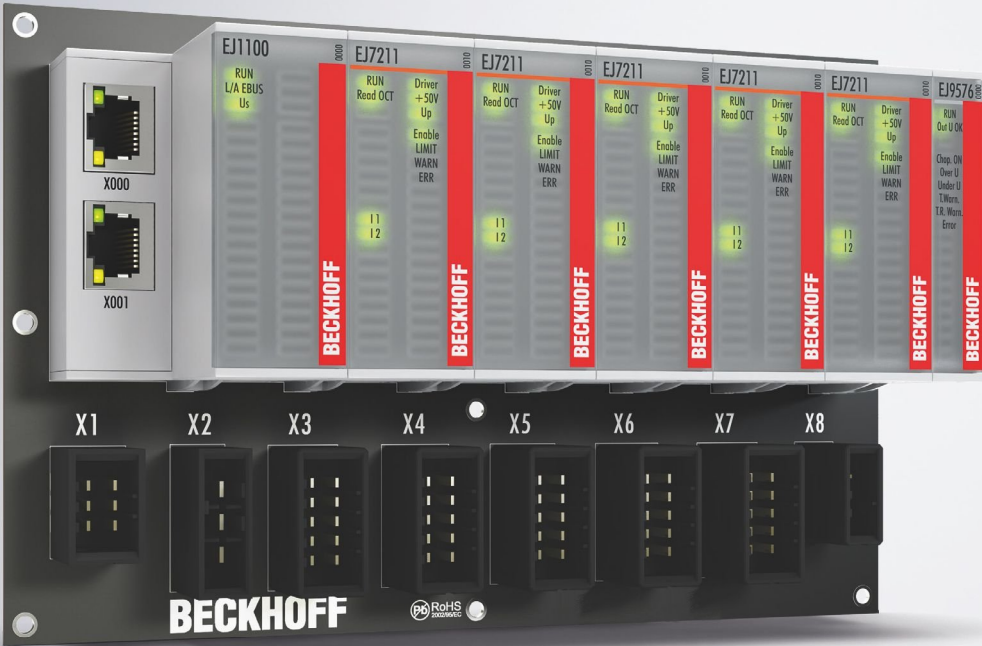


Documentation | EN

## EJ3255

5-Channel Potentiometer Measurement with Sensor Supply





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# 1 Foreword

## 1.1 Notes on the documentation

### Intended audience

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

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

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

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

### Disclaimer

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

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

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

### Trademarks

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

### Patent Pending

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



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

### Copyright

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Offenders will be held liable for the payment of damages. All rights reserved in the event of the grant of a patent, utility model or design.

## 1.2 Safety instructions

### Safety regulations

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

### Exclusion of liability

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

### Personnel qualification

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

### Signal words

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

#### Personal injury warnings

**⚠ DANGER**

Hazard with high risk of death or serious injury.

**⚠ WARNING**

Hazard with medium risk of death or serious injury.

**⚠ CAUTION**

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

#### Warning of damage to property or environment

**NOTICE**

The environment, equipment, or data may be damaged.

#### Information on handling the product



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

## 1.3 Intended use

### ⚠ WARNING

#### Caution - Risk of injury!

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

## 1.4 Signal distribution board

### NOTICE

#### Signal distribution board

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

## 1.5 Documentation issue status

| Version | Comment   |
|---------|---|
| 1.5     | <ul style="list-style-type: none"> <li>• Update Technical data</li> <li>• Update chapter <i>Installation of EJ modules</i></li> <li>• Update structure</li> </ul>   |
| 1.4     | <ul style="list-style-type: none"> <li>• Update chapter <i>Marking of EtherCAT plug-in modules</i></li> <li>• Update Technical data</li> <li>• Chapter <i>Disposal</i> added</li> <li>• Update structure</li> </ul>   |
| 1.3     | <ul style="list-style-type: none"> <li>• Update chapter <i>Technical data</i></li> </ul>  |
| 1.2     | <ul style="list-style-type: none"> <li>• New front page</li> <li>• Update chapter <i>EJ3255 - Pinout</i></li> <li>• Update revision status</li> <li>• Structural update</li> </ul>  |
| 1.1     | <ul style="list-style-type: none"> <li>• Chapters <i>Basics communication</i>, <i>TwinCAT Quick Start</i>, <i>TwinCAT development environment</i> and <i>General Notes - EtherCAT Slave Application</i> replaced by references in the chapter <i>Guide through documentation</i></li> <li>• Chapter <i>EJ3255 - Object description and parameterization</i> added</li> <li>• Update chapter <i>EJ3255 - Pinout</i></li> </ul> |
| 1.0     | <ul style="list-style-type: none"> <li>• First publication EJ3255</li> </ul>  |

## 1.6 Guide through documentation

### NOTICE



#### Further components of documentation

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

| Title  | Description  |
|--|--|
| <b>EtherCAT System Documentation</b> ( <a href="#">PDF</a> )   | <ul style="list-style-type: none"> <li>• System overview</li> <li>• EtherCAT basics</li> <li>• Cable redundancy</li> <li>• Hot Connect</li> <li>• EtherCAT devices configuration</li> </ul>  |
| <b>Design Guide EJ8xxx - Signal distribution board for standard EtherCAT plug-in modules</b> ( <a href="#">PDF</a> )                               | <p>Notes on the design of a signal distribution board for standard EtherCAT plug-in modules.</p> <ul style="list-style-type: none"> <li>• Requirements for the signal distribution board</li> <li>• Backplane mounting guidelines</li> <li>• Module placement</li> <li>• Routing guidelines</li> </ul> |
| <b>Documentation of the corresponding ELxxx EtherCAT Terminal</b><br>(s. <a href="#">note on documentation of ELxxx</a> ) [ <a href="#">▶ 37</a> ] | <ul style="list-style-type: none"> <li>• Notes on the principle of operation and</li> <li>• descriptions for configuration and parameterization are transferable to the corresponding EtherCAT plug-in modules</li> </ul>  |
| <b>I/O Analog Manual</b> ( <a href="#">PDF</a> )   | Notes on I/O components with analog in and outputs   |
| <b>Infrastructure for EtherCAT/Ethernet</b> ( <a href="#">PDF</a> )  | Technical recommendations and notes for design, implementation and testing   |
| <b>Software Declarations I/O</b> ( <a href="#">PDF</a> )   | Open source software declarations for Beckhoff I/O components  |

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

- the “Documentation and Download” area of the respective product page,
- the [Download finder](#),
- the [Beckhoff Information System](#).

## 1.7 Marking of EtherCAT plug-in modules

### Designation

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

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



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



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

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

**Notes**

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

**Serial number**

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

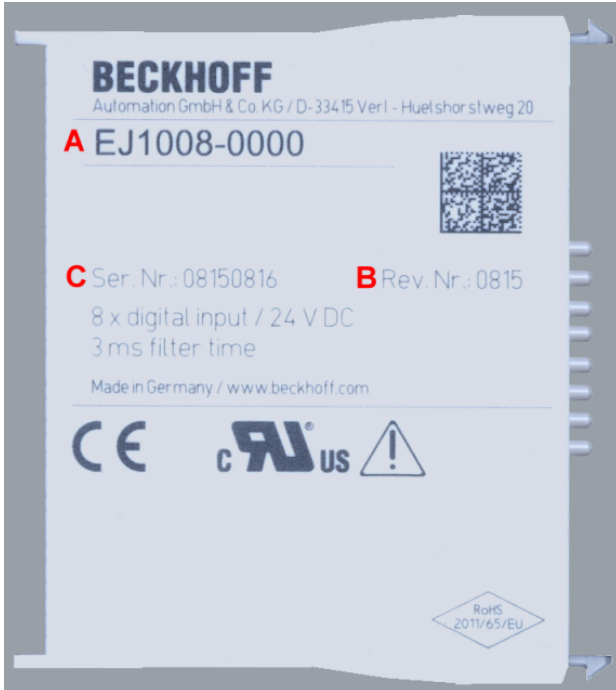


Fig. 2: Order identifier (A), revision number (B) and serial number (C) using the example of EJ1008

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

### 1.7.1 Beckhoff Identification Code (BIC)

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



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

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

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

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

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

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

The following information is contained:

| Item no. | Type of information                | Explanation   | Data identifier | Number of digits incl. data identifier | Example                     |
|----------|------------------------------------|---|-----------------|--|-----------------------------|
| 1        | Beckhoff order number              | <b>Beckhoff order number</b>  | 1P              | 8                                      | <b>1P</b> 072222            |
| 2        | Beckhoff Traceability Number (BTN) | <b>Unique serial number, see note below</b>                           | S               | 12                                     | <b>SBTN</b> k4p562d7        |
| 3        | Article description                | <b>Beckhoff article description, e.g. EL1008</b>                      | 1K              | 32                                     | <b>1KEL</b> 1809            |
| 4        | Quantity                           | <b>Quantity in packaging unit, e.g. 1, 10, etc.</b>                   | Q               | 6                                      | <b>Q1</b>                   |
| 5        | Batch number                       | Optional: Year and week of production                                 | 2P              | 14                                     | <b>2P</b> 401503180016      |
| 6        | ID/serial number                   | Optional: Present-day serial number system, e.g. with safety products | 51S             | 12                                     | <b>51S</b> 678294104        |
| 7        | Variant number                     | Optional: Product variant number on the basis of standard products    | 30P             | 32                                     | <b>30P</b> F971 ,<br>2*K183 |
| ...      |                                    |   |                 |  |                             |

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

### Structure of the BIC

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

**1P**072222**SBTN**k4p562d7**1KEL**1809 **Q1** **51S**678294

Accordingly as DMC:



Fig. 4: Example DMC **1P**072222**SBTN**k4p562d7**1KEL**1809 **Q1** **51S**678294

### BTN

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

### NOTICE

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

## 1.7.2 Electronic access to the BIC (eBIC)

### Electronic BIC (eBIC)

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

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

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

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

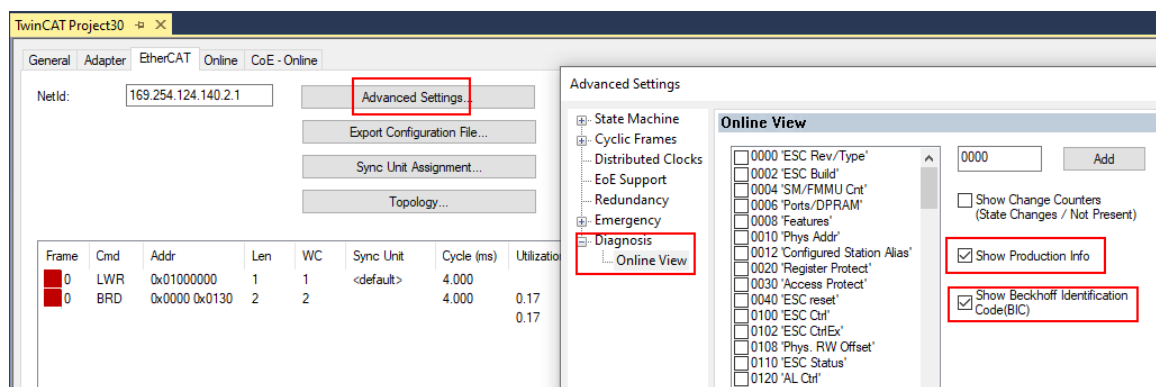
### EtherCAT devices (IP20, IP67)

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

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

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

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



- The BTN and its contents are then displayed:

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

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

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

| Index   | Name                                      | Flags | Value   |
|---------|---|-------|---|
| 1000    | Device type                               | RO    | 0x015E1389 (22942601)                           |
| 1008    | Device name                               | RO    | ELM3704-0000                                    |
| 1009    | Hardware version                          | RO    | 00  |
| 100A    | Software version                          | RO    | 01  |
| 100B    | Bootloader version                        | RO    | J0.1.27.0                                       |
| 1011:0  | Restore default parameters                | RO    | > 1 <   |
| 1018:0  | Identity                                  | RO    | > 4 <   |
| 10E2:0  | Manufacturer-specific Identification C... | RO    | > 1 <   |
| 10E2:01 | SubIndex 001                              | RO    | 1P158442SBTN0008jckp1KELM3704 Q1 2P482001000016 |
| 10F0:0  | Backup parameter handling                 | RO    | > 1 <   |
| 10F3:0  | Diagnosis History                         | RO    | > 21 <  |
| 10F8    | Actual Time Stamp                         | RO    | 0x170bfb277e                                    |

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

### PROFIBUS, PROFINET, DeviceNet devices etc.

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

### 1.7.3 Certificates

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



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



## 2 System overview

Electronically, the EJxxxx EtherCAT plug-in modules are based on the EtherCAT I/O system. The EJ system consists of the signal distribution board and EtherCAT plug-in modules. It is also possible to connect an IPC to the EJ system.

The EJ system is suitable for mass production applications, applications with small footprint and applications requiring a low total weight.

The machine complexity can be extended by means of the following:

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

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

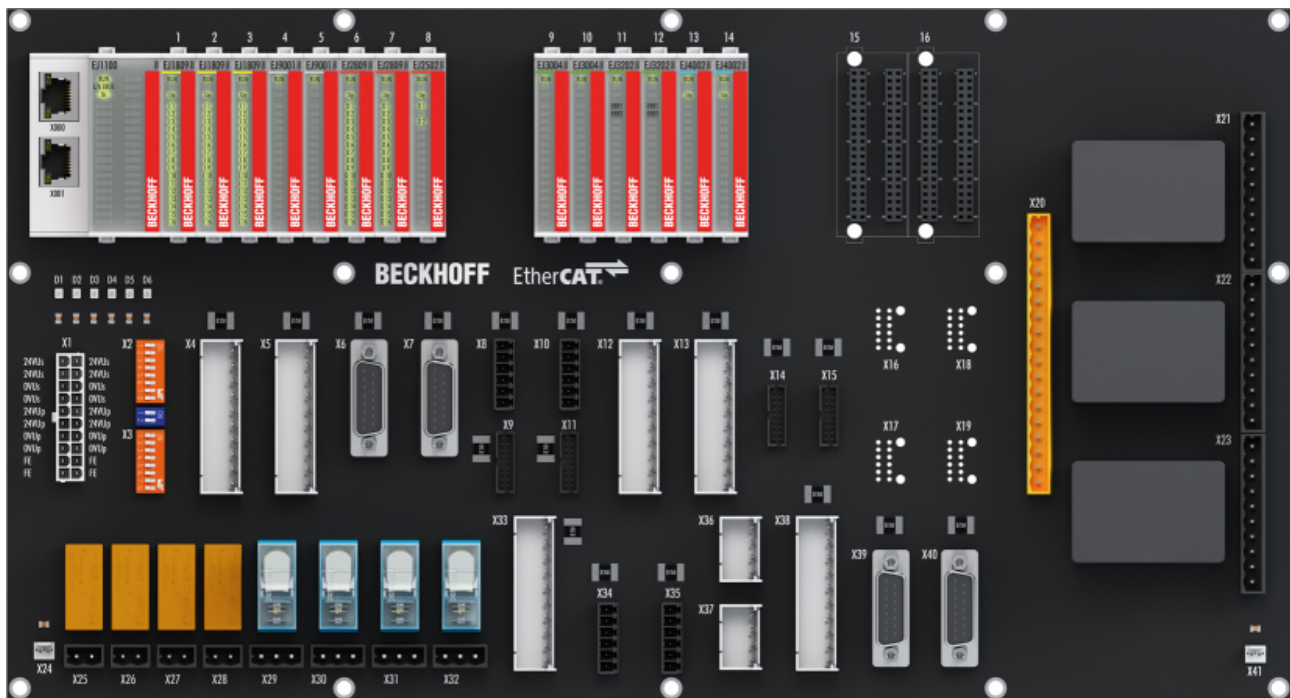


Fig. 6: EJ system sample

### Signal distribution board

The signal distribution board distributes the signals and the power supply to individual application-specific plug connectors, in order to connect the controller to further machine modules. Using pre-assembled cable harnesses avoids the need for time-consuming connection of individual wires. Coded components reduce the unit costs and the risk of miswiring.

Beckhoff offers development of signal distribution boards as an engineering service. Customers have the option to develop their own signal distribution board, based on the design guide.

### EtherCAT plug-in modules

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



## 3 EJ3255 - Product description

### 3.1 Introduction

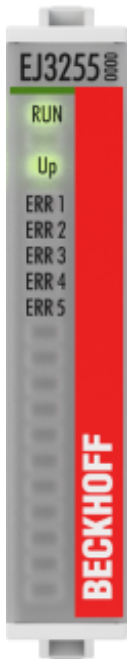


Fig. 7: EJ3255

#### **5-channel analog input module, potentiometer measurement with Sensor supply**

The EJ3255 EtherCAT plug-in module enables potentiometers to be connected directly. A stabilized power supply in the module for the connected potentiometers and ratiometric measurement of the input voltage offer the prerequisites for precise measuring. On account of its high sampling rate and together with potentiometer position encoders, the compact, 5-channel EtherCAT plug-in module enables a temporally high-resolution and cost-efficient position detection.

The EJ3255 diagnostics detect broken wire, loss of supply voltage and short-circuit for each channel.

The five channels are measured simultaneously (at the same time).

## 3.2 Technical data

| Technical data   | EJ3255  |
|--|---|
| Number of analog inputs                                | 5   |
| Power supply   | via Up contacts   |
| Technology   | ratiometric potentiometer evaluation with own supply, 3-wire connection   |
| Distributed Clocks                                     | yes   |
| Feed voltage potentiometer                             | typ. 10 V $\pm$ 10%   |
| Internal resistance                                    | >> 100 k $\Omega$ to wiper connection   |
| Input filter limit frequency                           | typ. -3 dB at 3 kHz and potentiometer 50 k $\Omega$   |
| Sensor types   | Potentiometer 300 $\Omega$ ... 50 k $\Omega$  |
| Output current   | max. 0.3 A total supply current for the potentiometers  |
| Wiring fail indication                                 | yes   |
| Conversion time  | typ. 300 ... 700 $\mu$ s, dependent on settings, default setting: approx.. 500 $\mu$ s (5 channels, filter deactivated) |
| Resolution   | 16 bits representation (including sign)   |
| Measuring error (total measuring range)                | < $\pm$ 0.5% (relative to full scale value)   |
| Electrical isolation                                   | 500 V (E-bus/signal voltage)  |
| Current consumption load voltage (Up contacts)         | dependent on the potentiometers, max. 125 mA  |
| Current consumption via E-bus                          | typ. 80 mA  |
| Special Features                                       | Open-circuit recognition, supply monitoring, activatable filters simultaneous measurement of the channels               |
| Permissible ambient temperature range during operation | -25°C ... +60°C (extended temperature range)  |
| Permissible ambient temperature range during storage   | -40°C ... +85°C   |
| Permissible relative air humidity                      | 95%, no condensation  |
| Operating altitude                                     | max. 2,000 m  |
| Dimensions (W x H x D)                                 | approx. 12 mm x 66 mm x 55 mm   |
| Weight   | approx. 30 g  |
| Mounting   | on signal distribution board  |
| Pollution degree                                       | 2   |
| Installation position                                  | Standard [ <a href="#">▶ 25</a> ]   |
| Position of the coding pins [ <a href="#">▶ 28</a> ]   | 1 and 6   |
| Color coding   | green   |
| Vibration/shock resistance                             | according to EN 60068-2-6/EN 60068-2-27 (with corresponding signal distribution board)                                  |
| EMC immunity/emission                                  | according to EN 61000-6-2/EN 61000-6-4 (with corresponding signal distribution board)                                   |
| Protection class                                       | EJ module: IP20<br>EJ system: Dependent on the signal distribution board  |
| Approvals/markings*                                    | CE, EAC, UKCA   |

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



### CE approval

The CE Marking refers to the EtherCAT plug-in module mentioned above.

If the EtherCAT plug-in module is used in the production of a ready-to-use end product (PCB in conjunction with a housing), the manufacturer of the end product must check compliance of the overall system with relevant directives and CE certification.

To operate the EtherCAT plug-in modules, they must be installed in a housing.

### 3.3 Pinout

| EJ3255 |    |            |            |
|--------|----|------------|------------|
| Pin#   |    | Signal     |            |
| 1      | 2  | $U_{EBUS}$ | $U_{EBUS}$ |
| 3      | 4  | GND        | GND        |
| 5      | 6  | RX0+       | TX1+       |
| 7      | 8  | RX0-       | TX1-       |
| 9      | 10 | GND        | GND        |
| 11     | 12 | TX0+       | RX1+       |
| 13     | 14 | TX0-       | RX1-       |
| 15     | 16 | GND        | GND        |
| 17     | 18 | 0V CH1     | 10V CH1    |
| 19     | 20 | Input 1    | Input 2    |
| 21     | 22 | 0V CH2     | 10V CH2    |
| 23     | 24 | 0V CH3     | 10V CH3    |
| 25     | 26 | Input 3    | Input4     |
| 27     | 28 | 0V CH4     | 10V CH4    |
| 29     | 30 | 0V CH5     | 10V CH5    |
| 31     | 32 | Input 5    | NC         |
| 33     | 34 | 0V Up      | 0V Up      |
| 35     | 36 | 0V Up      | 24V Up     |
| 37     | 38 | 24V Up     | 24V Up     |
| 39     | 40 | SGND       | SGND       |

**E-Bus Kontakte**

Die Spannungsversorgung  $U_{EBUS}$  wird vom Koppler zur Verfügung gestellt und aus der Versorgungsspannung  $U_S$  des EtherCAT-Kopplers versorgt.

**Signale und Versorgung des Potentiometers**


**Up-Kontakte**

Die Peripheriespannung  $U_P$  versorgt die Elektronik auf der Feldseite.

| Signal              | Beschreibung                                    |
|---------------------|---|
| $U_{EBUS}$          | Spannungsversorgung E-Bus 3,3 V                 |
| GND                 | E-Bus Signalmasse<br>Nicht mit 0V Up verbinden! |
| RXn+                | Positives E-Bus Receive Signal                  |
| RXn-                | Negatives E-Bus Receive Signal                  |
| TXn+                | Positives E-Bus Transmit Signal                 |
| TXn-                | Negatives E-Bus Transmit Signal                 |
| 0V CH1 ... 0V CH5   | Potentiometer1 ... 5 Speisung A                 |
| Input1 ... Input5   | Potentiometer1 ... 5 Abgriff                    |
| 10V CH1 ... 10V CH5 | Potentiometer1 ... 5 Speisung B                 |
| NC                  | Nicht belegen                                   |
| 0V Up               | GND Signal Feldseite                            |
| 24V Up              | Spannungsversorgung Feldseite 24 V              |
| SGND                | Schirm Masse                                    |

Fig. 8: EJ3255 - Pinout

The PCB footprint can be downloaded from the Beckhoff [homepage](#).

| <b>NOTICE</b>   |  |
|---|--|
|  | <p><b>Damage to devices possible!</b></p> <ul style="list-style-type: none"> <li>The pins named with "NC" must not be connected.</li> <li>Before installation and commissioning read the chapters <a href="#">Installation of EJ modules</a> [▶ 21] and <a href="#">Commissioning</a> [▶ 37]!</li> </ul> |

### 3.4 LEDs

| LED No. | EJ3255 |
|---------|--------|
| A       | RUN    |
| B       |        |
| C       | Up     |
|         |        |
| 1       | ERR 1  |
| 2       | ERR 2  |
| 3       | ERR 3  |
| 4       | ERR 4  |
| 5       | ERR 5  |
| 6       |        |
| 7       |        |
| 8       |        |
| 9       |        |
| 10      |        |
| 11      |        |
| 12      |        |
| 13      |        |
| 14      |        |
| 15      |        |
| 16      |        |

Fig. 9: EJ3255 - LEDs

| LED                                  | Color | Display      | State            | Description  |
|--------------------------------------|-------|--------------|------------------|--|
| RUN                                  | green | off          | Init             | State of the <u>EtherCAT State Machine</u> : <b>INIT</b> = initialization of the plug-in module  |
|                                      |       | flashing     | Pre-Operational  | State of the EtherCAT State Machine: <b>PREOP</b> = function for mailbox communication and different default settings set  |
|                                      |       | single flash | Safe-Operational | State of the EtherCAT State Machine: <b>SAFEOP</b> = verification of the <u>Sync-Manager</u> channels and the distributed clocks. Outputs remain in safe state   |
|                                      |       | on           | Operational      | State of the EtherCAT State Machine: <b>OP</b> = normal operating state; mailbox and process data communication are possible   |
|                                      |       | flickering   | Bootstrap        | State of the EtherCAT State Machine: <b>BOOTSTRAP</b> = function for <u>firmware updates</u> of the plug-in module   |
| Up                                   | green | off          | -                | No 24 V <sub>DC</sub> power supply connected   |
|                                      |       | on           | -                | 24 V <sub>DC</sub> power supply connected  |
| ERR1<br>ERR2<br>ERR3<br>ERR4<br>ERR5 | red   | off          | -                | No error   |
|                                      |       | on           | -                | <p>There is an error on the corresponding channel:</p> <ul style="list-style-type: none"> <li>• Broken wire on wiper or supply</li> <li>• Potentiometer outside the specified range (300.. 50 kΩ)</li> <li>• Short-circuit</li> <li>• Overload</li> </ul> <p>If channels are not used they can be deactivated via the PDO selection. The corresponding LED goes out.</p> |

## 4 Installation of EJ modules

### 4.1 Power supply for the EtherCAT plug-in modules

**⚠ WARNING**

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

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

Notes:

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

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

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

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

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

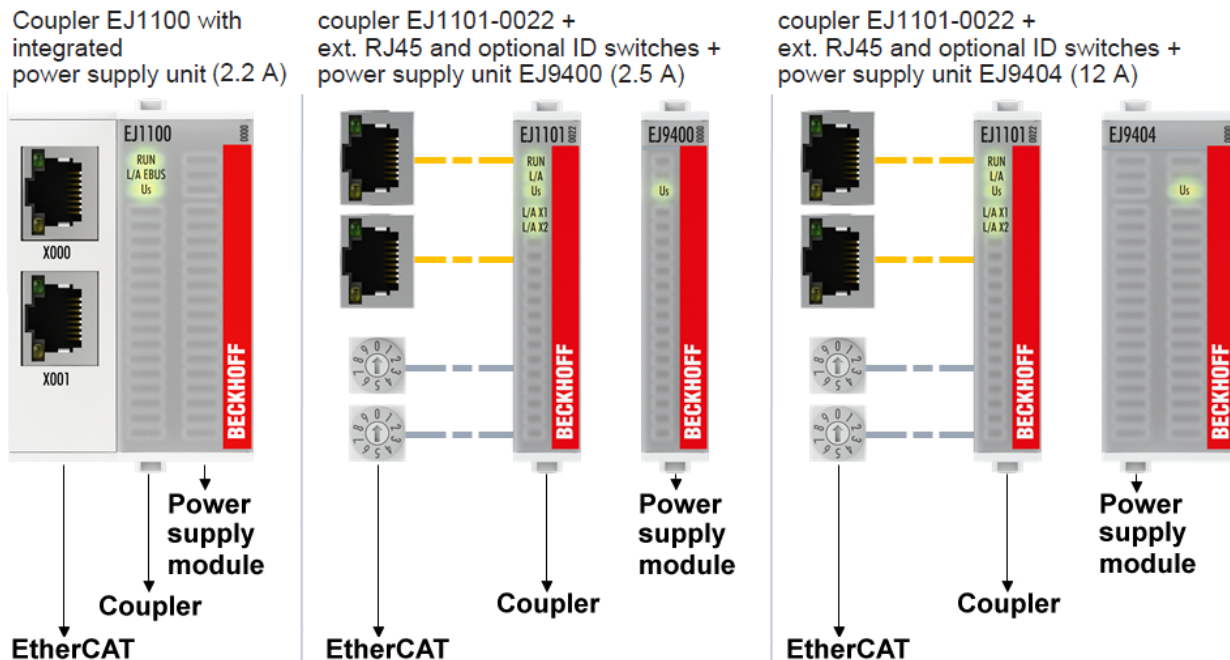


Fig. 10: E-bus power supply with EJ1100 or EJ1101-0022 + EJ940x

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

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

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

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

- with a supply voltage  $U_s$  of 24 V<sub>DC</sub> (-15 %/+20 %). This voltage supplies the E-bus and the bus terminal electronics.

The CXxxxx units supply the E-bus with up to 2,000 mA E-bus current. If a higher current is required due to the attached terminals, power feed terminals or power supply plug-in modules must be used for the E-bus supply.

- with a peripheral voltage  $U_p$  of 24 V<sub>DC</sub> to supply the field electronics.

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

- the E-bus signals,
- the E-bus voltage  $U_{EBUS}$  (3.3 V) and
- the peripheral voltage  $U_p$  (24 V<sub>DC</sub>).



Fig. 11: PCB with Embedded PC, EK1110-0043 and EJxxxx, rear view EK1110-0043

## 4.2 Note on load voltage supply

### ⚠ WARNING

#### Load voltage supply

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

Therefore, the load voltage supply should be designed as an SELV supply.

### 4.3 EJxxxx - dimensions

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

| Module type          | Dimensions (W x H x D) | Sample in figure below                   |
|----------------------|------------------------|--|
| Coupler              | 44 mm x 66 mm x 55 mm  | EJ1100 (ej_44_2xjr45_coupler)            |
| Single module        | 12 mm x 66 mm x 55 mm  | EJ1809 (ej_12_16pin_code13)              |
| Double module        | 24 mm x 66 mm x 55 mm  | EJ7342 (ej_24_2x16pin_code18)            |
| Single module (long) | 12 mm x 152 mm x 55 mm | EJ1957 (ej_12_2x16pin_extended_code4747) |

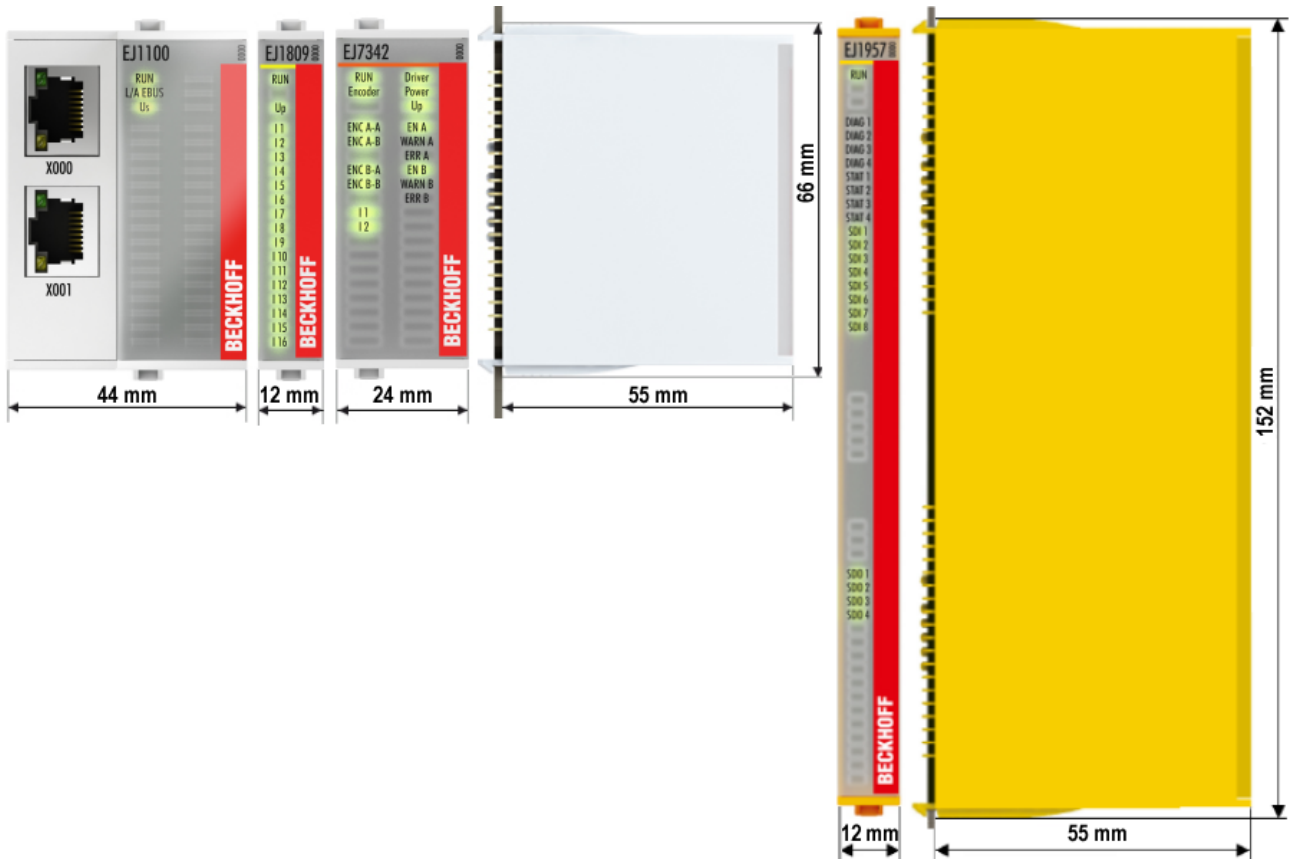


Fig. 12: EJxxxx - Dimensions

The technical drawings can be downloaded from the Beckhoff [homepage](#). The drawings are named as described in the drawing below.

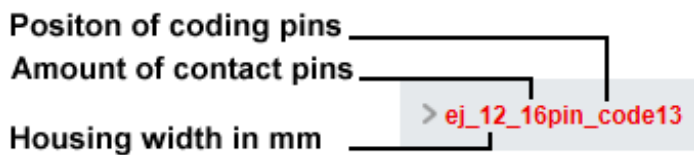


Fig. 13: Naming of the technical drawings

## 4.4 Installation positions and minimum distances

### 4.4.1 Minimum distances for ensuring installability

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

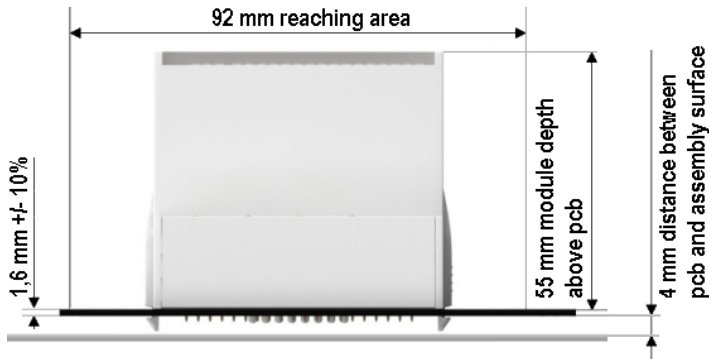


Fig. 14: Mounting distances EJ module - PCB

#### **i** Observing the reaching area

A minimum reaching area of 92 mm is required for assembly / disassembly, in order to be able to reach the mounting tabs with the fingers.

Adherence to the recommended minimum distances for ventilation (see [section Installation position \[▶ 25\]](#)) ensures an adequate reaching area.

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



### 4.4.2 Installation positions

**NOTICE**

**Constraints regarding installation position and operating temperature range**

Please refer to the [technical data \[►\\_18\]](#) for the installed components to ascertain whether any restrictions regarding the mounting position and/or the operating temperature range have been specified. During installation of modules with increased thermal dissipation, ensure adequate distance above and below the modules to other components in order to ensure adequate ventilation of the modules during operation!

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

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

**Optimum installation position (standard)**

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

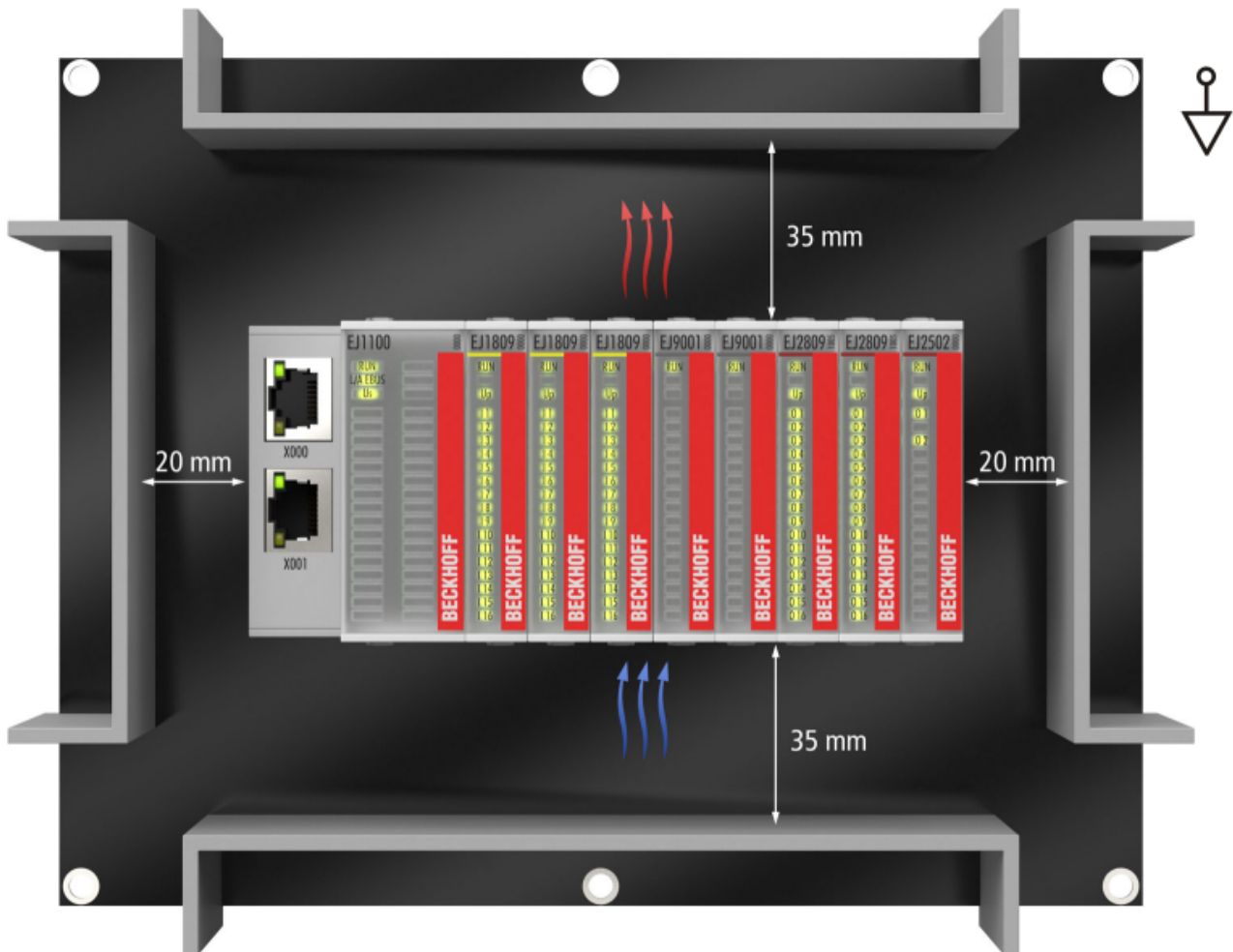


Fig. 15: Recommended distances for standard installation position

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

**Other installation positions**

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

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

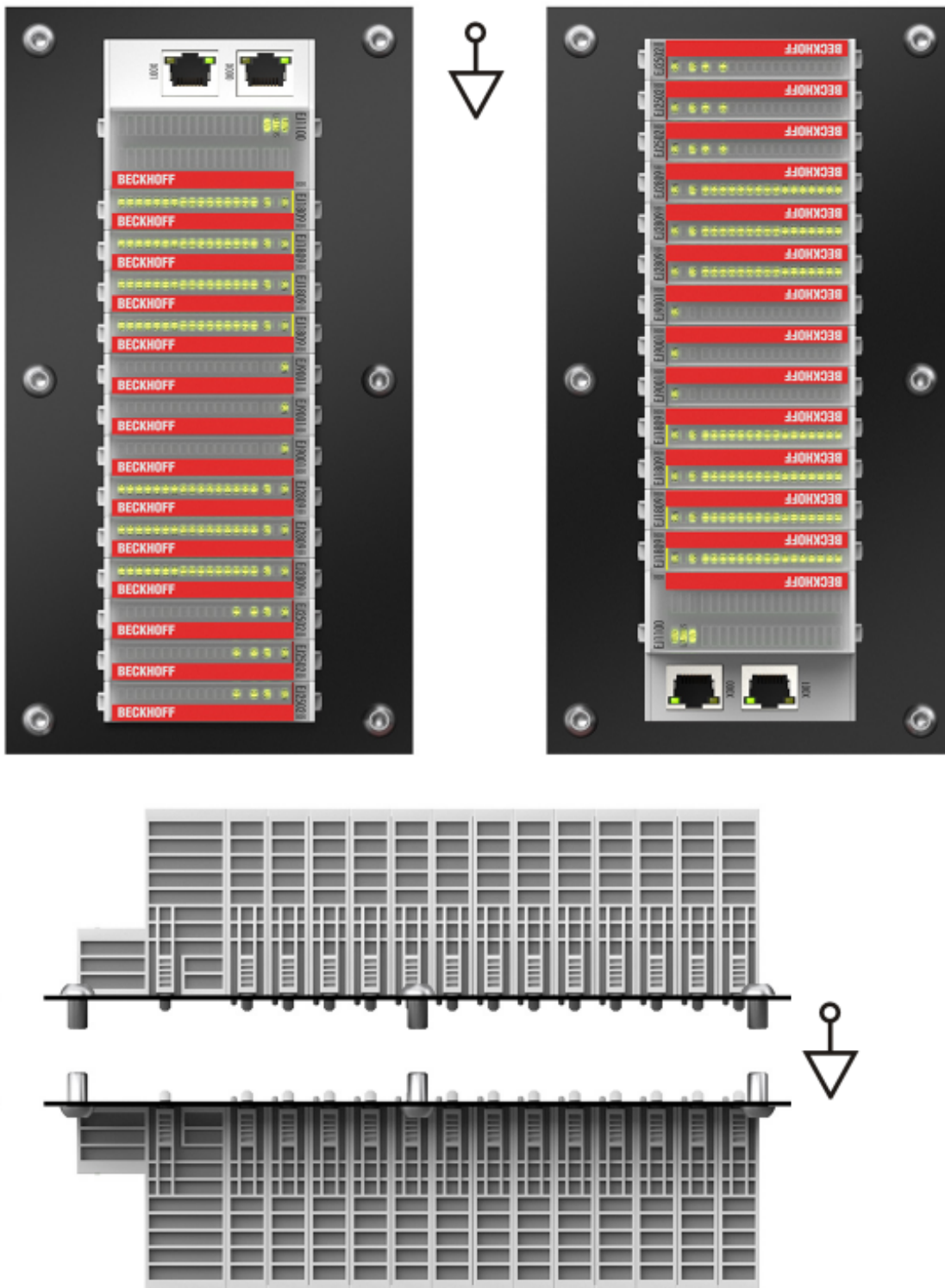


Fig. 16: Other installation positions

## 4.5 Codings

### 4.5.1 Color coding

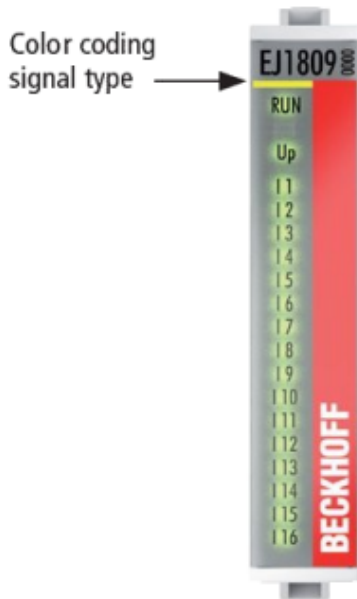


Fig. 17: EJ modules color code; sample: EJ1809

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

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

### 4.5.2 Mechanical position coding

The modules have two signal-specific coding pins on the underside (see Figs. B1 and B2 below). In conjunction with the coding holes in the signal distribution board (see Figs. A1 and A2 below), the coding pins provide an option for mechanical protection against incorrect connection. This significantly reduces the risk of error during installation and service.

Couplers and placeholder modules have no coding pins.

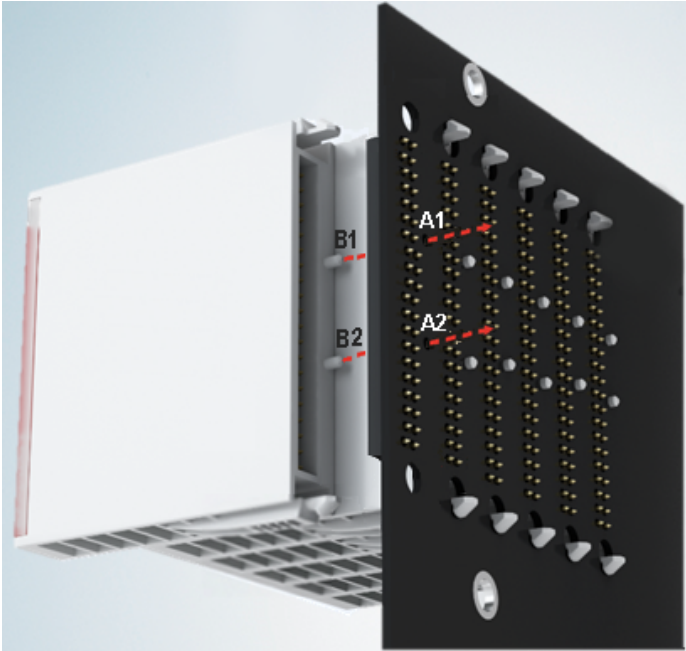


Fig. 18: Mechanical position coding with coding pins (B1 and B2) and coding holes (A1 and A2)

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

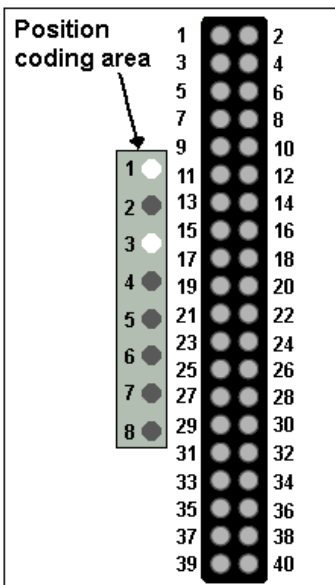


Fig. 19: Pin coding; sample: digital input modules

## 4.6 Installation on the signal distribution board

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

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

**⚠ WARNING**

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

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

**NOTICE**

**Risk of damage to components through electrostatic discharge!**

Observe the regulations for ESD protection.

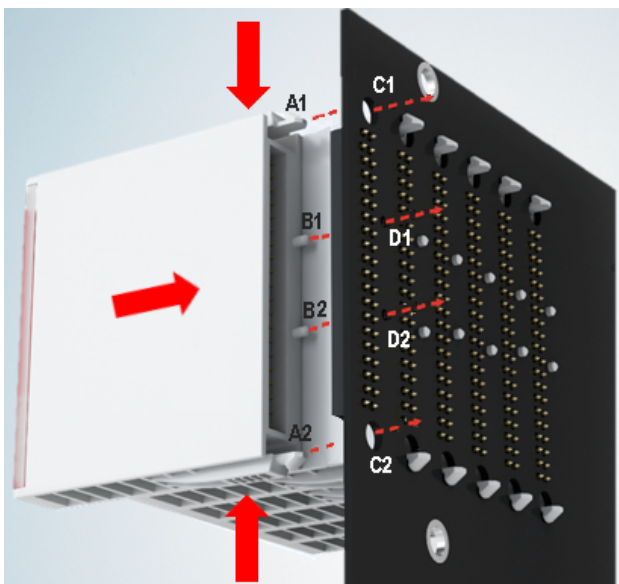


Fig. 20: Installation of EJ modules

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

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

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

**NOTICE**

- During installation ensure safe latching of the modules on the signal distribution board! The consequences of inadequate contact pressure include:
  - ⇒ loss of quality of the transferred signals,
  - ⇒ increased power dissipation of the contacts,
  - ⇒ impairment of the service life.



## 4.7 Extension options

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

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

### 4.7.1 Using placeholder modules for unused slots

The EJ9001 placeholder modules are used to close temporary gaps in the module strands (see Fig. A1 below). Gaps in the module strand cause interruption in EtherCAT communication and must be equipped with placeholder modules.

In contrast to the passive terminals of the EL series, the placeholder modules actively participate in the data exchange. Several placeholder modules can therefore be connected in series, without impairing the data exchange.

Unused slots at the end of the module strand can be left as reserve slots (see Fig. B1 below).

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

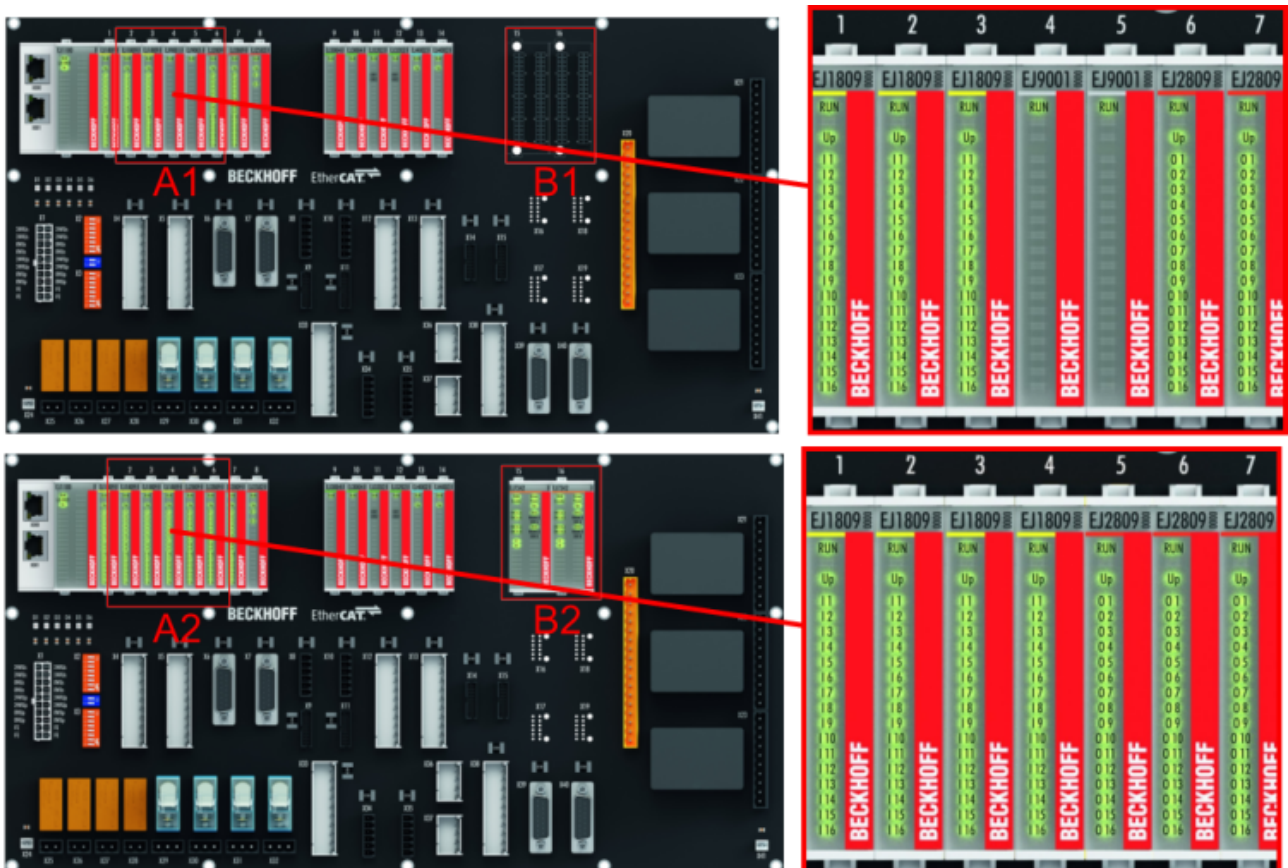


Fig. 21: Sample: Exchanging placeholder modules and assigning reserve slots

#### ● E-bus supply

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

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

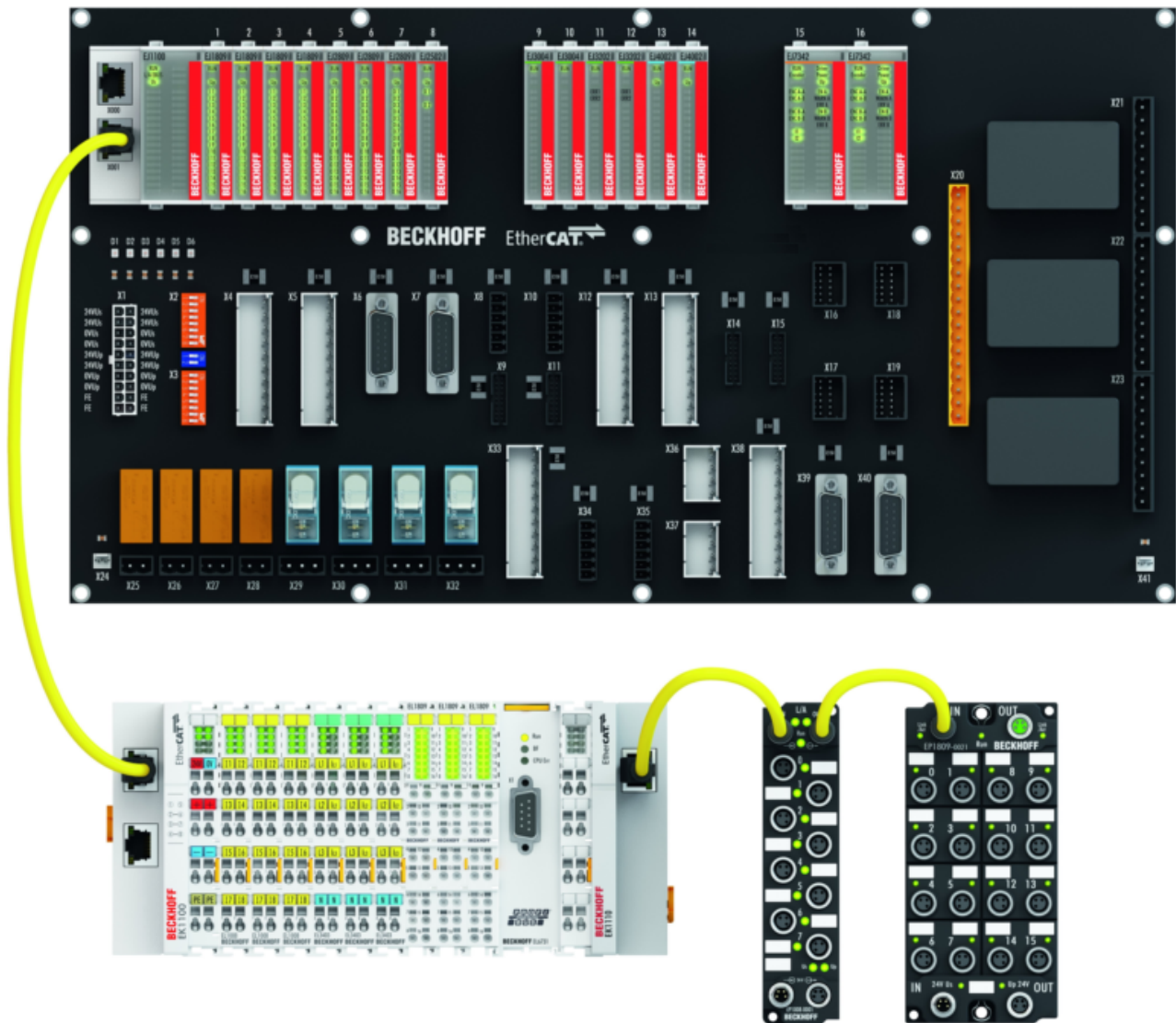


Fig. 22: Example of extension via an Ethernet/EtherCAT connection



## 4.8 IPC integration

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

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

The EK1110-004x are supplied from the power supply unit of the Embedded PC.

The E-bus signals and the supply voltage of the field side  $U_p$  are routed directly to the PCB via a plug connector at the rear of the EtherCAT EJ couplers.

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

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



Fig. 23: Example PCB with Embedded PC, EK1110-0043 and EJxxxx, rear view EK1110-0043

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


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

In combination with the ZS5000-0003 mounting set, it is possible to place the C6015 and C6017 IPCs compactly on the signal distribution board.

The EJ system is optimally connected to the IPC via the corresponding EtherCAT Cable (see following Fig. [A]).

The IPC can be supplied directly via the signal distribution board using the enclosed power plug (see Fig. [B] below).

**NOTICE**



**Positioning on the signal distribution board**

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

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



Fig. 24: Example for the connection of a C6015 IPC to an EJ system

## 4.9 Disassembly of the signal distribution board

### ⚠ WARNING

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

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

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

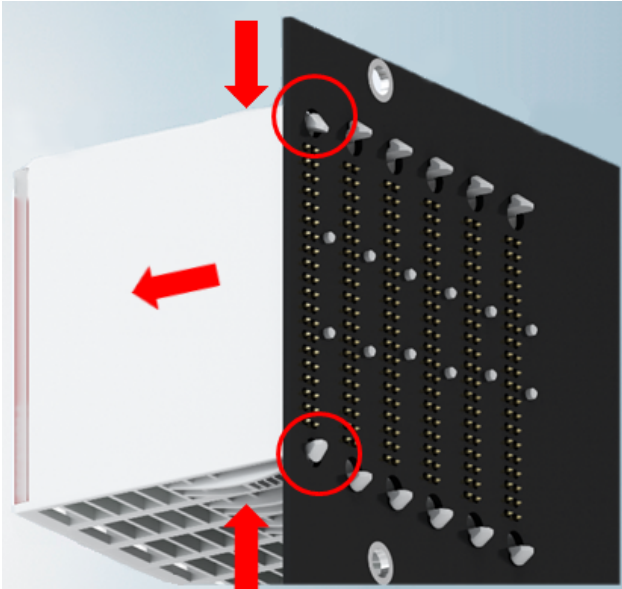


Fig. 25: Disassembly of EJ modules

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

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

## 4.10 Disposal



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

## 5 EtherCAT basics

Please refer to the [EtherCAT System Documentation](#) for the EtherCAT fieldbus basics.

## 6 Commissioning

### 6.1 Note on documentation for the EL3255

Detailed documentation on the commissioning of the EJ3255 module is being prepared.

#### NOTICE



##### Damage to devices or loss of data

The descriptions and notes on the commissioning of the EL3255 EtherCAT Terminal is transferable to the EJ3255 EtherCAT plug-in modules.

Before commissioning, read the detailed description of the process data, operating modes and parameterization in the [EL3255](#) documentation.

### 6.2 EJ3255 - Object description and parameterization

#### ● EtherCAT XML Device Description



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

#### NOTICE



##### Parameterization via the CoE list (CAN over EtherCAT)

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

Please note the general CoE notes in the EtherCAT System Documentation in chapter "[CoE-interface](#)" when using/manipulating the CoE parameters:

- Keep a startup list if components have to be replaced
- Differentiation between online/offline dictionary,
- existence of current XML description
- use "CoE reload" for resetting changes

#### ● Relevant objects



The object description refers to EtherCAT with different number of channels. Observe the indices with regard to the objects relevant for the respective device (channel dependent).

#### Introduction

The CoE overview contains objects for different purposes of use:

- [Objects required for parameterization \[▶ 39\]](#) and [profile-specific objects \[▶ 40\]](#) required during commissioning
- [Objects for indicating internal settings \[▶ 41\]](#) (may be fixed)

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

## 6.2.1 Restore object

### Index 1011 Restore default parameters

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

## 6.2.2 Configuration data

### Index 80n0 AI Settings for $0 \leq n \leq 4$ (Ch. 1 - 5, dependent on the number of channels)

**i** The filter characteristics are set via index 0x8000:15 [[▶ 39](#)]

The filter frequencies are set for all channels of the module centrally via index 0x8000:15 (channel 1). All other corresponding indices 0x80n0:15 have no parameterization function! The latest firmware version (see status table) returns an EtherCAT-compliant error message, if the filter characteristics of other channels (index 0x80n0:06, 0x80n0:15) are set.

| Index (hex) | Name                      | Meaning  | Data type | Flags | Default                            |
|-------------|---------------------------|--|-----------|-------|------------------------------------|
| 80n0:0      | AI Settings               | Maximum subindex   | UINT8     | RO    | 0x1C (28 <sub>dec</sub> )          |
| 80n0:01     | Enable user scale         | Enablement of the user scaling   | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:05     | Siemens bits              | The S5 bits are shown in the three low-order bits (value 0x60n0:11 [ <a href="#">▶ 40</a> ])<br>Bit 0 = 1 ("overrange" or "underrange")<br>Bit 1 (not used)<br>Bit 2 (not used)  | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:06     | Enable filter             | Enable filter, which makes PLC-cycle-synchronous data exchange unnecessary   | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:07     | Enable limit 1            | The status bits are set in relation to Limit 1.  | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:08     | Enable limit 2            | The status bits are set in relation to Limit 2.  | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:0A     | Enable user calibration   | Enabling of the user calibration   | BOOLEAN   | RW    | 0x00 (0 <sub>dec</sub> )           |
| 80n0:0B     | Enable vendor calibration | Enabling of the vendor calibration   | BOOLEAN   | RW    | 0x01 (1 <sub>dec</sub> )           |
| 80n0:0E     | Swap limit bits           | Swap limit bits  | BOOLEAN   | RW    | 0x01 (1 <sub>dec</sub> )           |
| 80n0:11     | User scale offset         | User scaling offset  | INT16     | RW    | 0x0000 (0 <sub>dec</sub> )         |
| 80n0:12     | User scale gain           | This is the user scaling gain.<br>The gain is represented in fixed-point format, with the factor 2 <sup>-16</sup> .<br>The value 1 corresponds to 65535 (0x00010000).  | INT32     | RW    | 0x00010000 (65536 <sub>dec</sub> ) |
| 80n0:13     | Limit 1                   | First limit value for setting the status bits (resolution 0.1°C)   | INT16     | RW    | 0x0000 (0 <sub>dec</sub> )         |
| 80n0:14     | Limit 2                   | Second limit value for setting the status bits (resolution 0.1°C)  | INT16     | RW    | 0x0000 (0 <sub>dec</sub> )         |
| Index (hex) | Name                      | Meaning  | Data type | Flags | Default                            |
| 80n0:15     | Filter settings           | This object determines the digital filter settings, if it is active via "Enable filter" (index 0x80n0:06). The possible settings are sequentially numbered. see note "Setting the filter characteristics via Index 0x8000:15"<br>0: 50 Hz<br>1: 60 Hz<br>2: IIR1 (400 Hz)<br>3: IIR2 (500 Hz)<br>4: IIR3 (100 Hz)<br>5: IIR4 (50 Hz)<br>6: IIR5 (24 Hz)<br>7: IIR6 (12 Hz)<br>8: IIR7 (6.2 Hz)<br>9: IIR8 (3.0 Hz) | UINT16    | RW    | 0x0000 (0 <sub>dec</sub> )         |
| 80n0:17     | User calibration offset   | User calibration offset  | INT16     | RW    | 0x0000 (0 <sub>dec</sub> )         |
| 80n0:18     | User calibration gain     | User gain calibration  | UINT16    | RW    | 0x4000 (16384 <sub>dec</sub> )     |
| 80n0:1C     | Linearization             | Linearization for potentiometer values ≥ 25 kΩ:<br>0 = off (up to 10 kΩ),<br>1 = 25 kΩ,<br>2 = 50 kΩ,  | INT16     | RW    | 0x0000 (0 <sub>dec</sub> )         |

## Index 8047 AI Device Settings

| Index (hex) | Name                    | Meaning   | Data type | Flags | Default                    |
|-------------|-------------------------|---|-----------|-------|----------------------------|
| 8047:0      | AI Device Settings      | Max. Subindex   | UINT8     | RO    | 0x11 (17 <sub>dec</sub> )  |
| 8047:11     | Wire breakage detection | 0: sensor/load/supply monitoring<br>1: load/supply monitoring<br>2: supply monitoring<br>3: off | ENUM16    | RW    | 0x0000 (0 <sub>dec</sub> ) |

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

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

### 6.2.4 Input data

#### Index 60n0 AI Inputs for $0 \leq n \leq 4$ (Ch. 1 - 5, dependent on the number of channels)

| Index (hex) | Name         | Meaning   | Data type | Flags | Default                    |
|-------------|--------------|---|-----------|-------|----------------------------|
| 60n0:0      | AI inputs    | Maximum subindex  | UINT8     | RO    | 0x11 (17 <sub>dec</sub> )  |
| 60n0:01     | Underrange   | The measuring range is undershot.   | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:02     | Overrange    | The measuring range is overshoot.<br>("open circuit" detection if "Error" [Index 0x60n0:07]) is set.  | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:03     | Limit 1      | Limit value monitoring  | BIT2      | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:05     | Limit 2      | 0: not active<br>1: Value > limit value<br>2: Value < limit value<br>3: Value = limit value   | BIT2      | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:07     | Error        | The error bit is set if the data is invalid.  | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:0E     | Sync Error   | The Sync Error bit is only required for the Distributed Clocks mode.<br>It indicates whether a synchronization error occurred in the expired cycle. |           |       |                            |
| 60n0:0F     | TxPDO State  | Validity of the data of the associated TxPDO<br>(0 = valid, 1 = invalid).   | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:10     | TxPDO Toggle | The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated.  | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )   |
| 60n0:11     | Value        | Measured value as 32 bit signed integer   | INT16     | RO    | 0x0000 (0 <sub>dec</sub> ) |

### 6.2.5 Configuration data vendor-specific

#### Index 80nF AI Vendor data for $0 \leq n \leq 4$ (Ch. 1 - 5)

| Index (hex) | Name               | Meaning                   | Data type | Flags | Default                        |
|-------------|--------------------|---------------------------|-----------|-------|--------------------------------|
| 80nF:0      | AI vendor data     | Maximum subindex          | UINT8     | RO    | 0x02 (2 <sub>dec</sub> )       |
| 80nF:01     | Calibration offset | Vendor calibration offset | INT32     | RW    | 0x00000000 (0 <sub>dec</sub> ) |
| 80nF:02     | Calibration gain   | Vendor calibration gain   | UINT16    | RW    | 0x4000 (16384 <sub>dec</sub> ) |

### 6.2.6 Information and diagnostic data

#### Index 80nE RTD Internal data for $0 \leq n \leq 4$ (Ch. 1 - 5, dependent on the number of channels)

| Index (hex) | Name             | Meaning          | Data type | Flags | Default                        |
|-------------|------------------|------------------|-----------|-------|--------------------------------|
| 80nE:0      | AI internal data | Maximum subindex | UINT8     | RO    | 0x01 (1 <sub>dec</sub> )       |
| 80nE:01     | ADC raw value 1  | ADC raw value 1  | INT32     | RO    | 0x00000000 (0 <sub>dec</sub> ) |



**Index F000 Modular device profile**

| Index (hex) | Name                      | Meaning  | Data type | Flags | Default                     |
|-------------|---------------------------|--|-----------|-------|-----------------------------|
| F000:0      | Modular device profile    | General information for the modular device profile       | UINT8     | RO    | 0x02 (2 <sub>dec</sub> )    |
| F000:01     | Module index distance     | Index distance of the objects of the individual channels | UINT16    | RO    | 0x0010 (16 <sub>dec</sub> ) |
| F000:02     | Maximum number of modules | Number of channels                                       | UINT16    | RO    | 0x0001 (1 <sub>dec</sub> )  |

**Index F008 Code word**

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

**Index F010 Module list [for {n=1} (1-channel) to {n=1,...,n=4} (5-channel)]**

| Index (hex) | Name         | Meaning          | Data type | Flags | Default                          |
|-------------|--------------|------------------|-----------|-------|----------------------------------|
| F010:0      | Module list  | Maximum subindex | UINT8     | RO    | 0x05 (5 <sub>dec</sub> )         |
| F010:0n     | Subindex 00n | AI Profiles      | INT32     | RO    | 0x0000012C (300 <sub>dec</sub> ) |

**6.2.7 Standard objects (0x1000-0x1FFF)**

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

**Index 1000 Device type**

| Index (hex) | Name        | Meaning   | Data type | Flags | Default                               |
|-------------|-------------|---|-----------|-------|---------------------------------------|
| 1000:0      | Device type | Device type of the EtherCAT slave: The Lo-Word contains the CoE profile used (5001). The Hi-Word contains the module profile according to the modular device profile. | UINT32    | RO    | 0x012C1389 (19665801 <sub>dec</sub> ) |

**Index 1008 Device name**

| Index (hex) | Name        | Meaning                           | Data type | Flags | Default |
|-------------|-------------|-----------------------------------|-----------|-------|---------|
| 1008:0      | Device name | Device name of the EtherCAT slave | STRING    | RO    | EJ3255  |

**Index 1009 Hardware version**

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

**Index 100A Software version**

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

**Index 1018 Identity**

| Index (hex) | Name          | Meaning   | Data type | Flags | Default                              |
|-------------|---------------|---|-----------|-------|--------------------------------------|
| 1018:0      | Identity      | Information for identifying the slave   | UINT8     | RO    | 0x04 (4 <sub>dec</sub> )             |
| 1018:01     | Vendor ID     | Vendor ID of the EtherCAT slave   | UINT32    | RO    | 0x00000002 (2 <sub>dec</sub> )       |
| 1018:02     | Product code  | Product code of the EtherCAT slave  | UINT32    | RO    | 0CB72852 (213330002 <sub>dec</sub> ) |
| 1018:03     | Revision      | Revision number of the EtherCAT slave; the Low Word (bit 0-15) indicates the special terminal number, the High Word (bit 16-31) refers to the device description  | UINT32    | RO    | 0x00000000 (0 <sub>dec</sub> )       |
| 1018:04     | Serial number | Serial number of the EtherCAT slave; the Low Byte (bit 0-7) of the Low Word contains the year of production, the High Byte (bit 8-15) of the Low Word contains the week of production, the High Word (bit 16-31) is 0 | UINT32    | RO    | 0x00000000 (0 <sub>dec</sub> )       |

**Index 10F0 Backup parameter handling**

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

**Index 1800 AI TxPDO-Par Standard Ch. 1**

| Index (hex) | Name                        | Meaning   | Data type       | Flags | Default                  |
|-------------|-----------------------------|---|-----------------|-------|--------------------------|
| 1800:0      | AI TxPDO-Par Standard Ch. 1 | PDO parameter TxPDO 1   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1800:06     | Exclude TxPDOs              | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 1. | OCTET-STRING[2] | RO    | 01 1A                    |

**Index 1801 AI TxPDO-Par Compact Ch. 1**

| Index (hex) | Name                      | Meaning   | Data type       | Flags | Default                  |
|-------------|---------------------------|---|-----------------|-------|--------------------------|
| 1801:0      | AI TxPDO-Par Compact Ch.1 | PDO parameter TxPDO 2   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1801:06     | Exclude TxPDOs            | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 2. | OCTET-STRING[2] | RO    | 00 1A                    |

**Index 1802 AI TxPDO-Par Standard Ch. 2**

| Index (hex) | Name                       | Meaning   | Data type       | Flags | Default                  |
|-------------|----------------------------|---|-----------------|-------|--------------------------|
| 1802:0      | AI TxPDO-Par Standard Ch.2 | PDO parameter TxPDO 3   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1802:06     | Exclude TxPDOs             | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 3. | OCTET-STRING[2] | RO    | 03 1A                    |

**Index 1803 AI TxPDO-Par Compact Ch. 2**

| Index (hex) | Name                      | Meaning   | Data type       | Flags | Default                  |
|-------------|---------------------------|---|-----------------|-------|--------------------------|
| 1803:0      | AI TxPDO-Par Compact Ch.2 | PDO parameter TxPDO 4   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1803:06     | Exclude TxPDOs            | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 4. | OCTET-STRING[2] | RO    | 02 1A                    |

**Index 1804 AI TxPDO-Par Standard Ch. 3**

| Index (hex) | Name                       | Meaning   | Data type       | Flags | Default                  |
|-------------|----------------------------|---|-----------------|-------|--------------------------|
| 1804:0      | AI TxPDO-Par Standard Ch.3 | PDO parameter TxPDO 5   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1804:06     | Exclude TxPDOs             | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 5. | OCTET-STRING[2] | RO    | 05 1A                    |

**Index 1805 AI TxPDO-Par Compact Ch. 3**

| Index (hex) | Name                      | Meaning   | Data type       | Flags | Default                  |
|-------------|---------------------------|---|-----------------|-------|--------------------------|
| 1805:0      | AI TxPDO-Par Compact Ch.3 | PDO parameter TxPDO 6   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1805:06     | Exclude TxPDOs            | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 6. | OCTET-STRING[2] | RO    | 04 1A                    |

**Index 1806 AI TxPDO-Par Standard Ch. 4**

| Index (hex) | Name                       | Meaning   | Data type       | Flags | Default                  |
|-------------|----------------------------|---|-----------------|-------|--------------------------|
| 1806:0      | AI TxPDO-Par Standard Ch.2 | PDO parameter TxPDO 7   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1806:06     | Exclude TxPDOs             | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 7. | OCTET-STRING[2] | RO    | 07 1A                    |

**Index 1807 AI TxPDO-Par Compact Ch. 4**

| Index (hex) | Name                      | Meaning   | Data type       | Flags | Default                  |
|-------------|---------------------------|---|-----------------|-------|--------------------------|
| 1807:0      | AI TxPDO-Par Compact Ch.4 | PDO parameter TxPDO 8   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1807:06     | Exclude TxPDOs            | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 8. | OCTET-STRING[2] | RO    | 06 1A                    |

**Index 1808 AI TxPDO-Par Standard Ch. 5**

| Index (hex) | Name                       | Meaning   | Data type       | Flags | Default                  |
|-------------|----------------------------|---|-----------------|-------|--------------------------|
| 1808:0      | AI TxPDO-Par Standard Ch.5 | PDO parameter TxPDO 9   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1808:06     | Exclude TxPDOs             | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 9. | OCTET-STRING[2] | RO    | 09 1A                    |

**Index 1809 AI TxPDO-Par Compact Ch. 5**

| Index (hex) | Name                      | Meaning  | Data type       | Flags | Default                  |
|-------------|---------------------------|--|-----------------|-------|--------------------------|
| 1809:0      | AI TxPDO-Par Compact Ch.5 | PDO parameter TxPDO 10   | UINT8           | RO    | 0x06 (6 <sub>dec</sub> ) |
| 1809:06     | Exclude TxPDOs            | Specifies the TxPDOs (index of TxPDO mapping objects) that must not be transferred together with TxPDO 10. | OCTET-STRING[2] | RO    | 08 1A                    |

**Index 1A00 AI TxPDO-Map Standard Ch. 1**

| Index (hex) | Name                       | Meaning   | Data type | Flags | Default                   |
|-------------|----------------------------|---|-----------|-------|---------------------------|
| 1A00:0      | AI TxPDO-Map Standard Ch.1 | PDO Mapping TxPDO 1   | UINT8     | RW    | 0x0B (11 <sub>dec</sub> ) |
| 1A00:01     | SubIndex 001               | 1. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x01 (Underrange))    | UINT32    | RW    | 0x6000:01, 1              |
| 1A00:02     | SubIndex 002               | 2. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x02 (Overrange))     | UINT32    | RW    | 0x6000:02, 1              |
| 1A00:03     | SubIndex 003               | 3. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x03 (Limit 1))       | UINT32    | RW    | 0x6000:03, 2              |
| 1A00:04     | SubIndex 004               | 4. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x05 (Limit 2))       | UINT32    | RW    | 0x6000:05, 2              |
| 1A00:05     | SubIndex 005               | 5. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x07 (Error))         | UINT32    | RW    | 0x6000:07, 1              |
| 1A00:06     | SubIndex 006               | 6. PDO Mapping entry (1 bit align)  | UINT32    | RW    | 0x0000:00, 1              |
| 1A00:07     | SubIndex 007               | 7. PDO Mapping entry (5 bits align)   | UINT32    | RW    | 0x0000:00, 5              |
| 1A00:08     | SubIndex 008               | 8. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x0E (Sync error))    | UINT32    | RW    | 0x6000:0E, 1              |
| 1A00:09     | SubIndex 009               | 9. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x0F (TxPDO-State))   | UINT32    | RW    | 0x6000:0F, 1              |
| 1A00:0A     | SubIndex 010               | 10. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x10 (TxPDO-Toggle)) | UINT32    | RW    | 0x6000:10, 1              |
| 1A00:0B     | SubIndex 011               | 11. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x11 (Value))        | UINT32    | RW    | 0x6000:11, 16             |

**Index 1A01 AI TxPDO-Map Compact Ch. 1**

| Index (hex) | Name                      | Meaning   | Data type | Flags | Default                  |
|-------------|---------------------------|---|-----------|-------|--------------------------|
| 1A01:0      | AI TxPDO-Map Compact Ch.1 | PDO Mapping TxPDO 2   | UINT8     | RW    | 0x01 (1 <sub>dec</sub> ) |
| 1A01:01     | SubIndex 001              | 1. PDO Mapping entry (object 0x6000 (AI Inputs Ch.1), entry 0x11 (Value)) | UINT32    | RW    | 0x6000:11, 1             |

**Index 1A02 AI TxPDO-Map Standard Ch. 2**

| Index (hex) | Name                       | Meaning   | Data type | Flags | Default                   |
|-------------|----------------------------|---|-----------|-------|---------------------------|
| 1A02:0      | AI TxPDO-Map Standard Ch.2 | PDO Mapping TxPDO 3   | UINT8     | RW    | 0x0B (11 <sub>dec</sub> ) |
| 1A02:01     | SubIndex 001               | 1. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x01 (Underrange))    | UINT32    | RW    | 0x6010:01, 1              |
| 1A02:02     | SubIndex 002               | 2. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x02 (Overrange))     | UINT32    | RW    | 0x6010:02, 1              |
| 1A02:03     | SubIndex 003               | 3. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x03 (Limit 1))       | UINT32    | RW    | 0x6010:03, 2              |
| 1A02:04     | SubIndex 004               | 4. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x05 (Limit 2))       | UINT32    | RW    | 0x6010:05, 2              |
| 1A02:05     | SubIndex 005               | 5. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x07 (Error))         | UINT32    | RW    | 0x6010:07, 1              |
| 1A02:06     | SubIndex 006               | 6. PDO Mapping entry (1 bit align)  | UINT32    | RW    | 0x0000:00, 1              |
| 1A02:07     | SubIndex 007               | 7. PDO Mapping entry (5 bits align)   | UINT32    | RW    | 0x0000:00, 5              |
| 1A02:08     | SubIndex 008               | 8. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x0E (Sync error))    | UINT32    | RW    | 0x6010:0E, 1              |
| 1A02:09     | SubIndex 009               | 9. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x0F (TxPDO-State))   | UINT32    | RW    | 0x6010:0F, 1              |
| 1A02:0A     | SubIndex 010               | 10. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x10 (TxPDO-Toggle)) | UINT32    | RW    | 0x6010:10, 1              |
| 1A02:0B     | SubIndex 011               | 11. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x11 (Value))        | UINT32    | RW    | 0x6010:11, 16             |

**Index 1A03 AI TxPDO-Map Compact Ch. 2**

| Index (hex) | Name                      | Meaning   | Data type | Flags | Default                  |
|-------------|---------------------------|---|-----------|-------|--------------------------|
| 1A03:0      | AI TxPDO-Map Compact Ch.2 | PDO Mapping TxPDO 4   | UINT8     | RW    | 0x01 (1 <sub>dec</sub> ) |
| 1A03:01     | SubIndex 001              | 1. PDO Mapping entry (object 0x6010 (AI Inputs Ch.2), entry 0x11 (Value)) | UINT32    | RW    | 0x6010:11, 1             |

**Index 1A04 AI TxPDO-Map Standard Ch. 3**

| Index (hex) | Name                       | Meaning   | Data type | Flags | Default                   |
|-------------|----------------------------|---|-----------|-------|---------------------------|
| 1A04:0      | AI TxPDO-Map Standard Ch.3 | PDO Mapping TxPDO 5   | UINT8     | RW    | 0x0B (11 <sub>dec</sub> ) |
| 1A04:01     | SubIndex 001               | 1. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x01 (Underrange))    | UINT32    | RW    | 0x6020:01, 1              |
| 1A04:02     | SubIndex 002               | 2. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x02 (Overrange))     | UINT32    | RW    | 0x6020:02, 1              |
| 1A04:03     | SubIndex 003               | 3. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x03 (Limit 1))       | UINT32    | RW    | 0x6020:03, 2              |
| 1A04:04     | SubIndex 004               | 4. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x05 (Limit 2))       | UINT32    | RW    | 0x6020:05, 2              |
| 1A04:05     | SubIndex 005               | 5. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x07 (Error))         | UINT32    | RW    | 0x6020:07, 1              |
| 1A04:06     | SubIndex 006               | 6. PDO Mapping entry (1 bit align)  | UINT32    | RW    | 0x0000:00, 1              |
| 1A04:07     | SubIndex 007               | 7. PDO Mapping entry (5 bits align)   | UINT32    | RW    | 0x0000:00, 5              |
| 1A04:08     | SubIndex 008               | 8. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x0E (Sync error))    | UINT32    | RW    | 0x6020:0E, 1              |
| 1A04:09     | SubIndex 009               | 9. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x0F (TxPDO-State))   | UINT32    | RW    | 0x6020:0F, 1              |
| 1A04:0A     | SubIndex 010               | 10. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x10 (TxPDO-Toggle)) | UINT32    | RW    | 0x6020:10, 1              |
| 1A04:0B     | SubIndex 011               | 11. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x11 (Value))        | UINT32    | RW    | 0x6020:11, 16             |

**Index 1A05 AI TxPDO-Map Compact Ch. 3**

| Index (hex) | Name                      | Meaning   | Data type | Flags | Default                  |
|-------------|---------------------------|---|-----------|-------|--------------------------|
| 1A05:0      | AI TxPDO-Map Compact Ch.3 | PDO Mapping TxPDO 6   | UINT8     | RW    | 0x01 (1 <sub>dec</sub> ) |
| 1A05:01     | SubIndex 001              | 1. PDO Mapping entry (object 0x6020 (AI Inputs Ch.3), entry 0x11 (Value)) | UINT32    | RW    | 0x6020:11, 1             |

**Index 1A06 AI TxPDO-Map Standard Ch. 4**

| Index (hex) | Name                       | Meaning   | Data type | Flags | Default                   |
|-------------|----------------------------|---|-----------|-------|---------------------------|
| 1A06:0      | AI TxPDO-Map Standard Ch.4 | PDO Mapping TxPDO 7   | UINT8     | RW    | 0x0B (11 <sub>dec</sub> ) |
| 1A06:01     | SubIndex 001               | 1. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x01 (Underrange))    | UINT32    | RW    | 0x6030:01, 1              |
| 1A06:02     | SubIndex 002               | 2. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x02 (Overrange))     | UINT32    | RW    | 0x6030:02, 1              |
| 1A06:03     | SubIndex 003               | 3. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x03 (Limit 1))       | UINT32    | RW    | 0x6030:03, 2              |
| 1A06:04     | SubIndex 004               | 4. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x05 (Limit 2))       | UINT32    | RW    | 0x6030:05, 2              |
| 1A06:05     | SubIndex 005               | 5. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x07 (Error))         | UINT32    | RW    | 0x6030:07, 1              |
| 1A06:06     | SubIndex 006               | 6. PDO Mapping entry (1 bit align)  | UINT32    | RW    | 0x0000:00, 1              |
| 1A06:07     | SubIndex 007               | 7. PDO Mapping entry (5 bits align)   | UINT32    | RW    | 0x0000:00, 5              |
| 1A06:08     | SubIndex 008               | 8. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x0E (Sync error))    | UINT32    | RW    | 0x6030:0E, 1              |
| 1A06:09     | SubIndex 009               | 9. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x0F (TxPDO-State))   | UINT32    | RW    | 0x6030:0F, 1              |
| 1A06:0A     | SubIndex 010               | 10. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x10 (TxPDO-Toggle)) | UINT32    | RW    | 0x6030:10, 1              |
| 1A06:0B     | SubIndex 011               | 11. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x11 (Value))        | UINT32    | RW    | 0x6030:11, 16             |

**Index 1A07 AI TxPDO-Map Compact Ch. 4**

| Index (hex) | Name                      | Meaning   | Data type | Flags | Default                  |
|-------------|---------------------------|---|-----------|-------|--------------------------|
| 1A07:0      | AI TxPDO-Map Compact Ch.4 | PDO Mapping TxPDO 8   | UINT8     | RW    | 0x01 (1 <sub>dec</sub> ) |
| 1A07:01     | SubIndex 001              | 1. PDO Mapping entry (object 0x6030 (AI Inputs Ch.4), entry 0x11 (Value)) | UINT32    | RW    | 0x6030:11, 1             |

**Index 1A08 AI TxPDO-Map Standard Ch. 5**

| Index (hex) | Name                       | Meaning   | Data type | Flags | Default                   |
|-------------|----------------------------|---|-----------|-------|---------------------------|
| 1A08:0      | AI TxPDO-Map Standard Ch.5 | PDO Mapping TxPDO 9   | UINT8     | RW    | 0x0B (11 <sub>dec</sub> ) |
| 1A08:01     | SubIndex 001               | 1. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x01 (Underrange))    | UINT32    | RW    | 0x6040:01, 1              |
| 1A08:02     | SubIndex 002               | 2. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x02 (Overrange))     | UINT32    | RW    | 0x6040:02, 1              |
| 1A08:03     | SubIndex 003               | 3. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x03 (Limit 1))       | UINT32    | RW    | 0x6040:03, 2              |
| 1A08:04     | SubIndex 004               | 4. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x05 (Limit 2))       | UINT32    | RW    | 0x6040:05, 2              |
| 1A08:05     | SubIndex 005               | 5. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x07 (Error))         | UINT32    | RW    | 0x6040:07, 1              |
| 1A08:06     | SubIndex 006               | 6. PDO Mapping entry (1 bit align)  | UINT32    | RW    | 0x0000:00, 1              |
| 1A08:07     | SubIndex 007               | 7. PDO Mapping entry (5 bits align)   | UINT32    | RW    | 0x0000:00, 5              |
| 1A08:08     | SubIndex 008               | 8. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x0E (Sync error))    | UINT32    | RW    | 0x6040:0E, 1              |
| 1A08:09     | SubIndex 009               | 9. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x0F (TxPDO-State))   | UINT32    | RW    | 0x6040:0F, 1              |
| 1A08:0A     | SubIndex 010               | 10. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x10 (TxPDO Toggle)) | UINT32    | RW    | 0x6040:10, 1              |
| 1A08:0B     | SubIndex 011               | 11. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x11 (Value))        | UINT32    | RW    | 0x6040:11, 16             |

**Index 1A09 AI TxPDO-Map Compact Ch. 5**

| Index (hex) | Name                      | Meaning   | Data type | Flags | Default                  |
|-------------|---------------------------|---|-----------|-------|--------------------------|
| 1A09:0      | AI TxPDO-Map Compact Ch.5 | PDO Mapping TxPDO 10  | UINT8     | RW    | 0x01 (1 <sub>dec</sub> ) |
| 1A09:01     | SubIndex 001              | 1. PDO Mapping entry (object 0x6040 (AI Inputs Ch.5), entry 0x11 (Value)) | UINT32    | RW    | 0x6040:11, 1             |

**Index 1C00 Sync manager type**

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

**Index 1C12 RxPDO assign**

| Index (hex) | Name         | Meaning            | Data type | Flags | Default                  |
|-------------|--------------|--------------------|-----------|-------|--------------------------|
| 1C12:0      | RxPDO assign | PDO Assign Outputs | UINT8     | RW    | 0x00 (0 <sub>dec</sub> ) |

**Index 1C13 TxPDO assign**

| Index (hex) | Name         | Meaning  | Data type | Flags | Default                       |
|-------------|--------------|--|-----------|-------|-------------------------------|
| 1C13:0      | TxPDO assign | PDO Assign Inputs  | UINT8     | RW    | 0x05 (5 <sub>dec</sub> )      |
| 1C13:01     | Subindex 001 | 1. allocated TxPDO (contains the index of the associated TxPDO mapping object) | UINT16    | RW    | 0x1A00 (6656 <sub>dec</sub> ) |
| 1C13:02     | Subindex 002 | 2. allocated TxPDO (contains the index of the associated TxPDO mapping object) | UINT16    | RW    | 0x1A02 (6658 <sub>dec</sub> ) |
| 1C13:03     | Subindex 003 | 3. allocated TxPDO (contains the index of the associated TxPDO mapping object) | UINT16    | RW    | 0x1A04 (6660 <sub>dec</sub> ) |
| 1C13:04     | Subindex 004 | 4. allocated TxPDO (contains the index of the associated TxPDO mapping object) | UINT16    | RW    | 0x1A06 (6662 <sub>dec</sub> ) |
| 1C13:05     | Subindex 005 | 5. allocated TxPDO (contains the index of the associated TxPDO mapping object) | UINT16    | RW    | 0x1A08 (6664 <sub>dec</sub> ) |

## Index 1C33 SM input parameter

| Index (hex) | Name                    | Meaning  | Data type | Flags | Default                             |
|-------------|-------------------------|--|-----------|-------|-------------------------------------|
| 1C33:0      | SM input parameter      | Synchronization parameters for the inputs  | UINT8     | RO    | 0x20 (32 <sub>dec</sub> )           |
| 1C33:01     | Sync mode               | Current synchronization mode: <ul style="list-style-type: none"> <li>0: Free Run</li> <li>1: Synchron with SM 3 Event (no outputs available)</li> <li>2: DC - Synchron with SYNC0 Event</li> <li>3: DC - Synchron with SYNC1 Event</li> <li>34: Synchron with SM 2 Event (outputs available)</li> </ul>  | UINT16    | RW    | 0x0001 (1 <sub>dec</sub> )          |
| 1C33:02     | Cycle time              | Cycle time (in ns): <ul style="list-style-type: none"> <li>Free Run: Cycle time of the local timer</li> <li>Synchron with SM 2 Event: Master cycle time</li> <li>DC mode: SYNC0/SYNC1 Cycle Time</li> </ul>  | UINT32    | RW    | 0x00030D40 (200000 <sub>dec</sub> ) |
| 1C33:03     | Shift time              | Time between SYNC0 event and reading of the inputs (in ns, DC mode only)   | UINT32    | RW    | 0x0002E630 (19000 <sub>dec</sub> )  |
| 1C33:04     | Sync modes supported    | Supported synchronization modes: <ul style="list-style-type: none"> <li>Bit 0: free run is supported</li> <li>Bit 1: Synchron with SM 2 Event is supported (outputs available)</li> <li>Bit 1: Synchron with SM 3 Event is supported (no outputs available)</li> <li>Bit 2-3 = 01: DC mode is supported</li> <li>Bit 4-5 = 01: Input Shift through local event (outputs available)</li> <li>Bit 4-5 = 10: Input Shift with SYNC1 Event (no outputs available)</li> <li>Bit 14 = 1: dynamic times (measurement through writing of 0x1C33:08)</li> </ul> | UINT16    | RO    | 0x400B (16359 <sub>dec</sub> )      |
| 1C33:05     | Minimum cycle time      | Minimum cycle time (in ns)   | UINT32    | RO    | 0x00030D40 (200000 <sub>dec</sub> ) |
| 1C33:06     | Calc and copy time      | Time between reading of the inputs and availability of the inputs for the master (in ns, DC mode only)   | UINT32    | RO    | 0x00002710 (10000 <sub>dec</sub> )  |
| 1C33:07     | Minimum delay time      | Minimum time between Sync-1 Event and reading of the inputs (in ns, DC mode only)  | UINT32    | RO    | 0x00000000 (0 <sub>dec</sub> )      |
| 1C33:08     | Command                 | <ul style="list-style-type: none"> <li>0: Measurement of the local cycle time is stopped</li> <li>1: Measurement of the local cycle time is started</li> </ul> <p>The entries 0x1C33:03, 0x1C33:06, 0x1C33:09 are updated with the maximum measured values. For a subsequent measurement the measured values are reset</p>   | UINT16    | RW    | 0x0000 (0 <sub>dec</sub> )          |
| 1C33:09     | Maximum Delay time      | Time between SYNC1 event and reading of the inputs (in ns, DC mode only)   | UINT32    | RO    | 0x00000000 (0 <sub>dec</sub> )      |
| 1C33:0B     | SM event missed counter | Number of missed SM events in OPERATIONAL (DC mode only)   | UINT16    | RO    | 0x0000 (0 <sub>dec</sub> )          |
| 1C33:0C     | Cycle exceeded counter  | Number of occasions the cycle time was exceeded in OPERATIONAL (cycle was not completed in time or the next cycle began too early)   | UINT16    | RO    | 0x0000 (0 <sub>dec</sub> )          |
| 1C33:0D     | Shift too short counter | Number of occasions that the interval between SYNC0 and SYNC1 event was too short (DC mode only)   | UINT16    | RO    | 0x0000 (0 <sub>dec</sub> )          |
| 1C33:20     | Sync error              | The synchronization was not correct in the last cycle (outputs were output too late; DC mode only)   | BOOLEAN   | RO    | 0x00 (0 <sub>dec</sub> )            |



## 7 Appendix

### 7.1 Support and Service

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

#### Beckhoff's branch offices and representatives

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

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

You will also find further documentation for Beckhoff components there.

#### Support

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

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

Hotline: +49 5246 963 157  
e-mail: [support@beckhoff.com](mailto:support@beckhoff.com)  
web: [www.beckhoff.com/support](http://www.beckhoff.com/support)

#### Service

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

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

Hotline: +49 5246 963 460  
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