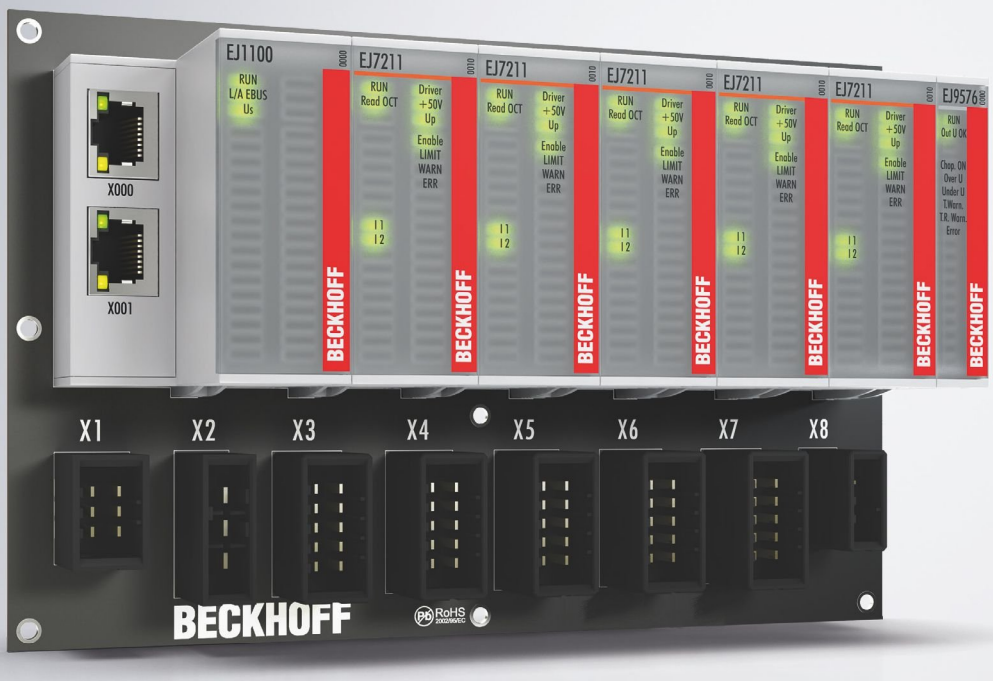
BECKHOFF New Automation Technology

Documentation | EN

EJ7334-0008

4-Channel motion interface, DC motor, 24 V DC, 3 A



2024-10-16 | Version: 1.5

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1 Foreword

1.1 Notes on the documentation

Intended audience

This description is only intended for the use of trained specialists in control and automation engineering who are familiar with the applicable national standards.
It is essential that the documentation and the following notes and explanations are followed when installing and commissioning these components.
The qualified personnel is obliged to always use the currently valid documentation.

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

Disclaimer

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

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

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

Trademarks

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

Patent Pending

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

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

Copyright

1.2 Safety instructions

Safety regulations

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

Exclusion of liability

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

Personnel qualification

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

Signal words

The signal words used in the documentation are classified below. In order to prevent injury and damage to persons and property, read and follow the safety and warning notices.

Personal injury warnings

⚠ DANGER
Hazard with high risk of death or serious injury.

⚠ WARNING
Hazard with medium risk of death or serious injury.

⚠ CAUTION
There is a low-risk hazard that could result in medium or minor injury.

Warning of damage to property or environment

NOTICE
The environment, equipment, or data may be damaged.

Information on handling the product

This information includes, for example:
recommendations for action, assistance or further information on the product.

1.3 Intended use

⚠ WARNING

Caution - Risk of injury!

EJ components may only be used for the purposes described below!

1.4 Signal distribution board

NOTICE

Signal distribution board

Make sure that the EtherCAT plug-in modules are used only on a signal distribution board that has been developed and manufactured in accordance with the Design Guide.

1.5 Documentation issue status

Version	Comment
1.5	• Update chapter *Technical data* • Update structure
1.4	• Chapter *Note on load voltage supply* added • Update structure
1.3	• Update chapter *Technical data*
1.2	• Update chapter *Technical data* • Update chapter *Pinout* • Update chapter *Installation of EJ modules* • Update structure
1.1	• Update chapter *Marking of EtherCAT plug-in modules* • Update structure
1.0	• First publication of EJ7334-0008

1.6 Guide through documentation

NOTICE

Further components of documentation

This documentation describes device-specific content. It is part of the modular documentation concept for Beckhoff I/O components. For the use and safe operation of the device / devices described in this documentation, additional cross-product descriptions are required, which can be found in the following table.

Title	Description
EtherCAT System Documentation (PDF)	• System overview • EtherCAT basics • Cable redundancy • Hot Connect • EtherCAT devices configuration
Design Guide EJ8xxx - Signal distribution board for standard EtherCAT plug-in modules (PDF)	Notes on the design of a signal distribution board for standard EtherCAT plug-in modules. • Requirements for the signal distribution board • Backplane mounting guidelines • Module placement • Routing guidelines
Infrastructure for EtherCAT/Ethernet (PDF)	Technical recommendations and notes for design, implementation and testing
Software Declarations I/O (PDF)	Open source software declarations for Beckhoff I/O components

The documentations can be viewed at and downloaded from the Beckhoff website (www.beckhoff.com) via:

- the “Documentation and Download” area of the respective product page,
- the Download finder,
- the Beckhoff Information System.

If you have any suggestions or proposals for our documentation, please send us an e-mail stating the documentation title and version number to: documentation@beckhoff.com

1.7 Marking of EtherCAT plug-in modules

Designation

A Beckhoff EtherCAT device has a 14-digit **technical designation**, made up as follows (e.g. EJ1008-0000-0017)

- **Order identifier**
  - family key: EJ
  - product designation: The first digit of product designation is used for assignment to a product group (e.g. EJ2xxx = digital output module).
  - Version number: The four digit version number identifies different product variants.
- **Revision number:**
  It is incremented when changes are made to the product.

The Order identifier and the revision number are printed on the side of EtherCAT plug-in modules (s. following illustration (A and B).

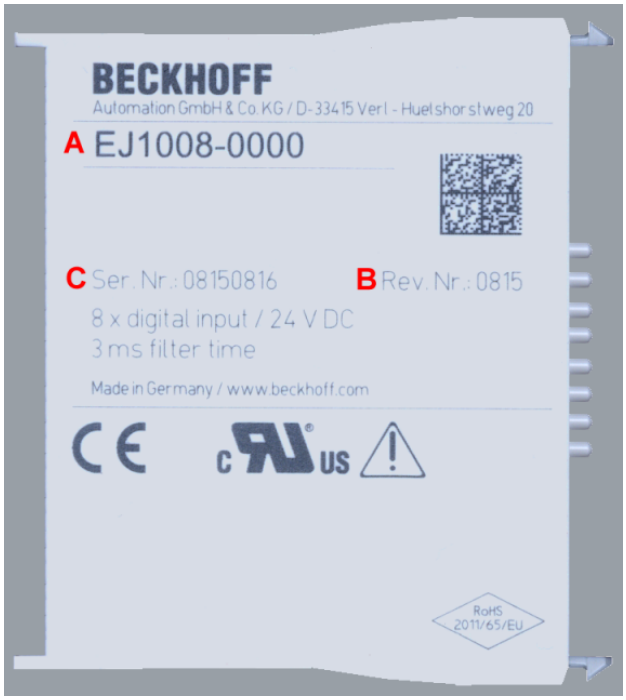


Fig. 1: Order identifier (A), Revision number (B) and serial number (C) using the example of EJ1008

Product group	Example		
	Product designation	Version	Revision
EtherCAT Coupler EJ11xx	EJ1101	-0022 (Coupler with external connectors, power supply module and optional ID switches	-0016
Digital input modules EJ1xxx	EJ1008 8-channel	-0000 (basic type)	-0017
Digital output modules EJ2xxx	EJ2521 1-channel	-0224 (2 x 24 V outputs)	-0016
Analog input modules EJ3xxx	EJ3318 8-channel thermocouple	-0000 (basic type)	-0017
Analog output modules EJ4xxx	EJ4134 4-channel	-0000 (basic type)	-0019
Special function modules EJ5xxx, EJ6xxx	EJ6224 IO-Link master	-0090 (with TwinSAFE SC)	-0016
Motion modules EJ7xxx	EJ7211 servomotor	-9414 (with ECT, STO and TwinSAFE SC)	-0029

Notes

- The elements mentioned above result in the **technical designation**. EJ1008-0000-0017 is used in the example below.
- EJ1008-0000 is the **order identifier**, in the case of “-0000” usually abbreviated to EJ1008.
- The **revision** -0017 shows the technical progress, such as the extension of features with regard to the EtherCAT communication, and is managed by Beckhoff.
  In principle, a device with a higher revision can replace a device with a lower revision, unless specified otherwise, e.g. in the documentation.
  Associated and synonymous with each revision there is usually a description (ESI, EtherCAT Slave Information) in the form of an XML file, which is available for download from the Beckhoff web site.
- The product designation, version and revision are read as decimal numbers, even if they are technically saved in hexadecimal.

Serial number

The serial number for EtherCAT plug-in modules is usually the 8-digit number printed on the side of the module (see following illustration C). The serial number indicates the configuration in delivery state and therefore refers to a whole production batch, without distinguishing the individual modules of a batch.

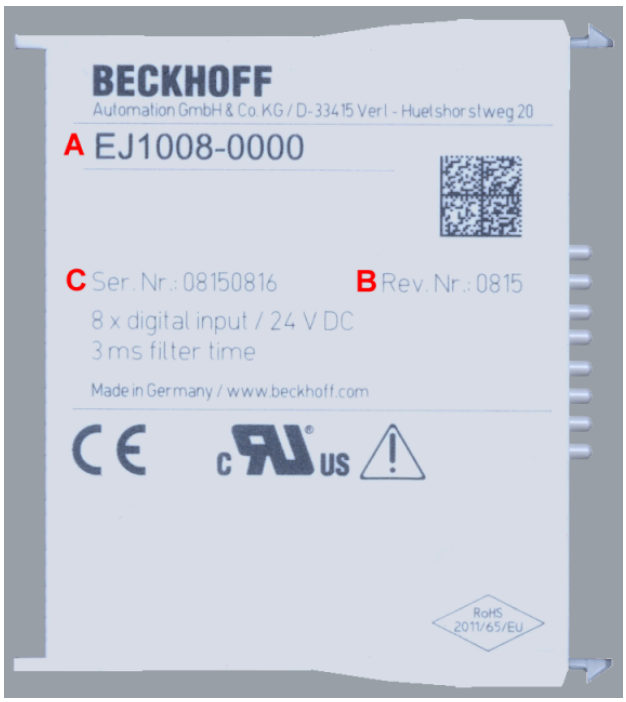


Fig. 2: Order identifier (A), revision number (B) and serial number (C) using the example of EJ1008

Serial number	Example serial number: 08 15 08 16
KK - week of production (CW, calendar week)	08 - week of production: 08
YY - year of production	15 - year of production: 2015
FF - firmware version	08 -f irmware version: 08
HH - hardware version	16 - hardware version: 16

1.7.1 Beckhoff Identification Code (BIC)

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

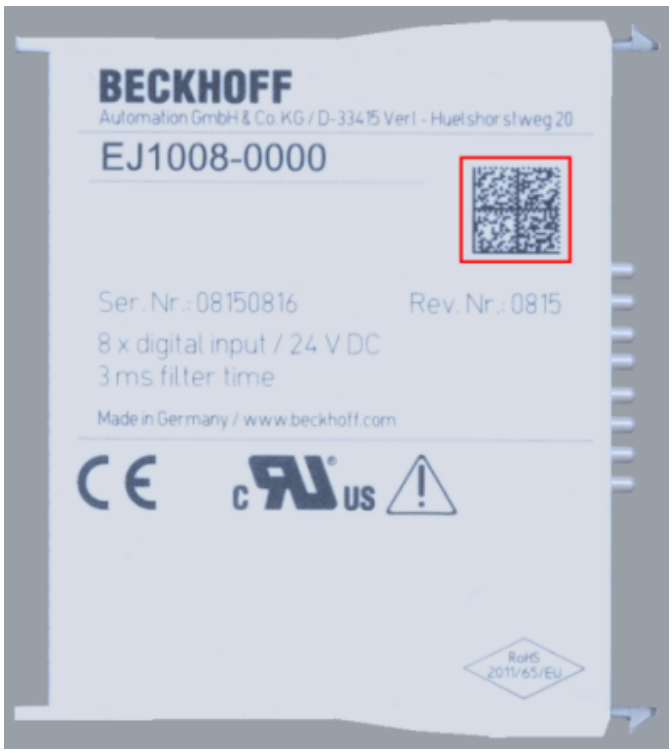


Fig. 3: BIC as data matrix code (DMC, code scheme ECC200)

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

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

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

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

Each piece of information can be uniquely identified using the so-called data identifier (ANSI MH10.8.2-2016). The data identifier is followed by a character string. Both together have a maximum length according to the table below. If the information is shorter, it shall be replaced by spaces. The data under positions 1-4 are always available.

The following information is contained:

Item no.	Type of information	Explanation	Data identifier	Number of digits incl. data identifier	Example
1	Beckhoff order number	**Beckhoff order number**	1P	8	1P072222
2	Beckhoff Traceability Number (BTN)	**Unique serial number, see note below**	S	12	SBTNk4p562d7
3	Article description	**Beckhoff article description, e.g. EL1008**	1K	32	1KEL1809
4	Quantity	**Quantity in packaging unit, e.g. 1, 10, etc.**	Q	6	Q1
5	Batch number	Optional: Year and week of production	2P	14	2P401503180016
6	ID/serial number	Optional: Present-day serial number system, e.g. with safety products	51S	12	51S678294104
7	Variant number	Optional: Product variant number on the basis of standard products	30P	32	30PF971 , 2*K183
...					

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

Structure of the BIC

Example of composite information from items 1 - 4 and with the above given example value on positon 6. The data identifiers are marked in bold font for better display:

1P072222**S**BTNk4p562d7**1K**EL1809 **Q**1 **51S**678294

Accordingly as DMC:

Fig. 4: Example DMC **1P**072222**S**BTNk4p562d7**1K**EL1809 **Q**1 **51S**678294

BTN

An important component of the BIC is the Beckhoff Traceability Number (BTN, item no. 2). The BTN is a unique serial number consisting of eight characters that will replace all other serial number systems at Beckhoff in the long term (e.g. batch designations on IO components, previous serial number range for safety products, etc.). The BTN will also be introduced step by step, so it may happen that the BTN is not yet coded in the BIC.

NOTICE

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

1.7.2 Electronic access to the BIC (eBIC)

Electronic BIC (eBIC)

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

The interface that the product can be electronically addressed by is crucial for the electronic readout.

K-bus devices (IP20, IP67)

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

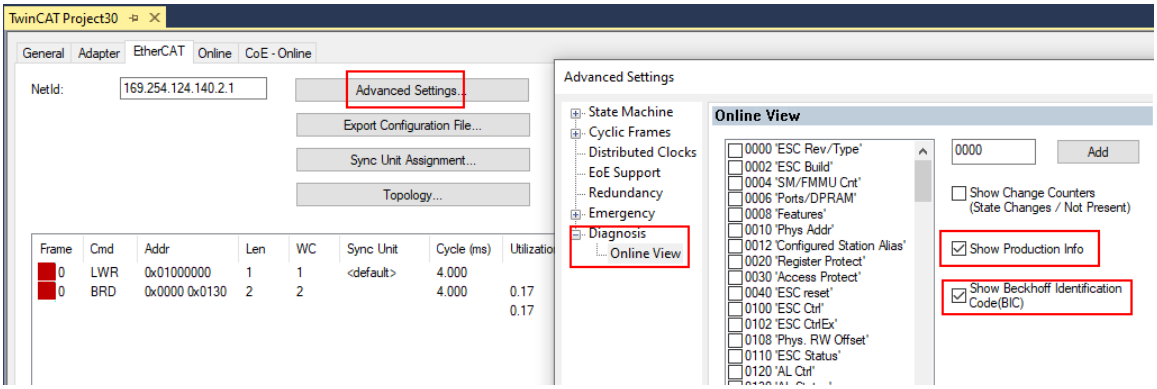
EtherCAT devices (IP20, IP67)

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

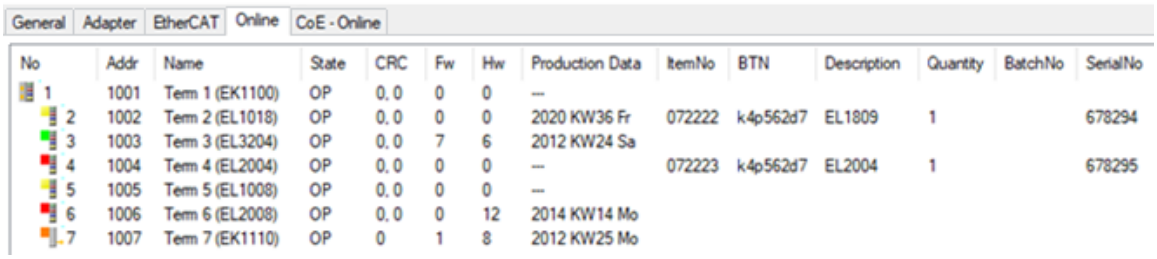
Beckhoff also stores the eBIC in the ESI-EEPROM. The eBIC was introduced into Beckhoff IO production (terminals, box modules) in 2020; as of 2023, implementation is largely complete.

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

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

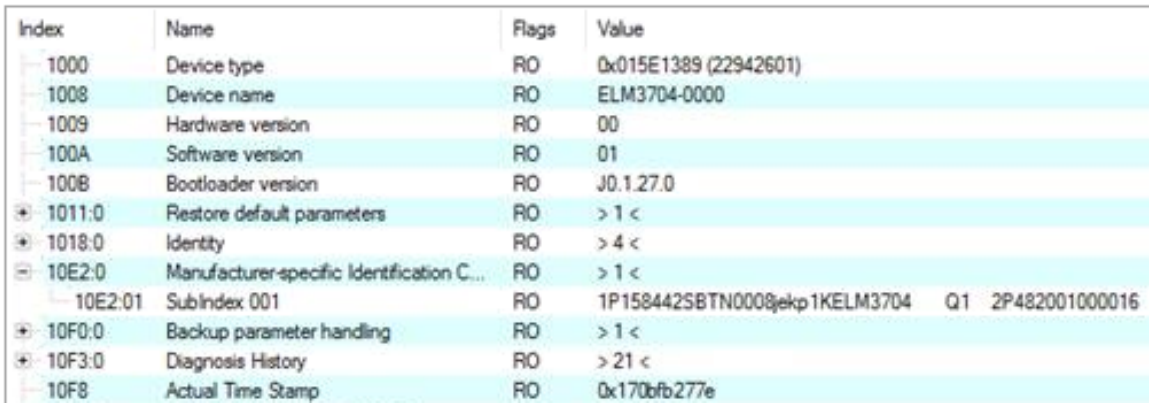


  - The BTN and its contents are then displayed:



  - Note: As shown in the figure, the production data HW version, FW version, and production date, which have been programmed since 2012, can also be displayed with "Show production info".
  - Access from the PLC: From TwinCAT 3.1. build 4024.24, the functions *FB_EcReadBIC* and *FB_EcReadBTN* for reading into the PLC are available in the Tc2_EtherCAT library from v3.3.19.0.
- EtherCAT devices with a CoE directory may also have the object 0x10E2:01 to display their own eBIC, which can also be easily accessed by the PLC:

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



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

  - The object 0x10E2 will be preferentially introduced into stock products in the course of necessary firmware revision.
  - From TwinCAT 3.1. build 4024.24, the functions *FB_EcCoEReadBIC* and *FB_EcCoEReadBTN* for reading into the PLC are available in the Tc2_EtherCAT library from v3.3.19.0
- The following auxiliary functions are available for processing the BIC/BTN data in the PLC in *Tc2_Utilities* as of TwinCAT 3.1 build 4024.24
  - F_SplitBIC: The function splits the Beckhoff Identification Code (BIC) sBICValue into its components using known identifiers and returns the recognized substrings in the ST_SplittedBIC structure as a return value
  - BIC_TO_BTN: The function extracts the BTN from the BIC and returns it as a return value
- Note: If there is further electronic processing, the BTN is to be handled as a string(8); the identifier "SBTN" is not part of the BTN.
- Technical background
  The new BIC information is written as an additional category in the ESI-EEPROM during device production. The structure of the ESI content is largely dictated by the ETG specifications, therefore the additional vendor-specific content is stored using a category in accordance with the ETG.2010. ID 03 tells all EtherCAT masters that they may not overwrite these data in the event of an update or restore the data after an ESI update.
  The structure follows the content of the BIC, see here. The EEPROM therefore requires approx. 50..200 bytes of memory.
- Special cases
  - If multiple hierarchically arranged ESCs are installed in a device, only the top-level ESC carries the eBIC information.
  - If multiple non-hierarchically arranged ESCs are installed in a device, all ESCs carry the eBIC information.
  - If the device consists of several sub-devices which each have their own identity, but only the top-level device is accessible via EtherCAT, the eBIC of the top-level device is located in the CoE object directory 0x10E2:01 and the eBICs of the sub-devices follow in 0x10E2:nn.

PROFIBUS; PROFINET, and DeviceNet devices

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

1.7.3 Certificates

- The EhterCAT plug-in modules meet the requirements of the EMC and Low Voltage Directive. The CE mark is printed on the side of the modules.
- The cRUus imprint identifies devices that meet product safety requirements according to U.S. and Canadian regulations.
- The warning symbol is a request to read the corresponding documentation. The documentations for EtherCAT plug-in modules can be downloaded from the Beckhoff homepage.

Fig. 5: Marking for CE and UL using EJ1008 as an example

2 System overview

Electronically, the EJxxxx EtherCAT plug-in modules are based on the EtherCAT I/O system. The EJ system consists of the signal distribution board and EtherCAT plug-in modules. It is also possible to connect an IPC to the EJ system.
The EJ system is suitable for mass production applications, applications with small footprint and applications requiring a low total weight.
The machine complexity can be extended by means of the following:

- reserve slots,
- the use of placeholder modules,
- linking of EtherCAT Terminals and EtherCAT Boxes via an EtherCAT connection.

The following diagram illustrates an EJ system. The components shown are schematic, to illustrate the functionality.

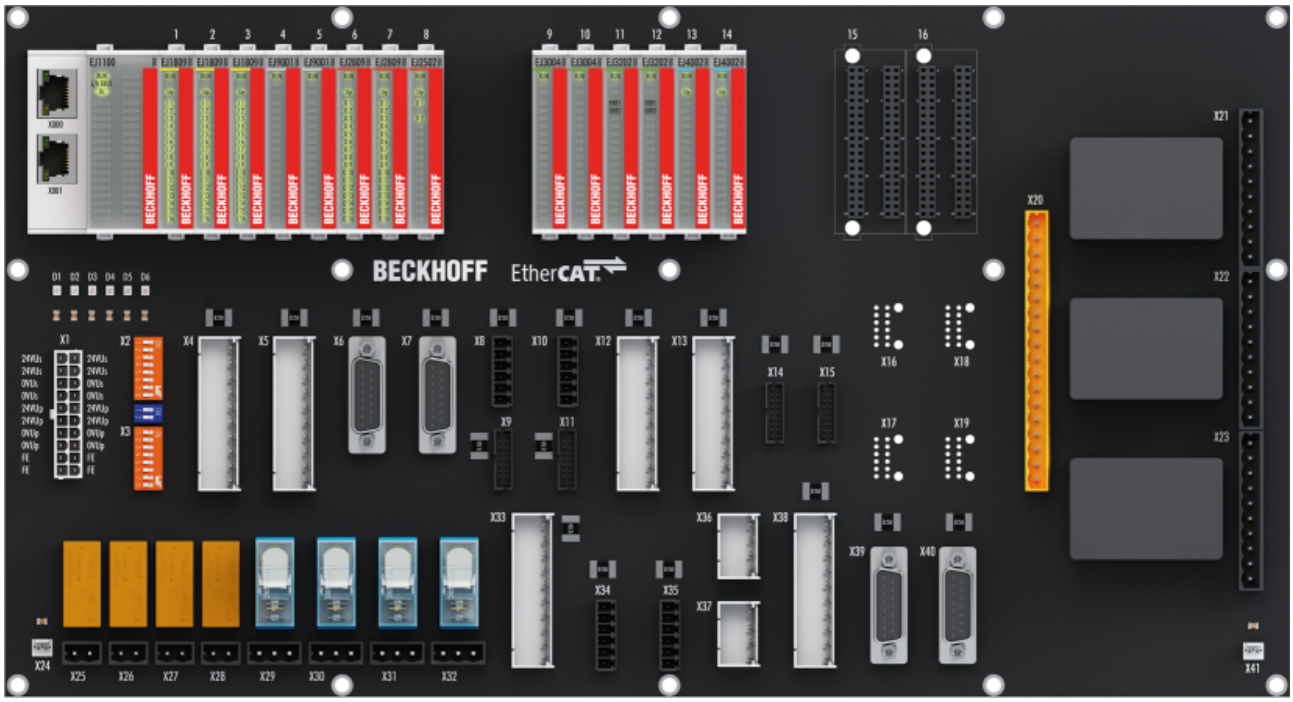


Fig. 6: EJ system sample

Signal distribution board

The signal distribution board distributes the signals and the power supply to individual application-specific plug connectors, in order to connect the controller to further machine modules. Using pre-assembled cable harnesses avoids the need for time-consuming connection of individual wires. Coded components reduce the unit costs and the risk of miswiring.
Beckhoff offers development of signal distribution boards as an engineering service. Customers have the option to develop their own signal distribution board, based on the design guide.

EtherCAT plug-in modules

Similar to the EtherCAT Terminal system, a module strand consists of a bus coupler and I/O modules. Almost all of the EtherCAT Terminals can also be manufactured in the EJ design as EtherCAT plug-in modules. The EJ modules are directly attached to the signal distribution board. The communication, signal distribution and supply take place via the contact pins at the rear of the modules and the PCB tracks of the signal distribution board. The coding pins at the rear serve as mechanical protection against incorrect connection. Color coding on the housing facilitates distinguishing of the modules.

3 EJ7334-0008 - Product description

3.1 Intrroduction

Fig. 7: EJ7334-0008

4-Channel motion interface, DC motor, 24 V_{DC}, 3 A

The EJ7334-0008 EtherCAT plug-in module enables direct operation of four DC motors and is electrically isolated from the E-bus.

The speed is preset by a 16 bit value from the automation unit.

The output stage is overload-proof.

If direction reversal is not required, up to eight motors can be operated unidirectionally on the EJ7334-0008.

3.2 Technical data

Technical data	EJ7334-0008
Technology	compact drive technology
Connection method	direct motor connection
Load type	DC brush motors, inductive > 1 mH
Number of channels	4 (bidirectional) / 8 (unidirectional)
Number of outputs	1 x DC motor per channel
Supply voltage electronics	24 V_{DC} (via distribution board)
Supply voltage power	8 V_{DC} … 24 V_{DC} (via distribution board)
Output current	From Hardware 01: ∑ 8.0 A, max. 3.0 A per channel (0 … +55°C) Hardware 00: ∑ 8.0 A, max. 3.0 A per channel (0 … +40°C) ∑ 6.0 A, max. 3.0 A per channel (0 … +45°C)
PWM clock frequency	16 kHz
Duty factor	0 … 98%
Resolution	max. 10 bit current, 16 bit speed
Current consumption from Up contacts	typ. 20 mA + motor current
Current consumption via E-bus	typ. 150 mA
Distributed Clocks	-
Electrical isolation	500 V (E-bus/field voltage)
Configuration	via EtherCAT master/CoE
Permissible ambient temperature range during operation	0°C ... +55°C (From Hardware 01) 0°C ... +45°C (Hardware 00)
Permissible ambient temperature range during storage	-25°C ... +85°C
Permissible relative air humidity	95%, no condensation
Operating altitude	max. 2,000 m
Dimensions (W x H x D)	approx. 12 mm x 66 mm x 55 mm
Weight	approx. 30 g
Mounting	on signal distribution board
Pollution degree	2
Mounting position	Standard [▶ 25]
Position of the coding pins [▶ 28]	1 and 8
Color coding	orange
Vibration/shock resistance	conforms to EN 60068-2-6 /EN 60068-2-27 (with corresponding signal distribution board)
EMC immunity/emission	conforms to EN 61000-6-2 /EN 61000-6-4 (with corresponding signal distribution board) according to IEC/EN 61800-3 (with corresponding signal distribution board)
EMC category	Category C3 - standard Category C2, C1 - auxiliary filter required
Protection class	EJ module: IP20 EJ system: dependent on the signal distribution board and housing
Approvals/markings*	CE

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

CE approval

The CE Marking refers to the EtherCAT plug-in module mentioned above.
If the EtherCAT plug-in module is used in the production of a ready-to-use end product (PCB in conjunction with a housing), the manufacturer of the end product must check compliance of the overall system with relevant directives and CE certification.
To operate the EtherCAT plug-in modules, they must be installed in a housing.

3.3 Pinout

EJ7334-0008				
Pin#		Signal		
1	2	U_{EBUS}	U_{EBUS}	**E-Bus contacts** The power supply U_{EBUS} is provided by the coupler and supplied from the supply voltage U_S of the EtherCAT coupler.
3	4	GND	GND	
5	6	RX0+	TX1+	
7	8	RX0-	TX1-	
9	10	GND	GND	
11	12	TX0+	RX1+	
13	14	TX0-	RX1-	
15	16	GND	GND	
17	18	PWM 1A	PWM 1B	**Signals and power supply of the motor**
19	20	PWM 2A	PWM 2B	
21	22	PWM 3A	PWM 3B	
23	24	PWM 4A	PWM 4B	
25	26	24V Motor	24V Motor	
27	28	24V Motor	24V Motor	
29	30	GND Motor	GND Motor	
31	32	GND Motor	GND Motor	
33	34	0V Up	0V Up	**U_P-Contacts** The peripheral voltage U_P supplies the electronics on the field side.
35	36	0V Up	24V Up	
37	38	24V Up	24V Up	
39	40	SGND	SGND	

Signal	Description
U_{EBUS}	E-Bus power supply 3.3 V
GND	E-Bus GND signal. Don't connect with 0V Up!
RXn+	Positive E-Bus receive signal
RXn-	Negative E-Bus receive signal
TXn+	Positive E-Bus transmit signal
TXn-	Negative E-Bus transmit signal
PWM 1A	Motor 1, Motor winding 1A
PWM 1B	Motor 1, Motor winding 1B
PWM 2A	Motor 2, Motor winding 2A
PWM 2B	Motor 2, Motor winding 2B
PWM 3A	Motor 3, Motor winding 3A
PWM 3B	Motor 3, Motor winding 3B
PWM 4A	Motor 4, Motor winding 4A
PWM 4B	Motor 4, Motor winding 4B
24 V Motor	Motor supply feed (24 V)
GND Motor	Motor supply feed (0 V)
0V Up	GND signal field side
24V Up	Power supply field side 24 V
SGND	Shield Ground

The PCB footprint can be downloaded from the Beckhoff homepage

NOTICE

Damage to devices possible!

Before installation and commissioning read the chapters Installation of EJ modules [▶ 21] and Commissioning [▶ 36]!

Shielding

Feedback signal, sensors and actuators should always be connected with shielded, twisted paired wires.

3.4 LEDs

LED No.	EJ7334-0008
A	RUN
B	Up
C	
1	EN1
2	EN2
3	EN3
4	EN4
5	EN5
6	EN6
7	EN7
8	EN8
9	
10	WARN
11	ERR
12	
13	
14	
15	
16	

Fig. 8: EJ7334-0008 - LEDs

LED	Color	Display	State	Description
RUN	green	off	Init	State of the EtherCAT State Machine: **INIT** = initialization of the plug-in module
		flashing	Pre-Operational	State of the EtherCAT State Machine: **PREOP =** function for mailbox communication and different default settings set
		single flash	Safe-Operational	State of the EtherCAT State Machine: **SAFEOP** = verification of the Sync-Manager channels and the distributed clocks. Outputs remain in safe state
		on	Operational	State of the EtherCAT State Machine: **OP =** normal operating state; mailbox and process data communication is possible
		flickering	Bootstrap	State of the EtherCAT State Machine: **BOOTSTRAP** = function for firmware updates of the plug-in module
Up	green	on	No power supply 24 V_{DC} is connected	
		off	Power supply 24 V_{DC} is connected	
EN1… EN8	green	on	The channel is enabled and free from errors.	
WARN	yellow	on	• 80°C temperature exceeded • DC link voltage lower than parameterized in CoE (0xF800:11) • DC link voltage higher than parameterized in CoE (0xF800:11) • The current consumption of a channel is currently above 4.5 A • The I2T utilization rate of a channel exceeds 100%.	
ERR	red	on	• 100°C temperature exceeded • DC link voltage lower than parameterized in CoE (0xF800:11) • DC link voltage higher than parameterized in CoE (0xF800:11) • The current consumption of a channel for a long time was above 4.5 A.	

4 Installation of EJ modules

4.1 Power supply for the EtherCAT plug-in modules

⚠ WARNING

Power supply from SELV / PELV power supply unit!

SELV / PELV circuits (safety extra-low voltage / protective extra-low voltage) according to IEC 61010-2-201 must be used to supply this device.

Notes:

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

The signal distribution board should have a power supply designed for the maximum possible current load of the module string. Information on the current required from the E-bus supply can be found for each module in the respective documentation in section “Technical data”, online and in the catalog. The power requirement of the module string is displayed in the TwinCAT System Manager.

E-bus power supply with EJ1100 or EJ1101-0022 and EJ940x

The EJ1100 Bus Coupler supplies the connected EJ modules with the E-bus system voltage of 3.3 V. The Coupler can accommodate a load up to 2.2 A. If a higher current is required, a combination of the coupler EJ1101-0022 and the power supply units EJ9400 (2.5 A) or EJ9404 (12 A) should be used. The EJ940x power supply units can be used as additional supply modules in the module string.

Depending on the application, the following combinations for the E-bus supply are available:

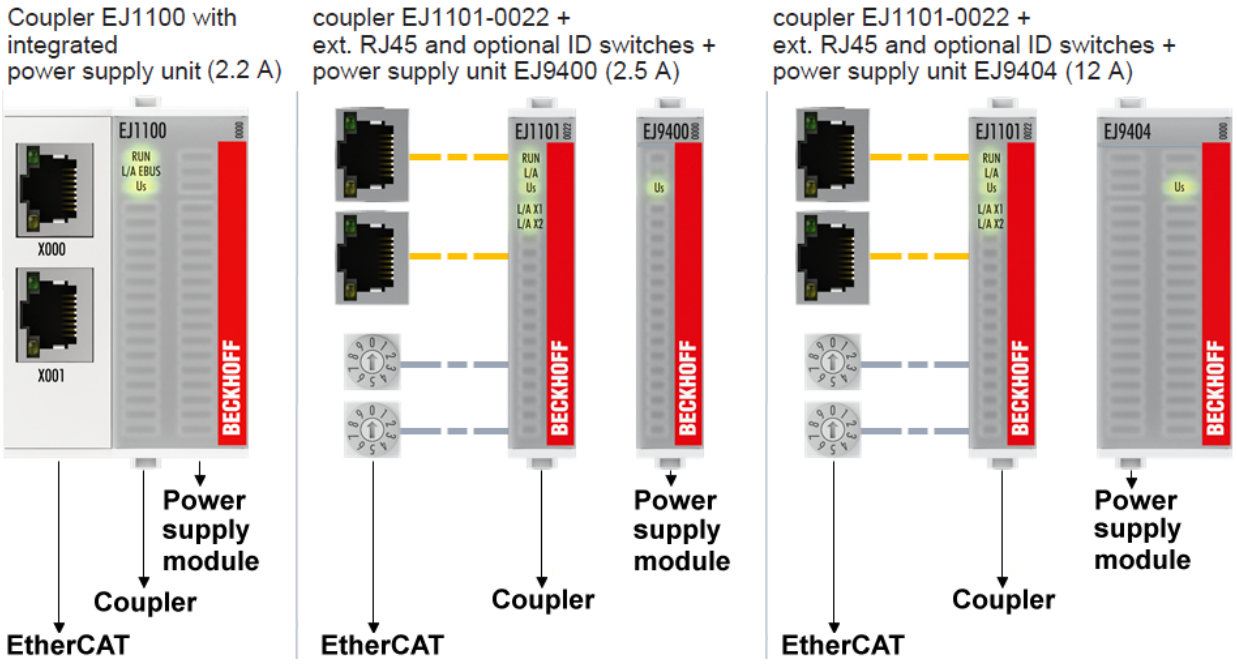


Fig. 9: E-bus power supply with EJ1100 or EJ1101-0022 + EJ940x

In the EJ1101-0022 coupler, the RJ45 connectors and optional ID switches are external and can be positioned anywhere on the signal distribution board, as required. This facilitates feeding through a housing.

The EJ940x power supply plug-in modules provide an optional reset function (see chapter Connection of the documentation for EJ9400 and EJ9404)

E-bus power supply with CXxxxx and EK1110-004x

The Embedded PC supplies the attached EtherCAT Terminals and the EtherCAT EJ coupler

- with a supply voltage Us of 24 V_{DC} (-15 %/+20 %). This voltage supplies the E-bus and the bus terminal electronics.
  The CXxxxx units supply the E-bus with up to 2,000 mA E-bus current. If a higher current is required due to the attached terminals, power feed terminals or power supply plug-in modules must be used for the E-bus supply.
- with a peripheral voltage Up of 24 V_{DC} to supply the field electronics.

The EK1110-004x EtherCAT EJ couplers relay the following parameters to the signal distribution board via the rear connector:

- the E-bus signals,
- the E-bus voltage U_{EBUS} (3.3 V) and
- the peripheral voltage U_P (24 V_{DC}).

Fig. 10: PCB with Embedded PC, EK1110-0043 and EJxxxx, rear view EK1110-0043

4.2 Note on load voltage supply

⚠ WARNING

Load voltage supply

Some devices permit an additional load voltage, e.g. 48 V DC, to be connected for the operation of a motor. In order to avoid stray currents on the protective conductor during operation, EN 60204-1:2018 provides for the possibility that the negative pole of the load voltage does not necessarily have to be connected to the protective conductor system (SELV).
Therefore, the load voltage supply should be designed as an SELV supply.

4.3 EJxxxx - dimensions

The EJ modules are compact and lightweight thanks to their design. Their volume is approx. 50% smaller than the volume of the EL terminals. A distinction is made between four different module types, depending on the width and the height:

Module type	Dimensions (W x H x D)	Sample in figure below
Coupler	44 mm x 66 mm x 55 mm	EJ1100 (ej_44_2xrj45_coupler)
Single module	12 mm x 66 mm x 55 mm	EJ1809 (ej_12_16pin_code13)
Double module	24 mm x 66 mm x 55 mm	EJ7342 (ej_24_2x16pin_code18)
Single module (long)	12 mm x 152 mm x 55 mm	EJ1957 (ej_12_2x16pin_extended_code4747)

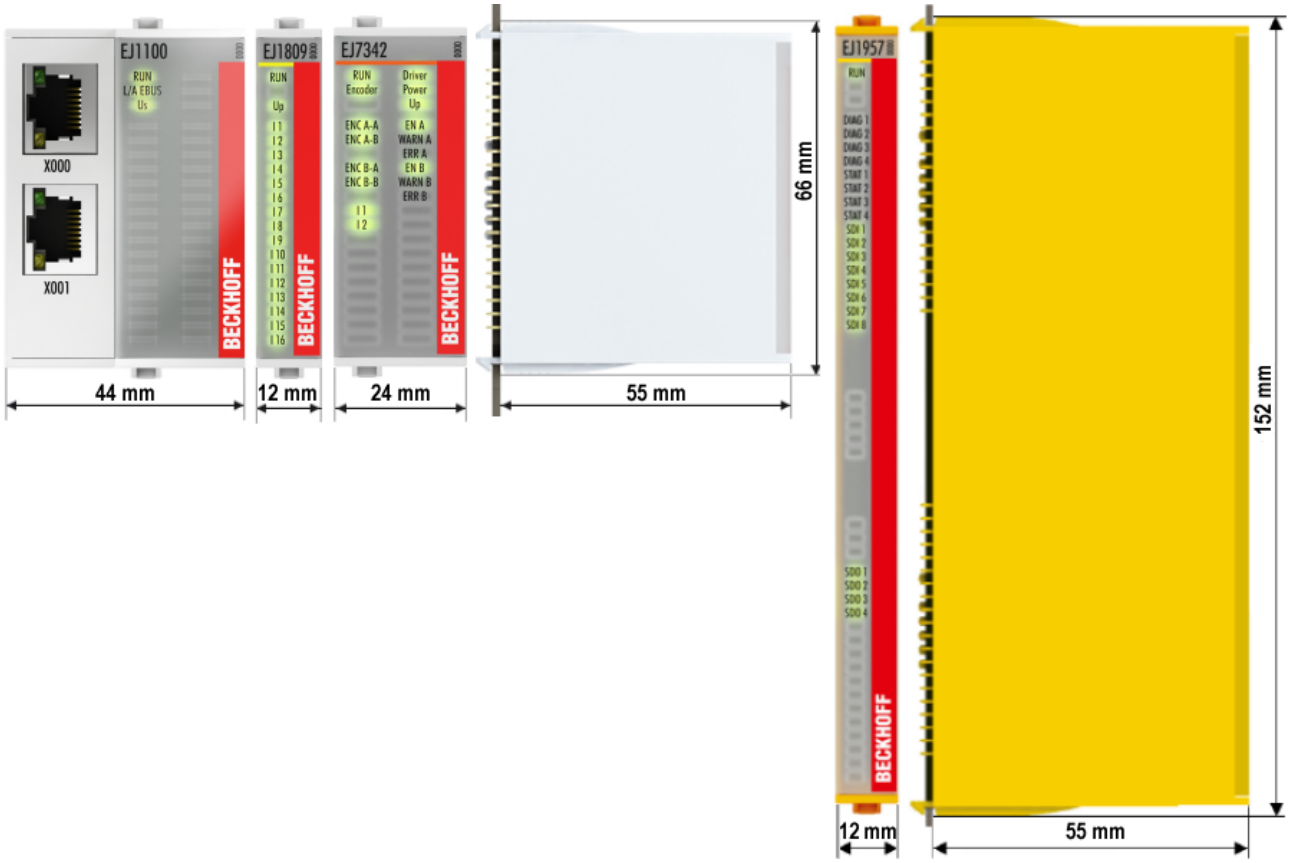


Fig. 11: EJxxxx - Dimensions

The technical drawings can be downloaded from the Beckhoff homepage. The drawings are named as described in the drawing below.

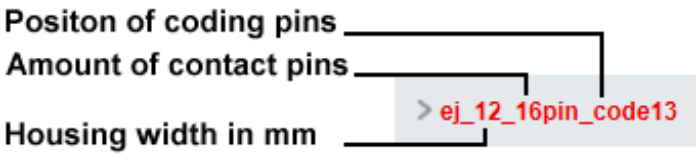


Fig. 12: Naming of the technical drawings

4.4 Installation positions and minimum distances

4.4.1 Minimum distances for ensuring installability

Note the dimensions shown in the following diagram for the design of the signal distribution board to ensure safe latching and simple assembly / disassembly of the modules.

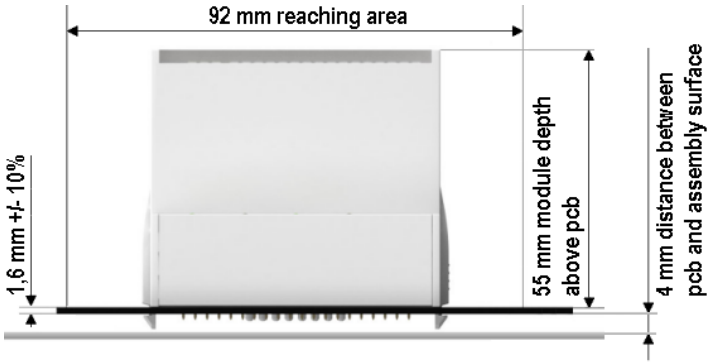


Fig. 13: Mounting distances EJ module - PCB

Observing the reaching area

A minimum reaching area of 92 mm is required for assembly / disassembly, in order to be able to reach the mounting tabs with the fingers.
Adherence to the recommended minimum distances for ventilation (see section Installation position [▶ 25]) ensures an adequate reaching area.

The signal distribution board must have a thickness of 1.6 mm and a minimum distance of 4 mm from the mounting surface, in order to ensure latching of the modules on the board.

4.4.2 Installation positions

NOTICE

Constraints regarding installation position and operating temperature range

Please refer to the technical data [▶ 18] for the installed components to ascertain whether any restrictions regarding the mounting position and/or the operating temperature range have been specified. During installation of modules with increased thermal dissipation, ensure adequate distance above and below the modules to other components in order to ensure adequate ventilation of the modules during operation!

The standard installation position is recommended. If a different installation position is used, check whether additional ventilation measures are required.

Ensure that the specified conditions (see Technical data) are adhered to!

Optimum installation position (standard)

For the optimum installation position the signal distribution board is installed horizontally, and the fronts of the EJ modules face forward (see Fig. *Recommended distances for standard installation position*). The modules are ventilated from below, which enables optimum cooling of the electronics through convection. “From below” is relative to the acceleration of gravity.

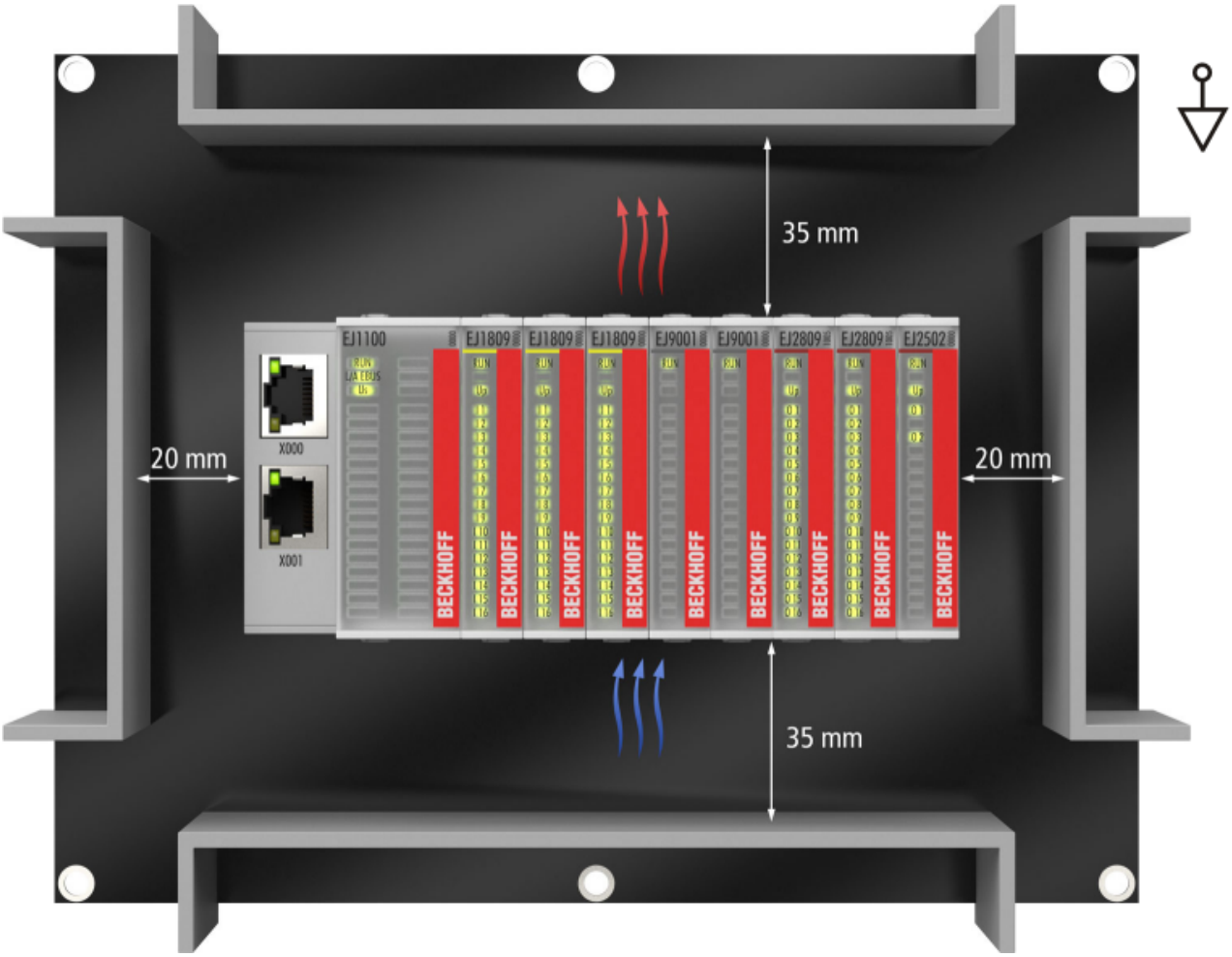


Fig. 14: Recommended distances for standard installation position

Compliance with the distances shown in Fig. *Recommended distances for standard installation position* is recommend. The recommended minimum distances should not be regarded as restricted areas for other components. The customer is responsible for verifying compliance with the environmental conditions described in the technical data. Additional cooling measures must be provided, if required.

Other installation positions

All other installation positions are characterized by a different spatial position of the signal distribution board, see Fig. *Other installation positions.*

The minimum distances to ambient specified above also apply to these installation positions.

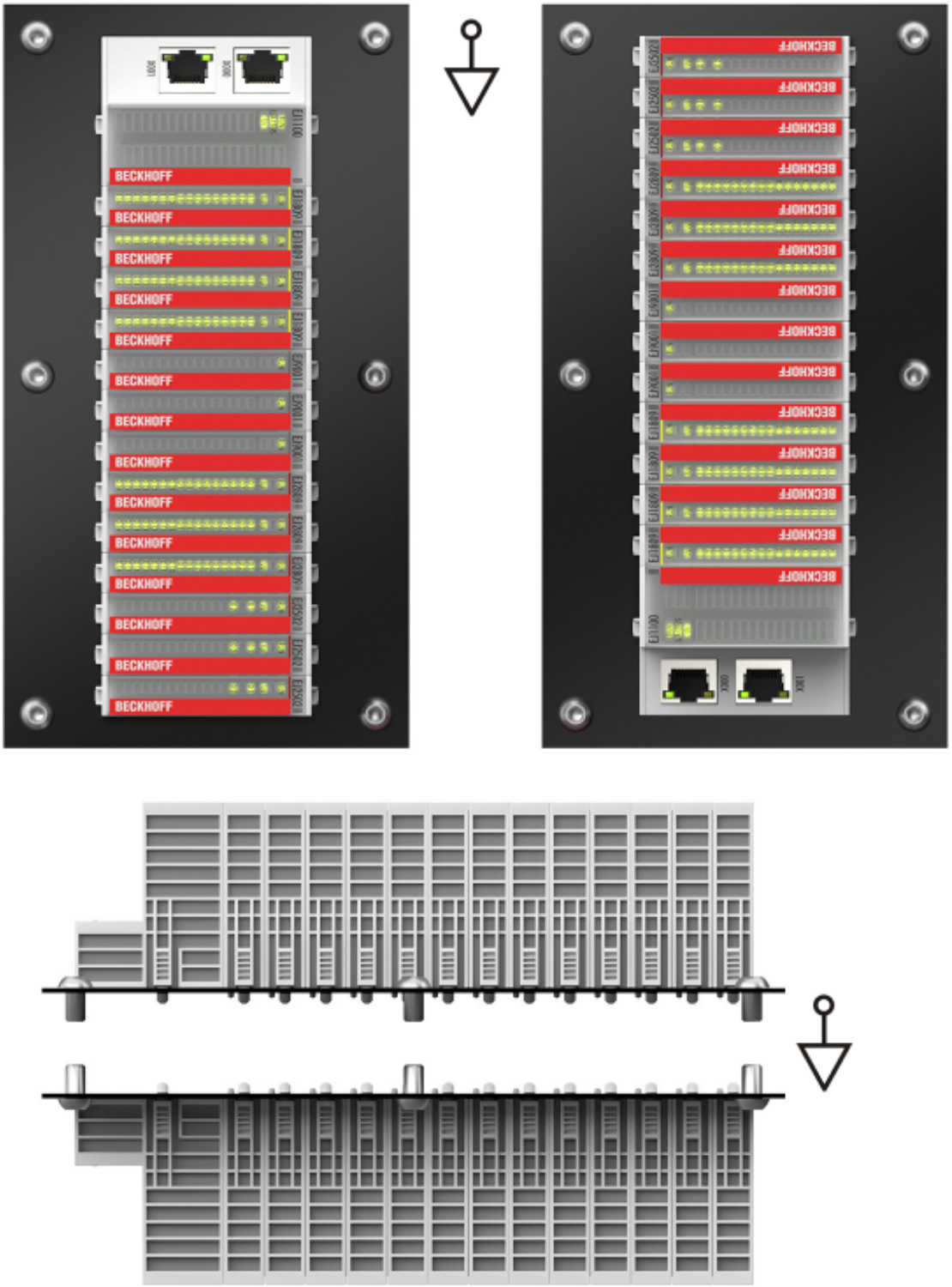


Fig. 15: Other installation positions

4.5 Codings

4.5.1 Color coding

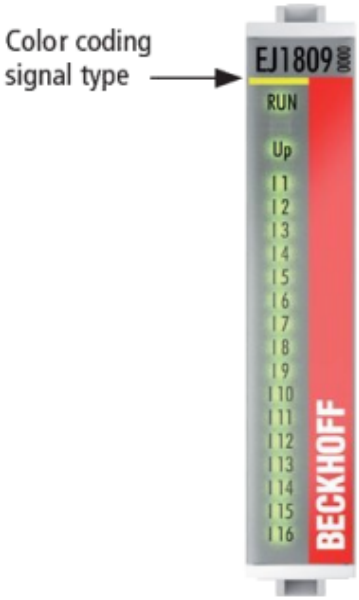


Fig. 16: EJ modules color code; sample: EJ1809

The EJ modules are color-coded for a better overview in the control cabinet (see diagram above). The color code indicates the signal type. The following table provides an overview of the signal types with corresponding color coding.

Signal type	Modules	Color
Coupler	EJ11xx	No color coding
Digital input	EJ1xxx	Yellow
Digital output	EJ2xxx	Red
Analog input	EJ3xxx	Green
Analog output	EJ4xxx	Blue
Position measurement	EJ5xxx	grey
Communication	EJ6xxx	grey
Motion	EJ7xxx	orange
System	EJ9xxx	grey

4.5.2 Mechanical position coding

The modules have two signal-specific coding pins on the underside (see Figs. B1 and B2 below). In conjunction with the coding holes in the signal distribution board (see Figs. A1 and A2 below), the coding pins provide an option for mechanical protection against incorrect connection. This significantly reduces the risk of error during installation and service.
Couplers and placeholder modules have no coding pins.

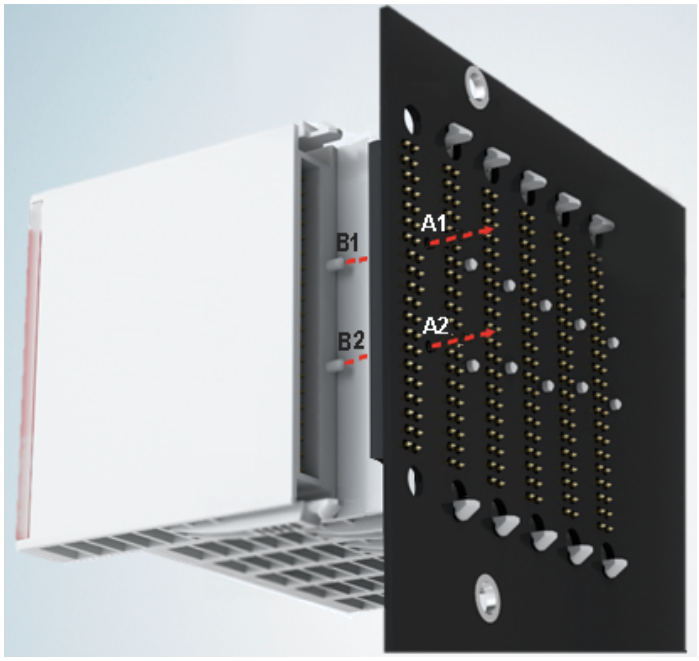


Fig. 17: Mechanical position coding with coding pins (B1 and B2) and coding holes (A1 and A2)

The following diagram shows the position of the position coding with position numbers on the left-hand side. Modules with the same signal type have the same coding. For sample, all digital input modules have the coding pins at positions one and three. There is no plug protection between modules with the same signal type. During installation the module type should therefore be verified based on the device name.

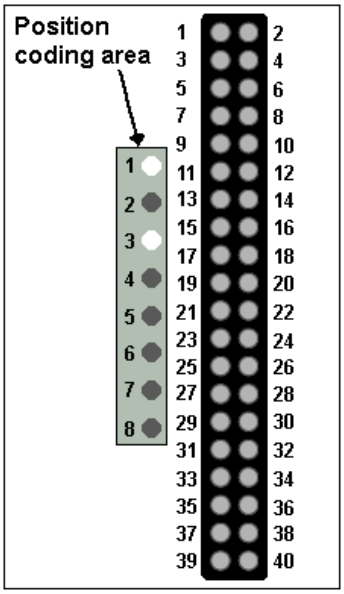


Fig. 18: Pin coding; sample: digital input modules

4.6 Installation on the signal distribution board

EJ modules are installed on the signal distribution board. The electrical connections between coupler and EJ modules are realized via the pin contacts and the signal distribution board.

The EJ components must be installed in a control cabinet or enclosure which must provide protection against fire hazards, environmental conditions and mechanical impact.

⚠ WARNING

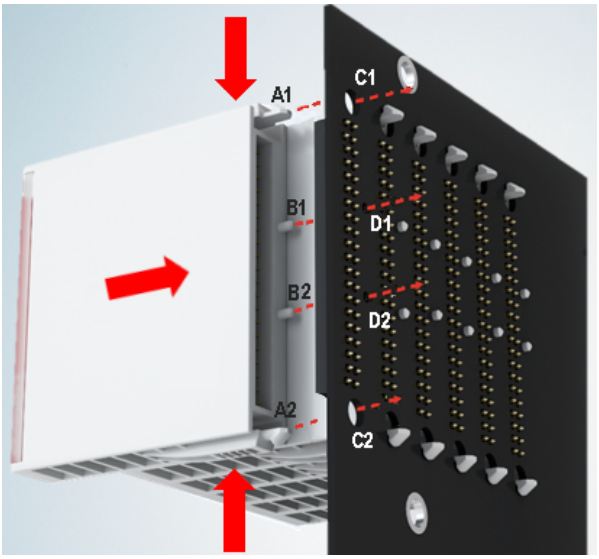
Risk of injury through electric shock and damage to the device!

Bring the module system into a safe, de-energized state before starting installation, disassembly or wiring of the modules.

NOTICE

Risk of damage to components through electrostatic discharge!

Observe the regulations for ESD protection.



A1 / A2: Latching lugs top / bottom
B1 / B2: Coding pins
C1 / C2: Mounting holes
D1 / D2: Coding holes

Installation of EJ modules

To install the modules on the signal distribution board proceed as follows:

1. Before the installation, ensure that the signal distribution board is securely connected to the mounting surface. Installation on an unsecured signal distribution board may result in damage to the board.
2. If necessary, check whether the positions of the coding pins (B) match the corresponding holes in the signal distribution board (D).
3. Compare the device name on the module with the information in the installation drawing.
4. Press the upper and the lower mounting tabs simultaneously and push the module onto the board while gently moving it up and down, until the module is latched securely.
   The required contact pressure can only be established and the maximum current carrying capacity ensured if the module is latched securely.
5. Use placeholder modules (EJ9001) to fill gaps in the module strand.

NOTICE

Ensure safe latching of the modules on the signal distribution board

- During installation ensure safe latching of the modules on the signal distribution board! The consequences of inadequate contact pressure include:

⇨ loss of quality of the transferred signals,

⇨ increased power dissipation of the contacts,

⇨ impairment of the service life.

4.7 Extension options

Three options are available for modifications and extensions of the EJ system.

- Replacing the placeholder modules with the function modules provided for the respective slot
- Assigning function modules specified for the respective slots for the reserve slots at the end of the module string
- Linking with EtherCAT Terminals and EtherCAT Box modules via an Ethernet/EtherCAT connection

4.7.1 Using placeholder modules for unused slots

The EJ9001 placeholder modules are used to close temporary gaps in the module strands (see Fig. A1 below). Gaps in the module strand cause interruption in EtherCAT communication and must be equipped with placeholder modules.
In contrast to the passive terminals of the EL series, the placeholder modules actively participate in the data exchange. Several placeholder modules can therefore be connected in series, without impairing the data exchange.
Unused slots at the end of the module strand can be left as reserve slots (see Fig. B1 below).

The machine complexity is extended (extended version) by allocating unused slots (see Figs. A2 below - Exchanging placeholder modules and B2 - Assigning reserve slots) according to the specifications for the signal distribution board.

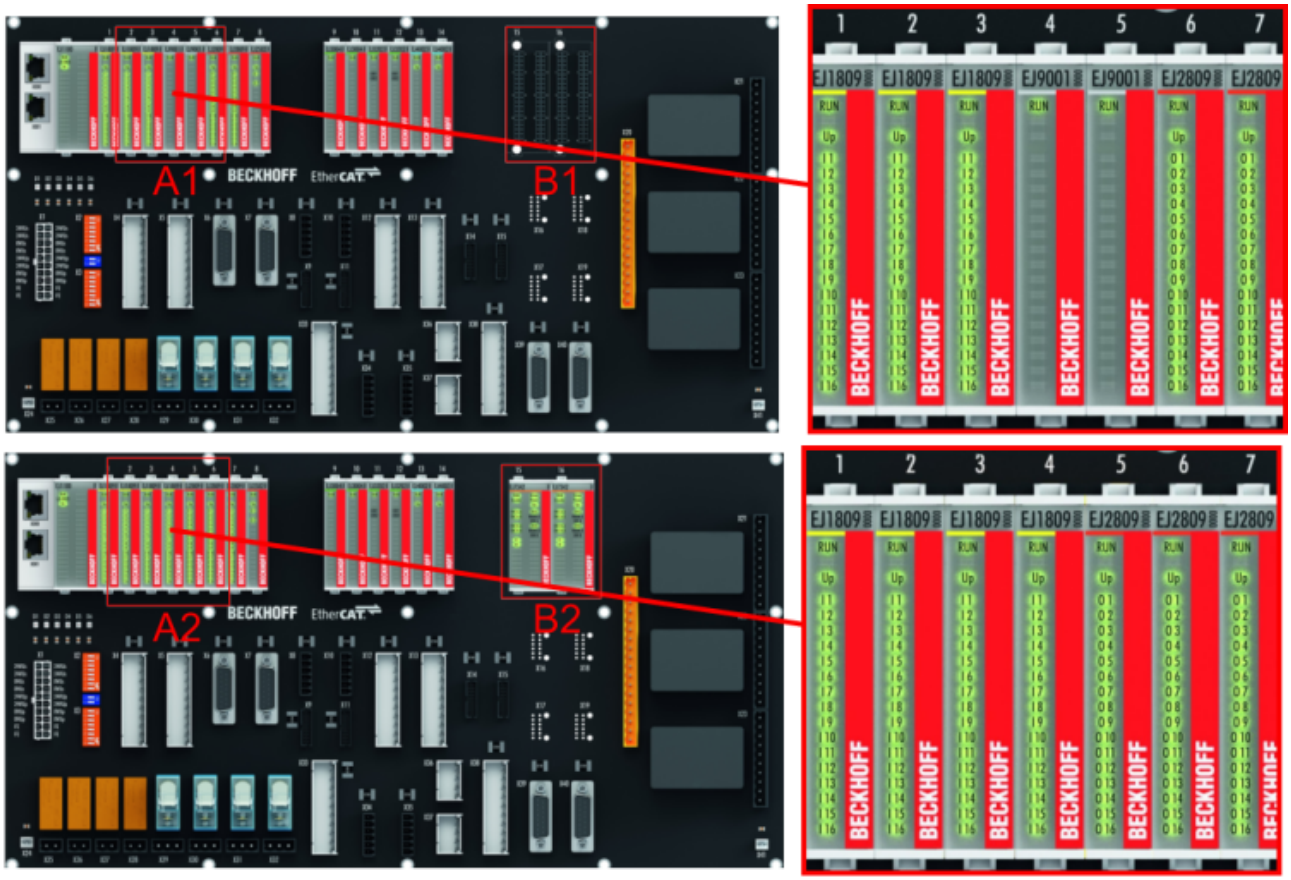


Fig. 19: Sample: Exchanging placeholder modules and assigning reserve slots

E-bus supply

Exchange the placeholder modules with other modules changes the current input from the E-Bus. Ensure that adequate power supply is provided.

4.7.2 Linking with EtherCAT Terminals and EtherCAT Box modules via an Ethernet/EtherCAT connection

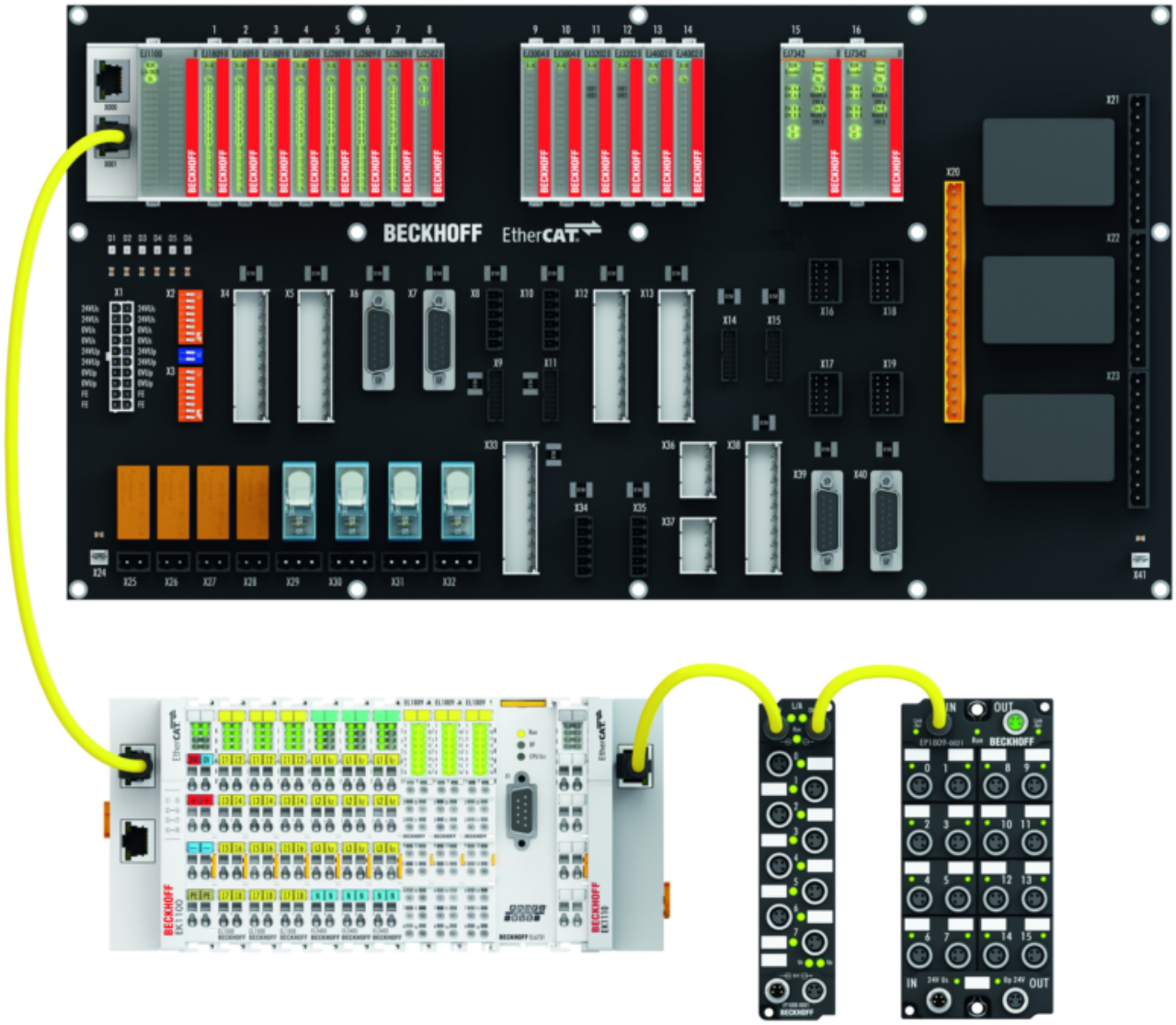


Fig. 20: Example of extension via an Ethernet/EtherCAT connection

4.8 IPC integration

Connection of CX and EL terminals via the EK1110-004x EtherCAT EJ coupler

The EK1110-0043 and EK1110-0044 EtherCAT EJ couplers connect the compact DIN-rail PCs of the CX series and attached EtherCAT Terminals (ELxxxx) with the EJ modules on the signal distribution board.

The EK1110-004x are supplied from the power supply unit of the Embedded PC.
The E-bus signals and the supply voltage of the field side U_P are routed directly to the PCB via a plug connector at the rear of the EtherCAT EJ couplers.

Due to the direct coupling of the Embedded PC and the EL terminals with the EJ modules on the PCB, no EtherCAT Extension (EK1110) or EtherCAT Coupler (EJ1100) is required.

The Embedded PC can be expanded with EtherCAT Terminals that are not yet available in the EJ system, for example.

Fig. 21: Example PCB with Embedded PC, EK1110-0043 and EJxxxx, rear view EK1110-0043

Connection of C6015 / C6017 via the EJ110x-00xx EtherCAT Coupler

Thanks to their ultra-compact design and versatile mounting options, the C6015 and C6017 IPCs are ideally suited for connection to an EJ system.

In combination with the ZS5000-0003 mounting set, it is possible to place the C6015 and C6017 IPCs compactly on the signal distribution board.
The EJ system is optimally connected to the IPC via the corresponding EtherCAT Cable (see following Fig. [A]).
The IPC can be supplied directly via the signal distribution board using the enclosed power plug (see Fig. [B] below).

NOTICE

Positioning on the signal distribution board

The dimensions and distances for placement and other details can be found in the Design Guide and the documentation for the individual components.

The figure below shows the connection of a C6015 IPC to an EJ system as an example. The components shown are schematic, to illustrate the functionality.

Fig. 22: Example for the connection of a C6015 IPC to an EJ system

4.9 Disassembly of the signal distribution board

⚠ WARNING

Risk of injury through electric shock and damage to the device!

Bring the module system into a safe, de-energized state before starting installation, disassembly or wiring of the modules.

Each module is secured through latching on the distribution board, which has to be released for disassembly.

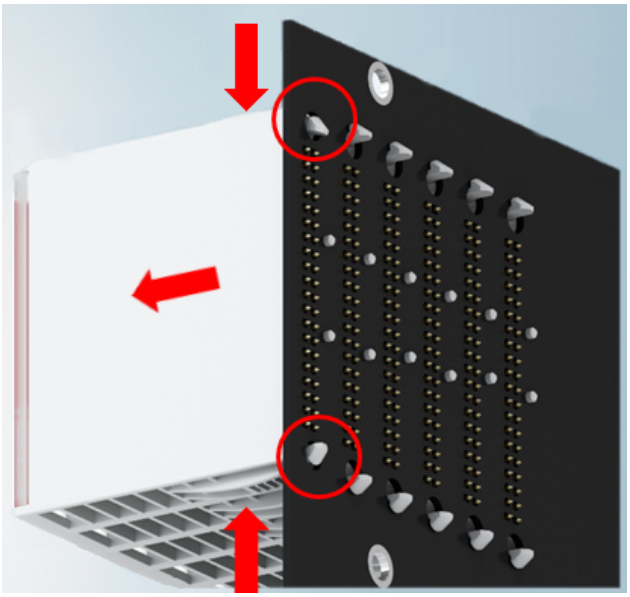


Fig. 23: Disassembly of EJ modules

To disassemble the module from the signal distribution board proceed as follows:

1. Before disassembly, ensure that the signal distribution board is securely connected to the mounting surface. Disassembly of an unsecured signal distribution board may result in damage to the board.
2. Press the upper and lower mounting tabs simultaneously and pull the module from board while gently moving it up and down.

4.10 Disposal

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

5 EtherCAT basics

Please refer to the EtherCAT System Documentation for the EtherCAT fieldbus basics.

6 Commissioning

A detailed documentation for the commissioning of the EJ7334-0008 module is in preparation.

6.1 EJ7334-0008 - Object description and parameterization

EtherCAT XML Device Description

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

NOTICE

Parameterization via the CoE list (CAN over EtherCAT)

The EtherCAT device is parameterized via the CoE - Online tab (with a double click on the respective object) or via the Process Data tab (assignment of PDOs). A detailed description can be found in the EtherCAT System-Documentation in chapter "EtherCAT subscriber configuration"

Please note the general CoE notes in the EtherCAT System Documentation in chapter "CoE-interface" when using/manipulating the CoE parameters:
- Keep a startup list if components have to be replaced
- Differentiation between online/offline dictionary,
- existence of current XML description
- use "CoE reload" for resetting changes

NOTICE

Risk of damage to the device

We strongly advise not to change settings in the CoE objects while the axis is active, since this could impair the control.

Introduction

The CoE overview contains objects for different intended applications:

Objects required for parameterization during commissioning:

- Restore object [▶ 37]
- Configuration data [▶ 38]
- Command object [▶ 39]

Profile-specific objects:

- Input data [▶ 39]
- Output data [▶ 39]
- Information and diagnosis data (channel specific) [▶ 40]
- Configuration data (vendor-specific) [▶ 40]
- Information and diagnosis data (device-specific) [▶ 41]

Standard objects [▶ 41]

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

6.1.1 Restore object

Index 1011 Restore default parameters

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

6.1.2 Cofiguration data

Index 80n0 DCM Motor Settings Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
80n0:0	DCM Motor Settings Ch. (n+1)	Max. Subindex	UINT8	RO	0x12 (18_{dec})
80n0:02	Nominal current	Motor nominal current **Unit:** 1 mA	UINT16	RW	0x03E8 (1000_{dec})
80n0:10	Ramp time	Ramp time **Unit:**1 s	UINT16	RW	0.250000 (2.500000e-01)
80n0:11	Motor I2T time constant	I^2T model time contsant **Unit:** 1 s	UINT16	RW	3.500000 (3.500000e+00)
80n0:12	Motor I2T warn level	I^2T model warn level **Unit:** 1 %	UINT16	RW	0x50 (80_{dec})

Index 80n2 DCM Features Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
80n2:0	DCM Features Ch.(n+1)	Max. Subindex	UINT8	RO	0x19 (25_{dec})
80n2:09	Invert motor polarity	Inverts the direction of rotation of the motor	BOOLEAN	RW	0x00 (0_{dec})
80n2:11	Select info data 1	Selection "Info data 1" 2: Motor coil current 5: Duty cycle ...: reserved 101: Internal temperature ...: reserved 104: Motor supply voltage 105: Motor I2T ...: reserved	UINT8	RW	0x02 (2_{dec})
80n2:19	Select info data 2	Selection "Info data 2" see subindex 0x80n2:11	UINT8	RW	0x05 (5_{dec})

Index F800 DCM Settings

Index (hex)	Name	Meaning	Data type	Flags	Default
F800:0	DCM Settings	Max. Subindex	UINT8	RO	0x06 (6_{dec})
F800:11	Min. DC link voltage	Minimum DC link voltage **Unit:** 1 mV	UINT32	RW	0x00001388 (5000_{dec})
F800:12	Max. DC link voltage	Maximum DC link voltage **Unit:** 1 mV	UINT32	RW	0x0007D00 (32000_{dec})

6.1.3 Command object

Index FB00 DCM Command

Index (hex)	Name	Meaning	Data type	Flags	Default
FB00:0	DCM Command	Max. Subindex	UINT8	RO	0x03 (3_{dec})
FB00:01	Request	reserved	OCTET-STRING[2]	RW	{0}
FB00:02	Status	0: Finished, no error, no response Command terminated without error and without response	UINT8	RO	0x00 (0_{dec})
		1: Finished, no error, response Command terminated without error and with response			
		2: Finished, error, no response Command terminated with error and without response			
		3: Finished, error, response Command terminated with error and with response			
		255: Executing Command is being executed			
FB00:03	Response	dependent on the request	OCTET-STRING[4]	RO	{0}

6.1.4 Input data

Index 60n0 DCM Inputs Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
60n0:0	DCM Inputs Ch.(n+1)	Max. Subindex	UINT8	RO	0x12 (18_{dec})
60n0:01	Ready to enable	Driver stage is ready for enabling	BOOLEAN	RO	0x00 (0_{dec})
60n0:02	Ready	Driver stage is ready for operation	BOOLEAN	RO	0x00 (0_{dec})
60n0:03	Warning	A warning has occurred	BOOLEAN	RO	0x00 (0_{dec})
60n0:04	Error	An error has occurred	BOOLEAN	RO	0x00 (0_{dec})
60n0:05	Moving positive	Driver stage is activated in positive direction	BOOLEAN	RO	0x00 (0_{dec})
60n0:06	Moving negative	Driver stage is activated in negative direction	BOOLEAN	RO	0x00 (0_{dec})
60n0:08	Limit	Limit value exceeded	BOOLEAN	RO	0x00 (0_{dec})
60n0:10	TxPDO Toggle	The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated.	BOOLEAN	RO	0x00 (0_{dec})
60n0:11	Info data 1	Synchronous information (selection via subindex 0x80n2:11 [▶ 38])	UINT16	RO	0x0000 (0_{dec})
60n0:12	Info data 2	Synchronous information (selection via subindex 0x80n2:19 [▶ 38])	UINT16	RO	0x0000 (0_{dec})

6.1.5 Output data

Index 70n0 DCM Outputs Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
70n0:0	DCM Outputs Ch.(n+1)	Max. Subindex	UINT8	RO	0x21 (33_{dec})
70n0:01	Enable	Activates the output stage	BOOLEAN	RO	0x00 (0_{dec})
70n0:02	Reset	All errors that may have occurred are reset by setting this bit (rising edge)	BOOLEAN	RO	0x00 (0_{dec})
70n0:21	Velocity	Set velocity specification	INT16	RO	0x0000 (0_{dec})

6.1.6 Information and diagnosis data (channel specific)

Index 90n0 DCM Info data Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
90n0:0	DCM Info data Ch.(n+1)	Max. Subindex	UINT8	RO	0x0A (10_{dec})
90n0:02	Motor coil voltage	Present coil voltage **Unit:** 1 mV	UINT16	RO	0x0000 (0_{dec})
90n0:03	Motor coil current	Present coil current **Unit:** 1 mA	INT16	RO	0x0000 (0_{dec})
90n0:06	Duty cycle	Present Duty-Cycle **Unit:** 1 %	INT8	RO	0x00 (0_{dec})
90n0:0A	Motor I2T temperature	Motor I^2T model utilization **Unit:** 1 %	INT8	RO	0x0000 (0_{dec})

6.1.7 Configuration data (vendor specific)

Index F80F DCM Vendor data

Index (hex)	Name	Meaning	Data type	Flags	Default
F80F:0	DCM Vendor data	Max. Subindex	UINT8	RO	0x09 (9_{dec})
F80F:04	Warning temperature	Threshold of the temperature warning **Unit:** 1 °C	INT8	RW	0x50 (80_{dec})
F80F:05	Switch off temperature	Switch-off temperature **Unit:** 1 °C	INT8	RW	0x64 (100_{dec})
F80F:07	Feature bits	Reserved	UINT32	RW	0x00000000 (00_{dec})
F80F:08	Module overall current	Total current of the module **Unit:** 1 mA	UINT32	RW	0x00001F40 (8000_{dec})
F80F:09	Module I2T time constant	I^2T model time constant of the module	UINT32	RW	3.500000 (3,500000e+00)

6.1.8 Information and diagnosis data (device specific)

Index F081 Download revision

Index (hex)	Name	Meaning	Data type	Flags	Default
F081:0	Download revision	Max. Subindex	UINT8	RO	0x01 (1_{dec})
F081:01	Revision number	The subindex 0xF081:01 (Download revision) describes the revision level of the module.	UINT32	RW	0x00000000 (0_{dec})

Index F900 DCM Info data

Index (hex)	Name	Meaning	Data type	Flags	Default
F900:0	DCM Info data	Max. Subindex	UINT8	RO	0x07 (7_{dec})
F900:02	Internal temperature	Internal terminal temperature **Unit:** 1 °C	INT8	RO	0x00 (0_{dec})
F900:05	Motor supply voltage	Load voltage **Unit:** 1 mV	UINT16	RO	0x0000 (0_{dec})
F900:07	Module I2T temperature	I^2T model utilization of the module **Unit:** 1 %	UINT16	RO	0x0000 (0_{dec})

6.1.9 Standard objects

Index 1000 Device type

Index (hex)	Name	Meaning	Data type	Flags	Default
1000:0	Device type	Device type of the EtherCAT slave: • The Lo-Word contains the CoE profile used (5001). • The Hi-Word contains the module profile according to the modular device profile.	UINT32	RO	0x20DE1389 (48108425_{dec})

Index 1008 Device name

Index (hex)	Name	Meaning	Data type	Flags	Default
1008:0	Device name	Device name of the EtherCAT slave	STRING	RO	EJ7334

Index 1009 Hardware version

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

Index 100A Software version

Index (hex)	Name	Meaning	Data type	Flags	Default
100A:0	Software version	Firmware version of the EtherCAT slave	STRING	RO	01

Index 100B Bootloader version

Index (hex)	Name	Meaning	Data type	Flags	Default
100B:0	Bootloader version	Bootloader version	STRING	RO	

Index 1018 Identity

Index (hex)	Name	Meaning	Data type	Flags	Default
1018:0	Identity	Information for identifying the slave	UINT8	RO	0x04 (4_{dec})
1018:01	Vendor ID	Vendor ID of the EtherCAT slave	UINT32	RO	0x00000002 (2_{dec})
1018:02	Product code	Product code of the EtherCAT slave	UINT32	RO	0x1CA62852 (480651346_{dec})
1018:03	Revision	Revision number of the EtherCAT slave; • The low word (bit 0-15) indicates the special terminal number. • The high word (bit 16-31) refers to the device description.	UINT32	RO	0x00000000 (0_{dec})
1018:04	Serial number	Serial number of the EtherCAT slave; • Low word ◦ The low byte (bit 0-7) of the low word contains the year of production. ◦ The high byte (bit 8-15) of the low word contains the week of production. • The high word (bit 16-31) is 0.	UINT32	RO	0x00000000 (0_{dec})

Index 10F0 Backup parameter handling

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

Index 10F3 Diagnosis History

Index (hex)	Name	Meaning	Data type	Flags	Default
10F3:0	Diagnosis History	Max. Subindex	UINT8	RO	0x15 (21_{dec})
10F3:01	Maximum Messages	Maximum number of stored messages. A maximum of 16 messages can be stored	UINT32	RO	0x00000000 0_{dec})
10F3:02	Newest Message	Subindex of the latest message	UINT8	RO	0x00 0_{dec})
10F3:03	Newest Acknowledged Message	Subindex of the last confirmed message	UINT8	RO	0x00 (0_{dec})
10F3:04	New Message available	Indicates that a new message is available	BOOLEAN	RO	0x00 (0_{dec})
10F3:05	Flags	not used	UINT16	RO	0x0000 (0_{dec})
10F3:06	Diagnosis Message 001	Message 1	OCTET-STRING[20]	RO	{0}
…	…	…	…	…	…
10F3:015	Diagnosis Message 016	Message 16	OCTET-STRING[20]	RO	{0}

Index 10F8 Actual Time Stamp

Index (hex)	Name	Meaning	Data type	Flags	Default
10F8:0	Actual Time Stamp	Timestamp	UINT64	RO	

Index 160n DCM RxPDO-Map Outputs Ch.1 (n = 0) to Ch.8 (n = 7)

Index (hex)	Name	Meaning	Data type	Flags	Default
160n:0	DCM RxPDO-Map Outputs Ch.(n+1)	PDO Mapping RxPDO 1	UINT8	RO	0x04 (4_{dec})
160n:01	SubIndex 001	1. PDO Mapping entry (object 0x70n0 (DCM Outputs Ch.(n+1), entry 0x01 (Enable))	UINT32	RO	0x70n0:01, 1
160n:02	SubIndex 002	2. PDO Mapping entry (object 0x70n0 (DCM Outputs Ch.(n+1), entry 0x02 (Reset))	UINT32	RO	0x70n0:02, 1
160n:03	SubIndex 003	3. PDO Mapping entry (14 bits align)	UINT32	RO	0x0000:00, 14
160n:04	SubIndex 004	4. PDO Mapping entry (object 0x70n0 (DCM Outputs Ch.(n+1), entry 0x21 (Velocity))	UINT32	RO	0x70n0:21, 16

Index 1A00 DCM TxPDO-Map Status Ch.1

Index (hex)	Name	Meaning	Data type	Flags	Default
1A00:0	DCM TxPDO-Map Status Ch.1	PDO Mapping TxPDO 1	UINT8	RO	0x10 (16_{dec})
1A00:01	SubIndex 001	1. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x01 (Ready to enable))	UINT32	RO	0x6000:01, 1
1A00:02	SubIndex 002	2. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x02 (Ready))	UINT32	RO	0x6000:02, 1
1A00:03	SubIndex 003	3. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x03 (Warning))	UINT32	RO	0x6000:03, 1
1A00:04	SubIndex 004	4. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x04 (Error))	UINT32	RO	0x6000:04, 1
1A00:05	SubIndex 005	5. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x05 (Moving positive))	UINT32	RO	0x6000:05, 1
1A00:06	SubIndex 006	6. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x06 (Moving negative))	UINT32	RO	0x6000:06, 1
1A00:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A00:08	SubIndex 008	8. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x08 (Limit))	UINT32	RO	0x6000:08, 1
1A00:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A00:0A	SubIndex 010	10. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6000:10, 1

Index 1A01 DCM TxPDO-Map Synchron info data Ch.1

Index (hex)	Name	Meaning	Data type	Flags	Default
1A01:0	DCM TxPDO-Map Synchron info data Ch.1	PDO Mapping TxPDO 2	UINT8	RO	0x02 (2_{dec})
1A01:01	SubIndex 001	1. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x11 (info data1))	UINT32	RO	0x6000:11, 16
1A01:02	SubIndex 002	2. PDO Mapping entry (object 0x6000 (DCM Inputs Ch.1), entry 0x12 (info data 2))	UINT32	RO	0x6000:12, 16

Index 1A02 DCM TxPDO-Map Status Ch.2

Index (hex)	Name	Meaning	Data type	Flags	Default
1A02:0	DCM TxPDO-Map Status Ch.2	PDO Mapping TxPDO 3	UINT8	RO	0x0A (10_{dec})
1A02:01	SubIndex 001	1. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x01 (Ready to enable))	UINT32	RO	0x6010:01, 1
1A02:02	SubIndex 002	2. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x02 (Ready))	UINT32	RO	0x6010:02, 1
1A02:03	SubIndex 003	3. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x03 (Warning))	UINT32	RO	0x6010:03, 1
1A02:04	SubIndex 004	4. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x04 (Error))	UINT32	RO	0x6010:04, 1
1A02:05	SubIndex 005	5. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x05 (Moving positive))	UINT32	RO	0x6010:05, 1
1A02:06	SubIndex 006	6. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x06 (Moving negative))	UINT32	RO	0x6010:06, 1
1A02:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A02:08	SubIndex 008	8. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x08 (Limit))	UINT32	RO	0x6010:08, 1
1A02:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A02:0A	SubIndex 010	10. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6010:10, 1

Index 1A03 DCM TxPDO-Map Synchron info data Ch.2

Index (hex)	Name	Meaning	Data type	Flags	Default
1A03:0	DCM TxPDO-Map Synchron info data Ch.2	PDO Mapping TxPDO 4	UINT8	RO	0x02 (2_{dec})
1A03:01	SubIndex 001	1. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x11 (Info data 1))	UINT32	RO	0x6010:11, 16
1A03:02	SubIndex 002	2. PDO Mapping entry (object 0x6010 (DCM Inputs Ch.2), entry 0x12 (Info data 2))	UINT32	RO	0x6010:12, 16

Index 1A04 DCM TxPDO-Map Status Ch.3

Index (hex)	Name	Meaning	Data type	Flags	Default
1A04:0	DCM TxPDO-Map Status Ch.3	PDO Mapping TxPDO 5	UINT8	RO	0x0A (10_{dec})
1A04:01	SubIndex 001	1. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x01 (Ready to enable))	UINT32	RO	0x6020:01, 1
1A04:02	SubIndex 002	2. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x02 (Ready))	UINT32	RO	0x6020:02, 1
1A04:03	SubIndex 003	3. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x03 (Warning))	UINT32	RO	0x6020:03, 1
1A04:04	SubIndex 004	4. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x04 (Error))	UINT32	RO	0x6020:04, 1
1A04:05	SubIndex 005	5. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x05 (Moving positive))	UINT32	RO	0x6020:05, 1
1A04:06	SubIndex 006	6. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x06 (Moving negative))	UINT32	RO	0x6020:06, 1
1A04:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A04:08	SubIndex 008	8. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x08 (Limit))	UINT32	RO	0x6020:08, 1
1A04:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A04:0A	SubIndex 010	10. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6020:10, 1

Index 1A05 DCM TxPDO-Map Synchron info data Ch.3

Index (hex)	Name	Meaning	Data type	Flags	Default
1A05:0	DCM TxPDO-Map Synchron info data Ch.3	PDO Mapping TxPDO 6	UINT8	RO	0x02 (2_{dec})
1A05:01	SubIndex 001	1. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x11 (Info data 1))	UINT32	RO	0x6020:11, 16
1A05:02	SubIndex 002	2. PDO Mapping entry (object 0x6020 (DCM Inputs Ch.3), entry 0x12 (Info data 2))	UINT32	RO	0x6020:12, 16

Index 1A06 DCM TxPDO-Map Status Ch.4

Index (hex)	Name	Meaning	Data type	Flags	Default
1A06:0	DCM TxPDO-Map Status Ch.4	PDO Mapping TxPDO 7	UINT8	RO	0x0A (10_{dec})
1A06:01	SubIndex 001	1. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x01 (Ready to enable))	UINT32	RO	0x6030:01, 1
1A06:02	SubIndex 002	2. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x02 (Ready))	UINT32	RO	0x6030:02, 1
1A06:03	SubIndex 003	3. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x03 (Warning))	UINT32	RO	0x6030:03, 1
1A06:04	SubIndex 004	4. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x04 (Error))	UINT32	RO	0x6030:04, 1
1A06:05	SubIndex 005	5. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x05 (Moving positive))	UINT32	RO	0x6030:05, 1
1A06:06	SubIndex 006	6. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x06 (Moving negative))	UINT32	RO	0x6030:06, 1
1A06:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A06:08	SubIndex 008	8. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x08 (Limit))	UINT32	RO	0x6030:08, 1
1A06:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A06:0A	SubIndex 010	10. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6030:10, 1

Index 1A07 DCM TxPDO-Map Synchron info data Ch.4

Index (hex)	Name	Meaning	Data type	Flags	Default
1A07:0	DCM TxPDO-Map Synchron info data Ch.4	PDO Mapping TxPDO 8	UINT8	RO	0x02 (2_{dec})
1A07:01	SubIndex 001	1. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x11 (Info data 1))	UINT32	RO	0x6030:11, 16
1A07:02	SubIndex 002	2. PDO Mapping entry (object 0x6030 (DCM Inputs Ch.4), entry 0x12 (Info data 2))	UINT32	RO	0x6030:12, 16

Index 1A08 DCM TxPDO-Map Status Ch.5

Index (hex)	Name	Meaning	Data type	Flags	Default
1A08:0	DCM TxPDO-Map Status Ch.5	PDO Mapping TxPDO 9	UINT8	RO	0x0A (10_{dec})
1A08:01	SubIndex 001	1. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x01 (Ready to enable))	UINT32	RO	0x6040:01, 1
1A08:02	SubIndex 002	2. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x02 (Ready))	UINT32	RO	0x6040:02, 1
1A08:03	SubIndex 003	3. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x03 (Warning))	UINT32	RO	0x6040:03, 1
1A08:04	SubIndex 004	4. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x04 (Error))	UINT32	RO	0x6040:04, 1
1A08:05	SubIndex 005	5. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x05 (Moving positive))	UINT32	RO	0x6040:05, 1
1A08:06	SubIndex 006	6. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x06 (Moving negative))	UINT32	RO	0x6040:06, 1
1A08:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A08:08	SubIndex 008	8. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x08 (Limit))	UINT32	RO	0x6040:08, 1
1A08:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A08:0A	SubIndex 010	10. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6040:10, 1

Index 1A09 DCM TxPDO-Map Synchron info data Ch.5

Index (hex)	Name	Meaning	Data type	Flags	Default
1A09:0	DCM TxPDO-Map Synchron info data Ch.5	PDO Mapping TxPDO 10	UINT8	RO	0x02 (2_{dec})
1A09:01	SubIndex 001	1. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x11 (Info data 1))	UINT32	RO	0x6040:11, 16
1A09:02	SubIndex 002	2. PDO Mapping entry (object 0x6040 (DCM Inputs Ch.5), entry 0x12 (Info data 2))	UINT32	RO	0x6040:12, 16

Index 1A0A DCM TxPDO-Map Status Ch.6

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0A:0	DCM TxPDO-Map Status Ch.6	PDO Mapping TxPDO 11	UINT8	RO	0x0A (10_{dec})
1A0A:01	SubIndex 001	1. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x01 (Ready to enable))	UINT32	RO	0x6050:01, 1
1A0A:02	SubIndex 002	2. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x02 (Ready))	UINT32	RO	0x6050:02, 1
1A0A:03	SubIndex 003	3. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x03 (Warning))	UINT32	RO	0x6050:03, 1
1A0A:04	SubIndex 004	4. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x04 (Error))	UINT32	RO	0x6050:04, 1
1A0A:05	SubIndex 005	5. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x05 (Moving positive))	UINT32	RO	0x6050:05, 1
1A0A:06	SubIndex 006	6. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x06 (Moving negative))	UINT32	RO	0x6050:06, 1
1A0A:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A0A:08	SubIndex 008	8. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x08 (Limit))	UINT32	RO	0x6050:08, 1
1A0A:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A0A:0A	SubIndex 010	10. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6050:10, 1

Index 1A0B DCM TxPDO-Map Synchron info data Ch.6

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0B:0	DCM TxPDO-Map Synchron info data Ch.6	PDO Mapping TxPDO 12	UINT8	RO	0x02 (2_{dec})
1A0B:01	SubIndex 001	1. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x11 (Info data 1))	UINT32	RO	0x6050:11, 16
1A0B:02	SubIndex 002	2. PDO Mapping entry (object 0x6050 (DCM Inputs Ch.6), entry 0x12 (Info data 2))	UINT32	RO	0x6050:12, 16

Index 1A0C DCM TxPDO-Map Status Ch.7

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0C:0	DCM TxPDO-Map Status Ch.7	PDO Mapping TxPDO 13	UINT8	RO	0x0A (10_{dec})
1A0C:01	SubIndex 001	1. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x01 (Ready to enable))	UINT32	RO	0x6060:01, 1
1A0C:02	SubIndex 002	2. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x02 (Ready))	UINT32	RO	0x6060:02, 1
1A0C:03	SubIndex 003	3. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x03 (Warning))	UINT32	RO	0x6060:03, 1
1A0C:04	SubIndex 004	4. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x04 (Error))	UINT32	RO	0x6060:04, 1
1A0C:05	SubIndex 005	5. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x05 (Moving positive))	UINT32	RO	0x6060:05, 1
1A0C:06	SubIndex 006	6. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x06 (Moving negative))	UINT32	RO	0x6060:06, 1
1A0C:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A0C:08	SubIndex 008	8. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x08 (Limit))	UINT32	RO	0x6060:08, 1
1A0C:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A0C:0A	SubIndex 010	10. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6060:10, 1

Index 1A0D DCM TxPDO-Map Synchron info data Ch.7

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0D:0	DCM TxPDO-Map Synchron info data Ch.7	PDO Mapping TxPDO 14	UINT8	RO	0x02 (2_{dec})
1A0D:01	SubIndex 001	1. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x11 (Info data 1))	UINT32	RO	0x6060:11, 16
1A0D:02	SubIndex 002	2. PDO Mapping entry (object 0x6060 (DCM Inputs Ch.7), entry 0x12 (Info data 2))	UINT32	RO	0x6060:12, 16

Index 1A0E DCM TxPDO-Map Status Ch.8

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0E:0	DCM TxPDO-Map Status Ch.7	PDO Mapping TxPDO 15	UINT8	RO	0x0A (10_{dec})
1A0E:01	SubIndex 001	1. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x01 (Ready to enable))	UINT32	RO	0x6070:01, 1
1A0E:02	SubIndex 002	2. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x02 (Ready))	UINT32	RO	0x6070:02, 1
1A0E:03	SubIndex 003	3. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x03 (Warning))	UINT32	RO	0x6070:03, 1
1A0E:04	SubIndex 004	4. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x04 (Error))	UINT32	RO	0x6070:04, 1
1A0E:05	SubIndex 005	5. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x05 (Moving positive))	UINT32	RO	0x6070:05, 1
1A0E:06	SubIndex 006	6. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x06 (Moving negative))	UINT32	RO	0x6070:06, 1
1A0E:07	SubIndex 007	7. PDO Mapping entry (1 bit align)	UINT32	RO	0x0000:00, 1
1A0E:08	SubIndex 008	8. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x08 (Limit))	UINT32	RO	0x6070:08, 1
1A0E:09	SubIndex 009	9. PDO Mapping entry (7 bits align)	UINT32	RO	0x0000:00, 7
1A0E:0A	SubIndex 010	10. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x10 (TxPDO Toggle))	UINT32	RO	0x6070:10, 1

Index 1A0F DCM TxPDO-Map Synchron info data Ch.8

Index (hex)	Name	Meaning	Data type	Flags	Default
1A0F:0	DCM TxPDO-Map Synchron info data Ch.8	PDO Mapping TxPDO 16	UINT8	RO	0x02 (2_{dec})
1A0F:01	SubIndex 001	1. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x11 (Info data 1))	UINT32	RO	0x6070:11, 16
1A0F:02	SubIndex 002	2. PDO Mapping entry (object 0x6070 (DCM Inputs Ch.8), entry 0x12 (Info data 2))	UINT32	RO	0x6070:12, 16

Index 1C00 Sync manager type

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

Index 1C12 RxPDO assign

Index (hex)	Name	Meaning	Data type	Flags	Default
1C12:0	RxPDO assign	PDO Assign Outputs	UINT8	RW	0x08 (8_{dec})
1C12:01	SubIndex 001	1. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1600 (5632_{dec})
1C12:02	SubIndex 002	2. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1601 (5633_{dec})
1C12:03	SubIndex 003	3. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1602 (5634_{dec})
1C12:04	SubIndex 004	4. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1603 (5635_{dec})
1C12:05	SubIndex 005	5. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1604 (5636_{dec})
1C12:06	SubIndex 006	6. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1605 (5637_{dec})
1C12:07	SubIndex 007	7. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1606 (5638_{dec})
1C12:08	SubIndex 008	8. allocated RxPDO (contains the index of the associated RxPDO mapping object)	UINT16	RW	0x1607 (5639_{dec})

Index 1C13 TxPDO assign

Index (hex)	Name	Meaning	Data type	Flags	Default
1C13:0	TxPDO assign	PDO Assign Inputs	UINT8	RW	0x08 (8_{dec})
1C13:01	SubIndex 001	1. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A00 (6656_{dec})
1C13:02	SubIndex 002	2. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A02 (6658_{dec})
1C13:03	SubIndex 003	3. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A04 (6660_{dec})
1C13:04	SubIndex 004	4. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A06 (6662_{dec})
1C13:05	SubIndex 005	5. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A08 (6664_{dec})
1C13:06	SubIndex 006	6. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A0A (6666_{dec})
1C13:07	SubIndex 007	7. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A0C (6668_{dec})
1C13:08	SubIndex 008	8. allocated TxPDO (contains the index of the associated TxPDO mapping object)	UINT16	RW	0x1A0E (6670_{dec})

Index 1C32 SM output parameter

Index (hex)	Name	Meaning	Data type	Flags	Default
1C32:0	SM output parameter	Synchronization parameters for the outputs	UINT8	RO	0x20 (32_{dec})
1C32:01	Sync mode	Current synchronization mode: • 0: “Free Run” • 1: “Synchronous with SM 2 event” • 2: “DC-Mode - Synchronous with SYNC0 Event” • 3: “DC-Mode - Synchronous with SYNC1 event”	UINT16	RW	0x0001 (1_{dec})
1C32:02	Cycle time	Cycle time (in ns): • “Free Run”: Cycle time of the local timer • “Synchron with SM 2 Event”: Master cycle time • “DC mode”: SYNC0/SYNC1 Cycle time	UINT32	RW	0x000F4240 (1000000_{dec})
1C32:03	Shift time	Time between SYNC0 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C32:04	Sync modes supported	Supported synchronization modes: • Bit 0 = 1: “Free Run” is supported • Bit 1 = 1: “Synchron with SM 2 event” is supported • Bit 2-3 = 01: “DC mode” is supported • Bit 4-5 = 10: Output shift with SYNC1 event (DC mode only) • Bit 14 = 1: dynamic times (measurement through writing of 0x1C32:08)	UINT16	RO	0x0002 (2_{dec})
1C32:05	Minimum cycle time	Minimum cycle time (in ns)	UINT32	RO	0x000186A0 (100000_{dec})
1C32:06	Calc and copy time	Minimum time between SYNC0 and SYNC1 event (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C32:07	Minimum delay time	Minimum time between SYNC1 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C32:08	Command	• 0: Measurement of the local cycle time is stopped • 1: Measurement of the local cycle time is started The entries 0x1C32:03, 0x1C32:05, 0x1C32:06, 0x1C32:09, 0x1C33:03 [▶ 51], 0x1C33:06 [▶ 51], 0x1C33:09 [▶ 51] are updated with the maximum measured values. For a subsequent measurement the measured values are reset.	UINT16	RW	0x0000 (0_{dec})
1C32:09	Maximum delay time	Time between SYNC1 event and output of the outputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C32:0B	SM event missed counter	Number of missed SM events in OPERATIONAL (DC mode only)	UINT16	RO	0x0000 (0_{dec})
1C32:0C	Cycle exceeded counter	Number of occasions the cycle time was exceeded in OPERATIONAL (cycle was not completed in time or the next cycle began too early)	UINT16	RO	0x0000 (0_{dec})
1C32:0D	Shift too short counter	Number of occasions that the interval between SYNC0 and SYNC1 event was too short (DC mode only).	UINT16	RO	0x0000 (0_{dec})
1C32:20	Sync error	The synchronization was not correct in the last cycle (outputs were output too late; DC mode only).	BOOLEAN	RO	0x00 (0_{dec})

Index 1C33 SM input parameter

Index (hex)	Name	Meaning	Data type	Flags	Default
1C33:0	SM input parameter	Synchronization parameters for the inputs	UINT8	RO	0x20 (32_{dec})
1C33:01	Sync mode	Current synchronization mode: • 0: “Free Run” • 1: “Synchron with SM 3 Event (no outputs available) • 2: “DC - Synchron with SYNC0 Event” • 3: “DC - Synchron with SYNC1 Event” • 34: “Synchron with SM 2 Event” (outputs available)	UINT16	RW	0x0022 (34_{dec})
1C33:02	Cycle time	Cycle time (in ns): • “Free Run”: Cycle time of the local timer • “Synchron with SM 2 Event”: Master cycle time • “DC mode”: SYNC0/SYNC1 Cycle time	UINT32	RW	0x000F4240 (1000000_{dec})
1C33:03	Shift time	Time between SYNC0 event and reading of the inputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C33:04	Sync modes supported	Supported synchronization modes: • Bit 0: “Free Run” is supported • Bit 1: “Synchronous with SM 2 Event” is supported (outputs available) • Bit 1: “Synchronous with SM 3 Event” is supported (no outputs available) • Bit 2-3 = 01: “DC mode” is supported • Bit 4-5 = 01: input shift through local event (outputs available) • Bit 4-5 = 10: input shift with SYNC1 event (no outputs available) • Bit 14 = 1: dynamic times (measurement through writing of 0x1C32:08 [▶ 50] or 0x1C33:08)	UINT16	RO	0x0002 (2_{dec})
1C33:05	Minimum cycle time	Minimum cycle time (in ns)	UINT32	RO	0x000186A0 (100000_{dec})
1C33:06	Calc and copy time	Time between reading of the inputs and availability of the inputs for the master (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C33:07	Minimum delay time	Minimum time between Sync-1 Event and reading of the inputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C33:08	Command	• 0: Measurement of the local cycle time is stopped • 1: Measurement of the local cycle time is started The entries 0x1C32:03, 0x1C32:05, 0x1C32:06, 0x1C32:09 [▶ 50], 0x1C33:03, 0x1C33:06, 0x1C33:09 are updated with the maximum measured values. For a subsequent measurement the measured values are reset.	UINT16	RW	0x0000 (0_{dec})
1C33:09	Maximum delay time	Time between SYNC1 event and reading of the inputs (in ns, DC mode only)	UINT32	RO	0x00000000 (0_{dec})
1C33:0B	SM event missed counter	Number of missed SM events in OPERATIONAL (DC mode only)	UINT16	RO	0x0000 (0_{dec})
1C33:0C	Cycle exceeded counter	Number of occasions the cycle time was exceeded in OPERATIONAL (cycle was not completed in time or the next cycle began too early)	UINT16	RO	0x0000 (0_{dec})
1C33:0D	Shift too short counter	Number of occasions that the interval between SYNC0 and SYNC1 event was too short (DC mode only)	UINT16	RO	0x0000 (0_{dec})
1C33:20	Sync error	The synchronization was not correct in the last cycle (outputs were output too late; DC mode only)	BOOLEAN	RO	0x00 (0_{dec})

Index F000 Modular device profile

Index (hex)	Name	Meaning	Data type	Flags	Default
F000:0	Modular device profile	General information for the modular device profile	UINT8	RO	0x02 (2_{dec})
F000:01	Module index distance	Index distance of the objects of the individual channels	UINT16	RO	0x0010 (16_{dec})
F000:02	Maximum number of modules	Number of channels	UINT16	RO	0x0008 (8_{dec})

Index F008 Code word

Index (hex)	Name	Meaning	Data type	Flags	Default
F008:0	Code word	reserved	UINT32	RW	0x00000000 (0_{dec})

7 Appendix

7.1 Support and Service

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

Beckhoff's branch offices and representatives

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

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

You will also find further documentation for Beckhoff components there.

Support

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

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

Hotline:	+49 5246 963 157
e-mail:	support@beckhoff.com
web:	www.beckhoff.com/support

Service

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

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

Hotline:	+49 5246 963 460
e-mail:	service@beckhoff.com
web:	www.beckhoff.com/service

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