Hardware data sheet

ET1200

EtherCAT® slave controller

Section I – Technology
(Online at http://www.beckhoff.com)

Section II – Register description
(Online at http://www.beckhoff.com)

Section III – Hardware description

Pinout, interface description, electrical and mechanical specification, ET1200 features and registers

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BECKHOFF

DOCUMENT ORGANIZATION

The Beckhoff EtherCAT slave controller (ESC) documentation covers the following Beckhoff ESCs:

- ET1200
- ET1100
- EtherCAT IP core for Altera® FPGAs
- EtherCAT IP core for AMD® FPGAs
- ESC20

The documentation is organized in three sections. Section I and section II are common for all Beckhoff ESCs, section III is specific for each ESC variant.

The latest documentation is available at the Beckhoff homepage (http://www.beckhoff.com).

Section I – Technology (all ESCs)

Section I deals with the basic EtherCAT technology. Starting with the EtherCAT protocol itself, the frame processing inside EtherCAT slaves is described. The features and interfaces of the physical layer with its two alternatives Ethernet and EBUS are explained afterwards. Finally, the details of the functional units of an ESC like FMMU, SyncManager, distributed clocks, slave information interface, interrupts, watchdogs, and so on, are described.

Since section I is common for all Beckhoff ESCs, it might describe features which are not available in a specific ESC. Refer to the feature details overview in section III of a specific ESC to find out which features are available.

Section II – Register description (all ESCs)

Section II contains detailed information about all ESC registers. This section is also common for all Beckhoff ESCs, thus registers, register bits, or features are described which might not be available in a specific ESC. Refer to the register overview and to the feature details overview in section III of a specific ESC to find out which registers and features are available.

Section III – Hardware description (specific ESC)

Section III is ESC specific and contains detailed information about the ESC features, implemented registers, configuration, interfaces, pinout, usage, electrical and mechanical specification, and so on. Especially the process data interfaces (PDI) supported by the ESC are part of this section.

Additional documentation

Application notes and utilities like pinout configuration tools for ET1200 can also be found at the Beckhoff homepage.

DOCUMENT HISTORY

Version	Comment
0.1	Initial release
0.2	Editorial changes
0.3	Register overview, PDI, Electrical and mechanical spec
0.4	Abbreviations, editorial changes
0.5	• Removed RJ45 description (will become part of section I) • EEPROM_LOADED pull-down resistor recommendation added • Frame processing order example corrected • I^2C EEPROM interface description added • PHY management interface description added • Corrected process RAM size in register overview • Revision/build information added • Recommendations for unused input pins added (should not be left open) • EEPROM_SIZE description corrected from Kbyte to Kbit, possible EEPROM sizes range from 16 Kbit to 4 Mbit • RoHS compliance added • Auto-negotiation is mandatory for ESCs • Description of power supply options added • Electrical characteristics added • SPI_IRQ delay added • TX shift timing diagram and description added • Pin overview table corrected • Internal 27 kΩ PU/PD resistors at EBUS-RX pins added • LED polarity depending on configuration pin setting described • Recommendation for voltage stabilization capacitors added • Description of digital I/O behavior on watchdog expiration enhanced • EBUS ports are open failsafe • Reset example schematic added • Ethernet PHY requirements and PHY connection schematic added • MI_DATA pull-up requirement added • Editorial changes
1.0	• RUN, LINKACT/x) and PERR(x) LED activity level corrected: active high if pulled down, active low if pulled up • TX shift description: timing figures corrected, minor changes, moved to MII interface chapter • Pin/signal description overview added • PERR(x) LEDs are only for testing/debugging • Electrical characteristics enhanced • DC characteristics enhanced: added $V_{Reset\ Core}$, V_{ID}, V_{IC} • Digital I/O and SPI timing characteristics revised • DC SYNC/LATCH signal description and timing characteristics added • MII interface chapter and MII timing characteristics added • EBUS interface chapter added • PHY requirements, EEPROM interface description and PHY management interface description moved to section I • Ambient temperature range instead of junction temperature range • Editorial changes

Version	Comment
1.1	• Clarified I/O voltage with respect to I/O power supply (only 3.3V I/O with $V_{CCI/O}$=3.3V, and no 5V input tolerance unless $V_{CCI/O}$=5V) • Update to ET1200 stepping 1 • Added/revised OSC_IN, CLK25OUT, and MII TX signal timings • Added soldering profile • PHY address configuration changed • Added feature detail overview, removed redundant feature details • PDI and DC SYNC/LATCH signals are not driven until EEPROM is loaded • Editorial changes
1.2	• PHY address configuration chapter added, configuration revised • Enhanced link detection for MII available depending on PHY address configuration • Ethernet management interface: read and write times were interchanged • Editorial changes
1.3	• Added reset timing figure and power-on value sample time • Direction of distributed clocks SYNC/LATCH signals is configurable • Information on CLK25OUT/CPU_CLK clock output during reset added • Description of internal PU/PD resistors at EBUS_RX pins enhanced • Power supply example schematic clarified • Enhanced package information: MSL and plating material • Digital I/O PDI: added SOF/OUTVALID description • SPI PDI: read busy signaling not recommended • Editorial changes
1.4	• OSC_IN/OSC_OUT pin capacitance added, crystal connection note extended • Release Notes added • Input threshold voltage for OSC_IN added • Renamed Err(x) LED to PERR(x) • Digital I/O PDI: OE_CONF functionality in bidirectional mode corrected • Digital I/O PDI: output event description corrected (EOF mode and WD_TRIG mode) • SPI PDI: access error if SPI_DI not 1 in the last read byte (not SPI_DO) • AC timing: forwarding delay figures added • Editorial changes
1.5	• AC timing: forwarding delay figures MII to MII added • Reset timing figure corrected • Maximum soldering profile added • SPI PDI updated • SII EEPROM interface is a point-to-point connection • Editorial changes
1.6	• Update to ET1200-0002 • Editorial changes
1.7	• Enhanced link Detection must not be activated if EBUS ports are used • Enhanced link Detection for MII ports requires PHY address offset = 0 • Digital output principle schematic updated • Chip label updated • Editorial changes
1.8	• Update to ET1200-0003 • Enhanced link Detection for MII ports supports PHY address offset 0 and 16 • Enhanced link Detection for MII ports can be disabled at any time • Enhanced link Detection for EBUS ports is always disabled • PHY management interface issues additional MCLK cycle after write accesses • Remote link down signaling time configurable 0x0100[22] • Editorial changes

Version	Comment
2.0	• Added thermal characteristics • Added RoHS 2 compliance including amendment "COMMISSION DELEGATED DIRECTIVE (EU) 2015/863" • Clarified soldering temperature and time • Updated recommended power supply options • Editorial changes
2.1	• The ET1200 is not recommended for use in new designs • Added Tape and Reel information • Update chip label description • Editorial changes
2.2	• Improve SPI timing specification for t_{read} • Add absolute maximum input voltage range • Add $V_{Reset\ I/O}$ and $V_{Reset\ Core}$ min/max values • Editorial changes

CONTENTS

TABLES

FIGURES

ABBREVIATIONS

(x)	Logical Port x
[z]	Bit z
{y}	Physical Port y
µC	Microcontroller
ADR	Address
AL	Application Layer
BD	Bidirectional
BHE	Bus High Enable
CMD	Command
DC	Distributed Clock
Dir.	Pin direction
DL	Data Link Layer
ECAT	EtherCAT
EMC	Electromagnetic Compatibility
EMI	Electromagnetic Interference
EOF	End of Frame
EP	Exposed Pad
ESC	EtherCAT Slave Controller
ESI	EtherCAT Slave Information
FMMU	Fieldbus Memory Management Unit
GPI	General Purpose Input
GPO	General Purpose Output
I	Input
I/O	Input or Output
IRQ	Interrupt Request
LDO	Low Drop-Out regulator
LI-	LVDS RX-
LI+	LVDS RX+
LO-	LVDS TX-
LO+	LVDS TX+
MAC	Media Access Controller
MDIO	Management Data Input / Output
MI	(PHY) Management Interface
MII	Media Independent Interface
MISO	Master In – Slave Out
MOSI	Master Out – Slave In
n.a.	not available
n.c.	not connected
O	Output
PD	Pull-down
PDI	Process Data Interface
PLL	Phase Locked Loop
PU	Pull-up
QFN	Quad Flat package No leads
SII	Slave Information Interface
SM	SyncManager
SOF	Start of Frame
SPI	Serial Peripheral Interface
UI	Unused Input (PDI: PD, others: GND)
WD	Watchdog
WPD	Weak Pull-down, sufficient only for configuration signals
WPU	Weak Pull-up, sufficient only for configuration signals

1 Overview

The ET1200 is not recommended for use in new designs.

The ET1200 ASIC is an EtherCAT slave controller (ESC). It takes care of the EtherCAT communication as an interface between the EtherCAT fieldbus and the slave application. The ET1200 supports different applications, from simple digital I/O nodes without external logic up to designs with a µController and distributed clocks.

Table 1: ET1200 main features

Feature	ET1200
Ports	2 permanent ports, optional one additional bridge port (each EBUS or MII, max. one MII port)
FMMUs	3
SyncManagers	4
RAM	1 Kbyte
Distributed clocks	Yes, 64 bit
Process data interfaces	• 16 bit digital I/O (unidirectional/bidirectional) • SPI slave
Power supply	Two integrated voltage regulators (LDO) for I/O (5V to 3.3V) and logic core/PLL (5V/3.3V to 2.5V), optional external power supply for I/O and logic core/PLL.
I/O	3.3V compatible I/O
Package	QFN48 (7x7 mm²)
Other features	• Internal 1GHz PLL • Clock output for external devices (10, 20, 25 MHz)

The general functionality of the ET1200 EtherCAT slave controller (ESC) is shown in Figure 1:

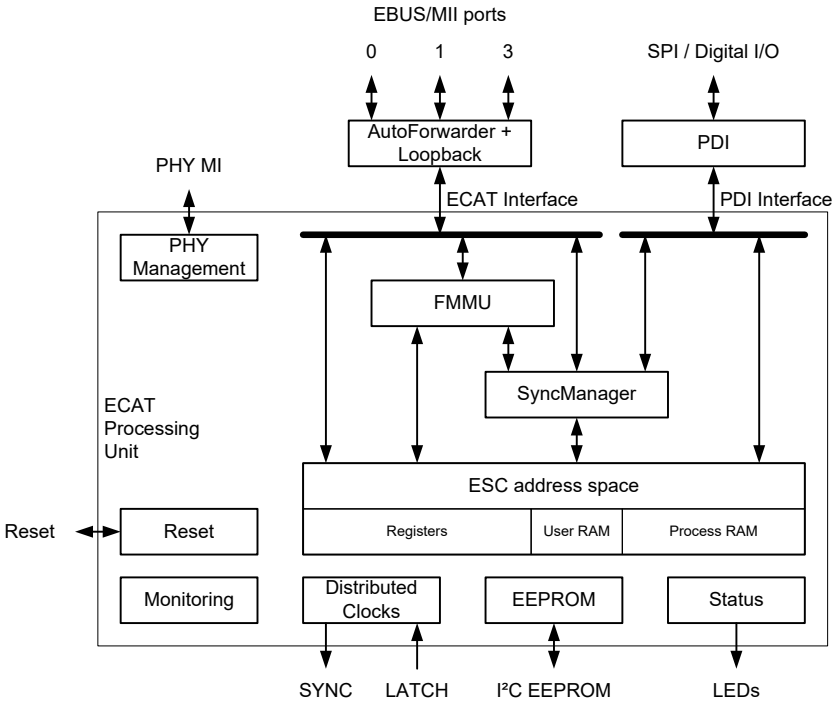

Figure 1: ET1200 block diagram

1.1 Frame processing order

The ET1200 supports two ports (logical ports 0 and 1) or three ports (logical ports 0, 1, and 3). The frame processing order of the ET1200 depends on the number of ports (logical port numbers are used):

Table 2: Frame processing order

Number of ports	Frame processing order
2	0→EtherCAT processing unit→1 / 1→0
3	0→EtherCAT processing unit→3 / 3→1 / 1→0

Figure 2 shows the frame processing in general:

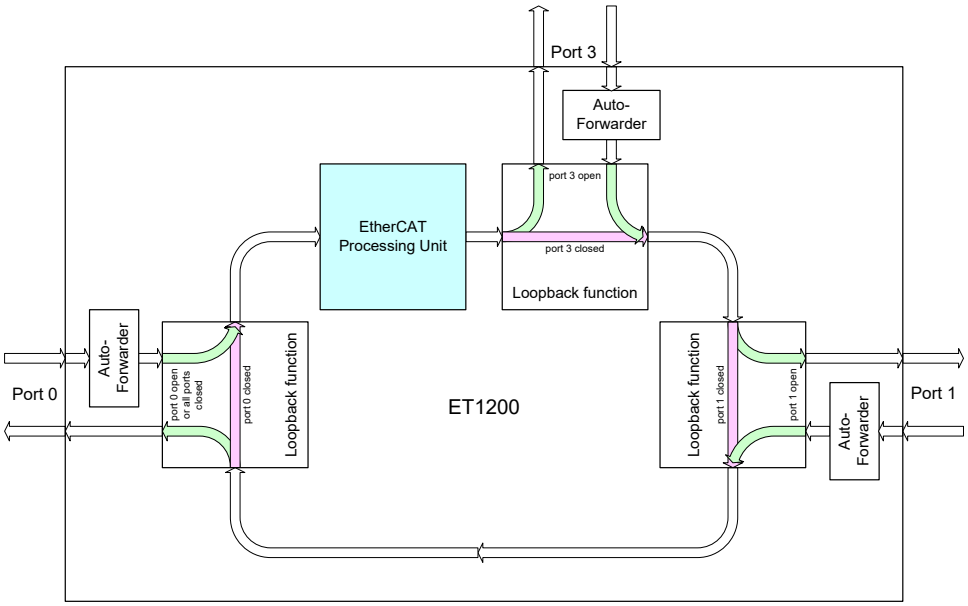

Figure 2: Frame processing

1.2 Scope of this document

This documentation refers to stepping ET1200-0003.

1.3 Revision/build history

Table 3: Revision/build history

Revision register 0x0001	Build register 0x0002:0x0003	Stepping
0x00	0x0000	ET1200-0000 or ET1200-0001
0x00	0x0002	ET1200-0002
0x00	0x0003	ET1200-0003

The stepping code is printed on the devices, do not confuse the stepping code with the ordering codes.

2 Features and registers

2.1 Features

Table 4: ET1200 feature details

Feature	ET1200 -0003
EtherCAT ports	**2-3**
Permanent ports	2
Optional bridge port 3 (EBUS or MII)	c
EBUS ports	1-3
MII ports	0-1
RMII ports	-
RGMII ports	-
Port 0	-
Ports 0, 1	x
Ports 0, 1, 2	-
Ports 0, 1, 3	x
Ports 0, 1, 2, 3	-
EtherCAT mode	Direct
Slave category	Full slave
Position addressing	x
Node addressing	x
Logical addressing	x
Broadcast addressing	x
Physical layer general features	
FIFO size configurable (0x0100[18:16])	x
FIFO size default from SII EEPROM	-
Auto-forwarder checks CRC and SOF	x
Forwarded RX error indication, detection and counter (0x0308:0x030B)	x
Lost link counter (0x0310:0x0313)	x
Prevention of circulating frames	x
Fallback: port 0 opens if all ports are closed	x
VLAN tag and IP/UDP support	x
Enhanced link detection per port configurable	-
EBUS features	
Low jitter	x
Enhanced link detection supported	-
Enhanced link detection compatible	x
EBUS signal validation	x
LVDS transceiver internal	x
LVDS current configuration	RBIAS
LVDS sample rate [MHz]	1,000
Remote link down signaling time configurable 0x0100[22]	x
General Ethernet features (MII/RMII/RGMII)	
PHY management interface (0x0510:0x051F)	x
Supported PHY address offsets	0/16
Individual port PHY addresses	-
Port PHY addresses readable	-
Link polarity configurable	-
Enhanced link detection supported	x
FX PHY support (native)	-
Fast hot connect support (native)	-
PHY reset out signals	-
Link detection using PHY signal (LED)	x
Link detection using RGMII in-band status	-
MI link status and configuration	-
User MI initialization values	-
MI controllable by PDI (0x0516:0x0517)	-
MI read error (0x0510[13])	-
MI PHY configuration update status (0x0518[5])	-
MI preamble suppression	-
Additional MCLK	x
Gigabit PHY configuration	-
Gigabit PHY register 9 detection	-
Clause 45 access	-
Transparent mode	-
MII features	
CLK25OUT as PHY clock source	x
Bootstrap TX shift settings	x
Automatic TX shift setting (with TX_CLK)	-
TX shift not necessary (PHY TX_CLK as clock source)	-
FIFO size reduction steps	1
MII back-to-back connections	x
PDI general features	
Internal PDI clock	25 MHz TD
Internal processing data bus width [bits]	8
Extended PDI configuration (0x0152:0x0153)	x
PDI error counter (0x030D)	-
PDI error code (0x030E:0x030F)	-
CPU_CLK output (10, 20, 25 MHz)	c
SOF, EOF, WD_TRIG and WD_STATE independent of PDI	-
Available PDIs and PDI features depending on port configuration	x
PDI selection at run-time (SII EEPROM)	x
PDI active immediately (SII EEPROM settings ignored)	-
PDI function acknowledge by write	-
PDI function acknowledge SyncManager/register independently	-
Digital I/O PDI	**x**
Digital I/O width [bits]	8/16
PDI control register value (0x0140:0x0141)	4
Control/status signals:	2/0[1]
LATCH_IN	x[1]
SOF	x[1]
OUTVALID	x[1]
WD_TRIG	x[1]
OE_CONF	-
OE_EXT	-
EEPROM_ Loaded	-
WD_STATE	-
EOF	-
OUT_START	-
Granularity of direction configuration [bits]	2
Bidirectional mode	x
Output high-Z if WD expired	x
Output 0 if WD expired	-
Output with EOF	x
Output with DC SyncSignals	x
Input with SOF	x
Input with DC SyncSignals	x
Digital I/O user mode from ECAT	-
Digital Input register	-
SPI slave PDI	**x**
Max. SPI clock [MHz]	6-20 (SPI mode dep.)
SPI modes configurable (0x0150[1:0])	x
SPI_IRQ driver configurable (0x0150[3:2])	x

[1] Availability depending on port configuration

Feature	ET1200 -0003
SPI_SEL polarity configurable (0x0150[4])	x
Data out sample mode configurable (0x0150[5])	x
Busy signaling	x
Wait state byte(s)	-
Number of address extension byte(s)	1
2/4 byte SPI master support	-
Extended error detection (read busy violation)	-
IRQ byte 0/1 swap	-
SPI user mode from PDI	-
SPI_IRQ delay	x
Status indication	x
EEPROM_ Loaded signal	x
Asynchronous µController PDI	**-**
Synchronous µController PDI	**-**
On-chip bus PDI	**-**
EtherCAT bridge (port 3, EBUS/MII)	**x**
Port open/closed configurable	-
General purpose I/O	**x**
GPO bits	0-12
GPI bits	-
GPIO available independent of PDI or port configuration	-
GPIO available without PDI	-
Concurrent access to GPO by ECAT and PDI	x
ESC information	
Basic information (0x0000:0x0006)	x
Port descriptor (0x0007)	x
ESC features supported (0x0008:0x0009)	x
Extended ESC feature availability in user RAM (0x0F80 ff.)	-
Write protection (0x0020:0x0031)	x
Data link layer features	
ECAT reset (0x0040)	x
PDI reset (0x0041)	-
ESC DL control (0x0100:0x0103) bytes	4
EtherCAT only mode (0x0100[0])	x
Temporary loop control (0x0100[1])	x
FIFO size configurable (0x0100[18:16])	x
Configured station address (0x0010:0x0011)	x
Configured station alias (0x0100[24], 0x0012:0x0013)	x
Physical read/write offset (0x0108:0x0109)	x
Application layer features	
Extended AL control/status bits (0x0120[15:5], 0x0130[15:5])	x
AL status emulation (0x0140[8])	x
AL status code (0x0134:0x0135)	x
Interrupts	
ECAT event mask (0x0200:0x0201)	x
AL event mask (0x0204:0x0207)	x
ECAT event request (0x0210:0x0211)	x
AL event request (0x0220:0x0223)	x
SyncManager activation changed (0x0220[4])	x
SyncManager watchdog expiration (0x0220[6])	-
DC SYNC interrupt	[1:0]
Error Counters	
RX error counter (0x0300:0x0307)	x
Forwarded RX error counter (0x0308:0x030B)	x
ECAT processing unit error counter (0x030C)	-
PDI error counter (0x030D)	-
Lost link counter (0x0310:0x0313)	x
Watchdog	
Watchdog divider configurable (0x0400:0x0401)	x
Watchdog process data	x
Watchdog PDI	x
Watchdog counter process data (0x0442)	x
Watchdog counter PDI (0x0443)	x

Feature	ET1200 -0003
SII EEPROM interface (0x0500:0x050F)	
I²C EEPROM sizes supported	1 Kbit-4 Mbit
I²C EEPROM size reflected in 0x0502[7]	x
EEPROM controllable by PDI	x
EEPROM emulation by PDI	-
EEPROM emulation CRC error 0x0502[11] PDI writable	-
Read data bytes (0x0502[6])	8
Internal pull-up resistors for EEPROM_CLK and EEPROM_DATA	x
ESC configuration area A	x
I2C base address	0
FMMUs	3
Bit-oriented operation	x
SyncManagers	4
Watchdog trigger generation for 1 byte Mailbox configuration independent of reading access	x
SyncManager event times (+0x8[7:6])	-
Buffer state (+0x5[7:6])	-
Distributed clocks	**x**
Width	64
Sync/Latch signals	1-2[2]
SyncManager event times (0x09F0:0x09FF)	-
DC receive times	x
DC time loop control controllable by PDI	-
DC sync/latch activation (0x0140[11:10])	-
Propagation delay measurement with traffic (BWR/FPWR 0x900 detected at each port)	-
LatchSignal state in latch status register (0x09AE:0x09AF)	-
SyncSignal auto-activation (0x0981[3])	-
SyncSignal 32 or 64 bit start time (0x0981[4])	-
SyncSignal late activation (0x0981[6:5])	-
SyncSignal debug pulse (0x0981[7])	-
SyncSignal activation state 0x0984)	-
Reset filters after writing filter depth	-
ESC specific registers (0x0E00:0x0EFF)	
Product and vendor ID	-
POR values	x
Process RAM and user RAM	
Process RAM (0x1000 ff.) [Kbyte]	1
User RAM (0x0F80:0x0FFF)	x
RAM initialization	-
Additional EEPROMs	1
SII EEPROM (I²C)	x
FPGA configuration EEPROM	-
LED signals	
RUN LED	x
RUN LED override	-
Link/activity(x) LED per port	x
PERR(x) LED per port	x
Device ERR LED	-
STATE_RUN LED	-
Optional LED states	
RUN LED: bootstrap	x
RUN LED: booting	-
RUN LED: device identification	-
RUN LED: loading SII EEPROM	-
RUN LED: POR values signaling	-
Error LED: SII EEPROM loading error	-
Error LED: invalid hardware configuration	-
Error LED: process data watchdog timeout	-
Error LED: PDI watchdog timeout	-

[2] SYNC/LATCH[1] available if no MII port is used.

Feature	ET1200 -0003
Error LED: BIST error	-
Error LED: error indication 0x0130[4]	-
Link/activity: port closed	-
Link/activity: local auto-negotiation error	-
Link/activity: remote auto-negotiation error	-
Link/activity: unknown PHY auto-negotiation error	-
LED test	-
Clock supply	
Crystal	x
Crystal oscillator	x
TX_CLK from PHY	x
25ppm clock source accuracy	x
Internal PLL	x
Power supply voltages	1-3
I/O voltages	
3.3 V	x
5 V	(x)

Feature	ET1200 -0003
Separate I/O voltages	-
Core voltage	2.5V
Internal regulators	2x LDO
Input voltage	3.3V/5V
Output core Voltage	x
Output I/O Voltage	3.3V
JTAG	-
Package	QFN48
Size [mm²]	7x7
Original release date	11/2006
Configuration and pinout calculator	x
Register configuration	fixed
Internal tri-state drivers	x

Table 5: Legend

Symbol	Description
x	available
-	not available
c	configurable

2.2 Register overview

An EtherCAT slave controller (ESC) has an address space of 64 Kbyte. The first block of 4 Kbyte (0x0000:0x0FFF) is dedicated for registers. The process data RAM starts at address 0x1000, its size is 1 Kbyte (end address 0x13FF).

Table 7 gives an overview of the available registers.

Table 6: Legend

Symbol	Description
x	Available
-	Not available
io	Available if digital I/O PDI is selected

Table 7: Register overview

Address	Length (byte)	Description	ET1200
0x0000	1	Type	x
0x0001	1	Revision	x
0x0002:0x0003	2	Build	x
0x0004	1	FMMUs supported	x
0x0005	1	SyncManagers supported	x
0x0006	1	RAM size	x
0x0007	1	Port descriptor	x
0x0008:0x0009	2	ESC features supported	x
0x0010:0x0011	2	Configured station address	x
0x0012:0x0013	2	Configured station alias	x
0x0020	1	Write register enable	x
0x0021	1	Write register protection	x
0x0030	1	ESC write enable	x
0x0031	1	ESC write protection	x
0x0040	1	ESC reset ECAT	x
0x0041	1	ESC reset PDI	-
0x0100:0x0101	2	ESC DL control	x
0x0102:0x0103	2	Extended ESC DL control	x
0x0108:0x0109	2	Physical read/write offset	x
0x0110:0x0111	2	ESC DL status	x
0x0120	5 bits [4:0]	AL control	x
0x0120:0x0121	2	AL control	x
0x0130	5 bits [4:0]	AL status	x
0x0130:0x0131	2	AL status	x
0x0134:0x0135	2	AL status Code	x
0x0138	1	RUN LED override	-
0x0139	1	ERR LED override	-
0x0140	1	PDI0 control	x

Address	Length (byte)	Description	ET1200
0x0141	1	ESC configuration A0	x
0x0150	1	PDI0 configuration	x
0x0151	1	DC sync/latch configuration	x
0x0152:0x0153	2	Extended PDI0 configuration	x
0x0158:0x0159	2	PDI0 user mode from ECAT	-
0x015C:0x015D	2	PDI0 user mode from PDI	-
0x0200:0x0201	2	ECAT event mask	x
0x0204:0x0207	4	PDI0 AL event mask	x
0x0210:0x0211	2	ECAT event request	x
0x0220:0x0223	4	AL event request	x
0x0300:0x0307	4x2	RX error counter[3:0]	x
0x0308:0x030B	4x1	Forwarded RX error counter[3:0]	x
0x030C	1	ECAT processing unit error counter	-
0x030D	1	PDI0 error counter	-
0x030E:0x030F	2	PDI0 error code	-
0x0310:0x0313	4x1	Lost link counter[3:0]	x
0x0400:0x0401	2	Watchdog divider	x
0x0410:0x0411	2	Watchdog time PDI0	x
0x0420:0x0421	2	Watchdog time process data	x
0x0440:0x0441	2	Watchdog status process data	x
0x0442	1	Watchdog counter process data	x
0x0443	1	Watchdog counter PDI0	x
0x0500:0x050F	16	SII EEPROM interface	x
0x0510:0x0515	6	PHY management interface	x
0x0516:0x0517	2	PHY management access state	-
0x0518:0x051B	4	PHY port status[3:0]	-
0x0600:0x06FC	16x13	FMMU[15:0]	3
0x0800:0x087F	16x8	SyncManager[15:0]	4

Address	Length (byte)	Description	ET1200
0x0900:0x090F	4x4	DC – receive times	x
0x0910:0x0917	8	DC – system time	x
0x0918:0x091F	8	DC – receive time EPU	x
0x0920:0x0927	8	DC – system time offset	x
0x0928:0x092B	4	DC – system time delay	x
0x092C:0x092F	4	DC – system time difference	x
0x0930:0x0931	2	DC – speed counter start	x
0x0932:0x0933	2	DC – speed counter diff	x
0x0934	1	DC – system time difference filter depth	x
0x0935	1	DC – speed counter filter depth	x
0x0936	1	DC – receive time latch mode	x
0x0980	1	DC – cyclic unit control	x
0x0981	1	DC – activation	x
0x0982:0x0983	2	DC – pulse length of SyncSignals	x
0x0984	1	DC – activation status	-
0x098E	1	DC – SYNC0 status	x
0x098F	1	DC – SYNC1 status	x
0x0990:0x0997	8	DC – start time cyclic operation/next SYNC0 pulse	x
0x0998:0x099F	8	DC – next SYNC1 pulse	x
0x09A0:0x09A3	4	DC – SYNC0 cycle time	x
0x09A4:0x09A7	4	DC – SYNC1 cycle time	x
0x09A8	1	DC – latch0 control	x
0x09A9	1	DC – latch1 control	x
0x09AE	1	DC – latch0 status	x
0x09AF	1	DC – latch1 status	x
0x09B0:0x09B7	8	DC – latch0 positive edge	x
0x09B8:0x09BF	8	DC – latch0 negative edge	x
0x09C0:0x09C7	8	DC – latch1 positive edge	x
0x09C8:0x09CF	8	DC – latch1 negative edge	x
0x09F0:0x09F3	4	DC – EtherCAT buffer change event time	-
0x09F8:0x09FB	4	DC – PDI buffer start event time	-
0x09FC:0x09FF	4	DC – PDI buffer change event time	-
0x0E00:0x0E07	8	Power-on values [bits]	8
0x0F00:0x0F03	4	Digital I/O output data	x
0x0F08:0x0F0B	4	Digital I/O input data	-
0x0F10:0x0F17	8	General purpose outputs [byte]	2
0x0F18:0x0F1F	8	General purpose inputs [byte]	-
0x0F80:0x0FFF	128	User RAM	x
0x1000:0x1003	4	Digital I/O input data	io
0x1000 ff.		Process data RAM [Kbyte]	1

3 Pin description

For pin configuration there is a table calculation file (ET1200 configuration and pinout V<version>.xls) available to make pin configuration easier. This file can be downloaded from the Beckhoff homepage (http://www.beckhoff.com). This documentation supersedes the table calculation file.

Input pins should not be left open/floating. Unused input pins (denoted with direction UI) without external or internal pull-up/pull-down resistor should not be left open. Unused configuration pins should be pulled down if the application allows this (take care of configuration signals in the PDI[17:0] area when bidirectional digital I/O is used). Unused PDI[17:0] input pins should be pulled down, all other input pins can be connected to GND directly.

Pull-up resistors must connect to $V_{CC\ I/O}$, not to a different power source. Otherwise the ET1200 could be powered via the resistors and the internal clamping diodes as long as $V_{CC\ I/O}$ is below the other power source.

Internal pull-up/pull-down resistor values shown in the pinout tables are nominal.

3.1 Overview

3.1.1 Pin overview

Table 8: Pin overview

Pin	Pin name	Dir.	Int. PU/PD	Pin	Pin name	Dir.	Int. PU/PD
EP	GND			25	RBIAS		
1	TESTMODE	I	WPD	26	Reset	BD	WPU
2	EBUS{1}-RX-/LINK_MII	LI-/I	27 kΩ PU	27	PDI[17]/RX_D[3]	BD	
3	EBUS{1}-RX+/RX_ERR	LI+/I	27 kΩ PD	28	PDI[16]/RX_D[2]	BD	
4	EBUS{0}-TX-	LO-		29	PDI[15]/RX_D[1]	BD	
5	EBUS{0}-TX+	LO+		30	PDI[14]/RX_D[0]	BD	
6	$V_{CC\ I/O}$	I/O		31	PDI[13]/RX_DV	BD	
7	$GND_{I/O}$	I/O*		32	PDI[12]/RX_CLK	BD	
8	EBUS{0}-RX-	LI-	27 kΩ PU	33	PDI[11]/TX_D[3]/C25_SHI[1]	BD	
9	EBUS{0}-RX+	LI+	27 kΩ PD	34	PDI[10]/TX_D[2]/C25_SHI[0]	BD	
10	EBUS{1}-TX-/MI_CLK	LO-/O		35	PDI[9]/TX_D[1]/C25_ENA	BD	
11	EBUS{1}-TX+/TX_ENA	LO+/O		36	PDI[8]/TX_D[0]/PHYAD_OFF	BD	
12	PERR(0)/CLK_MODE[0]	BD	WPD	37	PDI[7]/CPU_CLK	BD	
13	PERR(1)/CLK_MODE[1]	BD	WPD	38	PDI[6]/CLK25OUT	BD	
14	V_{CC}			39	PDI[5]	BD	
15	GND			40	PDI[4]	BD	
16	LINKACT(0)/MODE[0]	BD	WPD	41	$V_{CC\ Core}$ (2,5V)		
17	LINKACT(1)/MODE[1]	BD	WPD	42	GND_{Core}		
18	RUN/EEPROM_SIZE	BD	WPD	43	PDI[3]	BD/LI-	27 kΩ PU
19	EEPROM_CLK	BD	3.3 kΩ PU	44	PDI[2]	BD/LI+	27 kΩ PD
20	EEPROM_DATA	BD	3.3 kΩ PU	45	PDI[1]	BD/LO-	
21	OSC_IN	I		46	PDI[0]	BD/LO+	
22	OSC_OUT	O		47	SYNC/LATCH[0]	BD	
23	GND_{PLL}			48	SYNC/LATCH[1]/MI_DATA	BD	
24	Vcc_{PLL} (2,5V)						

NOTE: Pin EP is the exposed center pad at the bottom of the ET1200.

3.1.2 Signal overview

Table 9: Signal overview

Signal	Type	Dir.	Description
C25_ENA	Configuration	I	CLK25OUT enable
C25_SHI[1:0]	Configuration	I	TX shift: shifting/phase compensation of MII TX signals
CLK_MODE[1:0]	Configuration	I	CPU_CLK configuration
CLK25OUT	MII	O	25 MHz clock source for Ethernet PHY
CPU_CLK	PDI	O	Clock signal for µController
EBUS{1:0}-RX-	EBUS	LI-	EBUS LVDS receive signal -
EBUS{1:0}-RX+	EBUS	LI+	EBUS LVDS receive signal +
EBUS{1:0}-TX-	EBUS	LO-	EBUS LVDS transmit signal -
EBUS{1:0}-TX+	EBUS	LO+	EBUS LVDS transmit signal +
EEPROM_CLK	EEPROM	BD	EEPROM I^2C clock
EEPROM_DATA	EEPROM	BD	EEPROM I^2C data
EEPROM_SIZE	Configuration	I	EEPROM size configuration
PERR(1:0)	LED	O	Port receive error LED output (for testing)
GND	Power		Ground
GND_{Core}	Power		Core logic ground
$GND_{I/O}$	Power		I/O ground
GND_{PLL}	Power		PLL ground
LINK_MII(1:0)	MII	I	PHY signal indicating a link
LINKACT(1:0)	LED	O	Link/activity LED output
MI_CLK	MII	O	PHY management interface clock
MI_DATA	MII	BD	PHY management interface data
MODE[1:0]	Configuration	I	Chip mode, port configuration
OSC_IN	Clock	I	Clock source (crystal/oscillator)
OSC_OUT	Clock	O	Clock source (crystal)
PDI[17:0]	PDI	BD	PDI signal, depending on EEPROM content
PHYAD_OFF	Configuration	I	Ethernet PHY address offset
RBIAS	EBUS		BIAS resistor for LVDS TX current adjustment
RESET	General	BD	Open collector reset output/reset input
RUN	LED	O	Run LED controlled by AL status register
RX_CLK	MII	I	MII receive clock
RX_D[3:0]	MII	I	MII receive data
RX_DV	MII	I	MII receive data valid
RX_ERR	MII	I	MII receive error
SYNC/LATCH[1:0]	DC	I/O	Distributed clocks SyncSignal output or LatchSignal input
TESTMODE	General	I	Reserved for testing, connect to GND
TX_D[3:0]	MII	O	MII transmit data
TX_ENA	MII	O	MII transmit enable
V_{CC}	Power		Device power (LDO input)
$V_{CC\ Core}$	Power		Core logic power
$V_{CC\ I/O}$	Power		I/O power
$V_{CC\ PLL}$	Power		PLL power

3.1.3 PDI signal overview

Table 10: PDI signal overview

PDI	Signal	Dir.	Description
Digital I/O	I/O[15:0]	I/O/BD	Input/output or bidirectional data
	LATCH_IN/SOF	I/O	External data latch signal/start of frame
	OUTVALID/WD_TRIG	O	Output data is valid/output event/ watchdog trigger
SPI slave	EEPROM_LOADED	O	PDI is active, EEPROM is loaded
	SPI_CLK	I	SPI clock
	SPI_DI	I	SPI data MOSI
	SPI_DO	O	SPI data MISO
	SPI_IRQ	O	SPI interrupt
	SPI_SEL	I	SPI chip select
EBUS bridge	EBUS(3)-RX-	LI-	EBUS LVDS receive signal -
	EBUS(3)-RX+	LI+	EBUS LVDS receive signal +
	EBUS(3)-TX-	LO-	EBUS LVDS transmit signal -
	EBUS(3)-TX+	LO+	EBUS LVDS transmit signal +
	PERR(3)	O	Error LED output (for testing)
	LINKACT(3)	O	Link/activity LED output
	GPO[11:0]	O	General purpose output
MII bridge	TX_D(3)[3:0]	O	MII transmit data
	TX_ENA(3)	O	MII transmit enable
	RX_CLK(3)	I	MII receive clock
	RX_D(3)[3:0]	I	MII receive data
	RX_DV(3)	I	MII receive data valid
	RX_ERR(3)	I	MII receive error
	LINK_MII(3)	I	PHY signal indicating a link
	LINKACT(3)	O	Link/activity LED output
	PERR(3)	O	Error LED output (for testing)
	GPO[1]	O	General purpose output
	MI_CLK	O	PHY management interface clock
	CLK25OUT	O	25 MHz clock source for Ethernet PHY

3.2 Power supply

The ET1200 supports different power supply and I/O voltage options with 3.3V (or 5V I/O, not recommended) and optionally single or dual power supply.

The $V_{CCI/O}$ supply voltage directly determines the I/O voltages for all inputs and outputs, i.e., with 3.3V $V_{CCI/O}$, the inputs are 3.3V I/O compliant and they are not 5V tolerant ($V_{CCI/O}$ has to be 5V if 5V tolerant I/Os are required).

Two internal LDOs generate the I/O supply voltage $V_{CC\ I/O}$ (nom. 3.3V) and the core supply voltages $V_{CC\ Core}$/$V_{CC\ PLL}$ (nom. 2.5V) from the ET1200 power supply input V_{CC}. V_{CC} must be equal or greater than $V_{CC\ I/O}$, and $V_{CC\ PLL}$ is always equal to $V_{CC\ Core}$. The internal LDOs cannot be switched off, they stop operating if the external supply voltage is higher than the internal LDO output voltage, thus external supply voltages have to be higher (at least 0.1V) than the internal LDO output voltages.

Using the internal LDOs increases power dissipation, and power consumption for 5V I/O voltage is significantly higher than power consumption for 3.3V I/O. It is highly recommended to use 3.3V I/O voltage and the internal LDO for $V_{CC\ Core}$/$V_{CC\ PLL}$.

For 3.3V I/O with external 3.3V power supply, both V_{CC} and $V_{CCI/O}$ have to be connected to the external 3.3V supply voltage, and for 5V I/O voltage, both V_{CC} and $V_{CCI/O}$ have to be connected to the external 5V supply voltage.

Voltage stabilization capacitors at all power pairs are necessary.

Table 11: Power supply options (all voltages nominal)

V_{CC}	$V_{CC\ I/O}$	$V_{CC\ Core}$/$V_{CC\ PLL}$	Input signals	Output signals	Comment
3.3V	External 3.3V (= V_{CC})	Internal LDO (2.5V)	3.3V only	3.3V only	Single power supply, low power dissipation
5V	Internal LDO (3.3V)	Internal LDO (2.5V)	3.3V only	3.3V only	Single power supply, highest power dissipation due to LDO for $V_{CC\ I/O}$
Not recommended for future compatibility:					
3.3V	External 3.3V (= V_{CC})	External 2.5V	3.3V only	3.3V only	Dual power supply, lowest power dissipation.
5V	Internal LDO (3.3V)	External 2.5V	3.3V only	3.3V only	Dual power supply.
5V	External 5V (= V_{CC})	Internal LDO (2.5V)	5V only	5V only	Single power supply, high power dissipation
5V	External 5V (= V_{CC})	External 2.5V	5V only	5V only	Dual power supply, high power dissipation

Table 12: Power supply pins

Pin	Pin name
EP	GND
14	V_{CC}
15	GND
6	$V_{CC\ I/O}$
7	$GND_{I/O}$
41	$V_{CC\ Core}$ (2.5V)
42	GND_{Core}
24	$V_{CC\ PLL}$ (2.5V)
23	GND_{PLL}

3.2.1 Example schematics for power supply

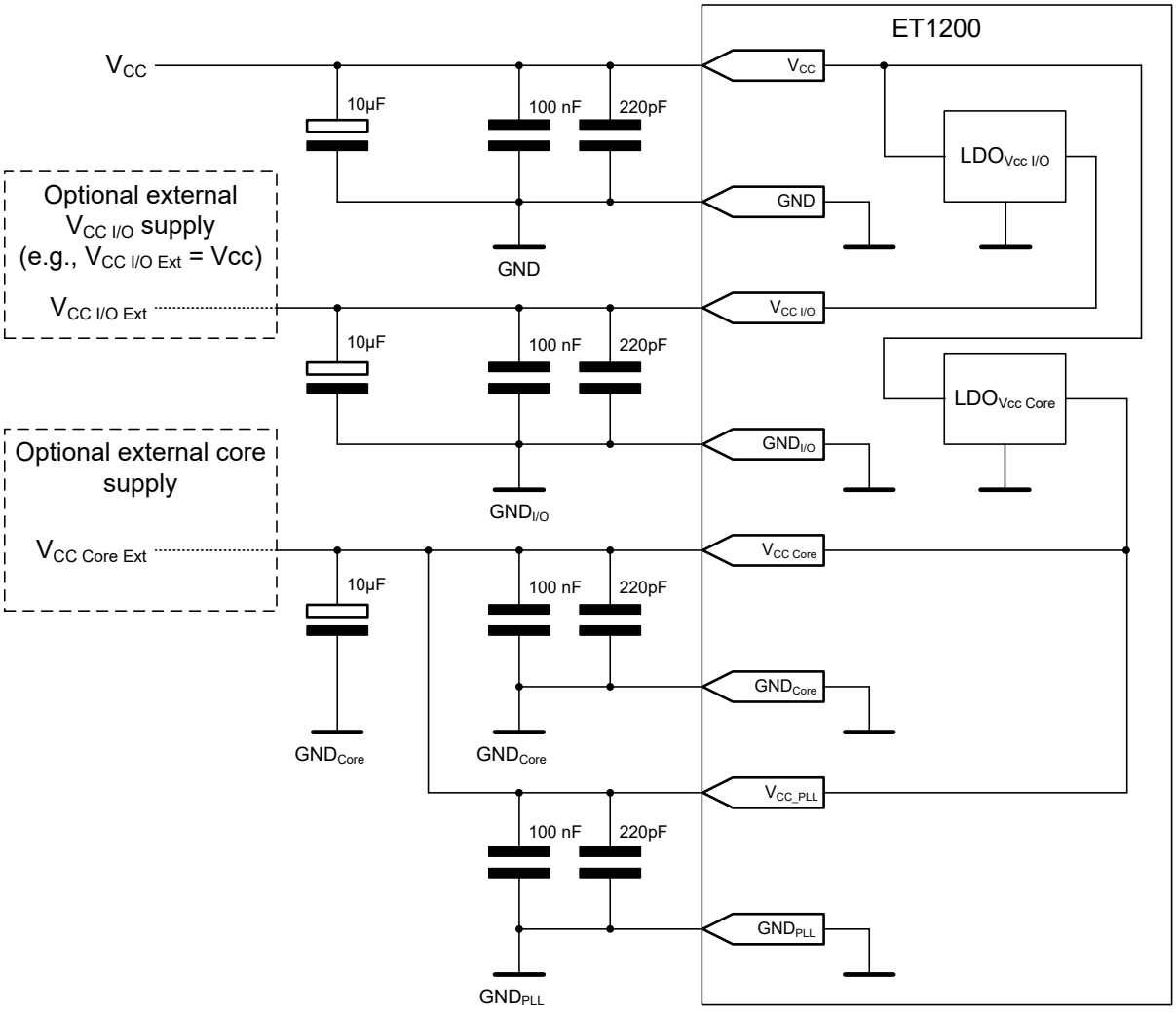

Figure 3: ET1200 power supply

Recommendation for voltage stabilization capacitors: 220pF and 100nF ceramic capacitors for each power pin pair, additional 10µF capacitor for V_{CC}, $V_{CC\ I/O}$, and $V_{CC\ Core}$/$V_{CC\ PLL}$, i.e., a total of three 10µF capacitors.

GND, $GND_{I/O}$, GND_{Core}, and GND_{PLL} can be connected to a single GND potential.

The internal LDOs are self-deactivating if the actual $V_{CCI/O}$ or VCC_{Core}/$V_{CC\ PLL}$ voltage is higher than the respective nominal LDO output voltage.

3.3 Clock supply

Table 13: Clock supply pins

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
21	OSC_IN	I	OSC_IN	I		
22	OSC_OUT	O	OSC_OUT	O		

OSC_IN
Connection to external crystal or oscillator input (25 MHz). An oscillator as the clock source for both ET1200 and the Ethernet PHY is mandatory if an MII port is used and CLK25OUT cannot be used as the clock source for the PHY. The 25 MHz clock source should have an initial accuracy of 25ppm or better (at room temperature).

OSC_OUT
Connection to external crystal. Should be left open if an oscillator is connected to OSC_IN.

3.3.1 Example schematics for clock supply

The layout of the clock source has the biggest influence on EMC/EMI of a system design.

Although a clock frequency of 25 MHz requires not extensive design efforts, the following rules shall help to improve system performance:

- Keep clock source and ESC as close as possible close together.
- Ground Layer should be seamless in this area.
- Power supply should be of low impedance for clock source and ESC clock supply.
- Capacitors shall be used as recommended by the clock source component.
- Capacities between clock source and ESC clock supply should be in the same size (values depend upon geometrical form of board).

The initial accuracy of the ET1200 clock source has to be 25ppm or better.

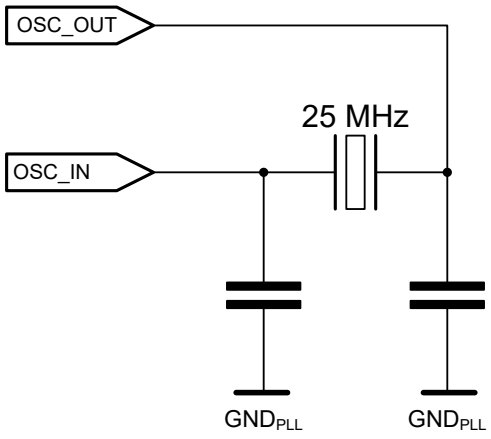

Figure 4: Quartz crystal connection

NOTE: The value of the load capacitors depends on the load capacitance of the crystal, the pin capacitance C_{OSC} of the ESC pins and the board design (typical 12pF each if C_L = 10pF).

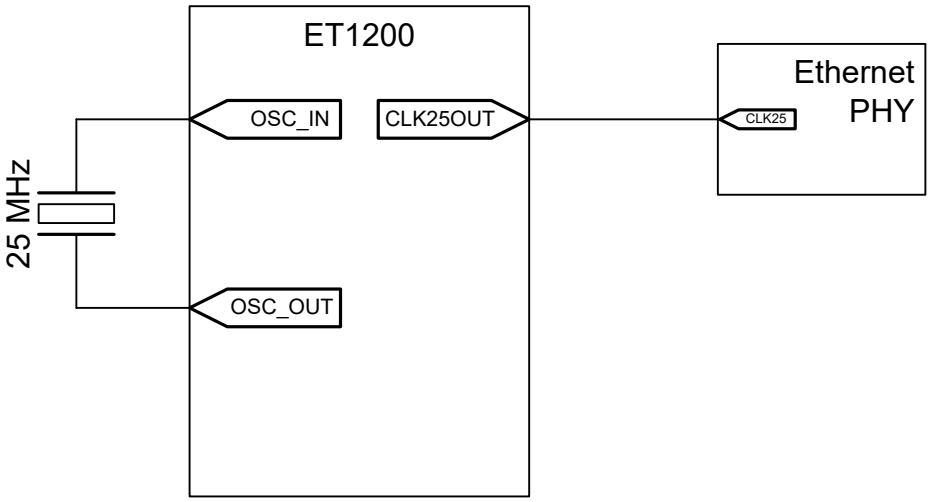

Figure 5: Quartz crystal clock source for ET1200 and Ethernet PHYs

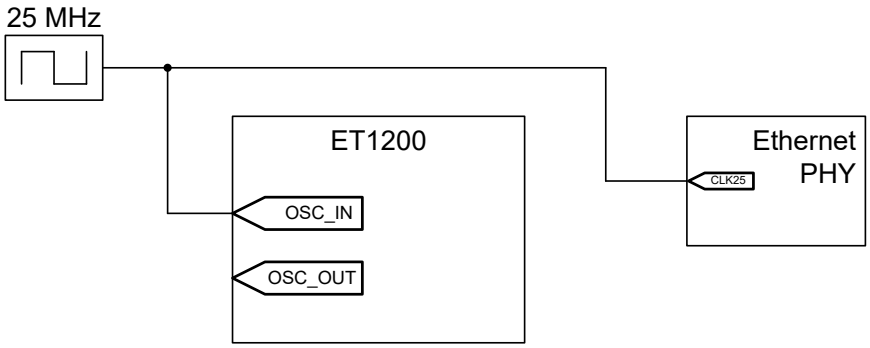

Figure 6: Oscillator clock source for ET1200 and Ethernet PHYs

3.4 Reset pin

Table 14: Reset pin

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
26	RESET	BD	RESET	BD		WPU

RESET
The open collector RESET input/output (active low) signals the reset state of ET1200. The reset state is entered at power-on, if the power supply is to low, or if a reset was initiated using the reset register 0x0040. ET1200 also enters reset state if RESET pin is held low by external devices.

3.4.1 Internal reset logic and example schematic for RESET pin

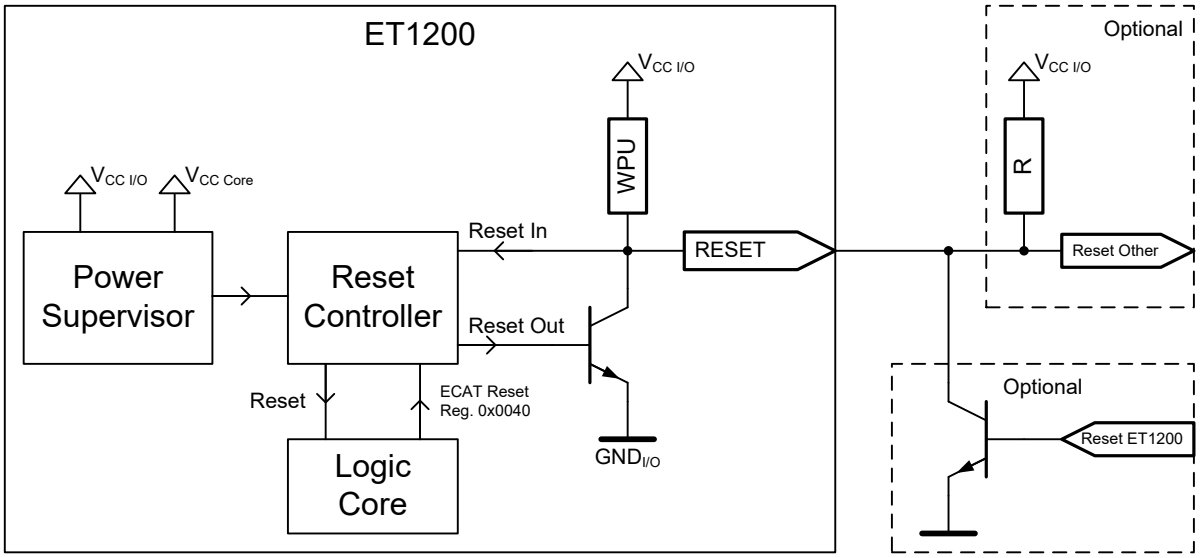

Figure 7: Reset logic

It is recommended to connect the PHYs and the µController to the RESET pin. This makes sure that the PHYs are not communicating while the ET1200 is in reset (lost frames), and it allows for resetting the whole EtherCAT slave device via EtherCAT in case of an unintended condition.

3.5 RBIAS pin

Table 15: RBIAS pin

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
25	RBIAS		RBIAS			

RBIAS
Bias resistor for LVDS TX current adjustment, should be 11 kΩ connected to GND.

3.5.1 Example schematic for RBIAS resistor

The LVDS RBIAS resistor should have a value of R_{BIAS}=11 kΩ.

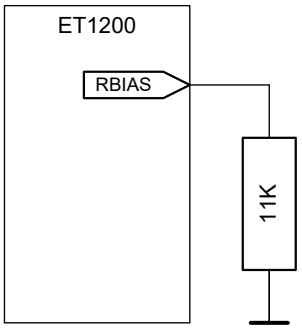

Figure 8: RBIAS resistor

3.6 Configuration pins

The configuration pins are used to configure the ET1200 at power-on with pull-up or pull down resistors. At power-on the ET1200 uses these pins as inputs to latch the configuration[3]. After power-on, the pins have their operation functionality which has been assigned to them, and therefore pin direction changes if necessary. The power-on phase finishes before the nRESET pin is released. In subsequent reset phases without power-on condition, the configuration pins still have their operation functionality, i.e., the ET1200 configuration is not latched again and output drivers remain active.

The configuration value 0 is realized by a pull-down resistor, a pull-up resistor is used for a 1. Since some configuration pins are also used as LED outputs, the polarity of the LED output depends on the configuration value.

3.6.1 Example schematics for configuration input/LED output pins

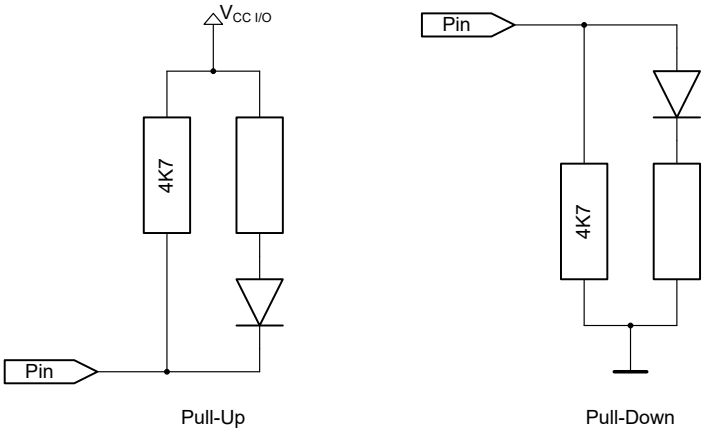

Figure 9: Dual purpose configuration input/LED output pins

[3] Take care of proper configuration: external devices attached to dual-purpose configuration pins might interfere sampling the intended configuration if they are e.g. not properly powered at the sample time (external device keeps configuration pin low although a pull-up resistor is attached). In such cases the ET1200 power-on value sampling time can be delayed by delaying power activation.

3.6.2 Chip mode

Chip mode configures the type of the two permanent ports 0 and 1. It is shown in Table 16. The chip mode affects the number of available PDI signals.

Chip mode is shown in Table 16.

Table 16: Chip mode

Description	Config signal	Pin name	Register	MODE[1:0] Values
Chip mode	MODE[0]	LINKACT(0)/MODE[0]	0x0E00[0]	00 = EBUS/EBUS (port 0 = EBUS, port 1 = EBUS) 01 = reserved 10 = MII/EBUS (port 0 = MII, port 1 = EBUS) 11 = EBUS/MII (port 0 = EBUS, port 1 = MII)
	MODE[1]	LINKACT(1)/MODE[1]	0x0E00[1]	

3.6.3 CPU_CLK MODE

CLK_MODE is used to provide a clock signal to an external microcontroller. If CLK_MODE is not 00, CPU_CLK is available on PDI[7], thus this pin is not available for PDI signals anymore.

The CPU_CLK MODE is shown in Table 17.

Table 17: CPU_CLK mode

Description	Config signal	Pin name	Register	Values
CPU_CLK MODE	CLK_MODE[0]	PERR(0)/CLK_MODE[0]	0x0E00[2]	00 = off, PDI[7]/CPU_CLK available for PDI 01 = 25 MHz clock output at PDI[7]/CPU_CLK 10 = 20 MHz clock output at PDI[7]/CPU_CLK 11 = 10 MHz clock output at PDI[7]/CPU_CLK
	CLK_MODE[1	PERR(1)/CLK_MODE(1)	0x0E00[3]	

3.6.4 TX shift

Phase shift (0/10/20/30ns) of MII TX signals (TX_ENA, TX_D[3:0]) can be attained via the C25_SHI[x] signals. TX shift settings are explained in Table 18. It is recommended to support all C25_SHI[1:0] configurations by hardware options to enable later adjustments.

Table 18: TX shift

Description	Config signal	Pin name	Register	Values
TX shift	C25_SHI[0]	PDI[10]/TX_D[2]/C25_SHI[0]	0x0E00[4]	00 = MII TX signals not delayed 01 = MII TX signals delayed by 10 ns 10 = MII TX signals delayed by 20 ns 11 = MII TX signals delayed by 30 ns
	C25_SHI[1]	PDI[11]/TX_D[3]/C25_SHI[1]	0x0E00[5]	

3.6.5 CLK25OUT enable

A 25MHz clock for the Ethernet PHY can be made available by the ET1200 on pin PDI[6]. This is only relevant for MODE 10 or 11. For MODE 00 with MII bridge port 3, CLK25OUT is available at PDI[6] anyway. CLK25OUT is not available in MODE 00 if MII bridge port 3 is not configured, CLK25OUT enable is ignored.

CLK_25OUT enable is explained in Table 19.

Table 19: CLK_25OUT enable

Description	Config signal	Pin name	Register	Values
CLK25OUT enable	C25_ENA	PDI[9]/TX_D[1]/C25_ENA	0x0E00[6]	0 = disable, PDI[6]/CLK25OUT is available for PDI 1 = enable, PDI[6]/CLK25OUT is 25 MHz clock output (MODE 10/11 only)

3.6.6 PHY address offset

The ET1200 supports two PHY address offset configurations, either 0 or 16. Refer to chapter 4.2 for details on PHY address configuration.

PHY address offset is explained in Table 20.

Table 20: PHY address offset

Description	Config signal	Pin name	Register	Values
PHY address offset	PHYAD_OFF	PDI[8]/TX_D[0]/PHYAD_OFF	0x0E00[7]	0 = PHY address offset 0 1 = PHY address offset 16

3.6.7 SII EEPROM size

EEPROM_SIZE determines the size of the EEPROM (and the number of I²C address bytes). EEPROM_SIZE is sampled at the beginning of the EEPROM access. EEPROM_ SIZE is shown in Table 21.

Table 21: SII EEPROM size

Description	Config signal	Pin name	Register	Values
EEPROM size	EEPROM_SIZE	RUN/EEPROM_SIZE	0x0502[7]	0 = 1 address byte (1 Kbit to 16 Kbit EEPROM) 1 = 2 address bytes (32 Kbit to 4 Mbit EEPROM)

3.7 SII EEPROM interface pins

Table 22: SII EEPROM pins

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
19	EEPROM_CLK	BD	EEPROM_CLK	BD		3.3 kΩ PU
20	EEPROM_DATA	BD	EEPROM_DATA	BD		3.3 kΩ PU

EEPROM_CLK
EEPROM I²C clock signal (open collector output).

EEPROM_DATA
EEPROM I²C data signal (open collector output).

3.8 Distributed clocks SYNC/LATCH pins, PHY management data

Table 23: DC SYNC/LATCH and PHY management pins

Pin	Pin		No MII port used		MII port used		Configuration	Internal PU/PD
	Name	Dir	Signal	Dir	Signal	Dir		
47	SYNC/LATCH[0]	BD	SYNC/LATCH[0]	I/O	SYNC/LATCH[0]	I/O		
48	SYNC/LATCH[1]/MI_DATA	BD	SYNC/LATCH[1]	I/O	MI_DATA	BD		

SYNC/LATCH[x]/MI_DATA
SYNC/LATCH[x] are distributed clocks SyncSignal output or LatchSignal input, depending on SII EEPROM configuration. If an MII port is used, SYNC/LATCH[1]/MI_DATA becomes MI_DATA, which is the Ethernet PHY management interface data signal. SYNC/LATCH signals are not driven (high impedance) until the EEPROM is loaded (MI_DATA is independent of the EEPROM loaded state).

NOTE: MI_DATA must have a pull-up resistor (4.7kΩ recommended for ESCs).

3.9 LED signals

All LED signals are also used as configuration signals. The polarity of each LED signal depends on the configuration: LED is active high if pin is pulled down for configuration, and active low if pin is pulled up. Refer to the chapter 3.6.1 for LED connection details.

Table 24: LED pins

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
18	RUN/EEPROM_SIZE	BD	RUN	O	EEPROM_SIZE	WPD
16	LINKACT(0)/MODE[0]	BD	LINKACT(0)	O	MODE[0]	WPD
12	PERR(0)/CLK_MODE[0]	BD	PERR(0)	O	CLK_MODE[0]	WPD
17	LINKACT(1)/MODE[1]	BD	LINKACT(1)	O	MODE[1]	WPD
13	PERR(1)/CLK_MODE[1]	BD	PERR(1)	O	CLK_MODE[1]	WPD

RUN/EEPROM_SIZE
SII EEPROM_SIZE configuration (either 1 Kbit-16 Kbit or 32 Kbit-4 Mbit) sampled at the beginning of the EEPROM access. RUN is active high if pin is pulled down, and active low if pin is pulled up. RUN LED should be green.

LINKACT(x)/MODE(x)
Chip mode configuration pin at power-on, link/activity LED output (off=no link, on=link without activity, blinking=link and activity) for logical port x afterwards. LINKACT(x) is active high if pin is pulled down, and active low if pin is pulled up. Link/activity LED should be green.

PERR(x)/CLK_MODE(x)
CPU_CLK mode configuration pin at power-on, Error LED output for logical port x afterwards. PERR(x) is active high if pin is pulled down, and active low if pin is pulled up.

NOTE: PERR(x) LEDs are not part of the EtherCAT indicator specification. They are only intended for testing and debugging. The PERR(x) LED flashes once if a physical layer receive error occurs. Do not confuse PERR(x) LEDs with application layer ERR LED, this is not supported by the ESCs and has to be controlled by a µController.

3.10 Physical ports and PDI pins

The ET1200 pin out is optimized in order to achieve an optimum of size and features. To obtain this, there is a number of pins where either communication or PDI functionality can be assigned to, depending on the chip mode. The selected chip mode might reduce PDI possibilities

The ET1200 has 18 PDI pins, PDI[17:0]. They are structured in two groups: PDI[7:0] and PDI[17:8]. PDI[7:0] are always available for PDI signals, PDI[17:8] are available for PDI signals in MODE 00, in MODE 10/11 they are used for MII signals.

Possible chip mode / PDI combinations

Table 25: Combinations of chip modes and PDIs

Chip mode	SPI slave	Digital I/O	EBUS bridge (log. port 3)	MII bridge (log. port 3)
MODE 00	SPI slave +12 bit GPO	16 bit I/O + control/status signals	EBUS bridge +12 bit GPO	MII bridge +CLK25OUT +1 bit GPO
MODE 10/11	SPI slave +12 bit GPO	8 bit I/O	EBUS bridge +2 bit GPO	Not available

3.10.1 MII signals

LINK_MII(x)
Input signal provided by the PHY if a 100 Mbit/s (full duplex) link is established. LINK_MII(x) is active low.

RX_CLK(x)
MII receive clock.

RX_DV(x)
MII receive data valid. There is an internal 27K pull up resistor at RX_DV(x) inside the ET1100.

RX_D(x)[3:0]
MII receive data. There is an internal 27K pull down resistor at RX_D(x)[1] inside the ET1100.

RX_ERR(x)
MII receive error.

TX_ENA(x)
MII transmit enable output.

TX_D(x)[3:0]
MII transmit data.

MI_CLK
PHY management interface clock.

3.10.1.1 CLK25OUT signal

The ET1200 has to provide an Ethernet PHY with a 25 MHz clock signal (CLK25OUT) if a 25 MHz crystal is used for clock generation. In case a 25 MHz oscillator is used, CLK25OUT is not necessary, because the Ethernet PHY and the ET1200 can share the oscillator output. CLK25OUT is not available at PDI[6]/CLK25OUT in chip mode 00 unless the MII bridge port is configured via SII EEPROM. With the MII bridge port, CLK25OUT is available regardless of C25ENA. For chip modes 10/11, PDI[7] may be configured to deliver CLK25OUT by pulling up the PDI[9]/TX_D[1]/C25ENA configuration signal.

CLK25OUT provides a clock signal – if configured – during external or ECAT reset, clock output is only turned off during power-on reset.

3.10.1.2 Example schematic for MII connection

Refer to chapter 3.10.1 for more information on special markings (!). Take care of proper configuration of TX shift and PHY addresses.

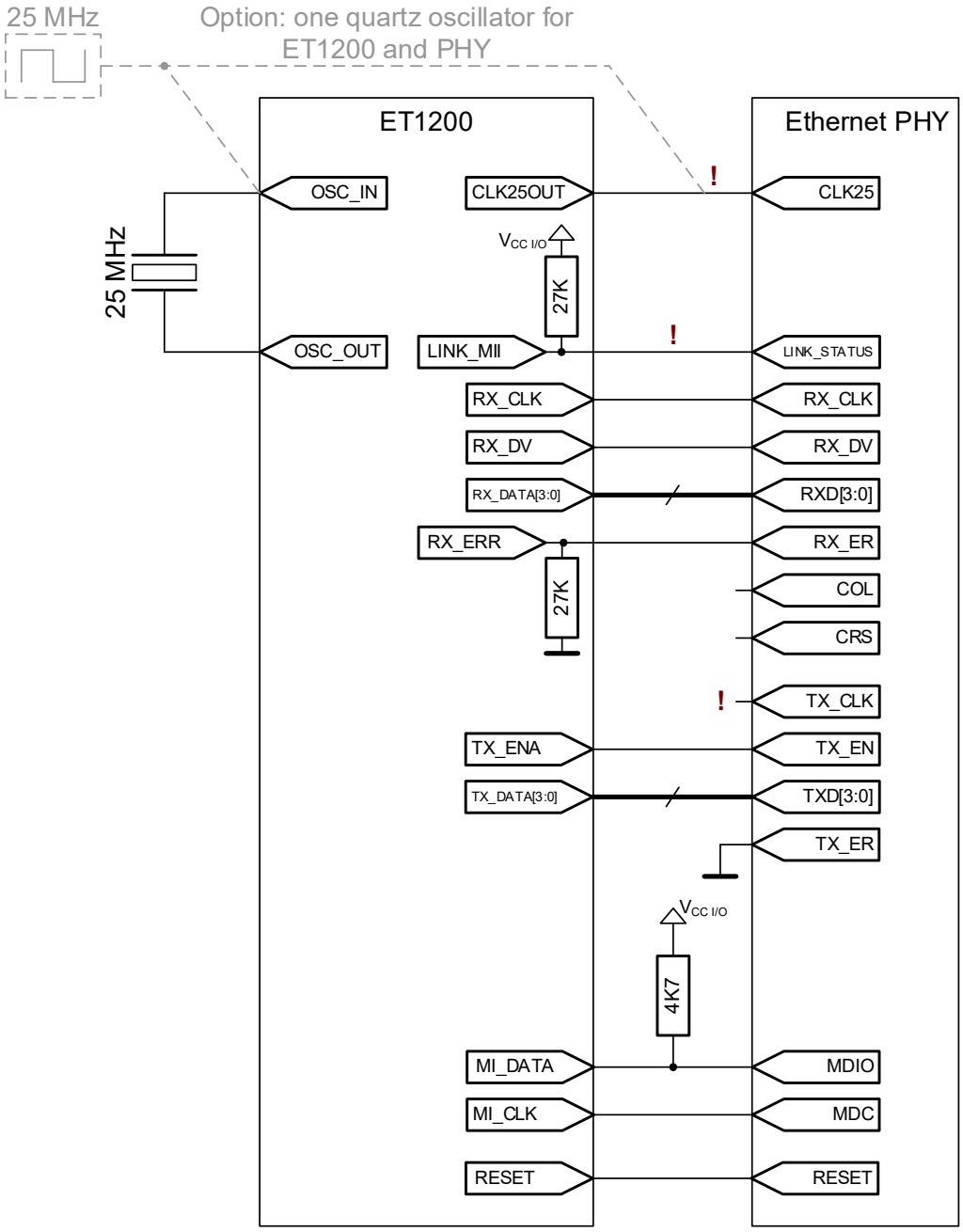

Figure 10: PHY connection

3.10.2 EBUS signals

The EBUS ports of the ET1200 are open failsafe, i.e., the ET1200 detects if an EBUS port is unconnected and closes the port internally (no physical link).

EBUS(x)-RX+/EBUS(x)-RX-
EBUS LVDS receive signals. EBUS_RX+ pins incorporate a pull-down resistor R_{LI+} and EBUS_RX- pins incorporate a pull-up resistor R_{LI-}, even if the pins are not configured for EBUS.

EBUS(x)-TX+/EBUS(x)-TX-
EBUS LVDS transmit signals.

3.10.2.1 Example schematic for EBUS termination

The LVDS termination with an impedance of 100 Ω is typically achieved by a resistor R_L=100 Ω. It is only necessary for EBUS ports and should be placed adjacent to the EBUS_RX inputs.

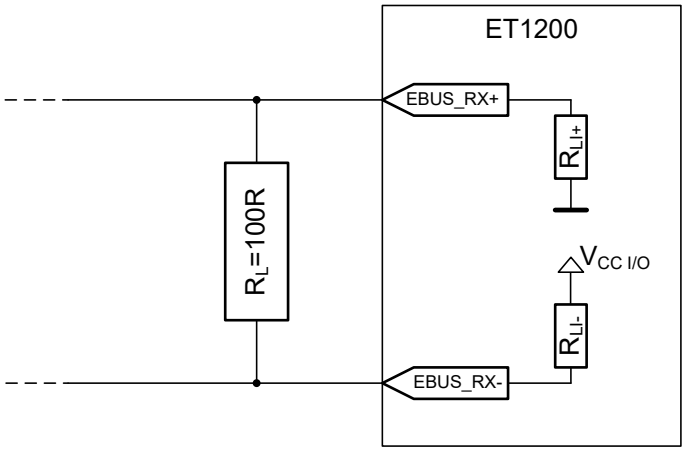

Figure 11: LVDS termination

3.10.3 PDI pins

PDI[x]

The function of PDI[x] signals depends on the configuration stored in the device SII EEPROM. PDI signals are not driven (high impedance) until the EEPROM is loaded. This has to be taken into account especially for digital outputs.

PDI signals are not driven (high impedance) if no PDI is configured (PDI control register 0x0140=0x00).

CPU_CLK

The ET1200 can provide a clock signal for µControllers on pin PDI[7]/CPU_CLK. The CPU_CLK output setting is controlled by the CLK_MODE configuration pin. If CPU_CLK is enabled, PDI[7] is not available for the PDI, i.e., I/O[7] is not available for digital I/O PDI.

CPU_CLK provides a clock signal – if configured – during external or ECAT reset, clock output is only turned off during power-on reset.

3.10.4 Port 0/1 and PDI[17:8] pins

Table 26 and Table 27 show the port 0/1 and PDI signals used for ports 0 and 1.

Table 26: Port 0/1 and PDI signals (configuration and chip mode 00)

Pin	Pin		Configuration	MODE[1:0]=00		Internal PU/PD
	Name	Dir		Signal	Dir.	
36	PDI[8]/TX_D[0]/PHYAD_OFF	BD	PHYAD_OFF	PDI[8]	BD	
35	PDI[9]/TX_D[1]/C25_ENA	BD	C25_ENA	PDI[9]	BD	
34	PDI[10]/TX_D[2]/C25_SHI[0]	BD	C25_SHI[0]	PDI[10]	BD	
33	PDI[11]/TX_D[3]/C25_SHI[1]	BD	C25_SHI[1]	PDI[11]	BD	
32	PDI[12]/RX_CLK	BD		PDI[12]	BD	
31	PDI[13]/RX_DV	BD		PDI[13]	BD	
30	PDI[14]/RX_D[0]	BD		PDI[14]	BD	
29	PDI[15]/RX_D[1]	BD		PDI[15]	BD	
28	PDI[16]/RX_D[2]	BD		PDI[16]	BD	
27	PDI[17]/RX_D[3]	BD		PDI[17]	BD	
2	EBUS{1}-RX-/LINK_MII	LI-/I		EBUS(1)-RX-	LI-	27 kΩ PU
3	EBUS{1}-RX+/RX_ERR	LI+/I		EBUS(1)-RX+	LI+	27 kΩ PD
10	EBUS{1}-TX-/MI_CLK	LO-/O		EBUS(1)-TX-	LO-	
11	EBUS{1}-TX+/TX_ENA	LO+/O		EBUS(1)-TX+	LO+	
8	EBUS{0}-RX-	LI-		EBUS(0)-RX-	LI-	27 kΩ PU
9	EBUS{0}-RX+	LI+		EBUS(0)-RX+	LI+	27 kΩ PD
4	EBUS{0}-TX-	LO-		EBUS(0)-TX-	LO-	
5	EBUS{0}-TX+	LO+		EBUS(0)-TX+	LO+	

Table 27: Port 0/1 and PDI signals (chip modes 10/11)

Pin	Pin		MODE[1:0]=10		MODE[1:0]=11		Internal PU/PD
	Name	Dir	Signal	Dir.	Signal	Dir.	
36	PDI[8]/TX_D[0]/PHYAD_OFF	BD	TX_D(0)[0]	O	TX_D(1)[0]	O	
35	PDI[9]/TX_D[1]/C25_ENA	BD	TX_D(0)[1]	O	TX_D(1)[1]	O	
34	PDI[10]/TX_D[2]/C25_SHI[0]	BD	TX_D(0)[2]	O	TX_D(1)[2]	O	
33	PDI[11]/TX_D[3]/C25_SHI[1]	BD	TX_D(0)[3]	O	TX_D(1)[3]	O	
32	PDI[12]/RX_CLK	BD	RX_CLK(0)	I	RX_CLK(1)	I	
31	PDI[13]/RX_DV	BD	RX_DV(0)	I	RX_DV(1)	I	
30	PDI[14]/RX_D[0]	BD	RX_D(0)[0]	I	RX_D(1)[0]	I	
29	PDI[15]/RX_D[1]	BD	RX_D(0)[1]	I	RX_D(1)[1]	I	
28	PDI[16]/RX_D[2]	BD	RX_D(0)[2]	I	RX_D(1)[2]	I	
27	PDI[17]/RX_D[3]	BD	RX_D(0)[3]	I	RX_D(1)[3]	I	
2	EBUS{1}-RX-/LINK_MII	LI-/I	LINK_MII(0)	I	LINK_MII(1)	I	27 kΩ PU
3	EBUS{1}-RX+/RX_ERR	LI+/I	RX_ERR(0)	I	RX_ERR(1)	I	27 kΩ PD
10	EBUS{1}-TX-/MI_CLK	LO-/O	MI_CLK	O	MI_CLK	O	
11	EBUS{1}-TX+/TX_ENA	LO+/O	TX_ENA(0)	O	TX_ENA(1)	O	
8	EBUS{0}-RX-	LI-	EBUS(1)-RX-	LI-	EBUS(0)-RX-	LI-	27 kΩ PU
9	EBUS{0}-RX+	LI+	EBUS(1)-RX+	LI+	EBUS(0)-RX+	LI+	27 kΩ PD
4	EBUS{0}-TX-	LO-	EBUS(1)-TX-	LO-	EBUS(0)-TX-	LO-	
5	EBUS{0}-TX+	LO+	EBUS(1)-TX+	LO+	EBUS(0)-TX+	LO+	

3.10.5 PDI[7:0] signals

Table 28 shows the PDI[7:0] signals. The direction of all PDI pins depends on the PDI configuration stored in the SII EEPROM.

Table 28: PDI pins

Pin	Pin		PDI, C25ENA=0, CLK_MODE=00		PDI, C25ENA=1, CLK_MODE/=00		Internal PU/PD
	Name	Dir.	Signal	Dir.	Signal	Dir.	
46	PDI[0]	BD/LO+	PDI[0]	BD/LO+	PDI[0]	BD/LO+	
45	PDI[1]	BD/LO-	PDI[1]	BD/LO-	PDI[1]	BD/LO-	
44	PDI[2]	BD/LI+	PDI[2]	BD/LI+	PDI[2]	BD/LI+	27 kΩ PD
43	PDI[3]	BD/LI-	PDI[3]	BD/LI-	PDI[3]	BD/LI-	27 kΩ PU
40	PDI[4]	BD	PDI[4]	BD	PDI[4]	BD	
39	PDI[5]	BD	PDI[5]	BD	PDI[5]	BD	
38	PDI[6]/CLK25OUT	BD	PDI[6]	BD	CLK25OUT	O	
37	PDI[7]/CPU_CLK	BD	PDI[7]	BD	CPU_CLK	O	

3.11 PDI signal pinout depending on selected PDI

The PDI signal pinout depends on the selected PDI (SII EEPROM). The PDI selection and PDI signal pinout is subject to restrictions introduced by the port configuration. Digital I/O and SPI slave PDI are available in any configuration – although the I/O width can be reduced depending on the configuration. The MII bridge port PDI is only available in chip mode 00.

Refer to PDI descriptions for further PDI and PDI signal descriptions.

The SPI slave PDI supports additional general purpose output signals, which are not part of the SPI slave PDI description:

GPO[x]
General purpose output signals.

3.11.1 Digital I/O pinout

Table 29: Mapping of digital I/O interface

PDI signal	MODE[1:0]=00		MODE[1:0]=10/11	
	Signal	Dir.	Signal	Dir.
PDI[0]	I/O[0]	BD	I/O[0]	BD
PDI[1]	I/O[1]	BD	I/O[1]	BD
PDI[2]	I/O[2]	BD	I/O[2]	BD
PDI[3]	I/O[3]	BD	I/O[3]	BD
PDI[4]	I/O[4]	BD	I/O[4]	BD
PDI[5]	I/O[5]	BD	I/O[5]	BD
PDI[6]/CLK25OUT	I/O[6]	BD	I/O[6]	BD
PDI[7]/CPU_CLK	I/O[7]	BD	I/O[7]	BD
PDI[8]	I/O[8]	BD	MII	
PDI[9]	I/O[9]	BD		
PDI[10]	I/O[10]	BD		
PDI[11]	I/O[11]	BD		
PDI[12]	I/O[12]	BD		
PDI[13]	I/O[14]	BD		
PDI[14]	I/O[15]	BD		
PDI[15]	I/O[16]	BD		
PDI[16]	OUTVALID/WD_TRIG	O		
PDI[17]	LATCH_IN/SOF	I/O		

3.11.2 SPI slave pinout

Table 30: Mapping of SPI slave interface

PDI signal	MODE[1:0]=00		MODE[1:0]=10/11	
	Signal	Dir.	Signal	Dir.
PDI[0]	SPI_CLK	I	SPI_CLK	I
PDI[1]	SPI_SEL	I	SPI_SEL	I
PDI[2]	SPI_DI	I	SPI_DI	I
PDI[3]	SPI_DO	O	SPI_DO	O
PDI[4]	SPI_IRQ	O	SPI_IRQ	O
PDI[5]	EEPROM_LOADED	O	EEPROM_LOADED	O
PDI[6]/CLK25OUT	GPO[0]	O	GPO[0]	O
PDI[7]/CPU_CLK	GPO[1]	O	GPO[1]	O
PDI[8]	GPO[2]	O	MII	
PDI[9]	GPO[3]	O		
PDI[10]	GPO[4]	O		
PDI[11]	GPO[5]	O		
PDI[12]	GPO[6]	O		
PDI[13]	GPO[7]	O		
PDI[14]	GPO[8]	O		
PDI[15]	GPO[9]	O		
PDI[16]	GPO[10]	O		
PDI[17]	GPO[11]	O		

3.11.3 EBUS/MII bridge port (logical port 3)

The bridge port is an additional port with logical number 3, it is configured via SII EEPROM, thus it is not available directly after power-on. The bridge port becomes available once the EEPROM is loaded successfully. The loop at this port is initially closed and has to be opened by the master explicitly. The bridge port may be either EBUS or MII. The MII bridge port is only available in chip mode 00.

The polarity of PERR(3) and LINKACT(3) is active high.

Table 31: Mapping of EBUS bridge signals

PDI signal	MODE[1:0]=00		MODE[1:0]=10/11	
	Signal	Dir.	Signal	Dir.
PDI[0]	EBUS(3)_TX+	LO+	EBUS(3)_TX+	LO+
PDI[1]	EBUS(3)_TX-	LO-	EBUS(3)_TX-	LO-
PDI[2]	EBUS(3)_RX+	LI+	EBUS(3)_RX+	LI+
PDI[3]	EBUS(3)_RX-	LI-	EBUS(3)_RX-	LI-
PDI[4]	PERR(3)	O	PERR(3)	O
PDI[5]	LINKACT(3)	O	LINKACT(3)	O
PDI[6]/CLK25OUT	GPO[0]	O	GPO[0]	O
PDI[7]/CPU_CLK	GPO[1]	O	GPO[1]	O
PDI[8]	GPO[2]	O	MII	
PDI[9]	GPO[3]	O		
PDI[10]	GPO[4]	O		
PDI[11]	GPO[5]	O		
PDI[12]	GPO[6]	O		
PDI[13]	GPO[7]	O		
PDI[14]	GPO[8]	O		
PDI[15]	GPO[9]	O		
PDI[16]	GPO[10]	O		
PDI[17]	GPO[11]	O		

Table 32: Mapping of MII bridge signals

PDI signal	MODE[1:0]=00	
	Signal	Dir.
PDI[0]	TX_ENA(3)	O
PDI[1]	MI_CLK	O
PDI[2]	RX_ERR(3)	I
PDI[3]	LINK_MII(3)	I
PDI[4]	PERR(3)	O
PDI[5]	LINKACT(3)	O
PDI[6]/CLK25OUT	CLK25OUT	O
PDI[7]/CPU_CLK	GPO[1]	O
PDI[8]	TX_D(3)[0]	O
PDI[9]	TX_D(3)[1]	O
PDI[10]	TX_D(3)[2]	O
PDI[11]	TX_D(3)[3]	O
PDI[12]	RX_CLK(3)	I
PDI[13]	RX_DV(3)	I
PDI[14]	RX_D(3)[0]	I
PDI[15]	RX_D(3)[1]	I
PDI[16]	RX_D(3)[2]	I
PDI[17]	RX_D(3)[3]	I

3.12 TESTMODE pin

Table 33: TESTMODE pin

Pin	Pin		Signal		Configuration	Internal PU/PD
	Name	Dir	Name	Dir		
1	TESTMODE	I	TESTMODE	I		WPD

TESTMODE
Reserved for testing, should be connected to GND.

4 MII interface

The ET1200 is connected with Ethernet PHYs using the MII interface. The MII interface of the ET1200 is optimized for low processing/forwarding delays by omitting a transmit FIFO. To allow this, the ET1200 has additional requirements to Ethernet PHYs, which are easily accomplished by several PHY vendors.

Refer to "Section I – Technology" for Ethernet PHY requirements.

Additional information regarding the ET1200:

- The clock source of the PHYs is either CLK25OUT of the ET1200, or the clock signal that is connected to OSC_IN if a quartz oscillator is used.
- The signal polarity of LINK_MII is not configurable, LINK_MII has to be active low.
- The TX_CLK signal of the PHYs is not connected to the ET1200. The ET1200 does not use the MII interface for link detection or link configuration.

For details about the ESC MII interface refer to section I.

4.1 MII interface signals

The MII interface of the ET1200 has the following signals:

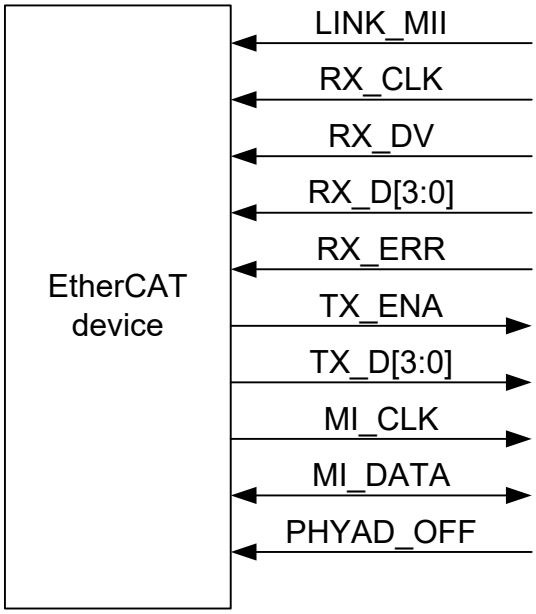

Figure 12: MII interface signals

Table 34: MII interface signals

Signal	Direction	Description
LINK_MII	IN	Input signal provided by the PHY if a 100 Mbit/s (Full Duplex) link is established Note: There is an internal 27K pull up resistor at LINK_MII inside the ET1200
RX_CLK	IN	Receive clock
RX_DV	IN	Receive data valid
RX_D[3:0]	IN	Receive data (alias RXD)
RX_ERR	IN	Receive error (alias RX_ER) Note: There is an internal 27K pull down resistor at RX_ERR inside the ET1200
TX_ENA	OUT	Transmit enable (alias TX_EN)
TX_D[3:0]	OUT	Transmit data (alias TXD)
MI_CLK	OUT	Management interface clock (alias MCLK)
MI_DATA	BIDIR	Management interface data (alias MDIO)
PHYAD_OFF	IN	Configuration: PHY address offset

MI_DATA must have an external pull-up resistor (4.7 kΩ recommended for ESCs). MI_CLK is driven rail-to-rail, idle value is high.

4.2 PHY address configuration

The ET1200 addresses Ethernet PHYs using logical port number (or PHY address register value) plus PHY address offset. Typically, the Ethernet PHY addresses should correspond with the logical port number, so PHY addresses 0-3 are used.

A PHY address offset of 16 can be applied which moves the PHY addresses to 16-19 by inverting the MSB of the PHY address internally.

If both alternatives cannot be used, the PHYs should be configured to use an actual PHY address offset of 1, i.e., PHY addresses 1-4. The PHY address offset configuration of the ET1200 remains 0.

Refer to section I for more details about PHY addressing.

4.3 TX shift compensation

Since ET1200 and the Ethernet PHY share the same clock source, TX_CLK from the PHY has a fixed phase relation to TX_ENA/TX_D[3:0]from the ET1200. Thus, TX_CLK is not connected and the delay of a TX FIFO inside the ET1200 is saved. The phase shift between TX_CLK and TX_ENA/TX_D[3:0] can be compensated by an appropriate value for TX shift, which will delay TX_ENA/ TX_D[3:0] by 0, 10, 20, or 30 ns.

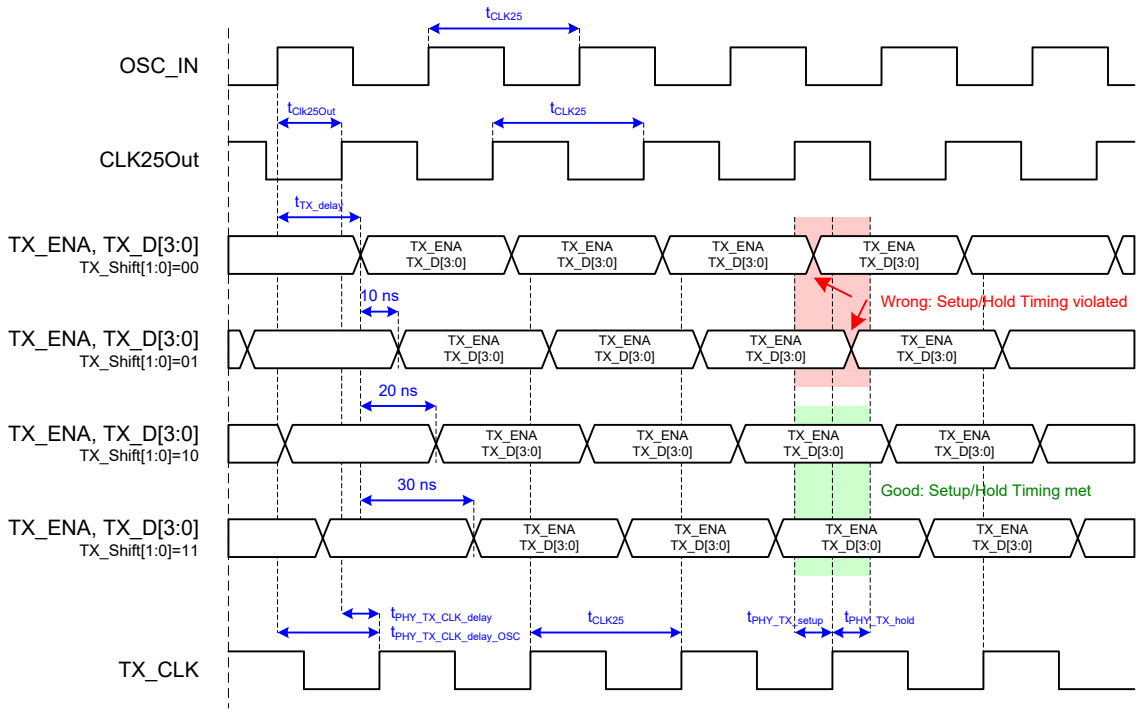

Figure 13: TX shift timing diagram

Table 35: TX shift timing characteristics

Parameter	Comment
t_{CLK25}	25 MHz clock source (OSC_IN, see f_{CLK25})
$t_{CLK25OUT}$	CLK25OUT delay after OSC_IN (refer to AC characteristics)
t_{TX_delay}	TX_ENA/TX_DATA[3:0] delay after rising edge of OSC_IN (refer to AC characteristics)
$t_{PHY\_TX\_CLK\_delay}$	Delay between PHY clock source CLK25OUT and TX_CLK output of the PHY, PHY dependent
$t_{PHY\_TX\_CLK\_delay\_OSC}$	Delay between PHY clock source OSC_IN and TX_CLK output of the PHY, PHY dependent
$t_{PHY\_TX\_setup}$	PHY setup requirement: TX_ENA/TX_DATA with respect to TX_CLK (PHY dependent, IEEE802.3 limit is 15 ns)
$t_{PHY\_TX\_hold}$	PHY hold requirement: TX_ENA/TX_DATA with respect to TX_CLK (PHY dependent, IEEE802.3 limit is 0 ns)

NOTE: TX shift can be adjusted by displaying TX_CLK of a PHY and TX_ENA/TX_D[3:0] on an oscilloscope. TX_ENA/TX_D is allowed to change between 0 ns and 25 ns after a rising edge of TX_CLK (according to IEEE802.3 – check your PHY's documentation, it may contain relaxed timing requirements). Configure TX shift so that TX_ENA/TX_D[3:0] change near the middle of this range. It is sufficient to check just one of the TX_ENA/TX_D[3:0] signals, because they are nearly generated at the same time.

4.4 Timing specifications

Table 36: MII timing characteristics

Parameter	Min	Typ	Max	Comment
t_{RX_CLK}		40 ns ± 100 ppm		RX_CLK period (100 ppm with maximum FIFO size only)
t_{RX_setup}	6			RX_DV/RX_DATA/RX_D[3:0] valid before rising edge of RX_CLK
t_{RX_hold}	5			RX_DV/RX_DATA/RX_D[3:0] valid after rising edge of RX_CLK
t_{Clk}		~ 1.44 µs		MI_CLK period (f_{Clk} ≈ 700 kHz)
t_{Write}		~ 92.16 µs		MI write access time
t_{Read}		~ 91.44 us		MI read access time

NOTE: For MI timing diagrams refer to section I.

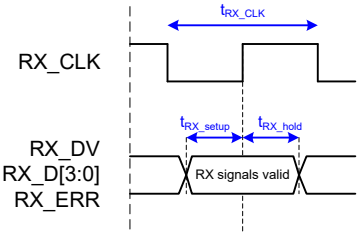

Figure 14: MII timing RX signals

5 EBUS/LVDS interface

For details about the ESC EBUS interface refer to section I.

5.1 EBUS interface signals

The EBUS interface of the ET1200 has the following signals:

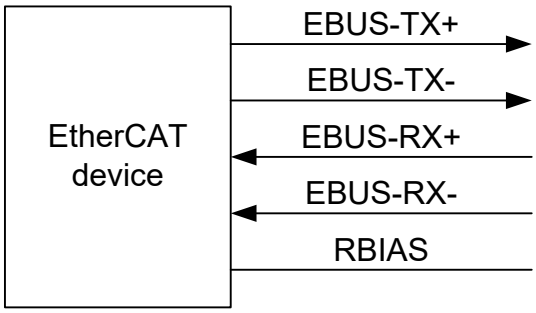

Figure 15: EBUS interface signals

Table 37: EBUS interface signals

Signal	Direction	Description
EBUS-TX+ EBUS-TX-	OUT	EBUS/LVDS transmit signals
EBUS-RX+ EBUS-RX-	IN	EBUS/LVDS receive signals.
RBIAS		BIAS resistor for EBUS-TX current adjustment

NOTE: An external LVDS termination with an impedance of 100 Ω between EBUS-RX+ and EBUS-RX- is necessary for EBUS ports. EBUS-RX+ incorporates a pull-down resistor and EBUS-RX- incorporated a pull-up resistor.

6 PDI description

Table 38: Available PDIs for ET1200

PDI number (PDI control register 0x0140[7:0])	PDI name	ET1200
0	Interface deactivated	x
4	Digital I/O	x
5	SPI slave	x
7	EtherCAT bridge (port 3)	x
8	16 bit async. µC	
9	8 bit async. µC	
10	16 bit sync. µC	
11	8 bit sync. µC	
16	32 digital input/0 digital output	
17	24 digital input/8 digital output	
18	16 digital input/16 digital output	
19	8 digital input/24 digital output	
20	0 digital input/32 digital output	
128	On-chip bus (Avalon or OPB)	
Others	Reserved	

6.1 PDI deactivated

The PDI is deactivated with PDI type 0x00. The PDI pins are not driven (high impedance).

6.2 Digital I/O interface

6.2.1 Interface

The digital I/O PDI is selected with PDI type 0x04. The signals of the digital I/O interface are:

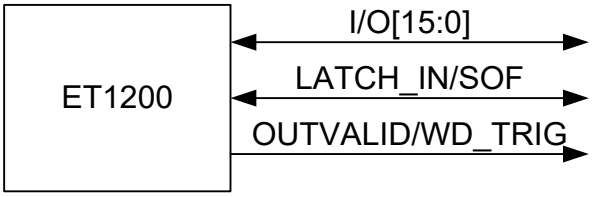

Figure 16: ET1200 digital I/O signals

Table 39: ET1200 digital I/O signals

Signal	Direction	Description	Signal polarity
I/O[15:0]	IN/OUT/BIDIR	Input/output or bidirectional data	
LATCH_IN/SOF	IN/OUT	External data latch signal or start of frame	act. high
OUTVALID/WD_TRIG	OUT	Output data is valid/output event or watchdog trigger	act. high

6.2.2 Configuration

The digital I/O interface is selected with PDI type 0x04 in the PDI control register 0x0140. It supports different configurations, which are located in registers 0x0150 – 0x0153.

6.2.3 Digital inputs

Digital input values appear in the process memory at address 0x1000:0x1003. EtherCAT devices use little endian byte ordering, so I/O[7:0] can be read at 0x1000 etc. Digital inputs are written to the process memory by the digital I/O PDI using standard PDI write operations.

Digital inputs can be configured to be sampled by the ESC in four ways:

- Digital inputs are sampled at the start of each Ethernet frame, so that EtherCAT read commands to address 0x1000:0x1003 will present digital input values sampled at the start of the same frame. The SOF signal can be used externally to update the input data, because the SOF is signaled before input data is sampled.
- The sample time can be controlled externally by using the LATCH_IN signal. The input data is sampled by the ESC each time a rising edge of LATCH_IN is recognized.
- Digital inputs are sampled at distributed clocks SYNC0 events.
- Digital inputs are sampled at distributed clocks SYNC1 events.

For distributed clock SYNC input, SYNC generation must be activated (register 0x0981). SYNC output is not necessary (register 0x0151). SYNC pulse length (registers 0x0982:0x0983) should not be set to 0, because acknowledging of SYNC events is not possible with digital I/O PDI. Sample time is the beginning of the SYNC event.

6.2.4 Digital outputs

Digital output values have to be written to register 0x0F00:0x0F03 (register 0x0F00 controls I/O[7:0] etc.). Digital output values are not read by the digital I/O PDI using standard read commands, instead, there is a direct connection for faster response times.

The process data watchdog (register 0x0440) has to be either active or disabled; otherwise digital outputs will not be updated. Digital outputs can be configured to be updated in four ways:

- Digital outputs are updated at the end of each EtherCAT frame (EOF mode).
- Digital outputs are updated with distributed clocks SYNC0 events (DC SYNC0 mode).
- Digital outputs are updated with distributed clocks SYNC1 events (DC SYNC1 mode).
- Digital outputs are updated at the end of an EtherCAT frame which triggered the process data watchdog (with typical SyncManager configuration: a frame containing a write access to at least one of the registers 0x0F00:0x0F03). Digital outputs are only updated if the EtherCAT frame was correct (WD_TRIG mode).

For distributed clock SYNC output, SYNC generation must be activated (register 0x0981). SYNC output is not necessary (register 0x0151). SYNC pulse length (registers 0x0982:0x0983) should not be set to 0, because acknowledging of SYNC events is not possible with digital I/O PDI. Output time is the beginning of the SYNC event.

An output event is always signaled by a pulse on OUTVALID even if the digital outputs remain unchanged.

For output data to be visible on the I/O signals, the following conditions have to be met:

- SyncManager watchdog must be either active (triggered) or disabled.
- Output values have to be written to the registers 0x0F00:0x0F03 within a valid EtherCAT frame.
- The configured output update event must have occurred.

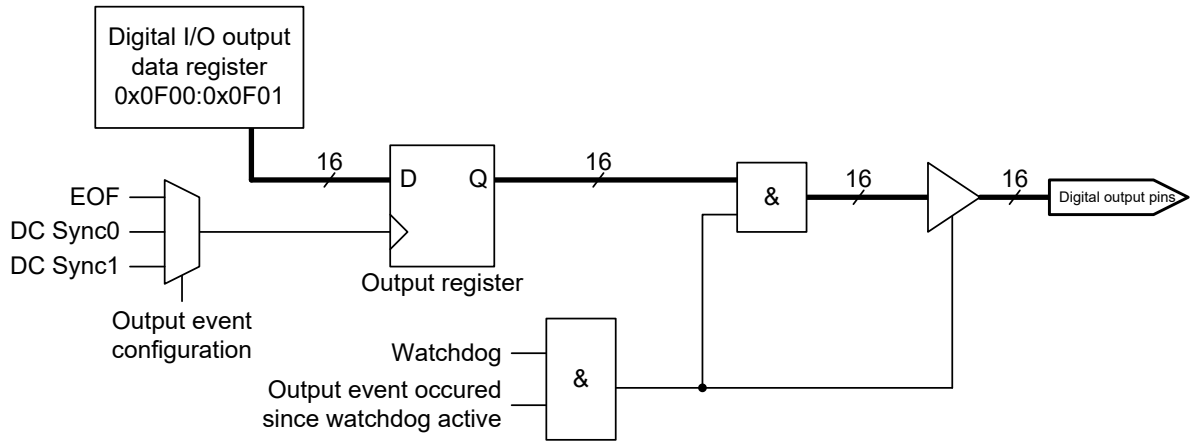

Figure 17: Digital output principle schematic

NOTE: The digital outputs are not driven (high impedance) until the EEPROM is loaded. The digital outputs are also not driven if the watchdog is expired. This behavior has to be taken into account when using digital output signals.

6.2.5 Bidirectional mode

In bidirectional mode, all DATA signals are bidirectional (individual input/output configuration is ignored). Input signals are connected to the ESC via series resistors, output signals are driven actively by the ESC. Output signals are permanently available if they are latched with OUTVALID (flip-flop or latch).

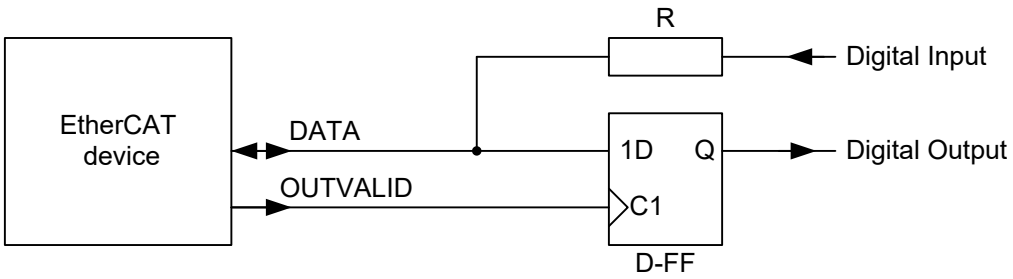

Figure 18: Bidirectional mode: input/output connection (R=4.7kΩ recommended)

Input sample event and output update event can be configured as described in the digital inputs/digital outputs chapter.

An output event is signaled by a pulse on OUTVALID even if the digital outputs remain unchanged. Overlapping input and output events will lead to corrupt input data.

6.2.6 Output Driver

The output drivers for the digital I/O signals of the ET1200 are active while the SyncManager watchdog is active (triggered) or disabled, otherwise the output driver is disabled (high impedance).

6.2.7 SyncManager watchdog

The SyncManager watchdog (registers 0x0440:0x0441) must be either active (triggered) or disabled for output values to appear on the I/O signals. The SyncManager watchdog is triggered by an EtherCAT write access to the output data registers.

If the output data bytes are written independently, a SyncManager with a length of 1 byte is used for each byte of 0x0F00:0x0F03 containing output bits (SyncManager N configuration: buffered mode, EtherCAT write/PDI read, and watchdog trigger enabled: 0x44 in register 0x0804+N*8). Alternatively, if all output data bits are written together in one EtherCAT command, one SyncManager with a length of 1 byte is sufficient (SyncManager N configuration: buffered mode, EtherCAT write/PDI read, and watchdog trigger enabled: 0x44 in register 0x0804+N*8). The start address of the SyncManager should be one of the 0x0F00:0x0F03 bytes containing output bits, e.g., the last byte containing output bits.

The SyncManager watchdog can also be disabled by writing 0 into registers 0x0440:0x0441.

The watchdog mode configuration bit is used to configure if the expiration of the SyncManager watchdog will have an immediate effect on the I/O signals (output reset immediately after watchdog timeout) or if the effect is delayed until the next output event (output reset with next output event). The latter case is especially relevant for distributed clock SYNC output events, because any output change will occur at the configured SYNC event.

Immediate output reset after watchdog timeout is not available if OUTVALID mode set to watchdog trigger (0x0150[1]=1).

For external watchdog implementations, the WD_TRIG (watchdog trigger) signal can be used. A WD_TRIG pulse is generated if the SyncManager watchdog is triggered. In this case, the internal SyncManager watchdog should be disabled. For devices without the WD_TRIG signal, OUTVALID can be configured to reflect WD_TRIG.

6.2.8 SOF

SOF indicates the start of an Ethernet/EtherCAT frame. It is asserted shortly after RX_DV=1 or EBUS SOF. Input data is sampled in the time interval between $t_{SOF\_to\_DATA\_setup}$ and $t_{SOF\_to\_DATA\_setup}$ after the SOF signal is asserted.

6.2.9 OUTVALID

A pulse on the OUTVALID signal indicates an output event. If the output event is configured to be the end of a frame, OUTVALID is issued shortly after RX_DV=0 or EBUS EOF, right after the CRC has been checked and the internal registers have taken their new values. OUTVALID is issued independent of actual output data values, i.e., it is issued even if the output data does not change.

6.2.10 Timing specifications

Table 40: Digital I/O timing characteristics ET1200

Parameter	Min	Max	Comment
t_{DATA_setup}	8 ns		Input data valid before LATCH_IN
t_{DATA_hold}	4 ns		Input data valid after LATCH_IN
t_{LATCH_IN}	8 ns		LATCH_IN high time
t_{SOF}	35 ns	45 ns	SOF high time
$t_{SOF\_to\_DATA\_setup}$		1,2 µs	Input data valid after SOF, so that inputs can be read in the same frame
$t_{SOF\_to\_DATA\_hold}$	1,6 µs		Input data invalid after SOF
$t_{input\_event\_delay}$	440 ns		Time between consecutive input events
$t_{OUTVALID}$	75 ns	85 ns	OUTVALID high time
$t_{DATA\_to\_OUTVALID}$	65 ns		Output data valid before OUTVALID
t_{WD_TRIG}	35 ns	45 ns	WD_TRIG high time
$t_{DATA\_to\_WD\_TRIG}$		35 ns	Output data valid after WD_TRIG
$t_{OE\_EXT\_to\_DATA\_invalid}$	-	-	Not applicable for ET1200
$t_{output\_event\_delay}$	320 ns		Time between consecutive output events
$t_{BIDIR\_DATA\_valid}$	65 ns		Bidirectional mode: I/O valid before OUTVALID
$t_{BIDIR\_DATA\_invalid}$	65 ns		Bidirectional mode: I/O invalid after OUTVALID
$t_{BIDIR\_event\_delay}$	440 ns		Bidirectional mode: time between consecutive input or output events

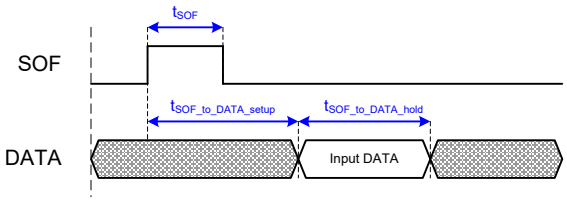

Figure 19: Digital input: input data sampled at SOF, I/O can be read in the same frame

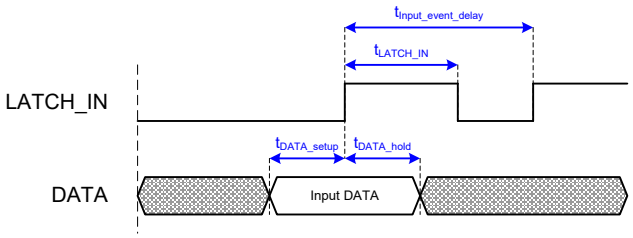

Figure 20: Digital input: input data sampled with LATCH_IN

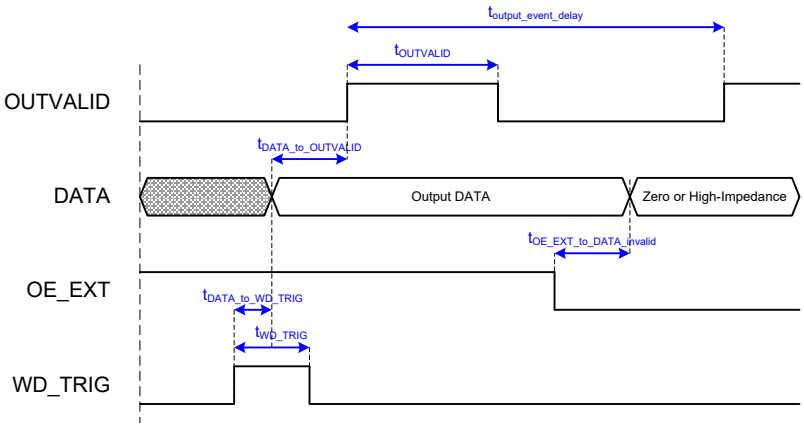

Figure 21: Digital output timing

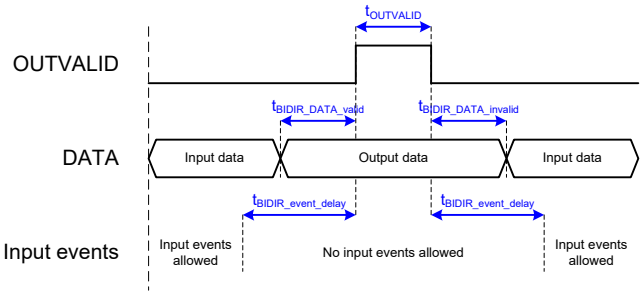

Figure 22: Bidirectional mode timing

6.3 SPI slave interface

6.3.1 Interface

An EtherCAT device with PDI type 0x05 is an SPI slave. The SPI has 5 signals: SPI_CLK, SPI_DI (MOSI), SPI_DO (MISO), SPI_SEL and SPI_IRQ:

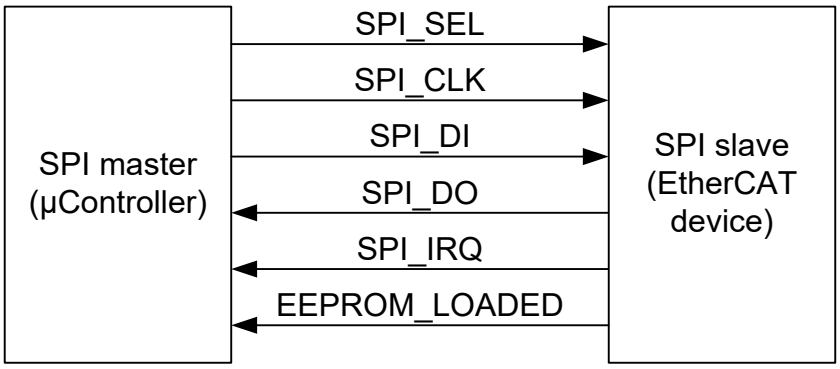

Figure 23: SPI master and slave interconnection

Table 41: SPI signals

Signal	Direction		Description	Signal polarity
SPI_SEL	IN	(master → slave)	SPI chip select	Typical: act. low
SPI_CLK	IN	(master → slave)	SPI clock	
SPI_DI	IN	(master → slave)	SPI data MOSI	act. high
SPI_DO	OUT	(slave → master)	SPI data MISO	act. high
SPI_IRQ	OUT	(slave → master)	SPI interrupt	Typical: act. low
EEPROM_LOADED	OUT	(slave → master)	PDI is active, EEPROM is loaded	act. high

6.3.2 Configuration

The SPI slave interface is selected with PDI type 0x05 in the PDI control register 0x0140. It supports different timing modes and configurable signal polarity for SPI_SEL and SPI_IRQ. The SPI configuration is located in register 0x0150.

NOTE: The maximum SPI_CLK frequency depends on the SPI mode (ET1200 only).

6.3.3 SPI access

Each SPI access is separated into an address phase and a data phase. In the address phase, the SPI master transmits the first address to be accessed and the command. In the data phase, read data is presented by the SPI slave (read command) or write data is transmitted by the master (write command). The address phase consists of 2 or 3 bytes depending on the address mode. The number of data bytes for each access may range from 0 to N bytes. The slave internally increments the address for the following bytes after reading or writing the start address. The bits of both address/command and data are transmitted in byte groups.

The master starts an SPI access by asserting SPI_SEL and terminates it by taking back SPI_SEL (polarity determined by configuration). While SPI_SEL is asserted, the master has to cycle SPI_CLK eight times for each byte transfer. In each clock cycle, both master and slave transmit one bit to the other side (full duplex). The relevant edges of SPI_CLK for master and slave can be configured by selecting SPI mode and data out sample mode.

The most significant bit of a byte is transmitted first, the least significant bit last, the byte order is low byte first. EtherCAT devices use little endian byte ordering.

6.3.4 Commands

The command CMD0 in the second address/command byte may be READ, WRITE, NOP, or address Extension. The command CMD1 in the third address/command byte may have the same values:

Table 42: SPI commands CMD0 and CMD1

CMD[2]	CMD[1]	CMD[0]	Command
0	0	0	NOP (no operation)
0	0	1	reserved
0	1	0	Read
0	1	1	reserved
1	0	0	Write
1	0	1	reserved
1	1	0	Address Extension (3 address/command bytes)
1	1	1	reserved

6.3.5 Address modes

The SPI slave interface supports two address modes, 2 byte addressing and 3 byte addressing. With two byte addressing, the lower 13 address bits A[12:0] are selected by the SPI master, while the upper 3 bits A[15:13] are assumed to be 000b inside the SPI slave, thus only the first 8 Kbyte in the EtherCAT slave address space can be accessed. Three byte addressing is used for accessing the whole 64 Kbyte address space of an EtherCAT slave.

Table 43: Address modes

Byte	2 byte address mode		3 byte address mode	
0	A[12:5]	address bits [12:5]	A[12:5]	address bits [12:5]
1	A[4:0] CMD0[2:0]	address bits [4:0] read/write command	A[4:0] CMD0[2:0]	address bits [4:0] 3 byte addressing: 110b
2	D0[7:0]	data byte 0	A[15:13] CMD1[2:0] res[1:0]	address bits [15:13] read/write command two reserved bits, set to 00b
3	D1[7:0]	data byte 1	D0[7:0]	data byte 0
4 ff.	D2[7:0]	data byte 2	D1[7:0]	data byte 1

6.3.6 Interrupt request register (AL event register)

During the address phase, the SPI slave transmits the PDI interrupt request registers 0x0220-0x0221 (2 byte address mode), and additionally register 0x0222 for 3 byte addressing on SPI_DO (MISO):

Table 44: Interrupt request register transmission

Byte	2 byte address mode			3 byte address mode		
	SPI_DI (MOSI)	SPI_DO (MISO)		SPI_DI (MOSI)	SPI_DO (MISO)	
0	A[12:5]	I0[7:0]	interrupt request register 0x0220	A[12:5]	I0[7:0]	interrupt request register 0x0220
1	A[4:0] CMD0[2:0]	I1[7:0]	interrupt request register 0x0221	A[4:0] CMD0[2:0]	I1[7:0]	interrupt request register 0x0221
2	(data phase)			A[15:13] CMD1[2:0]	I2[7:0]	interrupt request register 0x0222

6.3.7 Write access

In the data phase of a write access, the SPI master sends the write data bytes to the SPI slave (SPI_DI/MOSI). The write access is terminated by taking back SPI_SEL after the last byte. The SPI_DO signal (MISO) is undetermined during the data phase of write accesses.

6.3.8 Read access

In the data phase of a read access, the SPI slave sends the read data bytes to the SPI master (SPI_DO/MISO).

6.3.8.1 Read wait state

Between the last address phase byte and the first data byte of a read access, the SPI master has to wait for the SPI slave to fetch the read data internally. Subsequent read data bytes are prefetched automatically, so no further wait states are necessary.

The SPI master can choose between these possibilities:

- The SPI master may either wait for the specified worst case internal read time t_{read} after the last address/command byte and before the first clock cycle of the data phase.
- The SPI master may use the BUSY signaling of the SPI slave to achieve faster read times. The SPI slave presents its state on SPI_DO (MISO) after SPI_DI (MOSI) is set high between address and data phase (Busy out enable) until SPI_DI is set to low (Busy out enable is edge sensitive) . While the SPI slave is busy, it will drive SPI_DO high. Once it has finished, SPI_DO is set to low and the master may start with the next clock cycle for the first read data byte.
  BUSY signaling is not available in SPI mode 0/2 with normal data out sample.

6.3.8.2 Read termination

The SPI_DI signal (MOSI) is used for termination of the read access by the SPI master. For the last data byte, the SPI master has to set SPI_DI to high (read termination byte = 0xFF), so the slave will not prefetch the next read data internally. If SPI_DI is low during a data byte transfer, at least one more byte will be read by the master afterwards.

6.3.9 SPI access errors and SPI status flag

The following reasons for SPI access errors are detected by the SPI slave:

- The number of clock cycles recognized while SPI_SEL is asserted is not a multiple of 8 (incomplete bytes were transferred).
- For a read access, the data phase was not terminated by setting SPI_DI to high for the last byte.
- For a read access, additional bytes were read after termination of the access.

A wrong SPI access will have these consequences:

- Registers will not accept write data (nevertheless, RAM will be written).
- Special functions are not executed (e.g., SyncManager buffer switching).
- A status flag will indicate the error until the next access (not for SPI mode 0/2 with normal data out sample)

A status flag, which indicates if the last access had an error, is available in any mode except for SPI mode 0/2 with normal data out sample. The status flag is presented on SPI_DO (MISO) after the slave is selected (SPI_SEL) and until the first clock cycle occurs. So the status can be read either between two accesses by assertion of SPI_SEL without clocking, or at the beginning of an access just before the first clock cycle. The status flag will be high for a good access, and low for a wrong access.

6.3.10 EEPROM_LOADED

The EEPROM_LOADED signal indicates that the SPI interface is operational. Attach a pull-down resistor for proper function, since the PDI pin will not be driven until the EEPROM is loaded.

6.3.11 Timing specifications

Table 45: SPI timing characteristics ET1200

Parameter	Min	Max	Comment
t_{CLK}	a) 50 ns b) 166,7 ns c) 66,7 ns		SPI_CLK frequency a) SPI mode 1/3 with normal data out sample or SPI mode 0/1/2/3 with Late data out sample (f_{CLK}≤ 20 MHz) b) SPI mode 0/2 with normal data out sample (f_{CLK} ≤ 6 MHz) b) SPI mode 0/2 with normal data out sample and address Extension (f_{CLK} ≤ 15 MHz)
$t_{SEL\_to\_CLK}$	7 ns		First SPI_CLK cycle after SPI_SEL asserted
$t_{CLK\_to\_SEL}$	a) 5 ns b) t_{CLK}/2+5 ns		De-assertion of SPI_SEL after last SPI_CLK cycle a) SPI mode 0/2, SPI mode 1/3 with normal data out sample b) SPI mode 1/3 with late data out sample
t_{read}	a) 240 ns b) 0 ns c) t_{CLK}/2		Only for read access between address/command and first data byte. a) Not using BUSY in SPI mode 1/3, or SPI mode 0/2 with Late data out sample b) Using BUSY in SPI mode 1/3, or SPI mode 0/2 with Late data out sample c) SPI mode 0/2 with normal data out sample
$t_{C0\_to\_BUSY\_OE}$	t_{CLK}		BUSY OUT enable assertion after sample time of last command bit C0.
t_{BUSY_valid}		15 ns	BUSY valid after BUSY OUT enable
$t_{SEL\_to\_DO\_valid}$		15 ns	Status/interrupt byte 0 bit 7 valid after SPI_SEL asserted
$t_{SEL\_to\_DO\_invalid}$	0 ns		Status/interrupt byte 0 bit 7 invalid after SPI_SEL de-asserted
t_{STATUS_valid}	12 ns		Time until status of last access is valid. Can be ignored if status is not used.
t_{access_delay}	a) 15 ns b) 240 ns		Delay between SPI accesses a) typical b) If last access was shorter than 2 bytes, otherwise interrupt Request register value I0_[7:0] will not be valid.
t_{DI_setup}	8 ns		SPI_DI valid before SPI_CLK edge
t_{DI_hold}	3 ns		SPI_DI valid after SPI_CLK edge
$t_{CLK\_to\_DO\_valid}$		15 ns	SPI_DO valid after SPI_CLK edge
$t_{CLK\_to\_DO\_invalid}$	0 ns		SPI_DO invalid after SPI_CLK edge
$t_{EEPROM\_LOADED\_to\_access}$	300 ns		Time between EEPROM_LOADED and first access
t_{IRQ_delay}	160 ns		Internal delay between AL event and SPI_IRQ output to enable correct reading of the interrupt registers.

Table 46: Read/write timing diagram symbols

Symbol	Comment
A15..A0	Address bits [15:0]
D0_7..D0_0 D1_7..D1_0	Data bits byte 0 [7:0] Data bits byte 1 [7:0]
I0_7..I0_0 I1_7..I1_0 I2_7..I2_0	Interrupt request register 0x0220 [7:0] Interrupt request register 0x0221 [7:0] Interrupt request register 0x0222 [7:0]
C0_2..C0_0 C1_2..C1_0	Command 0 [2:0] Command 1 [2:0] (3 byte addressing)
Status	0: last SPI access had errors 1: last SPI access was correct
BUSY OUT enable	0: No Busy output, tread is relevant 1: Busy output on SPI_DO (edge sensitive)
BUSY	0: SPI slave has finished reading first byte 1: SPI slave is busy reading first byte

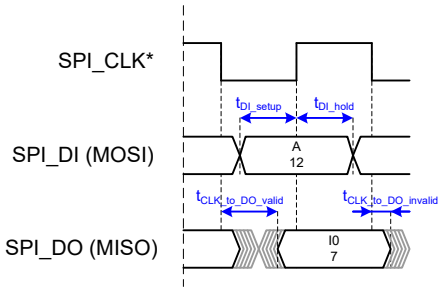

Figure 24: Basic SPI_DI/SPI_DO timing (*refer to timing diagram for relevant edges of SPI_CLK)

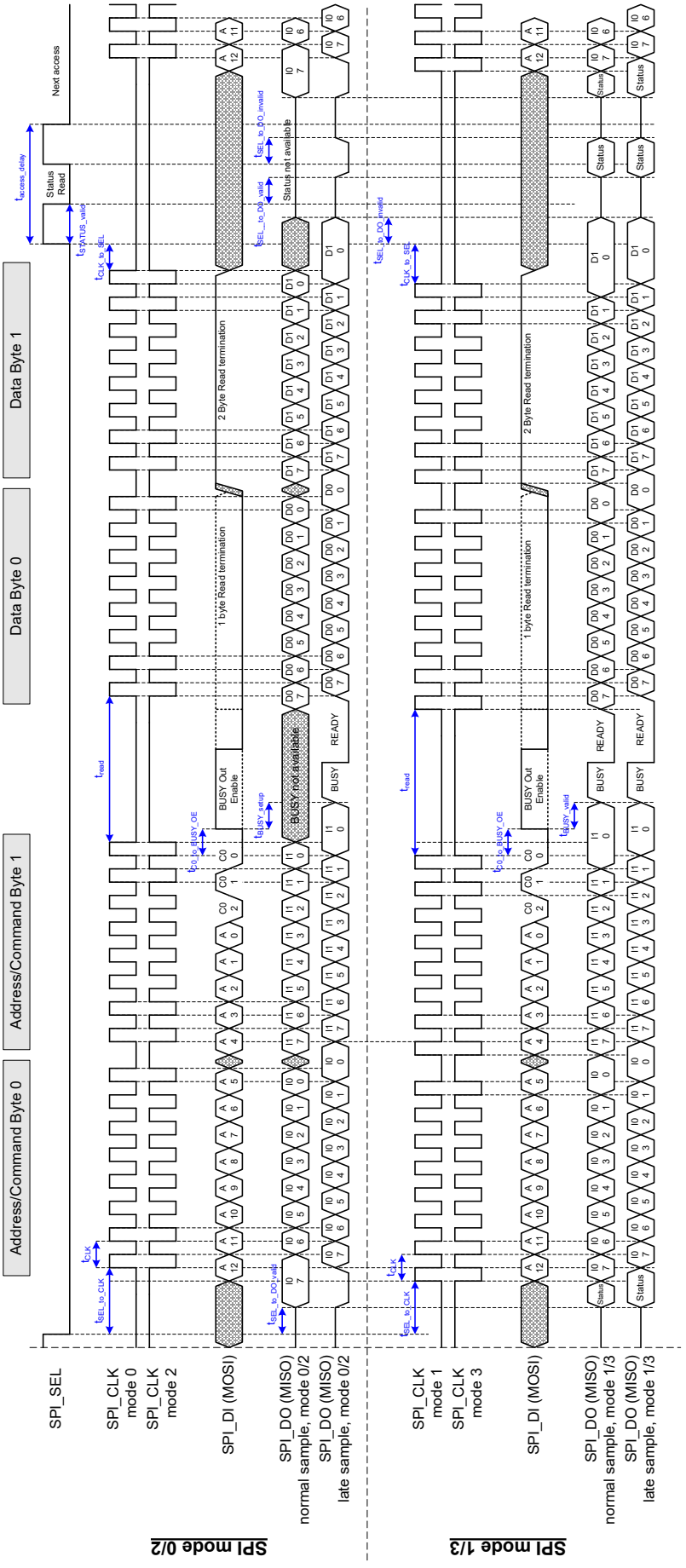

Figure 25: SPI read access (2 byte addressing, 2 byte read data) with BUSY and separate status reading

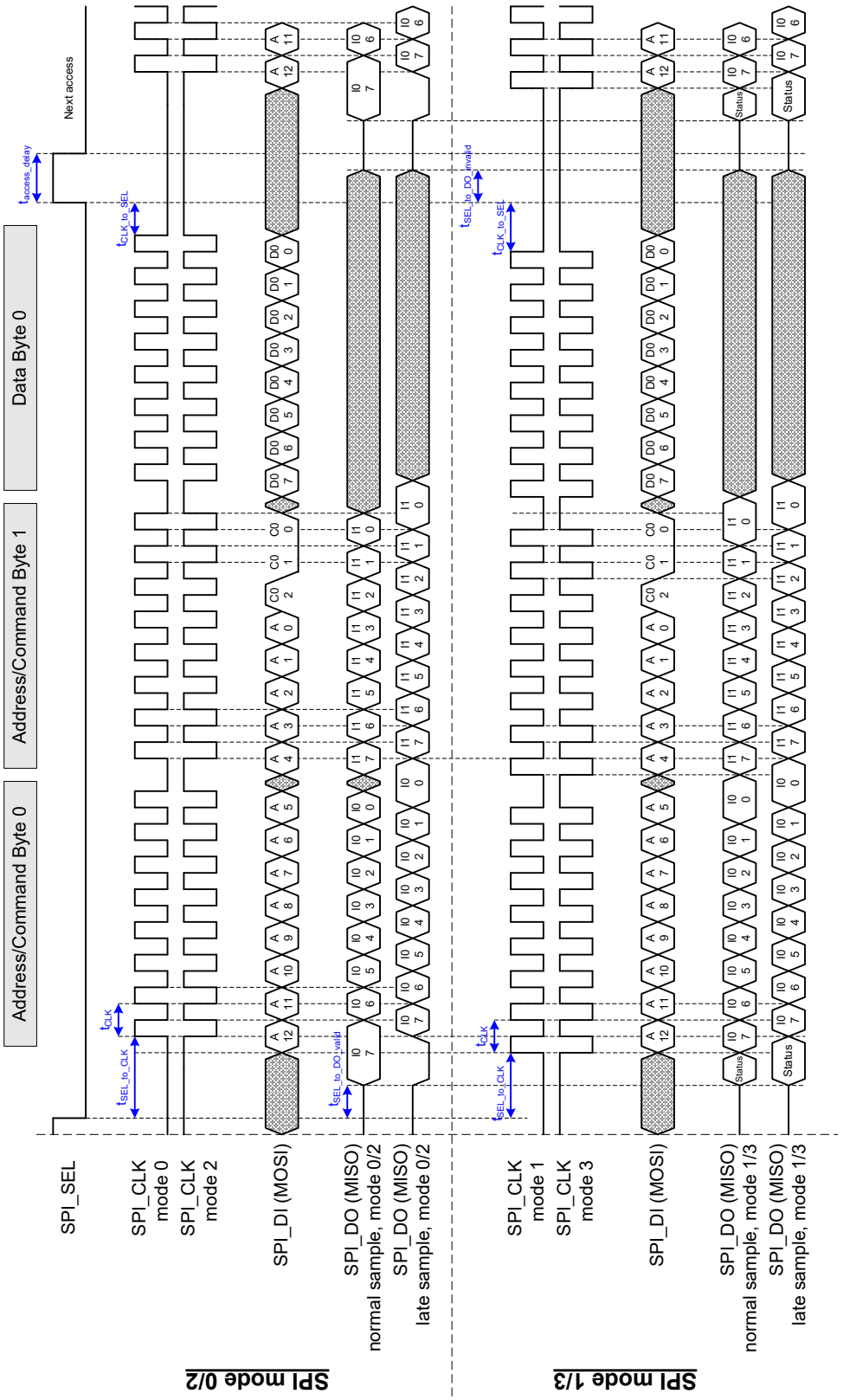

Figure 26: SPI write access (2 byte addressing, 1 byte write data)

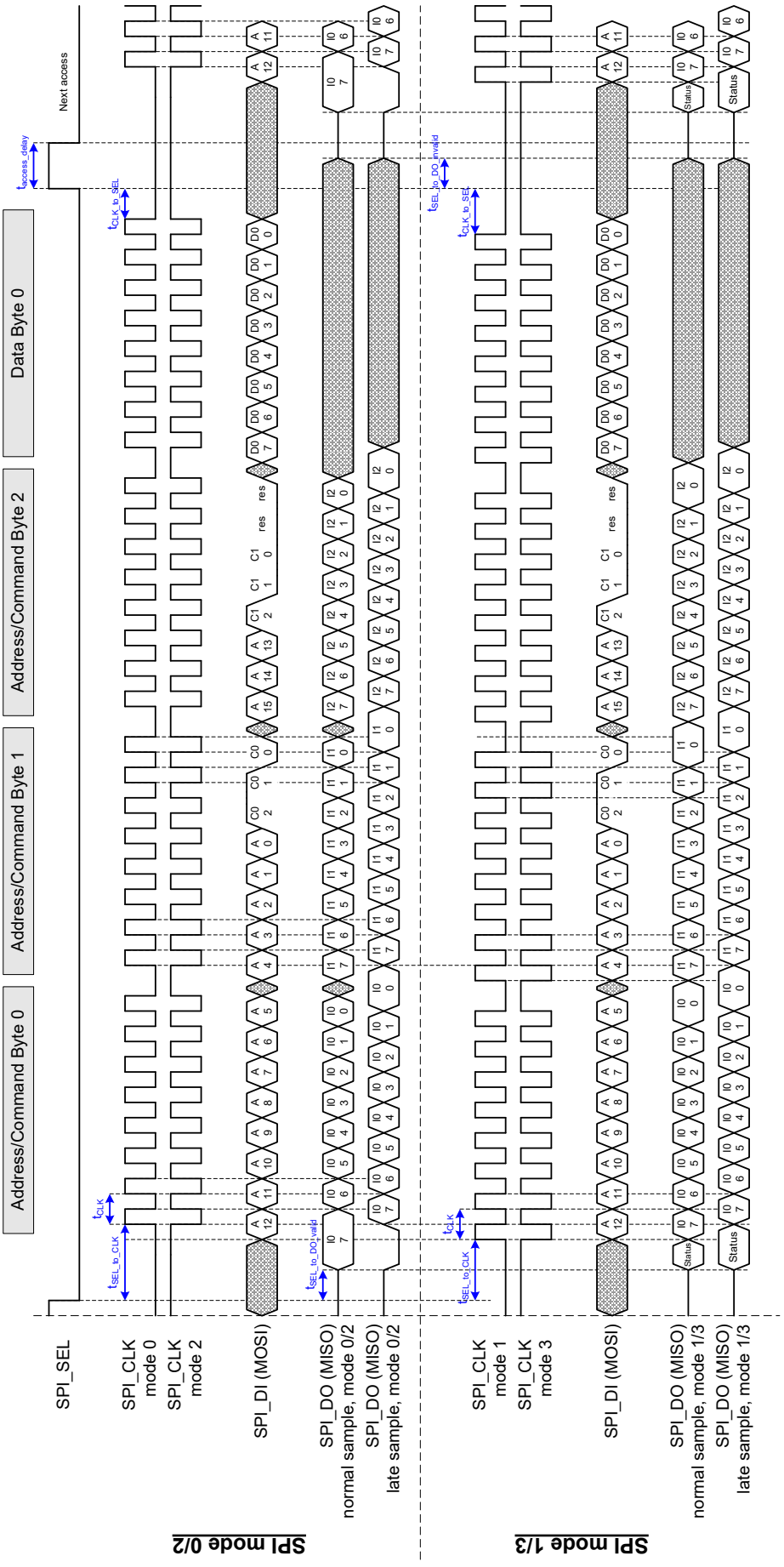

Figure 27: SPI write access (3 byte addressing, 1 byte write data)

7 Distributed clocks SYNC/LATCH signals

For details about the distributed clocks refer to section I.

7.1 Signals

The distributed clocks unit of the ET1200 has the following external signals (depending on the ESC configuration):

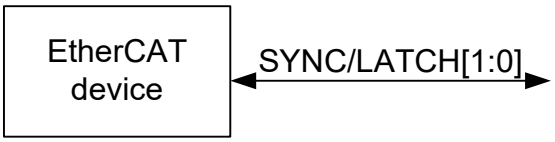

Figure 28: Distributed clocks signals

Table 47: Distributed clocks signals

Signal	Direction	Description
SYNC/LATCH[1:0]	OUT/IN	SyncSignal (OUT) or LatchSignal (IN), direction bitwise configurable via register 0x0151 / EEPROM.

NOTE: SYNC/LATCH signals are not driven (high impedance) until the EEPROM is loaded.

7.2 Timing specifications

Table 48: DC SYNC/LATCH timing characteristics ET1200

Parameter	Min	Max	Comment
t_{DC_LATCH}	15 ns		Time between Latch0/1 events
$t_{DC\_SYNC\_Jitter}$		15 ns	SYNC0/1 output jitter
$t_{DC\_SYNC\_Pulse\_IRQ}$	40 ns		Pulse length for SYNC0/1 if used as PDI interrupt in continuous mode

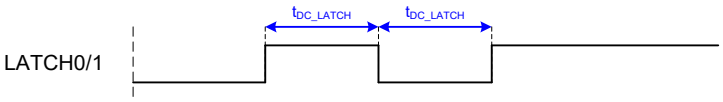

Figure 29: LatchSignal timing

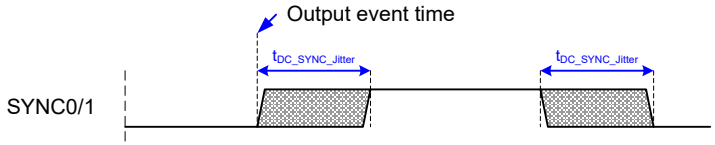

Figure 30: SyncSignal timing

8 SII EEPROM interface (I²C)

For details about the ESC SII EEPROM interface refer to section I. The SII EEPROM interface is intended to be a point-to-point interface between ET1200 and I²C EEPROM. If other I²C masters are required to access the I²C bus, the ET1200 must be held in reset state (e.g. for in-circuit-programming of the EEPROM), otherwise access collisions will be detected by the ET1200.

8.1 Signals

The EEPROM interface of the ET1200 has the following signals:

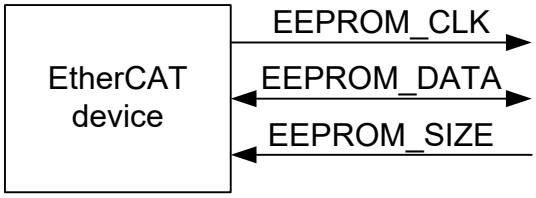

Figure 31: I²C EEPROM signals

Table 49: I²C EEPROM signals

Signal	Direction	Description
EEPROM_CLK	OUT	I²C clock
EEPROM_DATA	BIDIR	I²C data
EEPROM_SIZE	IN	EEPROM size configuration

The pull-up resistors for EEPROM_CLK and EEPROM_DATA are integrated into the ET1200. EEPROM_CLK must not be held low externally, because the ET1200 will detect this as an error.

8.2 Timing specifications

Table 50: EEPROM timing characteristics

Parameter	Typical		Comment
	1 Kbit-16 Kbit	32 Kbit-4 Mbit	
t_{Clk}	~ 6.72 µs		EEPROM clock period (f_{Clk} ≈ 150 kHz)
t_{Write}	~ 250 us	~ 310 µs	Write access time (without errors)
t_{Read}	a) ~ 680 µs b) ~ 1.16 ms	a) ~ 740 µs b) ~ 1.22 ms	Read access time (without errors): a) 4 words b) configuration (8 Words)
t_{Delay}	~ 168 ms		Time until configuration loading begins after reset is gone

9 Electrical and mechanical specifications

9.1 Absolute maximum conditions

Table 51: Absolute maximum conditions

Symbol	Parameter	Condition	Min	Max	Units
V_{CC}-V_{SS}	Supply voltage for internal LDO		-0.3	5.5	V
V_I	Input voltage	a) $V_{CC\ I/O}$=3.3V b) $V_{CC\ I/O}$=5V	-0.3	a) 3.6 b) 5.5	V
I_{CC}	Supply current	Internal LDOs used for $V_{CC\ I/O}$ and $V_{CC\ Core}$		110	mA
$I_{CC\ I/O}$	Supply current	$V_{CC\ I/O}$ sourced externally, LDO used for $V_{CC\ Core}$		100	mA
$I_{CC\ Core}$	Supply current	$V_{CC\ I/O}$ and $V_{CC\ Core}$ sourced externally		100	mA
V_{ESC}	ESD protection	Human body model, according to MIL-STD-883E-3015.7 Class 1	2		kV
I_{DC_ESD}	Permanent current into ESD protection diodes	Only in case of forward biased ESD diodes. Input voltage above $V_{CCI/O}$ or below V_{SS}		2	mA

NOTE: Supply current does not include output driver current for PDIs and LEDs.

9.2 Operating conditions

9.2.1 Power supply

Table 52: Power supply

Symbol	Parameter	Min	Typ	Max	Units
V_{CC}	Power supply	3.0	5.0	5.5	V
$V_{CC\ I/O}$	I/O power supply	3.0	3.3	5.5	V
$V_{CC\ Core}$	Logic power supply	2.25	2.5	2.75	V
$V_{CC\ PLL}$	PLL power supply	2.25	2.5	2.75	V
$V_{CC\ I/O\ Ext}$	External I/O power supply	3.3	3.3	5.5	V
$V_{CC\ Core\ Ext}$	External logic power supply	2.5	2.5	2.75	V
$V_{CC\ PLL\ Ext}$	External PLL power supply	2.5	2.5	2.75	V

9.2.2 Electrical characteristics

Table 53: DC characteristics

Symbol	Parameter	Condition	Min	Typ	Max	Units
$V_{CC\ I/O\ LDO}$	Internal LDO output voltage $V_{CC\ I/O}$			3.2		V
$V_{CC\ Core\ LDO}$	Internal LDO output voltage $V_{CC\ Core}$/$V_{CC\ PLL}$			2.4		V
$V_{Reset\ I/O}$	Reset threshold for $V_{CC\ I/O}$		2.64	2.8	2.92	V
$V_{Reset\ Core}$	Reset threshold for $V_{CC\ Core}$		1.46	1.6	1.74	V
V_{IL}	Input low voltage (not OSC_IN)				0.7	V
V_{IH}	Input high voltage (not OSC_IN)	a) $V_{CC\ I/O}$=3.3V b) $V_{CC\ I/O}$=5V	2.0		a) 3.6 b) 5.5	V
$V_{IT\ OSC\_IN}$	Input threshold voltage OSC_IN (no Schmitt trigger)	a) $V_{CC\ I/O}$=3.3V b) $V_{CC\ I/O}$=5V	a) 1.4 b) 2.2	a) 1.6 b) 2.5	a) 1.8 b) 2.8	V
V_{OL}	Output low voltage				0.4	V
V_{OH}	Output high voltage		2.4			V
V_{OD}	LVDS differential output voltage	R_L=100 Ω R_{BIAS}=11 kΩ	245	350	455	mV
ΔV_{OD}	Change in V_{OD} between 1 and 0				±50	mV
V_{OC}	LVSDS common mode output voltage		1.125	1.25	1.375	V
ΔV_{OC}	Change in V_{OC} between 1 and 0				±50	mV
V_{ID}	LVDS differential input voltage		100			mV
V_{IC}	LVDS input voltage range		0		2.4	V
I_{OH}	Output high current				4	mA
I_{OL}	Output low current				-3	mA
I_{IL}	Input leakage current (without internal PU/PD)				±10	µA
I_{OL}	Output leakage current (tristate, without internal PU/PD)				±10	µA
R_{PU}	Internal pull-up resistor		1.6	3.3	7	kΩ
R_{WPU}	Weak internal pull-up resistor	a) $V_{CC\ I/O}$=3.3V b) $V_{CC\ I/O}$=5V	a) 75 b) 50	a) 110 b) 70	a) 190 b) 120	kΩ
R_{WPD}	Weak internal pull-down resistor	a) $V_{CC\ I/O}$=3.3V b) $V_{CC\ I/O}$=5V	a) 60 b) 40	a) 95 b) 60	a) 180 b) 110	kΩ
R_{LI+}	Internal LVDS input pull-down resistor at EBUS_RX+ pins		15	27	45	kΩ
R_{LI-}	Internal LVDS input pull-up resistor at EBUS_RX- pins		15	27	45	kΩ
R_{BIAS}	External LVDS BIAS resistor			11		kΩ
R_L	LVDS RX load resistor			100		Ω
C_{OSC}	OSC_IN/OSC_OUT pin capacitance			1.2		pF

NOTE: R_{WPU}/R_{WPD} cannot be used externally, their full effectiveness appears only inside the ET1200 (realized as transistors).

NOTE: Input and output characteristics without special indication apply to all non-LVDS I/O signals.

Table 54: DC characteristics (supply current)

Configuration	External supply voltage			Supply current (typical)		
	V_{CC}	$V_{CC\ I/O}$	$V_{CC\ Core}$	I_{CC}	$I_{CC\ I/O}$	$I_{CC\ Core}$
2 EBUS ports	3.3V	3.3V	Int. LDO	70 mA	17 mA	-
	5V	Int. LDO	Int. LDO	87 mA	-	-
	5V	5V	Int. LDO	72 mA	36 mA	-
	3.3V	3.3V	2.5V	1 mA	17 mA	75 mA
	5V	Int. LDO	2.5V	16 mA	-	75 mA
	5V	5V	2.5V	1 mA	40 mA	75 mA
3 EBUS ports	3.3V	3.3V	Int. LDO	74 mA	24 mA	-
	5V	Int. LDO	Int. LDO	97 mA	-	-
	5V	5V	Int. LDO	76 mA	43 mA	-
	3.3V	3.3V	2.5V	1 mA	24 mA	79 mA
	5V	Int. LDO	2.5V	23 mA	-	79 mA
	5V	5V	2.5V	1 mA	43 mA	79 mA
1 EBUS port, 1 MII port	3.3V	3.3V	Int. LDO	68 mA	10 mA	-
	5V	Int. LDO	Int. LDO	78 mA	-	-
	5V	5V	Int. LDO	69 mA	25 mA	-
	3.3V	3.3V	2.5V	1 mA	10 mA	72 mA
	5V	Int. LDO	2.5V	10 mA	-	72 mA
	5V	5V	2.5V	1 mA	26 mA	72 mA
2 EBUS ports, 1 MII port	3.3V	3.3V	Int. LDO	71 mA	18 mA	-
	5V	Int. LDO	Int. LDO	89 mA	-	-
	5V	5V	Int. LDO	73 mA	34 mA	-
	3.3V	3.3V	2.5V	1 mA	18 mA	76 mA
	5V	Int. LDO	2.5V	17 mA	-	76 mA
	5V	5V	2.5V	1 mA	37 mA	76 mA

NOTE: Int. LDO means internal LDO is used, otherwise power is supplied externally. Supply current does not include output driver current for PDIs and LEDs.

9.2.3 Timing characteristics

Table 55: Timing characteristics

Symbol	Parameter	Min	Typ	Max	Units
f_{CLK25}	Clock source (OSC_IN) with initial accuracy		25 MHz ± 25 ppm		
$t_{CLK25OUT}$	CLK25OUT rising edge after OSC_IN rising edge		22		ns
t_{TX_delay}	TX_ENA/TX_D[3:0] edge (TX shift = 00) after rising edge of a) OSC_IN b) CLK25OUT		 a) 4 b) 22		ns
t_{CPU_CLK}	CPU_CLK (25 MHz) rising edge after OSC_IN rising edge		4		
t_{POR_Sample}	POR value sample time after power good		84		ms
t_{Driver_Enable}	Output drivers enabled after POR values sampled (not PDI and not Sync/LatchSignals)		80		ns
t_{Reset_In}	External reset input time	50			ns
t_{Reset_Out}	ET1200 reset output time	80	84		ms
t_{Reset_Func}	ET1200 functional after RESET signal high (EEPROM not loaded, PDI not functional)			50	µs
$t_{Startup}$	Startup time (PDI operational after power good, without SII loading error)			340	ms

The timing characteristics of the PDIs, distributed clocks, SII EEPROM I^2C interface, and MII interface can be found in their respective chapters.

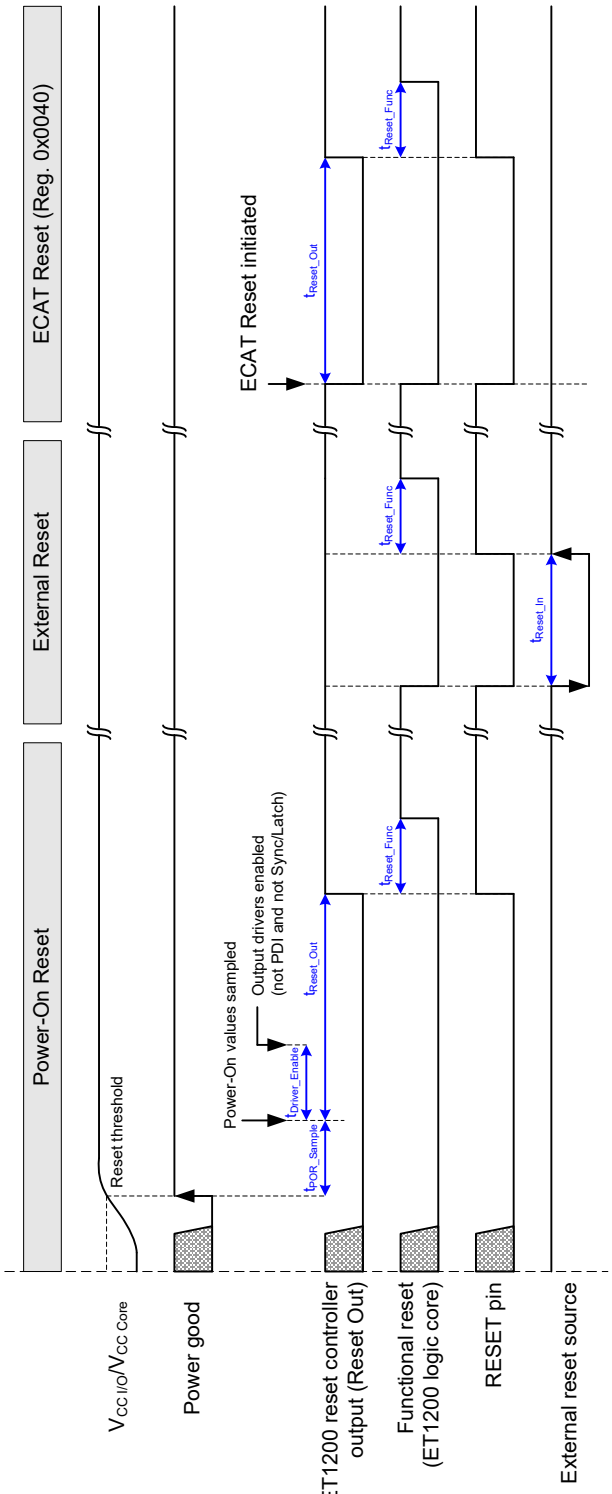

Figure 32: Reset timing

NOTE: External clock source (quartz oscillator) is assumed to be operational at power-good time. Otherwise t_{POR_Sampe} is delayed.

Table 56: Forwarding delays

Symbol	Parameter	Min	Average	Max	Units
t_{Diff}	Average difference processing delay minus forwarding delay (without RX FIFO jitter) between any two ports		20		ns
t_{EE}	EBUS port to EBUS port delay (FIFO size 7): a) Through ECAT processing unit (processing), low jitter off b) Alongside ECAT processing unit (forwarding), low jitter off c) Through ECAT processing unit (processing), low jitter on d) Alongside ECAT processing unit (forwarding), low jitter on	a) 140 b) 120 c) 150 d) 130	a) 150 b) 130 c) 155 d) 135	a) 160 b) 140 c) 160 d) 140	ns
t_{EM}	EBUS port to MII port delay (FIFO size 7): a) Through ECAT processing unit (processing) b) Alongside ECAT processing unit (forwarding)	a) 145 b) 125	a) 170 b) 150	a) 195 b) 175	ns
t_{ME}	MII port to EBUS port delay (FIFO size 7): a) Through ECAT processing unit (processing), low jitter off b) Alongside ECAT processing unit (forwarding), low jitter off c) Through ECAT processing unit (processing), low jitter on d) Alongside ECAT processing unit (forwarding), low jitter on	a) 255 b) 235 c) 265 d) 245	a) 280 b) 260 c) 290 d) 270	a) 305 b) 285 c) 315 d) 295	ns
t_{MM}	MII port to MII port delay (FIFO size 7, TX shift=00): Through ECAT processing unit (processing)	280	305	335	ns

NOTE: Average timings are used for distributed clocks calculations.

9.2.4 Thermal characteristics

Table 57: Thermal characteristics

Symbol	Parameter	Min	Typ	Max	Units
ϑ_A	Ambient temperature	-40		85	°C
ϑ_J	Junction temperature	-40		125	°C
Θ_{JA}	Thermal resistance Theta junction to ambient		27.8		°C/W
Θ_{JC}	Thermal resistance Theta junction to case		13.1		°C/W
Θ_{JB}	Thermal resistance Theta junction to board		6.8		°C/W
Ψ_{JT}	Thermal resistance PSI junction to top		0.2		°C/W
Ψ_{JB}	Thermal resistance PSI junction to bottom		6.8		°C/W

Note: Modeling test board (PCB) JEDEC 2s2p

9.3 Mechanical specifications

9.3.1 Package information

A 48 pin QFN package is used for the ET1200. The plating material of the leads is 100% Sn.

The ET1200 is compliant to RoHS 2 (2011/65/EU) including amendment "COMMISSION DELEGATED DIRECTIVE (EU) 2015/863".

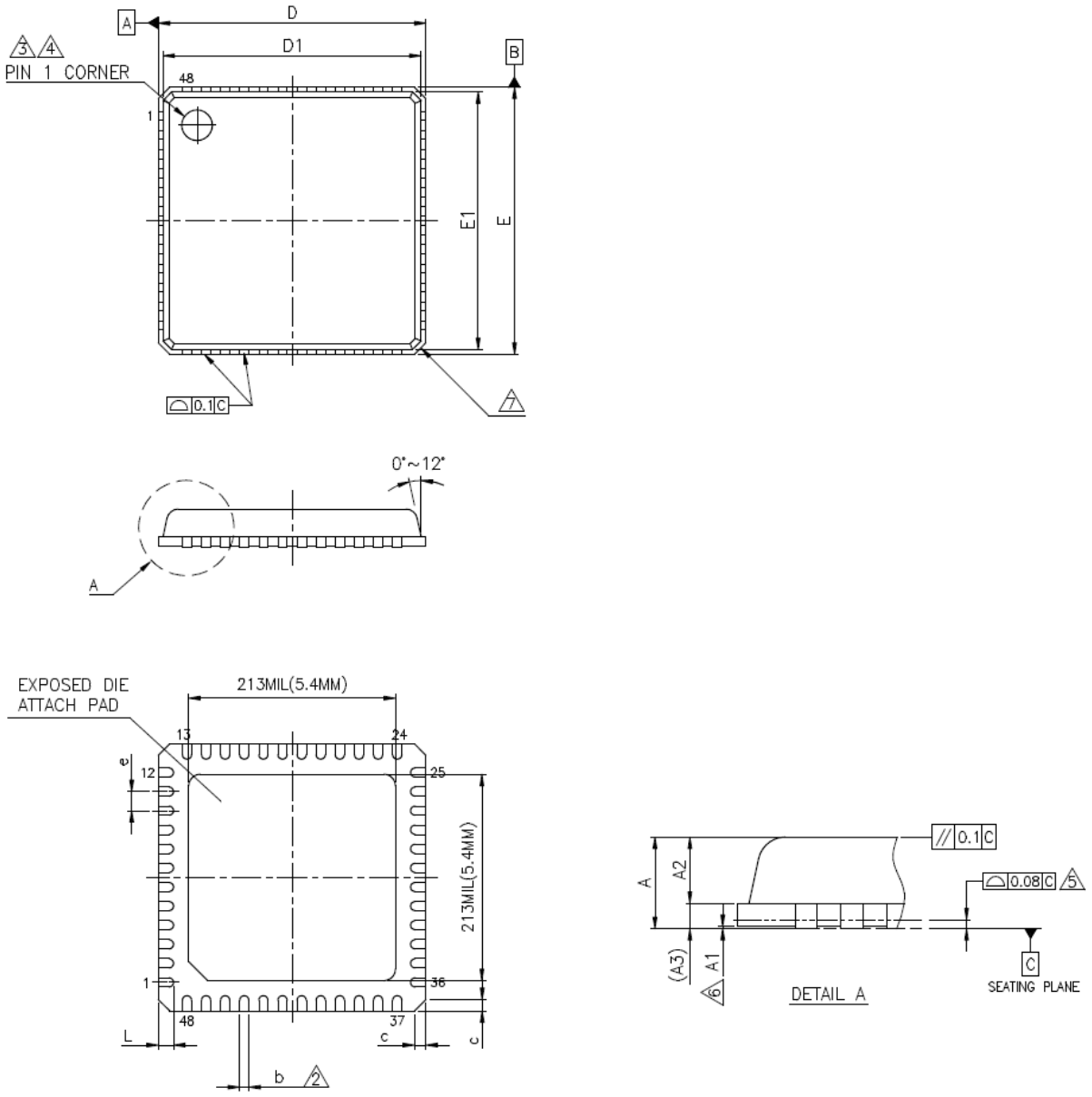

Figure 33: Package outline

SYMBOLS	MIN.	NOM.	MAX.
A	0.80	0.90	1.00
A1	0.00	0.02	0.05
⚠1 A2	0.65 REF.		
A3	0.203 REF.		
b	0.18	0.25	0.30
C	0.24	0.42	0.60
D	7.00 BSC.		
D1	6.75 BSC.		
E	7.00 BSC.		
E1	6.75 BSC.		
e	0.50 BSC.		
J			
K			
L	0.30	0.40	0.50

UNIT : mm

Figure 34: Package dimensions

NOTES :

1. JEDEC : MO-220-J.
2. DIE THICKNESS ALLOWABLE IS 0.305mm MAXIMUM (0.012 INCHES MAXIMUM).
3. ⚠2 DIMENSION APPLIES TO PLATED TERMINAL AND IS MEASURED BETWEEN 0.2 AND 0.25mm FROM TERMINAL TIP.
4. ⚠3 THE PIN #1 IDENTIFIER MUST BE PLACED ON THE TOP SURFACE OF THE PACKAGE BY USING INDENTATION MARK OR OTHER FEATURE OF PACKAGE BODY.
5. ⚠4 EXACT SHAPE AND SIZE OF THIS FEATURE IS OPTIONAL.
6. ⚠5 APPLIED FOR EXPOSED PAD AND TERMINALS. EXCLUDE EMBEDDING PART OF EXPOSED PAD FROM MEASURING.
7. ⚠6 APPLIED ONLY TO TERMINALS.
8. ⚠7 EXACT SHAPE OF EACH CORNER IS OPTIONAL.

Figure 35: Notes

The chip label contains the date code (X=stepping, YY=year, WW=week, LLLLLL.LL= lot ID, the dot and the last two digits are optional).

Figure 36: Chip label

9.3.2 Tape and reel information

The ET1200 is available as tape on reel.

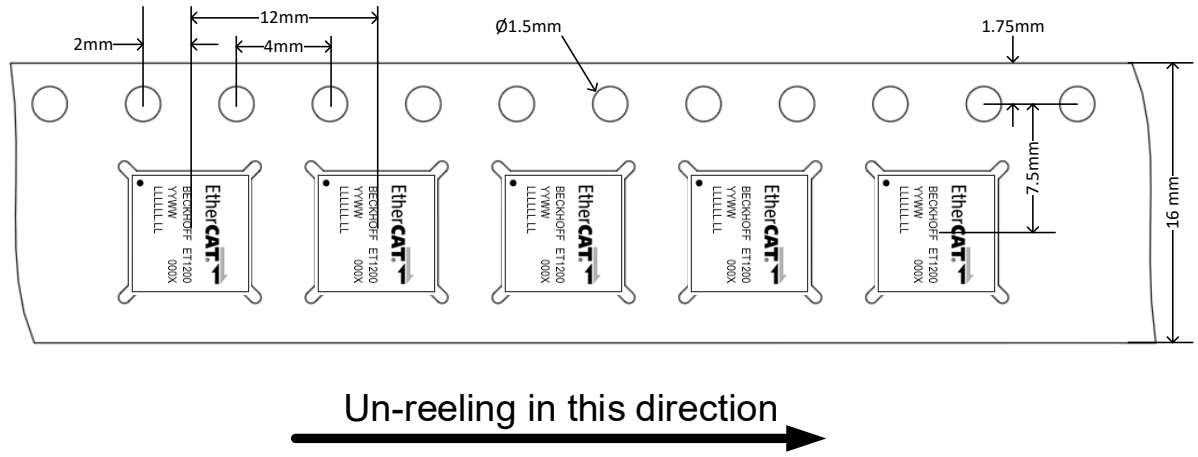

Figure 37: ET1200 tape information

Table 58: ET1200 reel information

Dimension	Value
Diameter	330 mm
Total width	16.5 mm

9.3.3 Moisture sensitivity and storage

The ET1200 is shipped in a sealed moisture barrier bag (dry-pack). There is a “caution” label on the dry-pack which contains all necessary information required for handling the devices. Refer to the JEDEC standards J-STD-020 and J-STD-033 for more details (http://www.jedec.org).

The information on the dry-pack takes precedence over information in this chapter.

The moisture sensitivity level of the ET1200 is MSL 3. The maximum shelf-life of the ET1200 packed in a dry-pack is one year after bag seal date. If the ET1200 is stored longer than one year, drying (baking) is required before soldering.

Drying and re-packaging can have negative effects on solderability and conducting surfaces. To minimize issues, the following steps should be taken:

- Visual inspection of the ET1200 devices
- solderability tests with some samples of the ET1200
- final test of the product using the ET1200 with focus on the ET1200 connections

Table 59: Absolute maximum storage conditions of ET1200 devices

Symbol	Parameter	Min	Max	Units
$\vartheta_{Storage}$	Storage temperature	-65	150	°C

9.4 Processing

9.4.1 PCB recommendations

PCB manufacturing technology is complex, please consult your PCB manufacturer and your PCB assembly house for advice.

9.4.2 Soldering profile

The following soldering profile is used to illustrate minimum and maximum values. For the actual soldering profile many factors have to be taken into consideration, e.g., solder paste characteristics, the PCB, plating, other components, materials, and process type.

Please consult your PCB assembly house for advice.

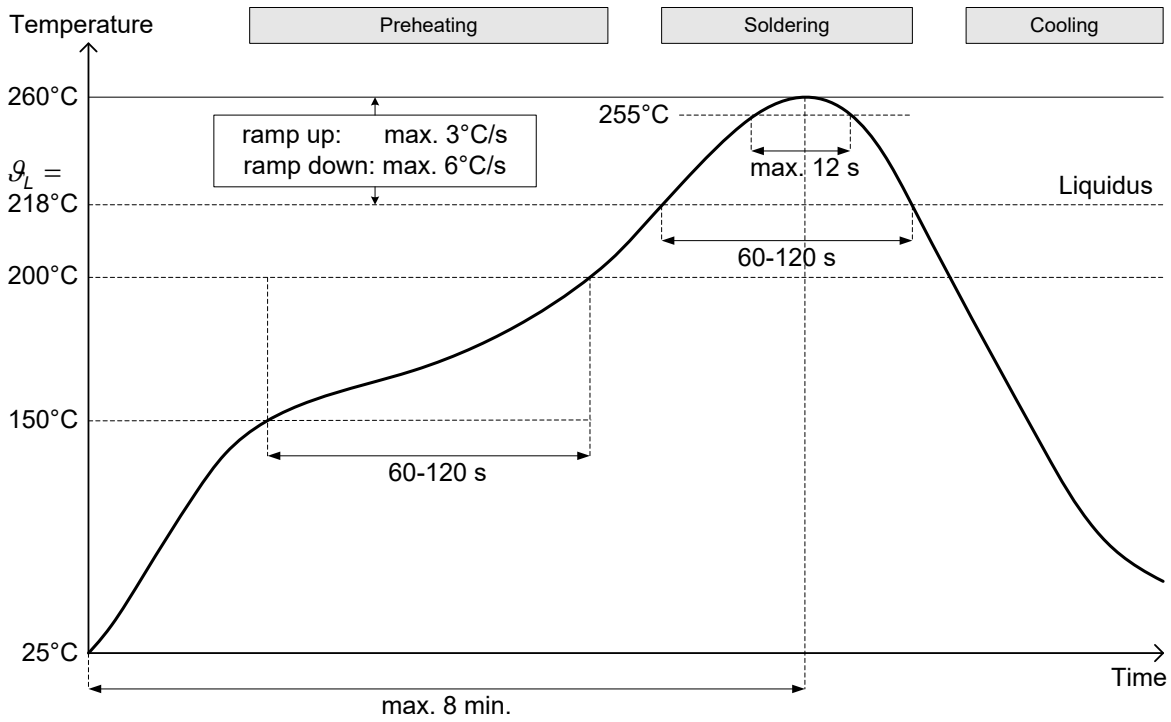

Figure 38: Soldering temperature and time

Table 60: Soldering temperature and time

Symbol	Parameter	Value	Abs. Max.	Units
ϑ_L	Liquidus temperature	218		°C
t_L	Time above ϑ_L (TAL)		120	s
ϑ_P	Peak temperature		260	°C
t_P	Time at ϑ_P		12	s
N_R	Number of reflow cycles		3	

NOTE: Recommended reading: “First Principles of Solder Reflow” by John Vivari.

10 Ordering codes

The ET1200 is not recommended for use in new designs.

The ordering codes for the ET1200 devices are composed like this:

ET1200-0000-NNNN

The code part NNNN identifies the size of the packing unit. Do not confuse the ordering codes with the stepping code ET1200-0000. You will always get the latest stepping while the ordering codes are unchanged.

11 Appendix

11.1 Support and service

Beckhoff and our 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.

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

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11.2 Beckhoff headquarters

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