

Manual | EN

CX7050

Embedded PC for CANopen commander (master)



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1 Notes on the documentation

This description is intended exclusively for trained specialists in control and automation technology who are familiar with the applicable national standards.

For installation and commissioning of the components, it is absolutely necessary to comply with the documentation and the following notes and explanations.

The qualified personnel is always obliged to use the currently valid documentation.

The responsible staff must ensure that the application or use of the products described satisfies all safety requirements, 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 notice.

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The EtherCAT Technology is covered by the following patent applications and patents, without this constituting an exhaustive list:

EP1590927, EP1789857, EP1456722, EP2137893, DE102015105702

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1.1 Representation and structure of warnings

The following warnings are used in the documentation. Read and follow the warnings.

Warnings relating to personal injury:

⚠ 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 can result in minor injury.

Warnings relating to damage to property or the environment:

NOTICE

There is a potential hazard to the environment and equipment.

Notes showing further information or tips:



This notice provides important information that will be of assistance in dealing with the product or software. There is no immediate danger to product, people or environment.

1.2 Documentation issue status

Version	Comment
1.0	First version.

2 For your safety

Read the chapter on safety and follow the instructions in order to protect from personal injury and damage to equipment.

Limitation of liability

All the components are supplied in particular hardware and software configurations appropriate for the application. Unauthorized modifications and changes to the hardware or software configuration, which go beyond the documented options, are prohibited and nullify the liability of Beckhoff Automation GmbH & Co. KG.

In addition, the following actions are excluded from the liability of Beckhoff Automation GmbH & Co. KG:

- Failure to comply with this documentation.
- Improper use.
- Use of untrained personnel.
- Use of unauthorized replacement parts.

2.1 Intended use

The embedded PC is a control system for use in machine and system engineering for automation, visualization and communication. The embedded PC is designed for installation in a control cabinet or terminal box and is used together with Bus or EtherCAT Terminals to receive digital and analog signals from sensors and output them to actuators or forward them to higher-level controllers.

The Embedded PC is designed for a working environment that meets the requirements of protection class IP20. This involves finger protection and protection against solid foreign objects up to 12.5 mm, but not protection against water. Operation of the devices in wet and dusty environments is not permitted, unless specified otherwise. The specified limits for electrical and technical data must be adhered to.

Improper use

The Embedded PC is not suitable for operation in the following areas:

- Potentially explosive atmospheres.
- Areas with an aggressive environment, e.g. aggressive gases or chemicals.
- Living areas. If the devices are to be used in living areas, the relevant standards and guidelines for interference emissions must be adhered to, and the devices must be installed in housings or control boxes with suitable shielding.

2.2 Staff qualification

All operations involving Beckhoff software and hardware may only be carried out by qualified personnel with knowledge of control and automation engineering. The qualified personnel must have knowledge of the administration of the Industrial PC and the associated network.

All interventions must be carried out with knowledge of control programming, and the qualified personnel must be familiar with the current standards and guidelines for the automation environment.

2.3 Safety instructions

The following safety instructions must be followed during installation and working with networks and the software.

Mounting

- Never work on live equipment. Always switch off the power supply for the device before installation, troubleshooting or maintenance. Protect the device against unintentional switching on.

- Observe the relevant accident prevention regulations for your machine (e.g. the BGV A 3, electrical systems and equipment).
- Ensure standard-compliant connection and avoid risks to personnel. Ensure that data and supply cables are laid in a standard-compliant manner and ensure correct connection.
- Observe the relevant EMC guidelines for your application.
- Avoid polarity reversal of the data and supply cables, as this may cause damage to the equipment.
- The devices contain electronic components, which may be destroyed by electrostatic discharge when touched. Observe the safety precautions against electrostatic discharge according to DIN EN 61340-5-1/-3.

Working with networks

- Restrict access to all devices to an authorized circle of persons.
- Change the default passwords to reduce the risk of unauthorized access.
- Protect the devices with a firewall.
- Apply the IT security precautions according to IEC 62443, in order to limit access to and control of devices and networks.

2.4 Notes on information security

The products of Beckhoff Automation GmbH & Co. KG (Beckhoff), insofar as they can be accessed online, are equipped with security functions that support the secure operation of plants, systems, machines and networks. Despite the security functions, the creation, implementation and constant updating of a holistic security concept for the operation are necessary to protect the respective plant, system, machine and networks against cyber threats. The products sold by Beckhoff are only part of the overall security concept. The customer is responsible for preventing unauthorized access by third parties to its equipment, systems, machines and networks. The latter should be connected to the corporate network or the Internet only if appropriate protective measures have been set up.

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To stay informed about information security for Beckhoff products, subscribe to the RSS feed at <https://www.beckhoff.com/secinfo>.

3 Transport and storage

Transport

NOTICE

Short circuit due to moisture

Moisture can form during transport in cold weather or in the event of large temperature fluctuations.

Avoid moisture formation (condensation) in the embedded PC, and leave it to adjust to room temperature slowly. If condensation has occurred, wait at least 12 hours before switching on the embedded PC.

Despite the robust design of the unit, the components are sensitive to strong vibrations and impacts. During transport the embedded PC must be protected from

- high mechanical stress and
- use the original packaging for shipping.

Table 1: Dimensions and weight.

	CX7050
Dimensions (W x H x D)	49 mm x 100 mm x 73 mm
Weight	approx. 142 g

Storage

- Store the Embedded PC in the original packaging.

4 Product overview

The CX7050 Embedded PC has an ARM Cortex™ M7 single-core processor running at 480 MHz and the following basic configuration:

- a microSD card slot with integrated 512 MB microSD card,
- an Ethernet interface (10/100 Mbit/s, RJ45),
- a USB interface (max. 12 Mbit/s, max. 100 mA),
- integrated multi-function I/Os.

The CX7050 is programmed with TwinCAT 3 via the Ethernet interface. In addition, the Beckhoff Device Manger is available as a web interface for configuring the CX7050.

The CANopen commander (master) interface of the CX7050 can also be used as a CAN or CANopen responder (slave).

Multi-function I/Os

Special features of the CX7000 series are the eight integrated multifunction inputs and four integrated multifunction outputs.

- 8 digital inputs, 24 V DC, filter 3 ms, type 3, 1-wire technique
- 4 digital outputs, 24 V DC, 0.5 A, 1-wire technique

The integrated multifunction I/Os of the CX7050 can be configured via TwinCAT 3 for other operation modes in order to enable fast counting or the processing of analog values:

- Counter mode: 1 x digital counter input 100 kHz, 1 x digital input for up/down counter 20 kHz, 2 x digital counter outputs
- Incremental encoder mode: 2 x digital inputs for 250 kHz encoder signal (A/B input), 2 x digital encoder output
- Analog signal mode: 2 x digital inputs configured as analog inputs 0 to 10 V, 12-bit resolution with 16-bit representation
- PWM signal mode: 2 x digital outputs configured for PWM signal, 15 Hz...100 kHz

Power supply terminal

EtherCAT Terminals (E-bus) or Bus Terminals (K-bus) can optionally be connected directly on the right-hand side; the CX7050 automatically recognizes which system is connected during the start-up phase. If further electrical signals are to be processed, the CX7050 can be extended as required and extremely flexibly by EtherCAT Terminals or Bus Terminals in addition to the integrated I/Os.

Firmware

The real-time operating system TC/RTOS, which is based on FreeRTOS, is used as the operating system or firmware. Note that TC/RTOS is a closed system and you cannot install your own software. This provides a certain level of security, as third-party software such as viruses or similar cannot be installed and the CX7050 can be connected to a network. The CX7050 can be used from TwinCAT 3.1 Build 4024.12. The following TC 3 functions are included and licensed:

- TC1000 TC3 ADS
- TC1100 TC3 IO
- TC1200 TC3 PLC
- TF4100 TC3 Controller Toolbox
- TF4110 TC3 Temperature Controller
- TF6255 TC3 Modbus-RTU
- TF6340 TC3 Serial Communication
- TF6701 | TwinCAT 3 IoT Communication (MQTT)^{*)}
- TF6730 | TwinCAT 3 IoT Communicator^{*)}

^{*)} Image version 114606 and TwinCAT 3 XAE 4024.47 or higher required.

The open source licenses can be viewed as a ZIP file on the microSD card.

4.1 Structure

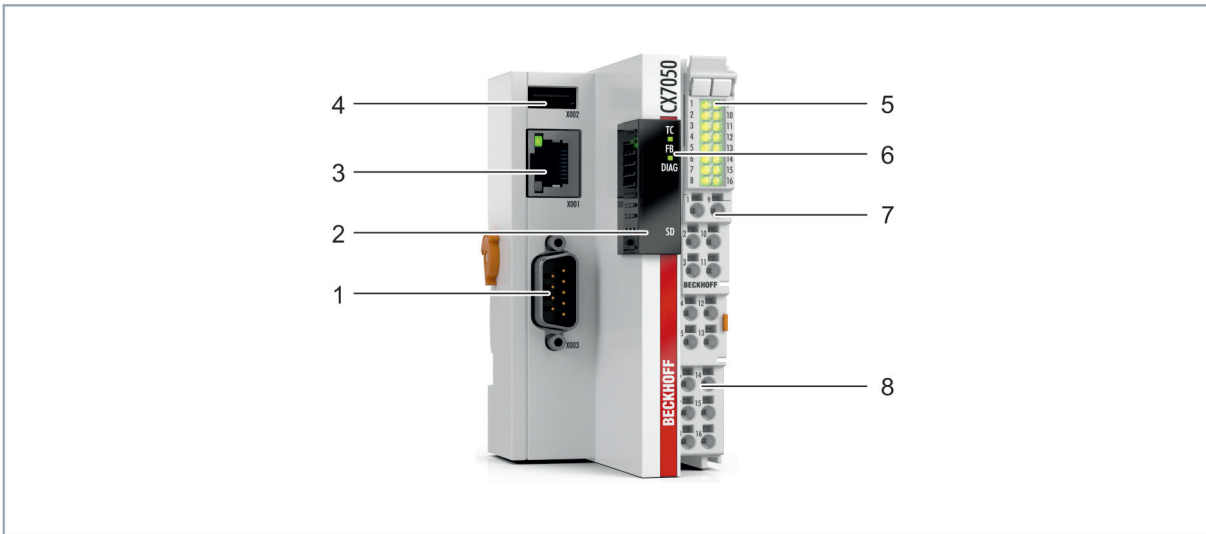


Fig. 1: Sample configuration of a CX7050 Embedded PC.

Table 2: Legend for the configuration of the basic CPU module

No.	Component	Description
1	D-sub connector (X003).	CANopen interface of the CX705x.
2	MicroSD card slot (under the cover).	Slot for industrial MicroSD cards. Memory space for firmware and TwinCAT 3 projects.
3	Ethernet interface (X001)	For the connection to local networks. Serves as a programming interface.
4	USB interface (X002)	Interface for additional USB data storage device.
5	I/O Status LEDs	Diagnosis of the power supply for the Embedded PC and the terminal bus. Status of the E-bus or K-bus communication and multifunction I/Os.
6	Diagnostic LEDs	1 x TwinCAT Status, 1 x Flash access, 1 x Error LED.
7	Spring-loaded terminals, +24 V and 0 V	Power supply (Us) for Embedded PC.
8	Spring-loaded terminals, +24 V and 0 V	Power supply (Up) for integrated multifunction I/Os and Bus Terminals via the power contacts.

4.2 Name plate

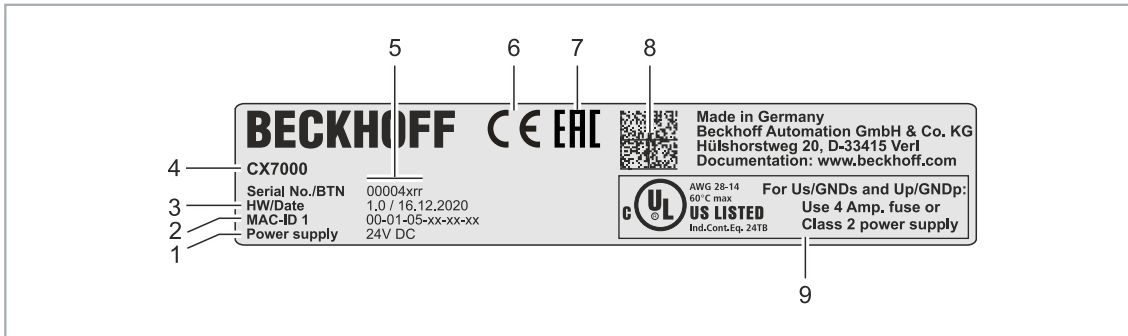


Fig. 2: Name plate example.

Table 3: Information on the name plate.

No.	Description
1	Power supply 24 V DC.
2	MAC addresses of the built-in Ethernet interface.
3	Hardware version and date of manufacture.
4	Product designation for identification of the Embedded PC.
5	Serial number/ Beckhoff Traceability Number (BTN) for the unambiguous identification of the product. The host name is formed from BTN and the serial number/ Beckhoff Traceability Number (BTN). Example: the BTN 00004xrr results in the host name BTN-00004xrr .
6	CE marking
7	EAC marking
8	Machine-readable information in the form of a Data Matrix Code (DMC, code scheme ECC200) that can be used for better identification and management.
9	UL marking with prescribed information on power supply, fuse, temperature and cable cross-sections.

4.3 Ethernet interface (X001)

You can program and commission the CX7050 Embedded PC via the X001 Ethernet interface. The Ethernet interface achieves speeds of 10 / 100 Mbit/s.

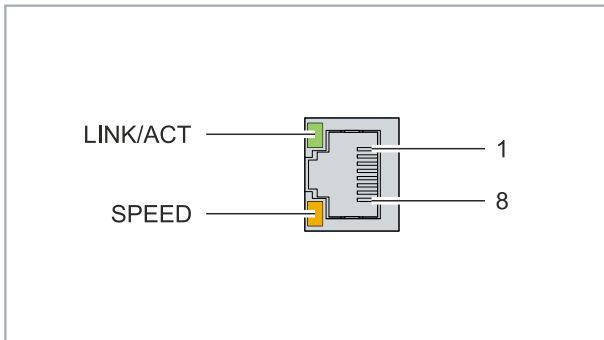


Fig. 3: Ethernet interface X001.

The LEDs on the left of the interface indicate the connection status. The upper LED (LINK/ACT) indicates whether the interface is connected to a network. If this is the case, the LED lights up green. The LED flashes when data transfer on the interface is in progress.

The lower LED (SPEED) indicates the connection speed. The LED is not lit if the speed is 10 Mbit/s. At 100 Mbit/s the LED lights up orange.

Table 4: Ethernet interface X001, pin assignment.

PIN	Signal	Description
1	TD +	Transmit +
2	TD -	Transmit -
3	RD +	Receive +
4	connected	reserved
5		
6	RD -	Receive -
7	connected	reserved
8		

Transmission standards

10Base5

The transmission medium for 10Base5 consists of a thick coaxial cable ("yellow cable") with a max. data transfer rate of 10 Mbaud arranged in a line topology with branches (drops) each of which is connected to one network device. Because all the devices are in this case connected to a common transmission medium, it is inevitable that collisions occur often in 10Base5.

10Base2

10Base2 (Cheaper net) is a further development of 10Base5, and has the advantage that the coaxial cable is cheaper and, being more flexible, is easier to lay. It is possible for several devices to be connected to one 10Base2 cable. It is frequent for branches from a 10Base5 backbone to be implemented in 10Base2.

10BaseT

Describes a twisted pair cable for 10 Mbaud. The network here is constructed as a star. It is no longer the case that every device is attached to the same medium. This means that a broken cable no longer results in failure of the entire network. The use of switches as star couplers enables collisions to be reduced. Using full-duplex connections they can even be entirely avoided.

100BaseT

Twisted pair cable for 100 Mbaud. It is necessary to use a higher cable quality and to employ appropriate hubs or switches in order to achieve the higher data rate.

10BaseF

The 10BaseF standard describes several optical fiber versions.

Short description of the 10BaseT and 100BaseT cable types

Twisted-pair copper cable for star topologies, where the distance between two devices may not exceed 100 meters.

UTP

Unshielded twisted-pair

This type of cable belongs to category 3, and is not recommended for use in an industrial environment.

S/UTP

Screened/unshielded twisted-pair (shielded with copper braid)

Has an overall shield of copper braid to reduce influence of external interference. This cable is recommended for use with Bus Couplers.

FTP

Foiled shielded twisted-pair (shielded with aluminum foil)

This cable has an outer shield of laminated aluminum and plastic foil.

S/FTP

Screened/foiled shielded twisted-pair (shielded with copper braid and aluminum foil)

Has a laminated aluminum shield with a copper braid on top. Such cables can provide up to 70 dB reduction in interference power.

STP

Shielded twisted-pair

Describes a cable with overall shielding without further specification of the type of shielding.

S/STP

Screened/shielded twisted-pair (wires are individually shielded)

This identification refers to a cable with a shield for each of the two wires as well as an outer shield.

ITP

Industrial Twisted-Pair

The structure is similar to that of S/STP, but, in contrast to S/STP, it has only two pairs of conductors.

4.4 USB interface (X002)

A USB flash drive can be connected to the USB interface and used as an additional memory. The USB interface supports transfer speeds of up to 12 Mbit/s and no more than 100 mA. The file is accessed from TwinCAT or the PLC program with the help of the associated function blocks. No other devices can be connected to the USB interface and used.

The same functional mode can be used for accessing files on the MicroSD card. Use *C:* as the drive letter for accessing the MicroSD card and *D:* for accessing the USB flash drive.

Function blocks for data access

The function blocks can be used to process files from the PLC locally on the PC. The TwinCAT target system is identified by the AMS network address. This mechanism makes it possible, amongst other things, to store or to edit files on other TwinCAT systems in the network. Access to files consists of three sequential phases:

1. Opening the file.
2. Read or write access to the opened file.
3. Closing the file.

Opening the file has the purpose of establishing a temporary connection between the external file, whose name is all that initially is known, and the running program. Closing the file has the purpose of indicating the end of the processing and placing it in a defined output state for processing by other programs.

Name	Description
FB_EOF	Check the end of file
FB_FileOpen	Open a file
FB_FileClose	Close a file
FB_FileGets	Get string from a file
FB_FilePuts	Put string to a file
FB_FileRead	Read from a file
FB_FileWrite	Write to a file
FB_FileSeek	Move the file pointer
FB_FileTell	Get the file pointer position
FB_FileDelete	Delete a file
FB_FileRename	Rename a file
FB_CreateDir	Create new directory
FB_RemoveDir	Remove directory

Requirements

Development environment	Target system type	PLC libraries to include (Category group)
TwinCAT v3.1.0	PC or CX (x86, x64, ARM)	Tc2_System (System)

4.5 D-sub connector (X003)

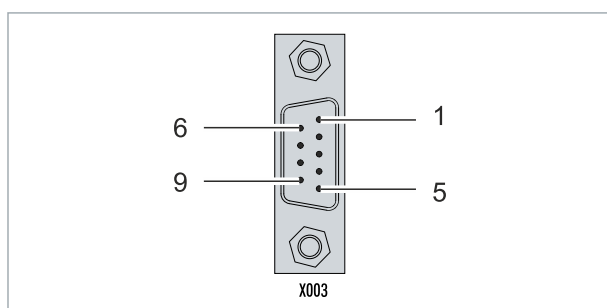


Fig. 4: CANopen interface X003.

The CAN bus line is connected via a 9-pin D-sub connector with the following pin assignment:

Pin	Connection
1	not used
2	CAN low (CAN-)
3	CAN Ground (internally connected to pin 6)
4	not used
5	Shield
6	CAN Ground (internally connected to pin 3)
7	CAN high (CAN+)
8	not used
9	not used

The DIN rail contact spring and the connector shield are connected together. An auxiliary voltage of up to 30 V_{DC} may be connected to pin 9, which is used by some CAN devices to supply the transceivers.

4.6 MicroSD card

The basic equipment of the CX7050 includes a 512 MB microSD card. You can optionally order the embedded PC with a larger microSD card (1 GB, 2 GB, 4 GB, 8 GB or 16 GB).

The cards employed are SLC memory with extended temperature range for industrial applications. Use exclusively microSD cards approved by Beckhoff.

Order identifier	Capacity	Description
CX1900-0123	1 GB	microSD card (SLC memory) with extended temperature range for industrial applications instead of the 512 MB card (ordering option)
CX1900-0125	2 GB	
CX1900-0127	4 GB	
CX1900-0129	8 GB	
CX1900-0131	16 GB	

Order identifier	Capacity	Description
CX1900-0122	512 MB	microSD card (SLC memory) with extended temperature range for industrial applications as spare part.
CX1900-0124	1 GB	
CX1900-0126	2 GB	
CX1900-0128	4 GB	
CX1900-0130	8 GB	
CX1900-0132	16 GB	

4.7 CANopen system overview

CANopen is a widely used CAN application layer, developed by the CAN-in-Automation association (CiA, <http://www.can-cia.org>), and which has meanwhile been adopted for international standardization.

Device Model

CANopen consists of the protocol definitions (communication profile) and of the device profiles that standardize the data contents for the various device classes. Process data objects (PDO) [▶ 26] are used for fast communication of input and output data. The CANopen device parameters and process data are stored in a structured object directory. Any data in this object directory is accessed via service data objects (SDO). There are, additionally, a few special objects (such as telegram types) for network management (NMT), synchronization, error messages and so on.

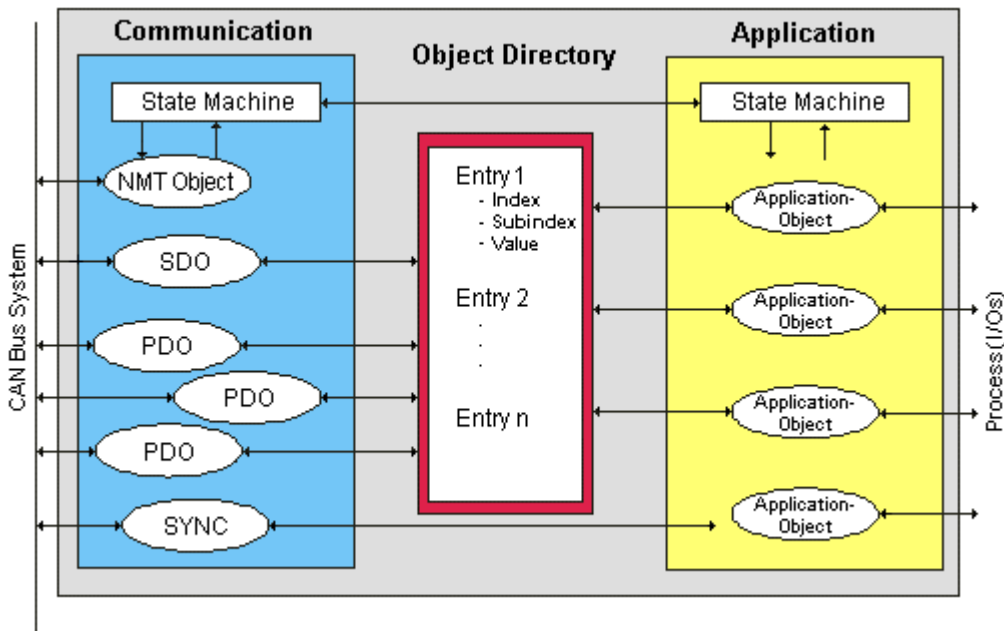


Fig. 5: CANopen Device Model

Communication Types

CANopen defines a number of communication classes for the input and output data (process data objects):

- Event driven [▶ 29]: Telegrams are sent as soon as their contents have changed. This means that the process image as a whole is not continuously transmitted, only its changes.
- Cyclic synchronous [▶ 29]: A SYNC telegram causes the modules to accept the output data that was previously received, and to send new input data.
- Requested (polled) [▶ 26]: A CAN data request telegram causes the modules to send their input data.

The desired communication type is set by the Transmission Type [▶ 26] parameter.

Device Profile

The BECKHOFF CANopen devices support all types of I/O communication, and correspond to the device profile for digital and analog input/output modules (DS401 Version 1). For reasons of backwards compatibility, the default mapping was not adapted to the DS401 V2 profile version.

Data transfer rates

Nine transmission rates from 10 kbit/s up to 1 Mbit/s are available for different bus lengths. The effective utilization of the bus bandwidth allows CANopen to achieve short system reaction times at relatively low data rates.

Topology

CAN is based on a linear topology. The number of devices participating in each network is logically limited by CANopen to 128, but physically the present generation of drivers allows up to 64 nodes in one network segment. The maximum possible size of the network for any particular data rate is limited by the signal propagation delay required on the bus medium. For 1 Mbit/s, for instance, the network may extend 25 m, whereas at 50 kbit/s the network may reach up to 1000 m. At low data rates the size of the network can be increased by repeaters, which also allow the construction of tree structures.

Bus access procedures

CAN utilizes the Carrier Sense Multiple Access (CSMA) procedure, i.e. all participating devices have the same right of access to the bus and may access it as soon as it is free (multi-master bus access). The exchange of messages is thus not device-oriented but message-oriented. This means that every message is unambiguously marked with a prioritized identifier. In order to avoid collisions on the bus when messages are sent by different devices, a bit-wise bus arbitration is carried out at the start of the data transmission. The bus arbitration assigns bus bandwidth to the messages in the sequence of their priority. At the end of the arbitration phase only one bus device occupies the bus, collisions are avoided and the bandwidth is optimally exploited.

Configuration and parameterization

The TwinCAT System Manager allows all the CANopen parameters to be set conveniently. An "eds" file (an electronic data sheet) is available on the Beckhoff website (<http://www.beckhoff.de>) for the parameterization of Beckhoff CANopen devices using configuration tools from other manufacturers.

Certification

The Beckhoff CANopen devices have a powerful implementation of the protocol, and are certified by the CAN in Automation Association (<http://www.can-cia.org>).

4.7.1 Network Management

Simple Boot-Up

CANopen allows the distributed network to boot in a very simple way. After initialization, the modules are automatically in the *Pre-Operational* state. In this state it is already possible to access the object directory using service data objects (SDOs) with default identifiers, so that the modules can be configured. Since default settings exist for all the entries in the object directory, it is in most cases possible to omit any explicit configuration.

Only one CAN message is then required to start the module: Start_Remote_Node: Identifier 0, two data bytes: 0x01, 0x00. It switches the node into the *Operational* state.

Network Status

The states and the state transitions involved as CANopen boots up can be seen from the state diagram:

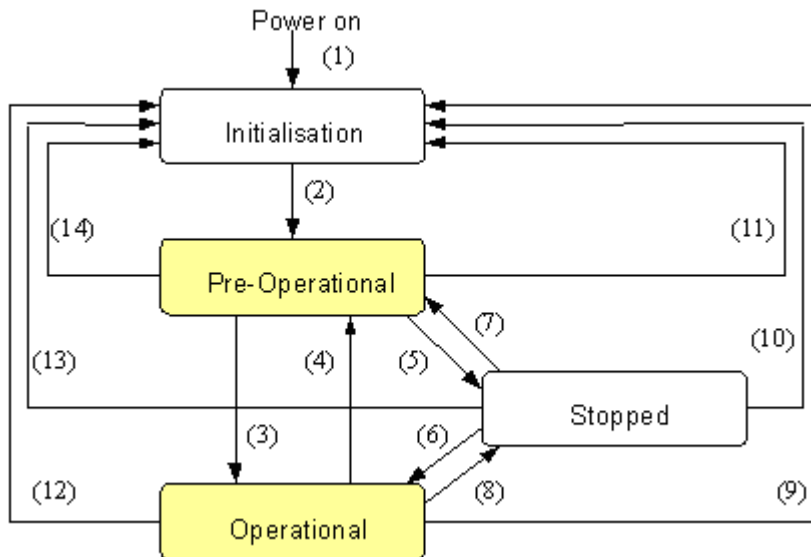


Fig. 6: CANopen bootup state diagram

Pre-Operational

After initialization the Bus Coupler goes automatically (i.e. without the need for any external command) into the *Pre-Operational* state. In this state it can be configured, since the service data objects (SDOs) are already active. The process data objects, on the other hand, are still locked.

Operational

In the *Operational* state the process data objects are also active.

If external influences (such as a CAN error, or absence of output voltage) or internal influences (such as a K-Bus error) mean that it is no longer possible for the Bus Coupler to set outputs, to read inputs or to communicate, it attempts to send an appropriate emergency message, goes into the error state, and thus returns to the *Pre-Operational* state. In this way the NMT status machine in the network master can also immediately detect fatal errors.

Stopped

In the *Stopped* state (formerly: *Prepared*) data communication with the Coupler is no longer possible - only NMT messages are received. The outputs go into the fault state.

State Transitions

The network management messages have a very simple structure: CAN identifier 0, with two bytes of data content. The first data byte contains what is known as the command specifier (cs), and the second data byte contains the node address, the node address 0 applying to all nodes (broadcast).

11 bit identifier	2 byte user data						
0x00	cs	Node ID					

The following table gives an overview of all the CANopen state transitions and the associated commands (command specifier in the NMT master telegram):

Status transition	Command Specifier cs	Explanation
(1)	-	The initialization state is reached automatically at power-up
(2)	-	After initialization the pre-operational state is reached automatically - this involves sending the boot-up message.
(3), (6)	cs = 1 = 0x01	Start_Remote_Node. Starts the module, enables outputs, starts transmission of PDOs.

Status transition	Command Specifier cs	Explanation
(4), (7)	cs = 128 = 0x80	Enter_Pre-Operational. Stops PDO transmission, SDO still active.
(5), (8)	cs = 2 = 0x02	Stop_Remote_Node. Outputs go into the fault state, SDO and PDO switched off.
(9), (10), (11)	cs = 129 = 0x81	Reset_Node. Carries out a reset. All objects are reset to their power-on defaults.
(12), (13), (14)	cs = 130 = 0x82	Reset_Communication. Carries out a reset of the communication functions. Objects 0x1000 - 0x1FFF are reset to their power-on defaults.

Sample 1

The following telegram puts all the modules in the network into the error state (outputs in a safe state):

11 bit identifier	2 byte of user data						
0x00	0x02	0x00					

Sample 2

The following telegram resets node 17:

11 bit identifier	2 byte of user data						
0x00	0x81	0x11					

Boot-up message

After the initialization phase and the self-test the Bus Coupler sends the boot-up message, which is a CAN message with a data byte (0) on the identifier of the guarding or heartbeat message: CAN-ID = 0x700 + node ID. In this way temporary failure of a module during operation (e.g. due to a voltage drop), or a module that is switched on at a later stage, can be reliably detected, even without Node Guarding. The sender can be determined from the message identifier (see default identifier allocation).

It is also possible, with the aid of the boot-up message, to recognize the nodes present in the network at start-up with a simple CAN monitor, without having to make write access to the bus (such as a scan of the network by reading out parameter 0x1000).

Finally, the boot-up message communicates the end of the initialization phase; the Bus Coupler signals that it can now be configured or started.



Firmware version BA

Up to firmware version BA the emergency identifier was used for the boot up message.

Format of the Boot-up message

11 bit identifier	1 byte of user data						
0x700 (=1792)+ node ID	0x00						

Node Monitoring

Heartbeat and guarding mechanisms are available to monitor failures in the CANopen network. These are of particular importance for CANopen, since modules do not regularly speak in the event-driven mode of operation. In the case of "guarding", the devices are cyclically interrogated about their status by means of a data request telegram (remote frame), whereas with "heartbeat" the nodes transmit their status on their own initiative.

Guarding: Node Guarding and Life Guarding

Node Guarding is used to monitor the non-central peripheral modules, while they themselves can use Life Guarding to detect the failure of the guarding master. Guarding involves the master sending remote frames (remote transmit requests) to the guarding identifier of the slaves that are to be monitored. These reply with the guarding message. This contains the slave's status code and a toggle bit that has to change after every message. If either the status or the toggle bit do not agree with that expected by the NMT master, or if there is no answer at all, the master assumes that there is a slave fault.

Guarding procedure

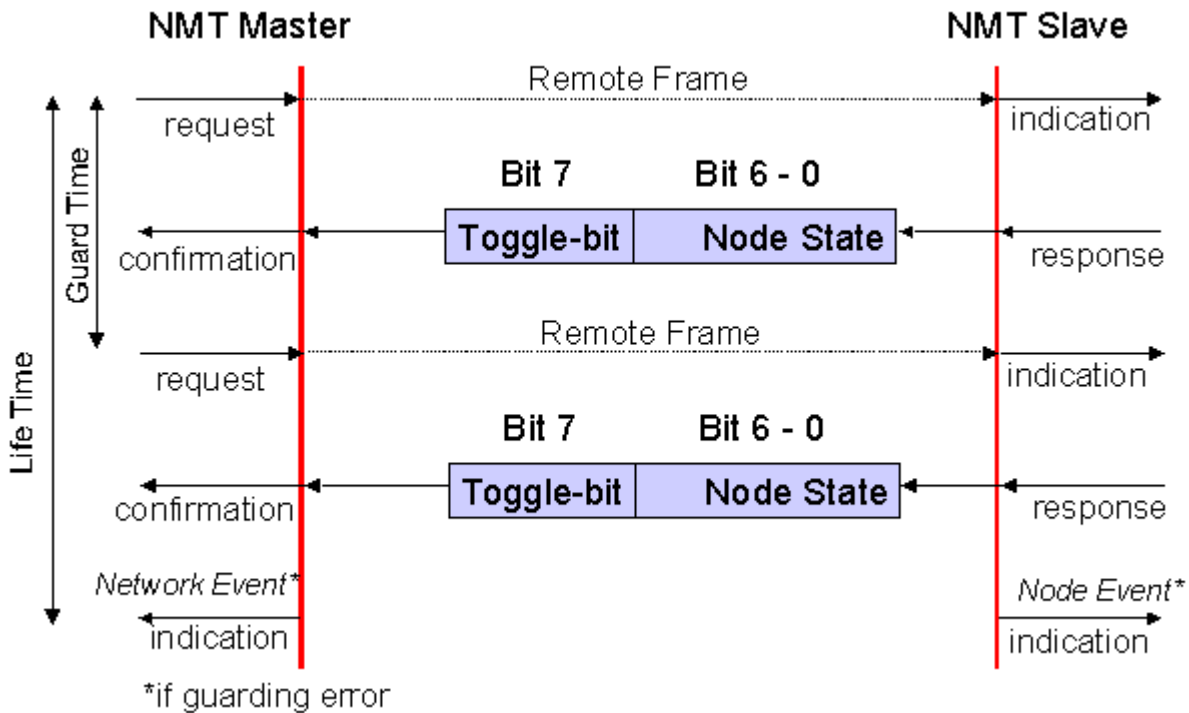


Fig. 7: Schematic diagram: "Guarding procedure"

Protocol

The toggle bit (t) transmitted in the first guarding telegram has the value 0. After this, the bit must change (toggle) in every guarding telegram so that the loss of a telegram can be detected. The node uses the remaining seven bits to transmit its network status (s):

s	Status
4 = 0x04	Stopped (previously: Prepared)
5 = 0x05	Operational
127 = 0x7F	Pre-Operational

Sample

The guarding message for node 27 (0x1B) must be requested by a remote frame having identifier 0x71B (1819_{dec}). If the node is *Operational*, the first data byte of the answer message alternates between 0x05 and 0x85, whereas in the *Pre-Operational* state it alternates between 0x7F and 0xFF.

Guard time and life time factor

If the master requests the guard messages in a strict cycle, the slave can detect the failure of the master. In this case, if the slave fails to receive a message request from the master within the set *Node Life Time* (a guarding error), it assumes that the master has failed (the watchdog function). It then puts its outputs into the error state, sends an emergency telegram, and returns to the pre-operational state. After a guarding time-out the procedure can be re-started by transmitting a guarding telegram again.

The node life time is calculated from the guard time (object 0x100C) and life time factor (object 0x100D) parameters:

$$\text{Life time} = \text{guard time} \times \text{life time factor}$$

If either of these two parameters is "0" (the default setting), the master will not be monitored (no life guarding).

Heartbeat: Node Monitoring without Remote Frame

In the heart beat procedure, each node transmits its status message cyclically on its own initiative. There is therefore no need to use remote frames, and the bus is less heavily loaded than under the guarding procedure.

The master also regularly transmits its heartbeat telegram, so that the slaves are also able to detect failure of the master.

Heartbeat procedure

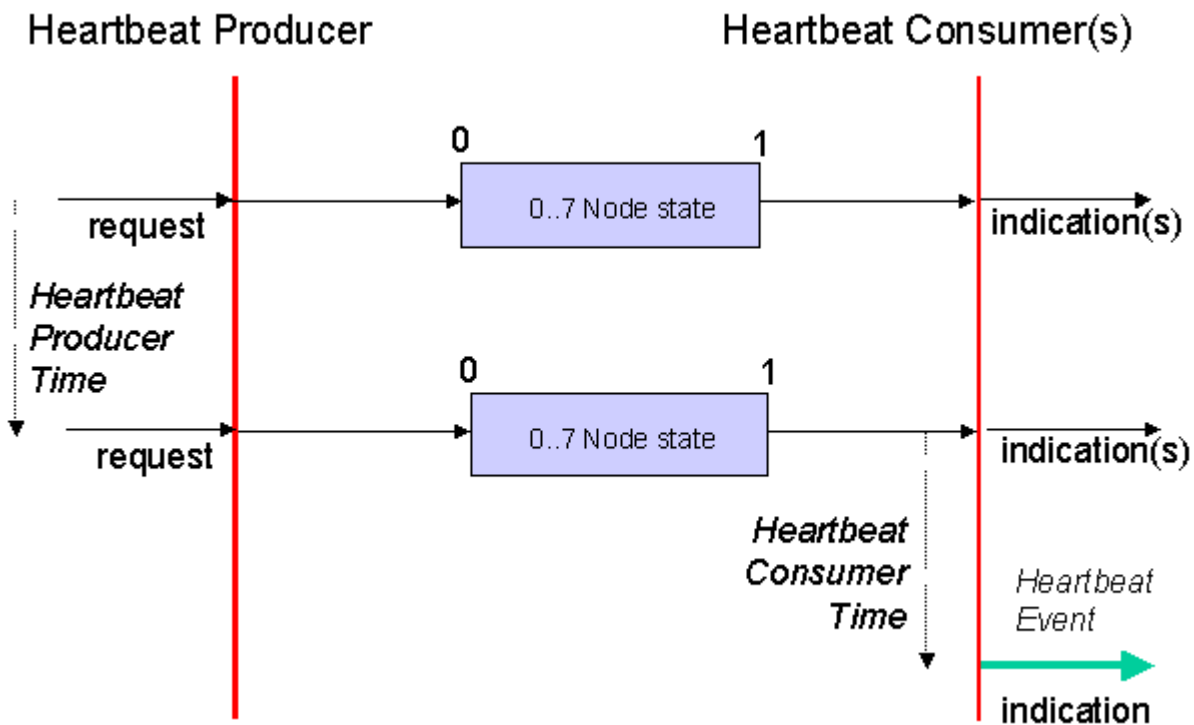


Fig. 8: Schematic diagram: "Heartbeat procedure"

Protocol

The toggle bit is not used in the heart beat procedure. The nodes send their status cyclically (s). See [Guarding \[▶ 25\]](#).

4.7.2 Process Data Objects (PDO)

Introduction

In many fieldbus systems the entire process image is continuously transferred - usually in a more or less cyclic manner. CANopen is not limited to this communication principle, since the multi-master bus access protocol allows CAN to offer other methods. Under CANopen the process data is not transferred in a master/slave procedure, but follows instead the producer-consumer model. In this model, a bus node transmits its data, as a producer, on its own accord. This might, for example, be triggered by an event. All the other nodes listen, and use the identifier to decide whether they are interested in this telegram, and handle it accordingly. These are the consumers.

The process data in CANopen is divided into segments with a maximum of 8 bytes. These segments are known as process data objects (PDOs). The PDOs each correspond to a CAN telegram, whose specific CAN identifier is used to allocate them and to determine their priority. Receive PDOs (RxPDOs) and transmit PDOs (TxPDOs) are distinguished, the name being chosen from the point of view of the device: an input/output module sends its input data with TxPDOs and receives its output data in the RxPDOs. **This naming convention is retained in the TwinCAT System Manager.**

Communication parameters

The PDOs can be given different communication parameters according to the requirements of the application. Like all the CANopen parameters, these are also available in the device's object directory, and can be accessed by means of the service data objects. The parameters for the receive PDOs are at index 0x1400 (RxPDO1) onwards. There can be up to 512 RxPDOs (ranging up to index 0x15FF). In the same way, the entries for the transmit PDOs are located from index 0x1800 (TxPDO1) to 0x19FF (TxPDO512).

The Beckhoff Bus Couplers or Fieldbus Coupler Box modules make 16 RxPDO and TxPDOs available for the exchange of process data (although the figure for Economy and LowCost BK5110 and LC5100 Couplers and the Fieldbus Boxes is 5 PDOs each, since these devices manage a lower quantity of process data). The FC510x CANopen master card supports up to 192 transmit and 192 receive PDOs for each channel - although this is restricted by the size of the DPRAM. The EL6751 CANopen terminal dynamically organizes the process image; i.e. the process data are written in succession, enabling a higher data transmission rate. Up to 32 TxPDOs and 32 RxPDOs can be handled in slave mode.

For each existing process data object there is an associated communication parameter object. The TwinCAT System Manager automatically assigns the set parameters to the relevant object directory entries. These entries and their significance for the communication of process data are explained below.

PDO Identifier

The most important communication parameter in a PDO is the CAN identifier (also known as the communication object identifier, or COB-ID). It is used to identify the data, and determines their priority for bus access. For each CAN data telegram there may only be one sender node (producer), although all messages sent in the CAN broadcast procedure can be received, as described, by any number of nodes (consumers). Thus a node can make its input information available to a number of bus devices at the same time - even without transferring them through a logical bus master. The identifier is located in sub-index 1 of the communication parameter set. It is coded as a 32-bit value in which the least significant 11 bits (bits 0...10) contain the identifier itself. The data width of the object of 32 bits also allows 29-bit identifiers in accordance with CAN 2.0B to be entered, although the default identifiers always refer to the more usual 11-bit versions. Generally speaking, CANopen is economical in its use of the available identifiers, so that the use of the 29-bit versions remains limited to unusual applications. It is therefore also not supported by a Beckhoff's CANopen devices. The highest bit (bit 31) can be used to activate the process data object or to turn it off.

A complete [identifier list \[► 201\]](#) is provided in the appendix.

PDO linking

In the system of default identifiers, all the nodes (here: slaves) communicate with one central station (the master), since slave nodes do not listen by default to the transmit identifier of any other slave node.

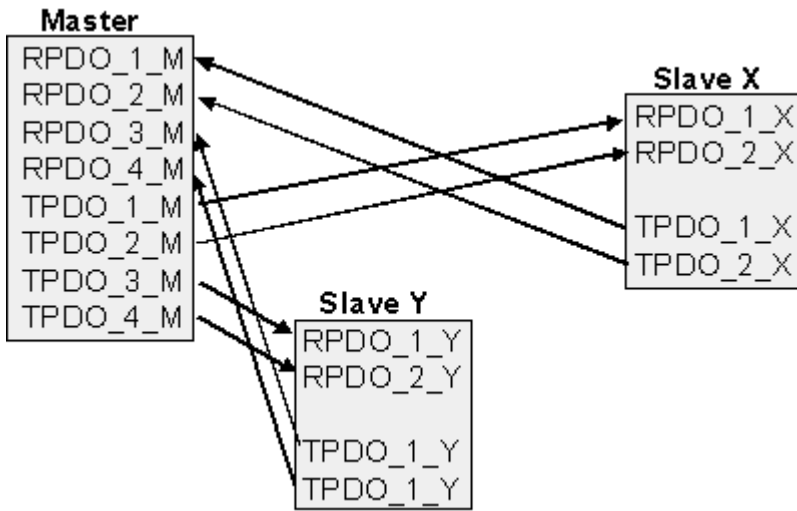


Fig. 9: Default identifier allocation: Master/Slave

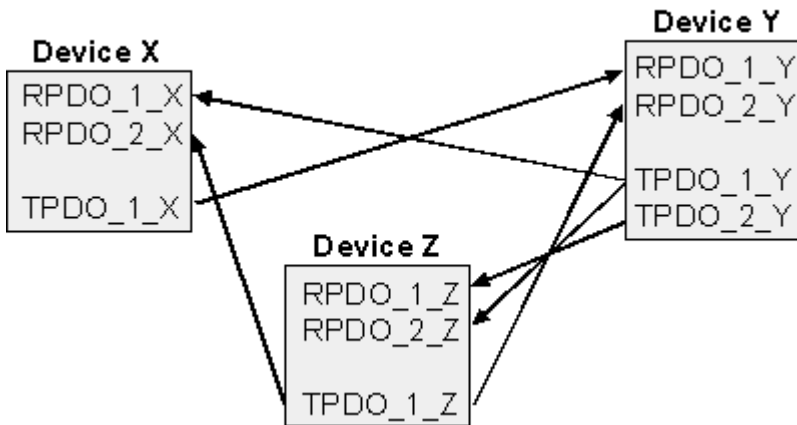


Fig. 10: PDO linking: Peer to Peer

If the consumer-producer model of CANopen PDOs is to be used for direct data exchange between nodes (without a master), the identifier allocation must be appropriately adapted, so that the TxPDO identifier of the producer agrees with the RxPDO identifier of the consumer: This procedure is known as PDO linking. It permits, for sample, easy construction of electronic drives in which several slave axes simultaneously listen to the actual value in the master axis TxPDO.

PDO Communication Types: Overview

CANopen offers a number of possible ways to transmit process data (see also: [Notes on PDO Parameterization](#) [▶ 33]).

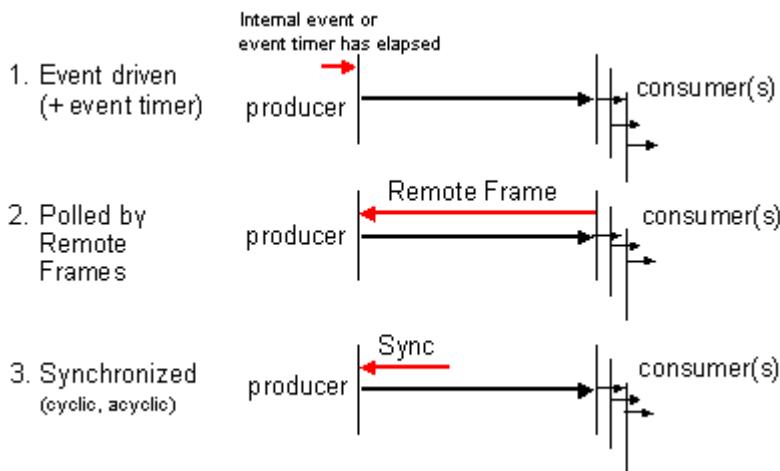


Fig. 11: Diagram: CAN process data transmission

Event driven

The "event" is the alteration of an input value, the data being transmitted immediately after this change. The event-driven flow can make optimal use of the bus bandwidth, since instead of the whole process image it is only the changes in it that are transmitted. A short reaction time is achieved at the same time, since when an input value changes it is not necessary to wait for the next interrogation from a master.

As from CANopen Version 4 it is possible to combine the event driven type of communication with a cyclic update. Even if an event has not just occurred, event driven TxPDOs are sent after the event timer has elapsed. If an event does occur, the event timer is reset. For RxPDOs the event timer is used as a watchdog in order to monitor the arrival of event driven PDOs . If a PDO does not arrive within a set period of time, the bus node adopts the error state.

Polled

The PDOs can also be polled by data request telegrams (remote frames). In this way it is possible to get the input process image of event-driven inputs onto the bus, even when they do not change, for instance through a monitoring or diagnostic device brought into the network while it is running. The time behavior of remote frame and response telegrams depends on what CAN controller is in use. Components with full integrated message filtering ("FullCAN") usually answer a data request telegram immediately, transmitting data that is waiting in the appropriate transmit buffer - it is the responsibility of the application to see that the data there is continuously updated. CAN controllers with simple message filtering (BasicCAN) on the other hand pass the request on to the application which can now compose the telegram with the latest data. This does take longer, but does mean that the data is up-to-date. Beckhoff use CAN controllers following the principle of Basic CAN.

Since this device behavior is usually not transparent to the user, and because there are CAN controllers still in use that do not support remote frames at all, polled communication can only with reservation be recommended for operative running.

Synchronized

It is not only for drive applications that it is worthwhile to synchronize the determination of the input information and the setting the outputs. For this purpose CANopen provides the SYNC object, a CAN telegram of high priority but containing no user data, whose reception is used by the synchronized nodes as a trigger for reading the inputs or for setting the outputs.

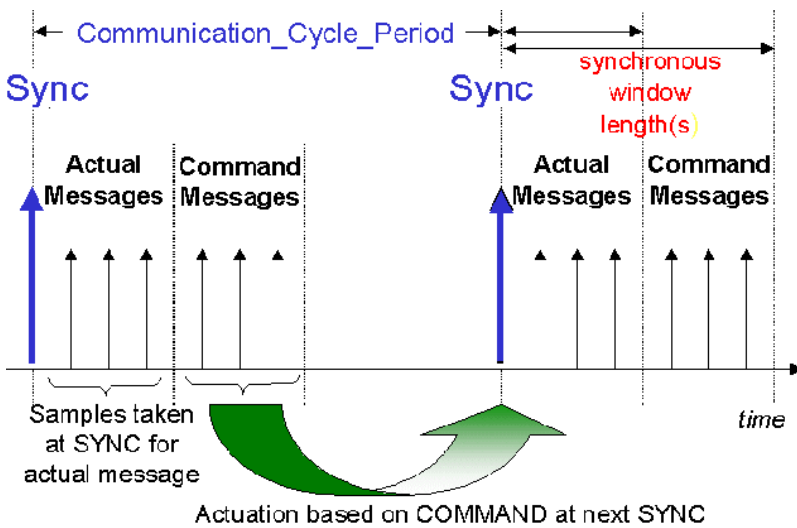


Fig. 12: Diagram: CAN "SYNC" telegram

PDO transmission types: Parameterization

The PDO transmission type parameter specifies how the transmission of the PDO is triggered, or how received PDOs are handled.

Transmission type	Cyclical	Acyclical	Synchronous	Asynchronous	Only RTR
0		X	X		
1-240	X		X		
241-251	- reserved -				
252			X		X
253				X	X
254, 255				X	

The type of transmission is parameterized for RxPDOs in the objects at 0x1400ff, sub-index 2, and for TxPDOs in the objects at 0x1800ff, sub-index 2.

Acyclic Synchronous

PDOs of transmission type 0 function synchronously, but not cyclically. An RxPDO is only evaluated after the next SYNC telegram has been received. In this way, for instance, axis groups can be given new target positions one after another, but these positions only become valid at the next SYNC - without the need to be constantly outputting reference points. A device whose TxPDO is configured for transmission type 0 acquires its input data when it receives the SYNC (synchronous process image) and then transmits it if the data correspond to an event (such as a change in input) having occurred. Transmission type 0 thus combines transmission for reasons that are event driven with a time for transmission (and, as far as possible, sampling) and processing given by the reception of "SYNC".

Cyclic Synchronous

In transmission types 1-240 the PDO is transmitted cyclically: after every "nth" SYNC (n = 1...240). Since transmission types can be combined on a device as well as in the network, it is possible, for example, for a fast cycle to be agreed for digital inputs (n = 1), whereas the data for analog inputs is transmitted in a slower cycle (e.g. n = 10). RxPDOs do not generally distinguish between transmission types 0...240: a PDO that has been received is set to valid when the next SYNC is received. The cycle time (SYNC rate) can be monitored (object 0x1006), so that if the SYNC fails the device reacts in accordance with the definition in the device profile, and switches, for sample, its outputs into the error state.

The FC510x card / EL6751 terminal fully support the synchronous communication method: transmitting the SYNC telegram is coupled to the linked task, so that new input data is available every time the task begins. If a synchronous PDO does not arrive, this is detected and reported to the application.

Only RTR

Transmission types 252 and 253 apply to process data objects that are transmitted exclusively on request by a remote frame. 252 is synchronous: when the SYNC is received the process data is acquired. It is only transmitted on request. 253 is asynchronous. The data here is acquired continuously, and transmitted on request. This type of transmission is not generally recommended, because fetching input data from some CAN controllers is only partially supported. Because, furthermore, the CAN controllers sometimes answer remote frames automatically (without first requesting up-to-date input data), there are circumstances in which it is questionable whether the polled data is up-to-date. Transmission types 252 and 253 are for this reason not supported by the Beckhoff PC cards / terminals.

Asynchronous

The transmission types 254 + 255 are asynchronous, but may also be event-driven. In transmission type 254, the event is specific to the manufacturer, whereas for type 255 it is defined in the device profile. In the simplest case, the event is the change of an input value - this means that every change in the value is transmitted. The asynchronous transmission type can be coupled with the event timer, thus also providing input data when no event has just occurred.

Inhibit time

The "inhibit time" parameter can be used to implement a "transmit filter" that does not increase the reaction time for relatively new input alterations, but is active for changes that follow immediately afterwards. The inhibit time (transmit delay time) specifies the minimum length of time that must be allowed to elapse between the transmission of two of the same telegrams. If the inhibit time is used, the maximum bus loading can be determined, so that the worst case latency can then be found.

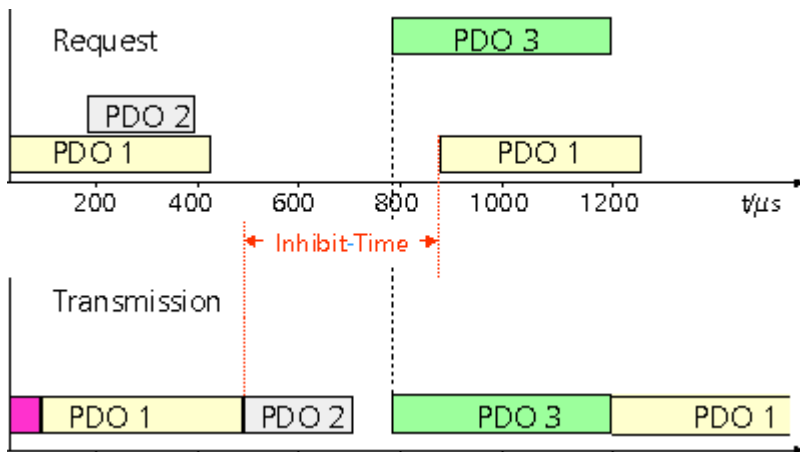


Fig. 13: Timing diagram: "Inhibit time"

Although the Beckhoff FC510x PC cards / EL6751 terminal can parameterize the inhibit time on slave devices, they do not themselves support it. The transmitted PDOs become automatically spread out (transmit delay) as a result of the selected PLC cycle time - and there is little value in having the PLC run faster than the bus bandwidth permits. The bus loading, furthermore, can be significantly affected by the synchronous communication.

Event Timer

An event timer for transmit PDOs can be specified by sub-index 5 in the communication parameters. Expiry of this timer is treated as an additional event for the corresponding PDO, so that the PDO will then be transmitted. If the application event occurs during a timer period, it will also be transmitted, and the timer is reset.

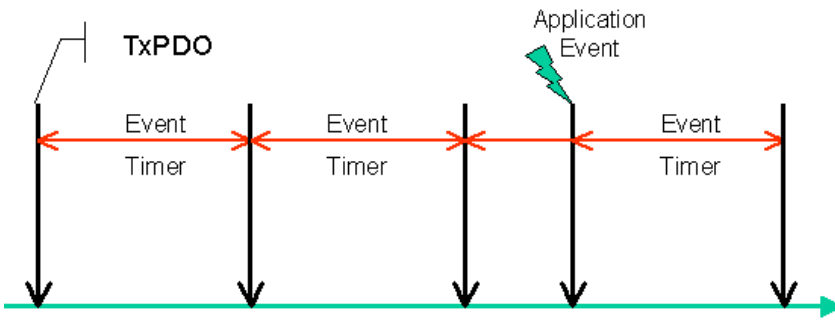


Fig. 14: Time representation of the event timer

In the case of receive PDOs, the timer is used to set a watchdog interval for the PDO: the application is informed if no corresponding PDO has been received within the set period. The FC510x / EL6751 can in this way monitor each individual PDO.

[Notes on PDO Parameterization \[▶ 33\]](#)

PDO Mapping

PDO mapping refers to mapping of the application objects (real time data) from the object directory to the process data objects. The CANopen device profile provide a default mapping for every device type, and this is appropriate for most applications. Thus the default mapping for digital I/O simply represents the inputs and outputs in their physical sequence in the transmit and receive process data objects.

The default PDOs for drives contain 2 bytes each of a control and status word and a set or actual value for the relevant axis.

The current mapping can be read by means of corresponding entries in the object directory. These are known as the mapping tables. The first location in the mapping table (sub-index 0) contains the number of mapped objects that are listed after it. The tables are located in the object directory at index 0x1600ff for the RxPDOs and at 0x1A00ff for the TxPDOs.

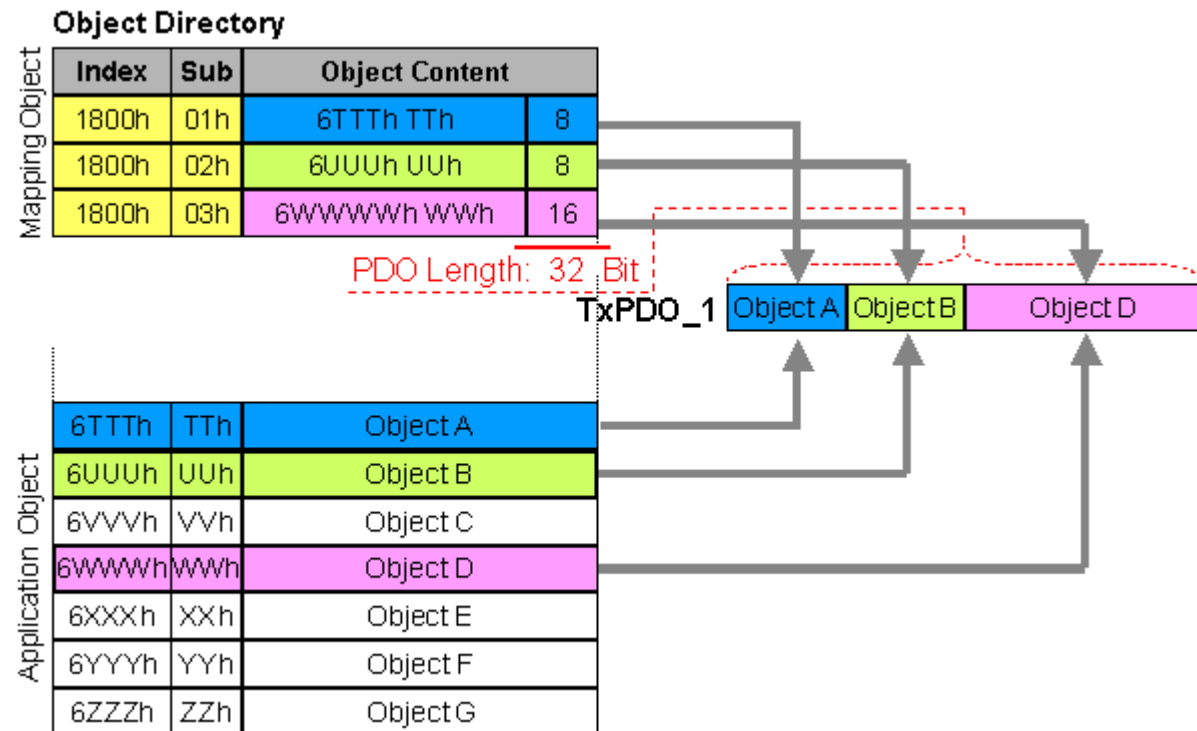


Fig. 15: Mapping representation

Digital and analog input/output modules: Read out the I/O number

The current number of digital and analog inputs and outputs can be determined or verified by reading out the corresponding application objects in the object directory:

Parameter	Object directory address
Number of digital input bytes	Index 0x6000, sub-index 0
Number of digital output bytes	Index 0x6200, sub-index 0
Number of analog inputs	Index 0x6401, sub-index 0
Number of analog outputs	Index 0x6411, sub-index 0

Variable mapping

As a rule, the default mapping of the process data objects already satisfies the requirements. For special types of application the mapping can nevertheless be altered: the Beckhoff CANopen Bus Couplers, for instance, thus support variable mapping, in which the application objects (input and output data) can be freely allocated to the PDOs. The mapping tables must be configured for this: as from Version 4 of CANopen, only the following procedure is permitted, and must be followed precisely:

1. First delete the PDO (set 0x1400ff, or 0x1800ff, sub-index 1, bit 31 to "1")
2. Set sub-index 0 in the mapping parameters (0x1600ff or 0x1A00ff) to "0"
3. Change mapping entries (0x1600ff or 0x1A00ff, SI 1..8)
4. Set sub-index 0 in the mapping parameters to the valid value. The device then checks the entries for consistency.
5. Create PDO by entering the identifier (0x1400ff or 0x1800ff, sub-index 1).

Dummy Mapping

A further feature of CANopen is the mapping of placeholders, or dummy entries. The data type entries stored in the object directory, which do not themselves have data, are used as placeholders. If such entries are contained in the mapping table, the corresponding data from the device is not evaluated. In this way, for instance, a number of drives can be supplied with new set values using a single CAN telegram, or outputs on a number of nodes can be set simultaneously, even in event-driven mode.

4.7.3 PDO Parameterization

Even though the majority of CANopen networks operate satisfactorily with the default settings, i.e. with the minimum of configuration effort, it is wise at least to check whether the existing bus loading is reasonable: 80% bus loading may be acceptable for a network operating purely in cyclic synchronous modes, but for a network with event-driven traffic this value would generally be too high, as there is hardly any bandwidth available for additional events.

Consider the Requirements of the Application

The communication of the process data must be optimized in the light of application requirements which are likely to be to some extent in conflict. These include

- Little work on parameterization - useable default values are optimal
- Guaranteed reaction time for specific events
- Cycle time for regulation processes over the bus
- Safety reserves for bus malfunctions (enough bandwidth for the repetition of messages)
- Maximum baud rate - depends on the maximum bus length
- Desired communication paths - who is speaking with whom

The determining factor often turns out to be the available bus bandwidth (bus load).

Baud rate

We generally begin by choosing the highest baud rate that the bus will permit. It should be borne in mind that serial bus systems are fundamentally more sensitive to interference as the baud rate is increased. The following rule therefore applies: just as fast as necessary. 1000 kbit/s are not usually necessary, and only to be unreservedly recommended on networks within a control cabinet where there is no electrical isolation between the bus nodes. Experience also tends to show that estimates of the length of bus cable laid are often over-optimistic - the length actually laid tends to be longer.

Determine the Communication Type

Once the baud rate has been chosen it is appropriate to specify the PDO communication type(s). These have different advantages and disadvantages:

- Cyclic synchronous communication provides an accurately predictable bus loading, and therefore a defined time behavior - you could say that the standard case is the worst case. It is easy to configure: with the SYNC-Rate parameter the bus load can be set globally. The process images are synchronized: inputs are read at the same time, output data is set valid simultaneously, although the quality of the synchronization depends on the implementation. The BECKHOFF FC510x PC cards / EL6751 CANopen terminal are capable of synchronizing the CANopen bus system with the cycles of the application programs (PLC or NC).

The guaranteed response time for cyclically synchronous communication is always at least as long as the cycle time, and the bus bandwidth is not used optimally, since old, unchanging data is also constantly transmitted. It is however possible to optimize the network through the selection of different SYNC multiples (transmission types 1...240), so that data that changes slowly is transmitted less often than, for instance, time-critical inputs. It must, however, be borne in mind that input states that last for a time that is shorter than the cycle time will not necessarily be communicated. If it is necessary for such conditions to be registered, the associated PDOs for asynchronous communication should be provided.

- Event-driven asynchronous communication is optimal from the point of view of reaction time and the exploitation of bus bandwidth - it can be described as "pure CAN". Your choice must, however, also take account of the fact that it is not impossible for a large number of events to occur simultaneously, leading to corresponding delays before a PDO with a relatively low priority can be sent. Proper network planning therefore necessitates a worst-case analysis. Through the use of, for instance, [inhibit time \[▶ 26\]](#), it is also necessary to prevent a constantly changing input with a high PDO priority from blocking the bus (technically known as a "babbling idiot"). It is for this reason that event driving is switched off by default in the device profile of analog inputs, and must be turned on specifically. The expiry timer can be used to set time windows for the transmit PDOs: The telegram is sent at the earliest after the [inhibit time \[▶ 26\]](#) has elapsed and is sent again at the latest after the expiry timer has elapsed.
- The communication type is parameterized by means of the [Transmission Type \[▶ 26\]](#).

It is also possible to combine the two PDO principles. It can, for instance, be helpful to exchange the set and actual values of an axis controller synchronously, while limit switches, or motor temperatures with limit values are monitored with event-driven PDOs. This combines the advantages of both principles: Synchronous axis communication and short response time for limit switches. In spite of being event-driven, the distributed limit value monitoring avoids a constant addition to the bus load from the analog temperature value.

In the example mentioned, it can also be useful to specifically influence the identifier distribution in order to optimize the bus access through the priority distribution: the highest priority is given to the PDO with the limit switch data, the lowest to the one with the temperature values.

Optimization of bus access latency time through modification of the identifier allocation is not, however, normally required. In contrast, the identifiers must be changed to enable masterless communication ([PDO Linking \[▶ 26\]](#)). In this example it would be possible for one RxPDO for each axis to be allocated the same identifier as the limit switch TxPDO, so that alterations of the input value can be received without delay.

Determining the Bus Loading

It is always worth determining the bus loading. But what bus loading values are permitted, or indeed sensible? It is first necessary to distinguish a short burst of telegrams in which a number of CAN messages follow one another immediately - a temporary 100% bus loading. This is only a problem if the sequence of receive interrupts that it caused at the CAN nodes cannot be handled. This would constitute a data overflow (or CAN queue overrun). This can occur at very high baud rates (> 500 kbit/s) at nodes with software

telegram filtering and relatively slow or heavily loaded microcontrollers if, for instance, a series of remote frames (which do not contain data bytes, and are therefore very short) follow each other closely on the bus (at 1 Mbit/s this can generate an interrupt every 40 μs; for example, an NMT master might transmit all its guarding requests in an unbroken sequence). This can be avoided through skilled implementation, and the user should be able to assume that the device suppliers have taken the necessary trouble. A burst condition is entirely normal immediately after the SYNC telegram, for instance: triggered by the SYNC, all the nodes that are operating synchronously try to send their data at almost the same time. A large number of arbitration processes take place, and the telegrams are sorted in order of priority for transmission on the bus. This is not usually critical, since these telegrams do contain some data bytes, and the telegrams trigger a sequence of receive interrupts at the CAN nodes which is indeed rapid, but is nevertheless manageable.

Bus loading most often refers to the value averaged over several primary cycles, that is the mean value over 100-500 ms. CAN, and therefore CANopen, is indeed capable of managing a bus loading of close to 100% over long periods, but this implies that no bandwidth is available for any repetitions that may be necessitated by interference, for asynchronous error messages, parameterization and so on. Clearly, the dominant type of communication will have a large influence on the appropriate level of bus loading: a network with entirely cyclic synchronous operation is always in any case near to the worst case state, and can therefore be operated with values in the 70-80% range. The figure is very hard to state for an entirely event-driven network: an estimate must be made of how many events additional to the current state of the system might occur, and of how long the resulting burst might last - in other words, for how long the lowest priority message will be delayed. If this value is acceptable to the application, then the current bus loading is acceptable. As a rule of thumb it can usually be assumed that an event-driven network running with a base loading of 30-40% has enough reserve for worst-case scenarios, but this assumption does not obviate the need for a careful analysis if delays could have critical results for the plant.

The BECKHOFF FC510x CANopen master cards / EL6751 CANopen master terminal display the bus load via the System Manager. This variable can also be processed in the PLC, or can be displayed in the visualization system.

The amount data in the process data objects is of course as relevant as the communication parameters: the PDO mapping. [▶ 32]

4.7.4 Service Data Objects (SDO)

The parameters listed in the object directory are read and written by means of service data objects. These SDOs are *Multiplexed Domains*, i.e. data structures of any size that have a multiplexer (address). The multiplexer consists of a 16-bit index and an 8-bit sub-index that address the corresponding entries in the object directory.

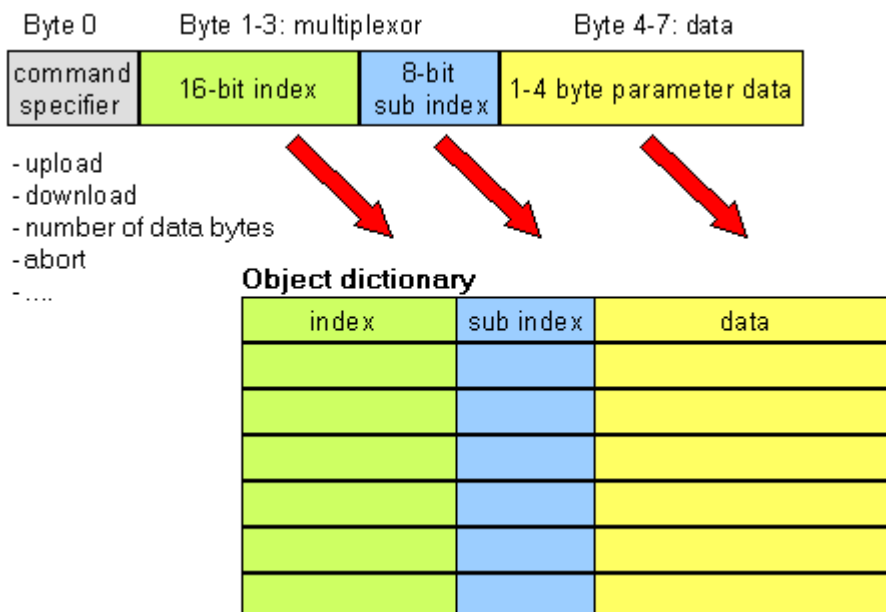


Fig. 16: SDO protocol: access to the object directory

The CANopen Bus Couplers are servers for the SDO, which means that at the request of a client (e.g. of the IPC or the PLC) they make data available (upload), or they receive data from the client (download). This involves a handshake between the client and the server.

When the size of the parameter to be transferred is not more than 4 bytes, a single handshake is sufficient (one telegram pair): For a download, the client sends the data together with its index and sub-index, and the server confirms reception. For an upload, the client requests the data by transmitting the index and sub-index of the desired parameter, and the server sends the parameter (including index and sub-index) in its answer telegram.

The same pair of identifiers is used for both upload and download. The telegrams, which are always 8 bytes long, encode the various services in the first data byte. All parameters with the exception of objects 1008h, 1009h and 100Ah (device name, hardware and software versions) are only at most 4 bytes long, so this description is restricted to transmission in expedited transfer.

Protocol

The structure of the SDO telegrams is described below.

Client -> Server, Upload Request

11 bit identifier	8 byte user data							
0x600 (=1536 _{dec}) + node ID	0x40	Index0	Index1	SubIdx	0x00	0x00	0x00	0x00

Parameter	Explanation
Index0	Index low byte (Unsigned16, LSB)
Index1	Index high byte (Unsigned16, MSB)
SubIdx	Sub-index (Unsigned8)

Client -> Server, Upload Response

11 bit identifier	8 byte user data							
0x580 (=1408 _{dec}) + node ID	0x4x	Index0	Index1	SubIdx	Data0	Data1	Data2	Data3

Parameter	Explanation
Index0	Index low byte (Unsigned16, LSB)
Index1	Index high byte (Unsigned16, MSB)
SubIdx	Sub-index (Unsigned8)
Data0	Data low low byte (LLSB)
Data3	Data high high byte (MMSB)

Parameters whose data type is Unsigned8 are transmitted in byte D0, parameters whose type is Unsigned16 use D0 and D1.

The number of valid data bytes is coded as follows in the first CAN data byte (0x4x):

Number of parameter bytes	1	2	3	4
First CAN data byte	0x4F	0x4B	0x47	0x43

Client -> Server, Download Request

11 bit identifier	8 byte user data							
0x600 (=1536 _{dec}) + node ID	0x22	Index0	Index1	SubIdx	Data0	Data1	Data2	Data3

Parameter	Explanation
Index0	Index low byte (Unsigned16, LSB)
Index1	Index high byte (Unsigned16, MSB)
SubIdx	Sub-index (Unsigned8)

Parameter	Explanation
Data0	Data low low byte (LLSB)
Data3	Data high high byte (MMSB)

It is optionally possible to give the number of valid parameter data bytes in the first CAN data byte

Number of parameter bytes	1	2	3	4
First CAN data byte	0x2F	0x2B	0x27	0x23

This is, however, not generally necessary, since only the less significant data bytes up to the length of the object directory entry that is to be written are evaluated. A download of data up to 4 bytes in length can therefore always be achieved in BECKHOFF bus nodes with 22 h in the first CAN data byte.

Client -> Server, Download Response

11 bit identifier	8 byte user data							
0x580 (=1408 _{dec}) + node ID	0x60	Index0	Index1	SubIdx	0x00	0x00	0x00	0x00

Parameter	Explanation
Index0	Index low byte (Unsigned16, LSB)
Index1	Index high byte (Unsigned16, MSB)
SubIdx	Sub-index (Unsigned8)

Breakdown of Parameter Communication

Parameter communication is interrupted if it is faulty. The client or server send an SDO telegram with the following structure for this purpose:

11 bit identifier	8 byte user data							
0x580 (client) or 0x600 (server) + node ID	0x80	Index0	Index1	SubIdx	Error0	Error1	Error2	Error3

Parameter	Explanation
Index0	Index low byte (Unsigned16, LSB)
Index1	Index high byte (Unsigned16, MSB)
SubIdx	Sub-index (Unsigned8)
Error0	SDO error code low low byte (LLSB)
Error3	SDO error code high high byte (MMSB)

List of SDO error codes (reason for abortion of the SDO transfer):

SDO error code	Explanation
0x05 03 00 00	Toggle bit not changed
0x05 04 00 01	SDO command specifier invalid or unknown
0x06 01 00 00	Access to this object is not supported
0x06 01 00 02	Attempt to write to a Read_Only parameter
0x06 02 00 00	The object is not found in the object directory
0x06 04 00 41	The object cannot be mapped into the PDO
0x06 04 00 42	The number and/or length of mapped objects would exceed the PDO length
0x06 04 00 43	General parameter incompatibility
0x06 04 00 47	General internal error in device
0x06 06 00 00	Access interrupted due to hardware error
0x06 07 00 10	Data type or parameter length do not agree or are unknown
0x06 07 00 12	Data type does not agree, parameter length too great
0x06 07 00 13	Data type does not agree, parameter length too short

SDO error code	Explanation
0x06 09 00 11	Sub-index not present
0x06 09 00 30	General value range error
0x06 09 00 31	Value range error: parameter value too great
0x06 09 00 32	Value range error: parameter value too small
0x06 0A 00 23	Resource not available
0x08 00 00 00	General error
0x08 00 00 21	Access not possible due to local application
0x08 00 00 22	Access not possible due to current device status

Further, manufacturer-specific error codes have been introduced for register communication (index 0x4500, 0x4501):

SDO error code	Explanation
0x06 02 00 11	Invalid table: Table or channel not present
0x06 02 00 10	Invalid register: table not present
0x06 01 00 22	Write protection still set
0x06 07 00 43	Incorrect number of function arguments
0x06 01 00 21	Function still active, try again later
0x05 04 00 40	General routing error
0x06 06 00 21	Error accessing BC table
0x06 09 00 10	General error communicating with terminal
0x05 04 00 47	Time-out communicating with terminal

4.7.5 Objekt dictionary

4.7.5.1 Object Directory - Structure

All the CANopen objects relevant for the Bus Coupler are entered into the CANopen object directory. The object directory is divided into three different regions:

1. communication-specific profile region (index 0x1000 – 0x1FFF).
This contains the description of all the parameters specific to communication.
2. manufacturer-specific profile region (index 0x2000 – 0x5FFF).
Contains the description of the manufacturer-specific entries.
3. standardized device profile region (0x6000 – 0x9FFF).
Contains the objects for a device profile according to DS-401.

Every entry in the object directory is identified by a 16 bit index. If an object consists of several components (e.g. object type array or record), the components are identified by an 8-bit sub-index. The object name describes the function of an object, while the data type attribute specifies the data type of the entry. The access attribute specifies whether an entry may only be read, only written, or may be both read and written.

Communication-specific region

All the parameters and objects necessary for the CANopen Bus Coupler's communication are in this region of the object directory. The region from 0x1000 to 0x1018 contains various general communication-specific parameters (e.g. the device name).

The communication parameters (e.g. identifiers) for the receive PDOs are located in the region from 0x1400 to 0x140F (plus sub-index). The mapping parameters of the receive PDOs are in the region from 0x1600 to 0x160F (plus sub-index). The mapping parameters contain the cross-references to the application objects that are mapped into the PDOs and the data width of the corresponding object (see also the section dealing with PDO Mapping).

The communication and mapping parameters for the transmit PDOs are located in the regions from 0x1800 to 0x180F and from 0x1A00 to 0x1A0F.

Manufacturer-specific region

This region contains entries that are specific to BECKHOFF, e.g.:

- data objects for special terminals
- objects for register communication providing access to all the Bus Couplers' and Bus Terminals' internal registers
- objects for simplified configuration of the PDOs

Standardized device profile region

The standardized device profile region supports the device profile of CANopen DS-401, Version 1. Functions are available for analog inputs that can adapt communication in the event-driven operating mode to the requirements of the application and to minimize the loading of the bus:

- limit value monitoring
- Delta function
- activation/deactivation of event-driven mode

4.7.5.2 Object List

i The objects in the object directory can be reached by SDO access, but not generally through the KS2000 configuration software. On the other hand, all the registers that can be configured with KS2000 can also be reached using SDO access to the object directory (objects 0x4500 and 0x4501) - even though this does not offer the same convenience as the KS2000 software.

Parameter	Index	BK5120/ BK515x	BK5110	LC5100	BX5100/ BC5150	CX705x/ CX8051/B510
Device type [▶ 41]	0x1000	x	x	x		x
Error register [▶ 41]	0x1001	x	x	x	x	x *
Error memory [▶ 41]	0x1003	x	x	x		
Sync Identifier [▶ 41]	0x1005	x	x	x	x	x
Sync Interval [▶ 41]	0x1006	x	x	x	x	x
Device name [▶ 41]	0x1008	x	x	x	x	x *
Hardware version [▶ 41]	0x1009	x	x	x		
Software version [▶ 41]	0x100A	x	x	x	x	x
Node number [▶ 41]	0x100B	x	x	x		
Guard Time [▶ 41]	0x100C	x	x	x	x	x
Life Time Factor [▶ 41]	0x100D	x	x	x	x	x
Guarding Identifier [▶ 41]	0x100E	x	x	x		
Save parameters [▶ 41]	0x1010	x	x	x		
Load default values [▶ 41]	0x1011	x	x	x		
Emergency Identifier [▶ 41]	0x1014	x	x	x		
Consumer Heartbeat Time [▶ 41]	0x1016	x	x	x	x	x
Producer Heartbeat Time [▶ 41]	0x1017	x	x	x	x	x
Device identifier (identity object) [▶ 41]	0x1018	x	x	x	x	x *
Server SDO parameters [▶ 41]	0x1200	x	x	x		
Communication parameters for the 1st - 5th RxPDO [▶ 41]	0x1400 - 0x1404	x	x	x	x	x
Communication parameters for the 6th - 16th RxPDO [▶ 41]	0x1405 - 0x140F	x			x	x

Parameter	Index	BK5120/ BK515x	BK5110	LC5100	BX5100/ BC5150	CX705x/ CX8051/B510
Communication parameters for the 17th - 32nd RxPDO [► 41]	0x1410 - 0x141F				x only BX5100	x
Mapping 1st -5th RxPDO [► 41]	0x1600 - 0x1604	x	x	x	x	x
Mapping 6th -16th RxPDO [► 41]	0x1605 - 0x160F	x			x	x
Mapping 17th -32nd RxPDO [► 41]	0x1610 - 0x161F				x only BX5100	x
Communication parameters for the 1st - 5th TxPDO [► 41]	0x1800 - 0x1804	x	x	x	x	x
Communication parameters for the 6th - 16th TxPDO [► 41]	0x1805 - 0x180F	x			x	x
Communication parameters for the 17th - 32nd TxPDO [► 41]	0x1810 - 0x181F				x only BX5100	x
Mapping 1st -5th TxPDO [► 41]	0x1A00 - 0x1A04	x	x	x	x	x
Mapping 6th -16th TxPDO [► 41]	0x1A05 - 0x1A0F	x			x	x
Mapping 17th -32nd TxPDO [► 41]	0x1A10 - 0x1A1F				x only BX5100	x
Flag area %MB0-511	0x2F00				x	
Flag area %MB511-1023	0x2F01				x	
Flag area %MB1024-1535	0x2F02				x	
Flag area %MB1536-2047	0x2F03				x	
Flag area %MB2048-2559	0x2F04				x	
Flag area %MB2560-3071	0x2F05				x	
Flag area %MB3072-3584	0x2F06				x	
Flag area %MB3585-4095	0x2F07				x	
3-byte special terminals, input data [► 41]	0x2600	x				
3-byte special terminals, output data [► 41]	0x2700	x				
4-byte special terminals, input data [► 41]	0x2800	x				
4-byte special terminals, output data [► 41]	0x2900	x				
5-byte special terminals, input data [► 41]	0x2A00	x				
5-byte special terminals, output data [► 41]	0x2B00	x				
6-byte special terminals, input data [► 41]	0x2C00	x				
6-byte special terminals, output data [► 41]	0x2D00	x				
8-byte special terminals, input data [► 41]	0x3000	x				
8-byte special terminals, output data [► 41]	0x3100	x				
Register communication, bus node [► 41]	0x4500	x	x	x		

Parameter	Index	BK5120/ BK515x	BK5110	LC5100	BX5100/ BC5150	CX705x/ CX8051/B510
Register communication, bus terminal/extension box [▶ 41]	0x4501	x	x	x		
Enable PDOs [▶ 41]	0x5500	x	x	x		
NetId	0x5FFE				x	
Digital inputs [▶ 41]	0x6000	x	x	x		
Interrupt mask [▶ 41]	0x6126	x	x	x		
Digital outputs [▶ 41]	0x6200	x	x	x		
Analog inputs [▶ 41]	0x6401	x				
Analog outputs [▶ 41]	0x6411	x				
Event control, analog inputs [▶ 41]	0x6423	x				
Upper limit value, analog inputs [▶ 41]	0x6424	x				
Lower limit value, analog inputs [▶ 41]	0x6425	x				
Delta function, analog inputs [▶ 41]	0x6426	x				

* When an ADS server is registered, these objects are relayed to the PLC via ADS notification and have to be answered there.

4.7.5.3 Objects and Data

Device type

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1000	0	Device type	Unsigned32	ro	N	0x00000000	Statement of device type

The 32 bit value is divided into two 16 bit fields:

MSB	LSB
Additional information	Device profile number
0000 0000 0000 wxyz	0x191 (401 _{dez})

The *additional information* contains data related to the signal type of the I/O device:

- z=1 signifies digital inputs,
- y=1 signifies digital outputs,
- x=1 signifies analog inputs,
- w=1 signifies analog outputs.

A BK5120 with digital and analog inputs, but with no outputs, thus returns 0x00 05 01 91.

Special terminals (such as serial interfaces, PWM outputs, incremental encoder inputs) are not considered. A Coupler that, for example, only has KL6001 serial interface terminals plugged in, thus returns 0x00 00 01 91.

The device type supplies only a rough classification of the device. The terminal identifier register of the Bus Coupler can be read for detailed identification of the Bus Couplers and the attached terminals (for details see register communication index 0x4500).

Error register

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1001	0	Error register	Unsigned8	ro	N	0x00	Error register

The 8 bit value is coded as follows:

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ManSpec.	reserved	reserved	Comm.	reserved	reserved	reserved	Generic

ManSpec. Manufacturer-specific error, specified more precisely in object 1003.

Comm. Communication error (CAN overrun)

Generic An error that is not more precisely specified has occurred (the flag is set at every error message)

Error store

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1003	0x00	Predefined error field (Error store)	Unsigned8	rw	N	0x00	Object 1003h contains a description of the error that has occurred in the device - sub-index 0 has the number of error states stored.
	1	Actual error	Unsigned32	ro	N	None	Last error state to have occurred
	--
	10	Standard error field	Unsigned32	ro	N	None	A maximum of 10 error states are stored.

The 32 bit value in the error store is divided into two 16 bit fields:

MSB	LSB
Additional code	Error Code

The additional code contains the error trigger (see emergency object) and thereby a detailed error description.

New errors are always saved at sub-index 1, all the other sub-indices being appropriately incremented. The whole error store is cleared by writing a 0 to sub-index 0.

If there has not been an error since power up, then object 0x1003 only consists of sub-index 0 with a 0 entered into it. The error store is cleared by a reset or a power cycle.

As is usual in CANopen, the LSB is transferred first, followed by the MSB.

Sync Identifier

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1005	0	COB-ID Sync Message	Unsigned32	rw	N	0x80000080	Identifier of the SYNC message

The bottom 11 bits of the 32 bit value contain the identifier (0x80=128 dec). Bit 30 indicates whether the device sends the SYNC telegram (1) or not (0). The CANopen I/O devices receive the SYNC telegram, and accordingly bit 30=0. For reasons of backwards compatibility, bit 31 has no significance.

Sync Interval

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1006	0	Communication cycle period	Unsigned32	rw	N	0x00000000	Length of the SYNC interval in µs.

If a value other than zero is entered here, the bus node will go into the fault state if, during synchronous PDO operation, no SYNC telegram is received within the watchdog time. The watchdog time corresponds here to 1.5 times the communication cycle period that has been set - the planned SYNC interval can therefore be entered.

The I/O update is carried out at the Beckhoff CANopen bus nodes immediately after reception of the SYNC telegram, provided the following conditions are satisfied:

- Firmware status C0 or above (CANopen Version 4.01 or higher).
- All PDOs that have data are set to synchronous communication (0..240).
- The sync interval has been entered in object 0x1006 and (sync interval x lowest PDO transmission type) is less than 90ms.

The modules are then synchronised throughout.

Device name

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1008	0	Manufacturer Device Name	Visible String	ro	N	BK51x0, LC5100, IPxxxx-B510 or ILxxxx-B510	Device name of the bus node

Since the returned value is longer than 4 bytes, the segmented SDO protocol is used for transmission.

Hardware version

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1009	0	Manufacturer hardware-version	Visible String	ro	N	-	Hardware version number of the bus node

Since the returned value is longer than 4 bytes, the segmented SDO protocol is used for transmission.

Software version

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x100A	0	Manufacturer software-version	Visible String	ro	N	-	Software version number of the bus node

Since the returned value is longer than 4 bytes, the segmented SDO protocol is used for transmission.

Node number

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x100B	0	Node-ID	Unsigned32	ro	N	none	Set node number

The node number is supported for reasons of compatibility.

Guard time

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x100C	0	Guard time [ms]	Unsigned16	rw	N	0	Interval between two guard telegrams. Is set by the NMT master or configuration tool.

Life time factor

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x100D	0	Life time factor	Unsigned8	rw	N	0	Life time factor x guard time = life time (watchdog for life guarding)

If a guarding telegram is not received within the life time, the node enters the error state. If the life time factor and/or guard time = 0, the node does not carry out any life guarding, but can itself be monitored by the master (node guarding).

Guarding identifier

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x100 E	0	COB-ID guarding protocol	Unsigned32	ro	N	0x000007xy, xy = NodeID	Identifier of the guarding protocol

The guarding identifier is supported for reasons of compatibility. Changing the guarding identifier has no longer been permitted since version 4 of CANopen.

Save parameters

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1010	0	Store Parameter	Unsigned8	ro	N	1	Number of store options
	1	store all parameters	Unsigned32	rw	N	1	Stores all (storable) parameters

By writing the string *save* in ASCII code (hexadecimal 0x657666173) to sub-index 1, the current parameters are placed into non-volatile storage. (The byte sequence on the bus including the SDO protocol: 0x23 0x10 0x10 0x01 0x73 0x61 0x76 0x65).

The storage process takes about 3 seconds, and is confirmed, if successful, by the corresponding TxSDO (0x60 in the first byte). Since the Bus Coupler is unable to send or receive any CAN telegrams during the storage process, saving is only possible when the node is in the pre-operational state. It is recommended that the entire network is placed into the pre-operational state before such storage. This avoids a buffer overflow.

Data saved includes:

- The terminals currently inserted (the number of each terminal category)
- All PDO parameters (identifier, transmission type, inhibit time, mapping).

● [Gefahrinformation hier einfügen!]

I Note The stored identifiers apply afterwards, not the default identifiers derived from the node addresses. Changes to the DIP switch setting no longer affects the PDOs!

- All SYNC parameters
- All guarding parameters
- Limit values, delta values and interrupt enables for analog inputs

Parameters directly stored in the terminals by way of register communication are immediately stored there in non-volatile form.

Load default values

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1011	0	Restore Parameter	Unsigned8	ro	N	4	Number of reset options
	1	Restore all parameters	Unsigned32	rw	N	1	Resets all parameters to their default values
	4	Set manufacturer Defaults	Unsigned32	rw	N	1	Resets all coupler parameters to manufacturer's settings (including registers)

Writing the string *load* in ASCII code (hexadecimal 0x64616F6C) into sub-index 1 resets all parameters to default values (as initially supplied) **at the next boot (reset)**.

(The byte sequence on the bus including the SDO protocol: 0x23 0x11 0x10 0x01 0x6C 0x6F 0x61 0x64).

This makes the default identifiers for the PDOs active again.

Emergency identifier

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1014	0	COB-ID Emergency	Unsigned32	rw	N	0x0000008 0, + NodeID	Identifier of the emergency telegram

The bottom 11 bits of the 32 bit value contain the identifier (0x80=128 dec). The MSBit can be used to set whether the device sends (1) the emergency telegram or not (0).

Alternatively, the bus node's diagnostic function can also be switched off using the *Device diagnostics* bit in the K-Bus configuration (see object 0x4500).

Consumer heartbeat time

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1016	0	Number of elements	Unsigned8	ro	N	2	The consumer heartbeat time describes the expected heartbeat cycle time and the node ID of the monitored node
	1	Consumer heartbeat time	Unsigned32	rw	N	0	Watchdog time in ms and node ID of the monitored node

The 32-bit value is used as follows:

MSB		LSB
Bit 31...24	Bit 23...16	Bit 15...0
Reserved (0)	Node ID (unsigned8)	Heartbeat time in ms (unsigned16)

The monitored identifier can be obtained from the node ID by means of the default identifier allocation:
Guard-ID = 0x700 + Node-ID.

As is usual in CANopen, the LSB is transferred first, followed by the MSB.

Producer heartbeat time

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1017	0	Producer heartbeat time	Unsigned16	rw	N	0	Interval in ms between two transmitted heartbeat telegrams

Device identifier (identity object)

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1018	0	Identity Object: Number of elements	Unsigned8	ro	N	4	The identity object contains general information about the type and version of the device.
	1	Vendor ID	Unsigned32	ro	N	0x00000002	Manufacturer identifier. Beckhoff has vendor ID 2
	2	Product Code	Unsigned32	ro	N	Depends on the product	Device identifier
	3	Revision Number	Unsigned32	ro	N	-	Version number
	4	Serial Number	Unsigned32	ro	N	-	Production date low word, high byte: calendar week (dec), low word, low byte: calendar year

Product	Product Code
BK5120	0x11400
BK5110	0x113F6
LC5100	0x113EC
IPwxyz-B510	0x2wxyz
IL2301-B510	0x2008FD

Server SDO parameters

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1200	0	Number of elements	Unsigned8	ro	N	2	Communication parameters of the server SDO. Sub-index 0: number of following parameters
	1	COB-ID Client ->Server	Unsigned32	ro	N	0x000006xy, xy=Node-ID	COB-ID RxSDO (Client -> Server)
	2	COB-ID Server ->Client	Unsigned32	ro	N	0x00000580 + Node-ID	COB-ID TxSDO (Client -> Server)

This is contained in the object directory for reasons of backwards compatibility.

Communication parameters for the 1st RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1400	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the first receive PDO. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x000002xy, xy=Node-ID	COB-ID (Communication Object Identifier) RxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Present for reasons of backwards compatibility, but not used in the RxPDO.
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer. Watchdog time defined for monitoring reception of the PDO.

Sub-index 1 (COB-ID): The bottom 11 bits of the 32 bit value (bits 0-10) contain the CAN identifier. The MSB (bit 31) indicates whether the PDO exists currently (0) or not (1). Bit 30 indicates whether an RTR access to this PDO is permissible (0) or not (1). Changing the identifier (bits 0-10) is not allowed while the object exists (bit 31=0). Sub-index 2 contains the type of the transmission (see introduction to PDOs).

Communication parameters for the 2nd RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1401	0	Number of elements	Unsigned8	ro	N	5	Communication parameter for the second receive PDO.
	1	COB-ID	Unsigned32	rw	N	0x000003xy, xy=Node-ID	COB-ID (Communication Object Identifier) RxPDO2
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Present for reasons of backwards compatibility, but not used in the RxPDO.
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer. Watchdog time defined for monitoring reception of the PDO.

Communication parameters for the 3rd RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1402	0	Number of elements	Unsigned8	ro	N	5	Communication parameter for the third receive PDO.
	1	COB-ID	Unsigned32	rw	N	0x000004xy, xy=Node-ID	COB-ID (Communication Object Identifier) RxPDO3
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Present for reasons of backwards compatibility, but not used in the RxPDO.
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer. Watchdog time defined for monitoring reception of the PDO.

Communication parameters for the 4th RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1403	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the fourth receive PDO.
	1	COB-ID	Unsigned32	rw	N	0x000005xy, xy=Node-ID	COB-ID (Communication Object Identifier) RxPDO4
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Present for reasons of backwards compatibility, but not used in the RxPDO.
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer. Watchdog time defined for monitoring reception of the PDO.

Communication parameters for the 5th-16th RxPDOs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1404 - 0x140F (depending on the device type)	0	Number of elements	Unsigned8	ro	N	5	Communication parameter for the 5 th to 16 th receive PDOs.
	1	COB-ID	Unsigned32	rw	N	0x8000000	COB-ID (Communication Object Identifier) RxPDO5...16
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Present for reasons of backwards compatibility, but not used in the RxPDO.
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer. Watchdog time defined for monitoring reception of the PDO.

The number of RxPDOs for each bus node type can be found in the technical data.

Mapping parameters for the 1st RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1600	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameter of the first receive PDO; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x62000108	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x62000208	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N	0x62000808	8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The first receive PDO (RxPDO1) is provided by default for digital output data. Depending on the number of outputs inserted, the necessary length of the PDO is automatically determined, and the corresponding objects are mapped. Since the digital outputs are organised in bytes, the length of the PDO in bytes can be found directly at sub-index 0.

Changes to the mapping

The following sequence must be observed in order to change the mapping (specified as from CANopen, version 4):

1. Delete PDO (set bit 31 in the identifier entry (sub-index 1) of the communication parameters to 1)
2. Deactivate mapping (set sub-index 0 of the mapping entry to 0)
3. Change mapping entries (sub-indices 1...8)
4. Activate mapping (set sub-index 0 of the mapping entry to the correct number of mapped objects)
5. Create PDO (set bit 31 in the identifier entry (sub-index 1) of the communication parameters to 0)

Mapping parameters for the 2nd RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1601	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameter of the second receive PDO; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x64110110	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x64110210	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N	0x00000000	8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The second receive PDO (RxPDO2) is provided by default for analog outputs. Depending on the number of outputs inserted, the necessary length of the PDO is automatically determined, and the corresponding objects are mapped. Since the analog outputs are organised in words, the length of the PDO in bytes can be found directly at sub-index 0.

A specific sequence must be observed in order to change the mapping (see object index 0x1600).

Mapping parameters for the 3rd-16th RxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1602-0x160F (depending on the device type)	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameters for the third to sixteenth receive PDOs; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The 3rd to 16th receive PDOs (RxPDO3ff) are automatically given a default mapping by the bus node depending on the attached terminals (or depending on the extension modules). The procedure is described in the section on PDO Mapping.

A specific sequence must be observed in order to change the mapping (see object index 0x1600).

[Gefahrinformation hier einfügen!]

i NoteDS401 V2 specifies analog input and/or output data as the default mapping for PDOs 3+4. This corresponds to Beckhoff's default mapping when less than 65 digital inputs or outputs are present. In order to ensure backwards compatibility, the Beckhoff default mapping is retained - the mapping behaviour of the devices therefore corresponds to DS401 V1, where in all other respects they accord with DS401 V2.

Communication parameters for the 1st TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1800	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the first transmit PDO. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x00000180 + Node-ID	COB-ID (Communication Object Identifier) TxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Repetition delay [value x 100 µs]
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer

Sub-index 1 (COB-ID): The bottom 11 bits of the 32 bit value (bits 0-10) contain the CAN identifier. The MSB (bit 31) indicates whether the PDO exists currently (0) or not (1). Bit 30 indicates whether an RTR access to this PDO is permissible (0) or not (1). Changing the identifier (bits 0-10) is not allowed while the object exists (bit 31=0). Sub-index 2 contains the type of transmission, sub-index 3 the repetition delay between two PDOs of the same type, while sub-index 5 contains the event timer. Sub-index 4 is retained for reasons of compatibility, but is not used. (See also the introduction to PDOs.)

Communication parameters for the 2nd TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1801	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the second transmit PDO. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x00000280 + Node-ID	COB-ID (Communication Object Identifier) TxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Repetition delay [value x 100 µs]
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer

The second transmit PDO is provided by default for analog inputs, and is configured for event-driven transmission (transmission type 255). Event-driven mode must first be activated (see object 0x6423), otherwise the inputs can only be interrogated (polled) by remote transmission request (RTR).

Communication parameters for the 3rd TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1802	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the third transmit PDO. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x00000380 + Node-ID	COB-ID (Communication Object Identifier) TxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Repetition delay [value x 100 µs]
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer

The third transmit PDO contains analog input data as a rule (see Mapping). It is configured for event-driven transmission (transmission type 255). Event-driven mode must first be activated (see object 0x6423), otherwise the inputs can only be interrogated (polled) by remote transmission request (RTR).

Communication parameters for the 4th TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1803	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the fourth transmit PDO. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x00000480 + Node-ID	COB-ID (Communication Object Identifier) TxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Repetition delay [value x 100 µs]
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer

The fourth transmit PDO contains analog input data as a rule (see Mapping). It is configured for event-driven transmission (transmission type 255). Event-driven mode must first be activated (see object 0x6423), otherwise the inputs can only be interrogated (polled) by remote transmission request (RTR).

Communication parameters for the 5th-16th TxPDOs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1804-0x180F (depending on the device type)	0	Number of elements	Unsigned8	ro	N	5	Communication parameters for the 5 th to 16 th transmit PDOs. Sub-index 0: number of following parameters
	1	COB-ID	Unsigned32	rw	N	0x00000000	COB-ID (Communication Object Identifier) TxPDO1
	2	Transmission Type	Unsigned8	rw	N	255	Transmission type of the PDO
	3	Inhibit Time	Unsigned16	rw	N	0	Repetition delay [value x 100 µs]
	4	CMS Priority Group	Unsigned8	rw	N	-	Present for reasons of backwards compatibility, but not used.
	5	Event Timer	Unsigned16	rw	N	0	Event-Timer

Mapping 1st TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1A00	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameter of the first transmit PDO; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x60000108	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x60000208	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N	0x60000808	8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The first transmit PDO (TxPDO1) is provided by default for digital input data. Depending on the number of inputs inserted, the necessary length of the PDO is automatically determined, and the corresponding objects are mapped. Since the digital inputs are organised in bytes, the length of the PDO in bytes can be found directly at sub-index 0.

A specific sequence must be observed in order to change the mapping (see object index 0x1600).

Mapping 2nd TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1A01	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameter of the second transmit PDO; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x64010110	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x64010210	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N		8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The second transmit PDO (TxPDO2) is provided by default for analog input data. Depending on the number of inputs inserted, the necessary length of the PDO is automatically determined, and the corresponding objects are mapped. Since the analog inputs are organised in words, the length of the PDO in bytes can be found directly at sub-index 0.

A specific sequence must be observed in order to change the mapping (see object index 0x1600).

Mapping 3rd-16th TxPDO

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x1A02-0x1A0F (depending on the device type)	0	Number of elements	Unsigned8	rw	N	Depending on type and fittings	Mapping parameters for the third to sixteenth transmit PDOs; sub-index 0: number of mapped objects.
	1	1 st mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	1 st mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)
	2	2 nd mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	2 nd mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

	8	8 th mapped object	Unsigned32	rw	N	0x00000000 0 (see text)	8 th mapped application object (2 bytes index, 1 byte sub-index, 1 byte bit width)

The 3rd to 16th transmit PDOs (TxPDO3ff) are automatically given a default mapping by the bus node depending on the attached terminals (or depending on the extension modules). The procedure is described in the section on PDO Mapping.

A specific sequence must be observed in order to change the mapping (see object index 0x1600).

● [Gefahrinformation hier einfügen!]

i NoteDS401 V2 specifies analog input and/or output data as the default mapping for PDOs 3+4. This corresponds to Beckhoff's default mapping when less than 65 digital inputs or outputs are present. In order to ensure backwards compatibility, the Beckhoff default mapping is retained - the mapping behavior of the devices therefore corresponds to DS401 V1, where in all other respects they accord with DS401 V2.

For the sake of completeness, the following object entries are also contained in the object directory (and therefore also in the EDS files):

Index	Meaning
0x2000	Digital inputs (function identical to object 0x6000)
0x2100	Digital outputs (function identical to object 0x6100)

Index	Meaning
0x2200	1-byte special terminals, inputs (at present no terminals corresponding to this type are included in the product range)
0x2300	1-byte special terminals, outputs (at present no terminals corresponding to this type are included in the product range)
0x2400	2-byte special terminals, inputs (at present no terminals corresponding to this type are included in the product range)
0x2500	2-byte special terminals, outputs (at present no terminals corresponding to this type are included in the product range)
0x2E00	7-byte special terminals, inputs (at present no terminals corresponding to this type are included in the product range)
0x2F00	7-byte special terminals, outputs (at present no terminals corresponding to this type are included in the product range)

3-byte special terminals, input data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2600	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 3-byte special channels, inputs
	1	1 st input block	Unsigned24	ro	Y	0x000000	1 st input channel

	0X80	128 th input block	Unsigned24	ro	Y	0x000000	128 th input channel

Example of special terminals with 3-byte input data (in the default setting): KL2502 (PWM outputs, 2 x 3 bytes)

3-byte special terminals, output data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2700	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 3-byte special channels, outputs
	1	1 st output block	Unsigned24	rww	Y	0x000000	1 st output channel

	0X80	128 th output block	Unsigned24	rww	Y	0x000000	128 th output channel

Example of special terminals with 3-byte output data (in the default setting): KL2502 (PWM outputs, 2 x 3 bytes)

4-byte special terminals, input data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2800	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 4-byte special channels, inputs
	1	1 st input block	Unsigned32	ro	Y	0x00000000	1 st input channel

	0X80	128 th input block	Unsigned32	ro	Y	0x00000000	128 th input channel

Examples of special terminals with 4-byte input data (in the default setting): KL5001, KL6001, KL6021, KL6051

4-byte special terminals, output data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2900	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 4-byte special channels, outputs
	1	1 st output block	Unsigned32	rww	Y	0x00000000	1 st output channel

	0X80	128 th output block	Unsigned32	rww	Y	0x00000000	128 th output channel

Examples of special terminals with 4-byte output data (in the default setting): KL5001, KL6001, KL6021, KL6051

5-byte special terminals, input data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2A00	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 5-byte special channels, inputs
	1	1 st input block	Unsigned40	ro	Y	0x00000000	1 st input channel

	0X40	64 th input block	Unsigned40	ro	Y	0x00000000	64 th input channel

Example of special terminals with 5-byte input data (in the default setting): KL1501

5-byte special terminals, output data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2B00	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 5-byte special channels, outputs
	1	1 st output block	Unsigned40	rww	Y	0x00000000	1 st output channel

	0X40	64 th output block	Unsigned40	rww	Y	0x00000000	64 th output channel

Example of special terminals with 5-byte output data (in the default setting): KL1501

6-byte special terminals, input data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2C00	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 6-byte special channels, inputs
	1	1 st input block	Unsigned48	ro	Y	0x00000000	1 st input channel

	0X40	64 th input block	Unsigned48	ro	Y	0x00000000	64 th input channel

Example of special terminals with 6-byte input data (in the default setting): KL5051, KL5101, KL5111

6-byte special terminals, output data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x2D00	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 6-byte special channels, outputs
	1	1 st output block	Unsigned48	rww	Y	0x00000000	1 st output channel

	0X40	64 th output block	Unsigned48	rww	Y	0x00000000	64 th output channel

Example of special terminals with 6-byte output data (in the default setting): KL5051, KL5101, KL5111

8-byte special terminals, input data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x3000	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 6-byte special channels, inputs
	1	1 st input block	Unsigned64	ro	Y	0x00000000	1 st input channel

	0x40	64 th input block	Unsigned64	ro	Y	0x00000000	64 th input channel

Example for special terminals with 8-byte input data: KL5101 (with word alignment, not according to the default setting)

8-byte special terminals, output data

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x3100	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available 6-byte special channels, outputs
	1	1 st output block	Unsigned64	rww	Y	0x00000000	1 st output channel

	0X40	64 th output block	Unsigned64	rww	Y	0x00000000	64 th output channel

Example for special terminals with 8-byte output data: KL5101 (with word alignment, not according to the default setting)

Bus node register communication

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x4500	0	Register Access	Unsigned32	rw	N	none	Access to internal bus node registers

The 32 bit value is composed as follows:

MSB		LSB	
Access (bit 7) + table number (bits 6...0)	Register number	High byte register value	Low byte register value
[0..1] + [0...0x7F]	[0...0xFF]	[0...0xFF]	[0...0xFF]

As is usual in CANopen, the LSB is transferred first, followed by the MSB.

Accessing index 0x4500 allows any registers in the bus station to be written or read. The channel number and the register are addressed here with a 32 bit data word.

Reading the register value

The coupler must first be informed of which register is to be read. This requires an SDO write access to the appropriate index/sub-index combination, with:

- table number (access bit = 0) in byte 3
- register address in byte 2 of the 32-bit data value.

Bytes 1 and 0 are not evaluated if the access bit (MSB of byte 3) equals 0. The register value can then be read with the same combination of index and sub-index.

After the writing of the register address to be read, the coupler sets the access bit to 1 until the correct value is available. Thus an SDO read access must check that the table number lies in the range from 0...0x7F.

An access error during register communication is indicated by the corresponding return value in the SDO protocol (see the SDO section, Breakdown of parameter communication).

An example of reading register values

It is necessary to determine which baud rate index has been assigned to switch setting 1,1 (DIP 7,8). (See the section covering *Network addresses and baud rates*). To do this, the value in table 100, register 3, must be read. This means that the following SDO telegrams must be sent:

Write access (download request) to index 4500, sub-index 0, with the 32 bit data value 0x64 03 00 00.

Id=0x600+Node-ID DLC=8; Data=23 00 45 00 00 00 03 64

Then a read access (upload request) to the same index/sub-index. The data value sent here is irrelevant (00 is used here).

Id=0x600+Node-ID DLC=8; Data=40 00 45 00 00 00 00 00

The coupler responds with the upload response telegram:

Id=0x580+Node-ID DLC=8; Data=43 00 45 00 04 00 03 64

This tells us that the value contained in this register is 4, and this baud rate index corresponds to 125 kbit/s (the default value).

Writing register values

SDO write access to the corresponding combination of index and sub-index with:

- table number + 0x80 (access bit = 1) in byte 3
- register address in byte 2
- high byte register value in byte 1
- low byte register value in byte 0 of the 32-bit data value.

Remove coupler write protection

Before the registers of the Bus Coupler can be written, the write protection must first be removed. In order to do this, the following values must be written in the given sequence to the corresponding registers:

Step	Table	Register	Value	Corresponding SDO download value (0x4500/0)
1.	99	2	45054 (0xAFFE)	0xE3 02 AF FE (0xE3=0x63(=99)+0x80)
2.	99	1	1 (0x0001)	0xE3 01 00 01
3.	99	0	257 (0x0101)	0xE3 00 01 01

Remove coupler write protection (CAN representation)

In order to remove the coupler write protection, the following SDO telegrams (download requests) must thus be sent to the coupler:

Id=0x600+Node-ID DLC=8; Data=23 00 45 00 FE AF 02 E3

Id=0x600+Node-ID DLC=8; Data=23 00 45 00 01 00 01 E3

Id=0x600+Node-ID DLC=8; Data=23 00 45 00 01 01 00 E3

An example of writing register values

After the write protection has been removed, the baud rate index for DIP switch setting 1,1 is to be set to the value 7. This will assign a baud rate of 20 kbaud to this switch setting.

This requires the value 7 to be written into table 100, register 3. This is done with an SDO write access (download request) to index 0x4500, sub-index 0 with the 32 bit value E4 03 00 07 (0xE4 = 0x64+0x80):

Id=0x600+Node-ID DLC=8; Data=23 00 45 00 07 00 03 E4

Identify terminals

The identifier of the coupler (or of the bus station) and of the attached Bus Terminals can be read from the Bus Coupler's table 9. Register 0 then contains the identifier of the Bus Coupler itself, register 1 the identifier of the first terminal and register n the identification of the nth terminal:

Table number	Register number	Description	Value range
9	0	Bus station identifier	0 - 65535
9	1-255	Identifier of the extension module/bus terminal	0 - 65535

The Bus Coupler description in register number 0 contains 5120 = 0x1400 for the BK5120, 5110 = 0x13F6 for the BK5110 and 5100 = 0x13EC for the LC5100. The Fieldbus Box modules contain the identifier 510 dec = 0x1FE in register 0.

In the case of analog and special terminals, the terminal identifier (dec) is contained in the extension module identifier or the terminal description.

Example: if a KL3042 is plugged in as the third terminal, then register 3 contains the value 3042_{dec} (0x0BE2).

The following bit identifier is used for digital terminals:

MSB								LSB							
1	s6	s5	s4	s3	s2	s1	s0	0	0	0	0	0	0	a	e

s6...s1: data width in bits; a=1: output terminal; e=1: input terminal

This identifier scheme results in the terminal descriptions listed below:

Extension module identifier	Meaning
0x8201	2 bit digital input terminal, e.g. KL1002, KL1052, KL9110, KL9260
0x8202	2 bit digital output terminal, e.g. KL2034, KL2612, KL2702
0x8401	4 bit digital input terminal, e.g. KL1104, KL1124, KL1194
0x8402	4 bit digital output terminal, e.g. KL2124, KL2134, KL2184
0x8403	4 bit digital input/output terminal, e.g. KL2212

General coupler configuration (table 0)

Table 0 of the Bus Coupler contains the data for the general coupler configuration. It is not, as a general rule, necessary to change this; however, for special applications it is possible to change the settings using the KS2000 configuration software, or through direct access via register communication. The write protection must first be removed in order to do this (see above).

The relevant register entries are described below:

K-Bus configuration

Table 0, register 2, contains the K-Bus configuration, and is coded as follows (default value: 0x0006):

MSB								LSB							
0	0	0	0	0	0	0	0	0	0	0	0	0	D	G	A

A: Auto-reset

If there is a K-Bus error, attempts are made cyclically to start the K-Bus up again through a reset. If emergency telegrams and guarding are not evaluated, activation of auto-reset can lead to output and input information being lost without that loss being noticed.

0: No auto-reset (default)

1: Auto-reset active

G: Device diagnostics

Reporting (by means of emergency telegram), that, for example
 - a current input is open circuit (with diagnostics)
 - 10 V exceeded at a 1-10V input terminal

0: Device diagnostics switched off

1: Device diagnostics active (default)

D: Diagnostic data

from digital terminals is included in the process image (e.g. KL2212). This flag is only evaluated when device diagnostics is active (see above).

0: Do not display

1: Display (default)

Process image description

Table 0, register 3, contains the process image description, and is coded as follows (default value: 0x0903):

MSB								LSB							
0	0	0	0	k1	k0	f1	f0	0	0	a	0	d	k	1	1

k0...k1: Reaction to K-Bus errors

0,2: Inputs remain unchanged (default = 2);

1: Set inputs to 0 (TxPDO with zeros is sent)

f0...f1: Reaction to fieldbus error

0: Stop the K-Bus cycles, watchdog in the terminals triggers, fault output values become active. The old output values are initially set during a restart.

1: Set outputs to 0, then stop the K-Bus cycles (default). 2: Outputs remain unchanged.

a: Word alignment (of analog and special terminals)

0: No alignment (default)

1: Map data to word boundaries (process data always starts on an even address in the PDO)

d: Data format for complex terminals (analog and special terminals)

0: Intel format (default)

1: Motorola format

k: Evaluation of complex terminals (analog and special terminals)

0: User data only (default)

1: Complete evaluation (note: analog channels then, for example, need 3 input and 3 output bytes instead of, e.g., 2 input bytes; instead of 4 channels per PDO, 2 channels require a RxPDO and a TxPDO)

Bus Terminal / Extension Box register communication

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x4501	0	Access Terminal Register	Unsigned8	ro	N	none	Index 0x4501 allows access to all the registers in the bus terminal or extension module. Sub-index 0 contains the number of attached bus terminals.
	1	Access Reg. Terminal 1	Unsigned32	rw	N	none	Access to bus terminal or extension module register 1

	0XFE	Access Reg. Terminal 254	Unsigned32	rw	N	none	Access to bus terminal or extension module register 254

The 32 bit value is composed as follows:

MSB			LSB
Access (bit 7) + channel number (bits 6...0)	Register number	High byte register value	Low byte register value
[0..1] + [0...0x7F]	[0...0xFF]	[0...0xFF]	[0...0xFF]

As is usual in CANopen, the LSB is transferred first, followed by the MSB.

Accessing index 0x4501 allows the user registers in the bus terminal or extension module to be written or read. The modules have a set of registers for each input or output channel. The modules are addressed by means of the sub-index; the channel number and register are addressed in the 32-bit data value. Channel number 0 corresponds here to the first channel, 1 to the second channel, and so forth.

Reading the register value

The coupler must first be informed of which register is to be read. This requires an SDO write access to the appropriate index/sub-index combination, with:

- channel number (access bit = 0) in byte 3
- register address in byte 2 of the 32-bit data value.

Bytes 1 and 0 are not evaluated if the access bit (MSB of byte 3) equals 0. The register value can then be read with the same combination of index and sub-index.

After the writing of the register address to be read, the coupler sets the access bit to 1 until the correct value is available. Thus an SDO read access must check that the table number lies in the range from 0...0x7F.

An access error during register communication is indicated by the corresponding return value in the SDO protocol (see the SDO section, Breakdown of parameter communication).

An example of reading register values

The thermocouple type to which the second input channel of a KL3202 Thermocouple Input Terminal has been set is to be determined. This requires feature register 32 to be read. The terminal is located in the fifth slot, next to the Bus Coupler. This means that the following SDO telegrams must be sent:

Write access (download request) to index 4501, sub-index 5 with 32 bit data value 01 20 00 00 (0x01 = 2nd channel, 0x20 = register 32)

Id=0x600+Node-ID DLC=8; Data=23 01 45 05 00 00 20 01

Then a read access (upload request) to the same index/sub-index. The data value sent here is irrelevant (0x00 is used here).

Id=0x600+Node-ID DLC=8; Data=40 01 45 05 00 00 00 00

The coupler responds with the upload response telegram:

Id=0x580+Node-ID DLC=8; Data=43 01 45 05 06 31 20 01

This means that the feature register contains the value 31 06. The upper 4 bits indicate the thermocouple type. Their value here is 3, which means that PT500 is the type that has been set for this channel (see the KL3202 documentation).

Writing register values

SDO write access to the corresponding combination of index and sub-index with:

- channel number + 0x80 (access bit = 1) in byte 3
- register address in byte 2
- high byte register value in byte 1
- low byte register value in byte 0 of the 32-bit data value.

NOTICE

[Gefahrinformation hier einfügen!]

Warning! If the write protection is not removed (as a result, for instance, of a faulty codeword), then although a write access to the terminal register will be confirmed (SDO download response), the value is not in fact entered into the register. It is therefore recommended that the value is read back after writing and compared.

Remove terminal write protection

Before the user registers in the Bus Terminal (register 32-xx, depending on terminal type or extension module) can be written to, it is first necessary for write protection to be removed. The following codeword is written for this purpose into register 31 of the channel concerned:

Write protection	Channel	Register	Value	Corresponding SDO download value (0x4500/0)
	1,2, 3 or 4	31 (0x1F)	4661 (0x1235)	8y 1F 12 35 (y = channel number)

Remove terminal write protection (CAN representation)

In order to remove the terminal's write protection, the following SDO telegram must thus be sent to the coupler:

Id=600 + Node-ID DLC=8; Data=23 01 45 xx 35 12 1F 8y

where xx is the terminal's slot, and y indicates the channel.

An example of removing write protection

Suppose that a KL3202 Thermocouple Input Terminal is inserted into slot 5 of a BK5120 that has node address 3, then the write protection for the first channel can be removed as follows:

Id=0x603 DLC=8; Data=23 01 45 05 35 12 1F 80

The following telegram is sent for the second channel:

Id=0x603 DLC=8; Data=23 01 45 05 35 12 1F 81

An example of writing register values

The type of thermocouple attached to the second channel of the KL3202 Terminal in slot 5 is now to be changed to PT1000. For this purpose, the value 2 must be written into the upper 4 bits (the upper nibble) of the feature register. It is assumed to that the default values are to be supplied for all the other bits in the feature register. Once the write protection has been removed, SDO write access (download request) is used to write the following 32 bit value into index 0x4501, sub-index 05: 81 20 21 06 (0x81=01+0x80; 0x20=32;0x2106 = register value).

The corresponding telegram on the bus looks like this:

Id=0x600+Node-ID DLC=8; Data=23 01 45 05 06 21 20 81

Activate PDOs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x5500	0	Activate PDO Defaults	Unsigned32	rw	N	0x00000000 0	sets PDO communication parameters for PDOs 2...11

CANopen defines default identifiers for 4 transmit (Tx) and 2 receive (Rx) PDOs, all other PDOs being initially deactivated after the nodes have started up. Index 0x5500 can activate all the PDOs that, in accordance with the terminals inserted, are filled with process data (manufacturer-specific default mapping). A manufacturer-specific default identifier allocation is carried out here for PDO5...11, while the transmission type and a uniform inhibit time is set for PDO2...11. PDOs that do not have process data (and which are thus superfluous in the present configuration) are not activated.



[Gefahrinformation hier einfügen!]

Note This object can only be written in the pre-operational state!

The 32-bit value is used as follows:

MSB		LSB	
Transmission Type RxPDOs	Transmission Type TxPDOs	High byte inhibit time	Low byte inhibit time

As is usual in CANopen, the LSB is transferred first, followed by the MSB.

Example

Activate PDOs for bus node number 1, set inhibit time to 10ms (=100 x 100µs), set transmission type for TxPDOs to 255, and set transmission type for RxPDOs to 1. The following telegram must be sent:
 Id=0x601 DLC=8; Data=23 00 55 00 64 00 FF 01

The node responds with the following telegram:
 Id=0x601 DLC=8; Data=60 00 55 00 00 00 00 00

Identifiers used

The default identifier allocation for the additional PDOs leaves the pre-defined regions for guarding, SDOs etc. free, assumes a maximum of 64 nodes in the network with PDO6 as the next node, and proceeds according to the following scheme:

Object	Function code	Resulting COB ID (hex)	Resulting COB ID (dec)
TxPDO5	1101	0x681 - 0x6BF	1665 - 1727
RxPDO5	1111	0x781 - 0x7BF	1921- 1983
TxPDO6	00111	0x1C1 - 0x1FF	449 - 511
RxPDO6	01001	0x241 - 0x27F	577 - 639
TxDPO7	01011	0x2C1 - 0x2FF	705 - 767
RxPDO7	01101	0x341 - 0x37F	833 - 895
TxPDO8	01111	0x3C1- 0x3FF	961 - 1023
RxPDO8	10001	0x441 - 0x47F	1089 - 1151
TxPDO9	10011	0x4C1 - 0x4FF	1217 - 1279
RxPDO9	10101	0x541 - 0x57F	1345 - 1407
TxDPO10	10111	0x5C1 - 0x5FF	1473 - 1535
RxPDO10	11001	0x641 - 0x67F	1601- 1663
TxPDO11	11011	0x6C1 - 0x6FF	1729 - 1791
RxPDO11	11101	0x741 - 0x77F	1857 - 1919

NOTICE

[Gefahrinformation hier einfügen!]

WarningEnsure that index 0x5500 is not used if Bus Couplers with more than 5 PDOs are present in networks with node addresses > 64, otherwise identification overlaps can occur. In that case, the PDO identifiers must be set individually.

For the sake of clarity, the default identifiers defined according to CANopen are also listed here:

Object	Function code	Resulting COB ID (hex)	Resulting COB ID (dec)
Emergency	0001	0x81 - 0xBF [0xFF]	129 - 191 [255]
TxPDO1	0011	0x181 - 0x1BF [0x1FF]	385 - 447 [511]
RxPDO1	0100	0x201 - 0x23F [0x27F]	513 - 575 [639]
TxPDO2	0101	0x281 - 0x2BF [0x2FF]	641 - 676 [767]
RxPDO2	0110	0x301 - 0x33F [0x37F]	769 - 831 [895]
TxDPO3	0111	0x381 - 0x3BF [0x3FF]	897 - 959 [1023]
RxPDO3	1000	0x401 - 0x43F [0x47F]	1025 - 1087 [1151]
TxPDO4	1001	0x481 - 0x4BF [0x4FF]	1153 - 1215 [1279]
RxPDO4	1010	0x501 - 0x53F [0x57F]	1281- 1343 [1407]
SDO (Tx)	1011	0x581 - 0x5BF [0x5FF]	1409 - 1471 [1535]
SDO (Rx)	1100	0x601 - 0x63F [0x67F]	1537 - 1599 [1663]
Guarding / Heartbeat/ Bootup	1110	0x701 - 0x73F [0x77F]	1793 - 1855 [1919]

The identifiers that result from the DIP switch settings on the coupler are given, as are the identifier regions for the node addresses 64...127 (not settable in Bus Couplers BK5110, BK5120 and LC5100) in square brackets. Addresses 1...99 can be set for the Fieldbus Box modules and the BK515x Bus Couplers.

The appendix contains a tabular summary of all the identifiers.

Digital inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6000	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available digital 8-bit input data blocks
	1	1 st input block	Unsigned8	ro	Y	0x00	1 st input channel

	0XFE	254 th input block	Unsigned8	ro	Y	0x00	254 th input channel

Interrupt mask

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6126	0	Number of elements	Unsigned8	ro	N	Depending on type	The number of 32-bit interrupt masks = 2 x the number of TxPDOs
	1	IR-Mask0 TxPDO1	Unsigned32	rw	N	0xFFFFFFFF	IR-mask bytes 0...3 TxPDO1
	2	IR-Mask1 TxPDO1	Unsigned32	rw	N	0xFFFFFFFF	IR-mask bytes 4...7 TxPDO1
	3	IR-Mask0 TxPDO2	Unsigned32	rw	N	0xFFFFFFFF	IR-mask bytes 0...3 TxPDO2

	0x20	IR-Mask1 TxPDO16	Unsigned32	rw	N	0xFFFFFFFF	IR-mask bytes 4...7 TxPDO16

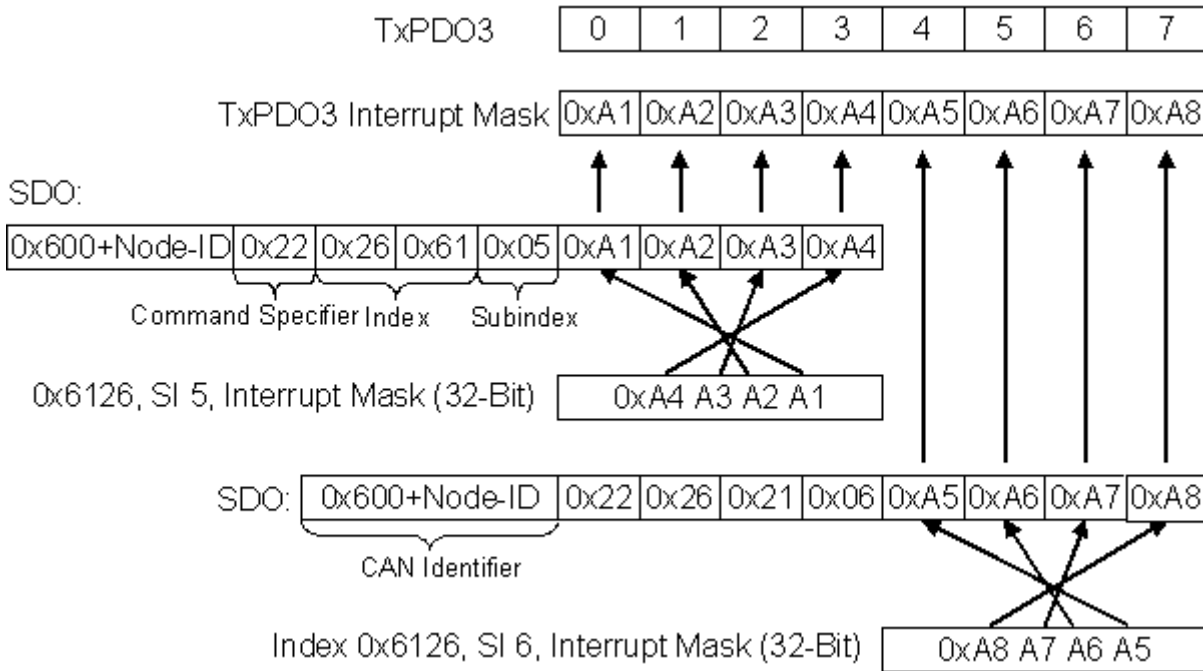
By default, every change in the value in an event-driven PDO causes a telegram to be sent. The interrupt mask makes it possible to determine which data changes are evaluated for this purpose. By clearing the appropriate ranges within the PDOs they are masked out for event-driving purposes (interrupt control). The interrupt mask does not just govern all the PDOs with digital inputs, but all the TxPDOs that are present. If the TxPDOs are shorter than 8 bytes, then the superfluous part of the IR mask is not evaluated.

The interrupt mask only has an effect on TxPDOs with transmission types 254 and 255. It is not stored in the device (not even through object 0x1010). Changes to the mask at runtime (when the status is operational) are possible, and are evaluated starting from the next change of input data.

The interrupt mask for TxPDOs with analog input data is not evaluated if either limit values (0x6424, 0x6425) or the delta function (0x6426) have been activated for the inputs.

This entry has been implemented in firmware C3 and above.

Example of data assignment



Application example

The value contained in a fast counter input is only to be transmitted when bits in the status word (the latch input, for instance) have changed. This requires the 32 bit counter value to be masked out (zeroed) in the interrupt mask. The status is located in byte 0, while the counter value is, by default, contained in bytes or 1..4 of the corresponding PDOs (TxPDO3 in this example, because < 65 digital and < 5 analog inputs are present).

This means that index 0x6126, sub-index5 must receive the value 0x0000 00FF and that sub-index6 must have 0xFFFF FF00 written into it.

The corresponding SDOs therefore appear as follows:

11 bit identifier	8 bytes of user data							
0x600+ node ID	0x22	0x26	0x61	0x05	0xFF	0x00	0x00	0x00

11 bit identifier	8 bytes of user data							
0x600+ node ID	0x22	0x26	0x61	0x06	0x00	0xFF	0xFF	0xFF

Digital outputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6200	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of available digital 8-bit output data blocks
	1	1 st input block	Unsigned8	rw	Y	0x00	1 st output channel

	0xFE	254 th input block	Unsigned8	rw	Y	0x00	254 th output channel

Analog inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6401	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of analog input channels available
	1	1 st input	Unsigned16	ro	Y	0x0000	1 st input channel

	0XFE	254 th input	Unsigned16	ro	Y	0x0000	254 th input channel

The analog signals are displayed left aligned. The representation in the process image is therefore independent of the actual resolution. Detailed information on the data format can be found at the relevant signal type.

Analog outputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6411	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of analog output channels available
	1	1 st input block	Unsigned16	rw	Y	0x0000	1 st output channel

	0XFE	254 th input block	Unsigned16	rw	Y	0x0000	254 th output channel

The analog signals are displayed left aligned. The representation in the process image is therefore independent of the actual resolution. Detailed information on the data format can be found at the relevant signal type.

Event driven analog inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6423	0	Global Interrupt Enable	Boolean	rw	N	FALSE (0)	Activates the event-driven transmission of PDOs with analog inputs.

Although, in accordance with CANopen, the analog inputs in TxPDO2..4 are by default set to transmission type 255 (event driven), the event (the alteration of an input value) is suppressed by the event control in object 0x6423, in order to prevent the bus from being swamped with analog signals. It is recommended that the flow of data associated with the analog PDOs is controlled either through synchronous communication or through using the event timer. In event-driven operation, the transmission behavior of the analog PDOs can be parameterized before activation by setting the inhibit time (object 0x1800ff, sub-index 3) and/or limit value monitoring (objects 0x6424 + 0x6425) and/or delta function (object 0x6426).

Upper limit value analog inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6424	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of analog input channels available
	1	upper limit 1 st input	Unsigned16	rw	Y	0x0000	Upper limit value for 1 st input channel

	0XFE	upper limit 254 th input	Unsigned16	rw	Y	0x0000	Upper limit value for 254 th input channel

Values different from 0 activate the upper limit value for this channel. A PDO is then transmitted if this limit value is exceeded. In addition, the event driven mode must be activated (object 0x6423). The data format corresponds to that of the analog inputs.

Lower limit value analog inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6425	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of analog input channels available
	1	lower limit 1 st input	Unsigned16	rw	Y	0x0000	Lower limit value for 1 st input channel

	0XFE	lower limit 254 th input	Unsigned16	rw	Y	0x0000	Lower limit value for 254 th input channel

Values different from 0 activate the lower limit value for this channel. A PDO is then transmitted if the value falls below this limit value. In addition, the event driven mode must be activated (object 0x6423). The data format corresponds to that of the analog inputs.

Delta function for analog inputs

Index	Sub-index	Name	Type	Attribute	Mapping	Default value	Meaning
0x6426	0	Number of elements	Unsigned8	ro	N	Depending on type and fittings	Number of analog input channels available
	1	delta value 1 st input	Unsigned16	rw	Y	0x0000	Delta value for the 1 st input channel

	0XFE	delta value 254 th input	Unsigned16	rw	Y	0x0000	Delta value for the 254 th input channel

Values different from 0 activate the delta function for this channel. A PDO is then transmitted if the value has changed by more than the delta value since the last transmission. In addition, the event driven mode must be activated (object 0x6423). The data format corresponds to that of the analog inputs (delta value: can only have positive values).

5 Commissioning

5.1 Mounting

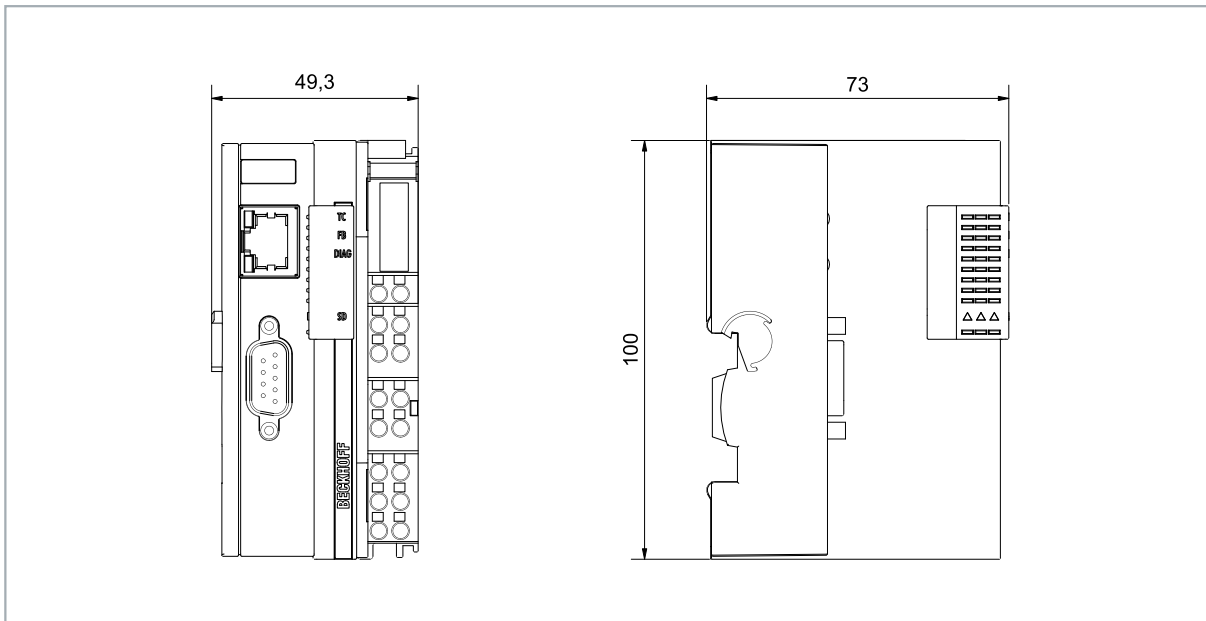


Fig. 17: CX70xx Embedded PC, dimensions.

5.1.1 Note the permissible installation positions

NOTICE

Overheating

The Embedded PC may overheat if the installation position is incorrect or the minimum distances are not adhered to. Adhere to the maximum ambient temperature of 60°C and the mounting instructions.

Install the Embedded PC horizontally in the control cabinet on a DIN rail, in order to ensure optimum heat dissipation.

Note the following specifications for the control cabinet:

- The Embedded PC should only be operated at ambient temperatures between -25 °C and 60 °C. Measure the temperature below the Embedded PC at a distance of 30 mm to the cooling fins, in order to determine the ambient temperature correctly.
- Adhere to the minimum distances of 30 mm above and below the Embedded PC.
- Additional electrical equipment affects the heat generation in the control cabinet. Select a suitable control cabinet enclosure depending on the application, or ensure that excess heat is dissipated from the control cabinet.

The Embedded PC must be mounted horizontally on the DIN rail. Ventilation openings are located at the top and bottom of the housing. This ensures an optimum airflow through the Embedded PC in vertical direction. In addition, a minimum clearance of 30 mm above and below the Embedded PC is required, in order to ensure adequate ventilation.

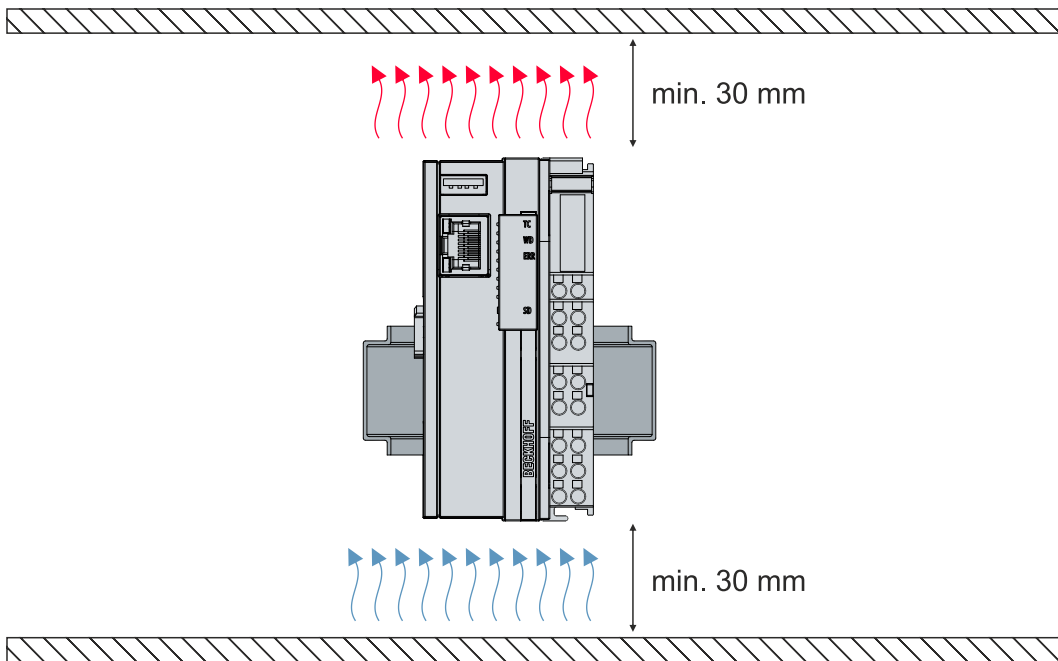


Fig. 18: CX70xx Embedded PC, permissible installation position.

If vibrations and impact occur in the same direction as the DIN rail, the Embedded PC must be secured with an additional bracket, in order to prevent it slipping.

Installation positions with reduced temperature range up to 45 °C

You can also mount the Embedded PC vertically or horizontally on the mounting rail. Note that you can then only operate the Embedded PC up to an ambient temperature of 45 °C.

Ensure that Bus Terminals that are connected to the Embedded PC are designed for operation in vertical or horizontal position.

Restrictions for E-bus/K-bus current

The maximum E-bus/K-bus current varies depending on the selected installation position and the ambient temperature.

Table 5: Maximum E-bus/K-bus current depending on the selected installation position and the ambient temperature.

E-bus/K-bus current	Installation position	Ambient temperature
max. 1.5 A	variable	-25...45 °C
max. 1.3 A	horizontal	-25...55 °C
max. 1 A	variable	-25...55 °C
max. 1 A	horizontal	-25...60 °C

5.1.2 Fastening to the DIN rail

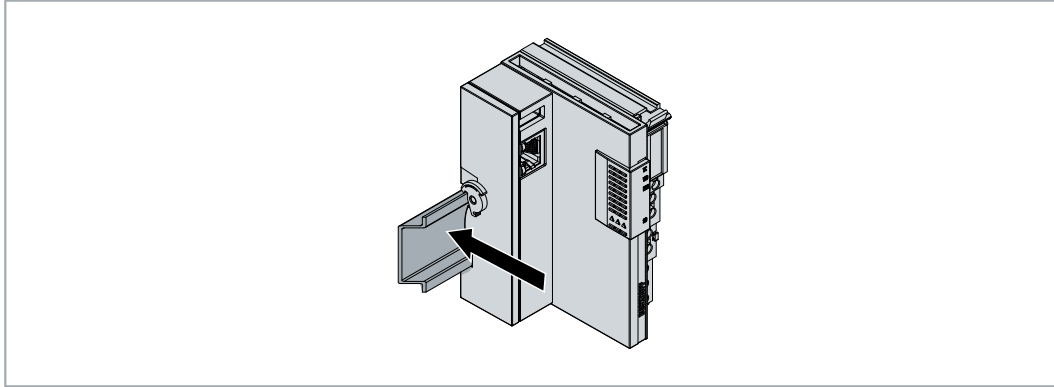
The housing is designed such that the Embedded PC can be pushed against the DIN rail and latched onto it.

Requirements:

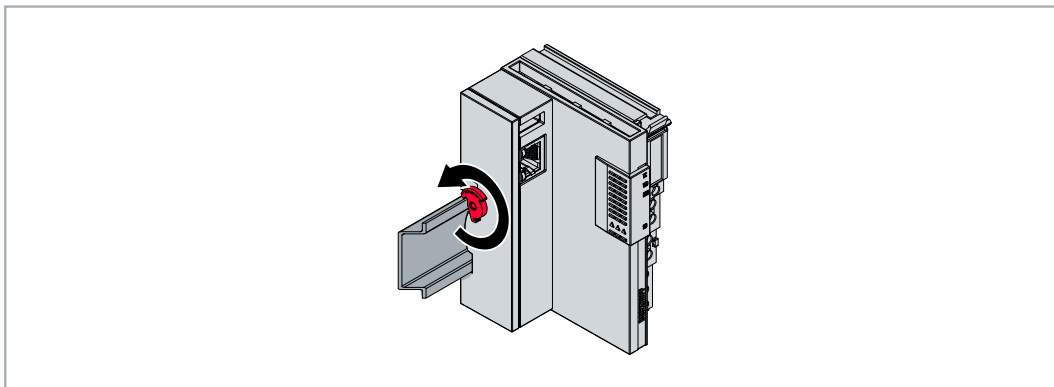
- DIN rail of the type TS35/7.5 or TS35/15 according to EN 60715.

Fasten the Embedded PC to the DIN rail as follows:

1. Place the Embedded PC on the DIN rail. Slightly press the Embedded PC onto the DIN rail until a soft click can be heard and the Embedded PC has latched.



2. Subsequently, lock the catch on the left side of the Embedded PC.
3. Turn the latch counter clockwise until the latch quietly clicks and engages.



- ⇒ You have installed the Embedded PC successfully. Check again that the mounting is correct and that the Embedded PC is engaged on the DIN rail.

5.1.3 Changing the MicroSD card

● Loss of data

i MicroSD cards are subjected to heavy load during operation and have to withstand many write cycles and extreme ambient conditions. MicroSD cards from other manufacturer may fail, resulting in data loss.

Only use industrial MicroSD cards provided by Beckhoff.

The MicroSD card slot is intended for an industrially compatible MicroSD card. The firmware of the Embedded PC is stored on the MicroSD card. If necessary, the MicroSD card can be written to from TwinCAT 3, allowing user-defined data to be stored.

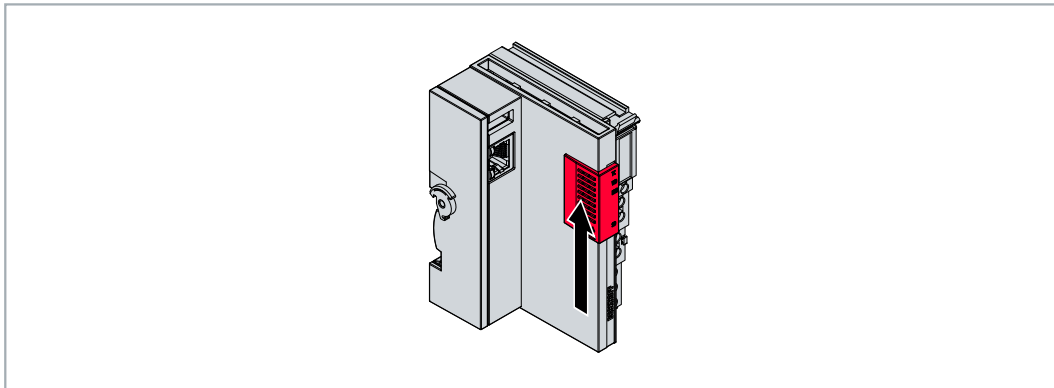
The eject mechanism is based on the push/push principle. Below, we show you how to change the MicroSD card.

Requirements:

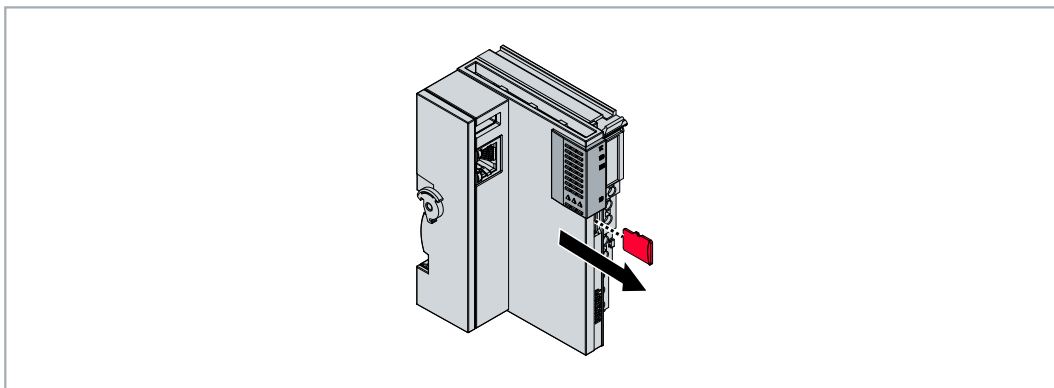
- The Embedded PC must be switched off. The MicroSD card may only be installed or removed in switched-off state.

Changing the MicroSD card

1. Push the black cover upwards.



2. Gently push the MicroSD card.
3. The card is unlatched with a quiet click and raised about 2 – 3 mm out of the housing.



4. Push the new MicroSD card into the card slot with the contacts at the front. The contacts face to the right.
5. A soft click can be heard when the MicroSD card engages.
⇒ The card is seated correctly when it is about 1 mm deeper than the front side of the housing.

5.1.4 Installing passive EtherCAT Terminals

Incorrectly installed passive EtherCAT Terminals

i The E-bus signal between an Embedded PC and the EtherCAT Terminals can be impaired due to incorrectly installed passive EtherCAT Terminals.

Passive EtherCAT Terminals should not be installed directly on the power supply unit.

EtherCAT Terminals that do not take part in active data exchange are referred to as passive terminals. Passive EtherCAT Terminals have no process image and do not require current from the terminal bus (E-bus).

Passive EtherCAT Terminals (e.g. EL9195) can be detected in TwinCAT. In the tree structure the EtherCAT Terminal is displayed without process image, and the value in column "E-bus (mA)" does not change, compared to the preceding EtherCAT Terminal.

Number	Box Name	Ad...	Type	In Size	Out Size	E-Bus (mA)
1	Term 7 (EK1200)		EK1200			
2	Term 8 (EL2828)	1001	EL2828	1.0		1890
3	Term 9 (EL2828)	1002	EL2828	1.0		1780
4	Term 10 (EL9195)		EL9195			1780
5	Term 11 (EL2828)	1003	EL2828	1.0		1670
6	Term 12 (EL9011)		EL9011			

Fig. 19: Identifying a passive EtherCAT Terminal in TwinCAT.

The entry "Current consumption via E-Bus" in the technical data of an EtherCAT Terminal indicates whether a particular EtherCAT Terminal requires power from the terminal bus (E-bus).

The following diagram shows the permissible installation of a passive EtherCAT Terminal. The passive EtherCAT Terminal was not directly attached to the power supply unit.

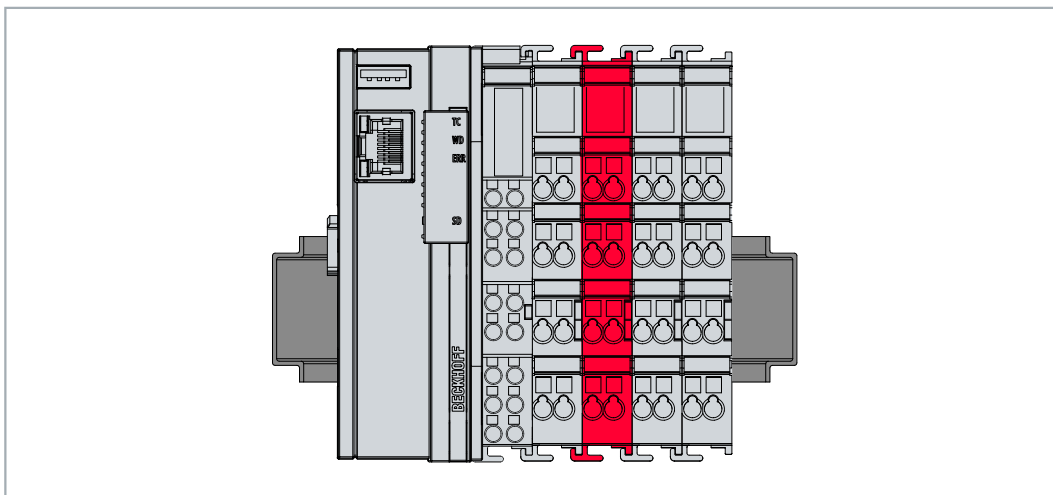


Fig. 20: Passive EtherCAT Terminals, permissible installation.

5.2 Power supply

NOTICE

Damage to the Embedded PCs

The Embedded PCs may be damaged during wiring. The cables for the power supply should only be connected in de-energized state.

The power supply terminals require an external voltage source, which provides 24 V DC (-15% / +20%).

The cabling of the Embedded PC in the control cabinet must be done in accordance with the standard EN 60204-1:2006 (PELV = Protective Extra Low Voltage):

- The "PE" and "0 V" conductors of the voltage source for a basic CPU module must be on the same potential (connected in the control cabinet).
- Standard EN 60204-1:2006, section 6.4.1:b stipulates that one side of the circuit, or one point of the energy source for this circuit must be connected to the protective earth conductor system.

Connections

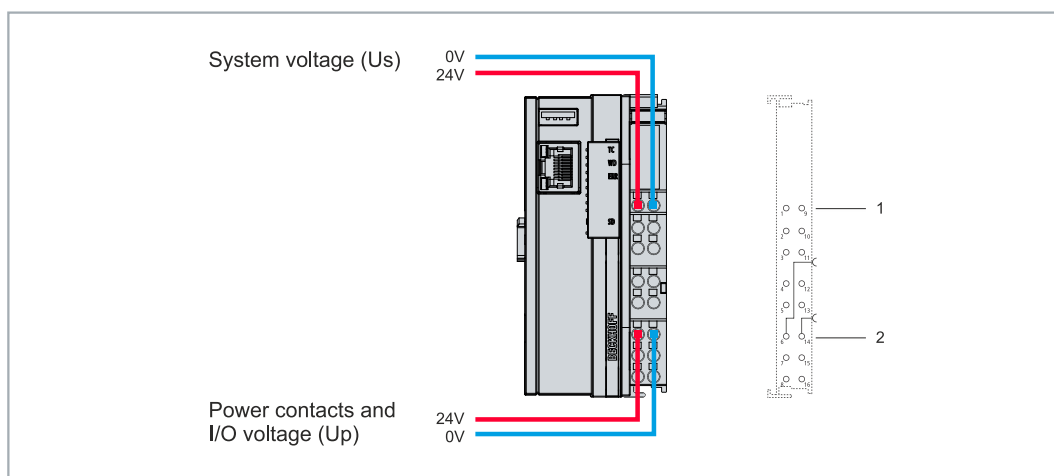


Fig. 21: Connections for system voltage (Us) and power contacts (Up).

Table 6: Legend for the connection example.

No.	Description
1	The upper spring-loaded terminals with the designations "+24 V Us" and "0 V Us" supply the basic CPU module and the terminal bus (data transmission via K-bus or E-bus) with voltage.
2	The upper spring-loaded terminals with the designations "+24 V Up" and "0 V Up" supply the multifunction I/Os, the Bus Terminals and EtherCAT terminals with voltage via the power contacts.

Fuse

- When dimensioning the fuse for the system voltage (Us), observe the maximum power consumption of the Embedded PC (see: [Technical data \[► 198\]](#))
- Protect the power contacts (Up) with a fuse with a max. rating of 10 A (slow-blow).

Interrupting / switching off the power supply

To switch off the Embedded PC, do not disconnect the ground (0 V), because otherwise current may continue to flow via the shielding, depending on the device, and damage the Embedded PC or peripheral devices.

Always disconnect the 24 V line. Devices connected to the Embedded PC, which have their own power supply (e.g. a Panel) must have the same potential for "PE" and "0 V" as the Embedded PC have (no potential difference).

5.2.1 Connect Embedded PC

The cables of an external voltage source are connected to spring-loaded terminals on the power supply terminal. Observe the required conductor cross-sections and strip lengths.

Table 7: Required wire cross-sections and strip lengths.

Conductor cross-section	e*: 0.08 ... 1.5 mm ² f*: 0.25 ... 1.5 mm ² a*: 0.14 ... 0.75 mm ²	e*: AWG 28 ... 16 f*: AWG 22 ... 16 a*: AWG 26 ... 19
Strip length	8 ... 9 mm	0.33 inch

*e: single-wire, solid wire; f: stranded wire; a: with wire end sleeve

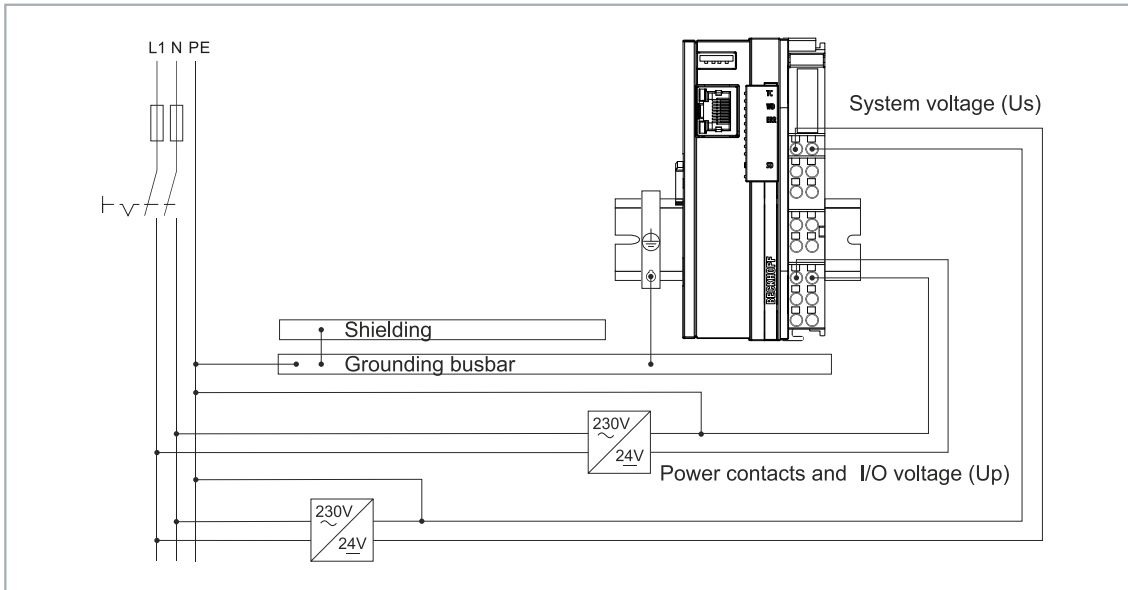
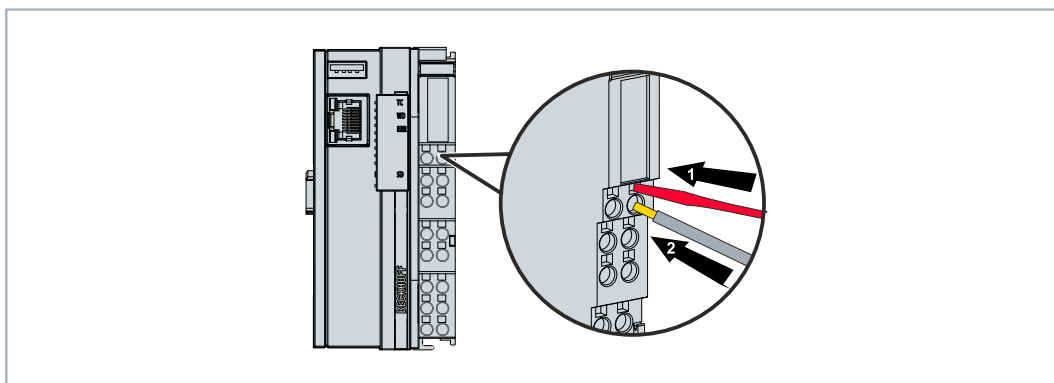


Fig. 22: Connection example with a CX7000.

Connect the Embedded PC as follows:

1. Open a spring-loaded terminal by slightly pushing with a screwdriver or a rod into the square opening above the terminal.



2. The wire can now be inserted into the round terminal opening without any force.
 3. The terminal closes automatically when the pressure is released, holding the wire safely and permanently.
- ⇒ You have successfully connected the voltage source to the power supply terminal when the two upper LEDs of the power supply terminal light up green.

The left LED (Us 24V) indicates the supply of the basic CPU module and terminal bus. The red LED (Up 24V) indicates the Bus Terminal supply via the power contacts.

5.2.2 UL requirements

The CX7050 Embedded PCs are UL-certified. The corresponding UL label can be found on the name plate.

The CX7050 Embedded PCs can thus be used in areas where special UL requirements have to be met. These requirements apply to the system voltage (U_s) and the power contacts (U_p). Applications without special UL requirements are not affected by UL regulations.

UL requirements:

- The Embedded PCs must not be connected to unlimited voltage sources.
- Embedded PCs may only be supplied from a 24 V DC voltage source. The voltage source must be insulated and protected with a fuse of maximum 4 A (corresponding to UL248).
- Or the power supply must originate from a voltage source that corresponds to NEC class 2. An NEC class 2 voltage source must not be connected in series or parallel with another NEC class 2 voltage source.

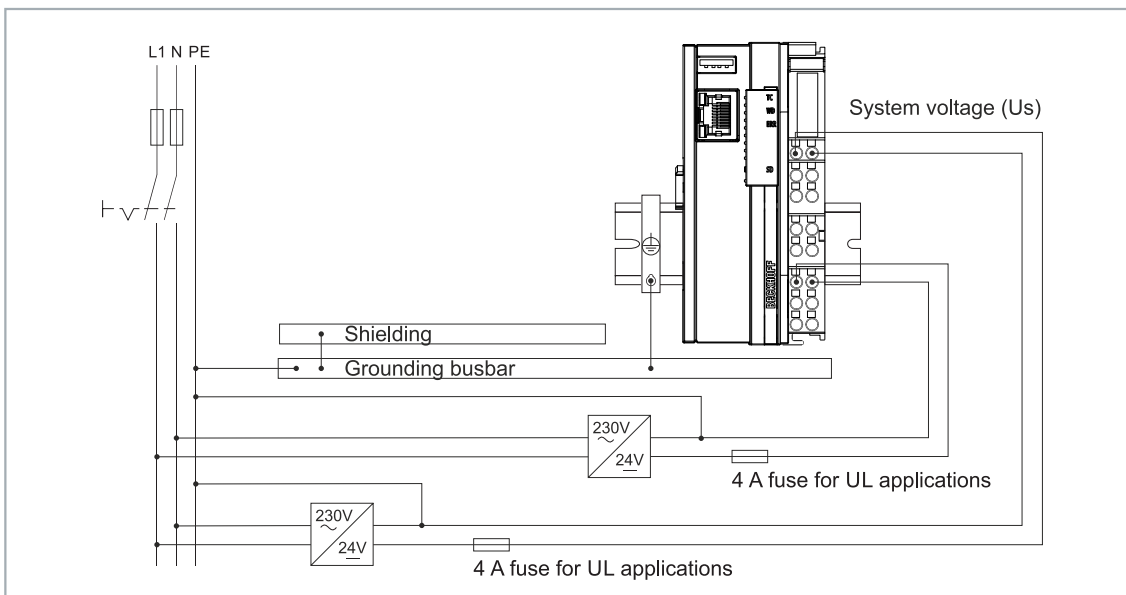


Fig. 23: Connection example for areas with special UL requirements.

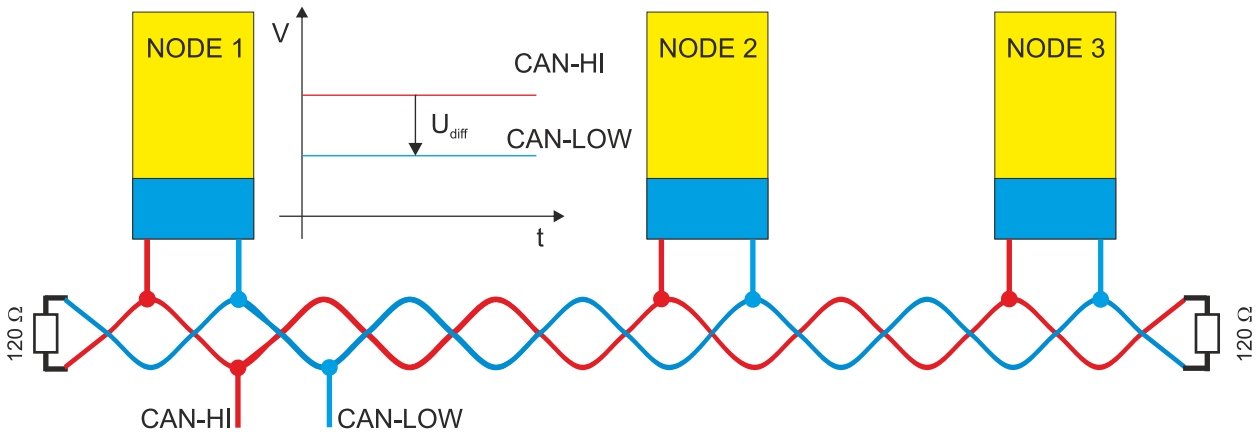
5.3 CANopen: Connection and wiring

NOTICE

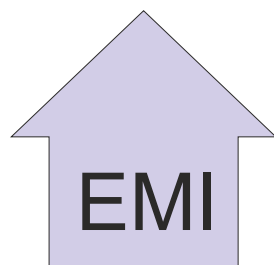
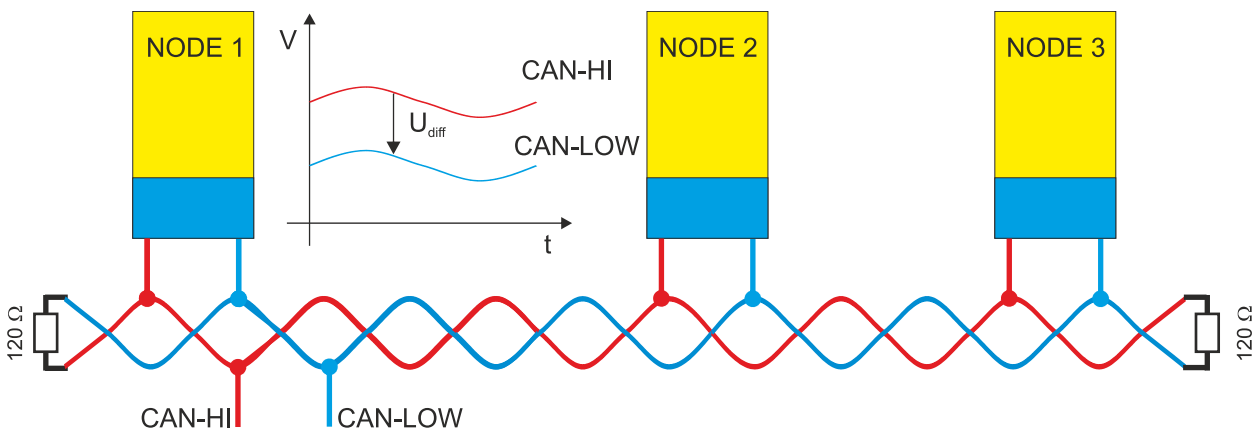
Improper wiring

On account of the lack of electrical isolation, the CAN driver can be destroyed or damaged due to incorrect cabling. Always carry out the cabling in the switched-off condition. First connect the power supply and then the CAN.

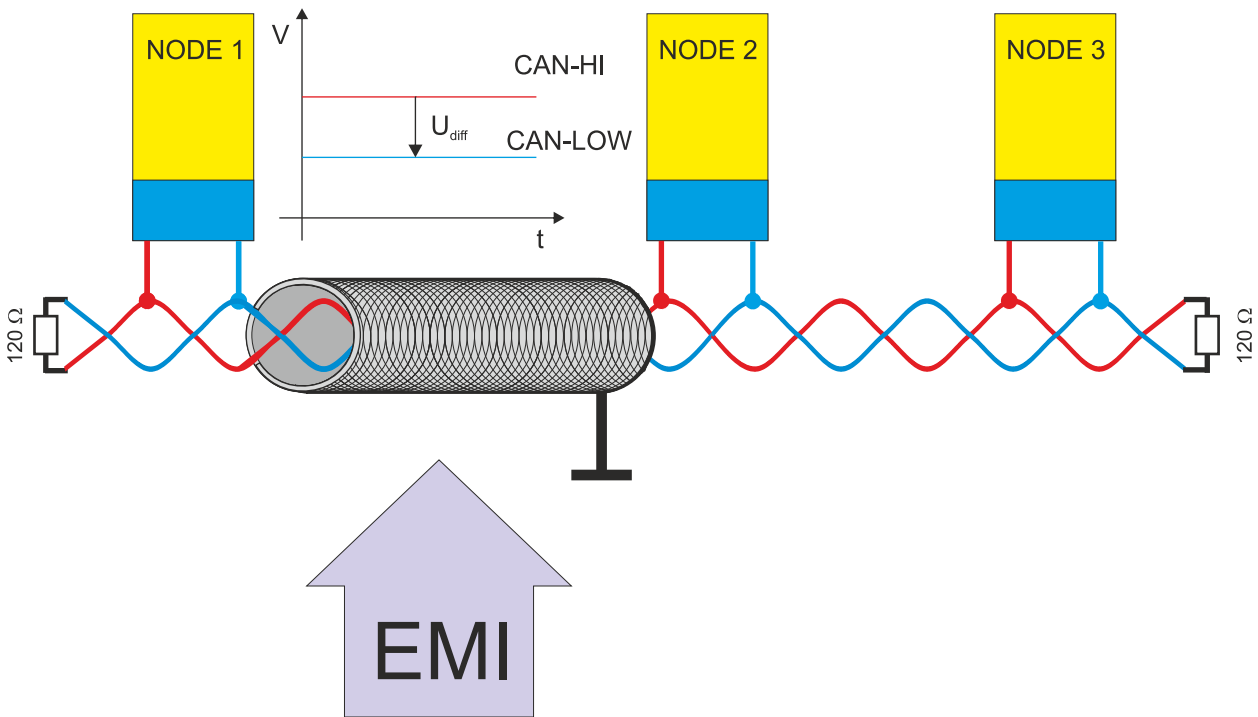
CAN is a 2-wire bus system, to which all devices are connected in parallel (i.e. using short drop lines). The bus must be terminated at each end with a 120 (or 121) ohm termination resistor to prevent reflections. This is also necessary even if the cable lengths are very short!



Since the CAN signals are represented as differential levels on the bus, the CAN line is comparatively insensitive to interference (EMI). Both lines are affected, so the interference hardly changes the differential level.



Additional shielding of the twisted wires can be used to further reduce EMI interference.



Bus length

The maximum length of a CAN bus is primarily limited by the signal propagation time. The multi-master bus access method (arbitration) requires that the signals are present quasi-simultaneously (before sampling within a bit time) at all nodes. Since the signal propagation time in the CAN connections (transceiver, optocoupler, CAN controller) are almost constant, the cable length must be adapted to the baud rate.

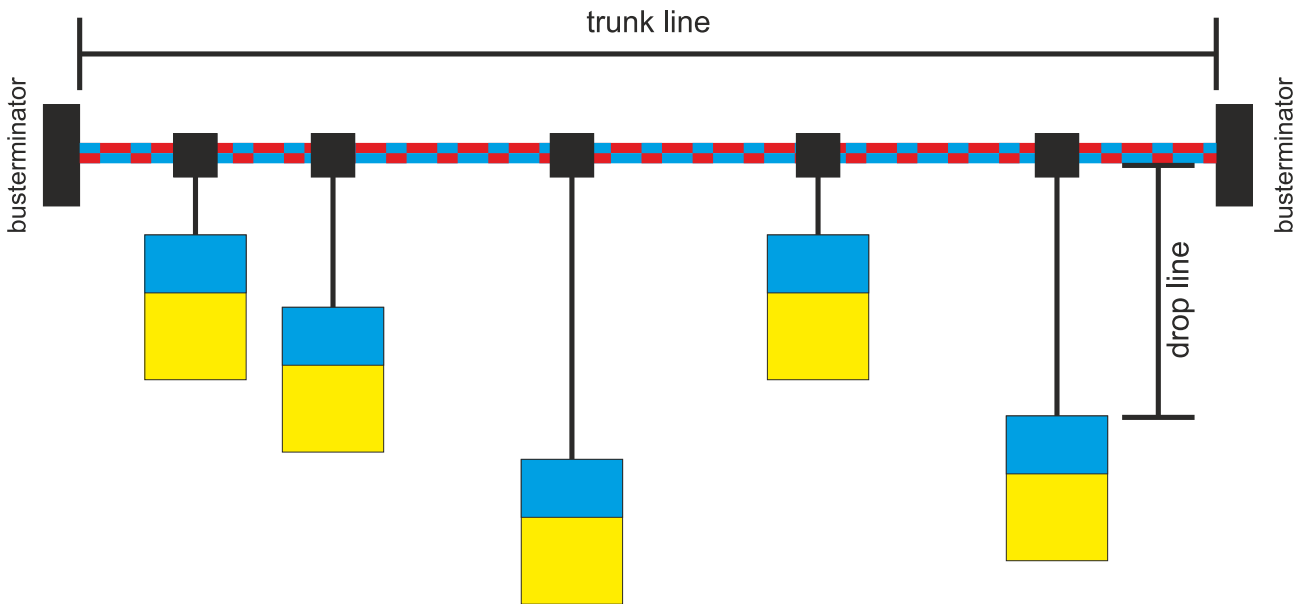
Baud rate	Bus length
1 Mbit/s	< 20 m*
500 kbit/s	< 100 m
250 kbit/s	< 250 m
125 kbit/s	< 500 m
50 kbit/s	< 1000 m
20 kbit/s	< 2500 m
10 kbit/s	< 5000 m

*) Often you can find the specification 40 m at 1 Mbit/s in the literature for CAN. However, this does not apply to networks with opto-decoupled CAN controllers. The worst case calculation for opto-couplers yields a figure 5 m at 1 Mbit/s - in practice, however, 20 m can be reached without difficulty.

It may be necessary to use repeaters for bus lengths greater than 1000 m.

Drop lines

Drop lines must always be avoided as far as possible, since they inevitably cause signal reflections. The reflections caused by drop lines are not however usually critical, provided they have decayed fully before the sampling time.



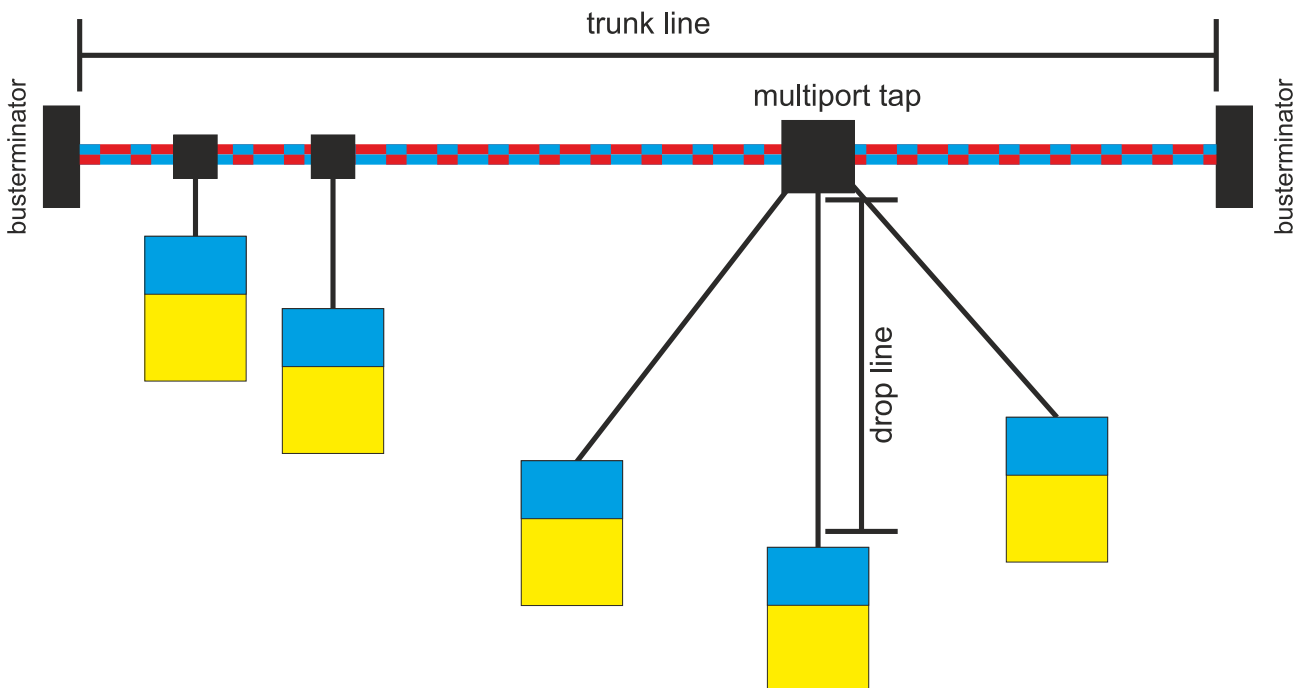
In the case of the bit timing settings selected in the bus couplers it can be assumed that this is the case, provided the following drop line lengths are not exceeded:

Baud rate	Drop line length	Total length of all drop lines
1 Mbit/s	< 1m	< 5 m
500 kbit/s	< 5 m	< 25 m
250 kbit/s	< 10 m	< 50 m
125 kbit/s	< 20m	< 100 m
50 kbit/s	< 50m	< 250 m

Drop lines must not have termination resistors.

Star Hub (Multiport Tap)

When using passive distributors ("Multiport Taps"), e.g. the BECKHOFF distribution box ZS5052-4500, shorter drop line lengths must be maintained.



The following table indicates the maximum drop line lengths and the maximum length of the trunk line (without the drop lines):

Baud rate	Drop line length with multiport topology	Trunk line length (without drop lines)
1 Mbit/s	< 0.3 m	< 25 m
500 kbit/s	< 1.2 m	< 66 m
250 kbit/s	< 2.4 m	< 120 m
125 kbit/s	< 4.8 m	< 310 m

5.3.1 D-sub connector (X003)

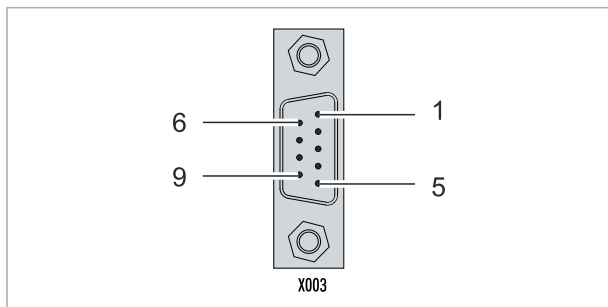


Fig. 24: CANopen interface X003.

The CAN bus line is connected via a 9-pin D-sub connector with the following pin assignment:

Pin	Connection
1	not used
2	CAN low (CAN-)
3	CAN Ground (internally connected to pin 6)
4	not used
5	Shield
6	CAN Ground (internally connected to pin 3)
7	CAN high (CAN+)
8	not used
9	not used

The DIN rail contact spring and the connector shield are connected together. An auxiliary voltage of up to 30 V_{DC} may be connected to pin 9, which is used by some CAN devices to supply the transceivers.

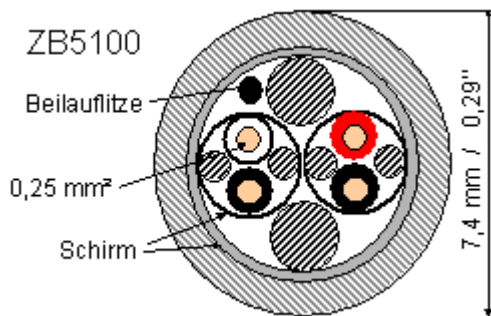
5.3.2 Cable and shielding

Shielded twisted-pair cables (2x2) with a characteristic impedance of between 108 and 132 ohm is recommended for the CAN wiring. If the CAN transceiver's reference potential (CAN ground) is not to be connected, the second pair of conductors can be omitted. (This is only recommended for networks of small physical size with a common power supply for all the devices).

ZB5100 CAN Cable

A high quality CAN cable with the following properties is included in BECKHOFF's range:

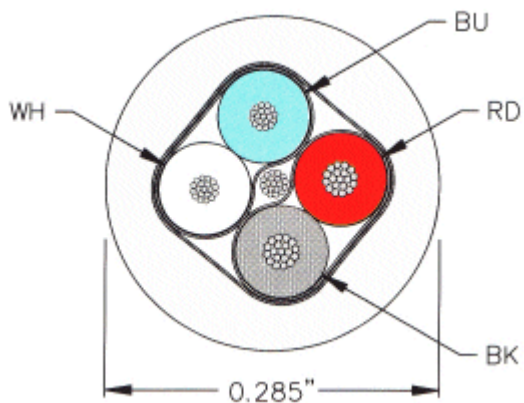
- 2 x 2 x 0.25 mm² (AWG 24) twisted pairs, cable colors: red/black + white/black
- double shielded
- shield braid with filler strand (can be attached directly to pin 3 of the 5-pin connection terminal),
- flexible (minimum bending radius 35 mm when bent once, 70 mm for repeated bending)
- characteristic impedance (60 MHz): 120 ohm
- conductor resistance < 80 ohm/km
- sheath: gray PVC, outer diameter 7.3 +/- 0.4 mm
- weight: 64 kg/km.
- printed with "Beckhoff ZB5100 CAN-BUS 2x2x0.25" and meter marking (length data every 20 cm)



ZB5200 CAN/DeviceNet Cable

The ZB5200 cable material corresponds to the DeviceNet specification, and is also suitable for CANopen systems. The ready-made ZK1052-xxxx-xxxx bus cables for the fieldbus box modules are made from this cable material. It has the following specification:

- 2 x 2 x 0.34 mm² (AWG 22) twisted pairs
- double shielded · shield braid with filler strand
- characteristic impedance (1 MHz): 126 ohm
- conductor resistance 54 ohm/km
- sheath: gray PVC, outer diameter 7.3 mm
- printed with "InterlinkBT DeviceNet Type 572" as well as UL and CSA ratings
- stranded wire colors correspond to the DeviceNet specification
- UL recognized AWM Type 2476 rating
- CSA AWM I/II A/B 80°C 300V FT1
- corresponds to the DeviceNet "Thin Cable" specification



Shielding

The shield is to be connected over the entire length of the bus cable, and only galvanically grounded at one point, in order to avoid ground loops.

The design of the shielding, in which HF interference is diverted through R/C elements to the mounting rail assumes that the rail is appropriately grounded and free from interference. If this is not the case, it is possible that HF interference will be transmitted from the mounting rail to the shield of the bus cable. In that case the shield should not be attached to the couplers - it should nevertheless still be fully connected through.

Cable colors

Recommended application of Beckhoff CAN cables:

Function	ZB5100 cable color	ZB5200 cable color
CAN Ground	black /(red)	black
CAN Low	black	blue
Shield	Filler strand	Filler strand
CAN high	white	white
not used	(red)	(red)

6 Multifunction I/Os

A total of four adjustable slots are available for configuring the operation modes. A slot is a certain number of inputs and outputs. For each slot a maximum of one module (DI, DIO, ENC, CNT or PWM) can be assigned, which in turn determines the operation mode for the respective slot. A module is therefore a function that these inputs and outputs can assume. The current module configuration is listed in TwinCAT under the CX7028 interface. Note that the CX7028 interface for controlling the multifunction I/Os has its own CPU and the CX7028 interface is not displayed or does not work under TwinCAT if the power supply (Up) is not connected.

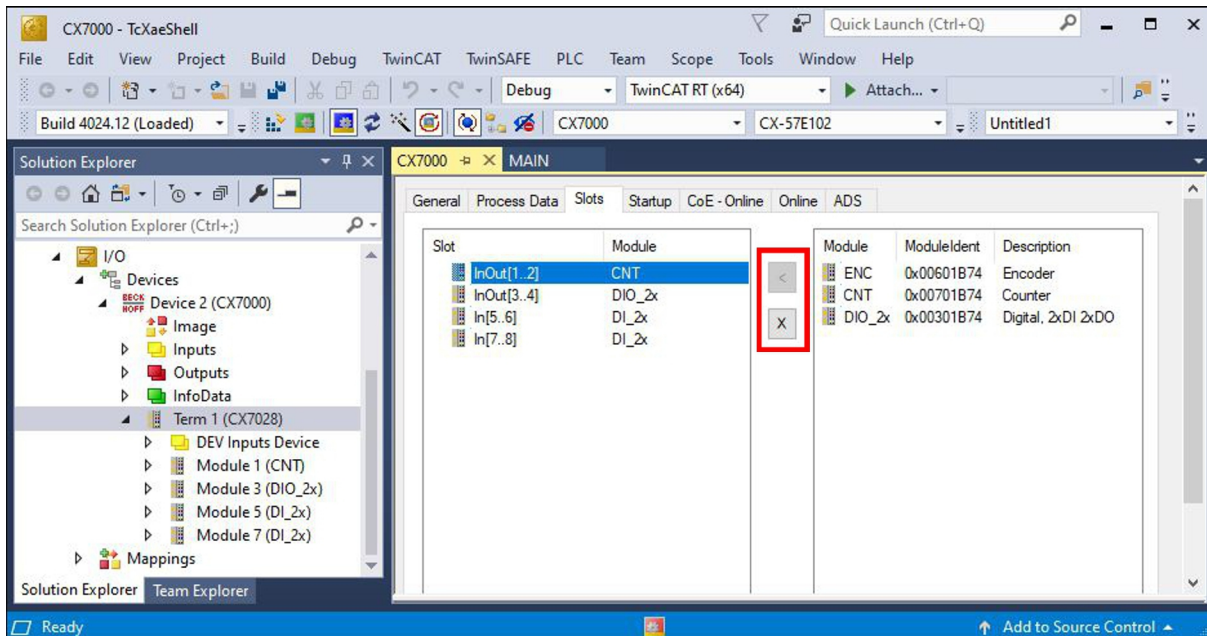


Fig. 25: CX7028 interface, slot and module configuration under TwinCAT.

Modules can be assigned to a specific slot with the button < or removed again with x. There is a choice of different modules depending on the slot used. The module used by each slot is listed in the following.

Cycle time for multifunction I/Os

Communication to the multifunction I/Os is monitored with a fixed watchdog of 100 ms. This means that the cycle time for the multifunction I/O must be faster than 100 ms.

Slot 1:

When using slot 1, inputs 1, 2 and (*3) as well as outputs 1 and 2 are configured.

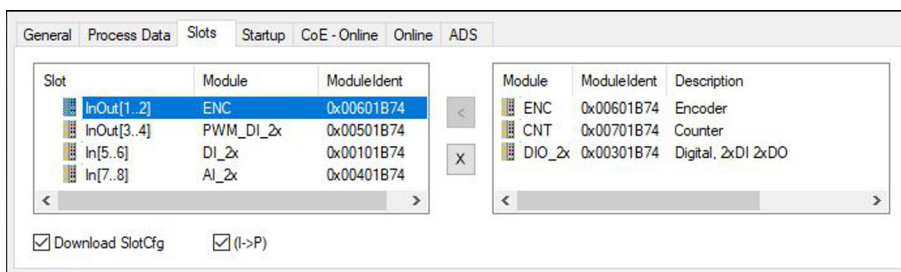


Fig. 26: Supported modules when using slot 1.

- ENC (incremental encoder mode). 2 x digital input for 250 kHz encoder signal, 2 x encoder digital output.
- CNT (counter mode). 1 x counter digital input 100 kHz, 1 x digital input as up/down counter 20 kHz, 2 x counter digital output.
- DIO_2x (digital inputs and outputs). 2 x digital input, 24 V DC, filter 3 ms, type 3, 2 x digital output, 24 V DC, 0.5 A, 1-wire technique.

*) Input 3 is only available in incremental encoder mode. If the level is high, the value of the incremental encoder can be latched or the counter reset.

Slot 2:

When using slot 2, inputs 3 and 4 as well as outputs 3 and 4 are configured.

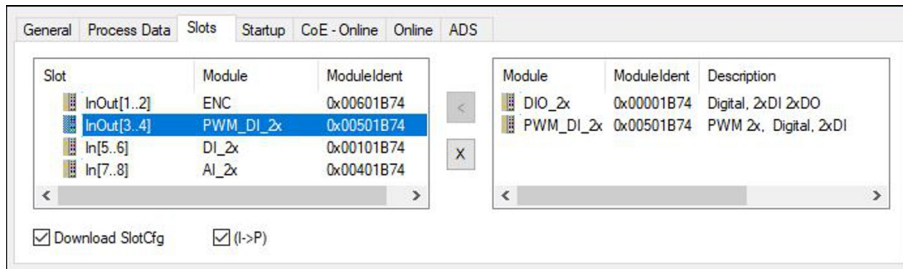


Fig. 27: Supported modules when using slot 2.

- DIO_2x (digital inputs and outputs). 2 x digital input, 24 V DC, filter 3 ms, type 3, 2 x digital output, 24 V DC, 0.5 A, 1-wire technique.
- PWM_DI_2x (PWM signal mode). 2 x digital input, 24 V DC, filter 3 ms, 2 x digital output configured for PWM signal.

Slot 3:

When using slot 3, inputs 5 and 6 are configured.

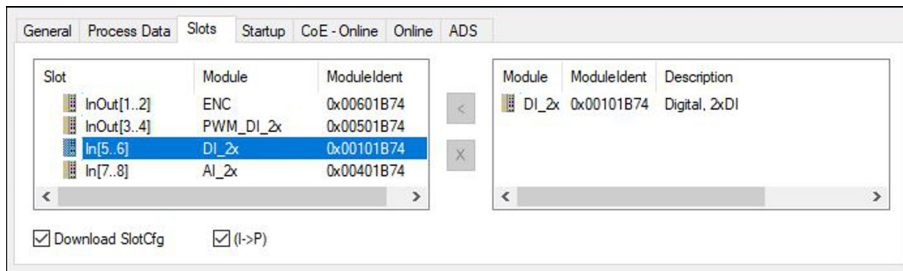


Fig. 28: Supported modules when using slot 3.

Slot 3 contains only one module and therefore cannot be configured differently. The module supports 2 x digital input, 24 V DC, filter 3 ms, type 3.

Slot 4:

When using slot 4, inputs 7 and 8 are configured.

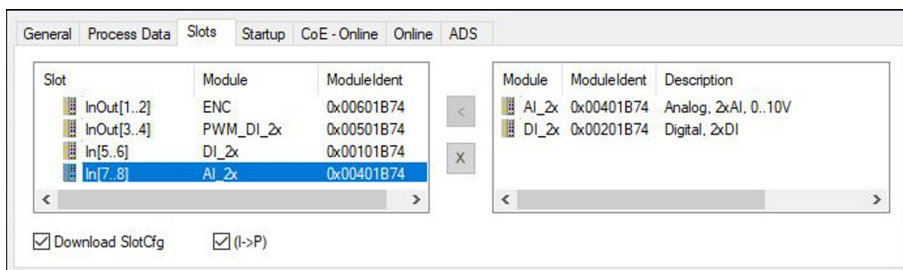


Fig. 29: Supported modules when using slot 4.

- AI_2x (analog signal mode). 2 x digital input configured as analog input 0 to 10 V, 12 bits
- DI_2x (digital input). 2 x digital input, 24 V DC, filter 3 ms, type 3

6.1 Digital inputs

The digital inputs acquire binary control signals from the process level. Typically, these are mechanical contacts such as normally closed contacts or normally open contacts, electronic sensors such as inductive proximity switches, optical sensors or other methods in order to generate a low/high signal in the sense of control technology. Thanks to integrated multi-function I/Os, the CX70xx has a total of 8 digital inputs, 24 V DC, filter 3 ms, type 3.

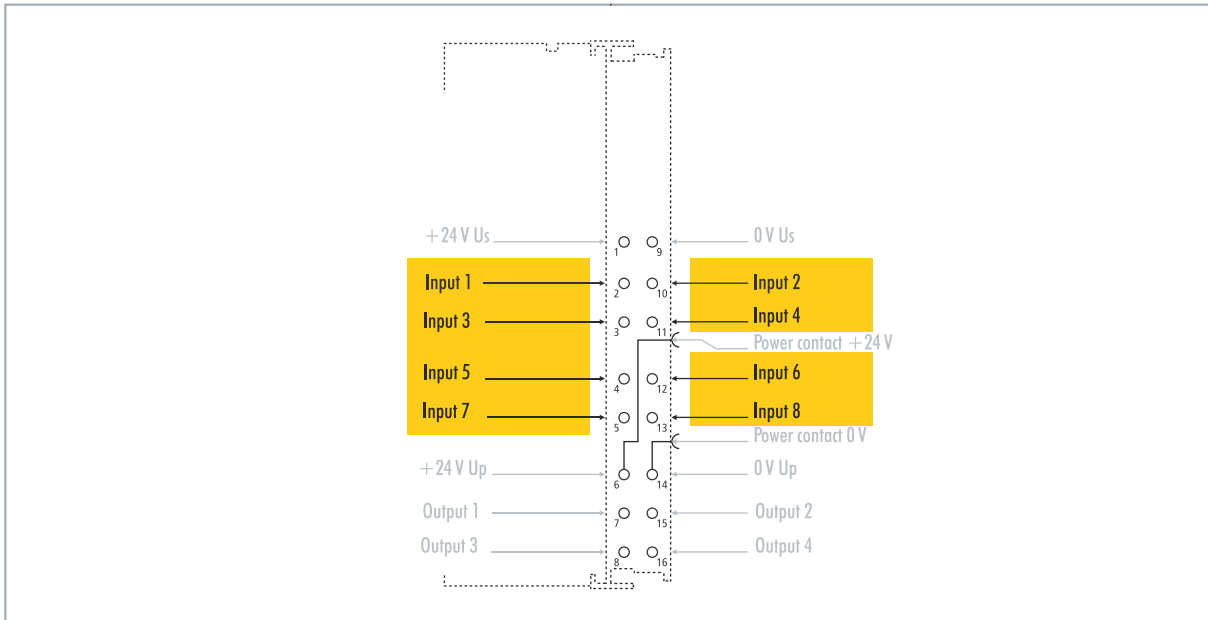


Fig. 30: Configurable digital inputs.

The digital inputs have a 3 ms input filter. The signal status of each individual input is displayed by an LED. For digital inputs 3, 4, 5 and 6, additional filter settings can be made in the appropriate CoE objects and, for example, the resolution and filter time can be set.

Table 8: Technical data, multi-function I/Os as digital inputs.

Technical data	CX7050
Connection technology	1-wire
Number of inputs	8
Nominal voltage	24 V DC (-15 %/+20 %)
Specification	EN 61131-2, type 3
Signal voltage "0"	-3...+5 V
Signal voltage "1"	11...30 V
Input filter	Configurable, default: 3 ms, min.: 10 μ s
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

*e: single-wire, solid wire; f: stranded wire; a: with ferrule

6.2 Digital outputs

NOTICE

Feedback at the 24 V outputs

A voltage of 24 V at the outputs can destroy the device if the power supply (Up) is not connected (feedback). Connect the power supply (Up) so that 24 V can be applied to the outputs.

The digital outputs forward binary 24 V DC control signals, electrically isolated, to actuators at the process level. The high level of the positive switching logic corresponds to the supply voltage.

Outputs 3 and 4 have a PWM output stage. If the two digital outputs are used as normal digital outputs, the internal wiring will cause a leakage current of less than 100 μ A, which will cause a voltage of about 5 V. If you want to reach nearly 0 V at the low level of the output, you have to connect a 47 k Ω resistance to ground.

Another possibility is to operate the two outputs in PWM mode and to write the variable `PWM output` of the PWM signal for FALSE with 0x0000 and for TRUE with 0xFFFF. This activates the PWM output stage, which does not generate any leakage current.

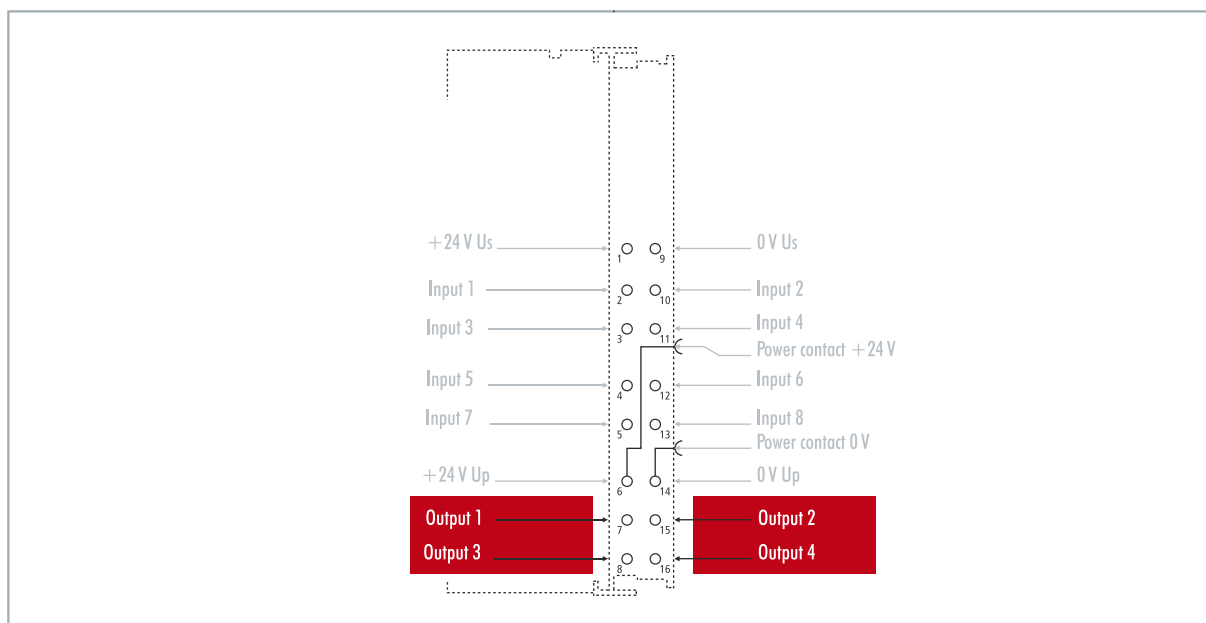


Fig. 31: Configurable digital outputs.

The CX7050 contains a total of four outputs, which indicate their signal state by means of light emitting diodes. The outputs can be used to switch standard actuators such as contactors and valves.

Table 9: Technical data, multi-function I/Os as digital outputs.

Technical data	CX7050
Connection technology	1-wire
Number of outputs	4
Nominal voltage	24 V DC (-15 %/+20 %)
Load type	ohmic, inductive, lamp load
Max. output current	24 V/0.5 A (short-circuit proof)
Changeover times	T_{ON} : 20 μ s typ., T_{OFF} : 10 μ s typ.
Short circuit current	< 2 A typ.
Max. breaking energy (ind.)	< 150 mJ/channel
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²

Technical data	CX7050
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

*e: single-wire, solid wire; f: stranded wire; a: with ferrule

6.3 Counter mode

The CX7050 Embedded PC can be configured as an up/down counter that enables the counting of a pulse. The embedded PC is suitable for fast counting tasks with a cut-off frequency of up to 100 kHz, whereby the CX7050 can be operated in 1-counter mode.

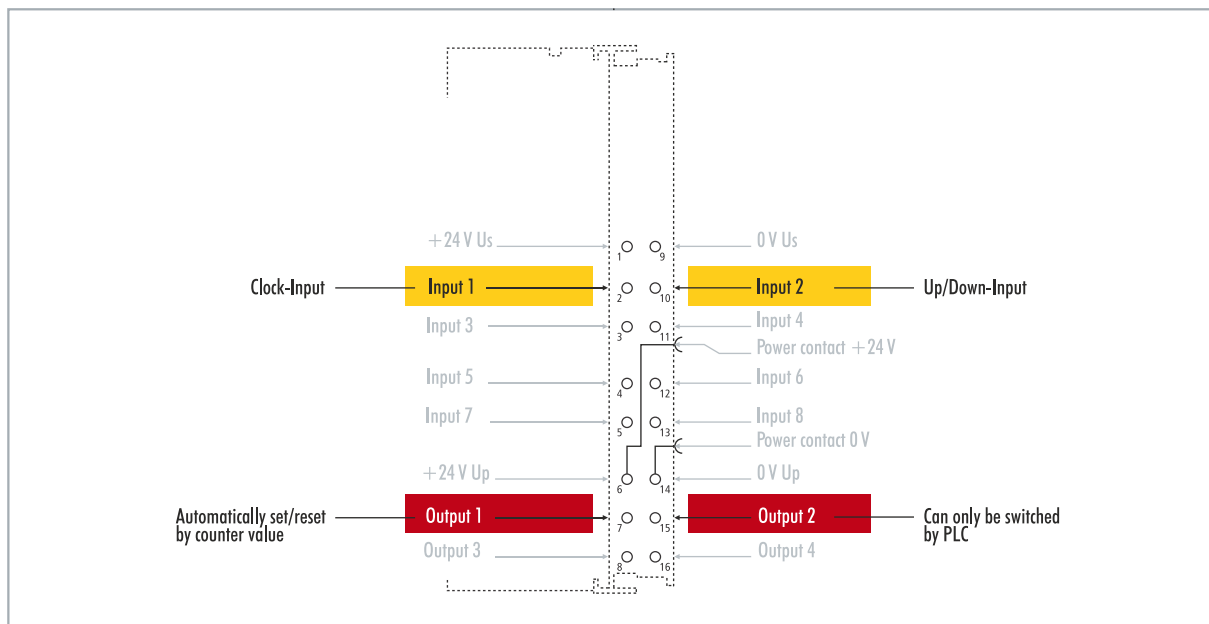


Fig. 32: Configurable inputs and outputs in counter mode.

The CX7050 supports three operation modes in counter mode:

- Up/down counter
- Up counter
- Down counter

In addition, output 1 can be switched depending on the counter value. Output 2 can be switched from the PLC. This allows fast control signals for field devices to be used and switched.

The operation modes are set in TwinCAT via CoE objects.

Up/down counter

In the up/down counter operation mode, the pulse to be counted is detected by digital input 1. The counting direction is specified by digital input 2.

If there is a high level at input 1 and at the same time at input 2, the counter counts upwards. If there is a high level at input 1 and a low level at input 2, the counter counts downwards.

Up counter

In this operation mode, the signal is detected at digital input 1.

Down counter

In this operation mode, the signal is detected at digital input 1.

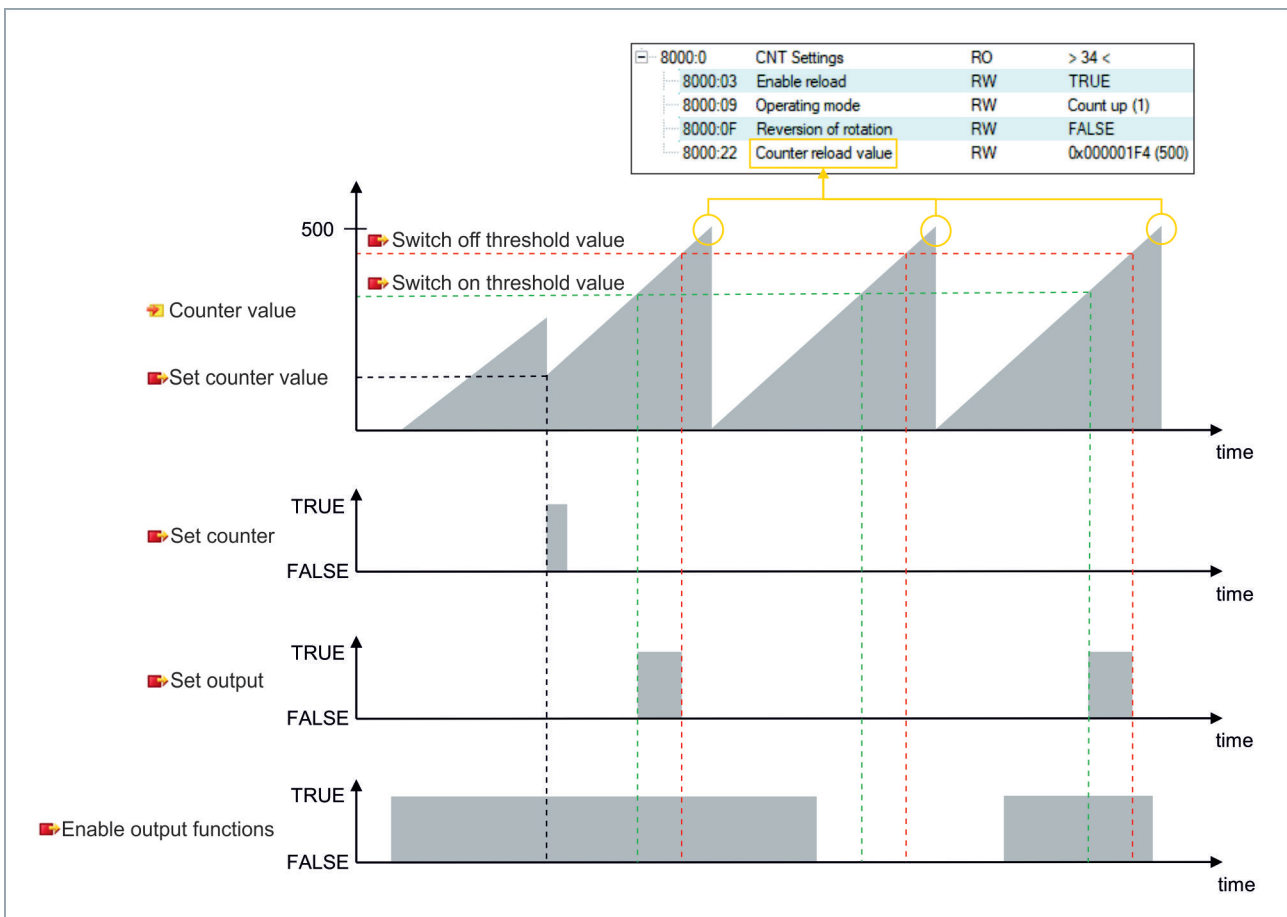


Table 10: Technical data, multi-function I/Os in counter mode.

Technical data	CX7050
Number of counters	1 x up/down counter, 1 x up or down counter
Nominal voltage	24 V DC (-15 %/+20 %)
Specification	EN 61131-2, type 3
Signal voltage "0"	-3...+5 V
Signal voltage "1"	11...30 V
Cut-off frequency	Up/down counter: 20 kHz ¹⁾ , counting in one direction only: 100 kHz
Counter depth	32-bit
Max. output current	24 V/0.5 A (short-circuit proof)
Special features	Set counter, switch outputs, reset counter
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

¹⁾ The up/down counter can also count up to 100 kHz, only with a direction reversal the counting frequency must be ≤ 20 kHz, otherwise pulses will be lost.

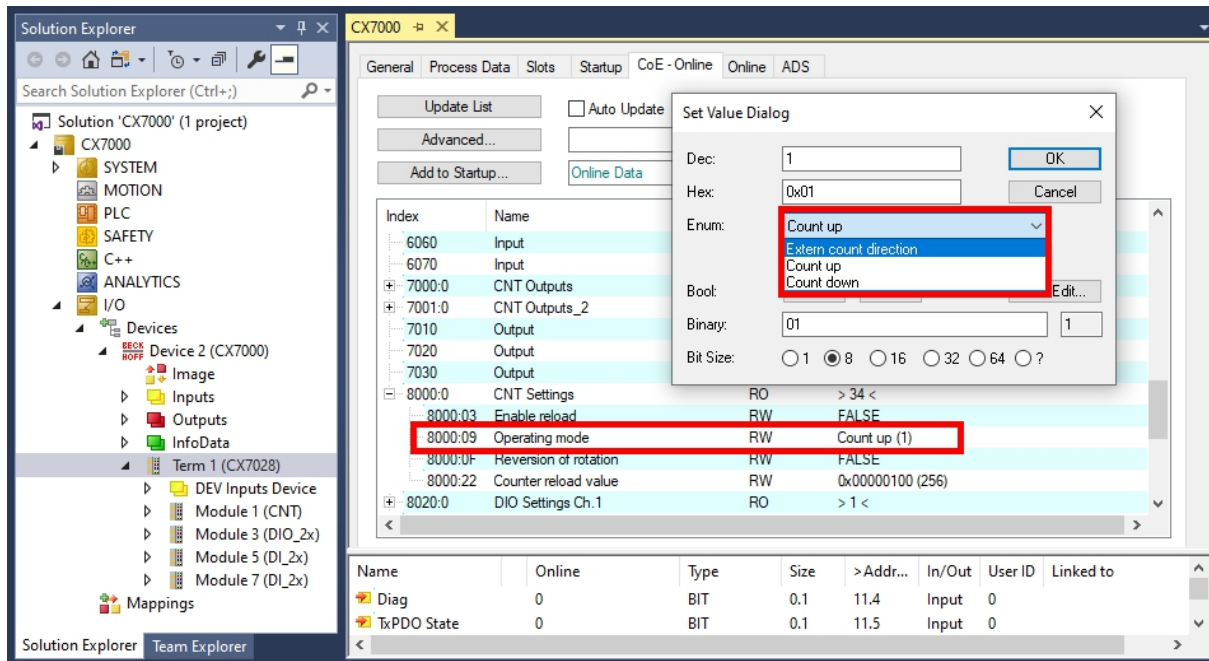
*e: single-wire, solid wire; f: stranded wire; a: with ferrule

6.3.1 Select operation mode

The CX7050 supports three operation modes in counter mode: The operation mode is set in TwinCAT via CoE objects. You can choose between the three operating modes up/down counter, up counter and down counter.

Proceed as follows:

1. Click the **CX7028 device** on the left in the structure tree.
2. Click the **CoE-Online** tab.



3. Double-click the CoE object **8000:09 Operating mode**.
 4. Under the **Enum** option, select the required operation mode.
- ⇒ The operation mode is applied. Note that you can only use one operation mode at a time with the CX7050 and mode mixing is not possible.

6.3.2 Switching outputs

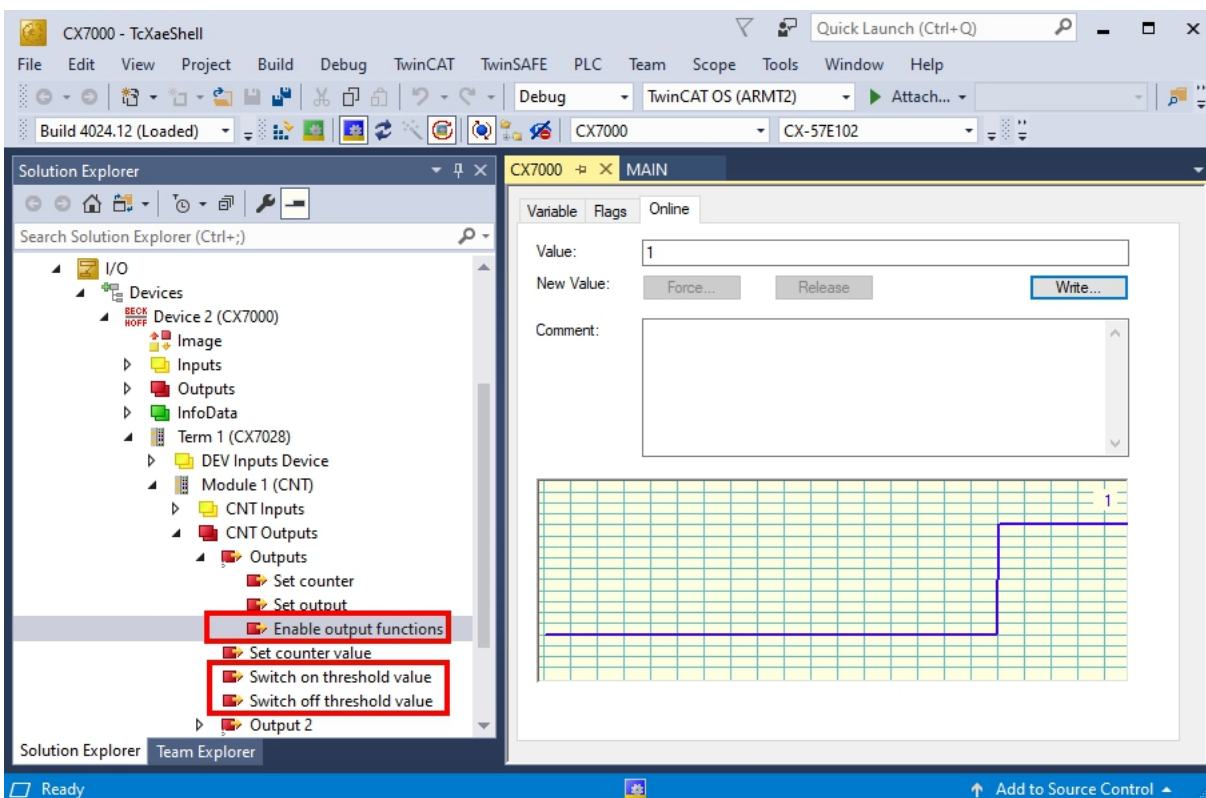
With the CX7050, it is possible to switch output 1 automatically as soon as a certain counter value is reached. This enables fast processing without the PLC. A second output, output 2, can be switched via the PLC irrespective of the counter value.

Output 1 is switched or switched off respectively by the variables **Switch on threshold value** and **Switch off threshold value**:

- If the value set under **Switch on threshold value** is reached, the output is switched.
- If the value set under **Switch off threshold value** is reached, the output is switched off.

When counting downwards, the corresponding switching instruction is executed in reverse. If the value falls below the value set in **Switch on threshold value**, output 1 is switched off.

Proceed as follows:



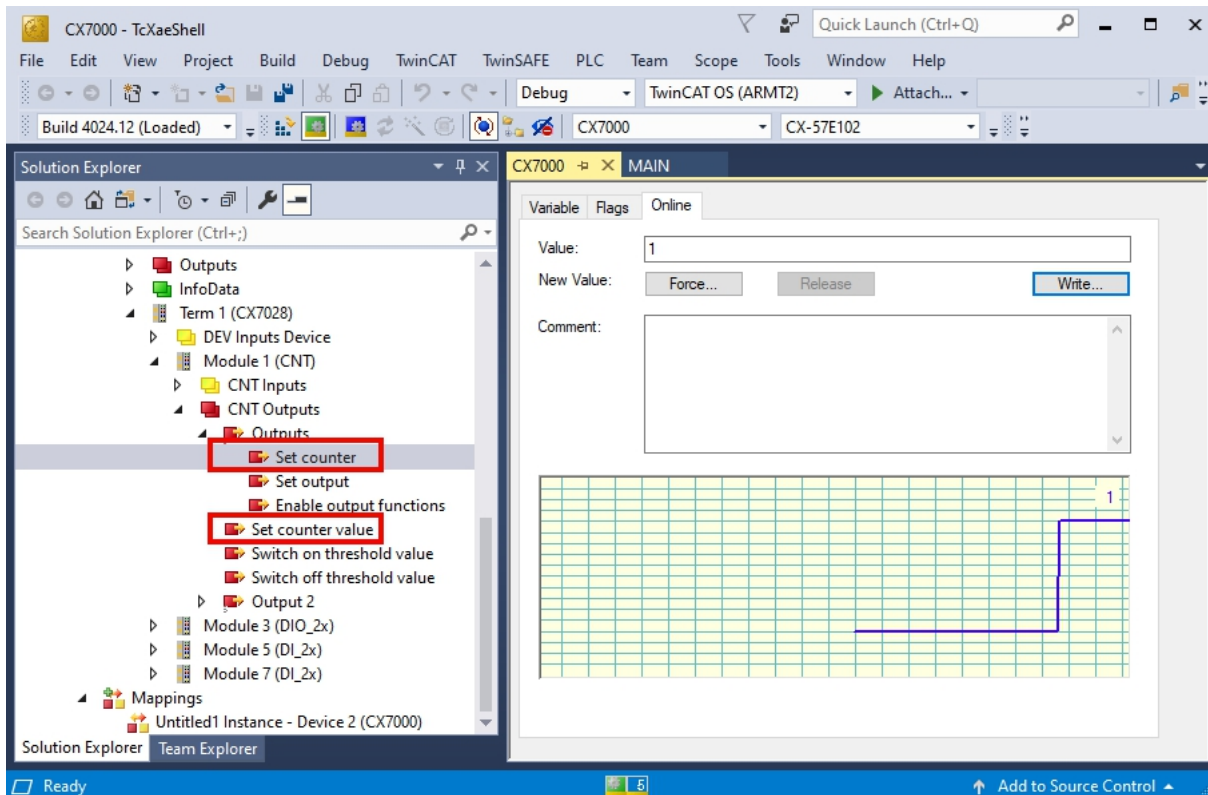
1. Use the variable **Switch on threshold value** to specify a counter value at which the output should be switched.
 2. Use the variable **Switch off threshold value** to specify a counter value at which the output should be switched off.
 3. Then set the variable **Enable output functions** to **True** so that the settings are applied.
- ⇒ Only when the variable **Enable output functions** is set to **True** the function is enabled and the output is switched.

If the parameterized counter value from **Switch on/off threshold** is reached or exceeded, but the variable **Enable output functions** is not set, the switching order is not executed. The output is switched as soon as **Enable output functions** is set. Likewise, a subsequently activated counter value **Switch on/off threshold** affects the output immediately when the switching condition is fulfilled.

6.3.3 Set counter value

This step shows you how to set the counter value to a specific value. The variable **Set counter value** is used to specify a value and the variable **Set counter** is used to set the counter value. Both variables can be controlled from the PLC.

Proceed as follows:



1. Use the variable **Set counter value** to specify a value to set as a counter value.
 2. Then set the variable **Set counter** to **True** to apply the settings.
- ⇒ Only when the variable **Set counter** is set to **True**, the value set under **Set counter value** is applied for the counter value.

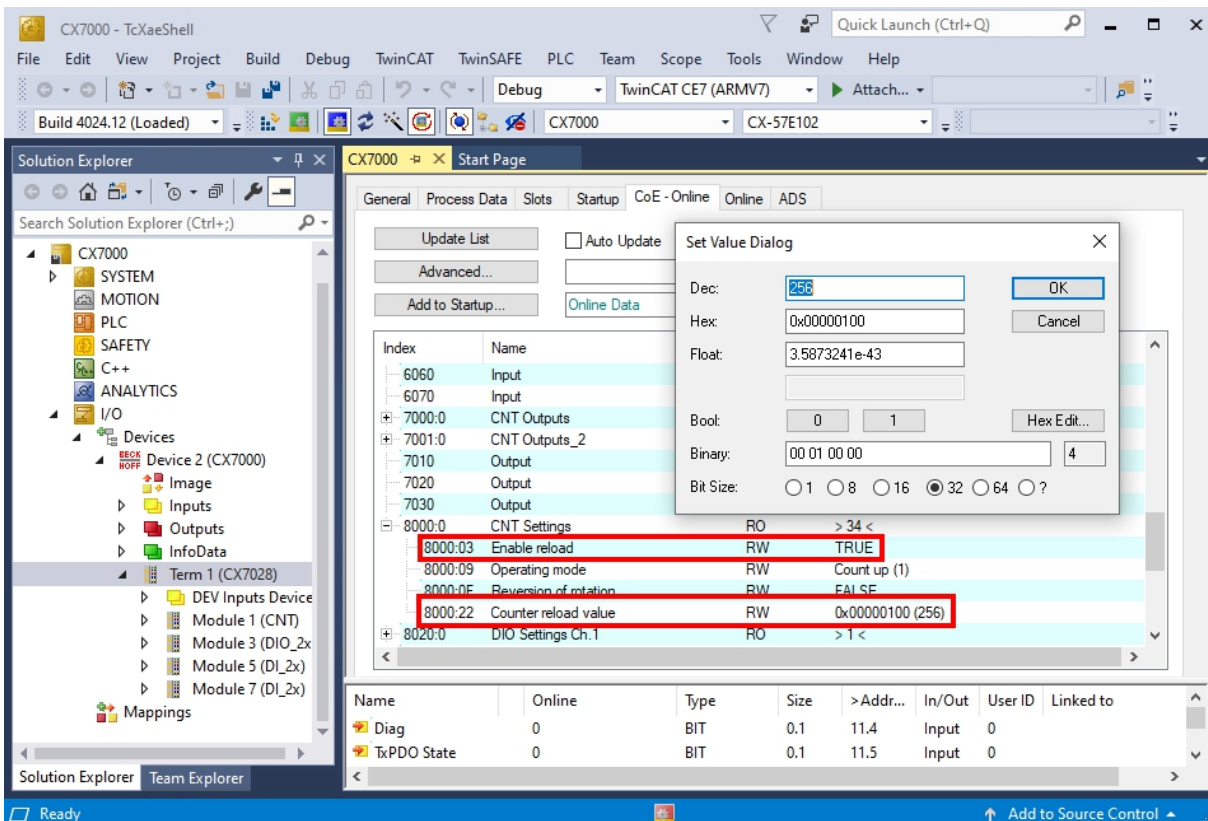
6.3.4 Setting the limit value for counters

This step shows you how to set a limit value in TwinCAT from which the counter value is automatically reset to zero. When counting upwards, the counter value is reset to zero when the limit value is reached. When counting downwards, the counter value is reset to the set limit value when zero is reached.

The counter value is a UDINT variable. The counter counts only in the positive range from 0 to 0xFFFF_FFFF (4294967295). If the value falls below zero, the counter is set to the maximum positive value. If it exceeds 4294967295, the counter is set to zero. The two variables **Counter underflow** or **Counter overflow** respectively indicate the overflow and are reset either on reaching 0x4000 in the positive direction or on reaching 0xFFFFC000 in a negative direction or if the corresponding other overflow has been reached.

Proceed as follows:

1. Click the **CX7028 device** on the left in the structure tree.
2. Click the **CoE-Online** tab.



3. Double-click the CoE object **8000:22 Counter reload value** and set the limit value.
 4. Then double-click the CoE object **8000:03 Enable reload** and set the value to **True**.
- ⇒ Only when the CoE object **8000:03 Enable reload** is set to **True** are the function and the defined limit value active.

6.4 Incremental encoder mode

In incremental encoder mode, the CX7050 can be configured as an interface for direct connection of 24 V incremental encoders. A quadruple evaluation is used and both high level and low level are detected at input 1 and input 2.

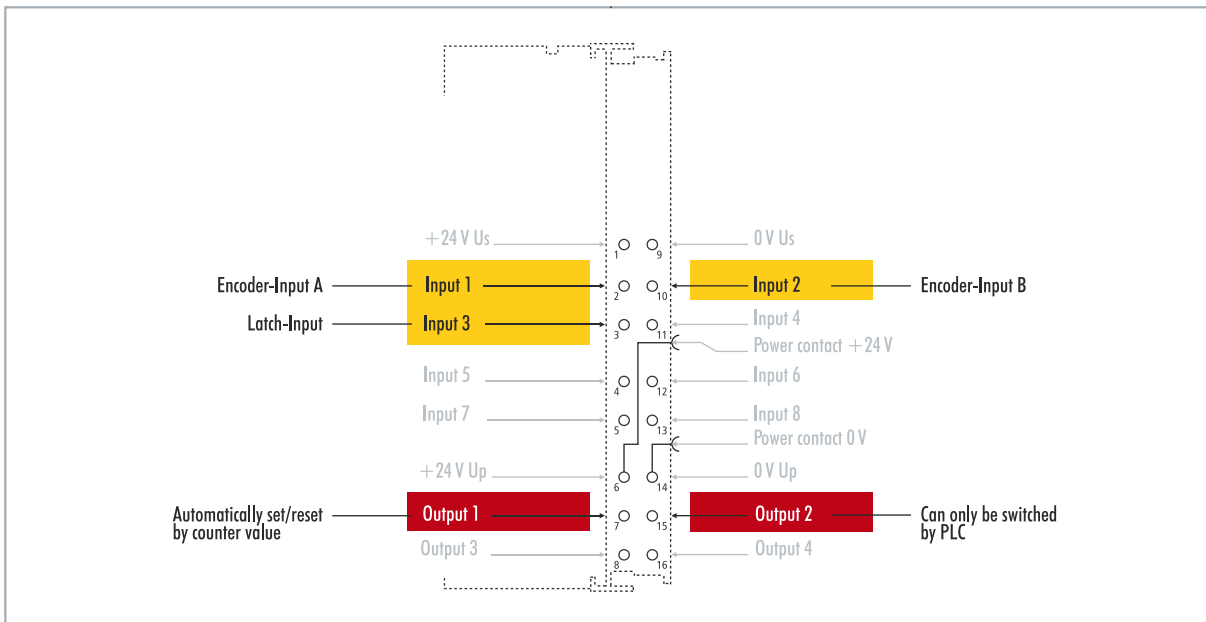


Fig. 33: Configurable inputs and outputs in incremental encoder mode.

The range of functions in encoder mode corresponds to the range of functions in counter mode. In addition, the counter value at input 3 can be latched, i.e. the value is entered in the process data on a high level at input 3. Alternatively, the counter can be reset on a high level at input 3.

In addition, output 1 can be switched depending on the counter value. Output 2 can be switched from the PLC. This allows fast control signals for field devices to be used and switched.

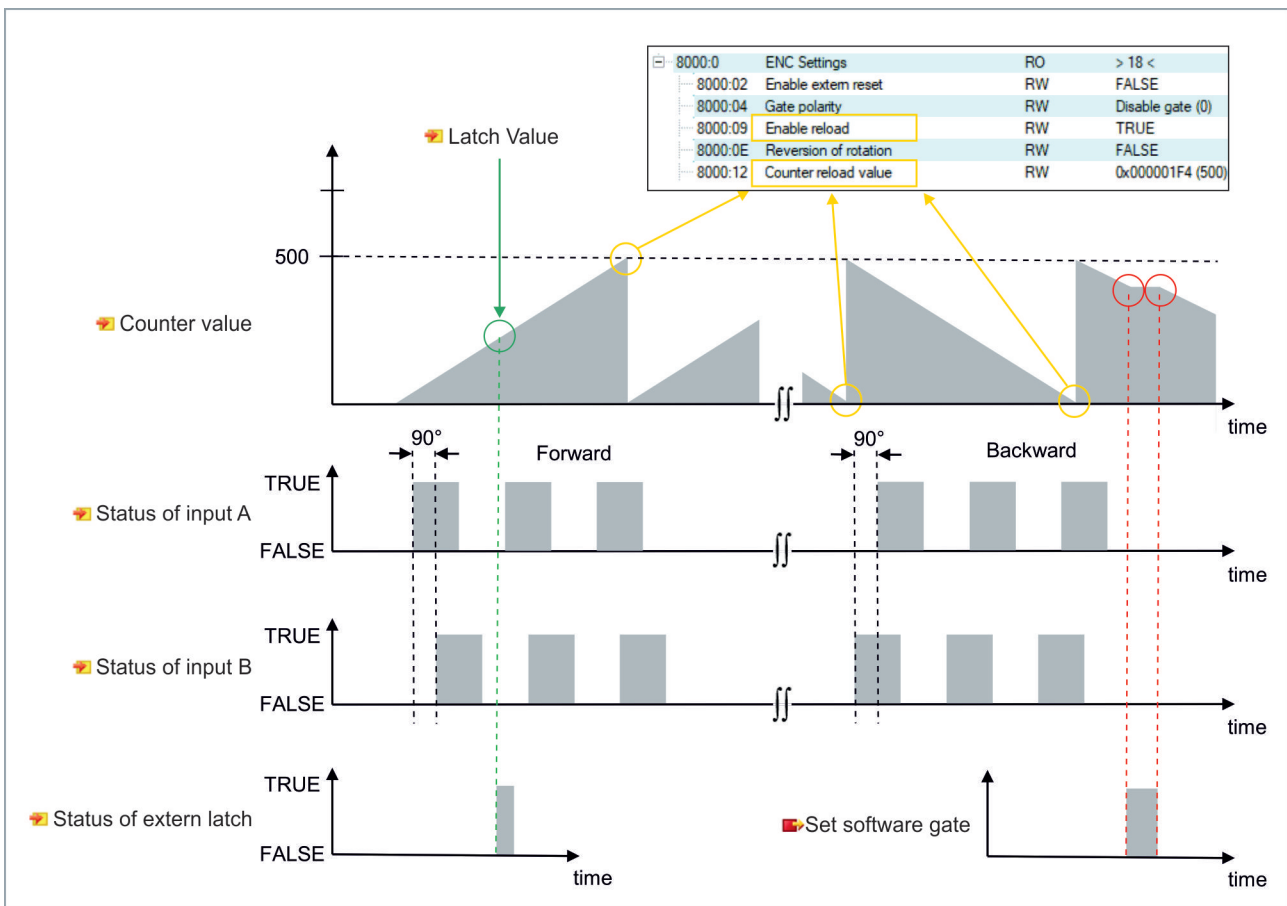


Table 11: Technical data, multi-function I/Os in encoder mode.

Technical data	CX7050
Technology	Incremental encoder interface
Nominal voltage	24 V DC (-15 %/+20 %)
Specification	EN 61131-2, type 3
Encoder connection	1 x A, B: 24 V, single-ended
Additional inputs	Latch input, 24 V DC
Cut-off frequency	250,000 increments/s (with 4-fold evaluation), corresponds to 62.5 kHz
Counter depth	32-bit
Quadrature decoder	4-fold evaluation
Max. output current	24 V/0.5 A (short-circuit proof)
Special features	Latch function, software gate, set counter, switch outputs, reset counters
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

*e: single-wire, solid wire; f: stranded wire; a: with ferrule

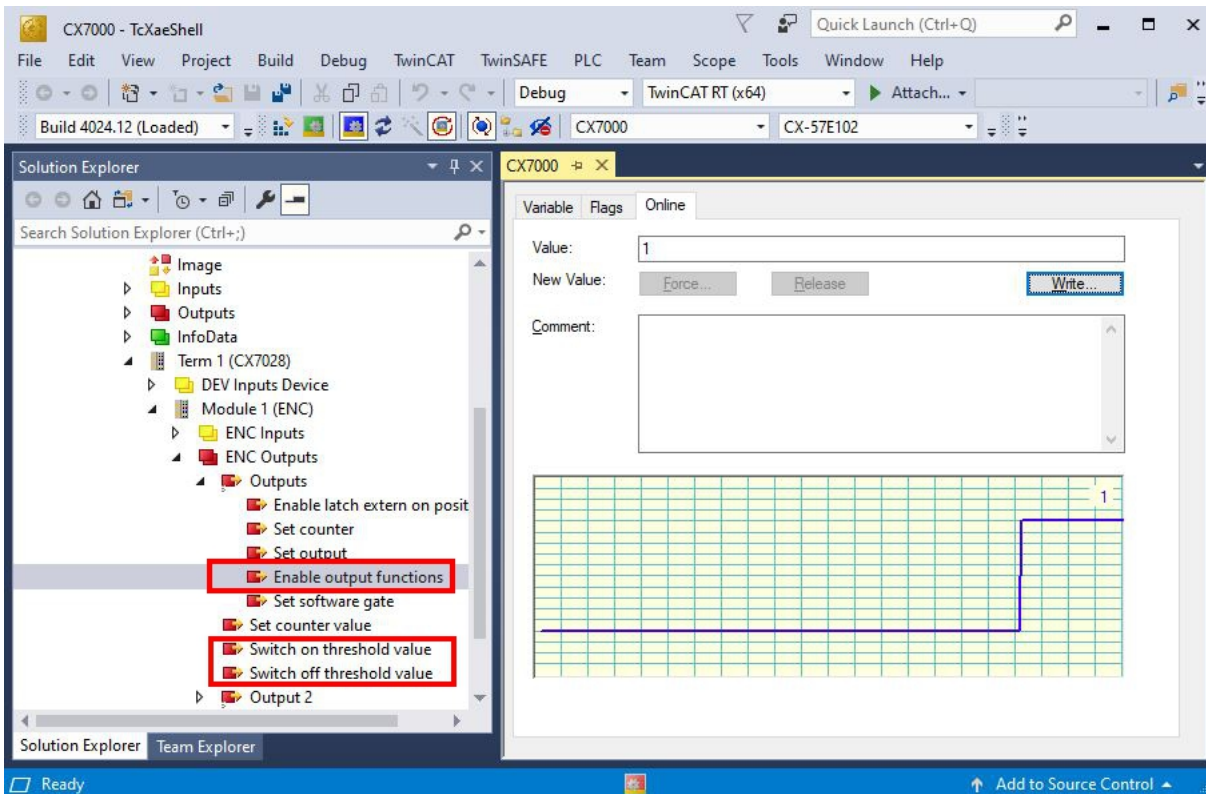
6.4.1 Switching outputs

With the CX7050, it is possible to switch output 1 automatically as soon as a certain counter value is reached. This enables fast processing without the PLC. A second output, output 2, can be switched via the PLC irrespective of the counter value.

Output 1 is switched or switched off respectively by the variables **Switch on threshold value** and **Switch off threshold value**:

- If the value set under **Switch on threshold value** is reached, the output is switched.
- If the value set under **Switch off threshold value** is reached, the output is switched off.

Proceed as follows:



1. Use the variable **Switch on threshold value** to specify a counter value at which the output should be switched.
 2. Use the variable **Switch off threshold value** to specify a counter value at which the output should be switched off.
 3. Then set the variable **Enable output functions** so that the settings are applied.
- ⇒ Only when the variable **Enable output functions** is set to **True** is the function enabled and the settings applied.

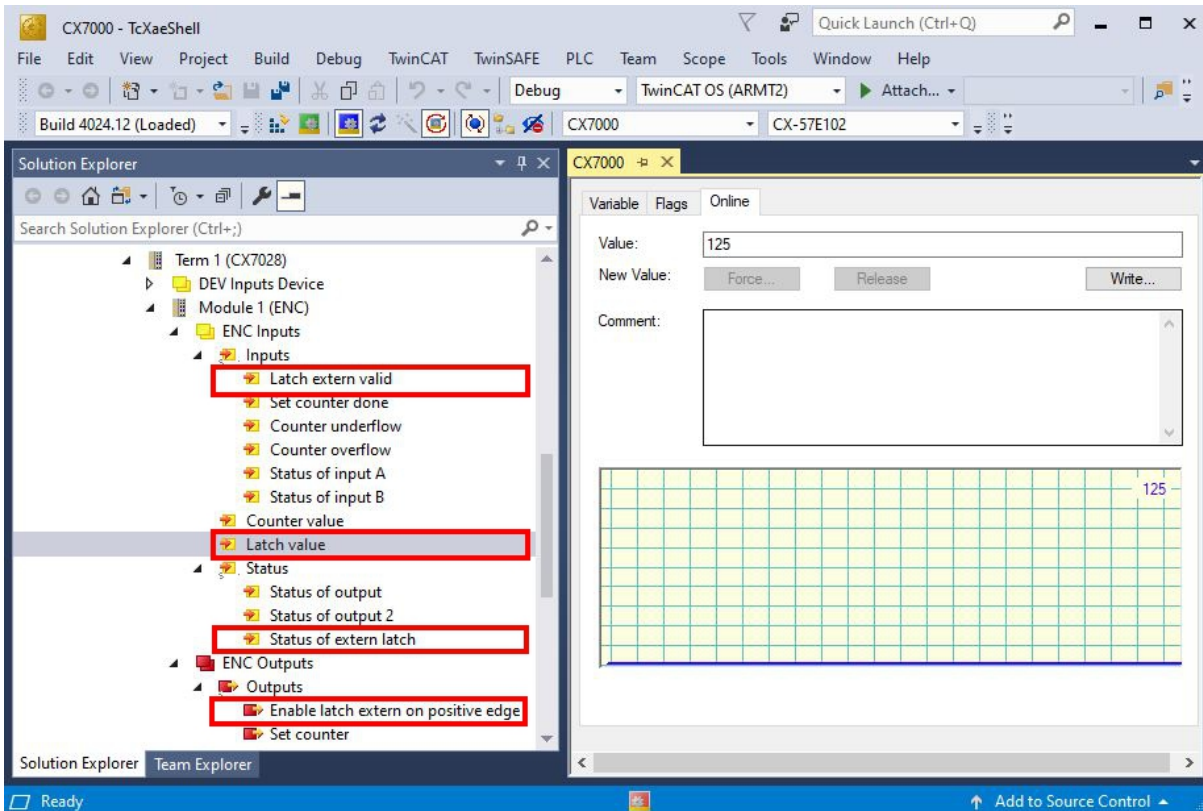
If the parameterized counter value from **Switch on/off threshold** is reached or exceeded, but the variable **Enable output functions** is not set, the switching order is not executed. The output is switched as soon as **Enable output functions** is set. Likewise, a subsequently activated counter value **Switch on/off threshold** affects the output immediately when the switching condition is fulfilled.

6.4.2 Latching the counter value

In incremental encoder mode, the counter value can be latched and thus the current value can be entered in the process data. Input 3 is used as a latch input.

To enable the function, the variable **Enable latch extern on positive edge** must be set to **True**. On a high level at input 3, the current counter value is entered into the variable **Latch Value**. You can monitor the validity of the variable. As soon as the latch value is entered, the variable **Latch extern valid** is also set to **True**.

Proceed as follows:



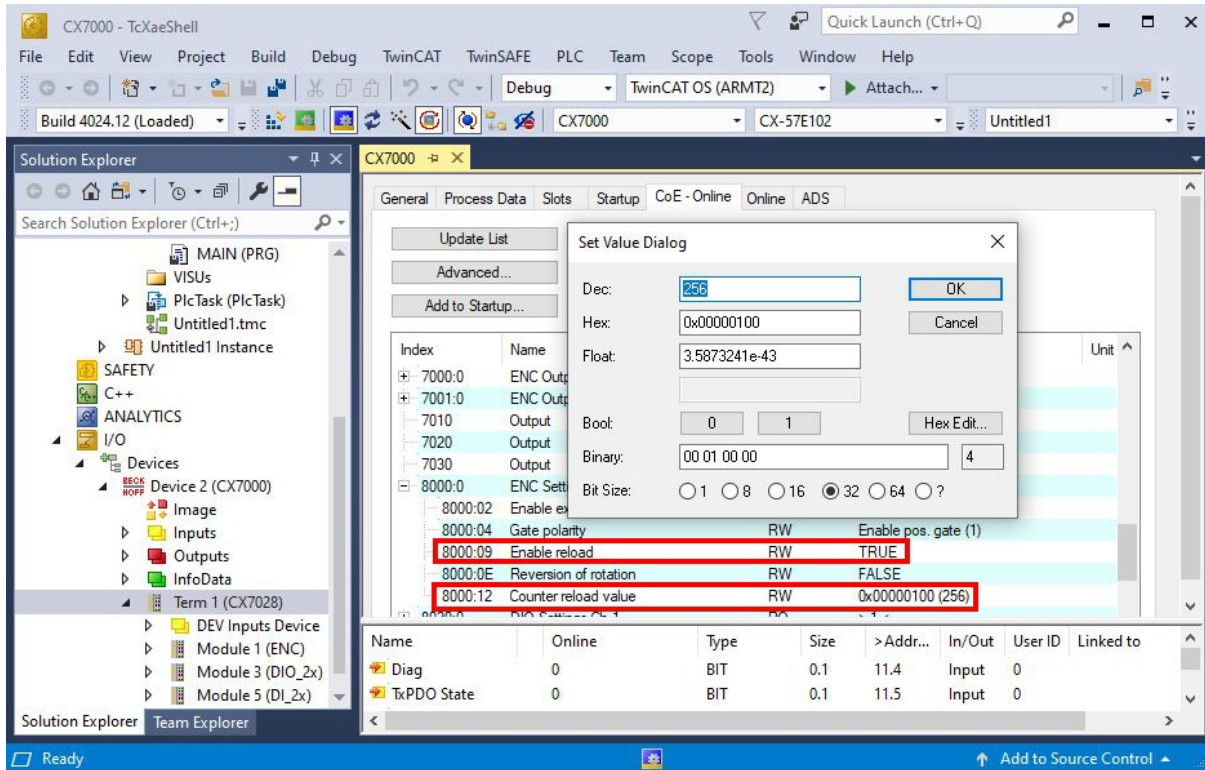
1. Set the variable **Enable latch extern on positive edge** to **True** to enable the latch function.
 2. Monitor the status of the latch input with the variable **Status of extern latch**.
 3. On a high level at input 3, the current counter value is entered into the variable **Latch Value**.
 4. Monitor the validity of the latch value via the variable **Latch extern valid**. Once the latch value has been written, the variable is also set to **True**.
- ⇒ To execute a latch again, the variable **Enable latch extern on positive edge** must receive a high level again.

6.4.3 Setting the limit value for counters

This step shows how you can set a limit value in TwinCAT from which the counter value is automatically reset to zero. When counting upwards, the counter value is reset to zero when the limit value is reached. When counting downwards, the counter value is reset to the set limit value when zero is reached.

Proceed as follows:

1. Click the **CX7028 device** on the left in the structure tree.
2. Click the **CoE-Online** tab.



3. Double-click the CoE object **8000:12 Counter reload value** and set the limit value.
 4. Then double-click the CoE object **8000:09 Enable reload** and set the value to **True**.
- ⇒ The function is only active when **Enable reload** is set. Alternatively, the latch input can be used and the counter value can thus be reset externally. To do this, the latch function must be disabled and the CoE object **Enable extern reset** set to **True**. With this setting, the current counter value is set to zero on a high level at input 3.

Index	Name	Flags	Value	Unit
7020	Output	RO P	FALSE	
7030	Output	RO P	FALSE	
8000:0	ENC Settings	RO	> 18 <	
8000:02	Enable extern reset	RW	TRUE	
8000:04	Gate polarity	RW	Enable pos. gate (1)	
8000:09	Enable reload	RW	TRUE	
8000:0E	Reversion of rotation	RW	FALSE	
8000:12	Counter reload value	RW	0x00000100 (256)	
8020:0	DIO Settings Ch.1	RO	> 1 <	

6.5 Analog signal mode

The single-ended inputs 7 and 8 acquire signals in the range of 0 to 10 V.

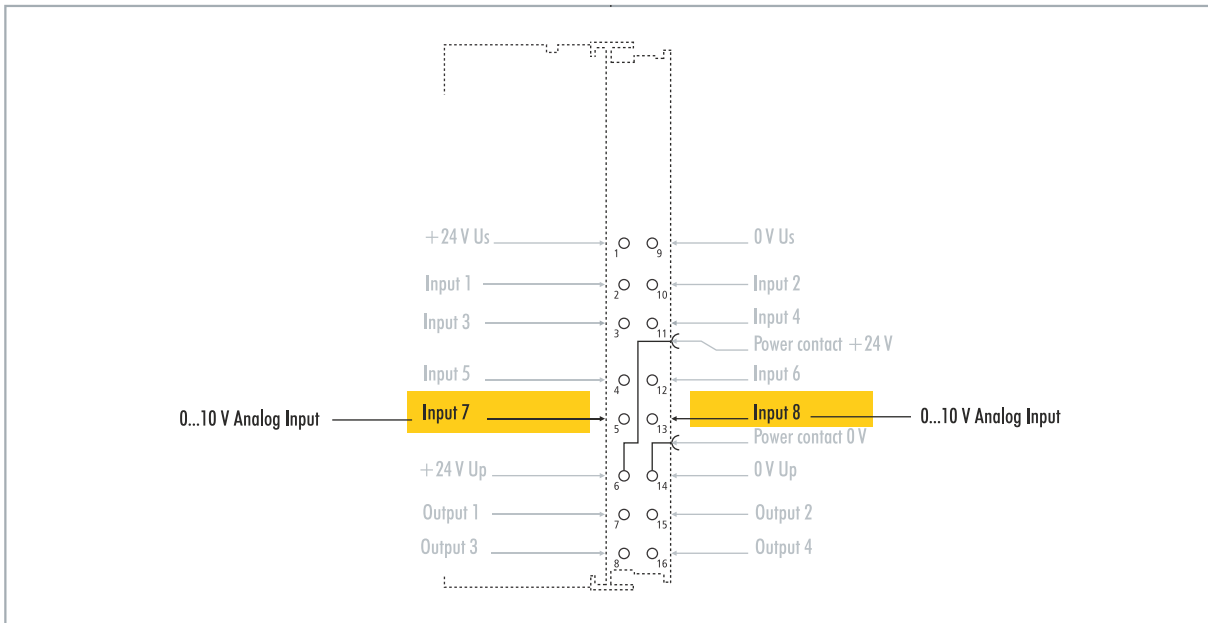


Fig. 34: Configurable analog inputs.

The voltage is digitized with a resolution of 12 bits. LEDs are used to indicate the signal state.

Table 12: Technical data, multi-function I/Os in analog mode.

Technical data	CX7050
Technology	single ended
Number of inputs	2
Signal voltage	0...10 V
Internal resistance	500 kΩ
Input filter cut-off frequency	2 kHz
Resolution	12-bit (16-bit representation)
Measuring error	< ±0.3 % (relative to full scale value)
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

*e: single-wire, solid wire; f: stranded wire; a: with ferrule

6.6 PWM signal mode

NOTICE

Feedback at the 24 V outputs

A voltage of 24 V at outputs 3 and 4 can destroy the device (feedback). No voltage may be applied to the outputs in PWM mode.

The PWM signal mode enables a pulse width modulated binary signal to be output at outputs 3 and 4.

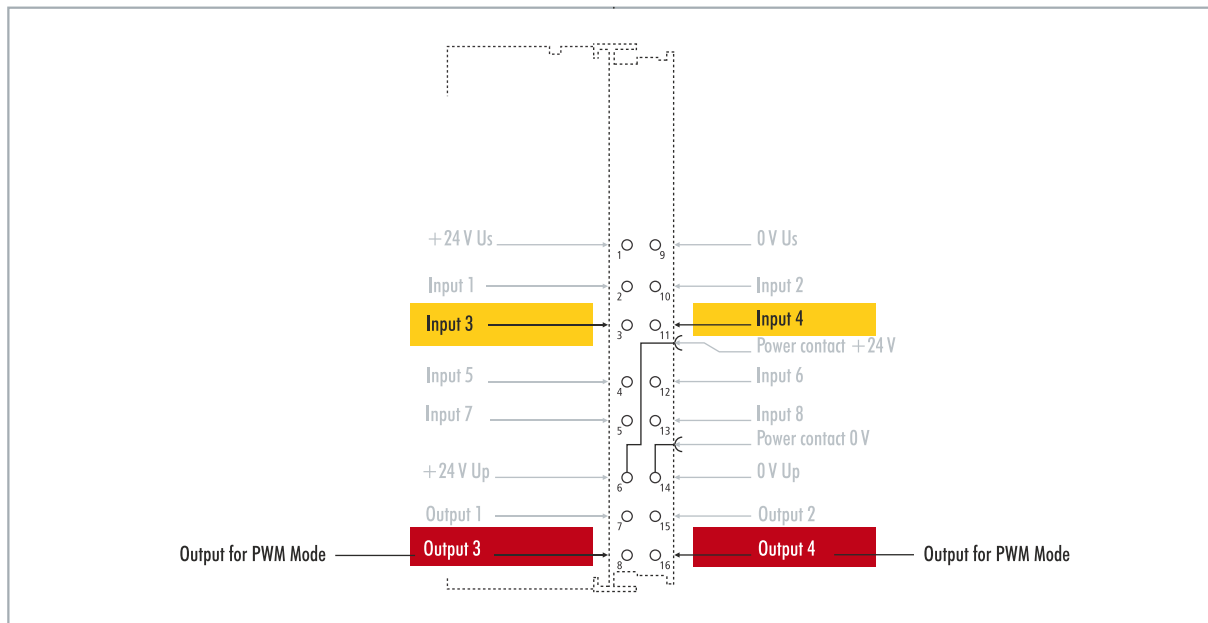


Fig. 35: Configurable inputs and outputs in PWM signal mode

This signal is separated into duty cycle (0... 100 %) and PWM clock frequency (15 Hz... 100 kHz). The LEDs are clocked with the outputs, and show the duty cycle by their brightness. The signal values are transferred in 16-bit values.

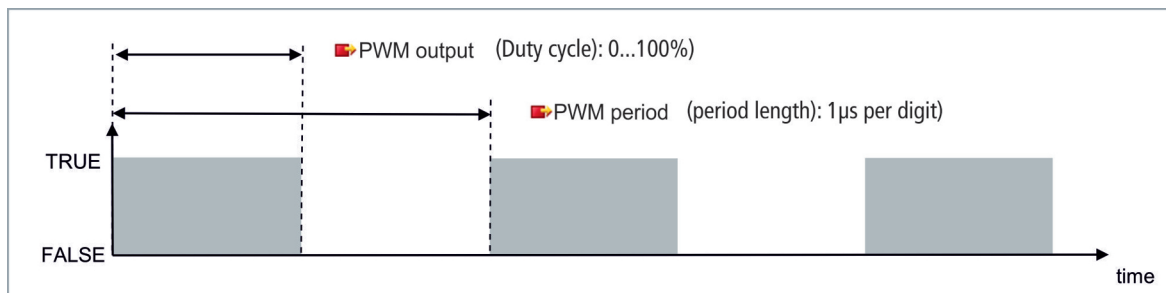


Table 13: Technical data, multi-function I/Os in PWM mode.

Technical data	Digital inputs
Connection technology	PWM output
Number of outputs	2
Nominal voltage	24 V DC (-15 %/+20 %)
Load type	ohmic, inductive, lamp load
Max. output current	24 V/0.5 A (short-circuit proof)
PWM clock frequency	15 Hz... 100 kHz
Duty cycle	0... 100 % (T _{ON} > 20 ns, T _{OFF} > 200 ns)
Short circuit current	< 2 A typ.
Special features	separate frequency can be set for each channel

Technical data	Digital inputs
Connection cross-section	e*: 0.08...1.5 mm ² , f*: 0.25...1.5 mm ² , a*: 0.14...0.75 mm ²
Connection cross section AWG	e*: AWG 28...16, f*: AWG 22...16, a*: AWG 26...19
Strip length	8 ... 9 mm

*e: single-wire, solid wire; f: stranded wire; a: with ferrule

6.6.1 Setting the PWM clock frequency and duty cycle

The signals at outputs 3 and 4 are output with pulse width modulation, the signals being separated into duty cycle and PWM clock frequency. Separate values for duty cycle and PWM clock frequency can be defined for both outputs.

Table 14: PWM output (duty cycle), representation of the PWM signal in the delivery state.

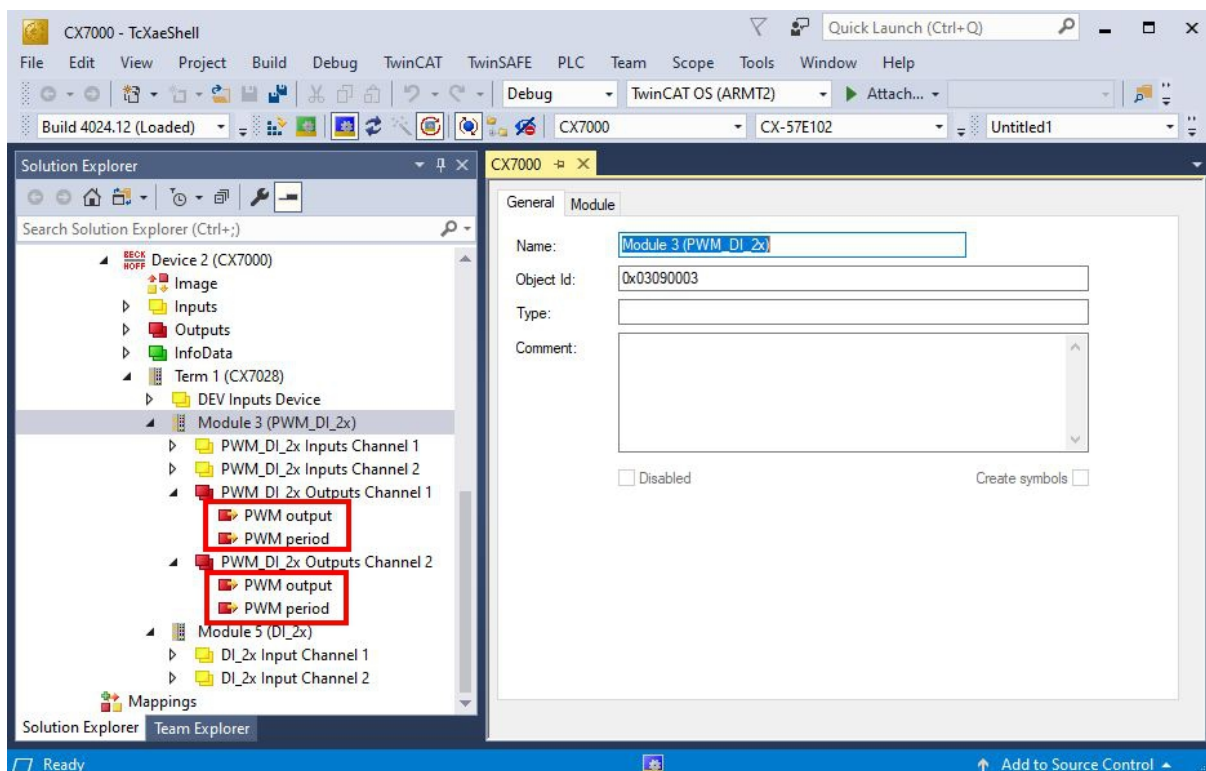
Value	Decimal	Hexadecimal
0 %	0	0x0000
25 %	16383	0x3FFF
50 %	32767	0x7FFF
100 %	65.535	0xFFFF

Table 15: PWM period (PWM clock frequency), representation of the PWM signal in the delivery state.

Value	Decimal	Hexadecimal	Frequency
0.010 ms	0..10	0x0000-0x000A	100 kHz
0.011 ms	11	0x000B	90.909 kHz
0.100 ms	100	0x0064	10 kHz
1.000 ms	1000	0x03E8	1 kHz
16.38 ms	16383	0x3FFF	61.04 Hz
65.53 ms	65535	0xFFFF	15.26 Hz

The variable **PWM output** correspond to the duty cycle and **PWM period** to the PWM clock frequency at which the signal is output.

Proceed as follows:



1. On the left in the structure tree, select an output for which you wish to set the duty cycle and PWM clock frequency.
2. Link the variables **PWM output** and **PWM period** with the appropriate variables from your PLC project.
3. In the variables, set the values for duty cycle and PWM clock frequency according to the above tables.

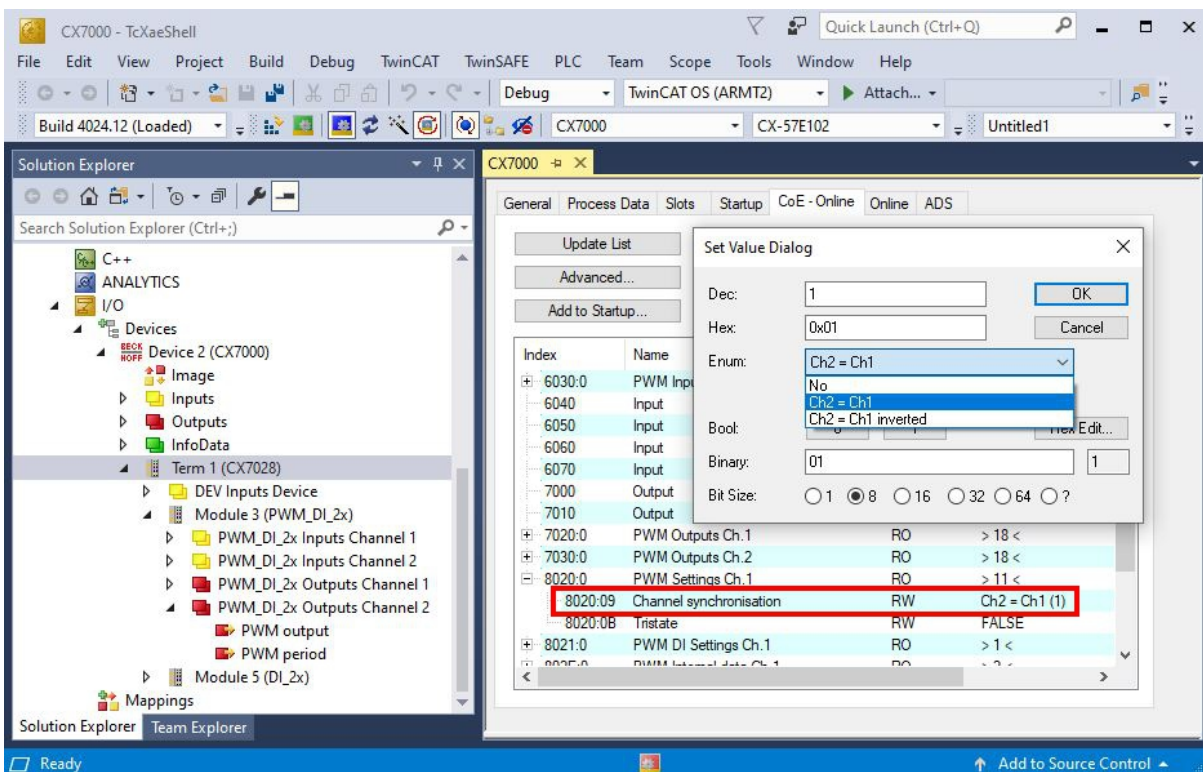
6.6.2 Setting the channel synchronization

The channel synchronization option makes the output of output 2 dependent on output 1. The following values are available in the CoE objects:

- No: no dependency
- Ch2 = Ch1: Duty cycle and PWM clock frequency of output 1 are also applied to output 2. The phase position is 0, i.e. the rising and falling edges of output 1 and output 2 are synchronized.
- Ch2 = Ch1 inverted: Duty cycle and PWM clock frequency of output 1 are also applied to output 2. However, the PWM clock frequency is inverted. The phase position is 0, i.e. a rising edge at output 1 triggers a falling edge at output 2 at the same time.

Proceed as follows:

1. Click the **CX7028 device** on the left in the structure tree.
2. Click the **CoE-Online** tab.



3. Double-click the CoEObject **8020:09 Channel synchronization**.
4. Under the option **Enum**, select the type of synchronization required.

7 Configuration

7.1 Starting the Beckhoff Device Manager

Using the Beckhoff Device Manager, an Industrial PC can be configured by remote access with the aid of a web browser. The access takes place via the HTTP protocol and Port 80 (TCP).

Requirements:

- Host PC and Embedded PC must be located in the same network. The network firewall must allow access via port 80 (HTTP).
- IP address or host name of the Embedded PC.

Table 16: Access data for the Beckhoff Device Manager on delivery.

User name	Password
Administrator	1

Start the Beckhoff Device Manager as follows:

1. Open a web browser on the host PC.
2. Enter the IP address or the host name of the Industrial PC in the web browser to start the Beckhoff Device Manager.
 - Example with IP address: <http://169.254.136.237/config>
 - Example with host name: <http://BTN-000f89fa/config>
3. Enter the user name and password. The start page appears:

The screenshot displays the Beckhoff Device Manager web interface. On the left, there is a vertical navigation menu with icons and labels for 'Device', 'Hardware', 'Software', 'TwinCAT', and 'Security'. The 'Device' option is highlighted in red. The main content area is titled 'Device' and shows a table of system information for the device 'BTN-000f89fa'. The table includes fields for Name, Date Time, Operating System, Image Version, Hardware Version, Serial number of IPC, and Device Manager Version. Below the table, there is a 'Workload' section with two progress bars: one for CPU usage at 7% (Max: 100%) and one for Memory usage at 29% (Max: 100%).

- ⇒ Navigate forward in the menu and configure the Industrial PC. Note that modifications only become active once they have been confirmed. It may be necessary to restart the Industrial PC.

7.2 Persistent data

NOTICE

Application example

In the following example, changes to the loads, the power supply or even just aging components can lead to the application no longer fulfilling the desired function. Beckhoff takes no responsibility for the implementation of the example in an application.

Normally, persistent data are only stored during the TwinCAT stop or by a function block. This chapter shows you how to store persistent data on a CX7050 without a UPS.

In the case of an Embedded PC with UPS, the function block is usually linked to the UPS. The function block becomes active as soon as a power failure is detected, writes the persistent data and then shuts down the Embedded PC. With a 1-second UPS, the Embedded PC is not shut down because there is too little time left for this.

In the case of a small controller such as the CX7050 which is delivered without a 1-second UPS, you can still use this function. All that is needed is to use a power supply unit that has enough residual energy to supply power to the CX7050 with this residual energy for a certain period of time. A small test can show you if this is possible with your power supply unit:

Testing a power supply unit

When the CX7050 is running, turn off the AC voltage of your power supply unit and measure how long the CX7050 continues to run. If it is more than three seconds, you may be able to use the power supply unit as a replacement for a 1-second UPS. Note that power supply units also age and lose capacity. You should therefore include a safety factor, such as a factor of three, so that you have enough reserve to be able to operate the power supply unit for a longer period of time as a replacement for a 1-second UPS.

Now determine how long the power supply unit maintains the supply of power. You need an EL1722 for this, which you connect to the AC side of the power supply unit. Then write a small program:

```
VAR
    bPower230V AT %I* : BOOL; (*link to the EL1722*)
END_VAR

VAR RETAIN
    Counter : INT;
END_VAR

Program:
IF NOT bPower230V THEN (*bPower230V is linked to the EL1722*)
    Counter:=counter+1; (*the counter is a retain value*)
END_IF
```

Create a boot project and turn off the AC voltage of the power supply unit. As soon as the EL1722 no longer displays a value, the counter is incremented and the data are copied to the internal NOVRAM. Turn the AC voltage back on and log in. You must now multiply the counter value by the task time. Repeat this a few times to be sure that the power supply unit always behaves in the same way. Next, you have to insert the function block `FB_WritePersistentData`. This is contained in the `Tc2_Uilities` library (in the "TwinCAT PLC" folder).

Then determine how long it takes to store the persistent data. Repeat this process a few times too, so that you obtain a constant value and can determine a maximum value in case of fluctuations. You can determine the time required via the Busy flag. The function block is being processed as long as the Busy flag is set. Multiply the value determined by two to incorporate a further safety factor.

Example:

Your measurement shows that the power supply unit maintains the supply of power for three seconds and that the persistent data is written in about 400 ms. With the recommended safety factors, the power supply is maintained for one second and the persistent data is written in about 800 ms.

The power supply is therefore maintained for a longer period of time than is needed to store the persistent data. Therefore you can use the example power supply unit as a replacement for the 1-second UPS.

7.3 NOVRAM

The NOVRAM can be used to reliably save important variable values, such as production data or counter values, in the event of a power failure. The memory size of the NOVRAM is limited and only suitable for smaller data quantities up to 4 kB.

In this chapter we show you how the NOVRAM is used in TwinCAT 3.

Functioning

The NOVRAM (Non-Volatile Random Access Memory) is a special memory component that is used to reliably save important data. The NOVRAM consists of two sections, a volatile memory and a non-volatile memory.

TwinCAT only writes to the volatile section of the NOVRAM. In the event of a power failure, the data are automatically copied from the volatile memory into the non-volatile memory. The energy required for this process is supplied by a capacitor. As soon as the power supply is restored, the data are automatically copied back into the volatile memory, so that TwinCAT can continue to use them.

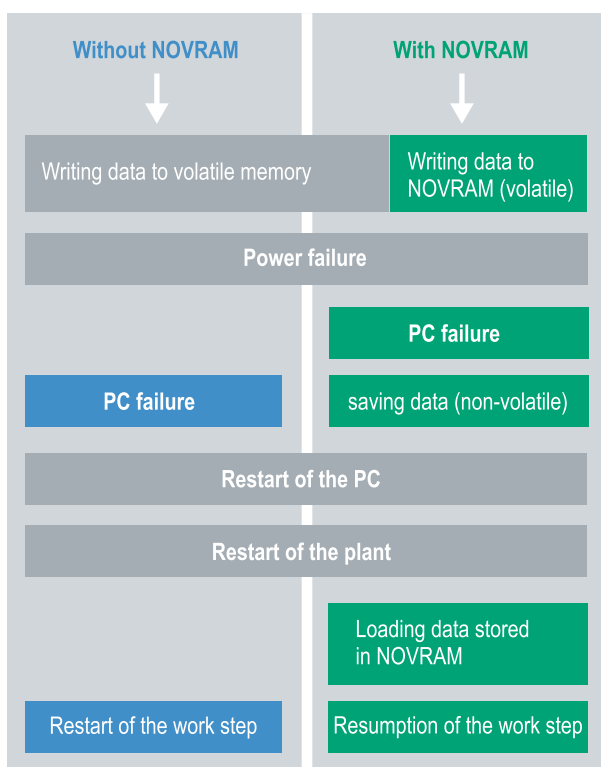


Fig. 36: Controller behavior with and without NOVRAM.

Memory size

The NOVRAM has a capacity of 4 kB. The data are saved cyclically and alternately based on the dual buffer principle, in order to avoid the risk of data inconsistency.

Requirements

Development environment	Target platforms	Hardware	PLC libraries to include
TwinCAT 3.1 Build: 4020	PC or CX (x86, x64, ARM)	CX70xx, CX9020, CX20x0, CX20x2, CX20x3	Tc2_IoFunctions

7.3.1 Creating a Retain Handler

Under TwinCAT 3 (from Build 4020) a delta algorithm is used to save data in the NOVRAM. The algorithm does not save all the variables in the NOVRAM. Instead, it searches for changes (delta function) compared to the previous cycle and only saves variables that have changed.

To use the delta algorithm, a Retain Handler must be created in TwinCAT 3, and the relevant variables must be declared in the PLC with the keyword VAR_RETAIN.

A new feature of this method is that no function blocks have to be used. The Retain Handler saves data in the NOVRAM in the event of a power failure and makes them available again once the power has been restored.

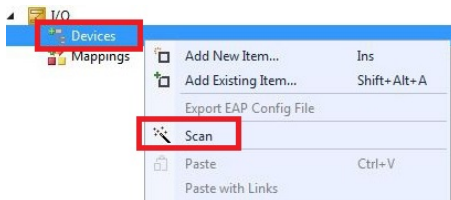
This chapter describes how to create a Retain Handler in TwinCAT 3. The Retain Handler saves data in the NOVRAM and makes them available again. In other words, important variable values such as production data or counter values are retained during a restart or power failure.

Requirements for this step:

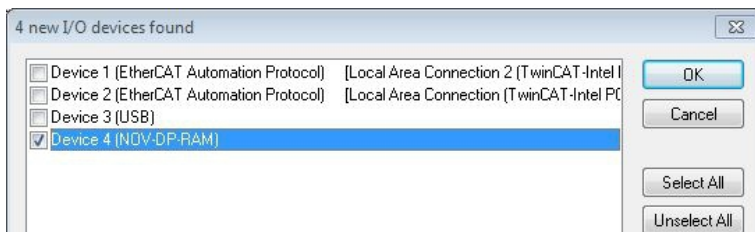
- TwinCAT 3.1 Build: 4020.
- A target device selected in TwinCAT.

Create the Retain Handler as follows:

1. Right-click on **Devices** in the tree view on the left-hand side.
2. In the context menu click on **Scan**.

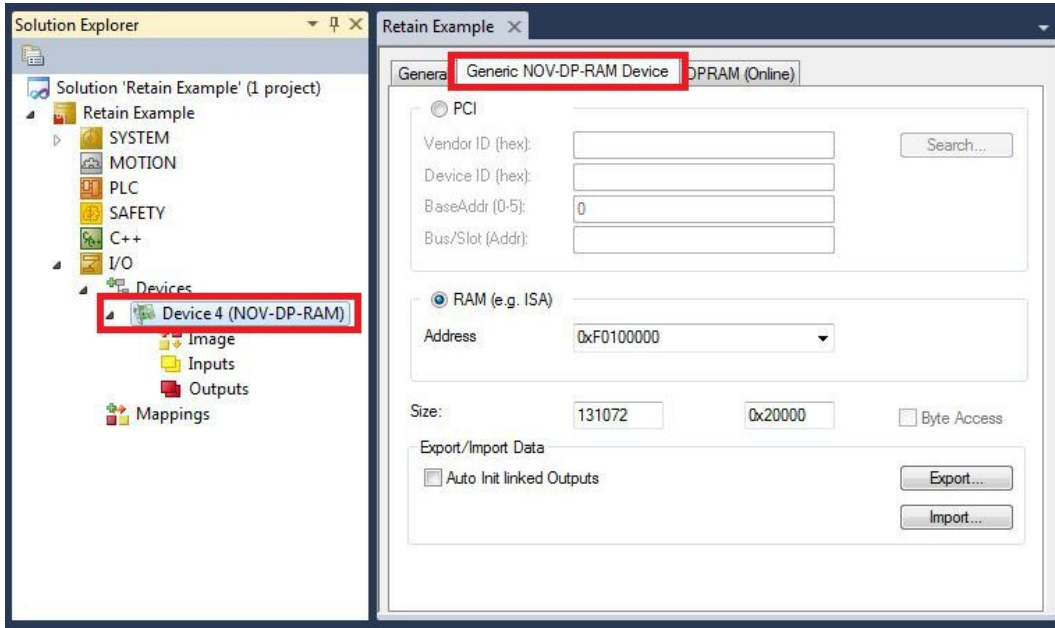


3. Select **Device (NOV-DP-RAM)** and confirm with **OK**.

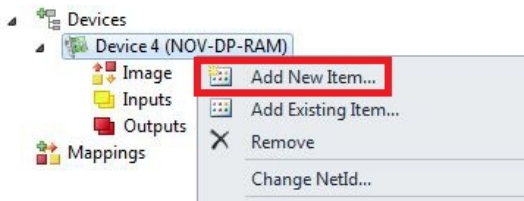


4. Click on **Yes** to search for boxes.

- Click on **Device (NOV-DP-RAM)** in the tree view on the left-hand side and then on the tab **Generic NOV-DP-RAM Device**.



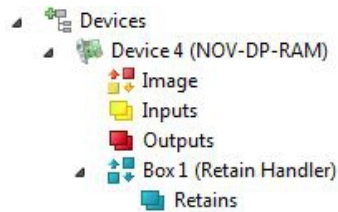
- Click the option **RAM**.
- Right-click on **Device (NOV-DP-RAM)** in the tree view and then on **Add New Item**.



- Select the **Retain Handler** and click on **OK**.



⇒ You have successfully created a Retain Handler in TwinCAT.



In the next step you can create retain variables in the PLC and link them with the Retain Handler.

7.3.2 Creating and linking variables

Once you have created a Retain Handler in TwinCAT, you can declare variables in the PLC and link them to the Retain Handler. The variables have to be identified in the PLC with the keyword VAR_RETAIN.

Prerequisite for this step:

- A PLC project created in TwinCAT.

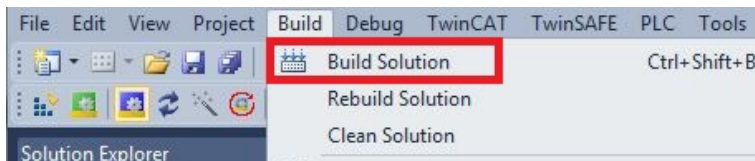
Create variables as follows:

1. Create the variables in your PLC project in a VAR_RETAIN area.

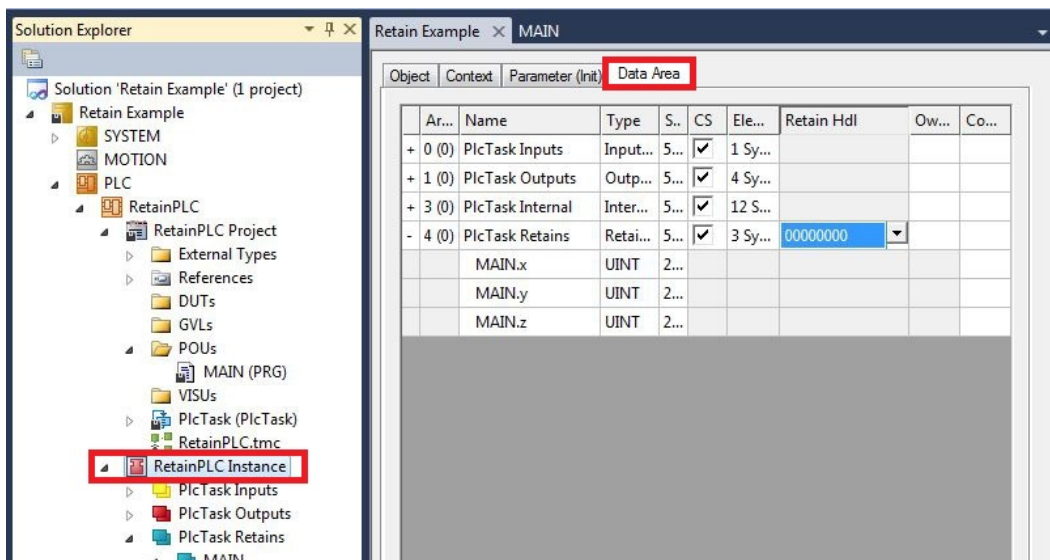
```

1  PROGRAM MAIN
2
3  VAR_RETAIN
4      x      :UINT;
5      y      :UINT;
6      z      :UINT;
7  END_VAR
8
9  VAR
10
11     datain  AT$I*: REAL;
12     dataout AT$Q*: BYTE;
13
14 END_VAR
    
```

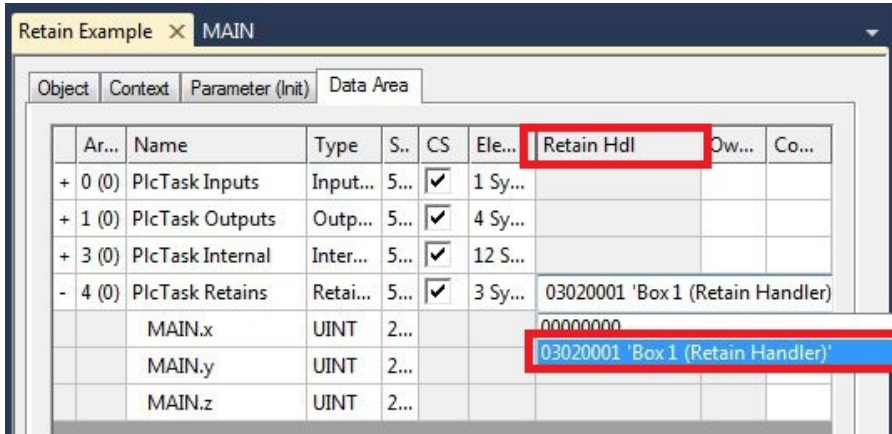
2. Click on **Build** in the toolbar at the top, then on **Build Solution**.



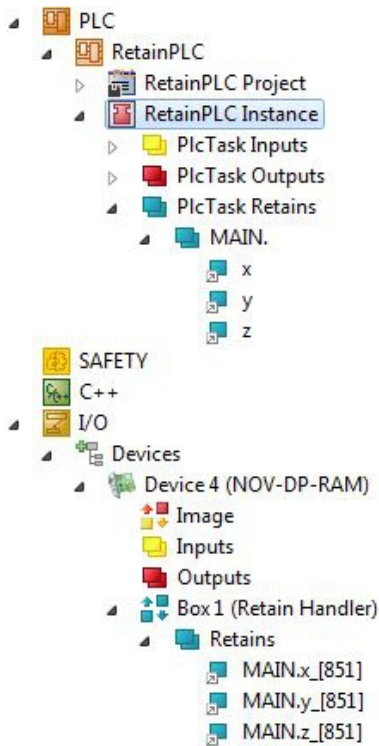
3. Click on **PLC Instance** in the tree view on the left and then on the tab **Data Area**.



4. Under **Retain Hdl**, select the Retain Handler that you have created.



⇒ After selecting a Retain Handler as a target, the symbols in the tree view are linked and a mapping is created.
 In the tree view the variables are created from the PLC under the Retain Handler and linked to the variables from the PLC instance.



An existing link is displayed with an arrow symbol.

7.3.3 Deleting variables under the Retain Handler

If variables are deleted from the PLC, the link with the Retain Handler is cancelled. However, the variables continue to be shown under the Retain Handler and are not deleted automatically.

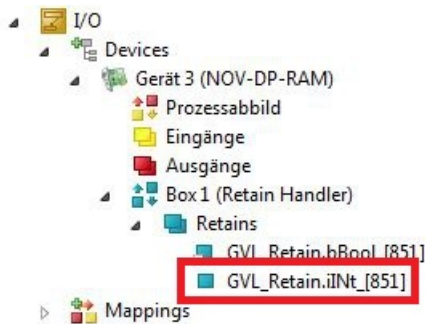
Under TwinCAT 3 the variables have to be deleted manually.

Prerequisites for this step:

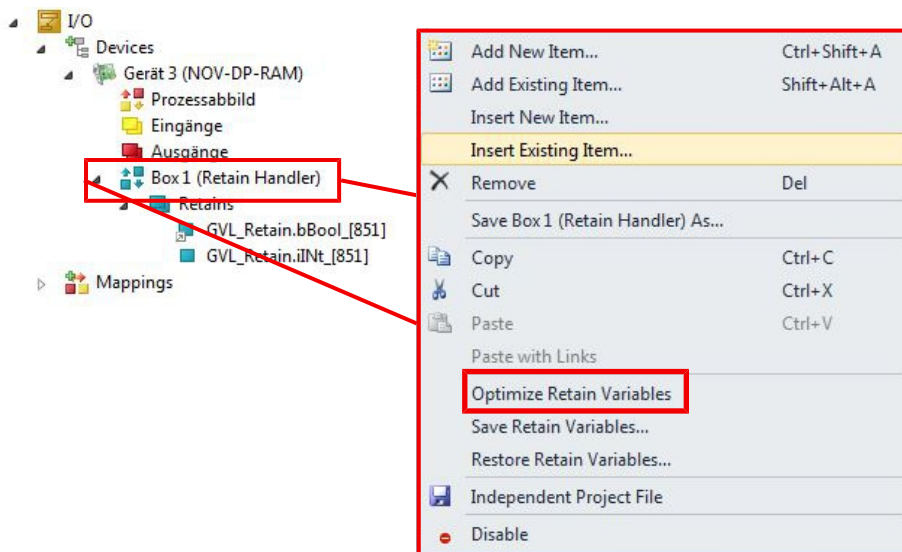
- Variables declared with VAR_RETAIN were deleted from the PLC.

Delete the variables under the Retain Handler as follows:

1. The variable GVL_Retain.iInt under the Retain Handler is to be deleted.



2. Right-click on the **Retain Handler** in the tree view on the left.
3. In the context menu click on **Optimize Retain Variables**.



⇒ The variable under the Retain Handler is deleted.

7.4 Software configuration

7.4.1 User name and password

In the delivery state, the CX7050 has a preset user name with password, which is necessary for logging in to TwinCAT or the Beckhoff Device Manager.

- User name: Administrator
- Password: 1

The user name is fixed and cannot be changed. It is also not possible to add another user name. The preset password can be changed via the Beckhoff Device Manager (see: Starting the Beckhoff Device Manager). The password can contain a maximum of 32 characters. Numbers, letters and special characters are allowed and a distinction is also made between upper and lower case letters.

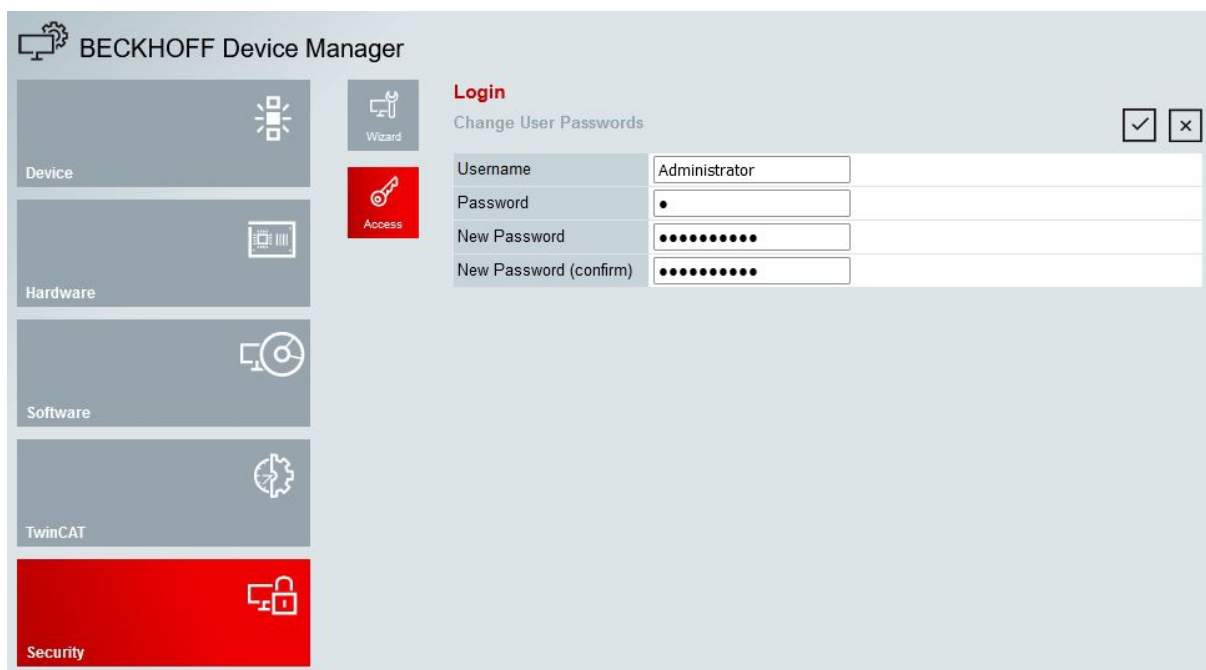


Fig. 37: Changing the password in the Beckhoff Device Manager.

You can restore the delivery state and preset password by removing the MicroSD card, accessing the MicroSD card with a card reader and deleting the `device.conf` file in the `/etc` folder. The password cannot be reset without physical access to the CX7050 and thus to the MicroSD card.

7.4.2 Setting the IP address

DHCP is enabled by default for the CX7050. Without a DHCP server, the CX7050 uses a local IP address in the address range 169.254.x.x

In the case of the CX7050 Embedded PC, there are several ways to set the IP address. One way is to call the Beckhoff Device Manager and set the IP address for the CX7050 in the browser (see: Starting the Beckhoff Device Manager).

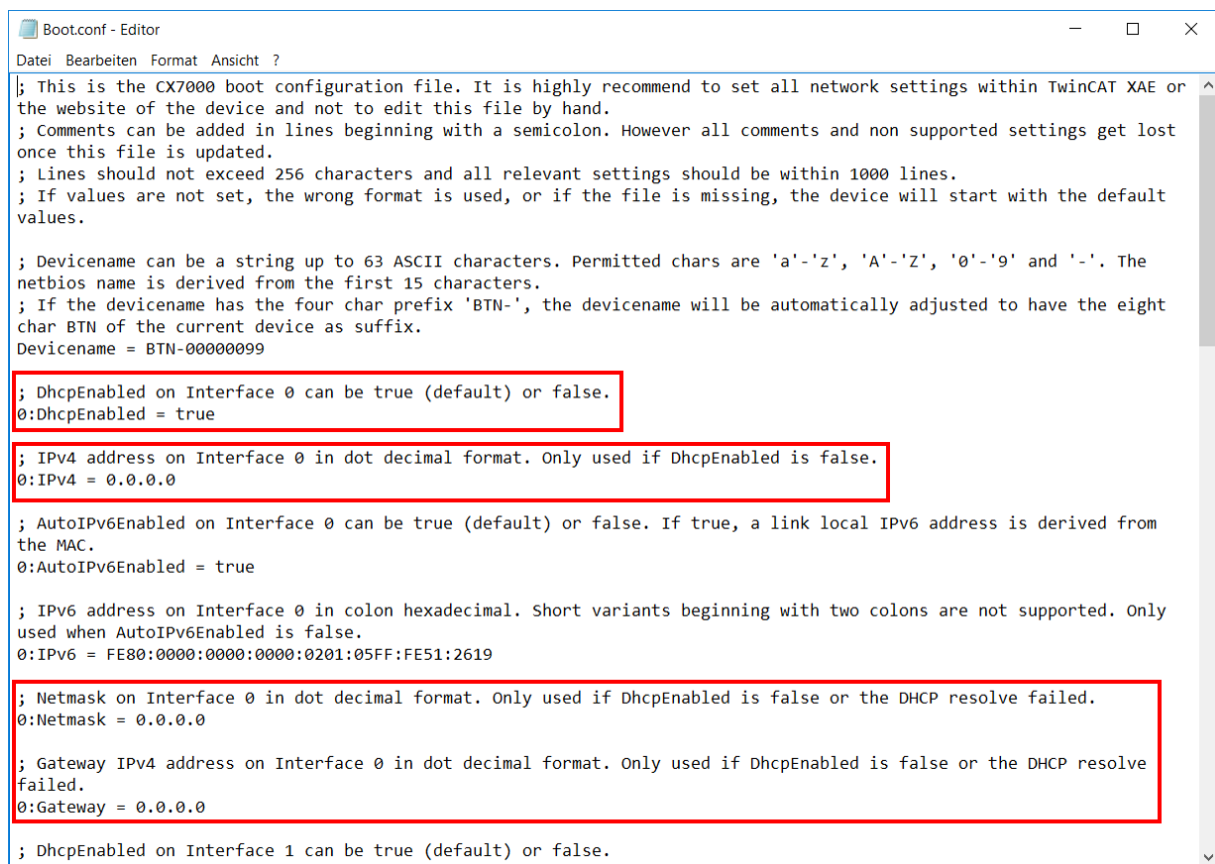
Another way to set the IP address is offered by the boot.conf file, which is created on the MicroSD card after the first start. This step shows you how to set the IP address in the boot.conf file.

Requirements:

- MicroSD card reader

Proceed as follows:

1. Switch the Embedded PC off and remove the MicroSD card from the Embedded PC.
2. Open the Boot.conf file under /etc



```
Boot.conf - Editor
Datei Bearbeiten Format Ansicht ?
; This is the CX7000 boot configuration file. It is highly recommend to set all network settings within TwinCAT XAE or
; the website of the device and not to edit this file by hand.
; Comments can be added in lines beginning with a semicolon. However all comments and non supported settings get lost
; once this file is updated.
; Lines should not exceed 256 characters and all relevant settings should be within 1000 lines.
; If values are not set, the wrong format is used, or if the file is missing, the device will start with the default
; values.

; Devicename can be a string up to 63 ASCII characters. Permitted chars are 'a'-'z', 'A'-'Z', '0'-'9' and '-'. The
; netbios name is derived from the first 15 characters.
; If the devicename has the four char prefix 'BTN-', the devicename will be automatically adjusted to have the eight
; char BTN of the current device as suffix.
Devicename = BTN-00000099

; DhcpEnabled on Interface 0 can be true (default) or false.
0:DhcpEnabled = true

; IPv4 address on Interface 0 in dot decimal format. Only used if DhcpEnabled is false.
0:IPv4 = 0.0.0.0

; AutoIPv6Enabled on Interface 0 can be true (default) or false. If true, a link local IPv6 address is derived from
; the MAC.
0:AutoIPv6Enabled = true

; IPv6 address on Interface 0 in colon hexadecimal. Short variants beginning with two colons are not supported. Only
; used when AutoIPv6Enabled is false.
0:IPv6 = FE80:0000:0000:0000:0201:05FF:FE51:2619

; Netmask on Interface 0 in dot decimal format. Only used if DhcpEnabled is false or the DHCP resolve failed.
0:Netmask = 0.0.0.0

; Gateway IPv4 address on Interface 0 in dot decimal format. Only used if DhcpEnabled is false or the DHCP resolve
; failed.
0:Gateway = 0.0.0.0

; DhcpEnabled on Interface 1 can be true (default) or false.
```

3. Set the **DhcpEnabled** entry to **false**.
 4. Assign an IP address under **IPv4**.
 5. Make the settings for subnet mask, gateway and DNS server.
- ⇒ Save the changes and install the MicroSD card in the Embedded PC again. The settings are effective after startup.

7.4.3 Update image

NOTICE

Failure of the power supply

The bootloader may be corrupted if the update is interrupted. The CX70x0 thus becomes unusable and must be sent in for repair. Ensure a stable power supply during initial start-up and do not interrupt the update.

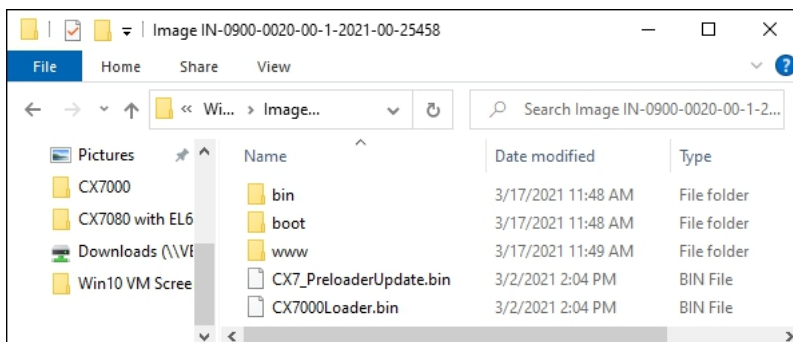
The new image will be copied directly to the MicroSD card in order to update the image of the Embedded PC. The new image is made available by Beckhoff Service. Perform the update only after consulting with Beckhoff Service.

Requirements:

- Card reader for MicroSD cards.

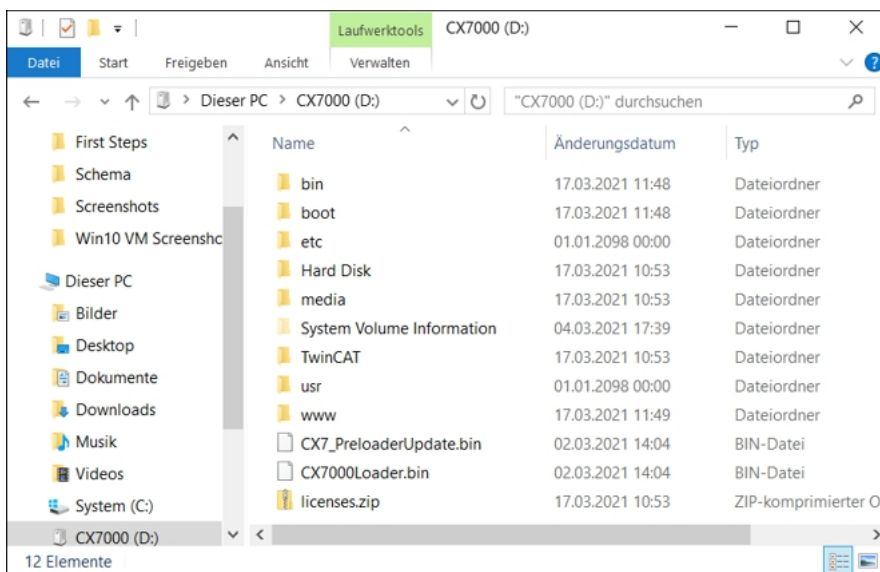
Update the image as follows:

1. Switch the Embedded PC off and remove the MicroSD card from the Embedded PC.
2. Insert the MicroSD card into an external card reader and open the MicroSD card's folder tree.
3. Delete all files and folders on the MicroSD card.
4. Copy all files and folders of the new image to the empty MicroSD card.



5. Re-install the MicroSD card in the Embedded PC and start the Embedded PC.

⇒ The Embedded PC is started and saves the current hardware configuration. New folders are created, such as Hard Disk or TwinCAT. The image has now been successfully updated.



7.4.4 Updating the firmware for multifunction I/Os

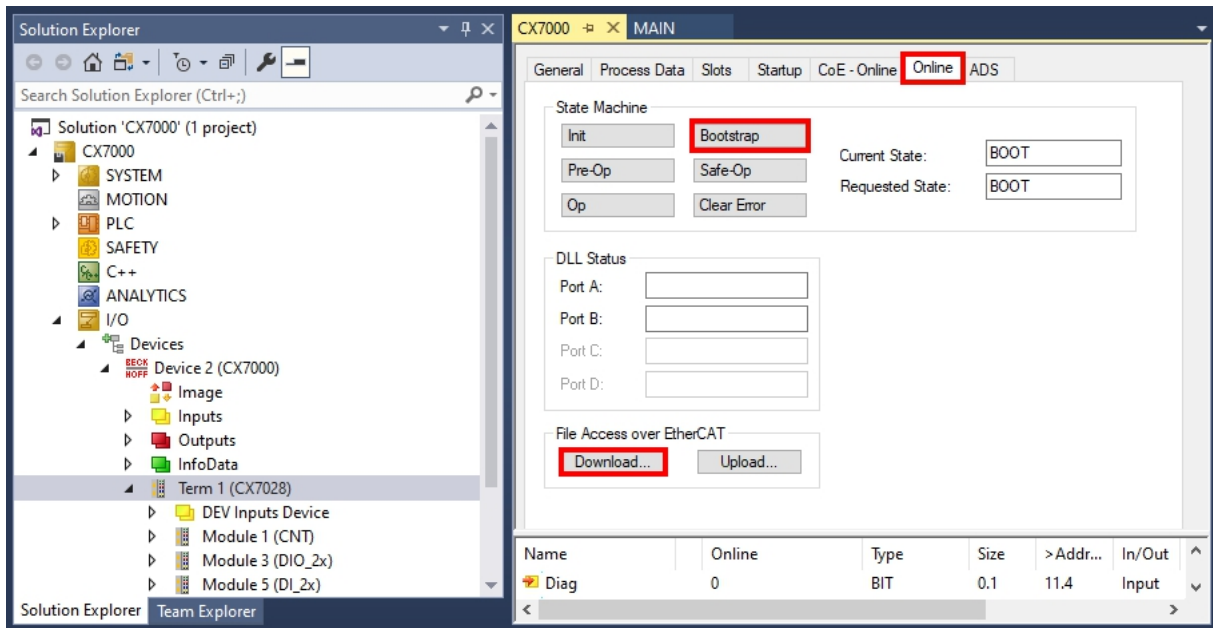
This step shows you how to update the firmware of the multifunction I/Os. The firmware is provided by Beckhoff Service and the update is carried out in TwinCAT.

Requirements:

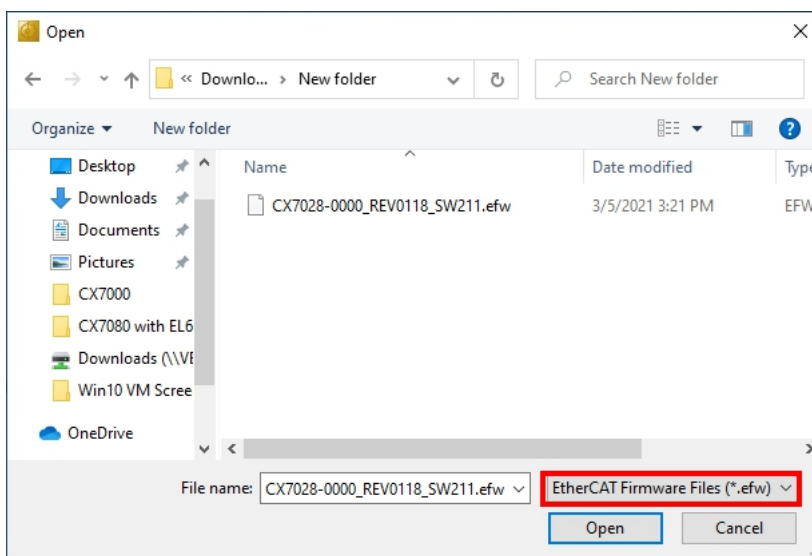
- EtherCAT firmware file (*.efw)

Proceed as follows:

1. Start TwinCAT in configuration mode (config mode).
2. On the left in the structure tree, click the CX7028 device and then click the **Online** tab.



3. Click the **Bootstrap** button to switch the multifunction I/Os to the bootstrap state.
4. Click the **Download** button and select a current efw file.



⇒ The update takes about 3 to 4 minutes. A progress bar indicates the progress of the update. Do not switch the CX7050 off during this time.

When the update is complete, return to the Operational (Op) state by clicking the **Op** button.

7.4.5 Updating the ESI device description

The TwinCAT System Manager and the TwinCAT EtherCAT Master require the device description files of all EtherCAT devices for configuration in online and offline mode. These device descriptions are the so-called ESI files (EtherCAT Slave Information) in XML format. These files can be requested from the respective vendor and are made available for download. An *.xml file may contain several device descriptions.

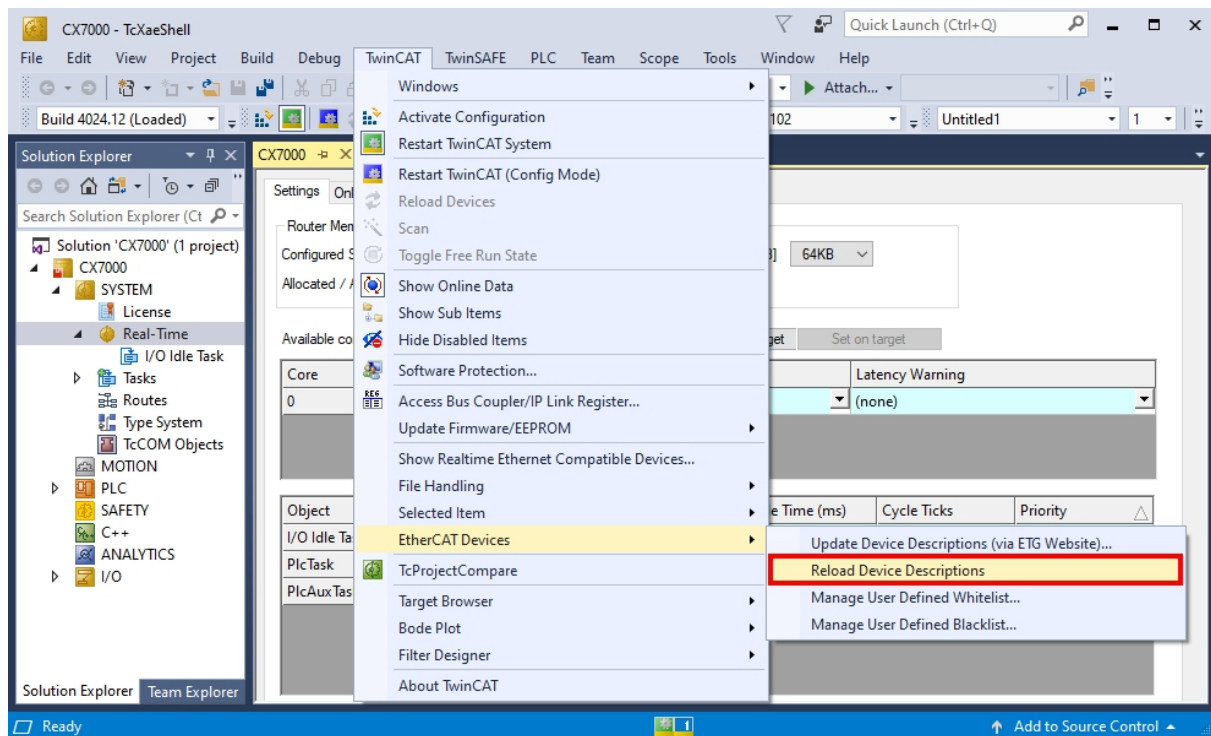
ESI files for Beckhoff EtherCAT devices are provided at <https://www.beckhoff.com>.

Requirements:

- ESI file for the CX7050 in XML format.
- If necessary, the associated *.xsd file, which describes the structure of the XML file.

Proceed as follows:

1. Copy the ESI file into the TwinCAT installation directory: `\TwinCAT\3.1\Config\Io\Onboard\Io`.
2. Create the folder manually if it doesn't exist.
3. Open TwinCAT and click in the menu under **TwinCAT > EtherCAT Devices** on **Reload Device Description**.



- ⇒ The ESI file is re-read into TwinCAT. An error is returned if there is a faulty ESI file. Check whether the structure of the *.xml corresponds to the associated *.xsd file or whether the files match the CX7050.

8 TwinCAT

8.1 First Steps

8.1.1 Connect to the CX70x0

Before you can configure the CX7050 in TwinCAT, you must establish a connection between your engineering computer and the CX7050 (target system). The engineering computer and the Embedded PC must be in the same network and subnet or alternatively connected directly via an Ethernet cable (peer-to-peer).

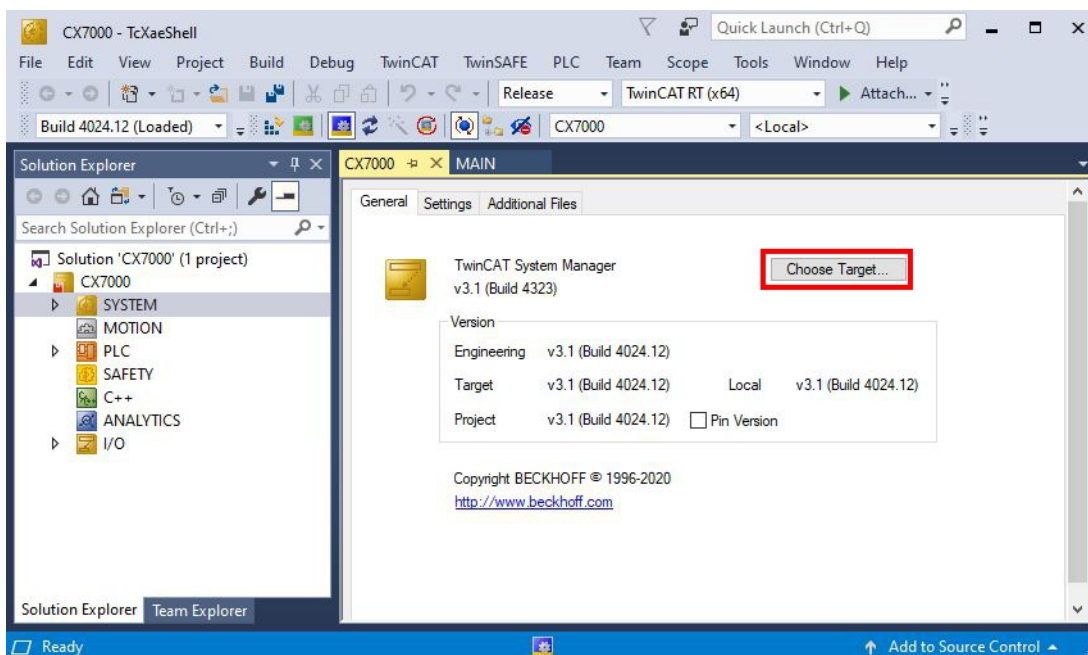
The IP address or host name of the CX7050 is required for the connection.

Requirements:

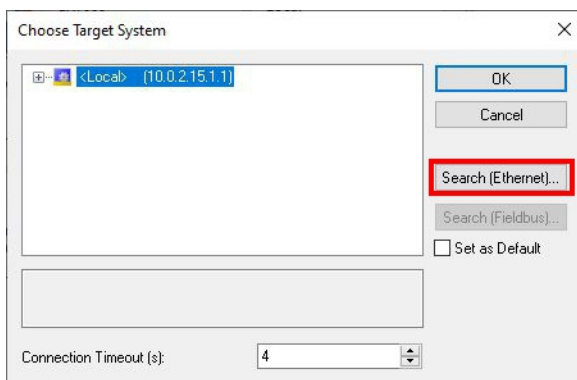
- TwinCAT must be in Config mode.
- IP address or host name of the Embedded PC.

Establish a connection as follows:

1. In the menu at the top click on **File > New > Project** and create a new TwinCAT XAE project.
2. In the tree view on the left click on **SYSTEM**, and then **Choose Target**.



3. Click on **Search (Ethernet)**.



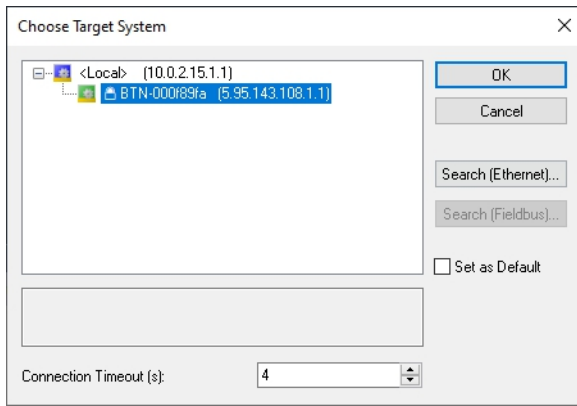
4. Click **Broadcast Search** and search for available devices on the network.

5. Mark the appropriate CX7050 and click **Add Route**. The host name and IP address facilitate identification.

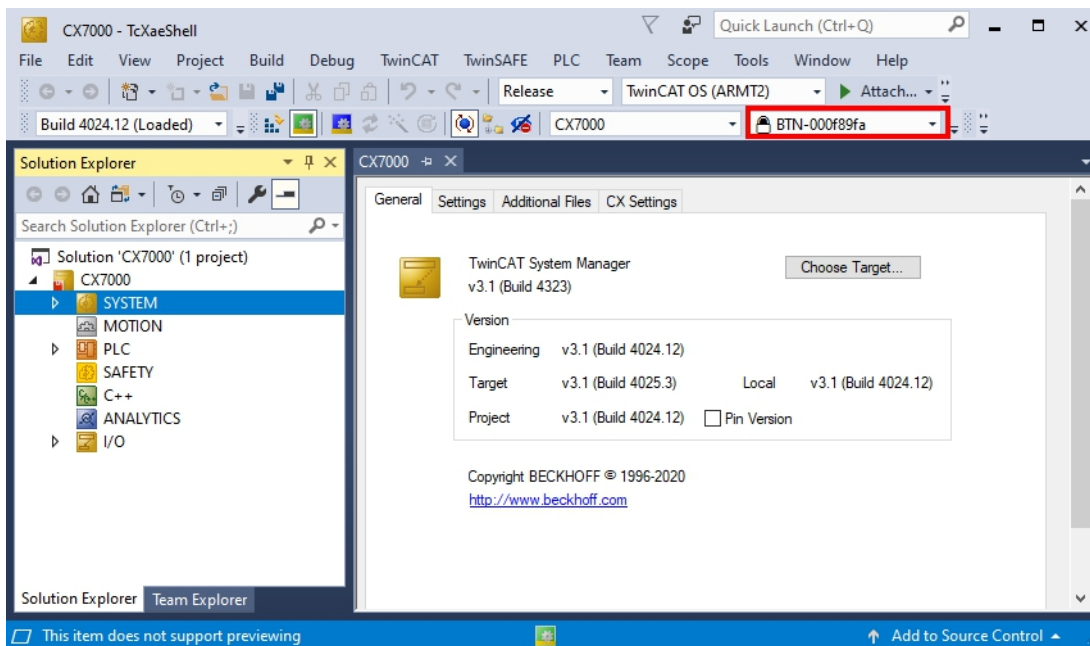
6. Enter the user name and password in the **User** and **Password** fields respectively and click **OK**. User name: Administrator Password: 1

7. The new device is displayed in the **Choose Target System** window.

8. Select the device you want to specify as target system and click **OK**.



⇒ You have successfully established a connection between your engineering computer and the CX7050 (target system) in TwinCAT. The new target system and the host name are displayed in the menu bar.



Using this procedure you can search for all available devices and also switch between the target systems at any time.

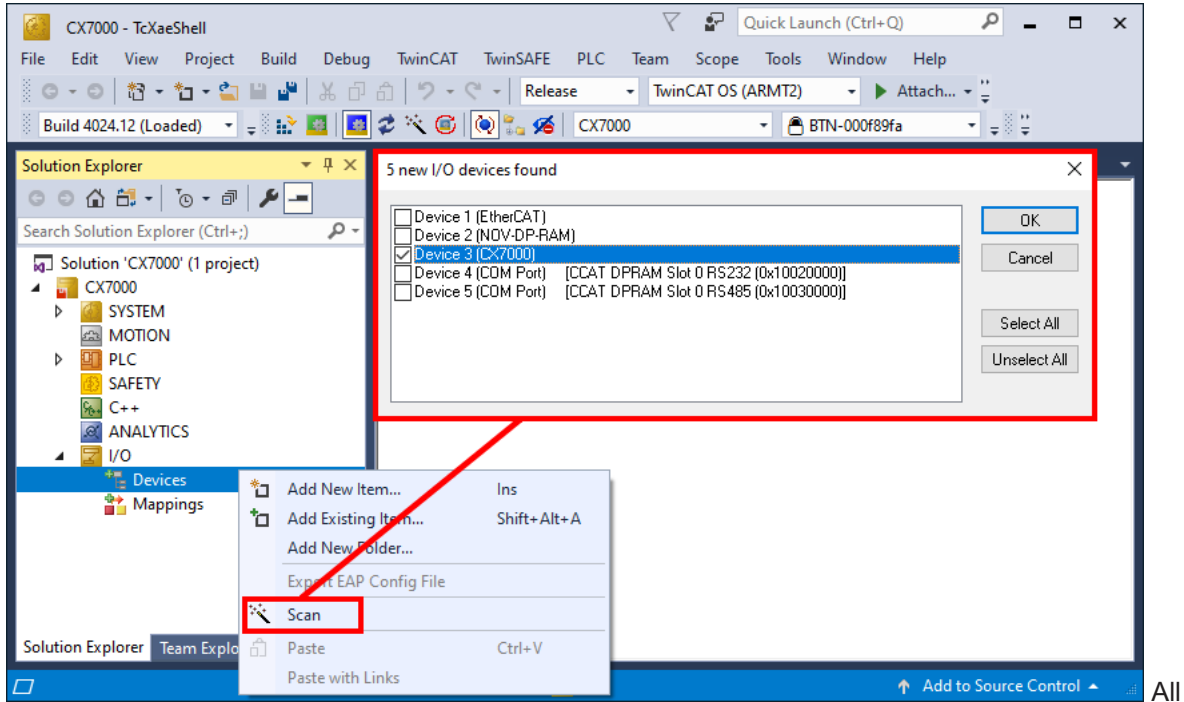
8.1.2 Scan multifunction I/Os

Special features of the CX7000 series are the eight integrated multifunction inputs and four integrated multifunction outputs. This chapter shows how to scan and create the multifunction I/Os in TwinCAT.

Note that the CX7028 interface for controlling the multifunction I/Os has its own CPU and the CX7028 interface is not displayed or does not work under TwinCAT if the power supply(Up) is not connected.

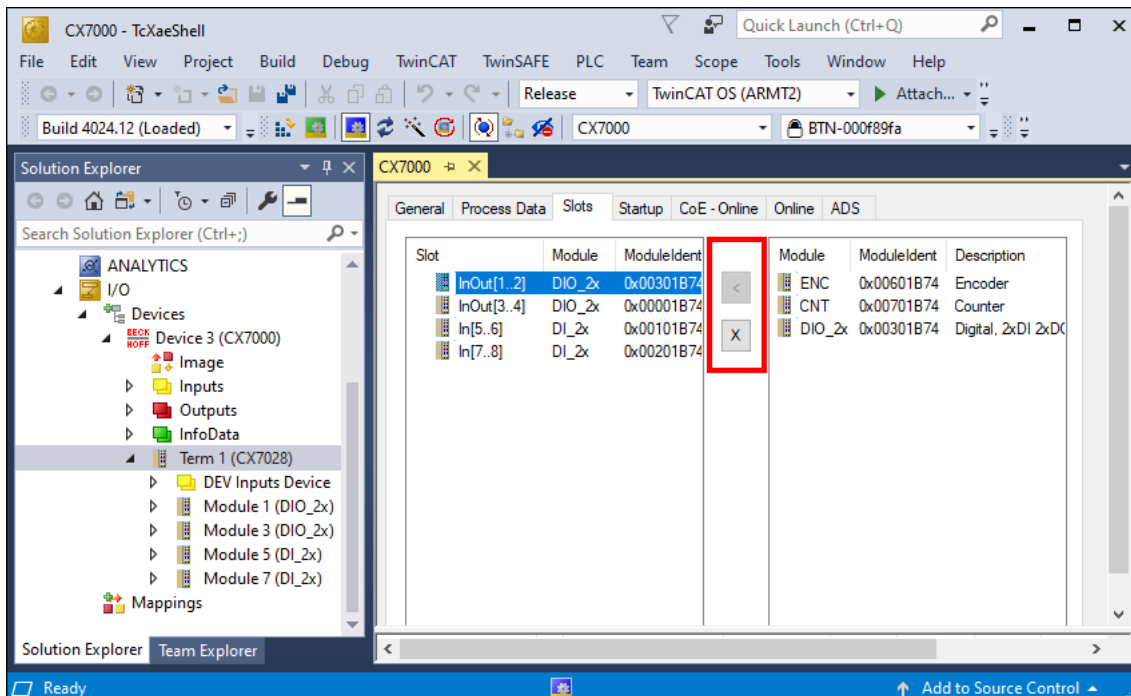
Proceed as follows:

1. On the left side of the tree view, right-click **Devices** and then click **Scan**.



available I/O devices are displayed.

2. Select the appropriate I/O devices. For this example, at least the CX7028 interface, i.e. the CX7000 device, must be selected. If you still want to operate Bus or EtherCAT Terminals on the CX7000, then you must also select EtherCAT as a device.
3. A total of four slots are created. For each slot a maximum of one module (DI, DIO, ENC, CNT or PWM) can be assigned, which in turn determines the operation mode for the respective slot.



4. Modules can be assigned to a specific slot with the button < or removed again with x.
 ⇒ Define the required modules according to their requirements. There is a choice of different modules depending on the slot used. Which modules are supported by which slot is listed in the chapter [Multifunction I/Os \[► 95\]](#).

8.1.3 Establishing ADS communication

This chapter shows you how to connect a CX7050 to another CX70x0 or any TwinCAT controller. The ADS protocol provides the simplest way to connect two TwinCAT systems to each other. With the ADS protocol, data can be both read and written. ADS function blocks are normally used for communication; these are included in the Tc2_System library. In the following example, data are to be written to and read from a memory area.

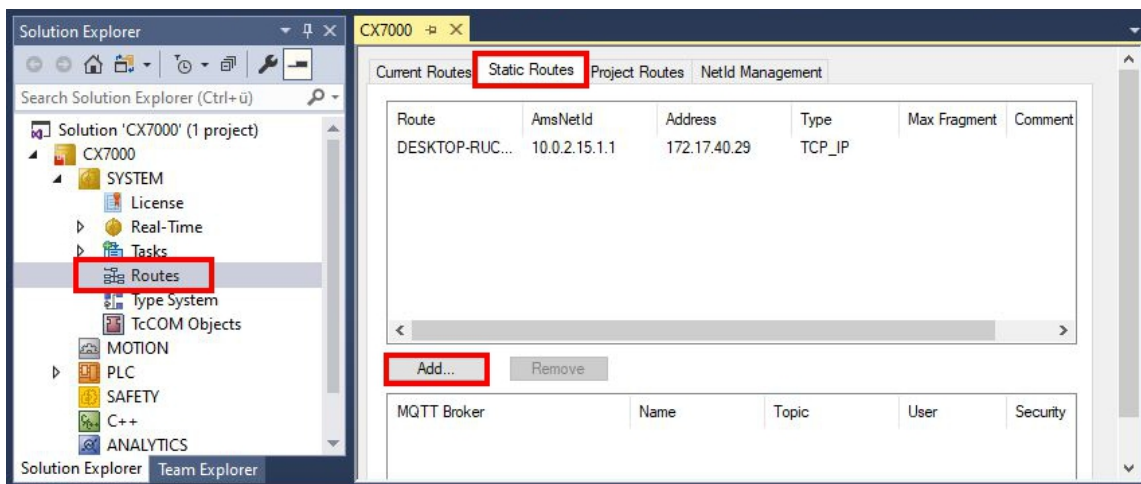
In order to set up an ADS connection, an ADS route is created first. Communication then takes place via Ethernet and data exchange via the TCP/IP protocol. The ADS route is then the interface between the ADS and TCP/IP connection. The ADS route indicates which AmsNetId is assigned to which TCP/IP address. As a result, the ADS function blocks no longer use the TCP/IP address, but the AmsNetId.

Requirements:

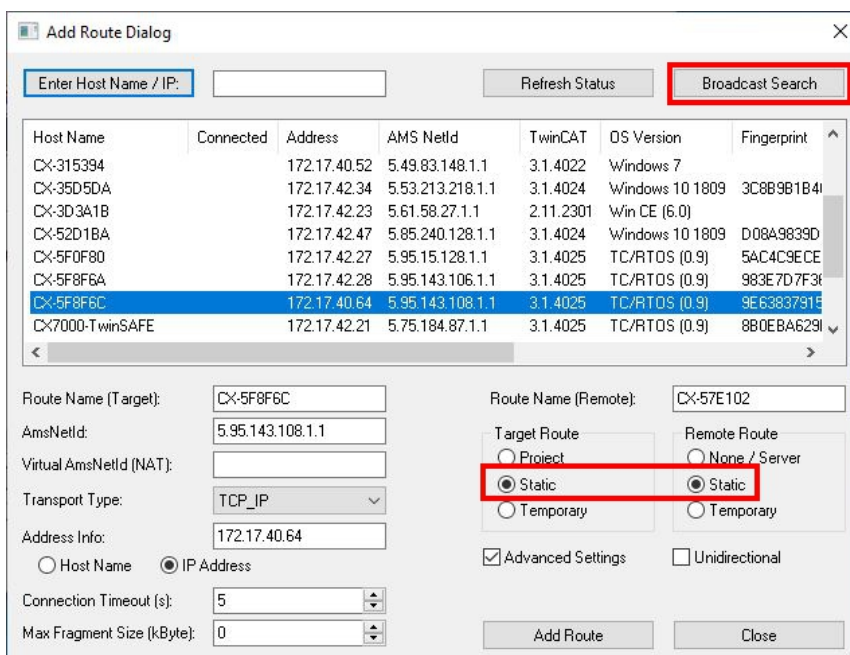
- Two CX70x0 Embedded PCs.
- Both CX70x0s are in the same network and accessible via ADS.

Proceed as follows:

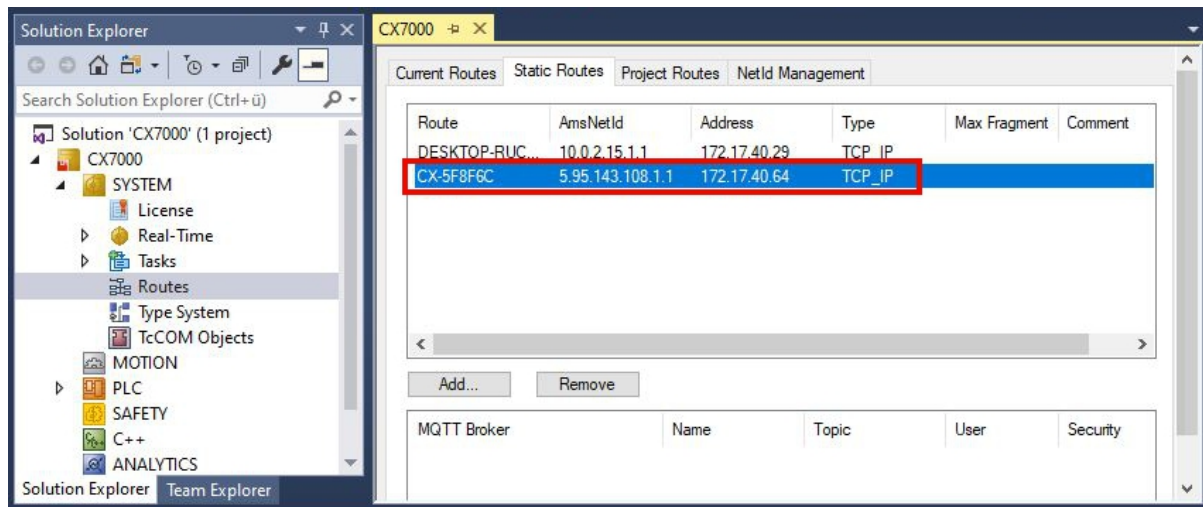
1. Start TwinCAT and connect to the first CX70x0 (see: [Connect to the CX70x0 \[P 129\]](#)).
2. On the left in the tree view, click **Routes**, select the **Static Routes** tab, and click the **Add** button.



3. Under **Remote Route**, select the **Static** option so that the ADS route remains in the project, and then click the **Broadcast Search** button.



- Select the second CX70x0 as the destination of the ADS route. The ADS route is entered for both Embedded PCs. The AmsNetId of the second CX70x0 is displayed and can be used in the program for ADS function blocks.



- Now connect to the second CX70x0, which has been set as the destination of the ADS route, and write a small program. Define an array and increment a value of the array.

```

VAR
  MarksTest AT %MB0      : ARRAY[0..9] of INT;
END_VAR

Program:
MarksTest[0]:=MarksTest[0]+1;

```

- Activate the configuration and switch the CX70x0 to Run mode.
- For the first CX70x0, write a program that reads the incremented value of the array.

```

VAR
  ADSREAD : ADSREAD;
  NetID : STRING:='5.81.38.23.1.1'; (* AMSNetId of the target*)
  Value : INT; (* value of target MarksTest[0]*)
  Error : INT;
  NoError : INT;
END_VAR

Program:
  ADSREAD(
    NETID:=NetID ,
    PORT:=851 , (* plc port of the target*)
    IDXGRP:=16#4020 , (* Marks %MB*)
    IDXOFFS:=0 , (* Marks offset in byte*)
    LEN:=2 , (* length of data in byte*)
    DESTADDR:=ADR(Value) , (* pointer to the data in which the value is to be stored *)
    READ:=TRUE ,
    TMOUT:= ,
    BUSY=> ,
    ERR=> ,
    ERRID=> );
  IF NOT ADSREAD.BUSY THEN
    IF NOT ADSREAD.ERR THEN
      NoError:=NoError+1;
    ELSE
      Error:=Error+1;
    END IF
  ADSREAD(Read:=FALSE);
END_IF

```

- The incremented value is read out and transmitted to the first CX70x0.
- ⇒ You should see on the first CX70x0 how the value of the `Value` variable is incremented. The writing of the data works in the same way. Data can be written with the `ADSWRITE` function block. Make sure that you set the offset (`IDXOFFSET`) to 10 in this sample setup so that the array [4... 9] is written. Limit the length to 10 bytes, as an array of 0... 9 of type `INT` was created and the memory thus uses %MB0... MB19 (10 * 2 bytes) (The elements 0...4 for reading the array and the elements 5...9 for writing it).

Use one ADS command at a time. Wait until the ADS service is finished, i.e. the `BUSY` output of the

function block is switched to FALSE, and only then use the next ADS function block. To optimize the access timing, you can also use an ADSREADWRITE function block that reads and writes the data at the same time.

8.1.4 Creating a PLC project

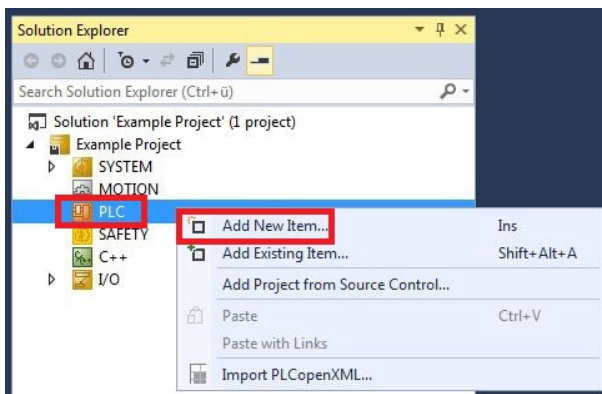
The next steps describe how to create a PLC project in TwinCAT and add it in the tree view.

Prerequisites for this step:

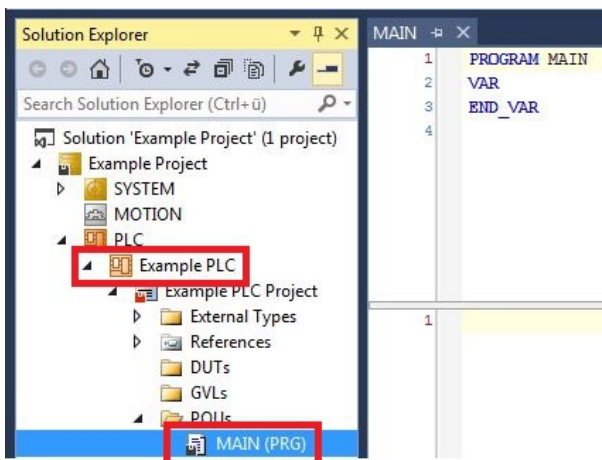
- A newly created TwinCAT XAE project.

Create a PLC project as follows:

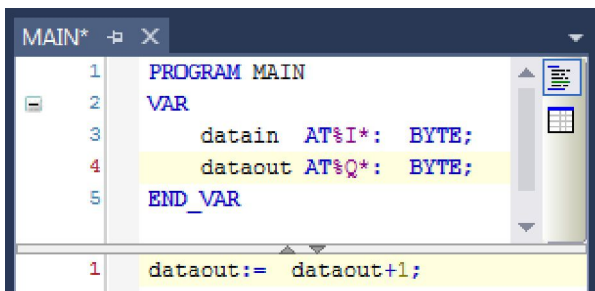
1. Right-click on **PLC** in the tree view.
2. In the context menu click on **Add New Item** and select the **Standard PLC Project**.



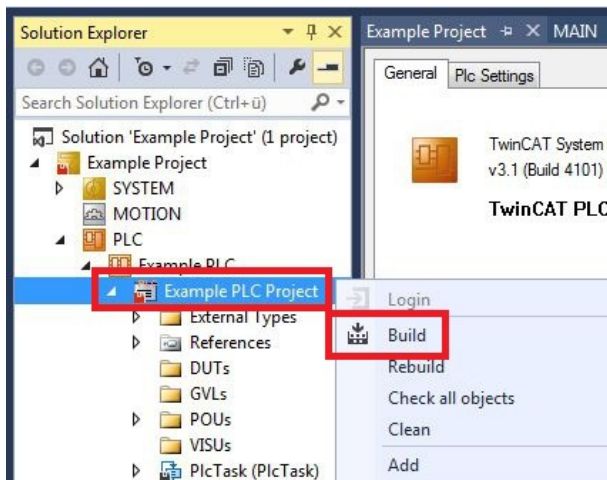
3. In the tree view click on the newly created PLC project, then double-click on **MAIN (PRG)** under **POUs**.



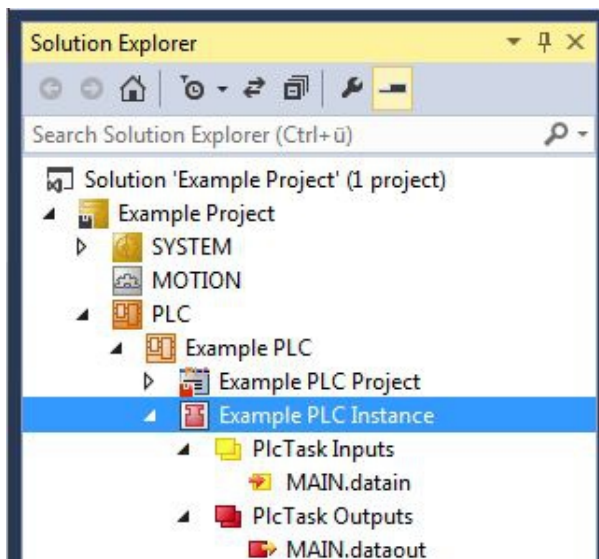
4. Write a small program, as shown in the diagram below.



5. In the tree view right-click on the PLC project, then click on **Build** in the context menu.



⇒ You have successfully created a PLC project and added the project in TwinCAT. A PLC instance with the variables for the inputs and outputs is created from the PLC project.



In the next step you can link the variables with the hardware.

8.1.5 Linking variables

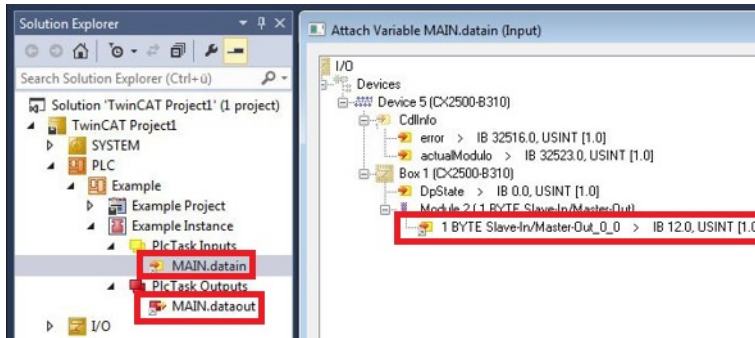
Once the PLC project was successfully added in the System Manager, you can link the newly created input and output variables from the PLC project with the inputs and outputs of your hardware.

Prerequisites for this step:

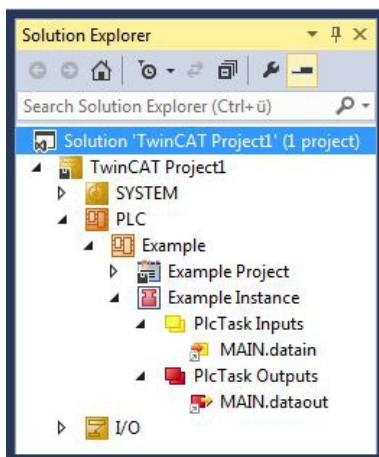
- A PLC program attached in TwinCAT.

Link the variables as follows:

1. Double-click on the input or output variables in the tree view under **PLC**.
The **Attach Variable** window appears and shows which inputs or outputs can be linked with the variables from the PLC project.



2. Double-click on the inputs or outputs of the hardware in the **Attach Variable** window.
Link the input variables with the inputs and the output variables with the outputs of the hardware.



Variables that are already linked are indicated with a small arrow icon in TwinCAT.

3. In the toolbar click on **Activate Configuration**.



4. Confirm the request whether TwinCAT is to start in Free Run mode with **Yes**.
⇒ You have successfully linked variables with the hardware. Use Activate Configuration to save and activate the current configuration.

The configuration can now be loaded on the CX, in order to automatically start TwinCAT in Run mode, followed by the PLC project.

8.1.6 Load configuration to CX

Once variables are linked, the configuration can be saved and loaded on the CX. This has the advantage that the PLC project is loaded and started automatically when the CX is switched on. The start of the previously created PLC project can thus be automated.

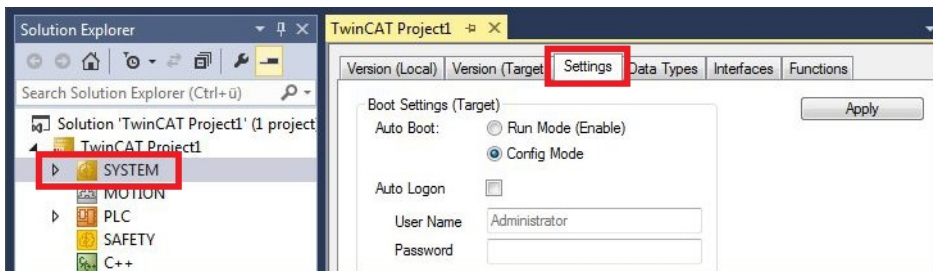
Prerequisites for this step:

- A completed PLC project, added in the System Manager.
- Variables from the PLC project, linked with the hardware in the System Manager.
- A CX selected as target system.

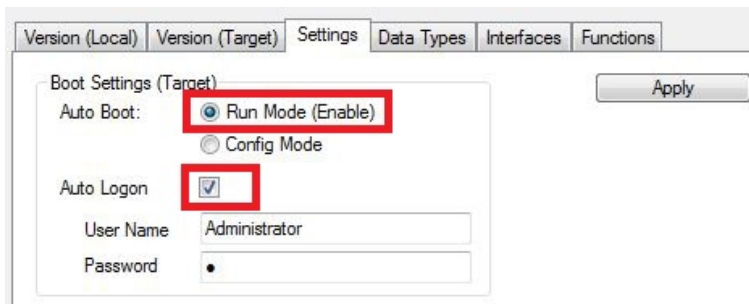
Load the configuration from the System Manager to the CX as follows:

1. In the tree view on the left click on **SYSTEM**.

2. Click on the **Settings** tab.



3. Under Boot Settings select the option **Run Mode (Enable)** and tick the **Auto Logon** checkbox.

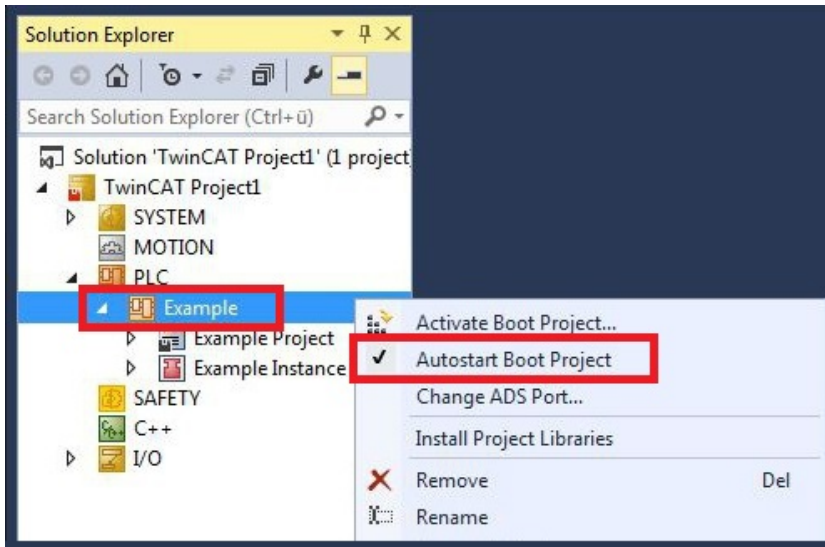


4. Enter the user name and password for the CX in the **User Name** and **Password** fields.

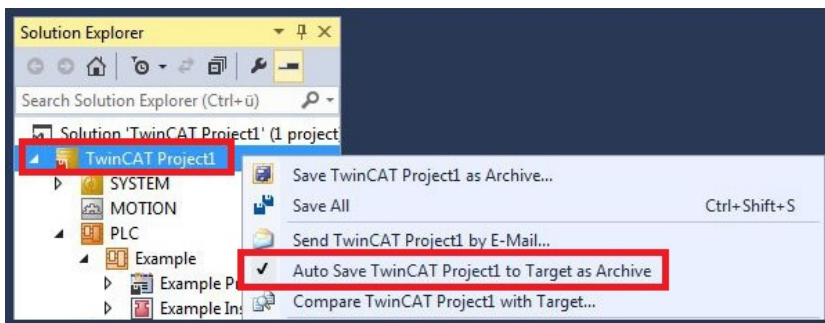
5. Click on **Apply**.

6. In the tree view on the left right-click on the PLC project under **PLC**.

- In the context menu click on **Autostart Boot Project**.
The setting is selected



- Right-click on the project folder in the tree view.
- In the context menu click on **Auto Save to Target as Archive**.
The setting is selected.



⇒ You have successfully loaded the CX configuration. From now on, TwinCAT will start in Run mode and the PLC project will start automatically.

Next, the master can be added in a new project in the System Manager and can then be used to find slaves that have already been set up.

8.2 TwinCAT tabs

In TwinCAT, information and settings for the CANopen interface are added under tabs. The main TwinCAT tabs are described in this chapter. In addition, the section illustrates how the CANopen interface is displayed in the tree view under TwinCAT.

8.2.1 Tree view

A CANopen master and a CANopen slave connected to it are displayed in the tree view as follows:

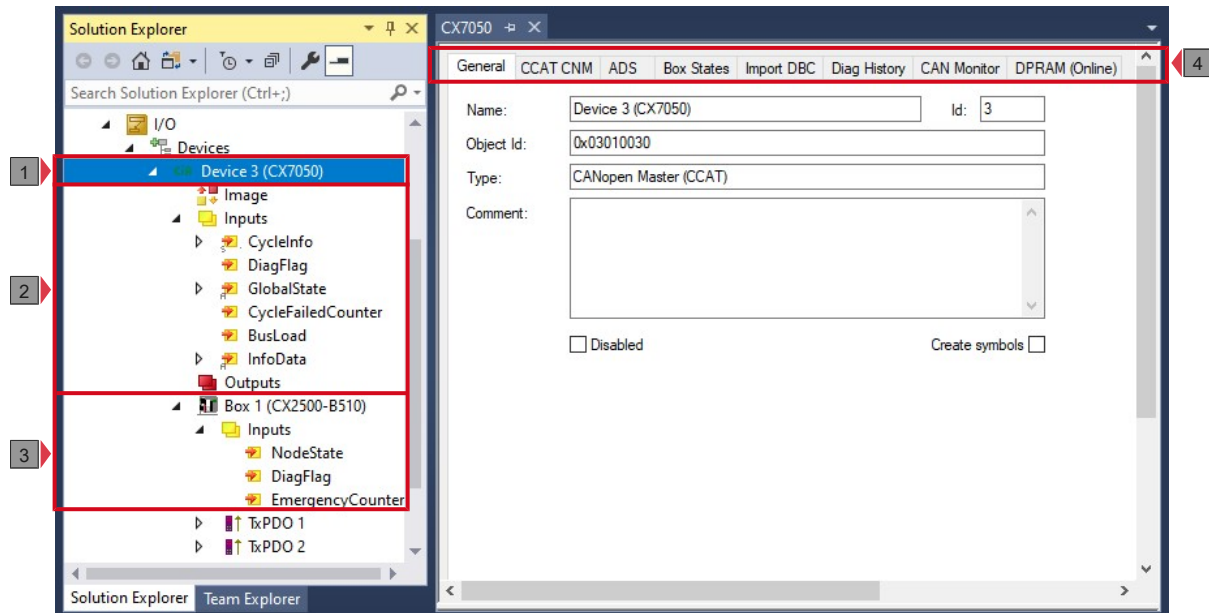


Fig. 38: CANopen master and CANopen slave in the TwinCAT tree view with tabs.

In this sample the slave was linked to the master. TwinCAT was then scanned for the master, and the master was created in TwinCAT together with the slave.

No.	Description
1	The device name of the master is shown in brackets. All CANopen slaves are added under the master.
2	Under the CANopen master, status messages are listed as input variables. The variables can be linked with the PLC and used for diagnostic purposes (e.g. error codes, counters, etc.).
3	CANopen slaves are added under the master, labeled as box and numbered consecutively. The device name appears in brackets after it. Each CANopen slave has its own input variables for diagnostic purposes, which indicate the state of the communication.
4	Further settings for the CANopen master or slave can be implemented under the tabs. Other tabs are displayed, depending on whether the master or slave is selected in the tree view.

A CANopen slave and the corresponding tabs are shown as follows in the tree view:

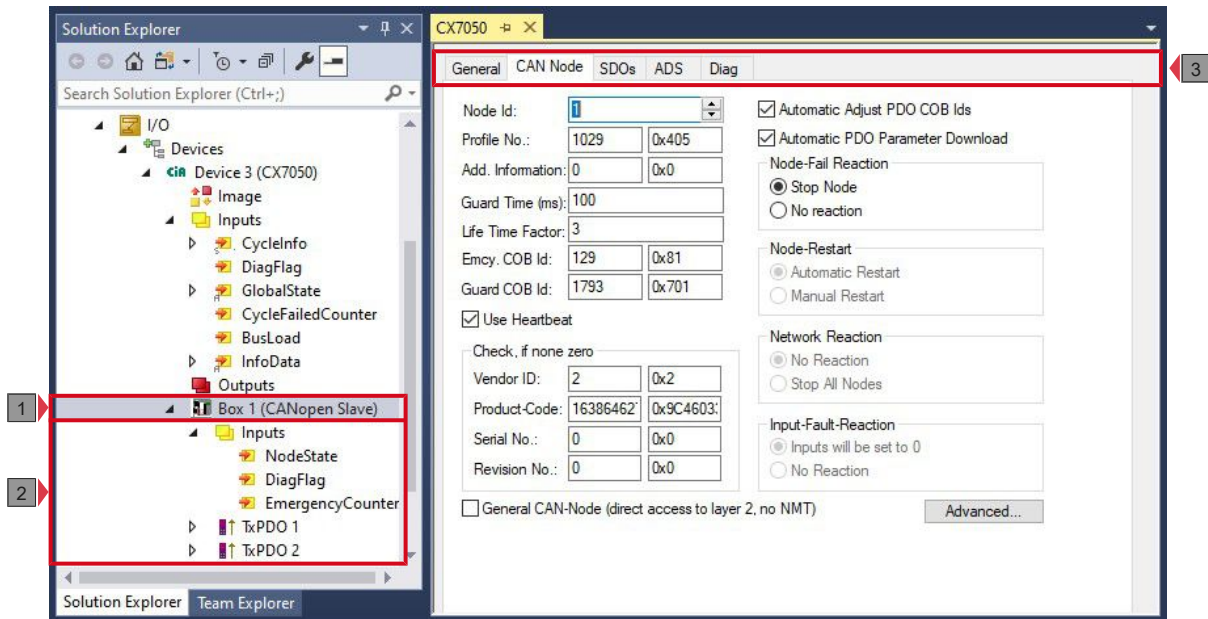


Fig. 39: CANopen slave in the TwinCAT tree view with associated tabs.

No.	Description
1	Under the CANopen slave, status messages are listed as input variables. The variables can be linked with the PLC and used for diagnostic purposes.
2	The process data objects (PDO) are displayed under the CANopen slave. At this point the variables for the data transmission are also created. The variables can be linked with the PLC. The data transfer direction is described from the perspective of the slave: <ul style="list-style-type: none"> • RxPDOs are received by the device. • TxPDOs are sent by the device.
3	Further settings for the CANopen slave can be implemented under the tabs. Other tabs are displayed, depending on whether slave or other entries are selected in the tree view.

When the PLC process image is read, the variables for status messages and the variables under the process data objects can be linked with the variables from the PLC program. Double-click on a variable name in the tree view to open the link dialog. The link variables are identified with a small arrow icon.

Further information about TwinCAT can be found in the TwinCAT documentation on the Beckhoff website: www.beckhoff.de

8.2.2 CANopen master

8.2.2.1 General

The General tab contains general information for a CANopen device, including name, type and ID.

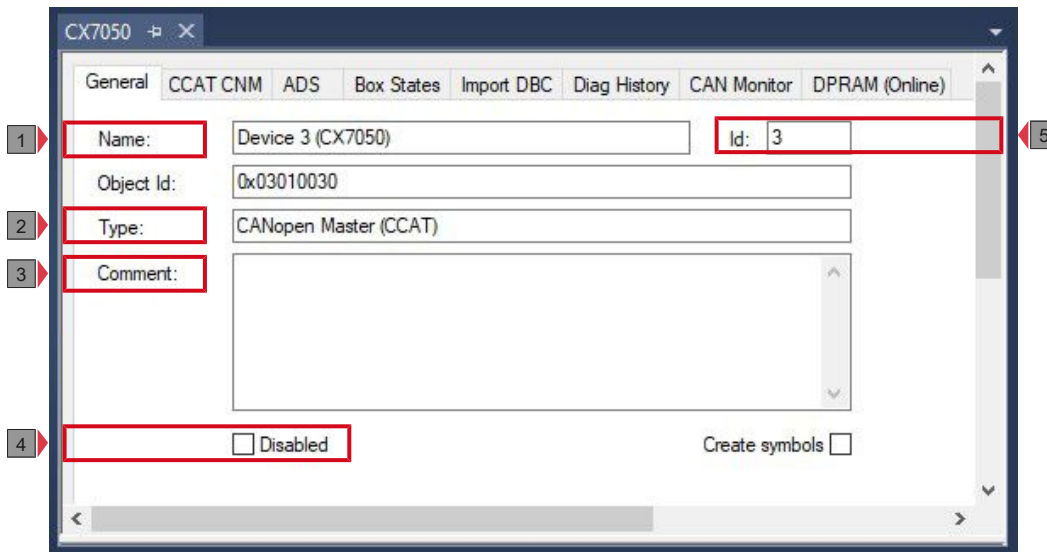


Fig. 40: General tab of a CANopen master in TwinCAT.

No.	Description
1	Name of the CANopen device
2	CANopen device type
3	Here you can add a comment (e.g. notes relating to the system component)
4	Here you can disable the CANopen device
5	Running No.

The CANopen device can be switched off via this tab. A comment box offers the option to add a label, in order to provide additional information on the device.

8.2.2.2 CCAT CNM

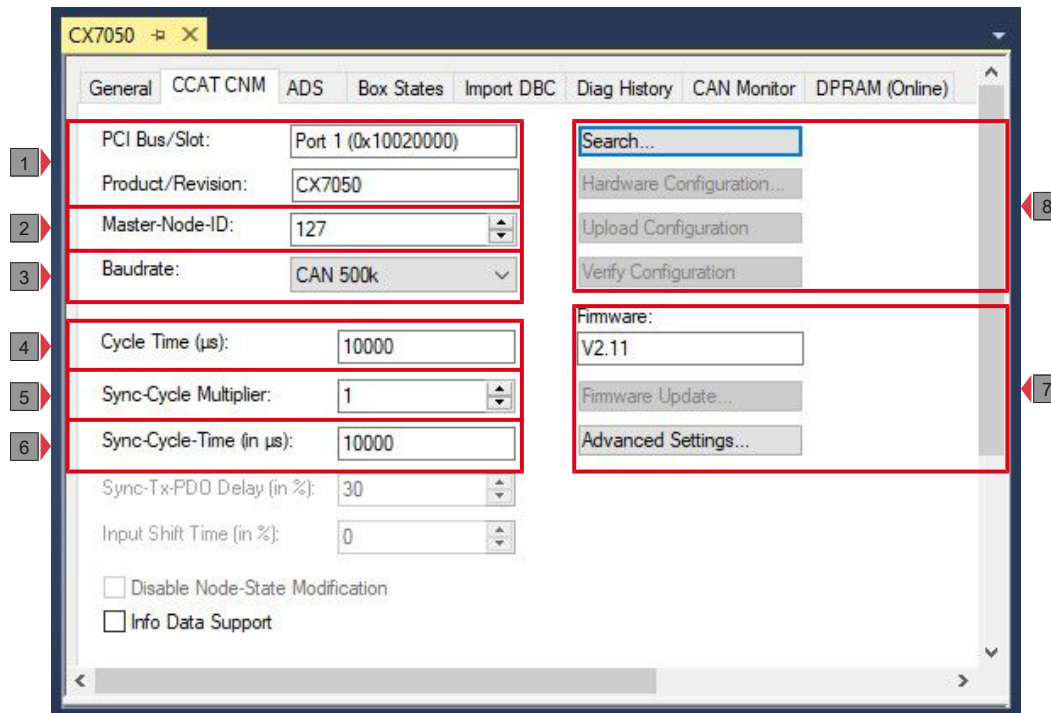


Fig. 41: CCAT-CNM tab of a CANopen master in TwinCAT.

No.	Description
1	Designation of the physical interface. Name and type of the CANopen device.
2	Name of the CANopen master. Range between 1 and 127. Determines the identifier of the master heartbeat telegram and must not match a slave node address.
3	The baud rate is set here. Automatically tests whether the connected slave supports this baud rate.
4	Displays the cycle time of the corresponding highest priority task.
5	With CANopen it is often the case that event-driven communication is combined with cyclic synchronous communication. In order to be able to respond to events quickly, the task cycle time must be less than the cycle time of the sync telegram. If the Sync-Cycle Multiplier is set to values > 1, the TwinCAT task is called repeatedly before the sync telegram is sent again.
6	The cycle time of the sync telegram is displayed here. It results from the cycle time of the highest priority task, its process data and from the Sync-Cycle Multiplier. Sync-Cycle-Time= Cycle Time x Sync-Cycle Multiplier
7	The current firmware version is displayed here.
8	The Search button is used to search for the physical interface and select the desired one, if not already done automatically.

8.2.2.3 ADS

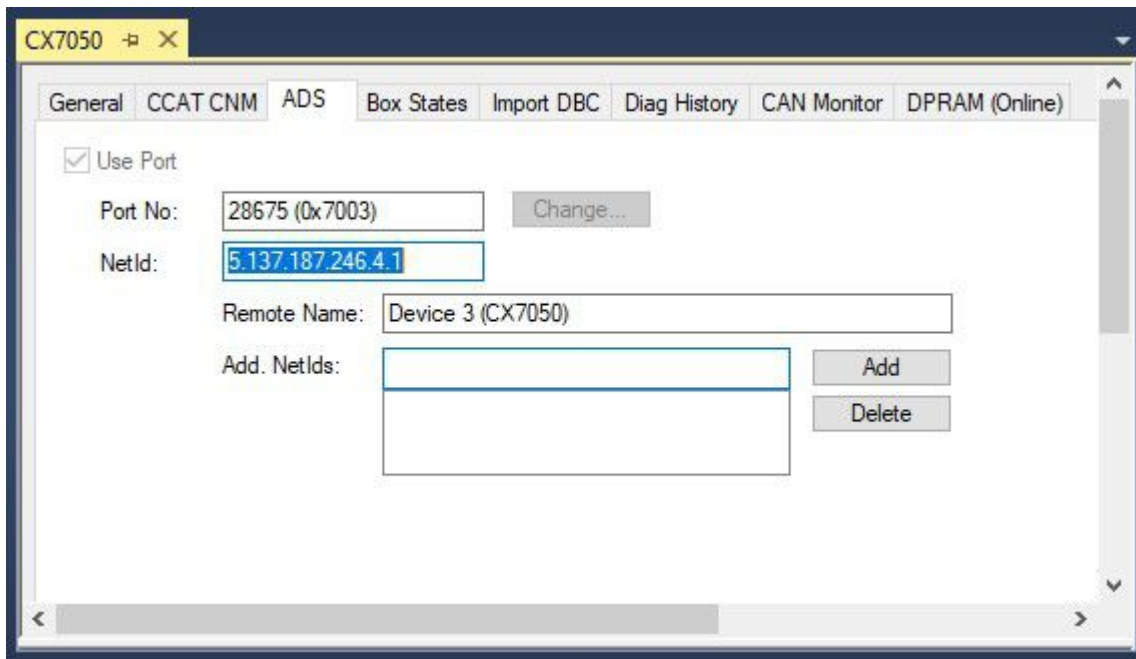


Fig. 42: ADS tab of a CANopen master in TwinCAT.

The CANopen master is an ADS device with its own Net ID, which can be modified here. All ADS services (diagnostics, acyclic communication) sent to the CANopen master must use this NetId and Port No.

8.2.3 CANopen slave

8.2.3.1 CAN node

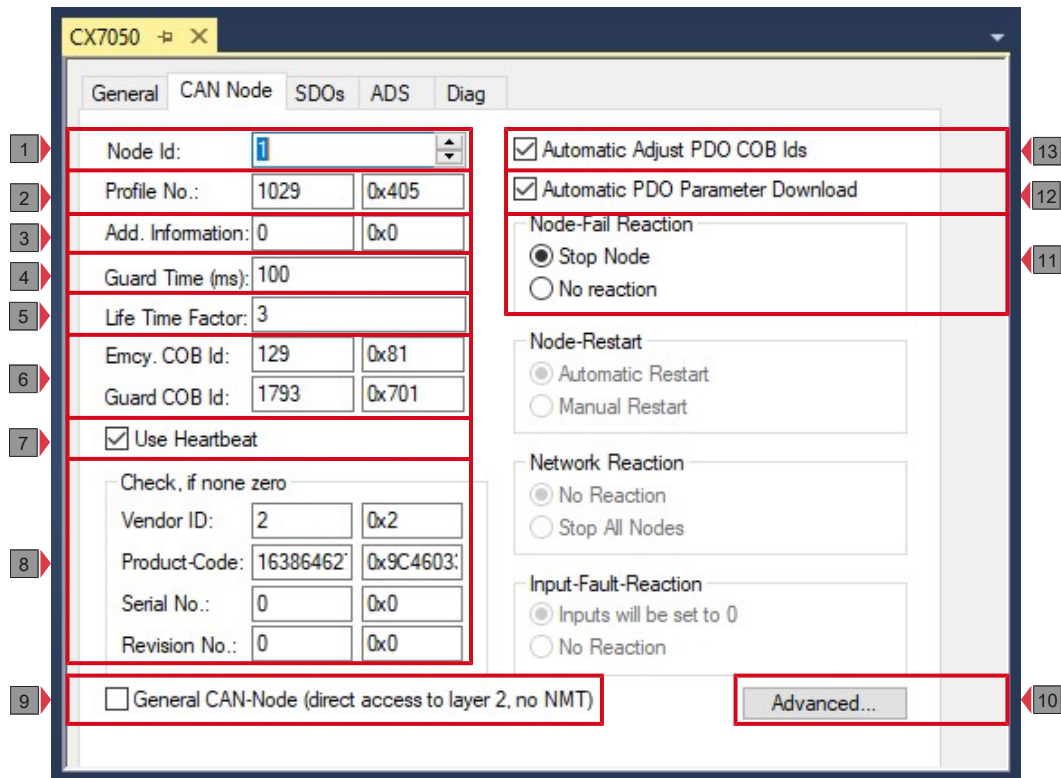


Fig. 43: CAN Node tab of a CANopen slave in TwinCAT.

No.	Description
1	The address is set here.
2	According to CANopen the parameter 0x1000 "Device Type" contains in the two least significant bytes the number of the device profile supported by the device. This number is entered here and compared with the parameter in the device on system startup. If no device profile is supported, the parameter will contain the value 0.
3	Add. Information: The Add. Information is in the two most significant bytes of the object dictionary entry 0x1000 (Device Type). The set/actual configuration comparison only takes place if Profile No. or Add. Information (i.e. object dictionary entry 0x1000) is set to a value that is not null. If the expected values do not match the actual values on system startup, the node start is aborted and a corresponding error message is displayed on the Diag tab.
4	Guard Time: The Guard Time determines the interval in which the node is monitored (Node Guarding). The value entered is rounded up to the next multiple of 10 ms. 0 signifies no monitoring.
5	Life Time Factor: Guard Time x Life Time Factor determines the watchdog length for the mutual monitoring of master and slave. The entry 0 means that the slave does not monitor the master. If 0 is entered, the master directly takes the guard time as watchdog length. The heartbeat protocol is also supported, and the system initially tries to initiate this form of node monitoring on the CANopen node. If this attempt fails, guarding is activated.
6	Emcy COB ID / Guard COB ID are identifiers for emergency messages or the guarding protocol. They result from the node address.

No.	Description
7	<p>Heartbeat is used for monitoring of the node. If heartbeat is disabled, guarding is used for monitoring.</p> <p>The guard time as producer heartbeat time and (guard time x lifetime factor) as consumer heartbeat time are entered. In this case a heartbeat telegram with the smallest configured guard time sent. The guard time can be set individually for each node.</p>
8	<p>If values other than zero are entered here, these identity object inputs (0x1018 in the object directory) are read off at the system StartUp and compared with the configured values. The corresponding node will be started only if the values coincide. It is also possible to compare only some of the values (e.g. the vendor ID and the product code). In this case, parameters that are not used must be set to zero.</p>
9	<p>If this option is selected, the entire CANopen network management is disabled for this device. It is not started, monitored, etc. The PDO entries are regarded as pure CAN telegrams (layer 2) and are made available to the controller on an event-driven basis.</p>
10	<p>Opens a window with further settings, which can be enabled:</p> <ul style="list-style-type: none"> • Switch off upload object 0x1000. • Switch off download object 0x1006. • Switch off automatic sending of start node (then has to be sent manually). • Continue to send start SDOs, in the event of a termination.
11	<p>The option StopNode is used to set the node to "stopped" state after a fault. It can be used to set nodes to a safe state, although they can no longer be addressed via SDO.</p>
12	<p>If the option is selected, entries are created automatically in TwinCAT, which are transferred via SDO on system startup (see: SDOs [► 147] tab).</p>
13	<p>If the option is selected, the default identifiers of the process data objects are automatically adjusted if the node ID changes (see: no. 6).</p>

8.2.3.2 SDOs

The SDO tab is used to display and manage entries, which are sent to the node on startup.

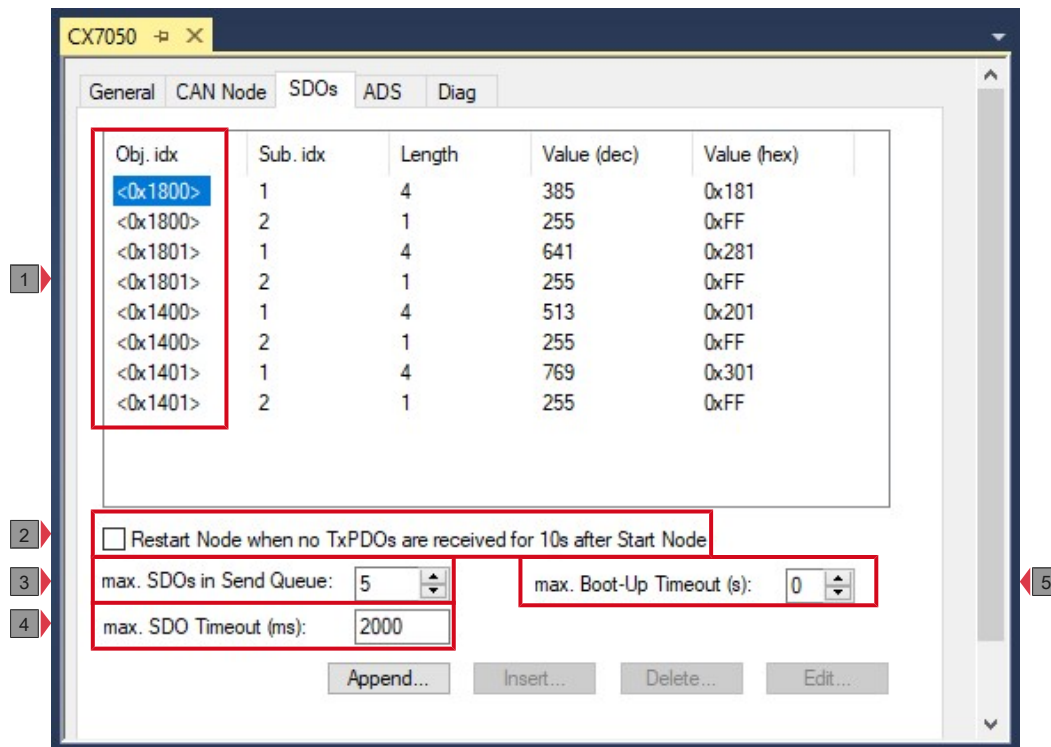


Fig. 44: SDO tab of a CANopen slave in TwinCAT.

No.	Description
1	Object index entries in angle brackets were created automatically based on the current configuration. Further entries can be created and managed via "Append", "Insert", "Delete" and "Edit".
2	If this option is selected, the slave is restarted if no TxPDO was received after 10 seconds.
3	This option can be used to set the maximum number of SDOs in the send queue.
4	The maximum timeout (ms) for the SDO is set here.
5	The boot-up timeout (s) is set here.

8.2.3.3 PDO

This tab appears if you click on a process data object (PDO) in the tree view.

Process Data Objects (PDOs) are CAN telegrams which transport process data without a protocol overhead.

- RxPDOs are received by the device.
- TxPDOs are sent by the device.

A device sends its input data with TxPDOs and receives the output data in the RxPDOs. This designation is retained in TwinCAT.

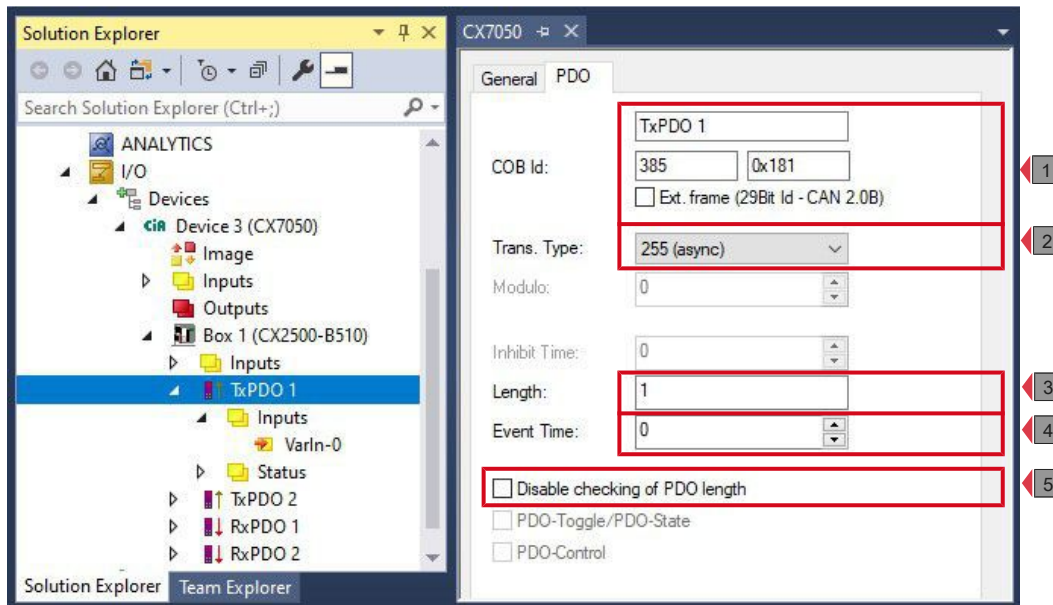


Fig. 45: PDO tab of a CANopen slave in TwinCAT.

No.	Description
1	CAN identifier of the PDO. For two send and receive PDOs per node, CANopen provides Default Identifiers. These can then be changed.
2	The Transmission Type determines the send behavior of the PDO. 255 corresponds to the event-driven sending (see: Setting the transmission type).
3	The length of the PDO depends on the created variables and can therefore not be edited here.
4	Enter the value for the Event Timer in ms. For send PDOs (RxPDOs), PDOs are sent again after a timer has elapsed. For receive PDOs (TxPDOs), the arrived PDOs are monitored, and the box state of the node may be modified. TwinCAT creates corresponding inputs in the node object directory on the basis of the parameters entered here. These are transferred via SDO at the system start. The entries can be viewed in the SDO tab (see: SDOs [► 147]). This function can be disabled via the checkbox Automatic PDO Parameter Download on the CAN Node tab (see: CAN node [► 145]).
5	The PDO length check can be disabled here.

8.3 Creating CX7050 as master

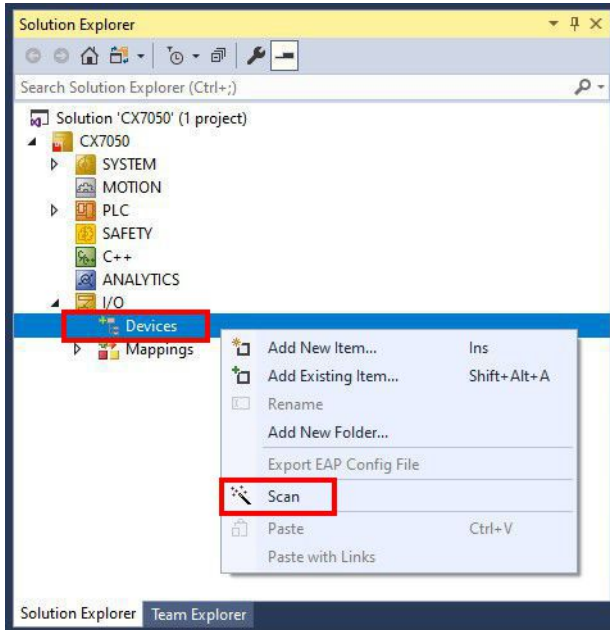
If the CX7050 is to be created as a CANopen master, it can be scanned for the device in TwinCAT and additionally all slaves connected in it can be created automatically. The following section illustrates how to create a CANopen master in TwinCAT.

Requirements for this step:

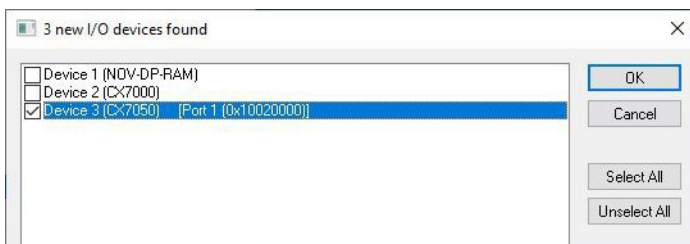
- TwinCAT must be in Config mode.
- A selected target system.

Create the CANopen device as follows:

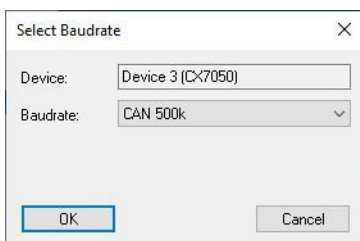
1. In the tree view on the left, right-click on **Devices**.
2. In the context menu click **Scan**.



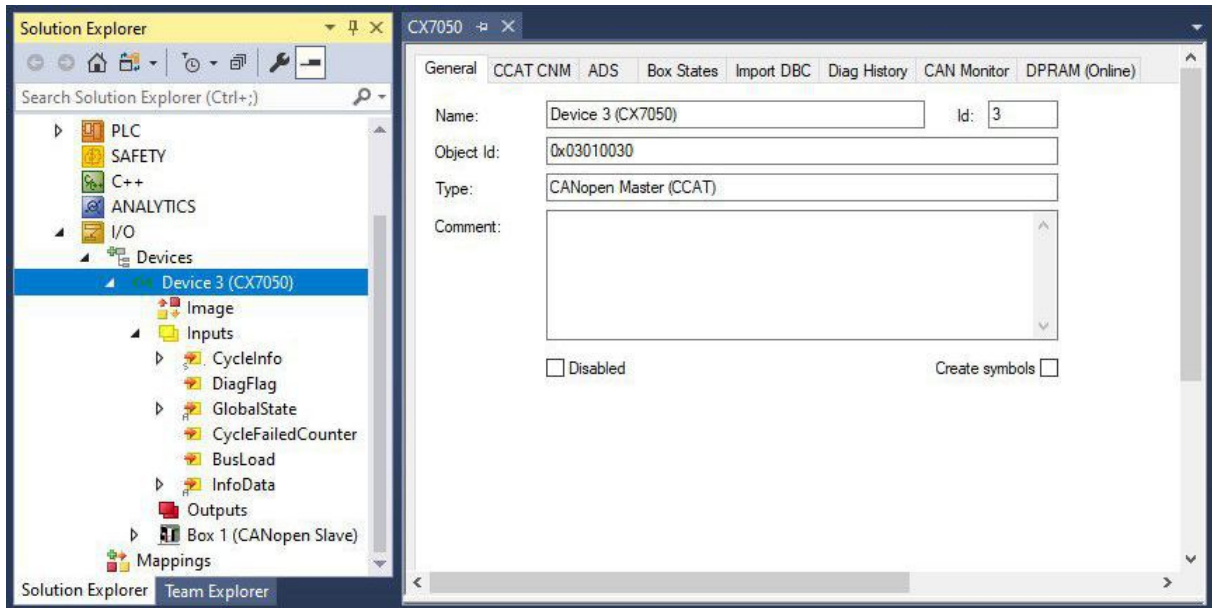
3. Select the devices you want to use and confirm the selection with **OK**.



4. Confirm the request with Yes to search for boxes.
The window **Select Baudrate** appears.
5. Under Baudrate select the appropriate baud rate for the CANopen master.



⇒ All found devices and slave boxes are displayed in the tree view on the left. The bus terminals connected to the devices or slave boxes are also displayed.



Repeat the steps if not all devices are displayed. If not all devices and slave boxes are found despite the repeat operation, check the cabling of the devices and slave boxes.

8.3.1 SDO communication from the PLC

ADS blocks are used for SDO communication from the PLC. These function blocks can be used for sending SDO telegrams and receiving the response of the slave (ADSWRITE/ADSREAD).

Input parameters	Description
NETID	ADS NetID of the CAN interface
Port number	0x1000 _{hex} + NodeId (slave number)
IDXGRP	SDO Index
IDXOFFS	SDO Subindex
LEN	Length of SDO data (1...4)

Manual network management

The CANopen state (STOPPED, PRE-OPERATIONAL, OPERATIONAL) of a CANopen slave can be changed via ADS write control. In this case the AMS address should be set as for SDO communication. The other parameter are listed in the following table:

ADS State	Device State	CANopen state transition
ADSSTATE_RUN (5)	0	OP->PREOP
ADSSTATE_RUN (5)	1	PREOP->OP
ADSSTATE_STOP (6)	0	OP->STOP
ADSSTATE_RUN (5)	1	STOP->OP (with communication reset)
ADSSTATE_RUN (5)	3	STOP->OP (without communication reset)
ADSSTATE_STOP (6)	0	PREOP->STOP
ADSSTATE_RUN (5)	2	STOP->PREOP (without communication reset)

Restarting the CAN interface

The ADSWRTCTL function block can be used to stop and restart the CAN interface. It should be stopped first before restarting it.

Input parameters	Description
NETID	ADS NetID of the CAN interface
Port number	200 _{dec}
ADSSTATE	ADSSTATE_STOP, ADSSTATE_RUN
DEVSTATE	0
LEN	0
SRCADDR	0

8.3.2 CAN interface

Almost all CANopen masters from Beckhoff offer the so-called CAN interface. The CAN interface is a Layer-2 implementation of the CAN interface. It enables any desired CAN telegrams to be received and transmitted. The higher-level protocol is not important here, i.e. all CAN-based protocols can be used; however the protocol part must then be implemented in the PLC.

A detailed description of the CAN interface can be found at:

https://download.beckhoff.com/download/document/io/infrastructure-components/can-interface_en.pdf

Any CAN data can be sent via the CAN interface. There is a choice between 11-bit identifier (CAN 2.0A) or 29-bit identifier (CAN 2.0B).

Message structure with 29-bit support

- Length (0..8)
- Cobld
 - Bit 0-28: 11-bit identifier / 29-bit identifier

- Bit 30: RTR
- Bit 31: 0: normal message (11-bit identifier), 1: extended message (29-bit identifier)
- Data[8]

Send data: In "NoOfTxMessages" enter the number of data you want to send from the Tx buffer. If the buffer has capacity for 10 entries, the maximum number of telegrams that can be send consecutively is 10.

"Length" defines the number of PDO data bytes (maximum 8 bytes). Fill in the data and enter the identifier of the CAN message in "codId". Now increment the TxCounter value.

Sample code: Sending messages from the PLC

```
if Outputs.TxCounter = Inputs.TxCounter then
  for i=0 to NumberOfMessagesToSend do
    Outputs.TxMessage[i] = MessageToSend[i];
  End_for
  Outputs.NoOfTxMessages = NumberOfMessagesToSend;
  Outputs.TxCounter := Outputs.TxCounter + 1;
end_if
```

Sample code: Receiving messages from the PLC

```
if Outputs.RxCounter <> Inputs.RxCounter then
  for i := 0 to (Inputs.NoOfRxMessages-1) do
    MessageReceived[i] := Inputs.RxMessage [i];
  End_for
  Outputs.RxCounter := Outputs.RxCounter+1;
end_if
```

8.4 Creating CX705x as slave

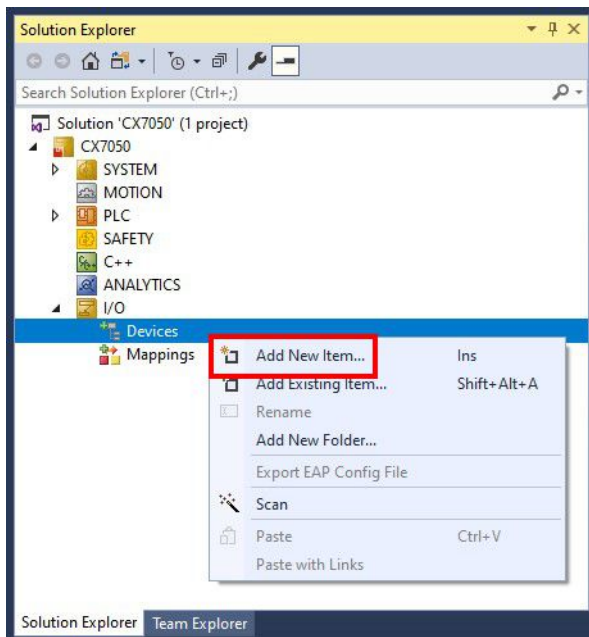
This section shows how to create a CX7050 as CANopen slave. In order for the CANopen slave to be recognized later by a CANopen master with all inputs and outputs, the CANopen slave must first be created in TwinCAT and configured with all associated PDOs and variables.

Requirements for this step:

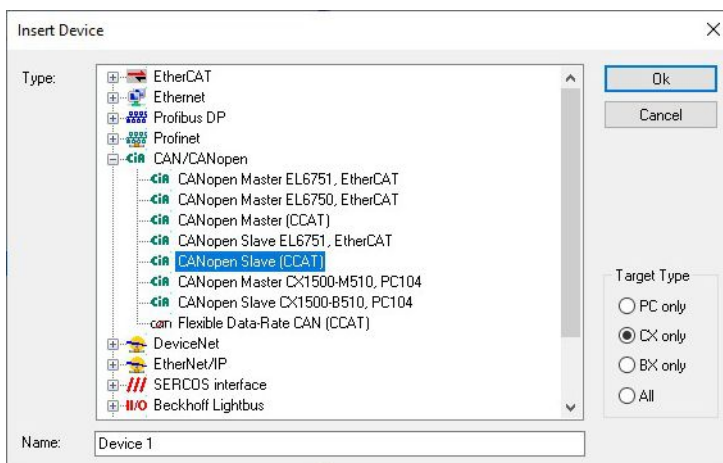
- CX7050 selected as target device.

Create the CANopen slave as follows:

1. In the tree view on the left, right-click on **Devices**.
2. In the context menu click **Add New Item**.

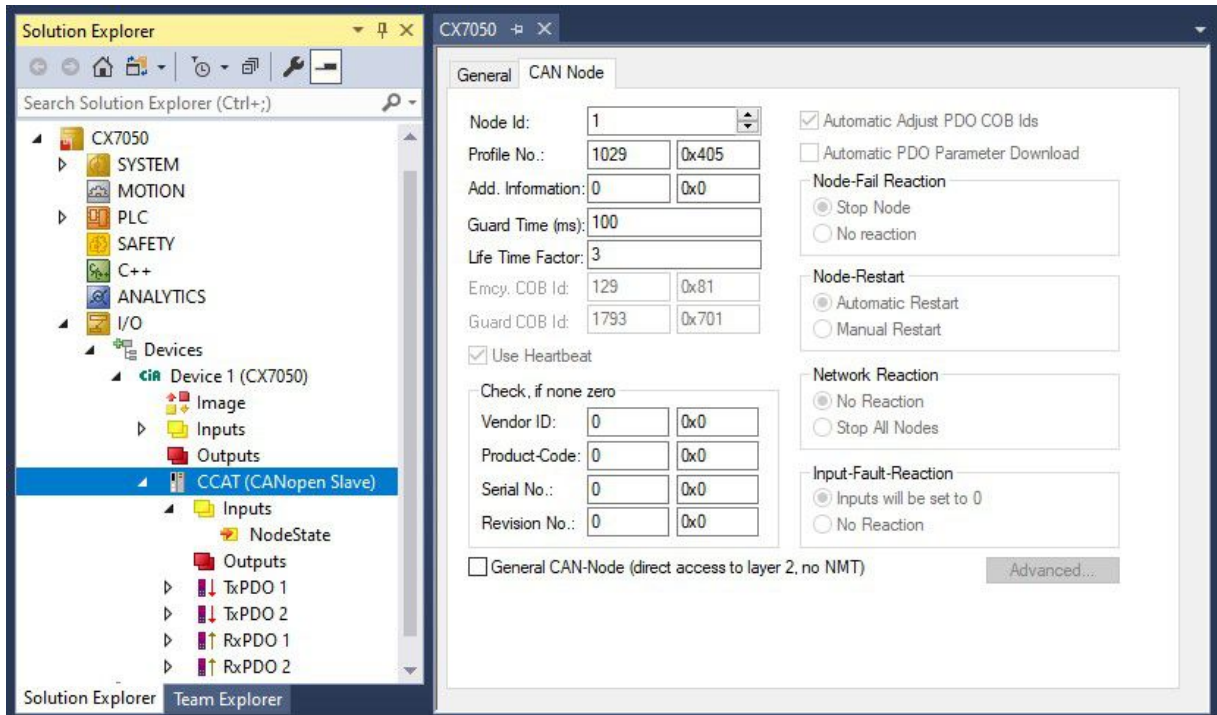


3. Select as device **CANopen Slave (CCAT)** and confirm the selection with **OK**.



4. Confirm the request with Yes, in order to look for boxes.

⇒ The CANopen slave has been successfully added in TwinCAT and is displayed in the tree view with the inputs and outputs.



In the next step you can extend the process image by creating additional virtual slaves. Or you can set the address, once the slave configuration is complete.

8.4.1 Creating a virtual slave

Additional virtual slaves can be created on the same hardware interface. This enables more data to be exchanged with a CANopen master, or a connection with a second CANopen master can be established. Up to three virtual slaves can be created on the same hardware interface of a slave.

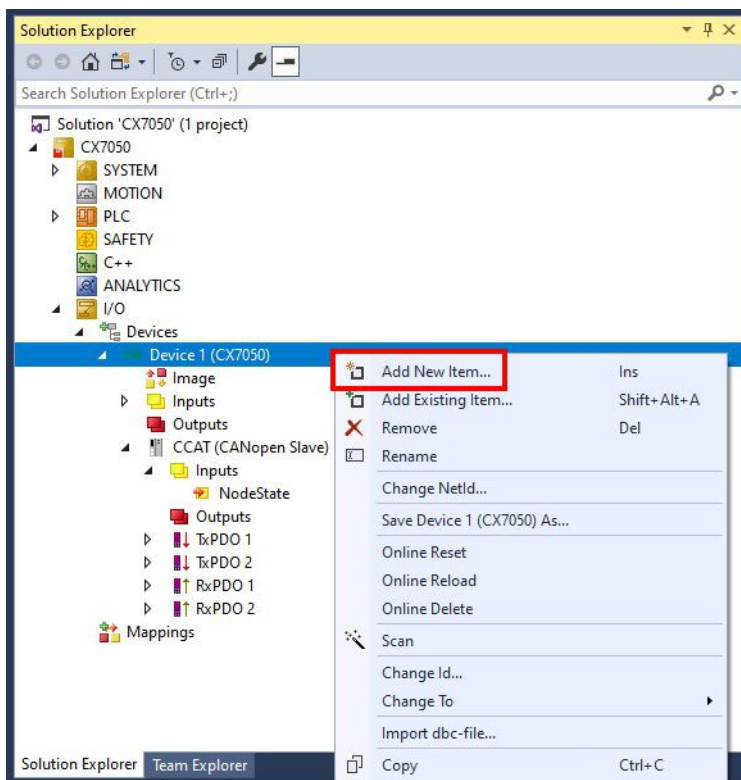
Because a maximum of 16 PDOs can be configured for each slave, the additional three virtual slaves increase the maximum possible number of PDOs to 4 x 16 PDOs in each send direction. Each virtual slave is assigned a dedicated address via TwinCAT and is configured like an independent device for the CANopen master.

Requirements for this step:

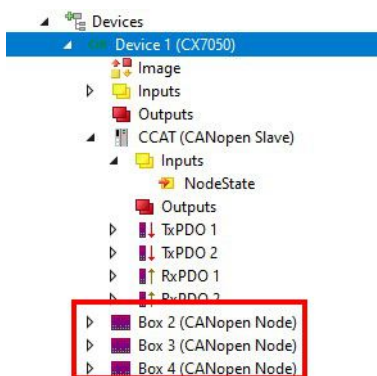
- A CANopen slave, created in TwinCAT.

Create a virtual slave as follows:

1. Right-click on a CANopen slave in the tree view on the left.
2. In the context menu click **Add New Item**.



⇒ Another box (virtual slave) is created.



Own variables can now be created for the virtual slave. In the next step you can set the address for the slave.

8.4.2 Setting the address

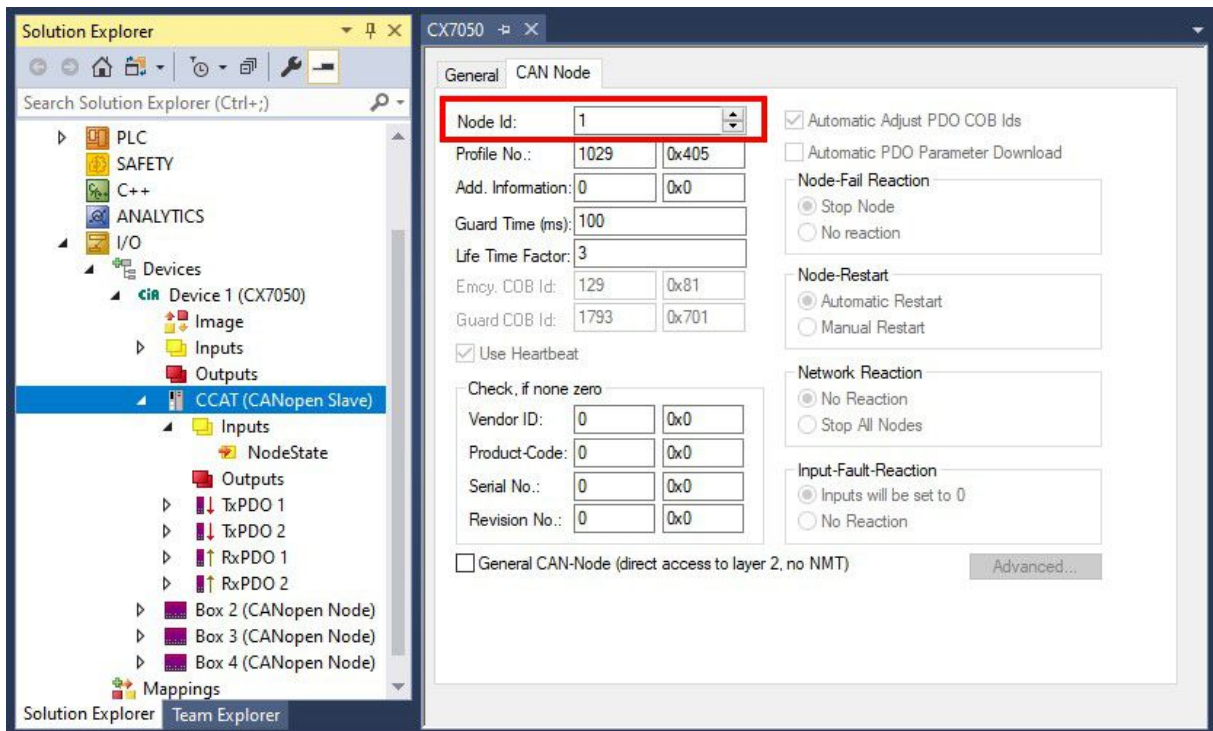
Once the CANopen slave was successfully added in TwinCAT, the address of the CANopen slave can be set. This step shows how to set the address in TwinCAT so that the CANopen slave can be reached by the CANopen master via this address.

Requirements for this step:

- An added CANopen slave in TwinCAT.

Parameterize the CANopen slave as follows:

1. Click on a slave box.
2. Click the **CAN Node** tab.
3. Enter a value for the CANopen address in the **Node Id** field, e.g. "1".



⇒ You have set the address successfully. The CANopen master can reach the CANopen slave with the set address. You can now create further PDOs.

8.4.3 Creating further PDOs

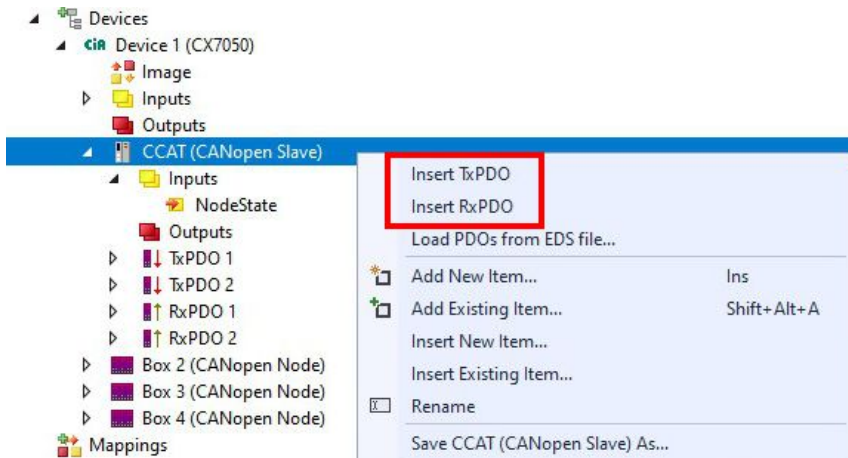
The CANopen slave can exchange up to 16 PDOs (each with 8 bytes of process data) with the CANopen master in input and output direction. By default 2 PDOs are created in Tx and Rx direction. Here we shown how to create further PDOs for a CANopen slave.

Requirements for this step:

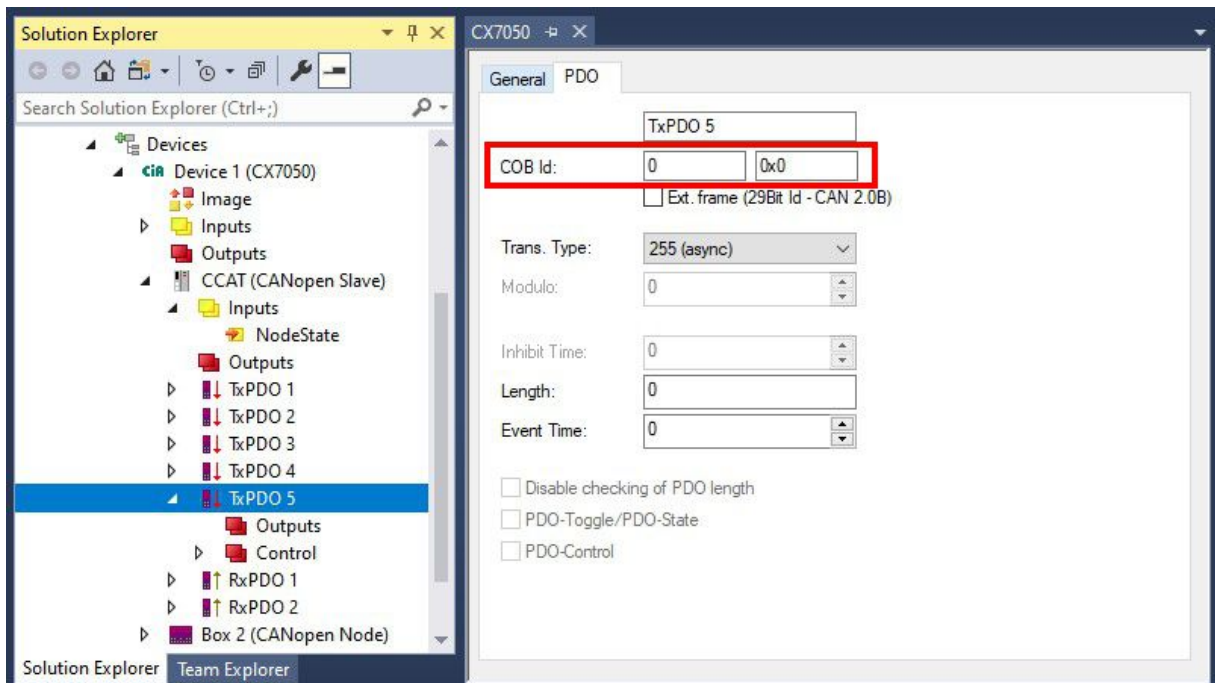
- A CANopen slave added in the tree view.

Create the PDOs as follows:

1. Right-click on a CANopen slave in the tree view.
2. Click in the context menu on **Insert TxPDO** or **Insert RxPDO** to create PDOs in Tx or Rx direction.



The new TxPDOs or RxPDOs are inserted under the already created PDOs and numbered consecutively in the tree view. **Notice** From the fifth PDO in Tx or Rx direction the COB Id is no longer entered automatically (see the following figure).



3. From the fifth PDO in Tx or Rx direction click on the **PDO** tab.
 4. Enter the desired value in the **COB Id** field.
- ⇒ You have successfully created further PDOs; in the next step you can create variables for the data exchange under the PDOs.

8.4.4 Creating variables

In TwinCAT the PDOs are filled with variables, which can later be linked with the PLC program. A maximum of 8 bytes of data can be created under the corresponding PDOs. It is also allowed to use different variable types, only the limit of 8 bytes per PDO must be observed.

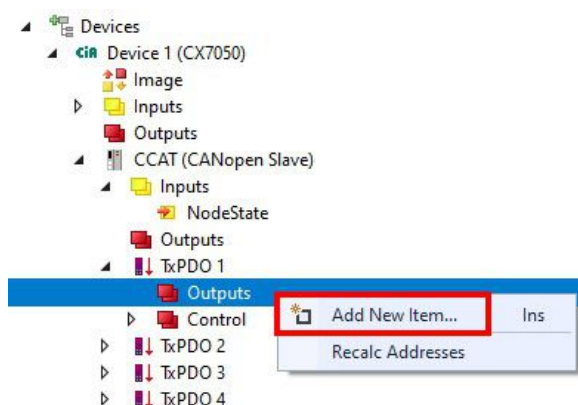
If it is not configured differently in the master, the data is sent automatically with every change. At the planning stage please ensure that the data in a PDO "only" change at a moderate rate (e.g. not with ms frequency). Failure to adhere to this can lead to CAN overload. If this is not observed, the CAN can be overloaded, which can happen quickly, especially at low baud rates.

Requirements for this step:

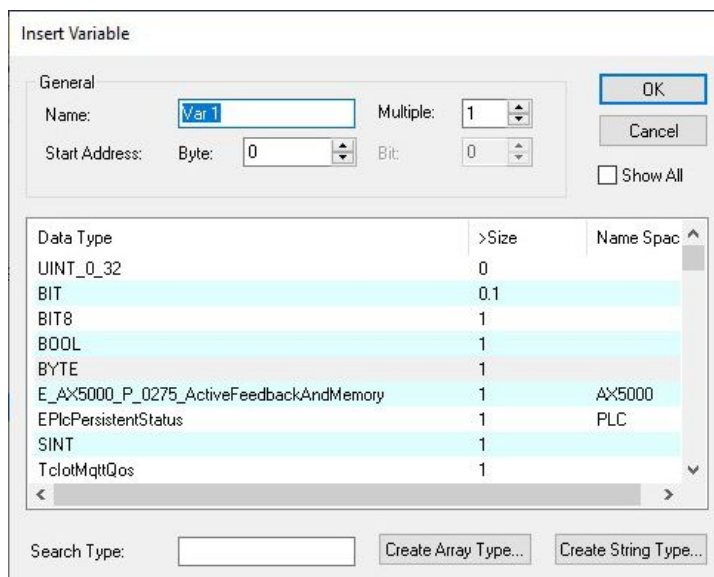
- Newly created PDOs, which are to be filled with variables.

Create the variables as follows:

1. In the tree view click on a TxPDO or RxPDO to show more information.
2. Right-click on Outputs or Inputs, depending on whether a TxPDO or RxPDO is selected.



3. Click **Add New Item** in the context menu. The **Insert Variable** window appears.
4. Click on the appropriate variable and click **OK**.



- ⇒ You have successfully created a variable. The new variable is shown in the tree view on the left. In this way you can add further variables for the CANopen slave. In the next step you can specify the transmission type, thereby specifying how the process data objects are transferred.

8.4.5 Setting the transmission type

The transmission type determines how the process data objects are transferred. The transmission type for the RxPDOs and TxPDOs is set on the PDO tab.

The available transmission types are: acyclic synchronous, cyclic synchronous and asynchronous.

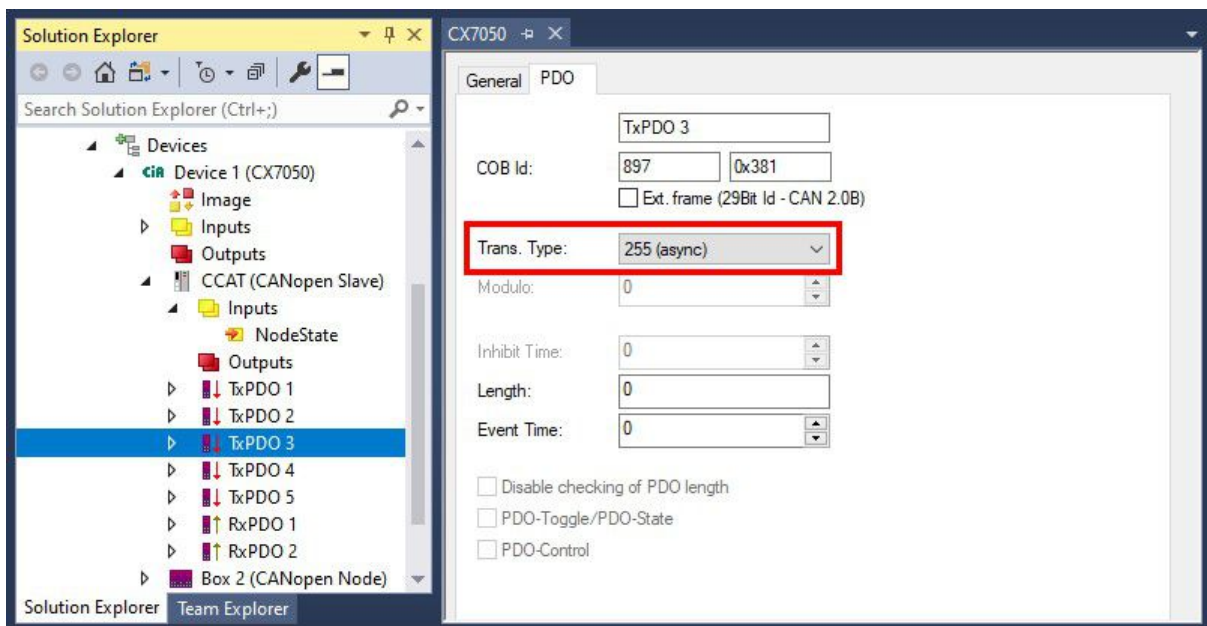
Transmission type:	Acyclic Synchronous	Cyclic Synchronous	Asynchronous
Name in TwinCAT:	(acyc, sync)	(cyc, sync)	(async)

Requirements for this step:

- A CANopen slave with process data objects (PDO) added in TwinCAT

Specify the transmission type as follows:

1. In the tree view, left-click on a process data object (PDO).
2. Click the **PDO** tab.
3. Select the required transmission type under **Trans. Type**.



⇒ You have successfully specified a transmission type for a process data object. The transmission types for the remaining process data objects are specified in the same way. Next, you can create a PLC project for the CANopen slave.

8.4.6 Receiving SDO data in the PLC

SDO data that are unknown to the CANopen part of the software and cannot be processed automatically are transferred to the PLC, where they are evaluated and answered via ADS notification.

To this end the ADS port must be enabled in the System Manager under CAN device.

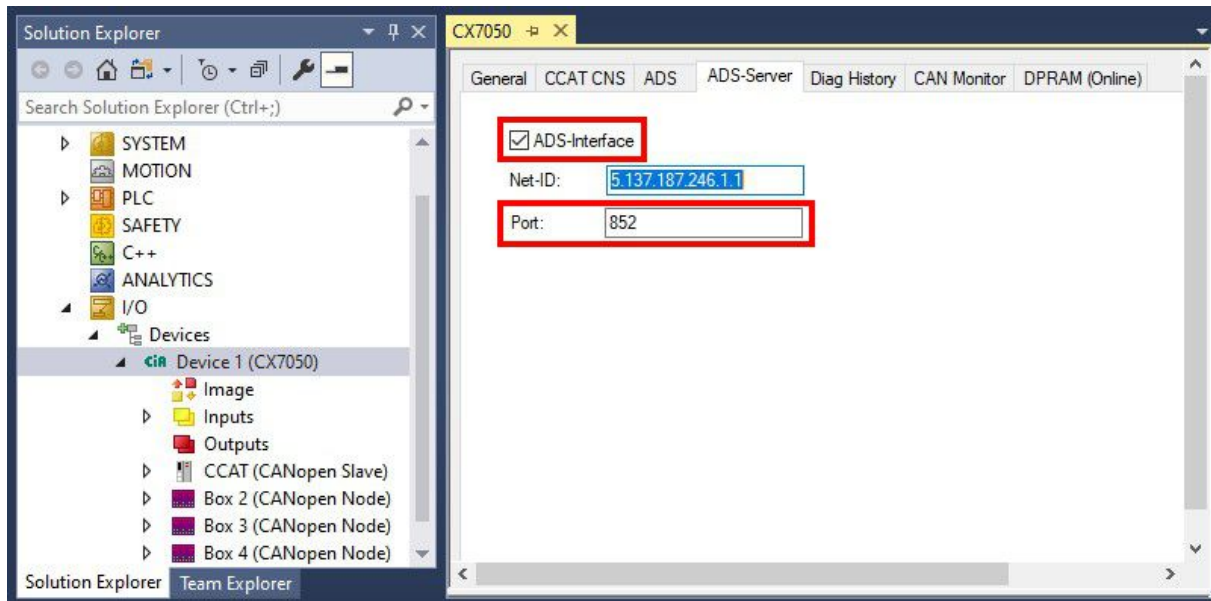


Fig. 46: Enabling of an ADS port for a CANopen slave.

SDO Read request

Data to be read must be received with ADSREADIND and answered with ADSREADRES.

Input parameter ADSREADIND	Description
NETID	NetID of the CAN interface
Port number	0x1000 _{hex} + Node number
IDXGRP	16#8000_0000 + SDO Index (IDXGRP.31 = ADS-Notification)
IDXOFFS	SDO Subindex
LEN	not required for reading

You now have to respond to the ADS indication with an ADS Read response.

Input parameter ADSREADRES	Description
NETID	NetID of the CAN interface
Port number	0x1000 _{hex} + Node number
INVOKEID	INVOKEID of the ADSREADIND function block
RESULT	Error <> 0, error-free = 0
LEN	Length of the data

SDO Write request

Data to be written must be received with ADSWRITEIND and answered with ADSWRITERES.

Output parameter ADSWRITEIND	Description
NETID	NetID of the CAN interface
Port number	0x1000 _{hex} + Node number
IDXGRP	16#8000_0000 + SDO Index (IDXGRP.31 = ADS Notification)
IDXOFFS	SDO Subindex

Output parameter ADSWRITEIND	Description
LEN	Number of received data in bytes

You now have to respond to the ADS indication with an ADS Write Response.

Input parameter ADSWRITERES	Description
NETID	NetID of the CAN interface
Port number	0x1000 _{hex} + Node number
INVOKEID	INVOKEID of the ADSWRITEIND function block
RESULT	Error <> 0, error-free = 0

8.4.7 Switching slave node to PreOp from the PLC

The ADSWRTCTL block can be used to set individual CANopen nodes to pre-operational or operational state. A fixed baud rate is required for this purpose.

Input parameters	Description
NETID	NetId of the CAN interface
Port number	0x1000 _{hex} + NodeId (slave number)
ADSSTATE	ADSSTATE_RUN
DEVSTATE	0 - Pre / 1 - Operational
LEN	0
SRCADDR	0

8.5 Reading the CAN baud rate

The baud rate can be displayed and evaluated via the variable InfoData[1]. This can be helpful for slaves with AutoBaud, if for example the communication is not running. This can be used to check whether the correct baud rate has been set with AutoBaud.

NodeState value	Description
0x01040400	1 Mbaud
0x01040600	800 kbaud
0x01040C00	500 kbaud
0x010A0C00	250 kbaud
0x01160C00	125 kbaud
0x011C0C00	100 kbaud
0x013A0C00	50 kbaud
0x01940C00	20 kbaud
0x01941A10	10 kbaud

8.6 Sending arbitrary CAN telegrams

The ADSWRITE command can be used to send any CAN message.

Input parameters	Description
NETID	NetId of the CAN interface
Port number	200
IDXGRP	16#0000F921
IDXOFFS	0
LEN	11 bytes
SRCADDR	Pointer to an 11 byte ARRAY

Table 17: Structure of the 11 byte CAN data

Byte	Description	Example Node 7 SDO 0x607 Len 8 Download Request 0x2100 (Index) Sub Index 1 - Value "1"
1	COB-ID LowByte	0x06 (SDO Low Byte)
2	COB-ID HighByte	0x07 (SDO High Byte)
3	LEN (length)	0x08 (LEN, may be 5 in this case)
4	Data[1]	0x22 (Download Request)
5	Data[2]	0x00 (Index Low Byte)
6	Data[3]	0x21 (Index High Byte)
7	Data[4]	0x01 (Sub Index)
8	Data[5]	0x01 (Value "1")
9	Data[6]	0x00
10	Data[7]	0x00
11	Data[8]	0x00

8.7 Reading the IP and MAC addresses

This sample shows you how to read the IP and MAC addresses. The function block FB_MDP_NIC_Read can be used to retrieve information from the network adapter.

Sample

```

Var
  FB_MDP_NIC_Read      : FB_MDP_NIC_Read;
END_VAR

PROGRAM:
FB_MDP_NIC_Read(
  bExecute:=TRUE ,
  tTimeout:= ,
  iModIdx:= ,
  sAmsNetId:= ,
  bBusy=> ,
  bError=> ,
  nErrID=> ,
  iErrPos=> ,
  stMDP_ModuleHeader=> ,
  stMDP_ModuleContent=> );

```

The output stMDP_ModuleHeader displays the header information. The output stMDP_ModuleContent displays, among other things, the information about the IP and MAC addresses.

stMDP_ModuleHeader	ST_MDP_ModuleHea...
iLen	UINT 4
nAddr	DWORD 131072
sType	T_MaxString 'Nic'
sName	T_MaxString 'st'
nDevType	DWORD 141072
stMDP_ModuleContent	ST_MDP_NIC_Prope...
iLen	UINT 8
sMACAddress	T_MaxString '00:01:05:5f:0f:7a'
sIPAddress	T_MaxString '169.254.123.15'
sSubnetMask	T_MaxString '255.255.0.0'
bDHCP	BOOL TRUE
iReserved	BYTE 0

Fig. 47: Content of the MDP module with IP and MAC address.

8.8 Virtual Ethernet interface

The virtual Ethernet interface integrates network adapters into the TwinCAT system. This makes it possible to establish a virtual Ethernet communication via ADS, TCP or UDP to a BK9xx0. Do not use more than two BK9xx0 and a cycle time > 50 ms.

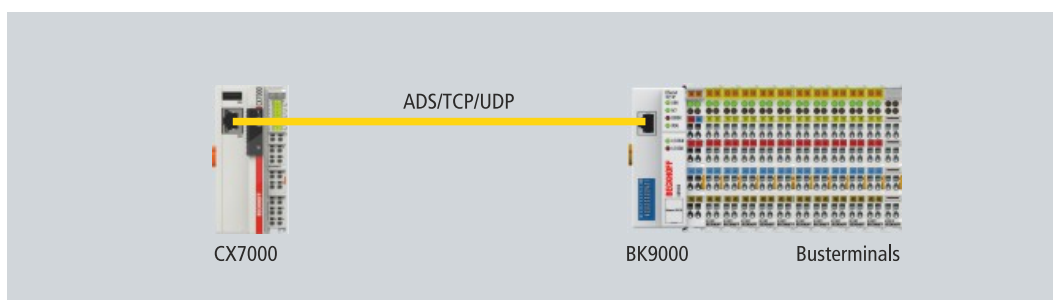
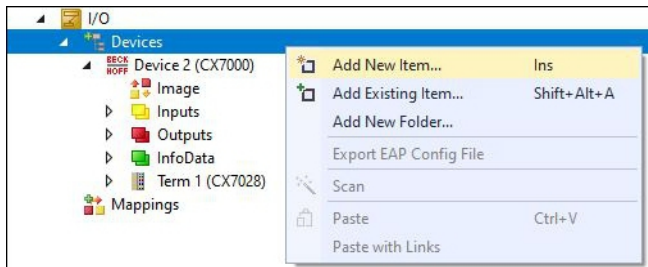


Fig. 48: Virtual Ethernet communication via ADS, TCP or UDP.

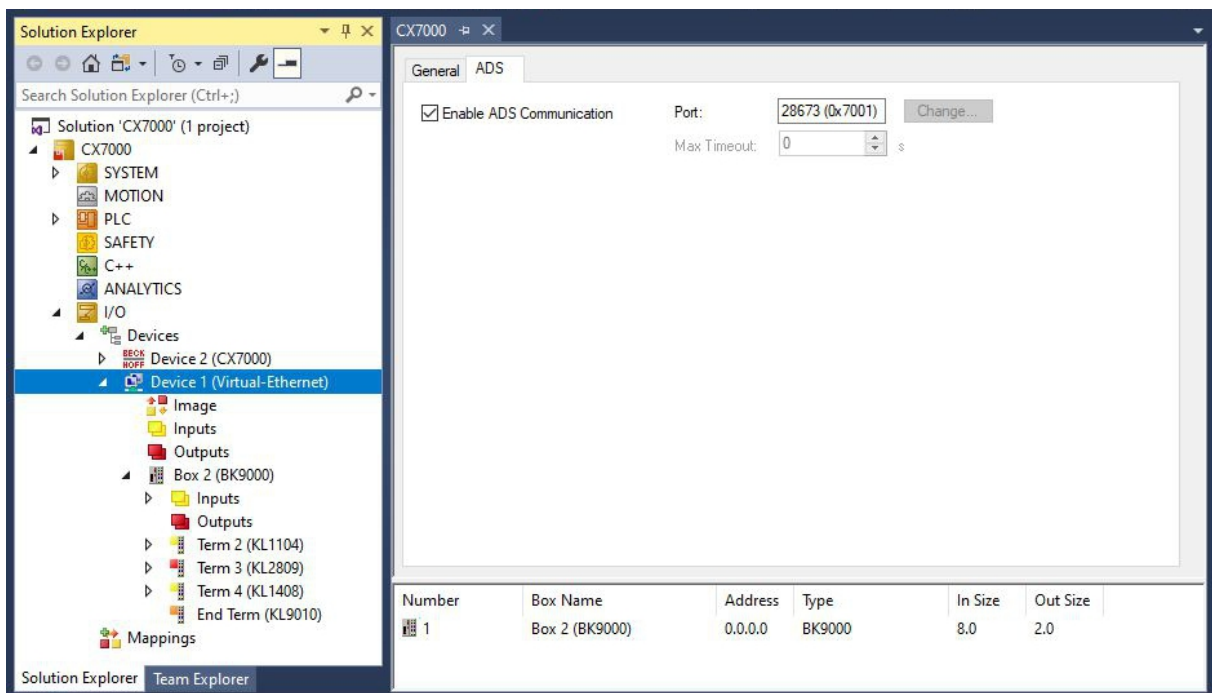
Proceed as follows:

1. In the tree view on the left, right-click on **Devices**.



2. Click on **Add New Item** and select the **Virtual Ethernet Interface**.

⇒ The Virtual Ethernet Interface is created in the tree view on the left. The ADS port number can be read out under the **ADS** tab. The **Enable ADS Communication** option must be active so that ADS communication to the BK9xx0 is possible.



8.9 CoE access to multi-function I/Os

The `FB_EcCoeSdoReadEx` function block allows data to be read from an object directory of an EtherCAT slave via SDO data (Service Data Object). The `nSubIndex` and `nIndex` parameters allow the object that is to be read to be selected. Via `bCompleteAccess := TRUE` the parameter can be read with subelements.

Sample: Read the firmware version of the multi-function I/Os.

```
VAR
AMSNetID AT %I*:T_AmsNetIdArr;
Port AT %I*:T_AmsPort;
FB_EcCoeSdoReadEx: FB_EcCoeSdoReadEx;
FirmwareVersion: STRING;
END_VAR
```

The `AmsNetId` and `port` number are required for communication with the CX7028 interface. The inputs of the function block `FB_EcCoeSdoReadEx` can be linked with the input variables `netId` and `port` under TwinCAT, so that the function block is permanently connected to the CX7028 interface.

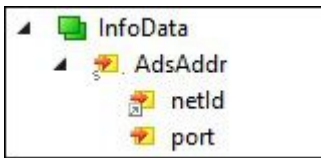


Fig. 49: CoE access to multi-function I/Os, input variables "netId" and "port" under TwinCAT.

The input `sNetId` of the function block corresponds to the input `netId` under TwinCAT. The function block requests a string and the link returns a byte array. You can convert the byte array to a string using the `F_CreateAmsNetId` function. The input `nSlaveAddr` corresponds to the input `port` under TwinCAT.

```
FB_EcCoESdoReadEx(
sNetId:=F_CreateAmsNetId(nIds:=AMSNID) , (* AmsNetId of the CX7028 Interface *)
nSlaveAddr:=Port , (* Port Number(nSlaveAddr): 0x1000 *)
nSubIndex:= ,
nIndex:=16#100A , (* Index Number *)
pDstBuf:=ADR(FirmwareVersion) ,
cbBufLen:=SIZEOF(FirmwareVersion) ,
bExecute:=TRUE ,
tTimeout:= ,
bCompleteAccess:= ,
bBusy=> ,
bError=> ,
nErrId=> );
```

The index number for the CoE object **Software version** is located under the CoE Online tab.

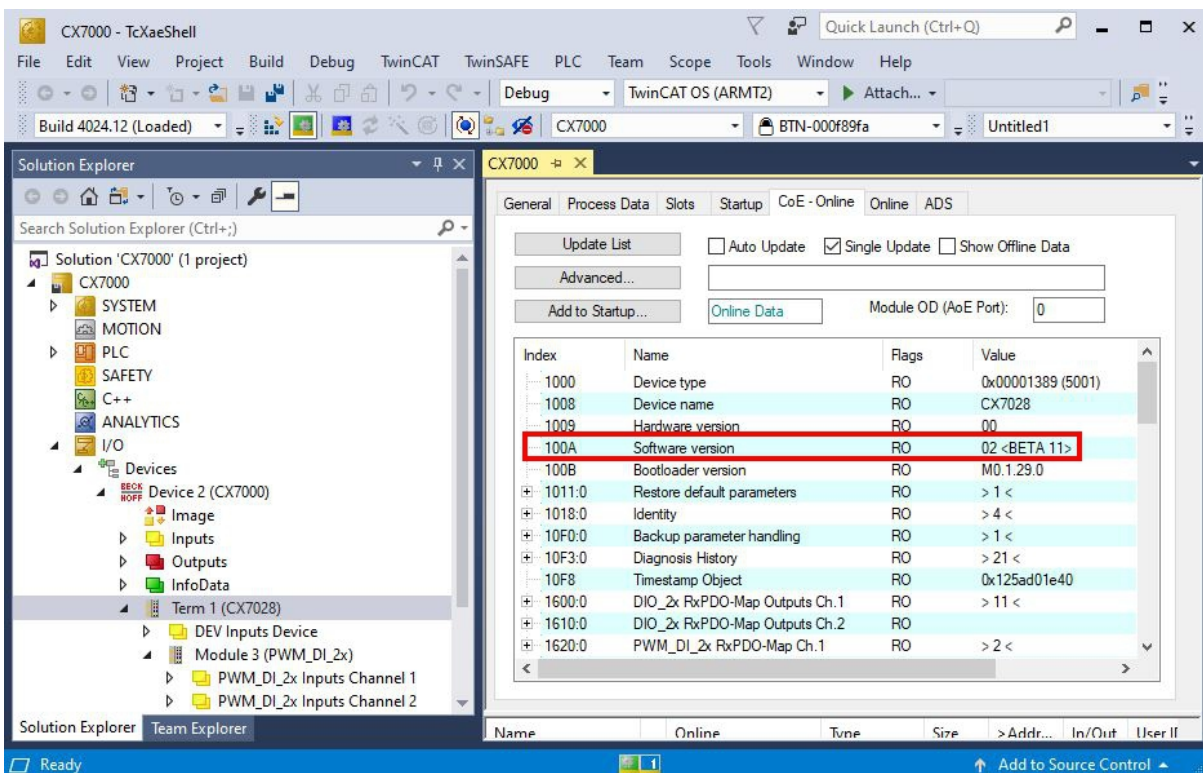


Fig. 50: CoE communication, listing of CoE objects with matching index number.

With the `FB_EcCoeSdoWriteEx` function block an object from the object directory of an EtherCAT slave can be written by SDO-Download. Pay attention to whether the object can be accessed for reading; this is displayed in the Flags column. The `nSubIndex` and `nIndex` parameters allow the object that is to be written to be selected. Via `bCompleteAccess := TRUE` the parameter can be written with subelements.

8.10 Power supply terminal

EtherCAT Terminals (E-bus) or Bus Terminals (K-bus) can optionally be connected directly on the right-hand side; the CX7050 automatically recognizes which system is connected during the start-up phase.

K-bus interface

The CX7050 reads out the terminal types during scanning and creates them in the System Manager under a Bus Coupler.

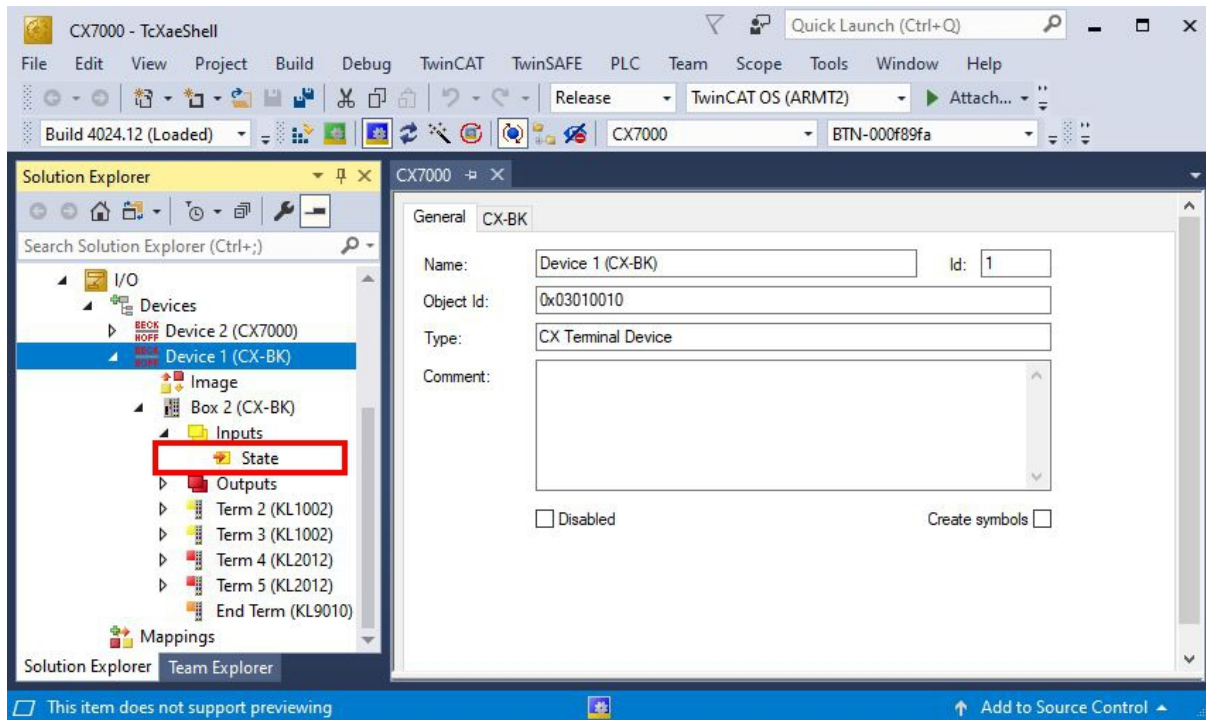


Fig. 51: K-bus interface of a CX7050 in the TwinCAT System Manager.

For K-bus diagnostics there is a status variable in TwinCAT under the Bus Coupler, which can be used for diagnostic purposes and indicates the status of the K-bus communication. For more information, refer to the chapter "Error handling and diagnostics" at [K-bus](#) [▶ 182].

E-bus interface

● Distributed clocks



The Embedded PCs of the CX7000 series are not suitable for the use of EtherCAT slaves that use distributed clocks or require them.

The operation of EtherCAT Terminals and EtherCAT devices is also possible at CX7050. The CX7050 also recognizes these terminals automatically during scanning, reads out the terminal types and creates them in the System Manager under an EtherCAT Coupler.

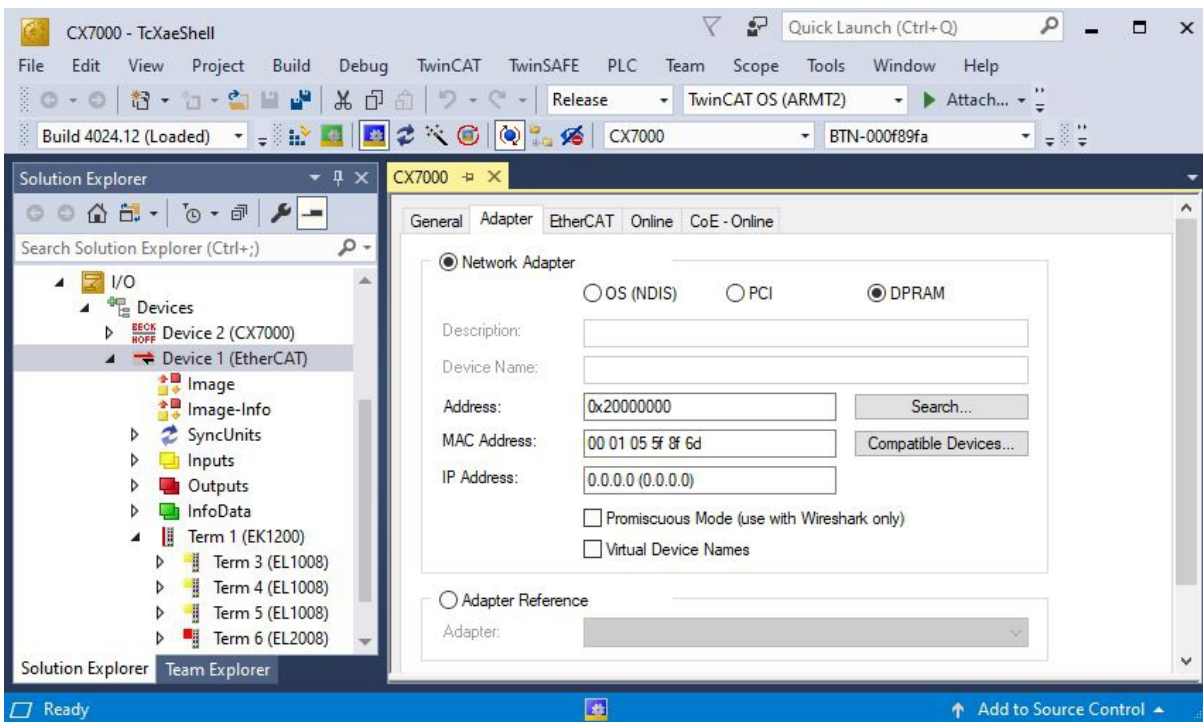


Fig. 52: E-bus interface of a CX7050 in the TwinCAT System Manager.

For more information on diagnostics, refer to the chapter "Error handling and diagnostics" at [E-bus \[► 185\]](#).

8.11 Cycle and processing times

8.11.1 Measuring processing time in the PLC program

This sample shows you how to determine the processing time of a program code with the help of a small PLC program. This allows you to measure, for example, how long the PLC needs for a mathematical function, a loop or a specific program part. The resolution is 1 ns per digit.

Sample

```
VAR
    MeasureStart      : T_DCTIME64;
    MeasureResult     : T_DCTIME64;
END_VAR

PROGRAM:
MeasureStart:=F_GetActualDcTime64(); (*Insert your program code to measure the processing time*)
MeasureResult:=F_GetActualDcTime64()-MeasureStart;
```

Requirements

Development environment	Target platform	PLC libraries to include
TwinCAT v3.1.0	PC or CX (x86, x64, ARM)	Tc2_EtherCAT

8.11.2 Real-Time Clock (RTC)

The CX7050 has an internal, capacitor-buffered real-time clock (RTC) for time and date, which continues to run in the switched-off state. The capacitance of the capacitor is sufficient for at least 30 days and, unlike a battery-backed solution, is maintenance-free. The time is lost and must be reset if the CX7050 is turned off for more than 30 days

The following settings are possible in the boot.conf file:

- SNTP Server
- Update time (default = 1 hour)
- Change UTC Offset
- DHCP server

Sample

The sample below shows you how to read the time. In the sample, the time is output as UTC time and one hour is added to get the CET time.

```
VAR
    FB_LocalSystemTime : FB_LocalSystemTime;
    DATEANDTIME        : DATE_AND_TIME;
    DATEANDTIME_Add1h  : DATE_AND_TIME;
END_VAR

PROGRAM:
FB_LocalSystemTime (
    sNetID:= ,
    bEnable:=TRUE ,
    dwCycle:= ,
    dwOpt:= ,
    tTimeout:= ,
    bValid=> ,
    systemTime=> ,
    tzID=> );

DATEANDTIME:=SYSTEMTIME_TO_DT(TIMESTR:=FB_LocalSystemTime.systemTime );      (*UTC Time*)
DATEANDTIME_Add1h:=DATEANDTIME+T#1H;      (*UTC Time + 1h*)
```

Requirements

Development environment	Target platform	PLC libraries to be integrated (category group)
TwinCAT v3.1.0	PC or CX (WES7/Win7/Win10: TC RT x86/x64, WEC6/7: TC RT x86, WEC7: TC CE7 ARMV7, TC/BSD: TC RT x64, TC OS ARMT2)	Tc2_Utilities (System)

8.11.3 Cycle time of 250 µs

Note that a cycle time of 250 µs on a CX7050 represents an extreme optimum and all boundary conditions must be right. Furthermore, a cycle time of 250 µs only makes sense if the inputs and outputs are correspondingly fast.

The CX7050 has different interfaces, including, for example, the K-bus. The K-bus can achieve perhaps 1 ms under optimal conditions and is therefore unsuitable for cycle times of 250 µs. The E-bus (EtherCAT) is much faster, but the structure of an EtherCAT frame and the merging of the data into an EtherCAT frame is much more complex, so that only 1 ms is possible here as well.

Of course, EtherCAT can be operated with other Industrial PCs under 100 µs. However, these are usually equipped with more powerful CPUs and may use a DMA controller for EtherCAT processing. That is not the case with the CX7050, however, so the CPU power and the interfaces to EtherCAT are the limiting factors. Of course, the CX7050 as a small controller was not developed for high-speed applications and, due to its cost-efficiency, should not be compared to more powerful Industrial PCs.

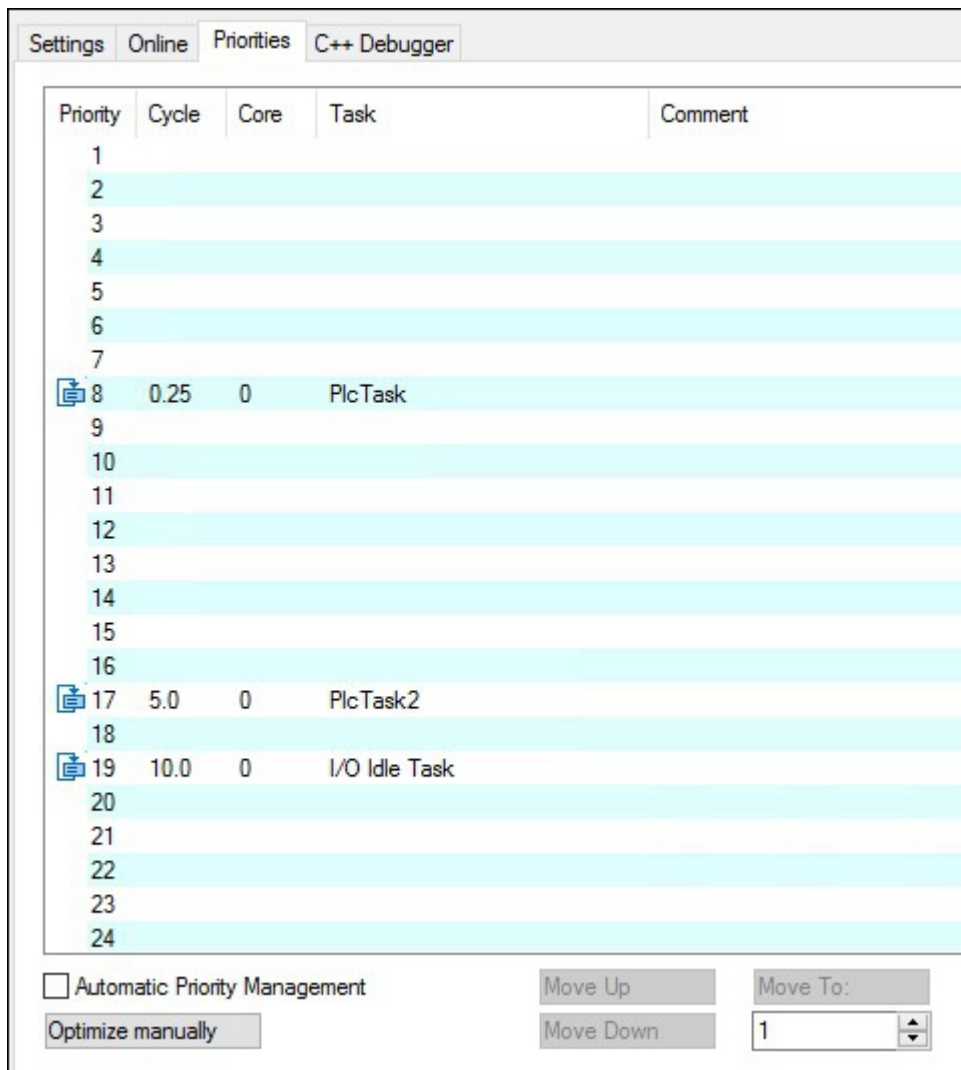
Setting a cycle time of 250 µs

A cycle time of 250 µs is possible on a CX7050 if the boundary conditions are right. The CX7050 is helped by the multifunction I/Os, which are connected to the CPU via a fast IO connection. The connection is kept very lean and has a correspondingly good data throughput. It is possible to reach the 250 µs with the help of the multifunction I/Os. Of course, the PLC program may contain only very little code and the core limit must be set to 90%, which in turn results in the described disadvantages (see: [Real-time and CPU load](#) [▶ 196]).

The screenshot shows the 'Settings' window with tabs for 'Online', 'Priorities', and 'C++ Debugger'. The 'Router Memory' section shows 'Configured Size [MB]' set to 4 and 'Allocated / Available' as 9 / 8. The 'Global Task Config' section shows 'Maximal Stack Size [KB]' set to 64KB. The 'Available Cores' section shows 'Shared / Isolated' as 1 / 0, with 'Read from Target' and 'Set on Target' buttons. Below this is a table with the following data:

Core	RT-Core	Base Time	Core Limit	Latency Warning
0	<input checked="" type="checkbox"/> Default	250 µs	90 %	(none)

In addition, you should set the priority of the task so that the 250 µs task has the highest priority in the system.



If you now allow a digital output of the CX7028 interface to toggle, for example with `Out_01:=not Out_01` in the 250 μ s task, the task is output at a frequency of 2 kHz. In order for the output to be optimally fast, this output should have a load. Only wire the output with a digital input; as a result, the load is very small and the switch-off behavior of the driver is relatively slow. Slow here means in relation to the 250 μ s task time. It makes a difference whether the output requires 50 μ s or 100 μ s to switch off. If you now wish to measure the response time, i.e. the time it takes for the CX7050 to react to an input, the following background is important:

From a cycle time of 1 ms or greater, an optimal cycle is operated, i.e. the inputs of the CX7028 interface are read by the processor of the CX7028 interface about 20% before the new task cycle. If the task time is faster than 1 ms, the time is not sufficient for the optimized response time. In this case the inputs are read with the task cycle. As a result, a task time of 500 μ s achieves the same response time as a task time of 1 ms. With a task time of less than 1 ms, the update needs four task cycles for a cycle. With 1 ms or slower it needs two task cycles. This should make you aware that it is not always the shortening of the cycle time that shortens the reaction time, but also the internal process, which plays a decisive role in the reading of the data.

Here is a sample, so that you can reproduce this behavior yourself and see and measure the differences:

1. Connect the +24 V Up and 0 V Up power supply to power the multifunction I/Os.
2. Connect output 1 to input 1 to toggle the output as described.
3. Connect output 2 to input 2.
4. Set the core limit to 90%, the base time to 250 μ s, the priority of the fast task to the highest priority, and the idle task to 10 ms.

The inputs have only a minimal filter time and are therefore well suited for the measurement. A load on the output is not necessary in this case. For the following samples, we always leave the base time at 250 μ s and only increase the number of cycle ticks in order to set the corresponding task time.

Task Online Parameter (Online) Add Symbols

Name: Port:

Auto start
 Auto Priority Management
Priority:
Cycle ticks: ms
Start tick (modulo):
 Separate input update
Pre ticks:
 Warning by exceeding
 Message box
Watchdog Cycles:

Object Id:

Options
 Disable
 Create symbols
 Include external symbols
 Floating point exceptions
 Watchdog stack

Sample program

```

PROGRAM MAIN
VAR
  bOut_1 AT %Q*:BOOL; (*toggle Output link to digital Output pin 7*)
  bOut_2 AT %Q*:BOOL; (*reaction time link to digital Output pin 14*)

  bIn_1 AT %I*: BOOL; (*toggle Output link to digital Input pin 2*)
  bIn_2 AT %I*: BOOL; (*reaction time link to digital Input pin 10*)

  fbTimer : TON;
  fbflanke1 : R_TRIG;
  fbflanke2 : R_TRIG;

  cnt1: INT; (*toggle Output*)
  cnt1_M: INT; (*toggle Output*)

  cnt2: INT; (*reaction time*)
  cnt2_M: INT; (*reaction time*)
END_VAR

PROGRAM MAIN
bOut_1:= NOT bOut_1; (*toggle Output*)
bOut_2:= NOT bIn_2; (*reaction time*)

fbflanke1(CLK:=bIn_1);
IF fbflanke1.Q THEN
  cnt1:=cnt1+1; (*toggle Output*)
END_IF

fbflanke2(CLK:=bIn_2);
IF fbflanke2.Q THEN
  cnt2:=cnt2+1; (*reaction time*)
END_IF

fbTimer(PT:=T#1S,in:=NOT fbTimer.Q);

IF fbTimer.Q THEN
  cnt2_M:=cnt2; (*reaction time*)
  cnt1_M:=cnt1; (*toggle Output*)
  cnt1:=0;
  cnt2:=0;
END_IF

```

The toggling of the output results in a frequency of 2 kHz – 250 µs On, 250 µs Off – i.e. a period duration of 500 µs. When measuring the positive edge, this is 2000 edge changes in one second.

⚙ bOut_1	BOOL	TRUE
⚙ bOut_2	BOOL	TRUE
⚙ bIn_1	BOOL	FALSE
⚙ bIn_2	BOOL	FALSE
⚙ fbTimer	TON	
⚙ fbflanke1	R_TRIG	
⚙ fbflanke2	R_TRIG	
⚙ cnt1	INT	1014
⚙ cnt1_M	INT	2000
⚙ cnt2	INT	253
⚙ cnt2_M	INT	500

Fig. 53: Measurement at a task time of 250 μ s.

In the case of the response time, it is 500 changes in one second, as the optimized access to the inputs does not apply here.

⚙ bOut_1	BOOL	TRUE
⚙ bOut_2	BOOL	TRUE
⚙ bIn_1	BOOL	TRUE
⚙ bIn_2	BOOL	FALSE
⚙ fbTimer	TON	
⚙ fbflanke1	R_TRIG	
⚙ fbflanke2	R_TRIG	
⚙ cnt1	INT	68
⚙ cnt1_M	INT	1001
⚙ cnt2	INT	17
⚙ cnt2_M	INT	250

Fig. 54: Measurement at a task time of 500 μ s.

As expected, the values are only half as large with a task time that is twice as long.

⚙ bOut_1	BOOL	FALSE
⚙ bOut_2	BOOL	TRUE
⚙ bIn_1	BOOL	FALSE
⚙ bIn_2	BOOL	FALSE
⚙ fbTimer	TON	
⚙ fbflanke1	R_TRIG	
⚙ fbflanke2	R_TRIG	
⚙ cnt1	INT	169
⚙ cnt1_M	INT	501
⚙ cnt2	INT	84
⚙ cnt2_M	INT	251

Fig. 55: Measurement at a task time of 1 ms.

With a task time of 1 ms, you can clearly see that the optimized mode actually helps to reduce the response time. While the toggle change has halved again, i.e. it is now still 500 Hz with a task time of 1 ms, the value for the response time has remained the same.

8.11.3.1 Cycle time ≥ 1 ms



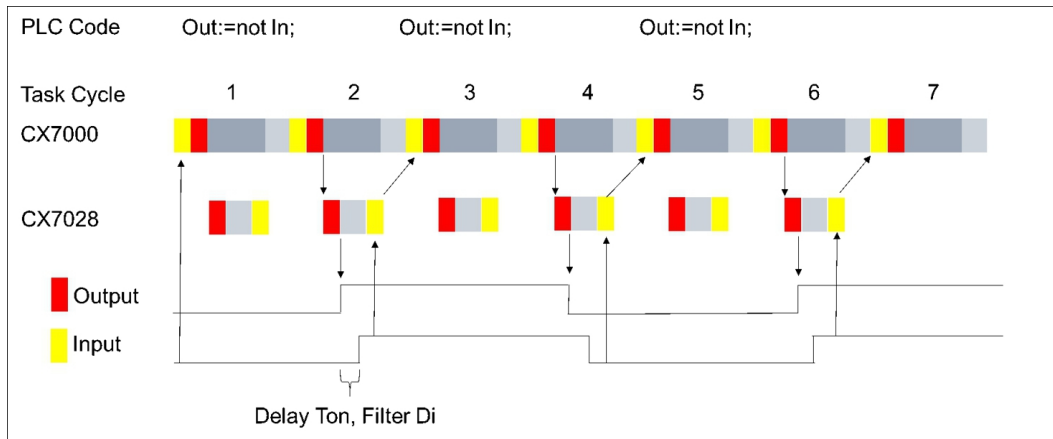
Fig. 56: CX7050 CPU and PLC.

Yellow and red: Mapping and update of the IOs.
Light grey: Time remaining until the task begins again (OS).
Dark grey: PLC cycle.



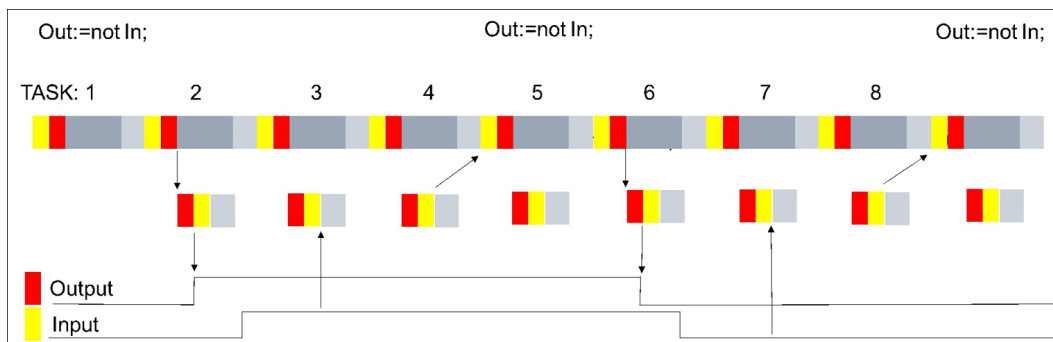
Fig. 57: CPU of the CX7028 interface.

Red: Output update.
Grey: CPU processing of the multifunction IOs.
Yellow: Input update (from a cycle time of 1 ms there is a waiting period of up to approx. 80% of the cycle time before the update of the input signals so that the inputs are read as late as possible, i.e. before the next cycle).



8.11.3.2 Cycle time < 1 ms

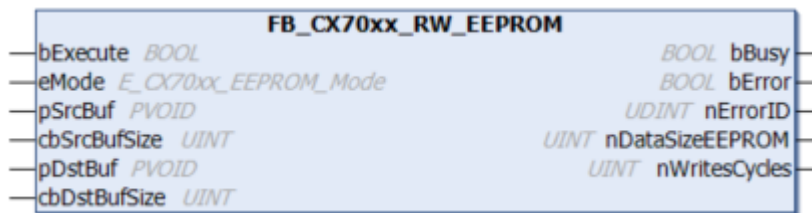
From a cycle time of < 1 ms, the update of the input signals is carried out immediately and is therefore only available with the next cycle. The input signals are therefore always one cycle old.



With this background knowledge, you should be able to make the right settings on the CX7050 for your application.

8.12 Function Blocks

8.12.1 FB_CX70xx_RW_EEPROM



The function block allows a maximum of 120 bytes to be written to the EEPROM (hardware) of the CX70xx. The EEPROM may be written to a maximum of 200 times. The memory is intended for one-time writing.

This function block can be used to personalize the CX70xx. That means, in the simplest case you write your company ID into the EEPROM. When starting the CX70xx program, read the contents of the memory. For example, if it is empty, you cannot continue to run the program because it is no longer your original CX70xx that you programmed.

If you want to exchange a CX70xx for a new device, the EEPROM must be written again by you.

Inputs

```
VAR_INPUT
  bExecute      : BOOL;           // rising edge triggers process with selected mode
  eMode         : E_CX70xx_EEPROM_Mode; // select RW mode
  pSrcBuf       : PVOID;         // pointer to WRITE EEPROM data buffer
  cbSrcBufSize  : UINT;          // size of WRITE EEPROM data buffer (max.120 Bytes)
  pDstBuf       : PVOID;         // pointer to READ EEPROM data buffer
  cbDstBufSize  : UINT;          // max.size of READ EEPROM data buffer (max.120 Bytes)
END_VAR
```

Name	Type	Description
bExecute	BOOL	A positive edge starts the function block.
eMode	E_CX70xx_EEPROM_Mode	ReadOnly: EEPROM read WriteOnly: EEPROM write WriteAndRead: EEPROM write and read
pSrcBuf	PVOID	Pointer to the data buffer to be written.
cbSrcBufLen	UINT	Length of data to be written (max. 120 bytes)
pDstBuf	PVOID	Pointer to the data buffer into which the contents of the EEPROM are to be copied.
cbDstBufLen	UINT	Length of data to be read. (maximum 120 bytes) When reading, the length information must be greater than or equal to the data contained in the EEPROM.

Outputs

```
VAR_OUTPUT
  bBusy         : BOOL;           // FB is working
  bError        : BOOL;           // FB has an Error
  nErrorID      : UDINT;          (* Error Code
  If nErrorID=DEVICE_INVALIDACCESS the EEPROM write cycles reached max. value.
  If nErrorID=DEVICE_INVALIDPARM the given pointer parameter is invalid/null.
  If nErrorID=DEVICE_INVALIDSIZE the given buffer size is too small or too big.
  If nErrorID=DEVICE_SRVNOTSUPP probably the image version need to be updated to support this feature. *)
  nDataSizeEEPROM : UINT;          // current size of (read) EEPROM data in bytes (max.120 Bytes)
  nWritesCycles  : UINT;          // already performed EEPROM write cycles (maximum possible = 200)
END_VAR
```

Name	Type	Description
bBusy	BOOL	The function block is active and working.

Name	Type	Description
bError	BOOL	The function block has an error.
nErrorID	UDINT	ADS Error Code Examples: DEVICE_INVALIDACCESS: the EEPROM write cycles have reached the maximum value. The EEPROM cannot be rewritten. DEVICE_INVALIDPARG: the allocated pointers are invalid/NULL. DEVICE_INVALIDSIZE: the allocated buffer size is too small or too large. DEVICE_SRVNOTSUPP: the image version of the CX70xx does not support this feature. An update (>=35695) is necessary.
nDataSizeEEPROM	UINT	Current size in bytes of the read EEPROM data
nWritesCycles	UINT	Number of write operations still available

8.12.2 FB_CX70xx_ResetOnBoardIO



The function block allows to execute a reset from the OnBoard I/O of the CX70xx Embedded PC.

Typical use case is after an error in the communication to the OnBoard I/Os (CX7028). Such an error occurs when the power supply (Up) of the OnBoard I/Os is interrupted.

NOTICE

State of the I/Os
Outputs that are still set in the process image are switched on again immediately after a reset.

Further details on the OnBoard I/O can be found in the [documentation of the CX70xx Embedded PC](#).

Inputs

```

VAR_INPUT
  bExecute      : BOOL;           // rising edge triggers process
  sNetId        : T_AmsNetID;    // AMS Net ID of the OnBoard I/Os
  tTimeout      : TIME := DEFAULT_ADS_TIMEOUT; // maximum time allowed for execution of this ADS command
END_VAR
    
```

Name	Type	Description
bExecute	BOOL	A positive edge starts the function block.
sNetId	T_AmsNetID	AMS Net ID of the OnBoard I/Os
tTimeout	TIME	States the length of the timeout that may not be exceeded by execution of the ADS command.

Outputs

```

VAR_OUTPUT
  bBusy         : BOOL;           // FB is working
  bError        : BOOL;           // FB has an Error
  nErrorID      : UDINT;          (* Error Code. If nErrorID=DEVICE_SRVNOTSUPP probably the image version need to be updated to support this feature. *)
END_VAR
    
```

Name	Type	Description
bBusy	BOOL	The function block is active and working.
bError	BOOL	The function block has an error.

Name	Type	Description
nErrorID	UDINT	ADS Error Code Examples: DEVICE_SRVNOTSUPP: the image version of the CX70xx does not support this feature. An update (>=47912) is necessary.

Sample:

```
FUNCTION_BLOCK FB_Test_ResetOnboardIO
VAR
  AMSNetID      : T_AmsNetIdArr;    // link to the AMS Net ID of the OnBoard IOs
  State         : WORD;             // link to the State of the OnBoard IOs
  bReset        : BOOL;             // if Ready to Reset you can reset the OnBoard IOs
  fbReset       : FB_CX70xx_ResetOnBoardIO;
END_VAR

IF State<>8 AND NOT State.8 AND State.4 THEN // if OnBoard IO device signals an error and is not OP
but present
  bReset := TRUE;
ELSE
  bReset := FALSE;
END_IF

IF NOT fbReset.bBusy AND bReset THEN
  fbReset(bExecute:=TRUE, sNetId:=F_CreateAmsNetId(AMSNetID));
ELSE
  fbReset(bExecute:=FALSE);
END_IF
```

8.13 Important attribute pragmas

Attribute pragmas are used to influence compilation and pre-compilation. TwinCAT supports a number of predefined attribute pragmas. Attributes are defined in the declaration part.

8.13.1 Attribute 'Tc2GvlVarNames'

The pragma has the effect that symbols, which are declared in a GVL, are addressed via ADS just like in TwinCAT 2 (without the use of the GVL name as namespace).

Syntax: {attribute 'Tc2GvlVarNames'}

Sample:

```
{attribute 'Tc2GvlVarNames'}
VAR_GLOBAL
  Test : INT;
END_VAR

GVL.Test:=GVL.Test+1;    (*without attribute*)
Test:=Test+1;           (*with attribute*)
```

8.13.2 Attribute 'pack_mode'

This attribute pragma specifies how a data structure is packaged during allocation. The attribute must be inserted above the data structure and affects the packing of the whole structure.

Syntax: {attribute 'pack_mode' := '<Value>'}

Sample

```
{attribute 'pack_mode' := '0'}
TYPE str_Test :
STRUCT
  byTest1 : BYTE;
  iTTest  : DINT;
  byTest2 : BYTE;
  nValue  : INT;
END_STRUCT
END_TYPE
```

In this sample, the pack mode has been set to 0. If you determine the size of the structure in the sample with SIZEOF, you get the value 8.

1 byte + 4 bytes (DINT) + 1 byte + 2 bytes (INT) = 8 bytes

If you set the pack mode to 2 (WordAlignment), you get the value 10 because a padding byte is inserted after each byte. If you set the pack mode to 4 (DWordAlignment), then you get the value 12, because this time three padding bytes are inserted after each byte. A pack mode of 8 (LWordAlignment) does not change anything, because the sample does not use variables that require 8 bytes.

The CX7050 works with the DWordAlignment (pack mode 4) if you do not use the attribute.

For more information about the pack_mode attribute, see: Attribute 'pack_mode'

8.13.3 Attribute 'TcCallAfterOutputUpdate'

The attribute pragma TcCallAfterOutputUpdate causes the IO update to take place before the PLC cycle and not after the PLC program as is set by default.

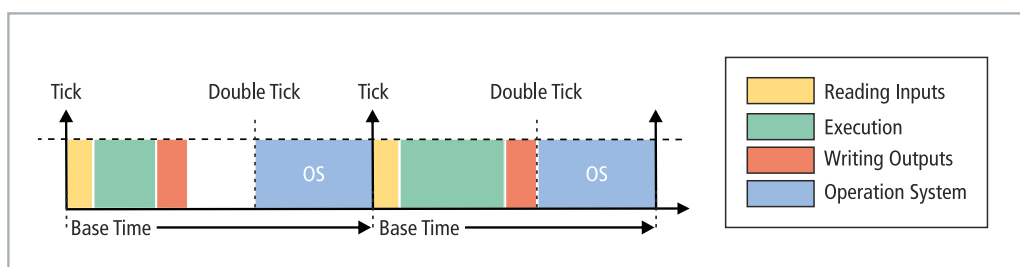


Fig. 58: Default calling of a PLC task.

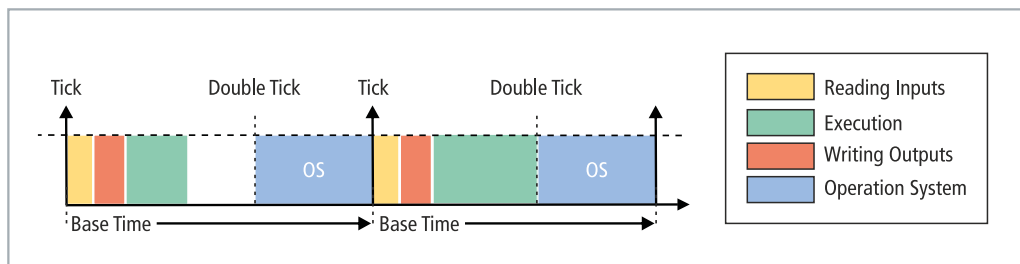


Fig. 59: Calling a PLC task with the attribute tcCallAfterOutputUpdate.

This function can be used for projects with strongly fluctuating cycle times. In projects with strongly fluctuating cycle times, the outputs, since they are written after the PLC cycle, are sometimes written earlier (short PLC cycle time) and sometimes later (long PLC cycle time). These fluctuations cause jitter in the outputs. The disadvantage is that the attribute cannot react quite as quickly and a cycle is always lost. You have to decide whether you want to react quickly to an input (default setting) or whether you prefer to have a deterministic behavior of the outputs (setting of the attribute).

Syntax: {attribute 'TcCallAfterOutputUpdate'}

Insertion location: This attribute must be added to all program POU's, which are to be called after the output update.

Sample:

To illustrate the behavior, you need a digital output terminal such as an EL2008 and an oscilloscope.

Write a small PLC program and link the variable bOut with a digital output:

```
bOut:=not bOut;
```

The PLC program is very simple and does not cause any fluctuations. The pulse is displayed on the oscilloscope as follows:

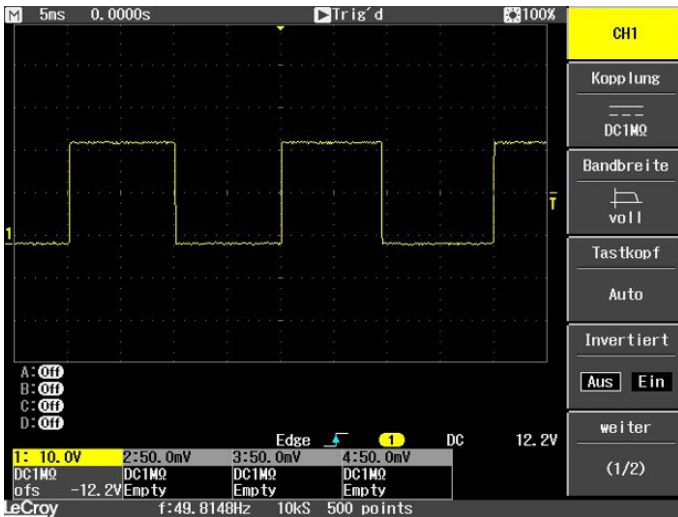


Fig. 60: Pulse of a digital output without load.

Now extend the PLC program with a For loop to create a program load. The mathematical function used does not matter and is intended only to generate a load:

```
bOut:=not bOut;

IF bOut THEN
  For loop:=1 to 2000 do
    lrTest:=SIN(INT_TO_LREAL(loop)*3.14);
  END_FOR
END_IF
```

Whenever the output is set to TRUE, the loop is run through and a load is generated. As a result, more time is needed to run the PLC and the output is written later than usual. During the next cycle, the output is set back to FALSE, the loop is not run through and the output is set to FALSE faster, because the PLC program is finished faster without a For loop. The result is that the pulse is very much shorter.

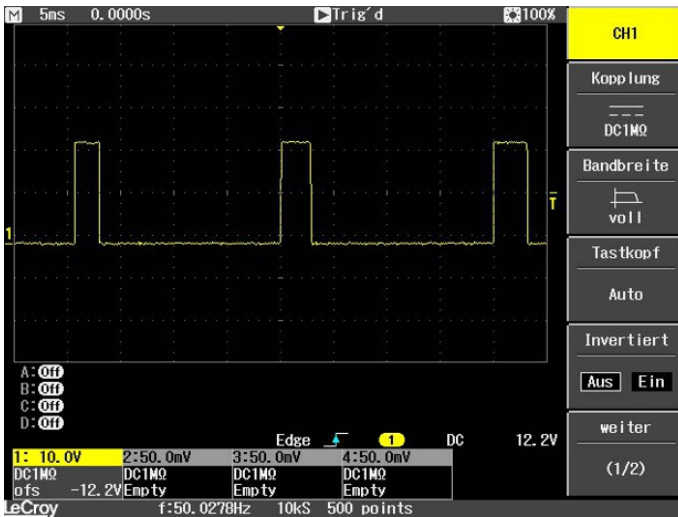


Fig. 61: Shortened pulse of a digital output with load.

If the For loop is called upon FALSE instead of TRUE, the result is inverted.

```
bOut:=not bOut;

IF not bOut THEN
  For loop:=1 to 2000 do
    lrTest:=SIN(INT_TO_LREAL(loop)*3.14);
  END_FOR
END_IF
```

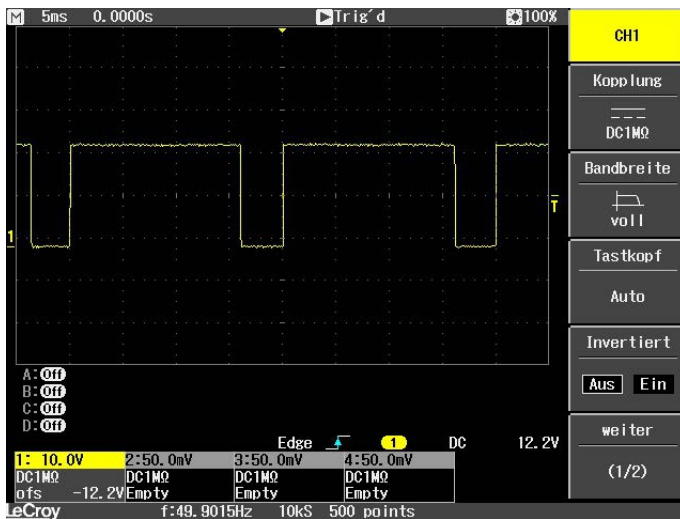


Fig. 62: Inverted representation of a digital output.

With the attribute pragma `TcCallAfterOutputUpdate`, the pulse is constant and is independent of how long the For loop takes or whether it is called. The whole thing only works if the PLC task is not exceeded. Therefore, when reproducing the sample, pay attention to the exceed counters of the task.

Detecting a PLC program with different runtimes

The PLC program must be supplemented in order to detect PLC programs with different runtimes. Different runtimes are not recognizable in the online view, since an average value is always formed over several cycles. Therefore, outliers can only be detected if they lie above the task time. If the outliers are still within the task time, they are not easily visible.

For this we then use the system variable: `PlcTaskSystemInfo`

```

VAR
    bOut : BOOL;
    PlcTaskSystemInfo : PlcTaskSystemInfo;
    udiValue : ARRAY[0..19] of UDINT;
    Cnt : INT;
END_VAR

Program:
bOut:=not bOut;

IF bOut THEN
    For loop:=1 to 2000 do
        lrTest:=SIN(INT_TO_LREAL(loop)*3.14);
    END_FOR
END_IF

PlcTaskSystemInfo:=_TaskInfo[1];

udiValue[Cnt]:= PlcTaskSystemInfo.LastExecTime;
cnt:=cnt+1;
IF Cnt >19 THEN
    Cnt:=0;
END_IF
    
```

With this program extension you can see that the PLC program with a For loop requires 7.7 ms and without a For loop 1.1 ms. The specification is 100 ns per digit.

udiValue	ARRAY [0..19] OF U...	
udiValue[0]	UDINT	77728
udiValue[1]	UDINT	10713
udiValue[2]	UDINT	71049
udiValue[3]	UDINT	11065
udiValue[4]	UDINT	69882
udiValue[5]	UDINT	11027
udiValue[6]	UDINT	77084
udiValue[7]	UDINT	11939
udiValue[8]	UDINT	77494
udiValue[9]	UDINT	18527
udiValue[10]	UDINT	76724
udiValue[11]	UDINT	11043
udiValue[12]	UDINT	71519
udiValue[13]	UDINT	11406
udiValue[14]	UDINT	79004
udiValue[15]	UDINT	11118
udiValue[16]	UDINT	70745
udiValue[17]	UDINT	12007
udiValue[18]	UDINT	77761

Fig. 63: Determination of different running times in the PLC program.

The measurement coincides with the displays on the oscilloscope, on which it can be seen that a pulse is sometimes 6.5 ms longer or 6.5 ms shorter. You can measure the processing time of the For loop ([Measuring processing time in the PLC program \[► 168\]](#)). The result of this measurement will coincide with the observed values through the program extension, with a certain inaccuracy and jitter.

9 Error handling and diagnostics

9.1 Diagnostic LEDs

Display	LED	Color	Description
	TC	Green	TwinCAT is in Run mode.
		Red	TwinCAT is in Stop mode. Additionally indicates errors during system startup by error code and error argument (see table: TC-LED, error description and remedy). The red LED flashes with two different frequencies.
		Blue	TwinCAT is in Config mode.
		Yellow	Error or crash of the PLC.
		Off	
	FB	Green	CAN is OK.
		Red	CAN in bus-off.
		Green and red flashing, 200 ms	CAN warning.
		Off	CAN not configured.
	DIAG	Green	All nodes have NodeState = 0
		Green and red flashing, 200 ms	All boxes in OP mode, but the task has not yet started.
		Red 200 ms	Not all nodes in OP mode.
		Off	No boxes configured.
		Red	If only the DIAG LED lights up when starting the CX70xx, then the bootloader is damaged and the device must be sent in for repair.

The TC-LED flashes at a specified frequency and in a specified order, thus indicating the error code and argument.

Table 18: TC LED, order and meaning.

Sequence	Meaning
Fast flashing	Starting the sequence
First slow sequence	Error code
No display	Pause, the LED is off
Second slow sequence	Error argument

Count how many times the red TC LED flashes in order to determine the error code and argument.

Table 19: TC LED, error description and remedy.

Error code	Error argument	Description	Remedy
1	1	microSD card not recognized	Check the microSD card. Image is defective. Install a new image on the microSD card.
	2	Card init failed - preloader	
	3	No partition found - preloader	
	4	Filesystem mount failed - preloader	
	5	Card init failed - loader	
	6	No partition found - loader	
	7	Filesystem mount failed - loader	
2	1	Loader not found	
	2	Loader file invalid (checksum, size, read error)	
	3	TC dll not found	

Error code	Error argument	Description	Remedy
	4	TC dll checksum error	
	5	EEPROM file missing or invalid	
	6	TcOsSys.dll version not compatible with loader	
3	1	Rbf not found	
	2	CCAT 1 init failed	
	3	CCAT 2 init failed	
	4	CCAT EEPROM writing failed	
	5	CCAT 1 EEPROM reloaded failed	
	6	CCAT 2 EEPROM reloaded failed	
4	1	Peripheral not working	
	2	Voltage Vo not reached	
	3	Low speed external oscillator not running	
	4	High speed external oscillator not running	
	5	Flash failed	
	6	Device overlocked (old Hardware)	
5	5	RAM error detected	

9.1.1 K-bus

The power supply unit checks the connected Bus Terminals for errors. The red LED "K-bus ERR" is off if no error is present. The red LED "K-bus ERR" flashes if Bus Terminal errors are present.

Table 20: Diagnostic LEDs in K-Bus mode.

Display	LED	Meaning
	Us 24 V	Power supply for basic CPU module. The LED lights green if the power supply is correct.
	Up 24V	Power supply for terminal bus. The LED lights green if the power supply is correct.
	K-BUS RUN	Diagnostic K-bus. The green LED lights up in order to indicate error-free operation. "Error-free" means that the communication with the fieldbus system is also running.
	K-BUS ERR	Diagnostic K-bus. The red LED flashes to indicate an error. The red LED flashes with two different frequencies.

The frequency and number of the flashes can be used to determine the error code and the error argument. An error is indicated by the "K-bus ERR" LED in a particular order.

Table 21: K-bus ERR LED, fault indication sequence through the LED.

Order	Meaning
Fast flashing	Starting the sequence
First slow sequence	Error code
No display	Pause, the LED is off
Second slow sequence	Error code argument

Count how often the red LED K-bus ERR flashes, in order to determine the error code and the error argument. In the error argument the number of pulses shows the position of the last Bus Terminal before the error. Passive Bus Terminals, such as a power feed terminal, are not included in the count.

Table 22: K-BUS ERR LED, fault description and troubleshooting.

Error code	Error code argument	Description	Remedy
Persistent, continuous flashing		EMC problems.	<ul style="list-style-type: none"> • Check power supply for undervoltage or overvoltage peaks. • Implement EMC measures. • If a K-bus error is present, it can be localized by a restart of the power supply unit (by switching it off and then on again).
3 pulses	0	K-bus command error.	<ul style="list-style-type: none"> • No Bus Terminal inserted. • One of the Bus Terminals is defective; halve the number of Bus Terminals attached and check whether the error is still present with the remaining Bus Terminals. Repeat this procedure until the faulty Bus Terminal has been found.
4 pulses	0	K-bus data error, break behind the power supply unit.	Check whether the Bus End Terminal 9010 is connected.
	n	Break behind Bus Terminal n.	Check whether Bus Terminal n+1 after the power supply unit is connected correctly; replace if necessary.
5 pulses	n	K-bus error in register communication with Bus Terminal n.	Replace Bus Terminal at location n.
6 pulses	0	Error at initialization.	Replace Embedded PC.
	1	Internal data error.	Hardware reset of the Embedded PC (switch off and back on again).
	8	Internal data error.	Hardware reset of the Embedded PC (switch off and back on again).
7 pulses	0	Process data lengths of the set and actual configurations do not correspond.	Check the configuration and the Bus Terminals for consistency.

For some error the LED "K-BUS ERR" does not go out, even if the error was rectified. Switch the power supply for the power supply unit off and back on again to switch off the LED after the error has been rectified.

State variable

In TwinCAT there is a State variable under the Bus Coupler for K-bus diagnostics.

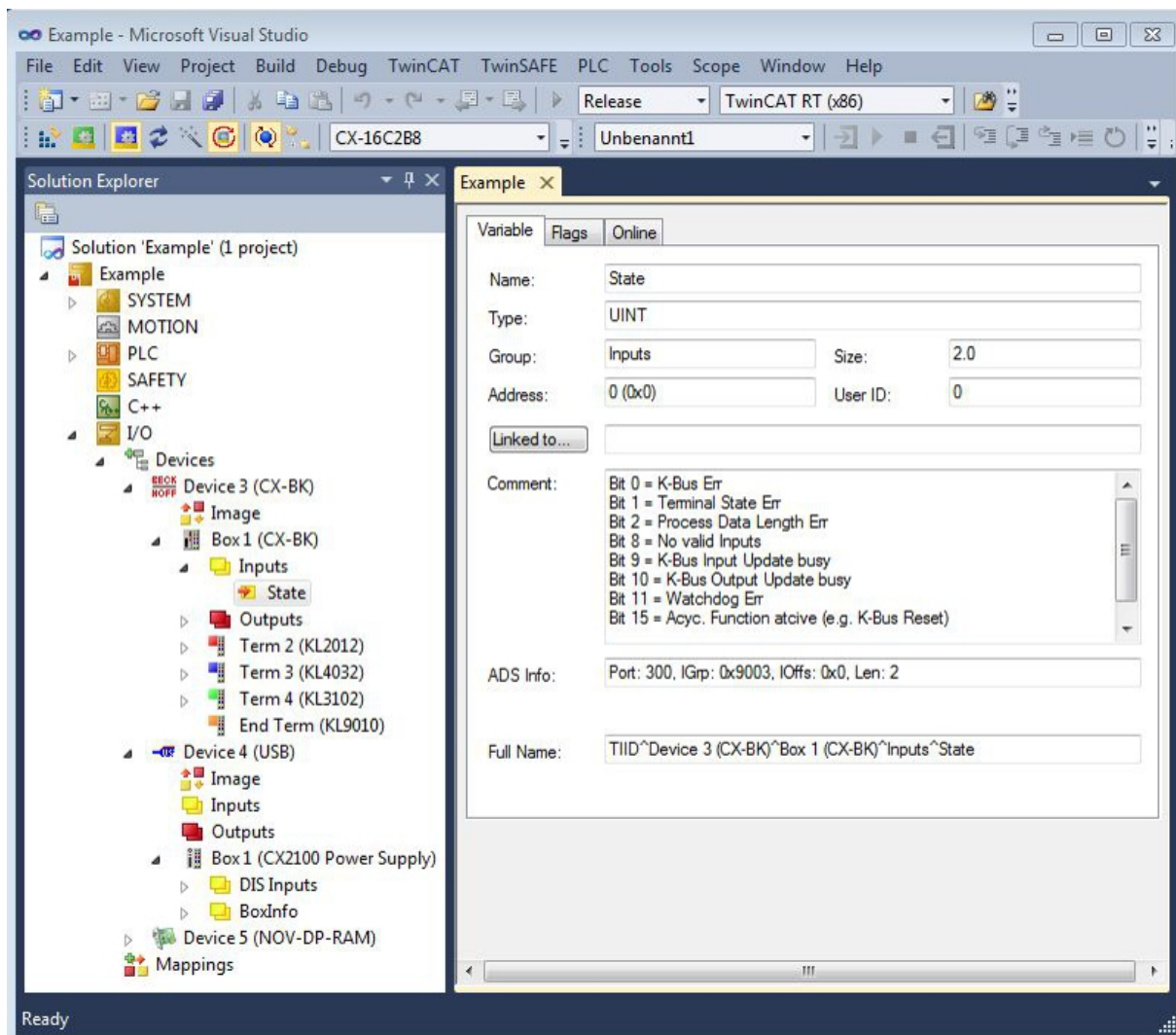


Fig. 64: Status variable for error handling and diagnostics under TwinCAT.

If the value is "0", the K-bus operates synchronous and without error. If the value is \neq "0" there may be a fault, or it may only be an indication that the K-bus cycle is longer than the task. In which case it would no longer be synchronous with the task. The task time should be faster than 100 ms. We recommend a task time of less than 50 ms. The K-bus update time typically lies between one and five ms.

Table 23: Description of the State variable values.

Bit	Description
Bit 0	K-bus error.
Bit 1	Terminal configuration has changed since the start.
Bit 2	Process image lengths do not match.
Bit 8	(still) no valid inputs.
Bit 9	K-bus input update not yet complete.
Bit 10	K-bus output update not yet complete.
Bit 11	Watchdog.
Bit 15	Acyclic K-bus function active (e.g. K-bus reset).

If there is a K-bus error, this can be reset via the IOF_DeviceReset function block (in the TcIoFunctions.lib).

9.1.2 E-bus

The power supply unit checks the connected EtherCAT Terminals. In E-bus mode the "Link/Act IO" LED is lit. When data are transferred, the "Link/Act IO" LED flashes.

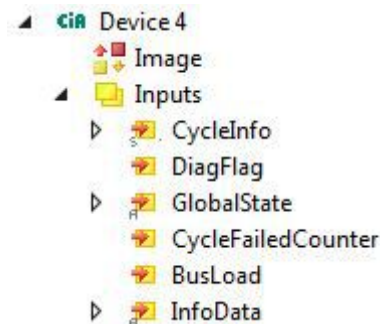
Table 24: Diagnostic LEDs in K-Bus mode.

Display	LED	Meaning	
	Us	Power supply for basic CPU module. The LED lights green if the power supply is correct.	
	Up	Power supply for terminal bus. The LED lights green if the power supply is correct.	
	Link/Act IO	off	E-bus not connected.
		on	E-bus connected / no data traffic.
	flashes	E-bus connected / data traffic on the E-bus.	

9.2 CANopen diagnostics

9.2.1 Status messages

The CANopen status messages provide additional information and can be used for diagnostic purposes.



The following table shows which values the variables can assume:

Inputs	Meaning
CycleInfo	Cycle Counter: This counter is incremented by one after each cycle. Error: Displays the number of boxes with a non-null BoxState. ActualCycle Time: Reserved for future use
DiagFlag	This variable provides information on changes to the diagnostic data. <ul style="list-style-type: none"> • 0: Data unchanged. • 1: Data changed. Use ADS Read to read the data.
GlobalState	This variable provides information on the status of the master. GlobalState[0]: 0: Device is in RUN state. 1: Device is in RESET state. 2: Device is in OFFLINE state. 3: Device is in STOP state. GlobalState[1] (FW V02.14 and higher): Bit 0-7: RxError counter of the CAN controller. Bit 8-15: TxError counter of the CAN controller. GlobalState[2]: Bit 0: CAN controller is in BUS-OFF. Bit 1: CAN controller warning limit reached. Bit 2: Rx-Queue exceeded. Bit 3: Hi-Prio Tx-Queue exceeded. Bit 4: Lo-Prio Tx-Queue exceeded. Bit 5: CAN-Send Error (FW V02.14 and higher). Bit 6-14: reserved for future use. Bit 15: switches on every SYNC message sent. GlobalState[3]: Bus utilization in %.
CycleFailedCounter	This counter is incremented by one whenever the last bus cycle is incomplete at the start of a TwinCAT cycle.
BusLoad	Bus load in %.
InfoData	

9.2.2 Communication

In the tree view, input variables are listed under the **Inputs** menu item, which provide information about a CANopen device.

The NodeState variable can be used to show the state of the CANopen communication, to indicate whether the slave is in data exchange or an error is present.

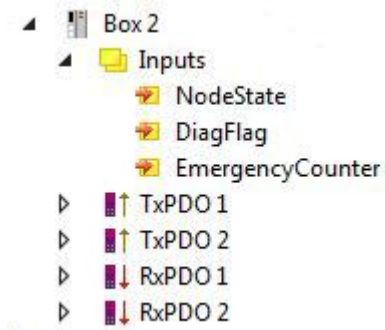


Fig. 65: Diagnosis of the CANopen communication with the variables NodeState, DiagFlag and EmergencyCounter.

NodeState

The following table shows which values the variable NodeState can assume:

Value	Meaning
0	No error
1	Node deactivated
2	Node not found
4	SDO syntax error at StartUp
5	SDO data mismatch at StartUp
8	Node StartUp in progress
11	FC510x Bus-OFF
12	Pre-Operational
13	Severe bus fault
14	Guarding: toggle error
20	TxPDO too short
22	Expected TxPDO is missing
23	Node is Operational but not all TxPDOs were received
31	only for EtherCAT gateways: WC-State of cyclic EtherCAT frame is 1
128	Node is Operational but not all RxPDOs were received
129	Node is Pre-Operational
130	Node is Stopped

DiagFlag

The following table shows which values the variable DiagFlag can assume. This variable provides information on changes to the diagnostic data.

Value	Meaning
0	Data unchanged.
1	Data changed. Use ADS Read to read the data.

EmergencyCounter

The EmergencyCounter variable is incremented by one if an emergency telegram was received.

Table 25: Reading the emergency telegrams with the ADSREAD function block.

Input parameters	Description
NETID	NetId of the CAN interface
Port number	200
IDXGRP	16#xxxxF180 (xxxx) Node-Id, the Diag flag is only reset when reading at least 106 bytes 16#xxxxF181 (xxxx) Node-Id, the Diag flag is reset immediately
IDXOFFS	Byte Offset

Table 26: Description of the array

Offset	Bit	Value / description
0 - 1	Bit 0	reserved
	Bit 1	Boot up message not received or incorrect
	Bit 2	Emergency-Overflow
	Bit 3 - 15	reserved
2 - 3	Bit 0 - 14	TX-PDO (i+1) received
	Bit 15	All TX PDOs 16-n received
4 - 5	Bit 0 - 4	1: Incorrect TX PDO length
		2: synchronous TX PDO missing
		3: Node signaling PRE-OPERATIONAL
		4: Event timer expired for a TX PDO
		5: no response during guarding
		6: toggling missed several times during guarding
	Bit 5 - 15	Associated COB ID
6	Bit 0 - 7	1: incorrect value during SDO upload
		2: incorrect length during SDO upload
		3: Abort during SDO up/download
		4: incorrect date during a boot-up message
		5: timeout while waiting for a boot-up message
7	Bit 0 - 7	2: incorrect SDO command specifier
		3: SDO toggle bit has not changed
		4: SDO length too great
		5: SDO-Abort
		6: SDO-Timeout
8 - 9	Bit 0 - 7	SDO up/download index
10	Bit 0 - 7	SDO up/download subindex
11	Bit 0 - 7	reserved
12	Bit 0 - 7	Abort errorClass
13	Bit 0 - 7	Abort errorCode
14 - 15	Bit 0 - 15	Abort additionalCode
16 - 19		Read value (if offset 6 = 1)
20 - 23		Expected value (if offset 6 = 1)
24 - 25		Number of consecutive emergencies
26 - n		Emergencies (8 bytes each)

9.2.3 PDOs

SendCounter

TxPDOs feature an additional SendCounter variable under the **Control** menu item.

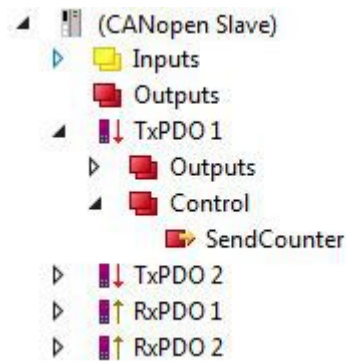


Fig. 66: Diagnostic variable SendCounter of a CANopen slave.

By default, PDOs are sent automatically when a change is made. This variable can be used if the data is to be sent not only when a change is made, but also when nothing has changed in the data in the PDO.

The variable must therefore be incremented by one if the data in the PDO is to be sent even without a change. If the variable is incremented in the same cycle and a change of data is made in parallel, only one telegram is sent.

Apart from this scenario, this variable can be used to monitor whether the corresponding PDO was sent when the data changed.

ReceiveCounter

RxPDOs feature an additional ReceiveCounter variable under the **Status** menu item.

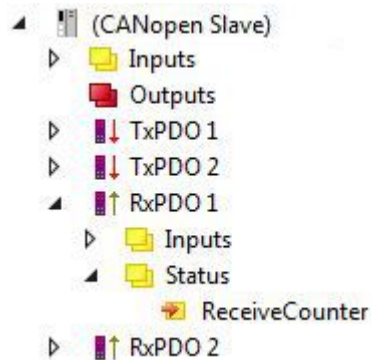


Fig. 67: Diagnostic variable ReceiveCounter of a CANopen slave.

The input variable is incremented by one whenever a PDO is received. In this way newly arrived PDO are always logged, even if the data in the PDO are unchanged. The variable also indicates whether a device is still sending data on a regular basis. It is useful to link variable with the PLC and monitor it.

9.2.4 Troubleshooting

Error Frames

One sign of errors in the CAN wiring, the address assignment or the setting of the baud rate is an increased number of error frames: the diagnostic LEDs then show *Warning Limit exceeded* or *Bus-off state entered*.

Error Frames

Warning limit exceeded, passive error or bus-off state are indicated first of all at those nodes that have detected the most errors. These nodes are not necessarily the cause for the occurrence of error frames!

If, for instance, one node contributes unusually heavily to the bus traffic (e.g. because it is the only one with analog inputs, the data for which triggers event-driven PDOs at a high rate), then the probability of its telegrams being damaged increases. Its error counter will, correspondingly, be the first to reach a critical level.

Node ID / Setting the Baud Rate

Care must be taken to ensure that node addresses are not assigned twice: there may only be one sender for each CAN data telegram.

Test 1

Check node addresses. If the CAN communication works at least temporarily and all devices support the boot-up message, the address assignment can also be checked by recording the boot-up messages after switching on the devices - but this does not detect any swapping of node addresses.

Test 2

Check that the same baud rate has been set everywhere. For special devices, if the bit timing parameters are accessible, do they agree with the CANopen definitions (sampling time, SJW, oscillator).

Testing the CAN wiring

These tests should not be carried out if the network is active: No communication should take place during the tests. The following tests should be carried out in the stated sequence, because some of the tests assume that the previous test was successful. Not all the tests are generally necessary.

Network terminator and signal leads

The nodes should be switched off or the CAN cable unplugged for this test, because the results of the measurements can otherwise be distorted by the active CAN transceiver.

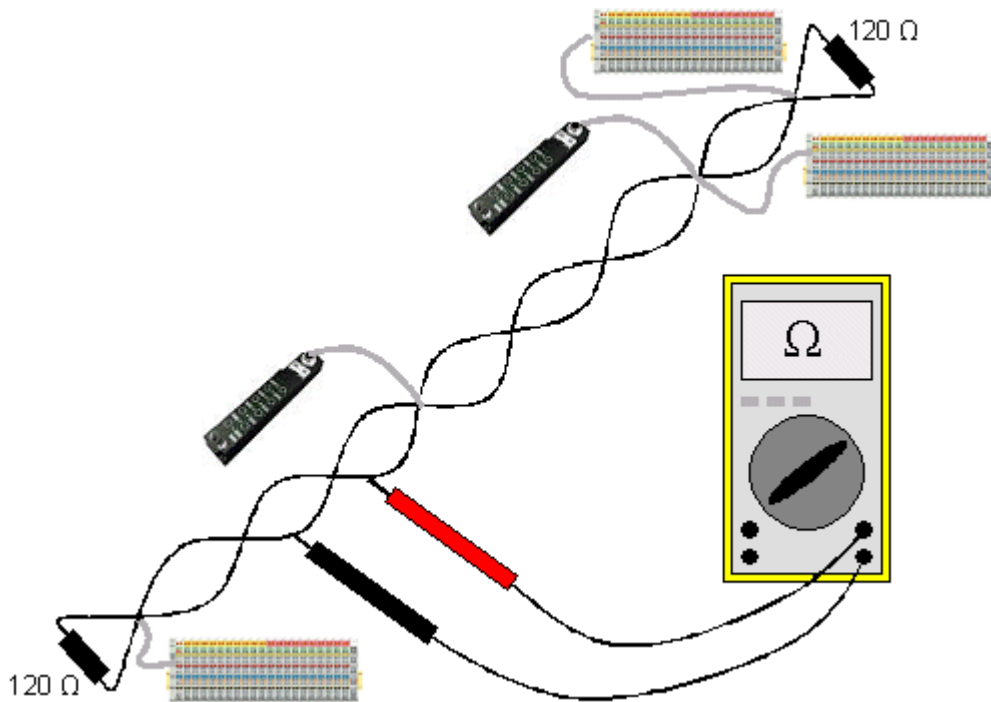


Fig. 68: Wiring diagram for test setup

Test 3

Determine the resistance between CAN high and CAN low - at each device, if necessary.

If the measured value is greater than 65 Ohms, it indicates the absence of a terminating resistor or a break in a signal lead. If the measured value is less than 50 Ohms, look for a short circuit between the CAN lines, more than the correct number of terminating resistors, or faulty transceivers.

Test 4

Check for a short circuit between the CAN ground and the signal leads, or between the screen and signal leads.

Test 5

Remove the earth connection from the CAN ground and screen. Check for a short circuit between the CAN ground and screen.

Topology

The cable length for CAN networks depends strongly on the selected baud rate. CAN will tolerate short drop lines - although this again depends on the baud rate. The maximum permitted drop line length should not be exceeded. The length of cable that has been installed is often underestimated - estimates can even be a factor of 10 less than the actual length. The following test is therefore recommended:

Test 6

Measure the lengths of the drop lines and the total bus lengths (do not just make rough estimates!) and compare them with the topology rules for the relevant baud rate.

Screening and earthing

The power supply and the screen should be carefully earthed at the power supply unit, once only and with low resistance. At all connecting points, branches and so forth the screen of the CAN cable (and possibly the CAN GND) must also be connected, as well as the signal leads. In the Beckhoff IP20 Bus Couplers, the screen is grounded for high frequencies via an R/C element.

Test 7

Use a DC ammeter (16 amp max.) to measure the current between the power supply ground and the shield at the end of the network most remote from the power supply unit. An equalization current should be present. If there is no current, then either the screen is not connected all the way through, or the power supply unit is not properly earthed. If the power supply unit is somewhere in the middle of the network, the measurement should be performed at both ends. When appropriate, this test can also be carried out at the ends of the drop line.

Test 8

Interrupt the screen at a number of locations and measure the connection current. If current is flowing, the screen is earthed at more than one place, creating a ground loop.

Potential differences

The screen must be connected all the way through for this test, and must not be carrying any current - this has previously been tested.

Test 9

Measure and record the voltage between the screen and the power supply ground at each node. The maximum potential difference between any two devices should be less than 5 volts.

Detect and localize faults

The "low-tech approach" usually works best: disconnect parts of the network and observe when the error disappears.

However, this does not work well for problems such as excessive potential differences, ground loops, EMC or signal distortion, since the reduction in the size of the network often solves the problem without the "missing" piece being the cause. The bus load also changes as the network is reduced in size, which can mean that external interference "hits" CAN telegrams less often.

Diagnosis by means of an oscilloscope usually does not lead to success: CAN signals sometimes look quite confused even in an undisturbed state. It may be possible to trigger on error frames using a storage oscilloscope - this type of diagnosis, however, is only possible for expert technicians.

Protocol problems

In rare cases, protocol problems (e.g. faulty or incomplete CANopen implementation, unfavorable timing at boot up, etc.) can be the cause of faults. In this case, a trace of the bus traffic with subsequent evaluation by CANopen experts is required - the Beckhoff support team can help here.

A free channel of a Beckhoff FC5102 CANopen PCI card is suitable for such a trace - Beckhoff provides the necessary trace software on the Internet. Alternatively, it is of course possible to use a normal commercial CAN analysis tool.

Protocol problems can be avoided if devices that have not been conformance tested are not used. The official CANopen Conformance Test (and the appropriate certificate) can be obtained from the CAN in Automation Association (<https://www.can-cia.org>).

9.3 Diagnosis of the multi-function I/Os

This chapter describes the diagnostic options for multi-function I/O communication. This is important, for example, if the 24 V power supply for the multi-function I/Os fails or the circuit breaker has triggered.

Status variable

The status variable `state` can be used for diagnostic purposes. In the normal state, the status variable takes the value `0x__8` (OP, Operational) and thus indicates that everything is error-free.

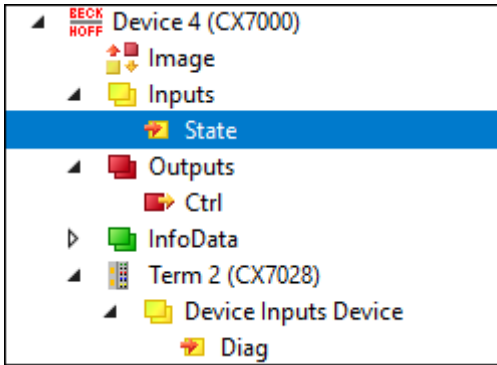


Fig. 69: Multi-function I/O status variable.

The following table shows which values the variables can assume:

Value	Meaning
0x__1	Slave in 'INIT' state
0x__2	Slave in 'PREOP' state
0x__3	Slave in 'BOOT' state
0x__4	Slave in 'SAFEOP' state
0x__8	Slave in 'OP' state
0x001_	Slave signals error
0x002_	Invalid vendorId, productCode... read
0x004_	Initialization error occurred
0x010_	Slave not present

If there is a power supply failure, the multi-function I/Os do not automatically go back into data exchange. To do this, the multi-function I/Os must be reset. A function block that can be used to reset the multi-function I/Os is the `FB_CX70xx_ResetOnBoardIO` [▶ 175] function block.

Notice: If outputs are still set in the PLC, the outputs of the multi-function I/Os are immediately reactivated as soon as the multi-function I/Os are reset with the function block.

Other diagnostic variables

The diagnostic variables `Diag` and `TxPDO State` are currently not in use and are reserved for future use. The variable `Input cycle counter`, on the other hand, increments with each cycle and indicates the number of I/O cycles exchanged with the multi-function I/Os. As soon as the variable is no longer incremented, no more I/O cycles are exchanged with the multi-function I/Os.

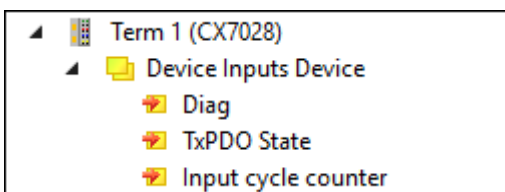


Fig. 70: Further diagnostic variables for multi-function I/Os

Variable	Meaning
Diag	Reserved, currently not used.
TxPDO State	Reserved, currently not used.
Input cycle counter	Incremented by 1 with each cycle. If this counter stops, then no more I/O cycles are exchanged with the multi-function I/Os.

9.4 Memory usage

The CX7050 has 32 MB of RAM that is used by the firmware (TC/RTOS) and TwinCAT (TwinCAT memory). The TwinCAT memory is further divided into the router memory and the PLC memory. The router memory is used for ADS communication and the PLC memory for the actual PLC program including TcConfiguration, mapping and data.

19.1 MB of TwinCAT memory are available to the CX7050. Because the size of the memory is limited, it is important to control the memory usage and to adapt your PLC project if it is exceeded.

Router memory

On the one hand, you can adjust the size of the router memory in TwinCAT and set a smaller router memory depending on the ADS communication actually used.

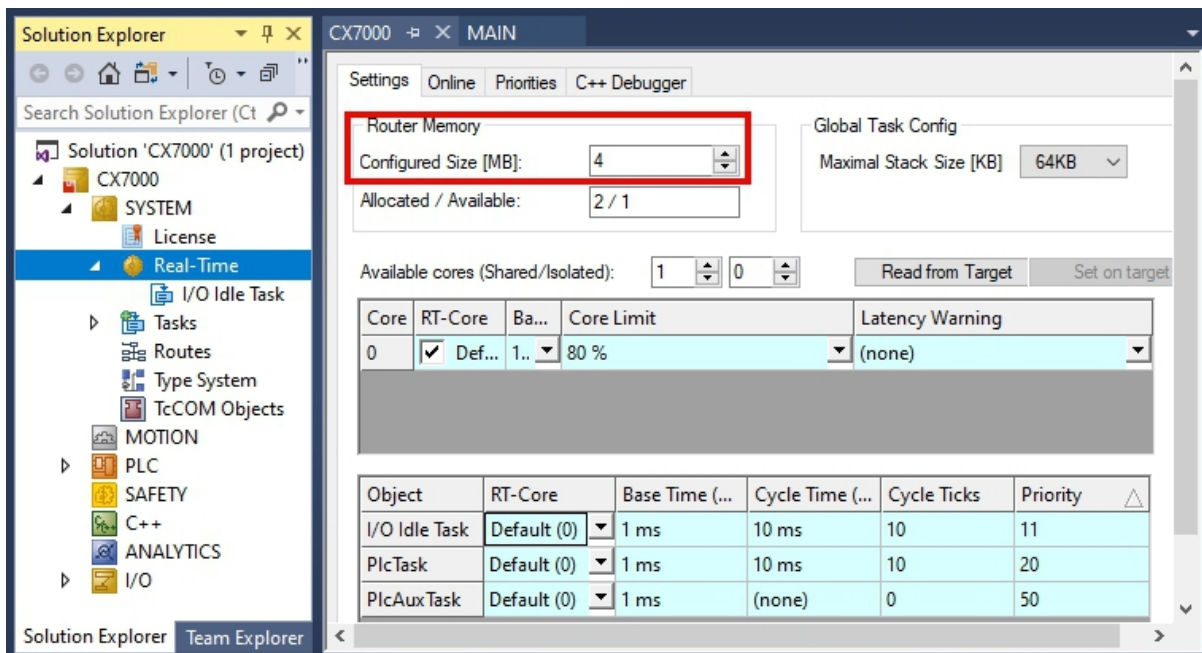


Fig. 71: Settings for router memory in the TwinCAT System Manager.

By default, a value of 32 MB is entered in TwinCAT, which in turn is limited to 9 MB for the CX7050 because of the small RAM in the CX7050. A router memory of 9 MB is usually much too large for a small controller. A router memory of 4 MB is recommended for the CX7050 and can be even smaller if little to no ADS communication is used. However, a router memory of at least 1 MB should be adhered to and should not be any smaller. You can determine how much router memory is used with the function block `FB_GetRouterStatusInfo` or alternatively with the Beckhoff Device Manager.

Note that the router memory is only re-created with a power off/on of the CX7050. A TwinCAT restart is not sufficient. The rule of thumb is: The smaller the router memory for ADS communication is set, the larger the application can be, i.e. the PLC program, TcConfiguration, mapping and data.

Determining the memory usage

With the function block `FB_GetRouterStatusInfo`, or alternatively with the Beckhoff Device Manager, it is possible to determine how large the memory requirement of the router memory is.

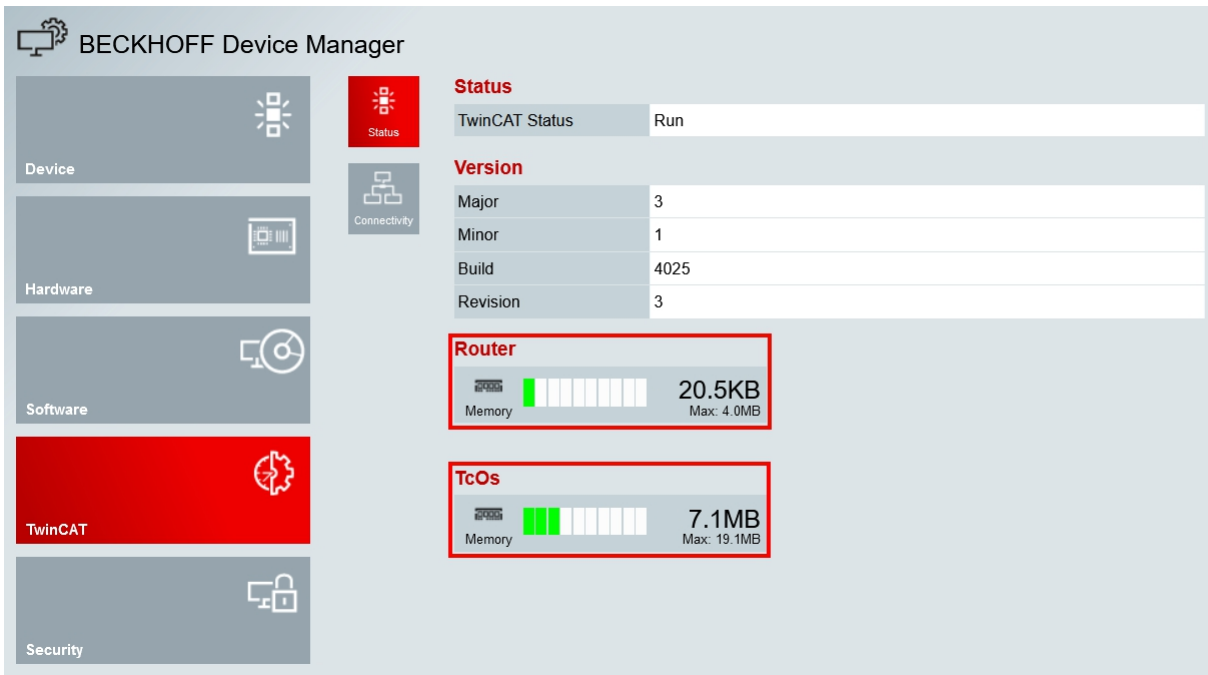


Fig. 72: Utilization of the router and TwinCAT memory.

The **Router** display can be used to determine the memory requirements of the router memory. In this example, 20.5 kB of a maximum of 4 MB are occupied. The **TcOs** display shows the total memory consumption of the TwinCAT memory including router memory and PLC program. In this example, 7.1 MB are occupied in total.

With the help of this display, the size of the PLC program can also be calculated, since the router memory is fixed at 4 MB and is part of the TwinCAT memory. If you subtract the 4 MB from 7.1 MB, therefore, the PLC program occupies 3.1 MB.

Memory reserve

Since in this example the TwinCAT memory occupies 7.1 MB of 19.1 MB, a reserve of 12 MB remains for the PLC program. Note that more memory is needed for a short time for an Online Change in TwinCAT. If you want to use the Online Change function, it is advisable to always have a certain reserve. In the most extreme case, twice the currently consumed PLC program may be required to perform an Online Change. An error message is displayed in TwinCAT if there is not enough memory available for the Online Change.

9.5 Real-time and CPU load

For the proper functioning of the CX7050, it is important to keep an eye on CPU load and real-time compliance. Otherwise, the CX7050 will no longer work reliably in the event of an overload. Note that in the event of an overload, the load indicator is also affected and no longer provides current values. For example, a load of 40% can be incorrectly displayed, but the PLCs are no longer working in real time and the system is overloaded. You should therefore gradually approach the load limit with a small controller.

What is meant by real-time in this context? By default, the PLC works in synchronization with the cycle, which means that a task time is always defined and called at a fixed time. The PLC works in synchronization with the cycle if the task time is not exceeded. For example, if you define a task time of 10 ms and the PLC only needs 2 ms for processing, the selected task time is fine and the PLCs work in synchronization with the cycle.

Even if you do not need the real-time, it is recommended to adhere to the real-time, because otherwise negative effects can occur. These could be connection problems or problems with subsystems such as K-bus or EtherCAT. You can perform the following steps to check whether the CX7050 is optimally set or rather overloaded:

- Observe the exceed counter.
- Check the CPU load.

Observe the exceed counter

The exceed counter is incremented as soon as the PLC no longer works in synchronization with the cycle and the defined task time is exceeded. Ideally, the counter value should be zero.

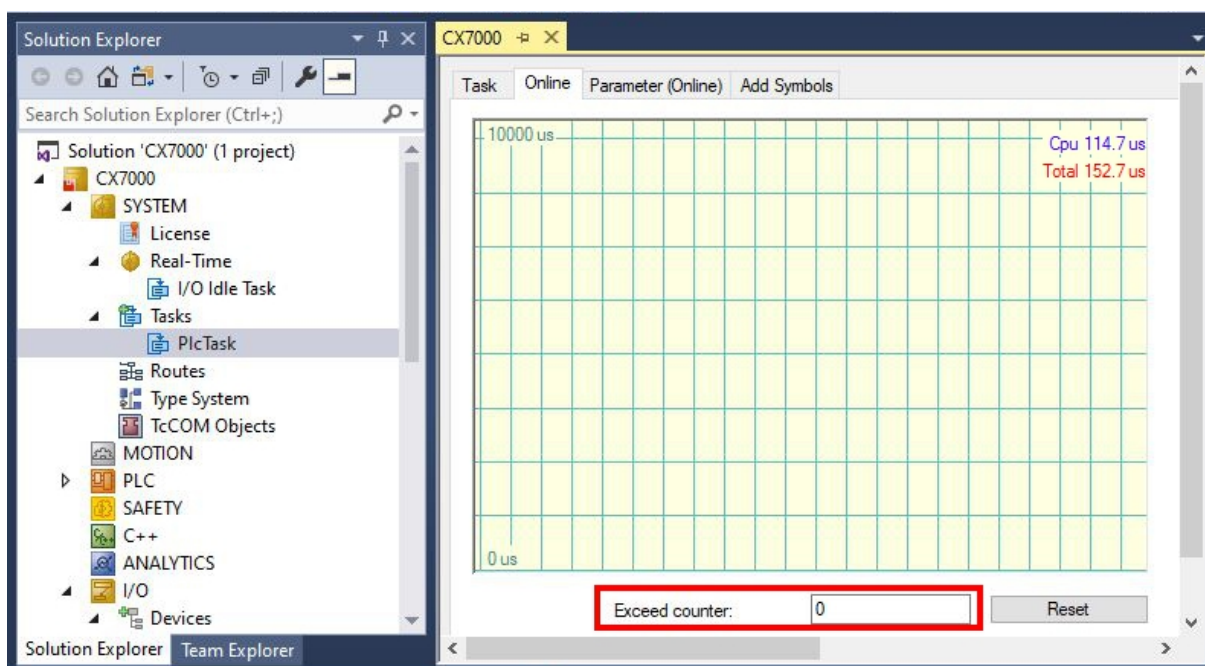


Fig. 73: Display of the exceed counter in TwinCAT.

It is possible for the exceed counter to be incremented at the start of the PLC, for example, because the PLC is called for the first time or certain components are initialized. Observe the exceed counter over a period of several hours. One can only speak of a stable state when the exceed counter is no longer incremented over a longer period of time.

Check the CPU load

In TwinCAT, the CPU load is displayed under Realtime and on the Online tab. Check the value to determine whether you can run additional program code or reduce the task time.

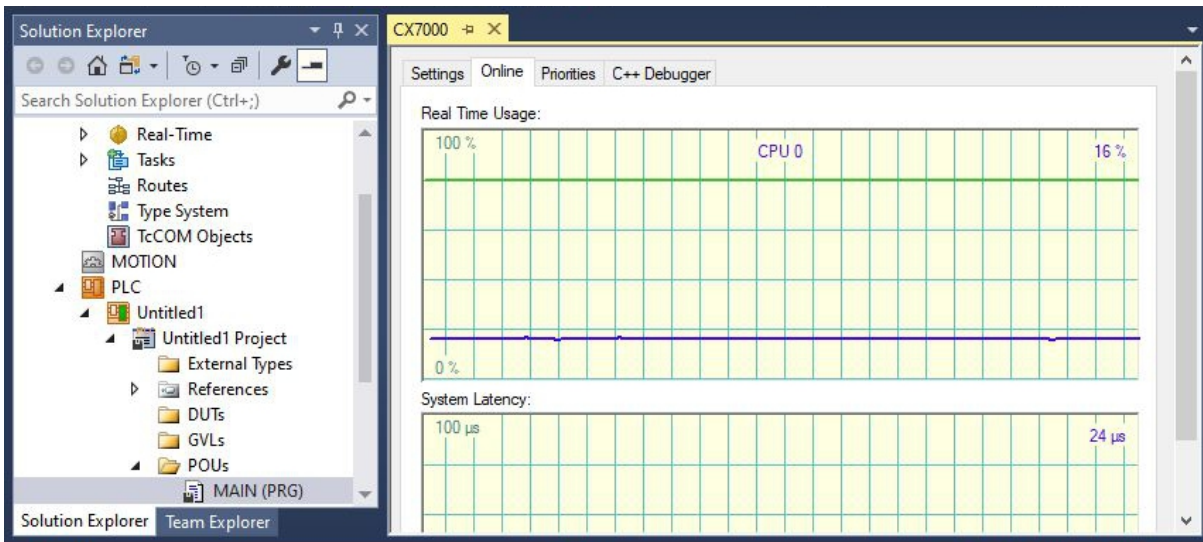


Fig. 74: Display of the CPU load in TwinCAT.

The light green line indicates the preset CPU limit. If the load is $\geq 65\%$, the CX7050 is already very busy and no more code should be executed or the task time shortened. You should not go to the limit and use the CX7050 to full capacity.

Measures in the event of overload

If an overload is detected with the help of the steps shown, the load can be reduced by improving the programming or increasing the task time. To find places in the program code with long processing times, the sample in [Measuring processing time in the PLC program](#) [► 168] can be used.

The selected terminal system also has an influence on the real-time. Depending on the number of terminals, the K-bus, for example, can also take several milliseconds and must be taken into account when choosing the task time. It may well be that, with a set task time of 10 ms, the PLC program only needs 5 ms, but the exceed counter still increments. This is due to the fact that the K-bus requires more than 5 ms for processing and the task time of 10 ms including PLC program and K-bus is exceeded. This problem can be solved by reducing the number of terminals or increasing the task time.

By default, the real-time is set to 80%. This is already the maximum value and an increase to 90% is equivalent to an increase to 100%.

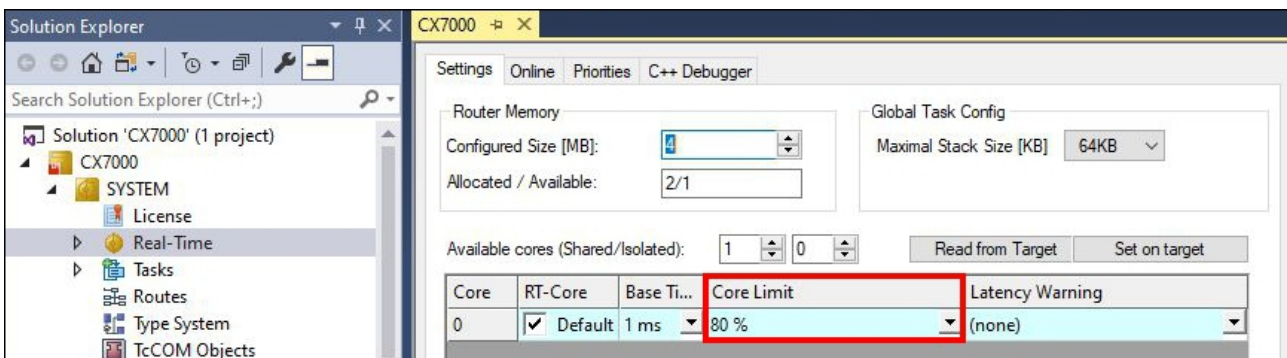


Fig. 75: Setting the real-time load in TwinCAT.

TwinCAT would then consume all the CPU power, and services that the operating system serves would no longer work or would not work adequately. If you increase the real-time load to 90%, you should be aware of the potential consequences for the operating system.

10 Technical data

Table 27: Technical data, dimensions and weights.

	CX7050
Dimensions (W x H x D)	49 mm x 100 mm x 73 mm
Weight	142 g

Table 28: Technical data, general data.

Technical data	CX7050
Processor	ARM Cortex™ M7, 480 MHz
Number of cores	1
Flash memory	512 MB microSD (optionally 1 GB, 2 GB, 4 GB or 8 GB)
Main memory	32 MB SDR (internal, non-extendable)
Number of inputs	8 multifunction inputs (24 V DC)
Number of outputs	4 multifunction outputs (24 V DC, 0.5 A, 1-wire technique)
NOVRAM	4 kB
Interfaces	1 x RJ45 10/100 Mbit/s, 1x USB (max 12 Mbit/s, max 100 mA)
Bus interface	D-sub connector, 9-pin, 1 x CANopen commander (master), CAN 2.0A/2.0B
Data transfer rate	10, 20, 50, 100, 125, 250, 500, 800, 1000 kbaud
Diagnostic LED	1 x TC Status, 1 x WD LED, 1 x ERR LED
Clock	internal, capacitor-buffered real-time clock for time and date (memory > 21 days)
Operating system	TC/RTOS
Control software	TwinCAT 3 Runtime (XAR)
Power supply	24 V _{DC} (-15 %/+20 %)
Max. power consumption	< 2 W (max. 12 W with E-bus/K-bus)
TwinCAT 3 functions included	TC1000 TwinCAT 3 ADS, TC1100 TwinCAT 3 I/O, TC1200 TwinCAT 3 PLC, TF4100 TwinCAT 3 Controller Toolbox, TF4110 TwinCAT 3 Temperature Controller, TF6255 TwinCAT 3 Modbus RTU, TF6340 TwinCAT 3 Serial Communication, TF6701 TwinCAT 3 IoT Communication (MQTT), TF6730 TwinCAT 3 IoT Communicator
Approvals	CE, UL

Table 29: Technical data, I/O terminals.

Technical data	CX7050
I/O connection	via power supply terminal (E-bus or K-bus, automatic recognition)
Power supply for I/O terminals	max. 1.5 A (installation position any, temp. -25...45 °C) max. 1.3 A (installation position horizontal, temp. -25...55 °C) max. 1 A (installation position any, temp. -25...55 °C) max. 1 A (installation position horizontal, temp. -25...60 °C)
Power contacts current load	max. 10 A
Process data on the K-bus	max. 512 bytes In and 512 bytes Out
max. number of terminals (K-bus)	64 (255 with K-bus extension)
E-bus process data	max. 4 kB In and 4 kB Out
max. number of terminals (E-bus)	up to 65534 terminals.

Table 30: Technical data, environmental conditions.

Technical data	CX7050
Ambient temperature during operation	-25° C ... +60° C

Technical data	CX7050
Ambient temperature during storage	-40° C ... +85° C see notes under: Transport and storage [▶ 12]
Relative humidity	95 % no condensation
Vibration resistance	conforms to EN 60068-2-6
Shock resistance	conforms to EN 60068-2-27
EMC immunity	conforms to EN 61000-6-2
EMC emission	conforms to EN 61000-6-4
Protection rating	IP20

Table 31: Technical data, Ethernet interface X001.

Technical data	CX7050
Data transfer medium	4 x 2 twisted pair copper cables category 5 (100 Mbit/s)
Cable length	100 m from switch to CX7050
Data transfer rate	10/100 Mbit/s
Topology	star wiring
Protocols	all non-real-time-capable protocols that are based on TCP or UDP and do not require a real-time extension

Table 32: Technical data, CANopen interface X003.

Technical data	CX7050
Fieldbus	CANopen
Data transfer rate	10, 20, 50, 100, 125, 250, 500, 800, 1,000 kbaud
Bus interface	1 x D sub-socket, 9-pin
Bus devices	max. 64
max. process image	512 Tx PDOs / 512 Rx PDOs
Autobaud	-
Electrical isolation	Yes
Protocol	
CANopen slave	Yes
CAN (virtual slave)	Yes
ADS Interface	yes (only via Ethernet)
Services	
CAN Layer 2	Yes
CAN 2.0A	Yes
CAN 2.0B	Yes, can only be used via the CAN interface

Table 33: Technical data, CANopen interface X003 parameterized as slave.

Technical data	CX7050 parameterized as slave
Fieldbus	CANopen
Data transfer rate	10, 20, 50, 100, 125, 250, 500, 800, 1,000 kbaud
Bus interface	1 x D sub-socket, 9-pin
Extendable process image	Up to 3 virtual slaves in addition
max. process image	4 slaves x (16 Tx PDOs / 16 Rx PDOs (8 bytes per PDO))
Autobaud	Yes
Electrical isolation	Yes
Protocol	
CANopen slave	Yes
CAN (virtual slave)	4 (3 virtual CANopen nodes)
ADS Interface	yes (only via Ethernet)

Technical data	CX7050 parameterized as slave
Services	
CAN Layer 2	No
CAN 2.0A	acc. to CANopen
CAN 2.0B	No

11 Appendix

11.1 CAN Identifier list

The list provided here should assist in identifying and assigning CANopen messages. All the identifiers allocated by the CANopen default identifier allocation are listed, as well as the manufacturer-specific default identifiers issued by BECKHOFF via object 0x5500 (only to be used in networks with node addresses less than 64).

The following values can be used as search aids and "entry points" in the extensive identifier table in the *chm edition of the documentation:

Decimal: [400 \[▶ 202\]](#), [500 \[▶ 207\]](#), [600 \[▶ 207\]](#), [700 \[▶ 203\]](#), [800 \[▶ 203\]](#), [900 \[▶ 204\]](#), [1000 \[▶ 208\]](#), [1100 \[▶ 209\]](#), [1200 \[▶ 205\]](#), [1300 \[▶ 205\]](#), [1400 \[▶ 209\]](#), [1500 \[▶ 210\]](#), [1600 \[▶ 210\]](#), [1700 \[▶ 206\]](#), [1800 \[▶ 212\]](#), [1900 \[▶ 206\]](#)

Hexadecimal: [0x181 \[▶ 202\]](#), [0x1C1 \[▶ 207\]](#), [0x201 \[▶ 202\]](#), [0x301 \[▶ 203\]](#), [0x401 \[▶ 205\]](#), [0x501 \[▶ 205\]](#), [0x601 \[▶ 212\]](#), [0x701 \[▶ 212\]](#)

The identifier distribution via object 0x5500 follows this pattern:

Object	Resulting COB ID (dec)	Resulting COB ID (hex)
Emergency [▶ 202]	129 to 191 [255]	0x81 to 0xBF [0xFF]
TxPDO1 [▶ 202]	385 to 447 [511]	0x181 to 0x1BF [0x1FF]
RxPDO1 [▶ 202]	513 to 575 [639]	0x201 to 0x23F [0x27F]
TxPDO2 [▶ 203]	641 to 676 [767]	0x281 to 0x2BF [0x2FF]
RxPDO2 [▶ 203]	769 to 831 [895]	0x301 to 0x33F [0x37F]
TxDPO3 [▶ 204]	897 to 959 [1023]	0x381 to 0x3BF [0x3FF]
RxPDO3 [▶ 205]	1025 to 1087 [1151]	0x401 to 0x43F [0x47F]
TxPDO4 [▶ 205]	1153 to 1215 [1279]	0x481 to 0x4BF [0x4FF]
RxPDO4 [▶ 205]	1281 to 1343 [1407]	0x501 to 0x53F [0x57F]
TxPDO5 [▶ 206]	1665 to 1727	0x681 to 0x6BF
RxPDO5 [▶ 206]	1921 to 1983	0x781 to 0x7BF
TxPDO6 [▶ 207]	449 to 511	0x1C1 to 0x1FF
RxPDO6 [▶ 207]	577 to 639	0x241 to 0x27F
TxDPO7 [▶ 207]	705 to 767	0x2C1 to 0x2FF
RxPDO7 [▶ 208]	833 to 895	0x341 to 0x37F
TxPDO8 [▶ 208]	961 to 1023	0x3C1 to 0x3FF
RxPDO8 [▶ 209]	1089 to 1151	0x441 to 0x47F
TxPDO9 [▶ 209]	1217 to 1279	0x4C1 to 0x4FF
RxPDO9 [▶ 209]	1345 to 1407	0x541 to 0x57F
TxDPO10 [▶ 210]	1473 to 1535	0x5C1 to 0x5FF
RxPDO10 [▶ 210]	1601 to 1663	0x641 to 0x67F
TxPDO11 [▶ 211]	1729 to 1791	0x6C1 to 0x6FF
RxPDO11 [▶ 211]	1857 to 1919	0x741 to 0x77F
SDO (Tx) [▶ 211]	1409 to 1471 [1535]	0x581 to 0x5BF [0x5FF]
SDO (Rx) [▶ 212]	1537 to 1599 [1663]	0x601 to 0x63F [0x67F]
Guarding / Heartbeat/ Bootup [▶ 212]	1793 to 1855 [1919]	0x701 to 0x73F [0x77F]

Identifier List

Identifiers marked with * are given manufacturer-specific assignments on the Bus Couplers after writing index 0x5500

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
0	0x00	NMT	149	0x95	EMCY Nd.21	171	0xAB	EMCY Nd.43
128	0x80	SYNC	150	0x96	EMCY Nd.22	172	0xAC	EMCY Nd.44
129	0x81	EMCY Nd.1	151	0x97	EMCY Nd.23	173	0xAD	EMCY Nd.45
130	0x82	EMCY Nd.2	152	0x98	EMCY Nd.24	174	0xAE	EMCY Nd.46
131	0x83	EMCY Nd.3	153	0x99	EMCY Nd.25	175	0xAF	EMCY Nd.47
132	0x84	EMCY Nd.4	154	0x9A	EMCY Nd.26	176	0xB0	EMCY Nd.48
133	0x85	EMCY Nd.5	155	0x9B	EMCY Nd.27	177	0xB1	EMCY Nd.49
134	0x86	EMCY Nd.6	156	0x9C	EMCY Nd.28	178	0xB2	EMCY Nd.50
135	0x87	EMCY Nd.7	157	0x9D	EMCY Nd.29	179	0xB3	EMCY Nd.51
136	0x88	EMCY Nd.8	158	0x9E	EMCY Nd.30	180	0xB4	EMCY Nd.52
137	0x89	EMCY Nd.9	159	0x9F	EMCY Nd.31	181	0xB5	EMCY Nd.53
138	0x8A	EMCY Nd.10	160	0xA0	EMCY Nd.32	182	0xB6	EMCY Nd.54
139	0x8B	EMCY Nd.11	161	0xA1	EMCY Nd.33	183	0xB7	EMCY Nd.55
140	0x8C	EMCY Nd.12	162	0xA2	EMCY Nd.34	184	0xB8	EMCY Nd.56
141	0x8D	EMCY Nd.13	163	0xA3	EMCY Nd.35	185	0xB9	EMCY Nd.57
142	0x8E	EMCY Nd.14	164	0xA4	EMCY Nd.36	186	0xBA	EMCY Nd.58
143	0x8F	EMCY Nd.15	165	0xA5	EMCY Nd.37	187	0xBB	EMCY Nd.59
144	0x90	EMCY Nd.16	166	0xA6	EMCY Nd.38	188	0xBC	EMCY Nd.60
145	0x91	EMCY Nd.17	167	0xA7	EMCY Nd.39	189	0xBD	EMCY Nd.61
146	0x92	EMCY Nd.18	168	0xA8	EMCY Nd.40	190	0xBE	EMCY Nd.62
147	0x93	EMCY Nd.19	169	0xA9	EMCY Nd.41	191	0xBF	EMCY Nd.63
148	0x94	EMCY Nd.20	170	0xAA	EMCY Nd.42			

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
385	0x181	TxPDO1, DI, Nd.1	406	0x196	TxPDO1, DI, Nd.22	427	0x1AB	TxPDO1, DI, Nd.43
386	0x182	TxPDO1, DI, Nd.2	407	0x197	TxPDO1, DI, Nd.23	428	0x1AC	TxPDO1, DI, Nd.44
387	0x183	TxPDO1, DI, Nd.3	408	0x198	TxPDO1, DI, Nd.24	429	0x1AD	TxPDO1, DI, Nd.45
388	0x184	TxPDO1, DI, Nd.4	409	0x199	TxPDO1, DI, Nd.25	430	0x1AE	TxPDO1, DI, Nd.46
389	0x185	TxPDO1, DI, Nd.5	410	0x19A	TxPDO1, DI, Nd.26	431	0x1AF	TxPDO1, DI, Nd.47
390	0x186	TxPDO1, DI, Nd.6	411	0x19B	TxPDO1, DI, Nd.27	432	0x1B0	TxPDO1, DI, Nd.48
391	0x187	TxPDO1, DI, Nd.7	412	0x19C	TxPDO1, DI, Nd.28	433	0x1B1	TxPDO1, DI, Nd.49
392	0x188	TxPDO1, DI, Nd.8	413	0x19D	TxPDO1, DI, Nd.29	434	0x1B2	TxPDO1, DI, Nd.50
393	0x189	TxPDO1, DI, Nd.9	414	0x19E	TxPDO1, DI, Nd.30	435	0x1B3	TxPDO1, DI, Nd.51
394	0x18A	TxPDO1, DI, Nd.10	415	0x19F	TxPDO1, DI, Nd.31	436	0x1B4	TxPDO1, DI, Nd.52
395	0x18B	TxPDO1, DI, Nd.11	416	0x1A0	TxPDO1, DI, Nd.32	437	0x1B5	TxPDO1, DI, Nd.53
396	0x18C	TxPDO1, DI, Nd.12	417	0x1A1	TxPDO1, DI, Nd.33	438	0x1B6	TxPDO1, DI, Nd.54
397	0x18D	TxPDO1, DI, Nd.13	418	0x1A2	TxPDO1, DI, Nd.34	439	0x1B7	TxPDO1, DI, Nd.55
398	0x18E	TxPDO1, DI, Nd.14	419	0x1A3	TxPDO1, DI, Nd.35	440	0x1B8	TxPDO1, DI, Nd.56
399	0x18F	TxPDO1, DI, Nd.15	420	0x1A4	TxPDO1, DI, Nd.36	441	0x1B9	TxPDO1, DI, Nd.57
400	0x190	TxPDO1, DI, Nd.16	421	0x1A5	TxPDO1, DI, Nd.37	442	0x1BA	TxPDO1, DI, Nd.58
401	0x191	TxPDO1, DI, Nd.17	422	0x1A6	TxPDO1, DI, Nd.38	443	0x1BB	TxPDO1, DI, Nd.59
402	0x192	TxPDO1, DI, Nd.18	423	0x1A7	TxPDO1, DI, Nd.39	444	0x1BC	TxPDO1, DI, Nd.60
403	0x193	TxPDO1, DI, Nd.19	424	0x1A8	TxPDO1, DI, Nd.40	445	0x1BD	TxPDO1, DI, Nd.61
404	0x194	TxPDO1, DI, Nd.20	425	0x1A9	TxPDO1, DI, Nd.41	446	0x1BE	TxPDO1, DI, Nd.62
405	0x195	TxPDO1, DI, Nd.21	426	0x1AA	TxPDO1, DI, Nd.42	447	0x1BF	TxPDO1, DI, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
513	0x201	RxPDO1, DO, Nd.1	534	0x216	RxPDO1, DO, Nd.22	555	0x22B	RxPDO1, DO, Nd.43
514	0x202	RxPDO1, DO, Nd.2	535	0x217	RxPDO1, DO, Nd.23	556	0x22C	RxPDO1, DO, Nd.44
515	0x203	RxPDO1, DO, Nd.3	536	0x218	RxPDO1, DO, Nd.24	557	0x22D	RxPDO1, DO, Nd.45
516	0x204	RxPDO1, DO, Nd.4	537	0x219	RxPDO1, DO, Nd.25	558	0x22E	RxPDO1, DO, Nd.46

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
517	0x205	RxPDO1, DO, Nd.5	538	0x21A	RxPDO1, DO, Nd.26	559	0x22F	RxPDO1, DO, Nd.47
518	0x206	RxPDO1, DO, Nd.6	539	0x21B	RxPDO1, DO, Nd.27	560	0x230	RxPDO1, DO, Nd.48
519	0x207	RxPDO1, DO, Nd.7	540	0x21C	RxPDO1, DO, Nd.28	561	0x231	RxPDO1, DO, Nd.49
520	0x208	RxPDO1, DO, Nd.8	541	0x21D	RxPDO1, DO, Nd.29	562	0x232	RxPDO1, DO, Nd.50
521	0x209	RxPDO1, DO, Nd.9	542	0x21E	RxPDO1, DO, Nd.30	563	0x233	RxPDO1, DO, Nd.51
522	0x20A	RxPDO1, DO, Nd.10	543	0x21F	RxPDO1, DO, Nd.31	564	0x234	RxPDO1, DO, Nd.52
523	0x20B	RxPDO1, DO, Nd.11	544	0x220	RxPDO1, DO, Nd.32	565	0x235	RxPDO1, DO, Nd.53
524	0x20C	RxPDO1, DO, Nd.12	545	0x221	RxPDO1, DO, Nd.33	566	0x236	RxPDO1, DO, Nd.54
525	0x20D	RxPDO1, DO, Nd.13	546	0x222	RxPDO1, DO, Nd.34	567	0x237	RxPDO1, DO, Nd.55
526	0x20E	RxPDO1, DO, Nd.14	547	0x223	RxPDO1, DO, Nd.35	568	0x238	RxPDO1, DO, Nd.56
527	0x20F	RxPDO1, DO, Nd.15	548	0x224	RxPDO1, DO, Nd.36	569	0x239	RxPDO1, DO, Nd.57
528	0x210	RxPDO1, DO, Nd.16	549	0x225	RxPDO1, DO, Nd.37	570	0x23A	RxPDO1, DO, Nd.58
529	0x211	RxPDO1, DO, Nd.17	550	0x226	RxPDO1, DO, Nd.38	571	0x23B	RxPDO1, DO, Nd.59
530	0x212	RxPDO1, DO, Nd.18	551	0x227	RxPDO1, DO, Nd.39	572	0x23C	RxPDO1, DO, Nd.60
531	0x213	RxPDO1, DO, Nd.19	552	0x228	RxPDO1, DO, Nd.40	573	0x23D	RxPDO1, DO, Nd.61
532	0x214	RxPDO1, DO, Nd.20	553	0x229	RxPDO1, DO, Nd.41	574	0x23E	RxPDO1, DO, Nd.62
533	0x215	RxPDO1, DO, Nd.21	554	0x22A	RxPDO1, DO, Nd.42	575	0x23F	RxPDO1, DO, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
641	0x281	TxPDO2, AI, Nd.1	662	0x296	TxPDO2, AI, Nd.22	683	0x2AB	TxPDO2, AI, Nd.43
642	0x282	TxPDO2, AI, Nd.2	663	0x297	TxPDO2, AI, Nd.23	684	0x2AC	TxPDO2, AI, Nd.44
643	0x283	TxPDO2, AI, Nd.3	664	0x298	TxPDO2, AI, Nd.24	685	0x2AD	TxPDO2, AI, Nd.45
644	0x284	TxPDO2, AI, Nd.4	665	0x299	TxPDO2, AI, Nd.25	686	0x2AE	TxPDO2, AI, Nd.46
645	0x285	TxPDO2, AI, Nd.5	666	0x29A	TxPDO2, AI, Nd.26	687	0x2AF	TxPDO2, AI, Nd.47
646	0x286	TxPDO2, AI, Nd.6	667	0x29B	TxPDO2, AI, Nd.27	688	0x2B0	TxPDO2, AI, Nd.48
647	0x287	TxPDO2, AI, Nd.7	668	0x29C	TxPDO2, AI, Nd.28	689	0x2B1	TxPDO2, AI, Nd.49
648	0x288	TxPDO2, AI, Nd.8	669	0x29D	TxPDO2, AI, Nd.29	690	0x2B2	TxPDO2, AI, Nd.50
649	0x289	TxPDO2, AI, Nd.9	670	0x29E	TxPDO2, AI, Nd.30	691	0x2B3	TxPDO2, AI, Nd.51
650	0x28A	TxPDO2, AI, Nd.10	671	0x29F	TxPDO2, AI, Nd.31	692	0x2B4	TxPDO2, AI, Nd.52
651	0x28B	TxPDO2, AI, Nd.11	672	0x2A0	TxPDO2, AI, Nd.32	693	0x2B5	TxPDO2, AI, Nd.53
652	0x28C	TxPDO2, AI, Nd.12	673	0x2A1	TxPDO2, AI, Nd.33	694	0x2B6	TxPDO2, AI, Nd.54
653	0x28D	TxPDO2, AI, Nd.13	674	0x2A2	TxPDO2, AI, Nd.34	695	0x2B7	TxPDO2, AI, Nd.55
654	0x28E	TxPDO2, AI, Nd.14	675	0x2A3	TxPDO2, AI, Nd.35	696	0x2B8	TxPDO2, AI, Nd.56
655	0x28F	TxPDO2, AI, Nd.15	676	0x2A4	TxPDO2, AI, Nd.36	697	0x2B9	TxPDO2, AI, Nd.57
656	0x290	TxPDO2, AI, Nd.16	677	0x2A5	TxPDO2, AI, Nd.37	698	0x2BA	TxPDO2, AI, Nd.58
657	0x291	TxPDO2, AI, Nd.17	678	0x2A6	TxPDO2, AI, Nd.38	699	0x2BB	TxPDO2, AI, Nd.59
658	0x292	TxPDO2, AI, Nd.18	679	0x2A7	TxPDO2, AI, Nd.39	700	0x2BC	TxPDO2, AI, Nd.60
659	0x293	TxPDO2, AI, Nd.19	680	0x2A8	TxPDO2, AI, Nd.40	701	0x2BD	TxPDO2, AI, Nd.61
660	0x294	TxPDO2, AI, Nd.20	681	0x2A9	TxPDO2, AI, Nd.41	702	0x2BE	TxPDO2, AI, Nd.62
661	0x295	TxPDO2, AI, Nd.21	682	0x2AA	TxPDO2, AI, Nd.42	703	0x2BF	TxPDO2, AI, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
769	0x301	RxPDO2, AO, Nd.1	790	0x316	RxPDO2, AO, Nd.22	811	0x32B	RxPDO2, AO, Nd.43

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
770	0x302	RxPDO2, AO, Nd.2	791	0x317	RxPDO2, AO, Nd.23	812	0x32C	RxPDO2, AO, Nd.44
771	0x303	RxPDO2, AO, Nd.3	792	0x318	RxPDO2, AO, Nd.24	813	0x32D	RxPDO2, AO, Nd.45
772	0x304	RxPDO2, AO, Nd.4	793	0x319	RxPDO2, AO, Nd.25	814	0x32E	RxPDO2, AO, Nd.46
773	0x305	RxPDO2, AO, Nd.5	794	0x31A	RxPDO2, AO, Nd.26	815	0x32F	RxPDO2, AO, Nd.47
774	0x306	RxPDO2, AO, Nd.6	795	0x31B	RxPDO2, AO, Nd.27	816	0x330	RxPDO2, AO, Nd.48
775	0x307	RxPDO2, AO, Nd.7	796	0x31C	RxPDO2, AO, Nd.28	817	0x331	RxPDO2, AO, Nd.49
776	0x308	RxPDO2, AO, Nd.8	797	0x31D	RxPDO2, AO, Nd.29	818	0x332	RxPDO2, AO, Nd.50
777	0x309	RxPDO2, AO, Nd.9	798	0x31E	RxPDO2, AO, Nd.30	819	0x333	RxPDO2, AO, Nd.51
778	0x30A	RxPDO2, AO, Nd.10	799	0x31F	RxPDO2, AO, Nd.31	820	0x334	RxPDO2, AO, Nd.52
779	0x30B	RxPDO2, AO, Nd.11	800	0x320	RxPDO2, AO, Nd.32	821	0x335	RxPDO2, AO, Nd.53
780	0x30C	RxPDO2, AO, Nd.12	801	0x321	RxPDO2, AO, Nd.33	822	0x336	RxPDO2, AO, Nd.54
781	0x30D	RxPDO2, AO, Nd.13	802	0x322	RxPDO2, AO, Nd.34	823	0x337	RxPDO2, AO, Nd.55
782	0x30E	RxPDO2, AO, Nd.14	803	0x323	RxPDO2, AO, Nd.35	824	0x338	RxPDO2, AO, Nd.56
783	0x30F	RxPDO2, AO, Nd.15	804	0x324	RxPDO2, AO, Nd.36	825	0x339	RxPDO2, AO, Nd.57
784	0x310	RxPDO2, AO, Nd.16	805	0x325	RxPDO2, AO, Nd.37	826	0x33A	RxPDO2, AO, Nd.58
785	0x311	RxPDO2, AO, Nd.17	806	0x326	RxPDO2, AO, Nd.38	827	0x33B	RxPDO2, AO, Nd.59
786	0x312	RxPDO2, AO, Nd.18	807	0x327	RxPDO2, AO, Nd.39	828	0x33C	RxPDO2, AO, Nd.60
787	0x313	RxPDO2, AO, Nd.19	808	0x328	RxPDO2, AO, Nd.40	829	0x33D	RxPDO2, AO, Nd.61
788	0x314	RxPDO2, AO, Nd.20	809	0x329	RxPDO2, AO, Nd.41	830	0x33E	RxPDO2, AO, Nd.62
789	0x315	RxPDO2, AO, Nd.21	810	0x32A	RxPDO2, AO, Nd.42	831	0x33F	RxPDO2, AO, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
897	0x381	TxPDO3*, Nd.1	918	0x396	TxPDO3*, Nd.22	939	0x3AB	TxPDO3*, Nd.43
898	0x382	TxPDO3*, Nd.2	919	0x397	TxPDO3*, Nd.23	940	0x3AC	TxPDO3*, Nd.44
899	0x383	TxPDO3*, Nd.3	920	0x398	TxPDO3*, Nd.24	941	0x3AD	TxPDO3*, Nd.45
900	0x384	TxPDO3*, Nd.4	921	0x399	TxPDO3*, Nd.25	942	0x3AE	TxPDO3*, Nd.46
901	0x385	TxPDO3*, Nd.5	922	0x39A	TxPDO3*, Nd.26	943	0x3AF	TxPDO3*, Nd.47
902	0x386	TxPDO3*, Nd.6	923	0x39B	TxPDO3*, Nd.27	944	0x3B0	TxPDO3*, Nd.48
903	0x387	TxPDO3*, Nd.7	924	0x39C	TxPDO3*, Nd.28	945	0x3B1	TxPDO3*, Nd.49
904	0x388	TxPDO3*, Nd.8	925	0x39D	TxPDO3*, Nd.29	946	0x3B2	TxPDO3*, Nd.50
905	0x389	TxPDO3*, Nd.9	926	0x39E	TxPDO3*, Nd.30	947	0x3B3	TxPDO3*, Nd.51
906	0x38A	TxPDO3*, Nd.10	927	0x39F	TxPDO3*, Nd.31	948	0x3B4	TxPDO3*, Nd.52
907	0x38B	TxPDO3*, Nd.11	928	0x3A0	TxPDO3*, Nd.32	949	0x3B5	TxPDO3*, Nd.53
908	0x38C	TxPDO3*, Nd.12	929	0x3A1	TxPDO3*, Nd.33	950	0x3B6	TxPDO3*, Nd.54
909	0x38D	TxPDO3*, Nd.13	930	0x3A2	TxPDO3*, Nd.34	951	0x3B7	TxPDO3*, Nd.55
910	0x38E	TxPDO3*, Nd.14	931	0x3A3	TxPDO3*, Nd.35	952	0x3B8	TxPDO3*, Nd.56
911	0x38F	TxPDO3*, Nd.15	932	0x3A4	TxPDO3*, Nd.36	953	0x3B9	TxPDO3*, Nd.57
912	0x390	TxPDO3*, Nd.16	933	0x3A5	TxPDO3*, Nd.37	954	0x3BA	TxPDO3*, Nd.58
913	0x391	TxPDO3*, Nd.17	934	0x3A6	TxPDO3*, Nd.38	955	0x3BB	TxPDO3*, Nd.59
914	0x392	TxPDO3*, Nd.18	935	0x3A7	TxPDO3*, Nd.39	956	0x3BC	TxPDO3*, Nd.60
915	0x393	TxPDO3*, Nd.19	936	0x3A8	TxPDO3*, Nd.40	957	0x3BD	TxPDO3*, Nd.61
916	0x394	TxPDO3*, Nd.20	937	0x3A9	TxPDO3*, Nd.41	958	0x3BE	TxPDO3*, Nd.62
917	0x395	TxPDO3*, Nd.21	938	0x3AA	TxPDO3*, Nd.42	959	0x3BF	TxPDO3*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1025	0x401	RxPDO3*, Nd.1	1046	0x416	RxPDO3*, Nd.22	1067	0x42B	RxPDO3*, Nd.43
1026	0x402	RxPDO3*, Nd.2	1047	0x417	RxPDO3*, Nd.23	1068	0x42C	RxPDO3*, Nd.44
1027	0x403	RxPDO3*, Nd.3	1048	0x418	RxPDO3*, Nd.24	1069	0x42D	RxPDO3*, Nd.45
1028	0x404	RxPDO3*, Nd.4	1049	0x419	RxPDO3*, Nd.25	1070	0x42E	RxPDO3*, Nd.46
1029	0x405	RxPDO3*, Nd.5	1050	0x41A	RxPDO3*, Nd.26	1071	0x42F	RxPDO3*, Nd.47
1030	0x406	RxPDO3*, Nd.6	1051	0x41B	RxPDO3*, Nd.27	1072	0x430	RxPDO3*, Nd.48
1031	0x407	RxPDO3*, Nd.7	1052	0x41C	RxPDO3*, Nd.28	1073	0x431	RxPDO3*, Nd.49
1032	0x408	RxPDO3*, Nd.8	1053	0x41D	RxPDO3*, Nd.29	1074	0x432	RxPDO3*, Nd.50
1033	0x409	RxPDO3*, Nd.9	1054	0x41E	RxPDO3*, Nd.30	1075	0x433	RxPDO3*, Nd.51
1034	0x40A	RxPDO3*, Nd.10	1055	0x41F	RxPDO3*, Nd.31	1076	0x434	RxPDO3*, Nd.52
1035	0x40B	RxPDO3*, Nd.11	1056	0x420	RxPDO3*, Nd.32	1077	0x435	RxPDO3*, Nd.53
1036	0x40C	RxPDO3*, Nd.12	1057	0x421	RxPDO3*, Nd.33	1078	0x436	RxPDO3*, Nd.54
1037	0x40D	RxPDO3*, Nd.13	1058	0x422	RxPDO3*, Nd.34	1079	0x437	RxPDO3*, Nd.55
1038	0x40E	RxPDO3*, Nd.14	1059	0x423	RxPDO3*, Nd.35	1080	0x438	RxPDO3*, Nd.56
1039	0x40F	RxPDO3*, Nd.15	1060	0x424	RxPDO3*, Nd.36	1081	0x439	RxPDO3*, Nd.57
1040	0x410	RxPDO3*, Nd.16	1061	0x425	RxPDO3*, Nd.37	1082	0x43A	RxPDO3*, Nd.58
1041	0x411	RxPDO3*, Nd.17	1062	0x426	RxPDO3*, Nd.38	1083	0x43B	RxPDO3*, Nd.59
1042	0x412	RxPDO3*, Nd.18	1063	0x427	RxPDO3*, Nd.39	1084	0x43C	RxPDO3*, Nd.60
1043	0x413	RxPDO3*, Nd.19	1064	0x428	RxPDO3*, Nd.40	1085	0x43D	RxPDO3*, Nd.61
1044	0x414	RxPDO3*, Nd.20	1065	0x429	RxPDO3*, Nd.41	1086	0x43E	RxPDO3*, Nd.62
1045	0x415	RxPDO3*, Nd.21	1066	0x42A	RxPDO3*, Nd.42	1087	0x43F	RxPDO3*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1153	0x481	TxPDO4*, Nd.1	1174	0x496	TxPDO4*, Nd.22	1195	0x4AB	TxPDO4*, Nd.43
1154	0x482	TxPDO4*, Nd.2	1175	0x497	TxPDO4*, Nd.23	1196	0x4AC	TxPDO4*, Nd.44
1155	0x483	TxPDO4*, Nd.3	1176	0x498	TxPDO4*, Nd.24	1197	0x4AD	TxPDO4*, Nd.45
1156	0x484	TxPDO4*, Nd.4	1177	0x499	TxPDO4*, Nd.25	1198	0x4AE	TxPDO4*, Nd.46
1157	0x485	TxPDO4*, Nd.5	1178	0x49A	TxPDO4*, Nd.26	1199	0x4AF	TxPDO4*, Nd.47
1158	0x486	TxPDO4*, Nd.6	1179	0x49B	TxPDO4*, Nd.27	1200	0x4B0	TxPDO4*, Nd.48
1159	0x487	TxPDO4*, Nd.7	1180	0x49C	TxPDO4*, Nd.28	1201	0x4B1	TxPDO4*, Nd.49
1160	0x488	TxPDO4*, Nd.8	1181	0x49D	TxPDO4*, Nd.29	1202	0x4B2	TxPDO4*, Nd.50
1161	0x489	TxPDO4*, Nd.9	1182	0x49E	TxPDO4*, Nd.30	1203	0x4B3	TxPDO4*, Nd.51
1162	0x48A	TxPDO4*, Nd.10	1183	0x49F	TxPDO4*, Nd.31	1204	0x4B4	TxPDO4*, Nd.52
1163	0x48B	TxPDO4*, Nd.11	1184	0x4A0	TxPDO4*, Nd.32	1205	0x4B5	TxPDO4*, Nd.53
1164	0x48C	TxPDO4*, Nd.12	1185	0x4A1	TxPDO4*, Nd.33	1206	0x4B6	TxPDO4*, Nd.54
1165	0x48D	TxPDO4*, Nd.13	1186	0x4A2	TxPDO4*, Nd.34	1207	0x4B7	TxPDO4*, Nd.55
1166	0x48E	TxPDO4*, Nd.14	1187	0x4A3	TxPDO4*, Nd.35	1208	0x4B8	TxPDO4*, Nd.56
1167	0x48F	TxPDO4*, Nd.15	1188	0x4A4	TxPDO4*, Nd.36	1209	0x4B9	TxPDO4*, Nd.57
1168	0x490	TxPDO4*, Nd.16	1189	0x4A5	TxPDO4*, Nd.37	1210	0x4BA	TxPDO4*, Nd.58
1169	0x491	TxPDO4*, Nd.17	1190	0x4A6	TxPDO4*, Nd.48	1211	0x4BB	TxPDO4*, Nd.59
1170	0x492	TxPDO4*, Nd.18	1191	0x4A7	TxPDO4*, Nd.49	1212	0x4BC	TxPDO4*, Nd.60
1171	0x493	TxPDO4*, Nd.19	1192	0x4A8	TxPDO4*, Nd.40	1213	0x4BD	TxPDO4*, Nd.61
1172	0x494	TxPDO4*, Nd.20	1193	0x4A9	TxPDO4*, Nd.41	1214	0x4BE	TxPDO4*, Nd.62
1173	0x495	TxPDO4*, Nd.21	1194	0x4AA	TxPDO4*, Nd.42	1215	0x4BF	TxPDO4*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1281	0x501	RxPDO4*, Nd.1	1302	0x516	RxPDO4*, Nd.22	1323	0x52B	RxPDO4*, Nd.43
1282	0x502	RxPDO4*, Nd.2	1303	0x517	RxPDO4*, Nd.23	1324	0x52C	RxPDO4*, Nd.44
1283	0x503	RxPDO4*, Nd.3	1304	0x518	RxPDO4*, Nd.24	1325	0x52D	RxPDO4*, Nd.45
1284	0x504	RxPDO4*, Nd.4	1305	0x519	RxPDO4*, Nd.25	1326	0x52E	RxPDO4*, Nd.46
1285	0x505	RxPDO4*, Nd.5	1306	0x51A	RxPDO4*, Nd.26	1327	0x52F	RxPDO4*, Nd.47
1286	0x506	RxPDO4*, Nd.6	1307	0x51B	RxPDO4*, Nd.27	1328	0x530	RxPDO4*, Nd.48
1287	0x507	RxPDO4*, Nd.7	1308	0x51C	RxPDO4*, Nd.28	1329	0x531	RxPDO4*, Nd.49
1288	0x508	RxPDO4*, Nd.8	1309	0x51D	RxPDO4*, Nd.29	1330	0x532	RxPDO4*, Nd.50
1289	0x509	RxPDO4*, Nd.9	1310	0x51E	RxPDO4*, Nd.30	1331	0x533	RxPDO4*, Nd.51
1290	0x50A	RxPDO4*, Nd.10	1311	0x51F	RxPDO4*, Nd.31	1332	0x534	RxPDO4*, Nd.52
1291	0x50B	RxPDO4*, Nd.11	1312	0x520	RxPDO4*, Nd.32	1333	0x535	RxPDO4*, Nd.53

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1292	0x50C	RxPDO4*, Nd.12	1313	0x521	RxPDO4*, Nd.33	1334	0x536	RxPDO4*, Nd.54
1293	0x50D	RxPDO4*, Nd.13	1314	0x522	RxPDO4*, Nd.34	1335	0x537	RxPDO4*, Nd.55
1294	0x50E	RxPDO4*, Nd.14	1315	0x523	RxPDO4*, Nd.35	1336	0x538	RxPDO4*, Nd.56
1295	0x50F	RxPDO4*, Nd.15	1316	0x524	RxPDO4*, Nd.36	1337	0x539	RxPDO4*, Nd.57
1296	0x510	RxPDO4*, Nd.16	1317	0x525	RxPDO4*, Nd.37	1338	0x53A	RxPDO4*, Nd.58
1297	0x511	RxPDO4*, Nd.17	1318	0x526	RxPDO4*, Nd.38	1339	0x53B	RxPDO4*, Nd.59
1298	0x512	RxPDO4*, Nd.18	1319	0x527	RxPDO4*, Nd.39	1340	0x53C	RxPDO4*, Nd.60
1299	0x513	RxPDO4*, Nd.19	1320	0x528	RxPDO4*, Nd.40	1341	0x53D	RxPDO4*, Nd.61
1300	0x514	RxPDO4*, Nd.20	1321	0x529	RxPDO4*, Nd.41	1342	0x53E	RxPDO4*, Nd.62
1301	0x515	RxPDO4*, Nd.21	1322	0x52A	RxPDO4*, Nd.42	1343	0x53F	RxPDO4*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1665	0x681	TxPDO5*, Nd.1	1686	0x696	TxPDO5*, Nd.22	1707	0x6AB	TxPDO5*, Nd.43
1666	0x682	TxPDO5*, Nd.2	1687	0x697	TxPDO5*, Nd.23	1708	0x6AC	TxPDO5*, Nd.44
1667	0x683	TxPDO5*, Nd.3	1688	0x698	TxPDO5*, Nd.24	1709	0x6AD	TxPDO5*, Nd.45
1668	0x684	TxPDO5*, Nd.4	1689	0x699	TxPDO5*, Nd.25	1710	0x6AE	TxPDO5*, Nd.46
1669	0x685	TxPDO5*, Nd.5	1690	0x69A	TxPDO5*, Nd.26	1711	0x6AF	TxPDO5*, Nd.47
1670	0x686	TxPDO5*, Nd.6	1691	0x69B	TxPDO5*, Nd.27	1712	0x6B0	TxPDO5*, Nd.48
1671	0x687	TxPDO5*, Nd.7	1692	0x69C	TxPDO5*, Nd.28	1713	0x6B1	TxPDO5*, Nd.49
1672	0x688	TxPDO5*, Nd.8	1693	0x69D	TxPDO5*, Nd.29	1714	0x6B2	TxPDO5*, Nd.50
1673	0x689	TxPDO5*, Nd.9	1694	0x69E	TxPDO5*, Nd.30	1715	0x6B3	TxPDO5*, Nd.51
1674	0x68A	TxPDO5*, Nd.10	1695	0x69F	TxPDO5*, Nd.31	1716	0x6B4	TxPDO5*, Nd.52
1675	0x68B	TxPDO5*, Nd.11	1696	0x6A0	TxPDO5*, Nd.32	1717	0x6B5	TxPDO5*, Nd.53
1676	0x68C	TxPDO5*, Nd.12	1697	0x6A1	TxPDO5*, Nd.33	1718	0x6B6	TxPDO5*, Nd.54
1677	0x68D	TxPDO5*, Nd.13	1698	0x6A2	TxPDO5*, Nd.34	1719	0x6B7	TxPDO5*, Nd.55
1678	0x68E	TxPDO5*, Nd.14	1699	0x6A3	TxPDO5*, Nd.35	1720	0x6B8	TxPDO5*, Nd.56
1679	0x68F	TxPDO5*, Nd.15	1700	0x6A4	TxPDO5*, Nd.36	1721	0x6B9	TxPDO5*, Nd.57
1680	0x690	TxPDO5*, Nd.16	1701	0x6A5	TxPDO5*, Nd.37	1722	0x6BA	TxPDO5*, Nd.58
1681	0x691	TxPDO5*, Nd.17	1702	0x6A6	TxPDO5*, Nd.38	1723	0x6BB	TxPDO5*, Nd.59
1682	0x692	TxPDO5*, Nd.18	1703	0x6A7	TxPDO5*, Nd.39	1724	0x6BC	TxPDO5*, Nd.60
1683	0x693	TxPDO5*, Nd.19	1704	0x6A8	TxPDO5*, Nd.40	1725	0x6BD	TxPDO5*, Nd.61
1684	0x694	TxPDO5*, Nd.20	1705	0x6A9	TxPDO5*, Nd.41	1726	0x6BE	TxPDO5*, Nd.62
1685	0x695	TxPDO5*, Nd.21	1706	0x6AA	TxPDO5*, Nd.42	1727	0x6BF	TxPDO5*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1921	0x781	RxPDO5*, Nd.1	1942	0x796	RxPDO5*, Nd.22	1963	0x7AB	RxPDO5*, Nd.43
1922	0x782	RxPDO5*, Nd.2	1943	0x797	RxPDO5*, Nd.23	1964	0x7AC	RxPDO5*, Nd.44
1923	0x783	RxPDO5*, Nd.3	1944	0x798	RxPDO5*, Nd.24	1965	0x7AD	RxPDO5*, Nd.45
1924	0x784	RxPDO5*, Nd.4	1945	0x799	RxPDO5*, Nd.25	1966	0x7AE	RxPDO5*, Nd.46
1925	0x785	RxPDO5*, Nd.5	1946	0x79A	RxPDO5*, Nd.26	1967	0x7AF	RxPDO5*, Nd.47
1926	0x786	RxPDO5*, Nd.6	1947	0x79B	RxPDO5*, Nd.27	1968	0x7B0	RxPDO5*, Nd.48
1927	0x787	RxPDO5*, Nd.7	1948	0x79C	RxPDO5*, Nd.28	1969	0x7B1	RxPDO5*, Nd.49
1928	0x788	RxPDO5*, Nd.8	1949	0x79D	RxPDO5*, Nd.29	1970	0x7B2	RxPDO5*, Nd.50
1929	0x789	RxPDO5*, Nd.9	1950	0x79E	RxPDO5*, Nd.30	1971	0x7B3	RxPDO5*, Nd.51
1930	0x78A	RxPDO5*, Nd.10	1951	0x79F	RxPDO5*, Nd.31	1972	0x7B4	RxPDO5*, Nd.52
1931	0x78B	RxPDO5*, Nd.11	1952	0x7A0	RxPDO5*, Nd.32	1973	0x7B5	RxPDO5*, Nd.53
1932	0x78C	RxPDO5*, Nd.12	1953	0x7A1	RxPDO5*, Nd.33	1974	0x7B6	RxPDO5*, Nd.54
1933	0x78D	RxPDO5*, Nd.13	1954	0x7A2	RxPDO5*, Nd.34	1975	0x7B7	RxPDO5*, Nd.55
1934	0x78E	RxPDO5*, Nd.14	1955	0x7A3	RxPDO5*, Nd.35	1976	0x7B8	RxPDO5*, Nd.56
1935	0x78F	RxPDO5*, Nd.15	1956	0x7A4	RxPDO5*, Nd.36	1977	0x7B9	RxPDO5*, Nd.57
1936	0x790	RxPDO5*, Nd.16	1957	0x7A5	RxPDO5*, Nd.37	1978	0x7BA	RxPDO5*, Nd.58
1937	0x791	RxPDO5*, Nd.17	1958	0x7A6	RxPDO5*, Nd.38	1979	0x7BB	RxPDO5*, Nd.59
1938	0x792	RxPDO5*, Nd.18	1959	0x7A7	RxPDO5*, Nd.39	1980	0x7BC	RxPDO5*, Nd.60
1939	0x793	RxPDO5*, Nd.19	1960	0x7A8	RxPDO5*, Nd.40	1981	0x7BD	RxPDO5*, Nd.61
1940	0x794	RxPDO5*, Nd.20	1961	0x7A9	RxPDO5*, Nd.41	1982	0x7BE	RxPDO5*, Nd.62
1941	0x795	RxPDO5*, Nd.21	1962	0x7AA	RxPDO5*, Nd.42	1983	0x7BF	RxPDO5*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
449	0x1C1	TxPDO6*, Nd.1	470	0x1D6	TxPDO6*, Nd.22	491	0x1EB	TxPDO6*, Nd.43
450	0x1C2	TxPDO6*, Nd.2	471	0x1D7	TxPDO6*, Nd.23	492	0x1EC	TxPDO6*, Nd.44
451	0x1C3	TxPDO6*, Nd.3	472	0x1D8	TxPDO6*, Nd.24	493	0x1ED	TxPDO6*, Nd.45
452	0x1C4	TxPDO6*, Nd.4	473	0x1D9	TxPDO6*, Nd.25	494	0x1EE	TxPDO6*, Nd.46
453	0x1C5	TxPDO6*, Nd.5	474	0x1DA	TxPDO6*, Nd.26	495	0x1EF	TxPDO6*, Nd.47
454	0x1C6	TxPDO6*, Nd.6	475	0x1DB	TxPDO6*, Nd.27	496	0x1F0	TxPDO6*, Nd.48
455	0x1C7	TxPDO6*, Nd.7	476	0x1DC	TxPDO6*, Nd.28	497	0x1F1	TxPDO6*, Nd.49
456	0x1C8	TxPDO6*, Nd.8	477	0x1DD	TxPDO6*, Nd.29	498	0x1F2	TxPDO6*, Nd.50
457	0x1C9	TxPDO6*, Nd.9	478	0x1DE	TxPDO6*, Nd.30	499	0x1F3	TxPDO6*, Nd.51
458	0x1CA	TxPDO6*, Nd.10	479	0x1DF	TxPDO6*, Nd.31	500	0x1F4	TxPDO6*, Nd.52
459	0x1CB	TxPDO6*, Nd.11	480	0x1E0	TxPDO6*, Nd.32	501	0x1F5	TxPDO6*, Nd.53
460	0x1CC	TxPDO6*, Nd.12	481	0x1E1	TxPDO6*, Nd.33	502	0x1F6	TxPDO6*, Nd.54
461	0x1CD	TxPDO6*, Nd.13	482	0x1E2	TxPDO6*, Nd.34	503	0x1F7	TxPDO6*, Nd.55
462	0x1CE	TxPDO6*, Nd.14	483	0x1E3	TxPDO6*, Nd.35	504	0x1F8	TxPDO6*, Nd.56
463	0x1CF	TxPDO6*, Nd.15	484	0x1E4	TxPDO6*, Nd.36	505	0x1F9	TxPDO6*, Nd.57
464	0x1D0	TxPDO6*, Nd.16	485	0x1E5	TxPDO6*, Nd.37	506	0x1FA	TxPDO6*, Nd.58
465	0x1D1	TxPDO6*, Nd.17	486	0x1E6	TxPDO6*, Nd.38	507	0x1FB	TxPDO6*, Nd.59
466	0x1D2	TxPDO6*, Nd.18	487	0x1E7	TxPDO6*, Nd.39	508	0x1FC	TxPDO6*, Nd.60
467	0x1D3	TxPDO6*, Nd.19	488	0x1E8	TxPDO6*, Nd.40	509	0x1FD	TxPDO6*, Nd.61
468	0x1D4	TxPDO6*, Nd.20	489	0x1E9	TxPDO6*, Nd.41	510	0x1FE	TxPDO6*, Nd.62
469	0x1D5	TxPDO6*, Nd.21	490	0x1EA	TxPDO6*, Nd.42	511	0x1FF	TxPDO6*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
577	0x241	RxPDO6*, Nd.1	598	0x256	RxPDO6*, Nd.22	619	0x26B	RxPDO6*, Nd.43
578	0x242	RxPDO6*, Nd.2	599	0x257	RxPDO6*, Nd.23	620	0x26C	RxPDO6*, Nd.44
579	0x243	RxPDO6*, Nd.3	600	0x258	RxPDO6*, Nd.24	621	0x26D	RxPDO6*, Nd.45
580	0x244	RxPDO6*, Nd.4	601	0x259	RxPDO6*, Nd.25	622	0x26E	RxPDO6*, Nd.46
581	0x245	RxPDO6*, Nd.5	602	0x25A	RxPDO6*, Nd.26	623	0x26F	RxPDO6*, Nd.47
582	0x246	RxPDO6*, Nd.6	603	0x25B	RxPDO6*, Nd.27	624	0x270	RxPDO6*, Nd.48
583	0x247	RxPDO6*, Nd.7	604	0x25C	RxPDO6*, Nd.28	625	0x271	RxPDO6*, Nd.49
584	0x248	RxPDO6*, Nd.8	605	0x25D	RxPDO6*, Nd.29	626	0x272	RxPDO6*, Nd.50
585	0x249	RxPDO6*, Nd.9	606	0x25E	RxPDO6*, Nd.30	627	0x273	RxPDO6*, Nd.51
586	0x24A	RxPDO6*, Nd.10	607	0x25F	RxPDO6*, Nd.31	628	0x274	RxPDO6*, Nd.52
587	0x24B	RxPDO6*, Nd.11	608	0x260	RxPDO6*, Nd.32	629	0x275	RxPDO6*, Nd.53
588	0x24C	RxPDO6*, Nd.12	609	0x261	RxPDO6*, Nd.33	630	0x276	RxPDO6*, Nd.54
589	0x24D	RxPDO6*, Nd.13	610	0x262	RxPDO6*, Nd.34	631	0x277	RxPDO6*, Nd.55
590	0x24E	RxPDO6*, Nd.14	611	0x263	RxPDO6*, Nd.35	632	0x278	RxPDO6*, Nd.56
591	0x24F	RxPDO6*, Nd.15	612	0x264	RxPDO6*, Nd.36	633	0x279	RxPDO6*, Nd.57
592	0x250	RxPDO6*, Nd.16	613	0x265	RxPDO6*, Nd.3	634	0x27A	RxPDO6*, Nd.58
593	0x251	RxPDO6*, Nd.17	614	0x266	RxPDO6*, Nd.8	635	0x27B	RxPDO6*, Nd.59
594	0x252	RxPDO6*, Nd.18	615	0x267	RxPDO6*, Nd.39	636	0x27C	RxPDO6*, Nd.60
595	0x253	RxPDO6*, Nd.19	616	0x268	RxPDO6*, N.40	637	0x27D	RxPDO6*, Nd.61
596	0x254	RxPDO6*, Nd.20	617	0x269	RxPDO6*, d.41	638	0x27E	RxPDO6*, Nd.62
597	0x255	RxPDO6*, Nd.21	618	0x26A	RxPDO6*,Nd.42	639	0x27F	RxPDO6*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
705	0x2C1	TxPDO7*, Nd.1	726	0x2D6	TxPDO7*, Nd.22	747	0x2EB	TxPDO7*, Nd.43
706	0x2C2	TxPDO7*, Nd.2	727	0x2D7	TxPDO7*, Nd.23	748	0x2EC	TxPDO7*, Nd.44
707	0x2C3	TxPDO7*, Nd.3	728	0x2D8	TxPDO7*, Nd.24	749	0x2ED	TxPDO7*, Nd.45
708	0x2C4	TxPDO7*, Nd.4	729	0x2D9	TxPDO7*, Nd.25	750	0x2EE	TxPDO7*, Nd.46
709	0x2C5	TxPDO7*, Nd.5	730	0x2DA	TxPDO7*, Nd.26	751	0x2EF	TxPDO7*, Nd.47
710	0x2C6	TxPDO7*, Nd.6	731	0x2DB	TxPDO7*, Nd.27	752	0x2F0	TxPDO7*, Nd.48
711	0x2C7	TxPDO7*, Nd.7	732	0x2DC	TxPDO7*, Nd.28	753	0x2F1	TxPDO7*, Nd.49
712	0x2C8	TxPDO7*, Nd.8	733	0x2DD	TxPDO7*, Nd.29	754	0x2F2	TxPDO7*, Nd.50
713	0x2C9	TxPDO7*, Nd.9	734	0x2DE	TxPDO7*, Nd.30	755	0x2F3	TxPDO7*, Nd.51
714	0x2CA	TxPDO7*, Nd.10	735	0x2DF	TxPDO7*, Nd.31	756	0x2F4	TxPDO7*, Nd.52
715	0x2CB	TxPDO7*, Nd.11	736	0x2E0	TxPDO7*, Nd.32	757	0x2F5	TxPDO7*, Nd.53

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
716	0x2CC	TxPDO7*, Nd.12	737	0x2E1	TxPDO7*, Nd.33	758	0x2F6	TxPDO7*, Nd.54
717	0x2CD	TxPDO7*, Nd.13	738	0x2E2	TxPDO7*, Nd.34	759	0x2F7	TxPDO7*, Nd.55
718	0x2CE	TxPDO7*, Nd.14	739	0x2E3	TxPDO7*, Nd.35	760	0x2F8	TxPDO7*, Nd.56
719	0x2CF	TxPDO7*, Nd.15	740	0x2E4	TxPDO7*, Nd.36	761	0x2F9	TxPDO7*, Nd.57
720	0x2D0	TxPDO7*, Nd.16	741	0x2E5	TxPDO7*, Nd.37	762	0x2FA	TxPDO7*, Nd.58
721	0x2D1	TxPDO7*, Nd.17	742	0x2E6	TxPDO7*, Nd.38	763	0x2FB	TxPDO7*, Nd.59
722	0x2D2	TxPDO7*, Nd.18	743	0x2E7	TxPDO7*, Nd.39	764	0x2FC	TxPDO7*, Nd.60
723	0x2D3	TxPDO7*, Nd.19	744	0x2E8	TxPDO7*, Nd.40	765	0x2FD	TxPDO7*, Nd.61
724	0x2D4	TxPDO7*, Nd.20	745	0x2E9	TxPDO7*, Nd.41	766	0x2FE	TxPDO7*, Nd.62
725	0x2D5	TxPDO7*, Nd.21	746	0x2EA	TxPDO7*, Nd.42	767	0x2FF	TxPDO7*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
833	0x341	RxPDO7*, Nd.1	854	0x356	RxPDO7*, Nd.22	875	0x36B	RxPDO7*, Nd.43
834	0x342	RxPDO7*, Nd.2	855	0x357	RxPDO7*, Nd.23	876	0x36C	RxPDO7*, Nd.44
835	0x343	RxPDO7*, Nd.3	856	0x358	RxPDO7*, Nd.24	877	0x36D	RxPDO7*, Nd.45
836	0x344	RxPDO7*, Nd.4	857	0x359	RxPDO7*, Nd.25	878	0x36E	RxPDO7*, Nd.46
837	0x345	RxPDO7*, Nd.5	858	0x35A	RxPDO7*, Nd.26	879	0x36F	RxPDO7*, Nd.47
838	0x346	RxPDO7*, Nd.6	859	0x35B	RxPDO7*, Nd.27	880	0x370	RxPDO7*, Nd.48
839	0x347	RxPDO7*, Nd.7	860	0x35C	RxPDO7*, Nd.28	881	0x371	RxPDO7*, Nd.49
840	0x348	RxPDO7*, Nd.8	861	0x35D	RxPDO7*, Nd.29	882	0x372	RxPDO7*, Nd.50
841	0x349	RxPDO7*, Nd.9	862	0x35E	RxPDO7*, Nd.30	883	0x373	RxPDO7*, Nd.51
842	0x34A	RxPDO7*, Nd.10	863	0x35F	RxPDO7*, Nd.31	884	0x374	RxPDO7*, Nd.52
843	0x34B	RxPDO7*, Nd.11	864	0x360	RxPDO7*, Nd.32	885	0x375	RxPDO7*, Nd.53
844	0x34C	RxPDO7*, Nd.12	865	0x361	RxPDO7*, Nd.33	886	0x376	RxPDO7*, Nd.54
845	0x34D	RxPDO7*, Nd.13	866	0x362	RxPDO7*, Nd.34	887	0x377	RxPDO7*, Nd.55
846	0x34E	RxPDO7*, Nd.14	867	0x363	RxPDO7*, Nd.35	888	0x378	RxPDO7*, Nd.56
847	0x34F	RxPDO7*, Nd.15	868	0x364	RxPDO7*, Nd.36	889	0x379	RxPDO7*, Nd.57
848	0x350	RxPDO7*, Nd.16	869	0x365	RxPDO7*, Nd.37	890	0x37A	RxPDO7*, Nd.58
849	0x351	RxPDO7*, Nd.17	870	0x366	RxPDO7*, Nd.38	891	0x37B	RxPDO7*, Nd.59
850	0x352	RxPDO7*, Nd.18	871	0x367	RxPDO7*, Nd.39	892	0x37C	RxPDO7*, Nd.60
851	0x353	RxPDO7*, Nd.19	872	0x368	RxPDO7*, Nd.40	893	0x37D	RxPDO7*, Nd.61
852	0x354	RxPDO7*, Nd.20	873	0x369	RxPDO7*, Nd.41	894	0x37E	RxPDO7*, Nd.62
853	0x355	RxPDO7*, Nd.21	874	0x36A	RxPDO7*, Nd.42	895	0x37F	RxPDO7*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
961	0x3C1	TxPDO8*, Nd.1	982	0x3D6	TxPDO8*, Nd.22	1003	0x3EB	TxPDO8*, Nd.43
962	0x3C2	TxPDO8*, Nd.2	983	0x3D7	TxPDO8*, Nd.23	1004	0x3EC	TxPDO8*, Nd.44
963	0x3C3	TxPDO8*, Nd.3	984	0x3D8	TxPDO8*, Nd.24	1005	0x3ED	TxPDO8*, Nd.45
964	0x3C4	TxPDO8*, Nd.4	985	0x3D9	TxPDO8*, Nd.25	1006	0x3EE	TxPDO8*, Nd.46
965	0x3C5	TxPDO8*, Nd.5	986	0x3DA	TxPDO8*, Nd.26	1007	0x3EF	TxPDO8*, Nd.47
966	0x3C6	TxPDO8*, Nd.6	987	0x3DB	TxPDO8*, Nd.27	1008	0x3F0	TxPDO8*, Nd.48
967	0x3C7	TxPDO8*, Nd.7	988	0x3DC	TxPDO8*, Nd.28	1009	0x3F1	TxPDO8*, Nd.49
968	0x3C8	TxPDO8*, Nd.8	989	0x3DD	TxPDO8*, Nd.29	1010	0x3F2	TxPDO8*, Nd.50
969	0x3C9	TxPDO8*, Nd.9	990	0x3DE	TxPDO8*, Nd.30	1011	0x3F3	TxPDO8*, Nd.51
970	0x3CA	TxPDO8*, Nd.10	991	0x3DF	TxPDO8*, Nd.31	1012	0x3F4	TxPDO8*, Nd.52
971	0x3CB	TxPDO8*, Nd.11	992	0x3E0	TxPDO8*, Nd.32	1013	0x3F5	TxPDO8*, Nd.53
972	0x3CC	TxPDO8*, Nd.12	993	0x3E1	TxPDO8*, Nd.33	1014	0x3F6	TxPDO8*, Nd.54
973	0x3CD	TxPDO8*, Nd.13	994	0x3E2	TxPDO8*, Nd.34	1015	0x3F7	TxPDO8*, Nd.55
974	0x3CE	TxPDO8*, Nd.14	995	0x3E3	TxPDO8*, Nd.35	1016	0x3F8	TxPDO8*, Nd.56
975	0x3CF	TxPDO8*, Nd.15	996	0x3E4	TxPDO8*, Nd.36	1017	0x3F9	TxPDO8*, Nd.57
976	0x3D0	TxPDO8*, Nd.16	997	0x3E5	TxPDO8*, Nd.37	1018	0x3FA	TxPDO8*, Nd.58
977	0x3D1	TxPDO8*, Nd.17	998	0x3E6	TxPDO8*, Nd.38	1019	0x3FB	TxPDO8*, Nd.59
978	0x3D2	TxPDO8*, Nd.18	999	0x3E7	TxPDO8*, Nd.39	1020	0x3FC	TxPDO8*, Nd.60
979	0x3D3	TxPDO8*, Nd.19	1000	0x3E8	TxPDO8*, Nd.40	1021	0x3FD	TxPDO8*, Nd.61
980	0x3D4	TxPDO8*, Nd.20	1001	0x3E9	TxPDO8*, Nd.41	1022	0x3FE	TxPDO8*, Nd.62
981	0x3D5	TxPDO8*, Nd.21	1002	0x3EA	TxPDO8*, Nd.42	1023	0x3FF	TxPDO8*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1089	0x441	RxPDO8*, Nd.1	1110	0x456	RxPDO8*, Nd.22	1131	0x46B	RxPDO8*, Nd.43
1090	0x442	RxPDO8*, Nd.2	1111	0x457	RxPDO8*, Nd.23	1132	0x46C	RxPDO8*, Nd.44
1091	0x443	RxPDO8*, Nd.3	1112	0x458	RxPDO8*, Nd.24	1133	0x46D	RxPDO8*, Nd.45
1092	0x444	RxPDO8*, Nd.4	1113	0x459	RxPDO8*, Nd.25	1134	0x46E	RxPDO8*, Nd.46
1093	0x445	RxPDO8*, Nd.5	1114	0x45A	RxPDO8*, Nd.26	1135	0x46F	RxPDO8*, Nd.47
1094	0x446	RxPDO8*, Nd.6	1115	0x45B	RxPDO8*, Nd.27	1136	0x470	RxPDO8*, Nd.48
1095	0x447	RxPDO8*, Nd.7	1116	0x45C	RxPDO8*, Nd.28	1137	0x471	RxPDO8*, Nd.49
1096	0x448	RxPDO8*, Nd.8	1117	0x45D	RxPDO8*, Nd.29	1138	0x472	RxPDO8*, Nd.50
1097	0x449	RxPDO8*, Nd.9	1118	0x45E	RxPDO8*, Nd.30	1139	0x473	RxPDO8*, Nd.51
1098	0x44A	RxPDO8*, Nd.10	1119	0x45F	RxPDO8*, Nd.31	1140	0x474	RxPDO8*, Nd.52
1099	0x44B	RxPDO8*, Nd.11	1120	0x460	RxPDO8*, Nd.32	1141	0x475	RxPDO8*, Nd.53
1100	0x44C	RxPDO8*, Nd.12	1121	0x461	RxPDO8*, Nd.33	1142	0x476	RxPDO8*, Nd.54
1101	0x44D	RxPDO8*, Nd.13	1122	0x462	RxPDO8*, Nd.34	1143	0x477	RxPDO8*, Nd.55
1102	0x44E	RxPDO8*, Nd.14	1123	0x463	RxPDO8*, Nd.35	1144	0x478	RxPDO8*, Nd.56
1103	0x44F	RxPDO8*, Nd.15	1124	0x464	RxPDO8*, Nd.36	1145	0x479	RxPDO8*, Nd.57
1104	0x450	RxPDO8*, Nd.16	1125	0x465	RxPDO8*, Nd.37	1146	0x47A	RxPDO8*, Nd.58
1105	0x451	RxPDO8*, Nd.17	1126	0x466	RxPDO8*, Nd.38	1147	0x47B	RxPDO8*, Nd.59
1106	0x452	RxPDO8*, Nd.18	1127	0x467	RxPDO8*, Nd.39	1148	0x47C	RxPDO8*, Nd.60
1107	0x453	RxPDO8*, Nd.19	1128	0x468	RxPDO8*, Nd.40	1149	0x47D	RxPDO8*, Nd.61
1108	0x454	RxPDO8*, Nd.20	1129	0x469	RxPDO8*, Nd.41	1150	0x47E	RxPDO8*, Nd.62
1109	0x455	RxPDO8*, Nd.21	1130	0x46A	RxPDO8*, Nd.42	1151	0x47F	RxPDO8*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1217	0x4C1	TxPDO9*, Nd.1	1238	0x4D6	TxPDO9*, Nd.22	1259	0x4EB	TxPDO9*, Nd.43
1218	0x4C2	TxPDO9*, Nd.2	1239	0x4D7	TxPDO9*, Nd.23	1260	0x4EC	TxPDO9*, Nd.44
1219	0x4C3	TxPDO9*, Nd.3	1240	0x4D8	TxPDO9*, Nd.24	1261	0x4ED	TxPDO9*, Nd.45
1220	0x4C4	TxPDO9*, Nd.4	1241	0x4D9	TxPDO9*, Nd.25	1262	0x4EE	TxPDO9*, Nd.46
1221	0x4C5	TxPDO9*, Nd.5	1242	0x4DA	TxPDO9*, Nd.26	1263	0x4EF	TxPDO9*, Nd.47
1222	0x4C6	TxPDO9*, Nd.6	1243	0x4DB	TxPDO9*, Nd.27	1264	0x4F0	TxPDO9*, Nd.48
1223	0x4C7	TxPDO9*, Nd.7	1244	0x4DC	TxPDO9*, Nd.28	1265	0x4F1	TxPDO9*, Nd.49
1224	0x4C8	TxPDO9*, Nd.8	1245	0x4DD	TxPDO9*, Nd.29	1266	0x4F2	TxPDO9*, Nd.50
1225	0x4C9	TxPDO9*, Nd.9	1246	0x4DE	TxPDO9*, Nd.30	1267	0x4F3	TxPDO9*, Nd.51
1226	0x4CA	TxPDO9*, Nd.10	1247	0x4DF	TxPDO9*, Nd.31	1268	0x4F4	TxPDO9*, Nd.52
1227	0x4CB	TxPDO9*, Nd.11	1248	0x4E0	TxPDO9*, Nd.32	1269	0x4F5	TxPDO9*, Nd.53
1228	0x4CC	TxPDO9*, Nd.12	1249	0x4E1	TxPDO9*, Nd.33	1270	0x4F6	TxPDO9*, Nd.54
1229	0x4CD	TxPDO9*, Nd.13	1250	0x4E2	TxPDO9*, Nd.34	1271	0x4F7	TxPDO9*, Nd.55
1230	0x4CE	TxPDO9*, Nd.14	1251	0x4E3	TxPDO9*, Nd.35	1272	0x4F8	TxPDO9*, Nd.56
1231	0x4CF	TxPDO9*, Nd.15	1252	0x4E4	TxPDO9*, Nd.36	1273	0x4F9	TxPDO9*, Nd.57
1232	0x4D0	TxPDO9*, Nd.16	1253	0x4E5	TxPDO9*, Nd.37	1274	0x4FA	TxPDO9*, Nd.58
1233	0x4D1	TxPDO9*, Nd.17	1254	0x4E6	TxPDO9*, Nd.38	1275	0x4FB	TxPDO9*, Nd.59
1234	0x4D2	TxPDO9*, Nd.18	1255	0x4E7	TxPDO9*, Nd.39	1276	0x4FC	TxPDO9*, Nd.60
1235	0x4D3	TxPDO9*, Nd.19	1256	0x4E8	TxPDO9*, Nd.40	1277	0x4FD	TxPDO9*, Nd.61
1236	0x4D4	TxPDO9*, Nd.20	1257	0x4E9	TxPDO9*, Nd.41	1278	0x4FE	TxPDO9*, Nd.62
1237	0x4D5	TxPDO9*, Nd.21	1258	0x4EA	TxPDO9*, Nd.42	1279	0x4FF	TxPDO9*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1345	0x541	RxPDO9*, Nd.1	1366	0x556	RxPDO9*, Nd.22	1387	0x56B	RxPDO9*, Nd.43
1346	0x542	RxPDO9*, Nd.2	1367	0x557	RxPDO9*, Nd.23	1388	0x56C	RxPDO9*, Nd.44
1347	0x543	RxPDO9*, Nd.3	1368	0x558	RxPDO9*, Nd.24	1389	0x56D	RxPDO9*, Nd.45
1348	0x544	RxPDO9*, Nd.4	1369	0x559	RxPDO9*, Nd.25	1390	0x56E	RxPDO9*, Nd.46
1349	0x545	RxPDO9*, Nd.5	1370	0x55A	RxPDO9*, Nd.26	1391	0x56F	RxPDO9*, Nd.47
1350	0x546	RxPDO9*, Nd.6	1371	0x55B	RxPDO9*, Nd.27	1392	0x570	RxPDO9*, Nd.48
1351	0x547	RxPDO9*, Nd.7	1372	0x55C	RxPDO9*, Nd.28	1393	0x571	RxPDO9*, Nd.49
1352	0x548	RxPDO9*, Nd.8	1373	0x55D	RxPDO9*, Nd.29	1394	0x572	RxPDO9*, Nd.50
1353	0x549	RxPDO9*, Nd.9	1374	0x55E	RxPDO9*, Nd.30	1395	0x573	RxPDO9*, Nd.51
1354	0x54A	RxPDO9*, Nd.10	1375	0x55F	RxPDO9*, Nd.31	1396	0x574	RxPDO9*, Nd.52
1355	0x54B	RxPDO9*, Nd.11	1376	0x560	RxPDO9*, Nd.32	1397	0x575	RxPDO9*, Nd.53

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1356	0x54C	RxPDO9*, Nd.12	1377	0x561	RxPDO9*, Nd.33	1398	0x576	RxPDO9*, Nd.54
1357	0x54D	RxPDO9*, Nd.13	1378	0x562	RxPDO9*, Nd.34	1399	0x577	RxPDO9*, Nd.55
1358	0x54E	RxPDO9*, Nd.14	1379	0x563	RxPDO9*, Nd.35	1400	0x578	RxPDO9*, Nd.56
1359	0x54F	RxPDO9*, Nd.15	1380	0x564	RxPDO9*, Nd.36	1401	0x579	RxPDO9*, Nd.57
1360	0x550	RxPDO9*, Nd.16	1381	0x565	RxPDO9*, Nd.37	1402	0x57A	RxPDO9*, Nd.58
1361	0x551	RxPDO9*, Nd.17	1382	0x566	RxPDO9*, Nd.38	1403	0x57B	RxPDO9*, Nd.59
1362	0x552	RxPDO9*, Nd.18	1383	0x567	RxPDO9*, Nd.39	1404	0x57C	RxPDO9*, Nd.60
1363	0x553	RxPDO9*, Nd.19	1384	0x568	RxPDO9*, Nd.40	1405	0x57D	RxPDO9*, Nd.61
1364	0x554	RxPDO9*, Nd.20	1385	0x569	RxPDO9*, Nd.41	1406	0x57E	RxPDO9*, Nd.62
1365	0x555	RxPDO9*, Nd.21	1386	0x56A	RxPDO9*, Nd.42	1407	0x57F	RxPDO9*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1473	0x5C1	TxPDO10*, Nd.1	1494	0x5D6	TxPDO10*, Nd.22	1515	0x5EB	TxPDO10*, Nd.43
1474	0x5C2	TxPDO10*, Nd.2	1495	0x5D7	TxPDO10*, Nd.23	1516	0x5EC	TxPDO10*, Nd.44
1475	0x5C3	TxPDO10*, Nd.3	1496	0x5D8	TxPDO10*, Nd.24	1517	0x5ED	TxPDO10*, Nd.45
1476	0x5C4	TxPDO10*, Nd.4	1497	0x5D9	TxPDO10*, Nd.25	1518	0x5EE	TxPDO10*, Nd.46
1477	0x5C5	TxPDO10*, Nd.5	1498	0x5DA	TxPDO10*, Nd.26	1519	0x5EF	TxPDO10*, Nd.47
1478	0x5C6	TxPDO10*, Nd.6	1499	0x5DB	TxPDO10*, Nd.27	1520	0x5F0	TxPDO10*, Nd.48
1479	0x5C7	TxPDO10*, Nd.7	1500	0x5DC	TxPDO10*, Nd.28	1521	0x5F1	TxPDO10*, Nd.49
1480	0x5C8	TxPDO10*, Nd.8	1501	0xDE	TxPDO10*, Nd.29	1522	0x5F2	TxPDO10*, Nd.50
1481	0x5C9	TxPDO10*, Nd.9	1502	0x5DE	TxPDO10*, Nd.30	1523	0x5F3	TxPDO10*, Nd.51
1482	0x5CA	TxPDO10*, Nd.10	1503	0x5DF	TxPDO10*, Nd.31	1524	0x5F4	TxPDO10*, Nd.52
1483	0x5CB	TxPDO10*, Nd.11	1504	0x5E0	TxPDO10*, Nd.32	1525	0x5F5	TxPDO10*, Nd.53
1484	0x5CC	TxPDO10*, Nd.12	1505	0x5E1	TxPDO10*, Nd.33	1526	0x5F6	TxPDO10*, Nd.54
1485	0x5CD	TxPDO10*, Nd.13	1506	0x5E2	TxPDO10*, Nd.34	1527	0x5F7	TxPDO10*, Nd.55
1486	0x5CE	TxPDO10*, Nd.14	1507	0x5E3	TxPDO10*, Nd.35	1528	0x5F8	TxPDO10*, Nd.56
1487	0x5CF	TxPDO10*, Nd.15	1508	0x5E4	TxPDO10*, Nd.36	1529	0x5F9	TxPDO10*, Nd.57
1488	0x5D0	TxPDO10*, Nd.16	1509	0x5E5	TxPDO10*, Nd.37	1530	0x5FA	TxPDO10*, Nd.58
1489	0x5D1	TxPDO10*, Nd.17	1510	0x5E6	TxPDO10*, Nd.38	1531	0x5FB	TxPDO10*, Nd.59
1490	0x5D2	TxPDO10*, Nd.18	1511	0x5E7	TxPDO10*, Nd.39	1532	0x5FC	TxPDO10*, Nd.60
1491	0x5D3	TxPDO10*, Nd.19	1512	0x5E8	TxPDO10*, Nd.40	1533	0x5FD	TxPDO10*, Nd.61
1492	0x5D4	TxPDO10*, Nd.20	1513	0x5E9	TxPDO10*, Nd.41	1534	0x5FE	TxPDO10*, Nd.62
1493	0x5D5	TxPDO10*, Nd.21	1514	0x5EA	TxPDO10*, Nd.42	1535	0x5FF	TxPDO10*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1601	0x641	RxPDO10*, Nd.1	1622	0x656	RxPDO10*, Nd.22	1643	0x66B	RxPDO10*, Nd.43
1602	0x642	RxPDO10*, Nd.2	1623	0x657	RxPDO10*, Nd.23	1644	0x66C	RxPDO10*, Nd.44
1603	0x643	RxPDO10*, Nd.3	1624	0x658	RxPDO10*, Nd.24	1645	0x66D	RxPDO10*, Nd.45
1604	0x644	RxPDO10*, Nd.4	1625	0x659	RxPDO10*, Nd.25	1646	0x66E	RxPDO10*, Nd.46
1605	0x645	RxPDO10*, Nd.5	1626	0x65A	RxPDO10*, Nd.26	1647	0x66F	RxPDO10*, Nd.47
1606	0x646	RxPDO10*, Nd.6	1627	0x65B	RxPDO10*, Nd.27	1648	0x670	RxPDO10*, Nd.48
1607	0x647	RxPDO10*, Nd.7	1628	0x65C	RxPDO10*, Nd.28	1649	0x671	RxPDO10*, Nd.49
1608	0x648	RxPDO10*, Nd.8	1629	0x65D	RxPDO10*, Nd.29	1650	0x672	RxPDO10*, Nd.50
1609	0x649	RxPDO10*, Nd.9	1630	0x65E	RxPDO10*, Nd.30	1651	0x673	RxPDO10*, Nd.51
1610	0x64A	RxPDO10*, Nd.10	1631	0x65F	RxPDO10*, Nd.31	1652	0x674	RxPDO10*, Nd.52
1611	0x64B	RxPDO10*, Nd.11	1632	0x660	RxPDO10*, Nd.32	1653	0x675	RxPDO10*, Nd.53
1612	0x64C	RxPDO10*, Nd.12	1633	0x661	RxPDO10*, Nd.33	1654	0x676	RxPDO10*, Nd.54
1613	0x64D	RxPDO10*, Nd.13	1634	0x662	RxPDO10*, Nd.34	1655	0x677	RxPDO10*, Nd.55
1614	0x64E	RxPDO10*, Nd.14	1635	0x663	RxPDO10*, Nd.35	1656	0x678	RxPDO10*, Nd.56
1615	0x64F	RxPDO10*, Nd.15	1636	0x664	RxPDO10*, Nd.36	1657	0x679	RxPDO10*, Nd.57
1616	0x650	RxPDO10*, Nd.16	1637	0x665	RxPDO10*, Nd.37	1658	0x67A	RxPDO10*, Nd.58
1617	0x651	RxPDO10*, Nd.17	1638	0x666	RxPDO10*, Nd.38	1659	0x67B	RxPDO10*, Nd.59
1618	0x652	RxPDO10*, Nd.18	1639	0x667	RxPDO10*, Nd.39	1660	0x67C	RxPDO10*, Nd.60
1619	0x653	RxPDO10*, Nd.19	1640	0x668	RxPDO10*, Nd.40	1661	0x67D	RxPDO10*, Nd.61
1620	0x654	RxPDO10*, Nd.20	1641	0x669	RxPDO10*, Nd.41	1662	0x67E	RxPDO10*, Nd.62
1621	0x655	RxPDO10*, Nd.21	1642	0x66A	RxPDO10*, Nd.42	1663	0x67F	RxPDO10*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1729	0x6C1	TxPDO11*, Nd.1	1750	0x6D6	TxPDO11*, Nd.22	1771	0x6EB	TxPDO11*, Nd.43
1730	0x6C2	TxPDO11*, Nd.2	1751	0x6D7	TxPDO11*, Nd.23	1772	0x6EC	TxPDO11*, Nd.44
1731	0x6C3	TxPDO11*, Nd.3	1752	0x6D8	TxPDO11*, Nd.24	1773	0x6ED	TxPDO11*, Nd.45
1732	0x6C4	TxPDO11*, Nd.4	1753	0x6D9	TxPDO11*, Nd.25	1774	0x6EE	TxPDO11*, Nd.46
1733	0x6C5	TxPDO11*, Nd.5	1754	0x6DA	TxPDO11*, Nd.26	1775	0x6EF	TxPDO11*, Nd.47
1734	0x6C6	TxPDO11*, Nd.6	1755	0x6DB	TxPDO11*, Nd.27	1776	0x6F0	TxPDO11*, Nd.48
1735	0x6C7	TxPDO11*, Nd.7	1756	0x6DC	TxPDO11*, Nd.28	1777	0x6F1	TxPDO11*, Nd.49
1736	0x6C8	TxPDO11*, Nd.8	1757	0x6DD	TxPDO11*, Nd.29	1778	0x6F2	TxPDO11*, Nd.50
1737	0x6C9	TxPDO11*, Nd.9	1758	0x6DE	TxPDO11*, Nd.30	1779	0x6F3	TxPDO11*, Nd.51
1738	0x6CA	TxPDO11*, Nd.10	1759	0x6DF	TxPDO11*, Nd.31	1780	0x6F4	TxPDO11*, Nd.52
1739	0x6CB	TxPDO11*, Nd.11	1760	0x6E0	TxPDO11*, Nd.32	1781	0x6F5	TxPDO11*, Nd.53
1740	0x6CC	TxPDO11*, Nd.12	1761	0x6E1	TxPDO11*, Nd.33	1782	0x6F6	TxPDO11*, Nd.54
1741	0x6CD	TxPDO11*, Nd.13	1762	0x6E2	TxPDO11*, Nd.34	1783	0x6F7	TxPDO11*, Nd.55
1742	0x6CE	TxPDO11*, Nd.14	1763	0x6E3	TxPDO11*, Nd.35	1784	0x6F8	TxPDO11*, Nd.56
1743	0x6CF	TxPDO11*, Nd.15	1764	0x6E4	TxPDO11*, Nd.36	1785	0x6F9	TxPDO11*, Nd.57
1744	0x6D0	TxPDO11*, Nd.16	1765	0x6E5	TxPDO11*, Nd.37	1786	0x6FA	TxPDO11*, Nd.58
1745	0x6D1	TxPDO11*, Nd.17	1766	0x6E6	TxPDO11*, Nd.38	1787	0x6FB	TxPDO11*, Nd.59
1746	0x6D2	TxPDO11*, Nd.18	1767	0x6E7	TxPDO11*, Nd.39	1788	0x6FC	TxPDO11*, Nd.60
1747	0x6D3	TxPDO11*, Nd.19	1768	0x6E8	TxPDO11*, Nd.40	1789	0x6FD	TxPDO11*, Nd.61
1748	0x6D4	TxPDO11*, Nd.20	1769	0x6E9	TxPDO11*, Nd.41	1790	0x6FE	TxPDO11*, Nd.62
1749	0x6D5	TxPDO11*, Nd.21	1770	0x6EA	TxPDO11*, Nd.42	1791	0x6FF	TxPDO11*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1857	0x741	RxPDO11*, Nd.1	1878	0x756	RxPDO11*, Nd.22	1899	0x76B	RxPDO11*, Nd.43
1858	0x742	RxPDO11*, Nd.2	1879	0x757	RxPDO11*, Nd.23	1900	0x76C	RxPDO11*, Nd.44
1859	0x743	RxPDO11*, Nd.3	1880	0x758	RxPDO11*, Nd.24	1901	0x76D	RxPDO11*, Nd.45
1860	0x744	RxPDO11*, Nd.4	1881	0x759	RxPDO11*, Nd.25	1902	0x76E	RxPDO11*, Nd.46
1861	0x745	RxPDO11*, Nd.5	1882	0x75A	RxPDO11*, Nd.26	1903	0x76F	RxPDO11*, Nd.47
1862	0x746	RxPDO11*, Nd.6	1883	0x75B	RxPDO11*, Nd.27	1904	0x770	RxPDO11*, Nd.48
1863	0x747	RxPDO11*, Nd.7	1884	0x75C	RxPDO11*, Nd.28	1905	0x771	RxPDO11*, Nd.49
1864	0x748	RxPDO11*, Nd.8	1885	0x75D	RxPDO11*, Nd.29	1906	0x772	RxPDO11*, Nd.50
1865	0x749	RxPDO11*, Nd.9	1886	0x75E	RxPDO11*, Nd.30	1907	0x773	RxPDO11*, Nd.51
1866	0x74A	RxPDO11*, Nd.10	1887	0x75F	RxPDO11*, Nd.31	1908	0x774	RxPDO11*, Nd.52
1867	0x74B	RxPDO11*, Nd.11	1888	0x760	RxPDO11*, Nd.32	1909	0x775	RxPDO11*, Nd.53
1868	0x74C	RxPDO11*, Nd.12	1889	0x761	RxPDO11*, Nd.33	1910	0x776	RxPDO11*, Nd.54
1869	0x74D	RxPDO11*, Nd.13	1890	0x762	RxPDO11*, Nd.34	1911	0x777	RxPDO11*, Nd.55
1870	0x74E	RxPDO11*, Nd.14	1891	0x763	RxPDO11*, Nd.35	1912	0x778	RxPDO11*, Nd.56
1871	0x74F	RxPDO11*, Nd.15	1892	0x764	RxPDO11*, Nd.36	1913	0x779	RxPDO11*, Nd.57
1872	0x750	RxPDO11*, Nd.16	1893	0x765	RxPDO11*, Nd.37	1914	0x77A	RxPDO11*, Nd.58
1873	0x751	RxPDO11*, Nd.17	1894	0x766	RxPDO11*, Nd.38	1915	0x77B	RxPDO11*, Nd.59
1874	0x752	RxPDO11*, Nd.18	1895	0x767	RxPDO11*, Nd.39	1916	0x77C	RxPDO11*, Nd.60
1875	0x753	RxPDO11*, Nd.19	1896	0x768	RxPDO11*, Nd.40	1917	0x77D	RxPDO11*, Nd.61
1876	0x754	RxPDO11*, Nd.20	1897	0x769	RxPDO11*, Nd.41	1918	0x77E	RxPDO11*, Nd.62
1877	0x755	RxPDO11*, Nd.21	1898	0x76A	RxPDO11*, Nd.42	1919	0x77F	RxPDO11*, Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1409	0x581	SDO Tx Nd.1	1430	0x596	SDO Tx Nd.22	1451	0x5AB	SDO Tx Nd.43
1410	0x582	SDO Tx Nd.2	1431	0x597	SDO Tx Nd.23	1452	0x5AC	SDO Tx Nd.44
1411	0x583	SDO Tx Nd.3	1432	0x598	SDO Tx Nd.24	1453	0x5AD	SDO Tx Nd.45
1412	0x584	SDO Tx Nd.4	1433	0x599	SDO Tx Nd.25	1454	0x5AE	SDO Tx Nd.46
1413	0x585	SDO Tx Nd.5	1434	0x59A	SDO Tx Nd.26	1455	0x5AF	SDO Tx Nd.47
1414	0x586	SDO Tx Nd.6	1435	0x59B	SDO Tx Nd.27	1456	0x5B0	SDO Tx Nd.48
1415	0x587	SDO Tx Nd.7	1436	0x59C	SDO Tx Nd.28	1457	0x5B1	SDO Tx Nd.49
1416	0x588	SDO Tx Nd.8	1437	0x59D	SDO Tx Nd.29	1458	0x5B2	SDO Tx Nd.50
1417	0x589	SDO Tx Nd.9	1438	0x59E	SDO Tx Nd.30	1459	0x5B3	SDO Tx Nd.51
1418	0x58A	SDO Tx Nd.10	1439	0x59F	SDO Tx Nd.31	1460	0x5B4	SDO Tx Nd.52
1419	0x58B	SDO Tx Nd.11	1440	0x5A0	SDO Tx Nd.32	1461	0x5B5	SDO Tx Nd.53

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1420	0x58C	SDO Tx Nd.12	1441	0x5A1	SDO Tx Nd.33	1462	0x5B6	SDO Tx Nd.54
1421	0x58D	SDO Tx Nd.13	1442	0x5A2	SDO Tx Nd.34	1463	0x5B7	SDO Tx Nd.55
1422	0x58E	SDO Tx Nd.14	1443	0x5A3	SDO Tx Nd.35	1464	0x5B8	SDO Tx Nd.56
1423	0x58F	SDO Tx Nd.15	1444	0x5A4	SDO Tx Nd.36	1465	0x5B9	SDO Tx Nd.57
1424	0x590	SDO Tx Nd.16	1445	0x5A5	SDO Tx Nd.37	1466	0x5BA	SDO Tx Nd.58
1425	0x591	SDO Tx Nd.17	1446	0x5A6	SDO Tx Nd.38	1467	0x5BB	SDO Tx Nd.59
1426	0x592	SDO Tx Nd.18	1447	0x5A7	SDO Tx Nd.39	1468	0x5BC	SDO Tx Nd.60
1427	0x593	SDO Tx Nd.19	1448	0x5A8	SDO Tx Nd.40	1469	0x5BD	SDO Tx Nd.61
1428	0x594	SDO Tx Nd.20	1449	0x5A9	SDO Tx Nd.41	1470	0x5BE	SDO Tx Nd.62
1429	0x595	SDO Tx Nd.21	1450	0x5AA	SDO Tx Nd.42	1471	0x5BF	SDO Tx Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1537	0x601	SDO Rx Nd.1	1558	0x616	SDO Rx Nd.22	1579	0x62B	SDO Rx Nd.43
1538	0x602	SDO Rx Nd.2	1559	0x617	SDO Rx Nd.23	1580	0x62C	SDO Rx Nd.44
1539	0x603	SDO Rx Nd.3	1560	0x618	SDO Rx Nd.24	1581	0x62D	SDO Rx Nd.45
1540	0x604	SDO Rx Nd.4	1561	0x619	SDO Rx Nd.25	1582	0x62E	SDO Rx Nd.46
1541	0x605	SDO Rx Nd.5	1562	0x61A	SDO Rx Nd.26	1583	0x62F	SDO Rx Nd.47
1542	0x606	SDO Rx Nd.6	1563	0x61B	SDO Rx Nd.27	1584	0x630	SDO Rx Nd.48
1543	0x607	SDO Rx Nd.7	1564	0x61C	SDO Rx Nd.28	1585	0x631	SDO Rx Nd.49
1544	0x608	SDO Rx Nd.8	1565	0x61D	SDO Rx Nd.29	1586	0x632	SDO Rx Nd.50
1545	0x609	SDO Rx Nd.9	1566	0x61E	SDO Rx Nd.30	1587	0x633	SDO Rx Nd.51
1546	0x60A	SDO Rx Nd.10	1567	0x61F	SDO Rx Nd.31	1588	0x634	SDO Rx Nd.52
1547	0x60B	SDO Rx Nd.11	1568	0x620	SDO Rx Nd.32	1589	0x635	SDO Rx Nd.53
1548	0x60C	SDO Rx Nd.12	1569	0x621	SDO Rx Nd.33	1590	0x636	SDO Rx Nd.54
1549	0x60D	SDO Rx Nd.13	1570	0x622	SDO Rx Nd.34	1591	0x637	SDO Rx Nd.55
1550	0x60E	SDO Rx Nd.14	1571	0x623	SDO Rx Nd.35	1592	0x638	SDO Rx Nd.56
1551	0x60F	SDO Rx Nd.15	1572	0x624	SDO Rx Nd.36	1593	0x639	SDO Rx Nd.57
1552	0x610	SDO Rx Nd.16	1573	0x625	SDO Rx Nd.37	1594	0x63A	SDO Rx Nd.58
1553	0x611	SDO Rx Nd.17	1574	0x626	SDO Rx Nd.38	1595	0x63B	SDO Rx Nd.59
1554	0x612	SDO Rx Nd.18	1575	0x627	SDO Rx Nd.39	1596	0x63C	SDO Rx Nd.60
1555	0x613	SDO Rx Nd.19	1576	0x628	SDO Rx Nd.40	1597	0x63D	SDO Rx Nd.61
1556	0x614	SDO Rx Nd.20	1577	0x629	SDO Rx Nd.41	1598	0x63E	SDO Rx Nd.62
1557	0x615	SDO Rx Nd.21	1578	0x62A	SDO Rx Nd.42	1599	0x63F	SDO Rx Nd.63

dec	hex	Telegram type	dec	hex	Telegram type	dec	hex	Telegram type
1793	0x701	Guarding Nd.1	1814	0x716	Guarding Nd.22	1835	0x72B	Guarding Nd.43
1794	0x702	Guarding Nd.2	1815	0x717	Guarding Nd.23	1836	0x72C	Guarding Nd.44
1795	0x703	Guarding Nd.3	1816	0x718	Guarding Nd.24	1837	0x72D	Guarding Nd.45
1796	0x704	Guarding Nd.4	1817	0x719	Guarding Nd.25	1838	0x72E	Guarding Nd.46
1797	0x705	Guarding Nd.5	1818	0x71A	Guarding Nd.26	1839	0x72F	Guarding Nd.47
1798	0x706	Guarding Nd.6	1819	0x71B	Guarding Nd.27	1840	0x730	Guarding Nd.48
1799	0x707	Guarding Nd.7	1820	0x71C	Guarding Nd.28	1841	0x731	Guarding Nd.49
1800	0x708	Guarding Nd.8	1821	0x71D	Guarding Nd.29	1842	0x732	Guarding Nd.50
1801	0x709	Guarding Nd.9	1822	0x71E	Guarding Nd.30	1843	0x733	Guarding Nd.51
1802	0x70A	Guarding Nd.10	1823	0x71F	Guarding Nd.31	1844	0x734	Guarding Nd.52
1803	0x70B	Guarding Nd.11	1824	0x720	Guarding Nd.32	1845	0x735	Guarding Nd.53
1804	0x70C	Guarding Nd.12	1825	0x721	Guarding Nd.33	1846	0x736	Guarding Nd.54
1805	0x70D	Guarding Nd.13	1826	0x722	Guarding Nd.34	1847	0x737	Guarding Nd.55
1806	0x70E	Guarding Nd.14	1827	0x723	Guarding Nd.35	1848	0x738	Guarding Nd.56
1807	0x70F	Guarding Nd.15	1828	0x724	Guarding Nd.36	1849	0x739	Guarding Nd.57
1808	0x710	Guarding Nd.16	1829	0x725	Guarding Nd.37	1850	0x73A	Guarding Nd.58
1809	0x711	Guarding Nd.17	1830	0x726	Guarding Nd.38	1851	0x73B	Guarding Nd.59
1810	0x712	Guarding Nd.18	1831	0x727	Guarding Nd.39	1852	0x73C	Guarding Nd.60
1811	0x713	Guarding Nd.19	1832	0x728	Guarding Nd.40	1853	0x73D	Guarding Nd.61
1812	0x714	Guarding Nd.20	1833	0x729	Guarding Nd.41	1854	0x73E	Guarding Nd.62
1813	0x715	Guarding Nd.21	1834	0x72A	Guarding Nd.42	1855	0x73F	Guarding Nd.63

11.2 Third-Party components

This device contains Beckhoff software and third-party software.
Please refer to the license file on the storage medium.

11.3 Accessories

Table 34: microSD cards.

Order number	Description
CX1900-0122	512 MB microSD card
CX1900-0132	16 GB microSD card

Table 35: Further spare parts.

Order number	Description
ZB8701	Slotted screwdriver 2.0 x 40 mm, HD terminals

11.4 Certifications

FCC Approvals for the United States of America

FCC: Federal Communications Commission Radio Frequency Interference Statement

This equipment has been tested and found to comply with the limits for a Class A digital device, pursuant to Part 15 of the FCC Rules. These limits are designed to provide reasonable protection against harmful interference when the equipment is operated in a commercial environment. This equipment generates, uses, and can radiate radio frequency energy and, if not installed and used in accordance with the instruction manual, may cause harmful interference to radio communications. Operation of this equipment in a residential area is likely to cause harmful interference in which case the user will be required to correct the interference at his own expense.

FCC Approval for Canada

FCC: Canadian Notice

This equipment does not exceed the Class A limits for radiated emissions as described in the Radio Interference Regulations of the Canadian Department of Communications.

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More Information:
www.beckhoff.com/CX7050

Beckhoff Automation GmbH & Co. KG
Hülshorstweg 20
33415 Verl
Germany
Phone: +49 5246 9630
info@beckhoff.com
www.beckhoff.com

