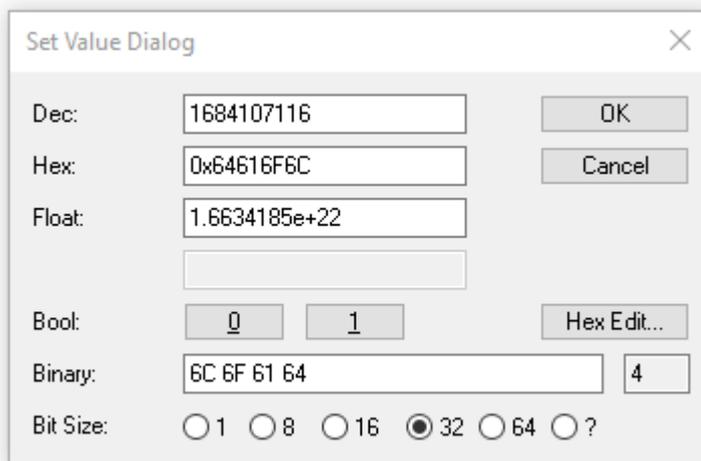


Fig. 21: Entering a restore value in the Set Value dialog

### **i** Alternative restore value

In some older terminals / boxes the backup objects can be switched with an alternative restore value:

Decimal value: 1819238756

Hexadecimal value: 0x6C6F6164

An incorrect entry for the restore value has no effect.

## 5.5 CoE objects

### 5.5.1 Object overview

#### **i** EtherCAT XML Device Description

The display matches that of the CoE objects from the EtherCAT XML Device Description. We recommend downloading the latest XML file from the download area of the Beckhoff website and installing it according to installation instructions.

Index (hex)	Name	Flags	Default value
1000 [▶ 49]	Device type	RO	0x00001389 (5001 <sub>dec</sub> )
1008 [▶ 49]	Device name	RO	EP1518-0002
1009 [▶ 49]	Hardware version	RO	00
100A [▶ 49]	Software version	RO	01.03
1011:0 [▶ 47]	<b>Subindex</b> Restore default parameters	RO	0x01 (1 <sub>dec</sub> )
	1011:01 SubIndex 001	RW	0x00000000 (0 <sub>dec</sub> )
1018:0 [▶ 49]	<b>Subindex</b> Identity	RO	0x04 (4 <sub>dec</sub> )
	1018:01 Vendor ID	RO	0x00000002 (2 <sub>dec</sub> )
	1018:02 Product code	RO	0x05EE4052 (99500114 <sub>dec</sub> )
	1018:03 Revision	RO	0x00100002 (1048578 <sub>dec</sub> )
	1018:04 Serial number	RO	0x00000000 (0 <sub>dec</sub> )
10F0:0 [▶ 49]	<b>Subindex</b> Backup parameter handling	RO	0x01 (1 <sub>dec</sub> )
	10F0:01 Checksum	RO	0x00000000 (0 <sub>dec</sub> )
1600:0 [▶ 49]	<b>Subindex</b> CNT RxPDO-Map Outputs Ch.1	RO	0x05 (5 <sub>dec</sub> )
	1600:01 SubIndex 001	RO	0x0000:00, 2
	1600:02 SubIndex 002	RO	0x7000:03, 1
	1600:03 SubIndex 003	RO	0x7000:04, 1
	1600:04 SubIndex 004	RO	0x0000:00, 12
	1600:05 SubIndex 005	RO	0x7000:11, 32
1601:0 [▶ 50]	<b>Subindex</b> CNT RxPDO-Map Outputs Ch.2	RO	0x05 (5 <sub>dec</sub> )
	1601:01 SubIndex 001	RO	0x0000:00, 2
	1601:02 SubIndex 002	RO	0x7010:03, 1
	1601:03 SubIndex 003	RO	0x7010:04, 1
	1601:04 SubIndex 004	RO	0x0000:00, 12
	1601:05 SubIndex 005	RO	0x7010:11, 32
1A00:0 [▶ 50]	<b>Subindex</b> CNT TxPDO-Map InputsCh.1	RO	0x0A (10 <sub>dec</sub> )
	1A00:01 SubIndex 001	RO	0x0000:00, 2
	1A00:02 SubIndex 002	RO	0x6000:03, 1
	1A00:03 SubIndex 003	RO	0x6000:04, 1
	1A00:04 SubIndex 004	RO	0x6000:05, 1
	1A00:05 SubIndex 005	RO	0x6000:06, 1
	1A00:06 SubIndex 006	RO	0x0000:00, 7
	1A00:07 SubIndex 007	RO	0x6000:0E, 1
	1A00:08 SubIndex 008	RO	0x6000:0F, 1
	1A00:09 SubIndex 009	RO	0x6000:10, 1
	1A00:0A SubIndex 010	RO	0x6000:11, 32

Index (hex)	Name	Flags	Default value
1A01:0	<b>Subindex</b> CNT TxPDO-Map Inputs Ch.2	RO	0x0A (10 <sub>dec</sub> )
[▶ 50]	1A01:01 SubIndex 001	RO	0x0000:00, 2
	1A01:02 SubIndex 002	RO	0x6010:03, 1
	1A01:03 SubIndex 003	RO	0x6010:04, 1
	1A01:04 SubIndex 004	RO	0x6010:05, 1
	1A01:05 SubIndex 005	RO	0x6010:06, 1
	1A01:06 SubIndex 006	RO	0x0000:00, 7
	1A01:07 SubIndex 007	RO	0x6010:0E, 1
	1A01:08 SubIndex 008	RO	0x6010:0F, 1
	1A01:09 SubIndex 009	RO	0x6010:10, 1
	1A01:0A SubIndex 010	RO	0x6010:11, 32
1A02:0	<b>Subindex</b> DIG TxPDO-Map Inputs	RO	0x09 (9 <sub>dec</sub> )
[▶ 51]	1A02:01 SubIndex 001	RO	0x6020:01, 1
	1A02:02 SubIndex 002	RO	0x6020:02, 1
	1A02:03 SubIndex 003	RO	0x6020:03, 1
	1A02:04 SubIndex 004	RO	0x6020:04, 1
	1A02:05 SubIndex 005	RO	0x6020:05, 1
	1A02:06 SubIndex 006	RO	0x6020:06, 1
	1A02:07 SubIndex 007	RO	0x6020:07, 1
	1A02:08 SubIndex 008	RO	0x6020:08, 1
	1A02:09 SubIndex 009	RO	0x0000:00, 8
1A03:0	<b>Subindex</b> DIG TxPDO-Map Inputs Device	RO	0x07 (7 <sub>dec</sub> )
[▶ 51]	1A03:01 SubIndex 001	RO	0x0000:00, 1
	1A03:02 SubIndex 002	RO	0xF600:02, 1
	1A03:03 SubIndex 003	RO	0xF600:03, 1
	1A03:04 SubIndex 004	RO	0x0000:00, 10
	1A03:05 SubIndex 005	RO	0xF600:0E, 1
	1A03:06 SubIndex 006	RO	0xF600:0F, 1
	1A03:07 SubIndex 007	RO	0xF600:10, 1
1C00:0	<b>Subindex</b> Sync manager type	RO	0x04 (4 <sub>dec</sub> )
[▶ 51]	1C00:01 SubIndex 001	RO	0x01 (1 <sub>dec</sub> )
	1C00:02 SubIndex 002	RO	0x02 (2 <sub>dec</sub> )
	1C00:03 SubIndex 003	RO	0x03 (3 <sub>dec</sub> )
	1C00:04 SubIndex 004	RO	0x04 (4 <sub>dec</sub> )
1C12:0	<b>Subindex</b> RxPDO assign	RW	0x02 (2 <sub>dec</sub> )
[▶ 51]	1C12:01 SubIndex 001	RW	0x1600 (5632 <sub>dec</sub> )
	1C12:02 SubIndex 002	RW	0x1601 (5633 <sub>dec</sub> )
1C13:0	<b>Subindex</b> TxPDO assign	RW	0x04 (4 <sub>dec</sub> )
[▶ 52]	1C13:01 SubIndex 001	RW	0x1A00 (6656 <sub>dec</sub> )
	1C13:02 SubIndex 002	RW	0x1A01 (6657 <sub>dec</sub> )
	1C13:03 SubIndex 003	RW	0x1A02 (6658 <sub>dec</sub> )
	1C13:04 SubIndex 004	RW	0x1A03 (6659 <sub>dec</sub> )

Index (hex)	Name	Flags	Default value
1C32:0	<b>Subindex</b> SM output parameter	RO	0x20 (32 <sub>dec</sub> )
▶ 52]	1C32:01	RW	0x0001 (1 <sub>dec</sub> )
	1C32:02	RW	0x000F4240 (1000000 <sub>dec</sub> )
	1C32:03	RO	0x00000000 (0 <sub>dec</sub> )
	1C32:04	RO	0xC007 (49159 <sub>dec</sub> )
	1C32:05	RO	0x0003D090 (250000 <sub>dec</sub> )
	1C32:06	RO	0x00000000 (0 <sub>dec</sub> )
	1C32:07	RO	0x00000000 (0 <sub>dec</sub> )
	1C32:08	RW	0x0000 (0 <sub>dec</sub> )
	1C32:09	RO	0x00000000 (0 <sub>dec</sub> )
	1C32:0B	RO	0x0000 (0 <sub>dec</sub> )
	1C32:0C	RO	0x0000 (0 <sub>dec</sub> )
	1C32:0D	RO	0x0000 (0 <sub>dec</sub> )
	1C32:20	RO	0x00 (0 <sub>dec</sub> )
1C33:0	<b>Subindex</b> SM input parameter	RO	0x20 (32 <sub>dec</sub> )
▶ 53]	1C33:01	RW	0x0022 (34 <sub>dec</sub> )
	1C33:02	RW	0x000F4240 (1000000 <sub>dec</sub> )
	1C33:03	RO	0x00000000 (0 <sub>dec</sub> )
	1C33:04	RO	0xC007 (49159 <sub>dec</sub> )
	1C33:05	RO	0x0003D090 (250000 <sub>dec</sub> )
	1C33:06	RO	0x00000000 (0 <sub>dec</sub> )
	1C33:07	RO	0x00000000 (0 <sub>dec</sub> )
	1C33:08	RW	0x0000 (0 <sub>dec</sub> )
	1C33:09	RO	0x00000000 (0 <sub>dec</sub> )
	1C33:0B	RO	0x0000 (0 <sub>dec</sub> )
	1C33:0C	RO	0x0000 (0 <sub>dec</sub> )
	1C33:0D	RO	0x0000 (0 <sub>dec</sub> )
	1C33:20	RO	0x00 (0 <sub>dec</sub> )
6000:0	<b>Subindex</b> CNT Inputs	RO	0x11 (17 <sub>dec</sub> )
▶ 54]	6000:03	RO	0x00 (0 <sub>dec</sub> )
	6000:04	RO	0x00 (0 <sub>dec</sub> )
	6000:05	RO	0x00 (0 <sub>dec</sub> )
	6000:06	RO	0x00 (0 <sub>dec</sub> )
	6000:0E	RO	0x00 (0 <sub>dec</sub> )
	6000:0F	RO	0x00 (0 <sub>dec</sub> )
	6000:10	RO	0x00 (0 <sub>dec</sub> )
	6000:11	RO	0x00000000 (0 <sub>dec</sub> )
6010:0	<b>Subindex</b> CNT Inputs	RO	0x11 (17 <sub>dec</sub> )
▶ 54]	6010:03	RO	0x00 (0 <sub>dec</sub> )
	6010:04	RO	0x00 (0 <sub>dec</sub> )
	6010:05	RO	0x00 (0 <sub>dec</sub> )
	6010:06	RO	0x00 (0 <sub>dec</sub> )
	6010:0E	RO	0x00 (0 <sub>dec</sub> )
	6010:0F	RO	0x00 (0 <sub>dec</sub> )
	6010:10	RO	0x00 (0 <sub>dec</sub> )
	6010:11	RO	0x00000000 (0 <sub>dec</sub> )

Index (hex)	Name	Flags	Default value
6020:0 [▶ 54]	<b>Subindex</b> DIG Inputs	RO	0x08 (8 <sub>dec</sub> )
	6020:01 Input 0	RO	0x00 (0 <sub>dec</sub> )
	6020:02 Input 1	RO	0x00 (0 <sub>dec</sub> )
	6020:03 Input 2	RO	0x00 (0 <sub>dec</sub> )
	6020:04 Input 3	RO	0x00 (0 <sub>dec</sub> )
	6020:05 Input 4	RO	0x00 (0 <sub>dec</sub> )
	6020:06 Input 5	RO	0x00 (0 <sub>dec</sub> )
	6020:07 Input 6	RO	0x00 (0 <sub>dec</sub> )
	6020:08 Input 7	RO	0x00 (0 <sub>dec</sub> )
7000:0 [▶ 54]	<b>Subindex</b> CNT Outputs	RO	0x11 (17 <sub>dec</sub> )
	7000:03 Set counter	RO	0x00 (0 <sub>dec</sub> )
	7000:04 Inhibit counter	RO	0x00 (0 <sub>dec</sub> )
	7000:11 Set counter value	RO	0x00000000 (0 <sub>dec</sub> )
7010:0 [▶ 55]	<b>Subindex</b> CNT Outputs	RO	0x11 (17 <sub>dec</sub> )
	7010:03 Set counter	RO	0x00 (0 <sub>dec</sub> )
	7010:04 Inhibit counter	RO	0x00 (0 <sub>dec</sub> )
	7010:11 Set counter value	RO	0x00000000 (0 <sub>dec</sub> )
8000:0 [▶ 48]	<b>Subindex</b> CNT Settings	RW	0x13 (19 <sub>dec</sub> )
	8000:03 Enable reload	RW	0x00 (0 <sub>dec</sub> )
	8000:04 Count down	RW	0x00 (0 <sub>dec</sub> )
	8000:05 Operating mode	RW	0x01 (1 <sub>dec</sub> )
	8000:13 Counter reload value	RW	0x00000000 (0 <sub>dec</sub> )
8010:0 [▶ 48]	<b>Subindex</b> CNT Settings	RW	0x13 (19 <sub>dec</sub> )
	8010:03 Enable reload	RW	0x00 (0 <sub>dec</sub> )
	8010:04 Count down	RW	0x00 (0 <sub>dec</sub> )
	8010:05 Operating mode	RW	0x01 (1 <sub>dec</sub> )
	8010:13 Counter reload value	RW	0x00000000 (0 <sub>dec</sub> )
8022:0 [▶ 48]	<b>Subindex</b> DIG Filter Settings	RW	0x08 (8 <sub>dec</sub> )
	8022:01 Input 0	RW	0x00 (0 <sub>dec</sub> )
	8022:02 Input 1	RW	0x00 (0 <sub>dec</sub> )
	8022:03 Input 2	RW	0x00 (0 <sub>dec</sub> )
	8022:04 Input 3	RW	0x00 (0 <sub>dec</sub> )
	8022:05 Input 4	RW	0x00 (0 <sub>dec</sub> )
	8022:06 Input 5	RW	0x00 (0 <sub>dec</sub> )
	8022:07 Input 6	RW	0x00 (0 <sub>dec</sub> )
	8022:08 Input 7	RW	0x00 (0 <sub>dec</sub> )
F000:0 [▶ 55]	<b>Subindex</b> Modular device profile	RO	0x02 (2 <sub>dec</sub> )
	F000:01 Module index distance	RO	0x0010 (16 <sub>dec</sub> )
	F000:02 Maximum number of modules	RO	0x0003 (3 <sub>dec</sub> )
F008 [▶ 55]	Code word	RW	0x00000000 (0 <sub>dec</sub> )
F010:0 [▶ 55]	<b>Subindex</b> Module list	RW	0x03 (3 <sub>dec</sub> )
	F010:01 SubIndex 001	RW	0x00000096 (150 <sub>dec</sub> )
	F010:02 SubIndex 002	RW	0x00000096 (150 <sub>dec</sub> )
	F010:03 SubIndex 003	RW	0x00000118 (280 <sub>dec</sub> )

Index (hex)	Name	Flags	Default value
F600:0	<b>Subindex</b> DIG Inputs	RO	0x10 (16 <sub>dec</sub> )
[▶ 55]	F600:02 Error channel 1	RO	0x00 (0 <sub>dec</sub> )
	F600:03 Error channel 2	RO	0x00 (0 <sub>dec</sub> )
	F600:0E Sync error	RO	0x00 (0 <sub>dec</sub> )
	F600:0F TxPDO State	RO	0x00 (0 <sub>dec</sub> )
	F600:10 TxPDO Toggle	RO	0x00 (0 <sub>dec</sub> )

**Key**

Flags:

RO (Read Only): this object can be read only

RW (Read/Write): this object can be read and written to

**5.5.2 Object description and parameterization**

● **Parameterization**

**i** The terminal is parameterized via the CoE - Online tab (double-click on the respective object) or via the Process Data tab (assignment of PDOs).

● **EtherCAT XML Device Description**

**i** The display matches that of the CoE objects from the EtherCAT XML Device Description. We recommend downloading the latest XML file from the download area on the Beckhoff website (<http://www.beckhoff.de/german/default.htm?download/elconfg.htm>) and installing it according to the installation instructions.

**Introduction**

The CoE overview contains objects for different intended applications:

- [Objects required for parameterization \[▶ 47\]](#) during commissioning
- Objects intended for regular operation, e.g. through ADS access.
- Objects for indicating internal settings (may be fixed)
- Further [profile-specific objects \[▶ 54\]](#) indicating inputs, outputs and status information

The following section first describes the objects required for normal operation, followed by a complete overview of missing objects.

**Additional objects**

**5.5.2.1 Objects to be parameterized during commissioning**

**Index 1011 Restore default parameters**

Index (hex)	Name	Meaning	Data type	Flags	Default
1011:0	Restore default parameters	Restore default parameters	UINT8	RO	0x01 (1 <sub>dec</sub> )
1011:01	SubIndex 001	If this object is set to "0x64616F6C" in the set value dialog, all backup objects are reset to their delivery state.	UINT32	RW	0x00000000 (0 <sub>dec</sub> )

## Index 8000 CNT Settings

Index (hex)	Name	Meaning	Data type	Flags	Default	
8000:0	CNT Settings	Maximum subindex	UINT8	RO	0x13 (19 <sub>dec</sub> )	
8000:03	Enable reload	The counter counts to the value in index <a href="#">0x8000:13</a> [ <a href="#">▶ 48</a> ]	BOOLEAN	RW	0x00 (0 <sub>dec</sub> )	
8000:04	Count down	Counting direction:	BOOLEAN	RW	0x00 (0 <sub>dec</sub> )	
		0 <sub>bin</sub>				Forward
		1 <sub>bin</sub>	Down			
8000:05	Operating mode	Operation mode	BIT2	RW	0x01 (1 <sub>dec</sub> )	
		01 <sub>bin</sub>				Enable pos. gate (gate inhibits with positive level)
		10 <sub>bin</sub>				Enable neg. gate (gate inhibits with negative level)
8000:13	Counter reload value	The limit that can be activated via "Enable reload" (index <a href="#">0x8000:03</a> [ <a href="#">▶ 48</a> ]). If counting upward, the counter counts up to this limit and, on exceeding it, starts again from zero. If counting downward, the counter counts down to 0 and, on falling below 0, is reloaded with the value from this register.	UINT32	RW	0x00000000 (0 <sub>dec</sub> )	

## Index 8010 CNT Settings

Index (hex)	Name	Meaning	Data type	Flags	Default	
8010:0	CNT Settings	Maximum subindex	UINT8	RO	0x13 (19 <sub>dec</sub> )	
8010:03	Enable reload	The counter counts to the value in index <a href="#">0x8010:13</a> [ <a href="#">▶ 48</a> ]	BOOLEAN	RW	0x00 (0 <sub>dec</sub> )	
8010:04	Count down	Counting direction:	BOOLEAN	RW	0x00 (0 <sub>dec</sub> )	
		0 <sub>bin</sub>				Forward
		1 <sub>bin</sub>	Down			
8010:05	Operating mode	Operation mode	BIT2	RW	0x01 (1 <sub>dec</sub> )	
		01 <sub>bin</sub>				Enable pos. gate (gate inhibits with positive level)
		10 <sub>bin</sub>				Enable neg. gate (gate inhibits with negative level)
8010:13	Counter reload value	The limit that can be activated via "Enable reload" ( <a href="#">index 0x8010:03</a> [ <a href="#">▶ 48</a> ]). If counting upward, the counter counts up to this limit and, on exceeding it, starts again from zero. If counting downward, the counter counts down to 0 and, on falling below 0, is reloaded with the value from this register.	UINT32	RW	0x00000000 (0 <sub>dec</sub> )	

## Index 8022 DIG Filter Settings

Index (hex)	Name	Meaning	Data type	Flags	Default	
8022:0	DIG Filter Settings	Maximum subindex	UINT8	RO	0x08 (8 <sub>dec</sub> )	
8022:01	Input 0	Filter time for the input	UINT8	RW	0x00 (0 <sub>dec</sub> )	
		0 <sub>dec</sub>				10 µs
		1 <sub>dec</sub>				200 µs
		2 <sub>dec</sub>				1 ms
		3 <sub>dec</sub>				3 ms
		4 <sub>dec</sub>				10 ms
		5 <sub>dec</sub>	100 ms			
8022:02	Input 1	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:03	Input 2	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:04	Input 3	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:05	Input 4	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:06	Input 5	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:07	Input 6	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	
8022:08	Input 7	see <a href="#">0x8022:01</a> [ <a href="#">▶ 48</a> ]	UINT8	RW	0x00 (0 <sub>dec</sub> )	

### 5.5.2.2 Standard objects (0x1000-0x1FFF)

The standard objects have the same meaning for all EtherCAT slaves.

#### Index 1000 Device type

Index (hex)	Name	Meaning	Data type	Flags	Default
1000:0	Device type	Device type of the EtherCAT slave: The Lo-Word contains the CoE profile used (5001). The Hi-Word contains the module profile according to the modular device profile.	UINT32	RO	0x00001389 (5001 <sub>dec</sub> )

#### Index 1008 Device name

Index (hex)	Name	Meaning	Data type	Flags	Default
1008:0	Device name	Device name of the EtherCAT slave	STRING	RO	EP1518-0002

#### Index 1009 Hardware version

Index (hex)	Name	Meaning	Data type	Flags	Default
1009:0	Hardware version	Hardware version of the EtherCAT slave	STRING	RO	00

#### Index 100A Software Version

Index (hex)	Name	Meaning	Data type	Flags	Default
100A:0	Software version	Firmware version of the EtherCAT slave	STRING	RO	01.03

#### Index 1018 Identity

Index (hex)	Name	Meaning	Data type	Flags	Default
1018:0	Identity	Information for identifying the slave	UINT8	RO	0x04 (4 <sub>dec</sub> )
1018:01	Vendor ID	Vendor ID of the EtherCAT slave	UINT32	RO	0x00000002 (2 <sub>dec</sub> )
1018:02	Product code	Product code of the EtherCAT slave	UINT32	RO	0x05EE4052 (99500114 <sub>dec</sub> )
1018:03	Revision	Revision number of the EtherCAT slave; the low word (bit 0-15) indicates the special terminal number, the high word (bit 16-31) refers to the device description	UINT32	RO	0x00100002 (1048578 <sub>dec</sub> )
1018:04	Serial number	Serial number of the EtherCAT slave; the low byte (bit 0-7) of the low word contains the year of production, the high byte (bit 8-15) of the low word contains the week of production, the high word (bit 16-31) is 0	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

#### Index 10F0 Backup parameter handling

Index (hex)	Name	Meaning	Data type	Flags	Default
10F0:0	Backup parameter handling	Information for standardized loading and saving of backup entries	UINT8	RO	0x01 (1 <sub>dec</sub> )
10F0:01	Checksum	Checksum across all backup entries of the EtherCAT slave	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

#### Index 1600 CNT RxPDO-Map Outputs Ch.1

Index (hex)	Name	Meaning	Data type	Flags	Default
1600:0	CNT RxPDO-Map Outputs Ch.1	PDO Mapping RxPDO 1	UINT8	RO	0x05 (5 <sub>dec</sub> )
1600:01	SubIndex 001	1. PDO Mapping entry (object 0x7040 (DO Outputs), entry 0x01 (Output 0))	UINT32	RO	0x0000:00, 2
1600:02	SubIndex 002	2. PDO Mapping entry (15 bits align)	UINT32	RO	0x7000:03, 1
1600:03	SubIndex 003	3. PDO Mapping entry (object 0x7010 (CNT Outputs), entry 0x03 (Set counter))	UINT32	RO	0x7000:04, 1
1600:04	SubIndex 004	4. PDO Mapping entry (object 0x7010 (CNT Outputs), entry 0x04 (Inhibit counter))	UINT32	RO	0x0000:00, 12
1600:05	SubIndex 005	5. PDO Mapping entry (12 bits align)	UINT32	RO	0x7000:11, 32

**Index 1601 CNT RxPDO-Map OutputsCh.2**

Index (hex)	Name	Meaning	Data type	Flags	Default
1601:0	CNT RxPDO-Map Outputs Ch.2	PDO Mapping RxPDO 2	UINT8	RO	0x05 (5 <sub>dec</sub> )
1601:01	SubIndex 001	1. PDO Mapping entry (object 0x7020 (CNT Outputs), entry 0x01 (Enable output functions))	UINT32	RO	0x0000:00, 2
1601:02	SubIndex 002	2. PDO Mapping entry (object 0x7020 (CNT Outputs), entry 0x02 (Set output))	UINT32	RO	0x7010:03, 1
1601:03	SubIndex 003	3. PDO Mapping entry (object 0x7020 (CNT Outputs), entry 0x03 (Set counter))	UINT32	RO	0x7010:04, 1
1601:04	SubIndex 004	4. PDO Mapping entry (object 0x7020 (CNT Outputs), entry 0x04 (Inhibit counter))	UINT32	RO	0x0000:00, 12
1601:05	SubIndex 005	5. PDO Mapping entry (12 bits align)	UINT32	RO	0x7010:11, 32

**Index 1A00 CNT TxPDO-Map InputsCh.1**

Index (hex)	Name	Meaning	Data type	Flags	Default
1A00:0	CNT TxPDO-Map InputsCh.1	PDO Mapping TxPDO 1	UINT8	RO	0x0A (10 <sub>dec</sub> )
1A00:01	SubIndex 001	1. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x01 (Input 0))	UINT32	RO	0x0000:00, 2
1A00:02	SubIndex 002	2. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x02 (Input 1))	UINT32	RO	0x6000:03, 1
1A00:03	SubIndex 003	3. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x03 (Input 2))	UINT32	RO	0x6000:04, 1
1A00:04	SubIndex 004	4. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x04 (Input 3))	UINT32	RO	0x6000:05, 1
1A00:05	SubIndex 005	5. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x05 (Input 4))	UINT32	RO	0x6000:06, 1
1A00:06	SubIndex 006	6. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x06 (Input 5))	UINT32	RO	0x0000:00, 7
1A00:07	SubIndex 007	7. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x06 (Input 6))	UINT32	RO	0x6000:0E, 1
1A00:08	SubIndex 008	8. PDO Mapping entry (object 0x6000 (DI Inputs Ch.1), entry 0x08 (Input 7))	UINT32	RO	0x6000:0F, 1
1A00:09	SubIndex 009	9. PDO Mapping entry (8 bits align)	UINT32	RO	0x6000:10, 1
1A00:0A	SubIndex 010	10. PDO Mapping entry (object 0x6000 (CNT Inputs), entry 0x11 (Counter value))	UINT32	RO	0x6000:11, 32

**Index 1A01 CNT TxPDO-Map InputsCh.2**

Index (hex)	Name	Meaning	Data type	Flags	Default
1A01:0	CNT TxPDO-Map Inputs Ch.2	PDO Mapping TxPDO 2	UINT8	RO	0x0A (10 <sub>dec</sub> )
1A01:01	SubIndex 001	1. PDO Mapping entry (15 bits align)	UINT32	RO	0x0000:00, 2
1A01:02	SubIndex 002	2. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6010:03, 1
1A01:03	SubIndex 003	3. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x11 (Counter value))	UINT32	RO	0x6010:04, 1
1A01:04	SubIndex 004	4. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x04 (Counter inhibited))	UINT32	RO	0x6010:05, 1
1A01:05	SubIndex 005	5. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x05 (Status of input UD))	UINT32	RO	0x6010:06, 1
1A01:06	SubIndex 006	6. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x06 (Status of input clock))	UINT32	RO	0x0000:00, 7
1A01:07	SubIndex 007	7. PDO Mapping entry (8 bits align)	UINT32	RO	0x6010:0E, 1
1A01:08	SubIndex 008	8. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x0F (TxPDO State))	UINT32	RO	0x6010:0F, 1
1A01:09	SubIndex 009	9. PDO Mapping entry (object 0x6020 (CNT Inputs), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6010:10, 1
1A01:0A	SubIndex 010	10. PDO Mapping entry (object 0x6010 (CNT Inputs), entry 0x11 (Counter value))	UINT32	RO	0x6010:11, 32

**Index 1A02 DIG TxPDO-Map Inputs**

Index (hex)	Name	Meaning	Data type	Flags	Default
1A02:0	DIG TxPDO-Map Inputs	PDO Mapping TxPDO 3	UINT8	RO	0x09 (9 <sub>dec</sub> )
1A02:01	SubIndex 001	1. PDO Mapping entry (2 bits align)	UINT32	RO	0x6020:01, 1
1A02:02	SubIndex 002	2. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x03 (Set counter done))	UINT32	RO	0x6020:02, 1
1A02:03	SubIndex 003	3. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x04 (Counter underflow))	UINT32	RO	0x6020:03, 1
1A02:04	SubIndex 004	4. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x05 (Counter overflow))	UINT32	RO	0x6020:04, 1
1A02:05	SubIndex 005	5. PDO Mapping entry (3 bits align)	UINT32	RO	0x6020:05, 1
1A02:06	SubIndex 006	6. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x09 (Status of input A))	UINT32	RO	0x6020:06, 1
1A02:07	SubIndex 007	7. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x0A (Status of input B))	UINT32	RO	0x6020:07, 1
1A02:08	SubIndex 008	8. PDO Mapping entry (object 0x6030 (ENC Inputs), entry 0x0B (Status of input C))	UINT32	RO	0x6020:08, 1
1A02:09	SubIndex 009	9. PDO Mapping entry (4 bits align)	UINT32	RO	0x0000:00, 8

**Index 1A03 DIG TxPDO-Map Inputs Device**

Index (hex)	Name	Meaning	Data type	Flags	Default
1A03:0	DIG TxPDO-Map Inputs Device	PDO Mapping TxPDO 4	UINT8	RO	0x07 (7 <sub>dec</sub> )
1A03:01	SubIndex 001	1. PDO Mapping entry (1 bits align)	UINT32	RO	0x0000:00, 1
1A03:02	SubIndex 002	2. PDO Mapping entry (object 0xF600 (DIG Inputs), entry 0x02 (Error channel 1))	UINT32	RO	0xF600:02, 1
1A03:03	SubIndex 003	3. PDO Mapping entry (object 0xF600 (DIG Inputs), entry 0x03 (Error channel 2))	UINT32	RO	0xF600:03, 1
1A03:04	SubIndex 004	4. PDO Mapping entry (10 bits align)	UINT32	RO	0x0000:00, 10
1A03:05	SubIndex 005	5. PDO Mapping entry (object 0xF600 (DIG Inputs), entry 0x0E (Sync error))	UINT32	RO	0xF600:0E, 1
1A03:06	SubIndex 006	6. PDO Mapping entry (1 bits align)	UINT32	RO	0xF600:0F, 1
1A03:07	SubIndex 007	7. PDO Mapping entry (object 0xF600 (DIG Inputs), entry 0x10 (TxPDO Toggle))	UINT32	RO	0xF600:10, 1

**Index 1C00 Sync manager type**

Index (hex)	Name	Meaning	Data type	Flags	Default
1C00:0	Sync manager type	Using the sync managers	UINT8	RO	0x04 (4 <sub>dec</sub> )
1C00:01	SubIndex 001	Sync-Manager Type Channel 1: Mailbox Write	UINT8	RO	0x01 (1 <sub>dec</sub> )
1C00:02	SubIndex 002	Sync-Manager Type Channel 2: Mailbox Read	UINT8	RO	0x02 (2 <sub>dec</sub> )
1C00:03	SubIndex 003	Sync-Manager Type Channel 3: Process Data Write (Outputs)	UINT8	RO	0x03 (3 <sub>dec</sub> )
1C00:04	SubIndex 004	Sync-Manager Type Channel 4: Process Data Read (Inputs)	UINT8	RO	0x04 (4 <sub>dec</sub> )

**Index 1C12 RxPDO assign**

Index (hex)	Name	Meaning	Data type	Flags	Default
1C12:0	RxPDO assign	PDO Assign Outputs	UINT8	RW	0x02 (2 <sub>dec</sub> )
1C12:01	Subindex 001	1. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1600 (5632 <sub>dec</sub> )
1C12:02	Subindex 002	2. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1601 (5633 <sub>dec</sub> )

## Index 1C13 TxPDO assign

Index (hex)	Name	Meaning	Data type	Flags	Default
1C13:0	TxPDO assign	PDO Assign Inputs	UINT8	RW	0x04 (4 <sub>dec</sub> )
1C13:01	Subindex 001	1. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A00 (6656 <sub>dec</sub> )
1C13:02	Subindex 002	2. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A01 (6657 <sub>dec</sub> )
1C13:03	Subindex 003	3. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A02 (6658 <sub>dec</sub> )
1C13:04	Subindex 004	4. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A03 (6659 <sub>dec</sub> )

## Index 1C32 SM output parameter

Index (hex)	Name	Meaning	Data type	Flags	Default
1C32:0	SM output parameter	Synchronization parameters for the outputs	UINT8	RO	0x20 (32 <sub>dec</sub> )
1C32:01	Sync mode	<ul style="list-style-type: none"> <li>0: Free Run</li> <li>1: Synchronous with SM 2 event</li> <li>2: DC-Mode - Synchronous with SYNC0 Event</li> <li>3: DC-Mode - Synchronous with SYNC1 event</li> </ul>	UINT16	RW	0x0001 (1 <sub>dec</sub> )
1C32:02	Cycle time	Cycle time (in ns): <ul style="list-style-type: none"> <li>Synchronous with SM 2 event: Master cycle time</li> <li>DC mode: SYNC0/SYNC1 Cycle Time</li> </ul>	UINT32	RW	0x000F4240 (1000000 <sub>dec</sub> )
1C32:03	Shift time	Time between SYNC0 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C32:04	Sync modes supported	Supported synchronization modes: <ul style="list-style-type: none"> <li>Bit 0 = 1: free run is supported</li> <li>Bit 1 = 1: synchronous with SM 2 event is supported</li> <li>Bit 2-3 = 01: DC mode is supported</li> <li>Bit 4-5 = 10: Output shift with SYNC1 event (only DC mode)</li> <li>Bit 14 = 1: dynamic times (measurement through writing of 0x1C32:08 [► 52])</li> </ul>	UINT16	RO	0xC007 (49159 <sub>dec</sub> )
1C32:05	Minimum cycle time	Minimum cycle time (in ns)	UINT32	RO	0x0003D090 (250000 <sub>dec</sub> )
1C32:06	Calc and copy time	Minimum time between SYNC0 and SYNC1 event (in ns, DC mode only)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C32:07	Minimum delay time	Minimum time between SYNC1 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C32:08	Command	<ul style="list-style-type: none"> <li>0: Measurement of the local cycle time is stopped</li> <li>1: Measurement of the local cycle time is started</li> </ul> The entries 0x1C32:03 [► 52], 0x1C32:05 [► 52], 0x1C32:06 [► 52], 0x1C32:07 [► 52], 0x1C32:09 [► 52], 0x1C33:03 [► 53], 0x1C33:06 [► 52], 0x1C33:07 [► 52] and 0x1C33:09 [► 53] are updated with the maximum measured values. For a subsequent measurement the measured values are reset	UINT16	RW	0x0000 (0 <sub>dec</sub> )
1C32:09	Maximum delay time	Minimum time between SYNC1 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C32:0B	SM event missed counter	Number of missed SM events in OPERATIONAL (DC mode only)	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C32:0C	Cycle exceeded counter	Number of occasions the cycle time was exceeded in OPERATIONAL (cycle was not completed in time or the next cycle began too early)	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C32:0D	Shift too short counter	Number of occasions that the interval between SYNC0 and SYNC1 event was too short (DC mode only)	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C32:20	Sync error	The synchronization was not correct in the last cycle (outputs were output too late; DC mode only)	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )

**Index 1C33 SM input parameter**

Index (hex)	Name	Meaning	Data type	Flags	Default
1C33:0	SM input parameter	Synchronization parameters for the inputs	UINT8	RO	0x20 (32 <sub>dec</sub> )
1C33:01	Sync mode	Current synchronization mode: <ul style="list-style-type: none"> <li>• 0: Free Run</li> <li>• 1: Synchronous with SM 3 Event (no outputs available)</li> <li>• 2: DC - Synchronous with SYNC0 Event</li> <li>• 3: DC - Synchronous with SYNC1 Event</li> <li>• 34: Synchronous with SM 2 event (outputs available)</li> </ul>	UINT16	RW	0x0022 (34 <sub>dec</sub> )
1C33:02	Cycle time	as <a href="#">0x1C32:02</a> [ <a href="#">▶ 52</a> ]	UINT32	RW	0x000F4240 (1000000 <sub>dec</sub> )
1C33:03	Shift time	Time between SYNC0 event and reading of the inputs (in ns, only DC mode)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C33:04	Sync modes supported	Supported synchronization modes: <ul style="list-style-type: none"> <li>• Bit 0: free run is supported</li> <li>• Bit 1: Synchronous with SM 2 Event is supported (outputs available)</li> <li>• Bit 1: Synchronous with SM 3 Event is supported (no outputs available)</li> <li>• Bit 2-3 = 01: DC mode is supported</li> <li>• Bit 4-5 = 01: Input shift through local event (outputs available)</li> <li>• Bit 4-5 = 10: Input shift with SYNC1 event (no outputs available)</li> <li>• Bit 14 = 1: dynamic times (measurement through writing of <a href="#">0x1C32:08</a> [<a href="#">▶ 52</a>] or <a href="#">0x1C33:08</a> [<a href="#">▶ 53</a>])</li> </ul>	UINT16	RO	0xC007 (49159 <sub>dec</sub> )
1C33:05	Minimum cycle time	as <a href="#">0x1C32:05</a> [ <a href="#">▶ 52</a> ]	UINT32	RO	0x0003D090 (250000 <sub>dec</sub> )
1C33:06	Calc and copy time	Time between reading of the inputs and availability of the inputs for the master (in ns, only DC mode)	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C33:07	Minimum delay time	as <a href="#">0x1C32:07</a> [ <a href="#">▶ 52</a> ]	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C33:08	Command	as <a href="#">0x1C32:08</a> [ <a href="#">▶ 52</a> ]	UINT16	RW	0x0000 (0 <sub>dec</sub> )
1C33:09	Maximum delay time	as <a href="#">0x1C32:09</a> [ <a href="#">▶ 52</a> ]	UINT32	RO	0x00000000 (0 <sub>dec</sub> )
1C33:0B	SM event missed counter	as 0x1C32:11	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C33:0C	Cycle exceeded counter	as 0x1C32:12	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C33:0D	Shift too short counter	as 0x1C32:13	UINT16	RO	0x0000 (0 <sub>dec</sub> )
1C33:20	Sync error	as 0x1C32:32	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )

### 5.5.2.3 Profile-specific objects (0x6000-0xFFFF)

The profile-specific objects have the same meaning for all EtherCAT slaves that support the profile 5001.

#### Index 6000 CNT Inputs

Index (hex)	Name	Meaning	Data type	Flags	Default
6000:0	CNT Inputs	Maximum subindex	UINT8	RO	0x11 (17 <sub>dec</sub> )
6000:03	Set counter done	The counter was set	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:04	Counter inhibited	The counter is stopped for as long as this bit is set	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:05	Status of input UD	The state of the up/down input	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:06	Status of input clock	The state of the clock input	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:0E	Sync error	Synchronization error	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:0F	TxPDO State	Validity of the data of the associated TxPDO (0 = valid, 1 = invalid)	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:10	TxPDO Toggle	The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6000:11	Counter value	Counter value	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

#### Index 6010 CNT Inputs

Index (hex)	Name	Meaning	Data type	Flags	Default
6010:0	CNT Inputs	Maximum subindex	UINT8	RO	0x11 (17 <sub>dec</sub> )
6010:03	Set counter done	The counter was set	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:04	Counter inhibited	The counter is stopped for as long as this bit is set	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:05	Status of input UD	The state of the up/down input	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:06	Status of input clock	The state of the clock input	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:0E	Sync error	Synchronization error	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:0F	TxPDO State	Validity of the data of the associated TxPDO (0 = valid, 1 = invalid)	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:10	TxPDO Toggle	The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6010:11	Counter value	Counter value	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

#### Index 6020 DIG Inputs

Index (hex)	Name	Meaning	Data type	Flags	Default
6020:0	DIG Inputs	Maximum subindex	UINT8	RO	0x08 (8 <sub>dec</sub> )
6020:01	Input 0	Digital input 0	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:02	Input 1	Digital input 1	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:03	Input 2	Digital input 2	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:04	Input 3	Digital input 3	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:05	Input 4	Digital input 4	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:06	Input 5	Digital input 5	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:07	Input 6	Digital input 6	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
6020:08	Input 7	Digital input 7	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )

#### Index 7000 CNT Outputs

Index (hex)	Name	Meaning	Data type	Flags	Default
7000:0	CNT Outputs	Maximum subindex	UINT8	RO	0x11 (17 <sub>dec</sub> )
7000:03	Set counter	Set counter value	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
7000:04	Inhibit counter	The counter is stopped, as long as this bit is active. The previous counter state is retained.	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
7000:11	Set counter value	This is the counter value to be set via "Set counter" (index 0x7000:03 <a href="#">▶ 54</a> ).	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

**Index 7010 CNT Outputs**

Index (hex)	Name	Meaning	Data type	Flags	Default
7010:0	CNT Outputs	Maximum subindex	UINT8	RO	0x11 (17 <sub>dec</sub> )
7010:03	Set counter	Set counter value	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
7010:04	Inhibit counter	The counter is stopped, as long as this bit is active. The previous counter state is retained.	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
7010:11	Set counter value	This is the counter value to be set via "Set counter" (index 0x7000:03 [► 55]).	UINT32	RO	0x00000000 (0 <sub>dec</sub> )

**Index F000 Modular Device Profile**

Index (hex)	Name	Meaning	Data type	Flags	Default
F000:0	Modular device profile	General information for the modular device profile	UINT8	RO	0x02 (2 <sub>dec</sub> )
F000:01	Module index distance	Index distance of the objects of the individual channels	UINT16	RO	0x0010 (16 <sub>dec</sub> )
F000:02	Maximum number of modules	Number of channels	UINT16	RO	0x0003 (3 <sub>dec</sub> )

**Index F008 Code word**

Index (hex)	Name	Meaning	Data type	Flags	Default
F008:0	Code word	reserved	UINT32	RW	0x00000000 (0 <sub>dec</sub> )

**Index F010 Module List**

Index (hex)	Name	Meaning	Data type	Flags	Default
F010:0	Module list	Maximum subindex	UINT8	RW	0x03 (3 <sub>dec</sub> )
F010:01	SubIndex 001	reserved	UINT32	RW	0x00000096 (150 <sub>dec</sub> )
F010:02	SubIndex 002	reserved	UINT32	RW	0x00000096 (150 <sub>dec</sub> )
F010:03	SubIndex 003	reserved	UINT32	RW	0x00000118 (280 <sub>dec</sub> )

**Index F600 DIG Inputs**

Index (hex)	Name	Meaning	Data type	Flags	Default
F600:0	DIG Inputs	Maximum subindex	UINT8	RO	0x10 (16 <sub>dec</sub> )
F600:02	Error channel 1	If this bit is set, a short circuit has been detected in the supply voltage to sensor group 1 (inputs 0 - 3).	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
F600:03	Error channel 2	If this bit is set, a short circuit has been detected in the supply voltage to sensor group 2 (inputs 4 - 7).	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
F600:0E	Sync error	Synchronization error	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
F600:0F	TxPDO State	Validity of the data of the associated TxPDO (0 = valid, 1 = invalid)	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )
F600:10	TxPDO Toggle	The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated	BOOLEAN	RO	0x00 (0 <sub>dec</sub> )

## 6 Appendix

### 6.1 General operating conditions

#### Protection degrees (IP-Code)

The standard IEC 60529 (DIN EN 60529) defines the degrees of protection in different classes.

1. Number: dust protection and touch guard	Definition
0	Non-protected
1	Protected against access to hazardous parts with the back of a hand. Protected against solid foreign objects of Ø 50 mm
2	Protected against access to hazardous parts with a finger. Protected against solid foreign objects of Ø 12.5 mm.
3	Protected against access to hazardous parts with a tool. Protected against solid foreign objects Ø 2.5 mm.
4	Protected against access to hazardous parts with a wire. Protected against solid foreign objects Ø 1 mm.
5	Protected against access to hazardous parts with a wire. Dust-protected. Intrusion of dust is not totally prevented, but dust shall not penetrate in a quantity to interfere with satisfactory operation of the device or to impair safety.
6	Protected against access to hazardous parts with a wire. Dust-tight. No intrusion of dust.
2. Number: water* protection	Definition
0	Non-protected
1	Protected against water drops
2	Protected against water drops when enclosure tilted up to 15°.
3	Protected against spraying water. Water sprayed at an angle up to 60° on either side of the vertical shall have no harmful effects.
4	Protected against splashing water. Water splashed against the disclosure from any direction shall have no harmful effects
5	Protected against water jets
6	Protected against powerful water jets
7	Protected against the effects of temporary immersion in water. Intrusion of water in quantities causing harmful effects shall not be possible when the enclosure is temporarily immersed in water for 30 min. in 1 m depth.

\*) These protection classes define only protection against water.

#### Chemical Resistance

The Resistance relates to the Housing of the IP67 modules and the used metal parts. In the table below you will find some typical resistance.

Character	Resistance
Steam	at temperatures >100°C: not resistant
Sodium base liquor (ph-Value > 12)	at room temperature: resistant > 40°C: not resistant
Acetic acid	not resistant
Argon (technical clean)	resistant

#### Key

- resistant: Lifetime several months
- non inherently resistant: Lifetime several weeks
- not resistant: Lifetime several hours resp. early decomposition

## 6.2 Accessories

### Mounting

Ordering information	Description	Link
ZS5300-0011	Mounting rail	<a href="#">Website</a>

### Cables

A complete overview of pre-assembled cables for fieldbus components can be found [here](#).

Ordering information	Description	Link
ZK1090-3xxx-xxxx	EtherCAT cable M8, green	<a href="#">Website</a>
ZK1093-3xxx-xxxx	EtherCAT cable M8, yellow	<a href="#">Website</a>
ZK2000-6xxx-xxxx	Sensor cable M12, 4-pin	<a href="#">Website</a>
ZK2020-3xxx-xxxx	Power cable M8, 4-pin	<a href="#">Website</a>

### Labeling material, protective caps

Ordering information	Description
ZS5000-0010	Protective cap for M8 sockets, IP67 (50 pieces)
ZS5000-0020	Protective cap for M12 sockets, IP67 (50 pcs.)
ZS5100-0000	Inscription labels, unprinted, 4 strips of 10
ZS5000-xxxx	Printed inscription labels on enquiry

### Tools

Ordering information	Description
ZB8801-0000	Torque wrench for plugs, 0.4...1.0 Nm
ZB8801-0001	Torque cable key for M8 / wrench size 9 for ZB8801-0000
ZB8801-0002	Torque cable key for M12 / wrench size 13 for ZB8801-0000
ZB8801-0003	Torque cable key for M12 field assembly / wrench size 18 for ZB8801-0000

### **i** Further accessories

Further accessories can be found in the price list for fieldbus components from Beckhoff and online at <https://www.beckhoff.com>.

## 6.3 Version identification of EtherCAT devices

### 6.3.1 General notes on marking

#### Designation

A Beckhoff EtherCAT device has a 14-digit designation, made up of

- family key
- type
- version
- revision

Example	Family	Type	Version	Revision
EL3314-0000-0016	EL terminal (12 mm, non-pluggable connection level)	3314 (4-channel thermocouple terminal)	0000 (basic type)	0016
ES3602-0010-0017	ES terminal (12 mm, pluggable connection level)	3602 (2-channel voltage measurement)	0010 (high-precision version)	0017
CU2008-0000-0000	CU device	2008 (8-port fast ethernet switch)	0000 (basic type)	0000

#### Notes

- The elements mentioned above result in the **technical designation**. EL3314-0000-0016 is used in the example below.
- EL3314-0000 is the order identifier, in the case of “-0000” usually abbreviated to EL3314. “-0016” is the EtherCAT revision.
- The **order identifier** is made up of
  - family key (EL, EP, CU, ES, KL, CX, etc.)
  - type (3314)
  - version (-0000)
- The **revision** -0016 shows the technical progress, such as the extension of features with regard to the EtherCAT communication, and is managed by Beckhoff.  
In principle, a device with a higher revision can replace a device with a lower revision, unless specified otherwise, e.g. in the documentation.  
Associated and synonymous with each revision there is usually a description (ESI, EtherCAT Slave Information) in the form of an XML file, which is available for download from the Beckhoff web site.  
From 2014/01 the revision is shown on the outside of the IP20 terminals, see Fig. “EL5021 EL terminal, standard IP20 IO device with batch number and revision ID (since 2014/01)”.
- The type, version and revision are read as decimal numbers, even if they are technically saved in hexadecimal.

### 6.3.2 Version identification of EP/EPI/EPP/ER/ERI boxes

The serial number/ data code for Beckhoff IO devices is usually the 8-digit number printed on the device or on a sticker. The serial number indicates the configuration in delivery state and therefore refers to a whole production batch, without distinguishing the individual modules of a batch.

Structure of the serial number: **KK YY FF HH**

- KK - week of production (CW, calendar week)
- YY - year of production
- FF - firmware version
- HH - hardware version

Example with serial number 12 06 3A 02:

- 12 - production week 12
- 06 - production year 2006
- 3A - firmware version 3A
- 02 - hardware version 02

Exceptions can occur in the **IP67 area**, where the following syntax can be used (see respective device documentation):

Syntax: D ww yy x y z u

- D - prefix designation
- ww - calendar week
- yy - year
- x - firmware version of the bus PCB
- y - hardware version of the bus PCB
- z - firmware version of the I/O PCB
- u - hardware version of the I/O PCB

Example: D.22081501 calendar week 22 of the year 2008 firmware version of bus PCB: 1 hardware version of bus PCB: 5 firmware version of I/O PCB: 0 (no firmware necessary for this PCB) hardware version of I/O PCB: 1

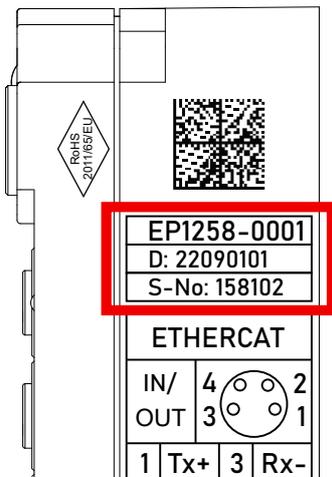


Fig. 22: EP1258-00001 IP67 EtherCAT Box with batch number/DateCode 22090101 and unique serial number 158102

### 6.3.3 Beckhoff Identification Code (BIC)

The Beckhoff Identification Code (BIC) is increasingly being applied to Beckhoff products to uniquely identify the product. The BIC is represented as a Data Matrix Code (DMC, code scheme ECC200), the content is based on the ANSI standard MH10.8.2-2016.

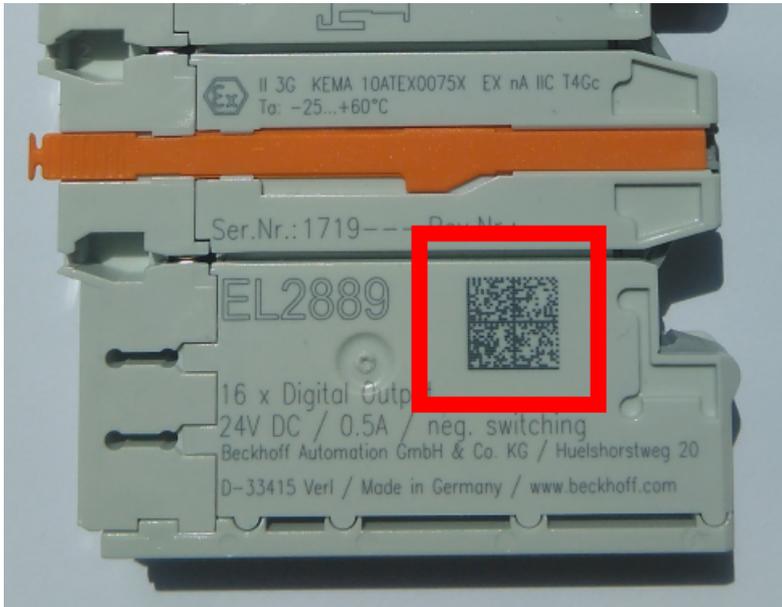


Fig. 23: BIC as data matrix code (DMC, code scheme ECC200)

The BIC will be introduced step by step across all product groups.

Depending on the product, it can be found in the following places:

- on the packaging unit
- directly on the product (if space suffices)
- on the packaging unit and the product

The BIC is machine-readable and contains information that can also be used by the customer for handling and product management.

Each piece of information can be uniquely identified using the so-called data identifier (ANSI MH10.8.2-2016). The data identifier is followed by a character string. Both together have a maximum length according to the table below. If the information is shorter, spaces are added to it.

Following information is possible, positions 1 to 4 are always present, the other according to need of production:

Position	Type of information	Explanation	Data identifier	Number of digits incl. data identifier	Example
1	Beckhoff order number	<b>Beckhoff order number</b>	1P	8	<b>1P</b> 072222
2	Beckhoff Traceability Number (BTN)	<b>Unique serial number, see note below</b>	SBTN	12	<b>S</b> BTNk4p562d7
3	Article description	<b>Beckhoff article description, e.g. EL1008</b>	1K	32	<b>1K</b> EL1809
4	Quantity	<b>Quantity in packaging unit, e.g. 1, 10, etc.</b>	Q	6	<b>Q</b> 1
5	Batch number	Optional: Year and week of production	2P	14	<b>2P</b> 401503180016
6	ID/serial number	Optional: Present-day serial number system, e.g. with safety products	51S	12	<b>51S</b> 678294
7	Variant number	Optional: Product variant number on the basis of standard products	30P	32	<b>30P</b> F971, 2*K183
...					

Further types of information and data identifiers are used by Beckhoff and serve internal processes.

**Structure of the BIC**

Example of composite information from positions 1 to 4 and with the above given example value on position 6. The data identifiers are highlighted in bold font:

**1P**072222**S**BTNk4p562d7**1K**EL1809 **Q**1 **51S**678294

Accordingly as DMC:

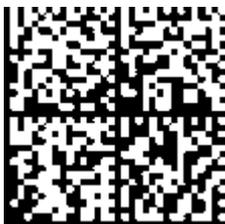


Fig. 24: Example DMC **1P**072222**S**BTNk4p562d7**1K**EL1809 **Q**1 **51S**678294

**BTN**

An important component of the BIC is the Beckhoff Traceability Number (BTN, position 2). The BTN is a unique serial number consisting of eight characters that will replace all other serial number systems at Beckhoff in the long term (e.g. batch designations on IO components, previous serial number range for safety products, etc.). The BTN will also be introduced step by step, so it may happen that the BTN is not yet coded in the BIC.

**NOTE**

This information has been carefully prepared. However, the procedure described is constantly being further developed. We reserve the right to revise and change procedures and documentation at any time and without prior notice. No claims for changes can be made from the information, illustrations and descriptions in this information.

## 6.3.4 Electronic access to the BIC (eBIC)

### Electronic BIC (eBIC)

The Beckhoff Identification Code (BIC) is applied to the outside of Beckhoff products in a visible place. If possible, it should also be electronically readable.

Decisive for the electronic readout is the interface via which the product can be electronically addressed.

### K-bus devices (IP20, IP67)

Currently, no electronic storage and readout is planned for these devices.

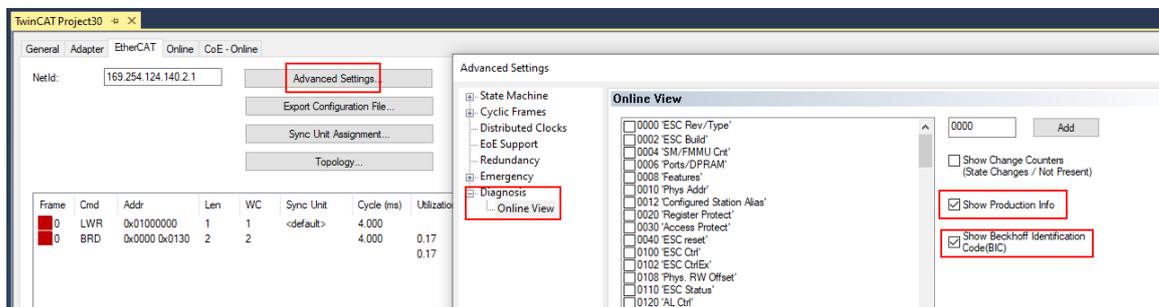
### EtherCAT devices (IP20, IP67)

All Beckhoff EtherCAT devices have a so-called ESI-EEPROM, which contains the EtherCAT identity with the revision number. Stored in it is the EtherCAT slave information, also colloquially known as ESI/XML configuration file for the EtherCAT master. See the corresponding chapter in the EtherCAT system manual ([Link](#)) for the relationships.

The eBIC is also stored in the ESI-EEPROM. The eBIC was introduced into the Beckhoff I/O production (terminals, box modules) from 2020; widespread implementation is expected in 2021.

The user can electronically access the eBIC (if existent) as follows:

- With all EtherCAT devices, the EtherCAT master (TwinCAT) can read the eBIC from the ESI-EEPROM
  - From TwinCAT 3.1 build 4024.11, the eBIC can be displayed in the online view.
  - To do this, check the checkbox "Show Beckhoff Identification Code (BIC)" under EtherCAT → Advanced Settings → Diagnostics:



- The BTN and its contents are then displayed:

No	Addr	Name	State	CRC	Fw	Hw	Production Data	ItemNo	BTN	Description	Quantity	BatchNo	SerialNo
1	1001	Term 1 (EK1100)	OP	0,0	0	0	---						
2	1002	Term 2 (EL1018)	OP	0,0	0	0	2020 KW36 Fr	072222	k4p562d7	EL1809	1		678294
3	1003	Term 3 (EL3204)	OP	0,0	7	6	2012 KW24 Sa						
4	1004	Term 4 (EL2004)	OP	0,0	0	0	---	072223	k4p562d7	EL2004	1		678295
5	1005	Term 5 (EL1008)	OP	0,0	0	0	---						
6	1006	Term 6 (EL2008)	OP	0,0	0	12	2014 KW14 Mo						
7	1007	Term 7 (EK1110)	OP	0	1	8	2012 KW25 Mo						

- Note: as can be seen in the illustration, the production data HW version, FW version and production date, which have been programmed since 2012, can also be displayed with "Show Production Info".
- From TwinCAT 3.1. build 4024.24 the functions *FB\_EcReadBIC* and *FB\_EcReadBTN* for reading into the PLC and further eBIC auxiliary functions are available in the Tc2\_EtherCAT Library from v3.3.19.0.
- In the case of EtherCAT devices with CoE directory, the object 0x10E2:01 can additionally be used to display the device's own eBIC; the PLC can also simply access the information here:

- The device must be in PREOP/SAFEOP/OP for access:

Index	Name	Flags	Value
1000	Device type	RO	0x015E1389 (22942601)
1008	Device name	RO	ELM3704-0000
1009	Hardware version	RO	00
100A	Software version	RO	01
100B	Bootloader version	RO	J0.1.27.0
1011:0	Restore default parameters	RO	> 1 <
1018:0	Identity	RO	> 4 <
10E2:0	Manufacturer-specific Identification C...	RO	> 1 <
10E2:01	SubIndex 001	RO	1P158442SBTN0008jekp1KELM3704 Q1 2P482001000016
10F0:0	Backup parameter handling	RO	> 1 <
10F3:0	Diagnosis History	RO	> 21 <
10F8	Actual Time Stamp	RO	0x170bfb277e

- the object 0x10E2 will be introduced into stock products in the course of a necessary firmware revision.
- From TwinCAT 3.1. build 4024.24 the functions *FB\_EcCoEReadBIC* and *FB\_EcCoEReadBTN* for reading into the PLC and further eBIC auxiliary functions are available in the Tc2\_EtherCAT Library from v3.3.19.0.
- Note: in the case of electronic further processing, the BTN is to be handled as a string(8); the identifier "SBTN" is not part of the BTN.
- Technical background  
The new BIC information is additionally written as a category in the ESI-EEPROM during the device production. The structure of the ESI content is largely dictated by the ETG specifications, therefore the additional vendor-specific content is stored with the help of a category according to ETG.2010. ID 03 indicates to all EtherCAT masters that they must not overwrite these data in case of an update or restore the data after an ESI update.  
The structure follows the content of the BIC, see there. This results in a memory requirement of approx. 50..200 bytes in the EEPROM.
- Special cases
  - If multiple, hierarchically arranged ESCs are installed in a device, only the top-level ESC carries the eBIC Information.
  - If multiple, non-hierarchically arranged ESCs are installed in a device, all ESCs carry the eBIC Information.
  - If the device consists of several sub-devices with their own identity, but only the top-level device is accessible via EtherCAT, the eBIC of the top-level device is located in the CoE object directory 0x10E2:01 and the eBICs of the sub-devices follow in 0x10E2:nn.

**Profibus/Profinet/DeviceNet... Devices**

Currently, no electronic storage and readout is planned for these devices.

## 6.4 Support and Service

Beckhoff and their partners around the world offer comprehensive support and service, making available fast and competent assistance with all questions related to Beckhoff products and system solutions.

### Beckhoff's branch offices and representatives

Please contact your Beckhoff branch office or representative for local support and service on Beckhoff products!

The addresses of Beckhoff's branch offices and representatives round the world can be found on her internet pages: <https://www.beckhoff.com>

You will also find further documentation for Beckhoff components there.

### Beckhoff Support

Support offers you comprehensive technical assistance, helping you not only with the application of individual Beckhoff products, but also with other, wide-ranging services:

- support
- design, programming and commissioning of complex automation systems
- and extensive training program for Beckhoff system components

Hotline: +49 5246 963 157  
Fax: +49 5246 963 9157  
e-mail: [support@beckhoff.com](mailto:support@beckhoff.com)

### Beckhoff Service

The Beckhoff Service Center supports you in all matters of after-sales service:

- on-site service
- repair service
- spare parts service
- hotline service

Hotline: +49 5246 963 460  
Fax: +49 5246 963 479  
e-mail: [service@beckhoff.com](mailto:service@beckhoff.com)

### Beckhoff Headquarters

Beckhoff Automation GmbH & Co. KG

Huelshorstweg 20  
33415 Verl  
Germany

Phone: +49 5246 963 0  
Fax: +49 5246 963 198  
e-mail: [info@beckhoff.com](mailto:info@beckhoff.com)  
web: <https://www.beckhoff.com>



More Information:  
[www.beckhoff.com/ep1518/](http://www.beckhoff.com/ep1518/)

Beckhoff Automation GmbH & Co. KG  
Hülshorstweg 20  
33415 Verl  
Germany  
Phone: +49 5246 9630  
[info@beckhoff.com](mailto:info@beckhoff.com)  
[www.beckhoff.com](http://www.beckhoff.com)

