EC4-ENC2IT

EtherCAT SubDevice Slim Two-Channel Incremental Encoder Counter Module

with Compare Trigger and Latch Function

User Manual

(Version 1.0)

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CONTACT US

If you have any questions, please feel free to contact us via email at:
service@icpdas.com
service.icpdas@gmail.com

Revision

Revision	Date	Description	Author
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Contents

1 Product Overview 3
1.1 Introduction 3
1.2 Technical Data 4
1.3 Specification 4
1.4 Dimensions 6
2 Scope of Delivery 7
3 LED Definition 8
4 Wiring 9
4.1 Connection Interfaces 9
4.2 Internal I/O Structure 10
4.3 Jumper Settings 10
4.4 Digital Input Wiring 13
4.5 Compare Trigger Output Wiring 14
5 Basics Communication 15
5.1 EtherCAT Cabling 15
5.2 EtherCAT State Machine 15
5.3 Synchronization Modes 17
5.3.1 Free Run Mode 17
5.3.2 SM-Synchron 19
5.3.3 Distributed Clocks (DC Mode) 20
6 Project Integration 23
6.1 ESI File 23
6.1.1 Import of ESI File 23
6.2 Device Setup and Configuration 23
6.2.1 Scanning of the EtherCAT Device 24
6.2.2 Encoder Counter Configuration 25
6.2.3 EtherCAT Slave Process Data Assignment 28
7 Parameter Description 32
7.1 Configuration Parameters 32
7.1.1 Counting Mode 32
7.1.2 Signal Polarity Setting 34
7.1.2.1 Encoder Input Signal 34
7.1.2.2 Extern Latch Input Signal 35
7.1.3 Extern Latch Mode 36
7.1.4 Low Pass Filter Setting 37
7.1.5 Position Compare Configuration 38
7.1.5.1 Compare Trigger Pulse Width 38
7.1.5.2 Compare DO Trigger Signal Type 39
7.1.5.3 Compare Mode 39
Number of Compare Position 40

7.1.6 Velocity Calculation Setting 41
7.1.7 Repeat Signal 41
7.2 Process Data Parameter 42
7.2.1 Counter 42
7.2.2 Position Compare Trigger 44
7.2.2.1 Equidistant Compare Mode 45
7.2.2.2 Array Compare Mode 48
7.2.3 Index and Extern Latch 53
7.2.4 Velocity Calculation 58
8 CoE Interface 59
8.1 General Description 59
8.2 Save Data to Memory 60
8.2.1 Save Configuration Data 60
8.2.2 Save Position Compare Values 63
9 Object Description and Parameterization 67
9.1 Standard Objects 67
9.2 RxPDO Mapping Objects 68
9.3 TxPDO Mapping Objects 69
9.4 Sync Manager Objects 71
9.5 Position Compare Array 75
9.6 Input Data 76
9.7 Output Data 78
9.8 Configuration Data 82
9.9 Configuration Parameters Storage 85

1 Product Overview

1.1 Introduction

The EC4-ENC2IT is an incremental encoding counter module with two independent high-speed counter channels, based on a slim design. It reads the pulse train generated by an incremental encoder and can be used in positioning feedback applications. Each channel has two counter (A, B) and one index inputs (C). The inputs can either be single-ended or differential signals. Three counting modes are supported: clockwise/counterclockwise, pulse/direction and quadrant counting mode. Each 32-bit counter and the trigger level (falling/rising edge) can be configured and set by software.

In addition to the encoder inputs A, B and C, a latch input I for each encoder channel allows the latching and clearing of each encoder counter. Encoder position are latched at rising and falling input signal and are recorded in two separate register.

The EC4-ENC2IT supports position compare: Each encoder channel is equipped with one 32-bit compare register which compares the counter position with the compare position and generates an output signal when the counter reaches or passes the compare position. The compare function supports single, auto incremental and array position compare. The pulse width of the compare output can be set.

Each channel has got an adjustable input signal filter for filtering out electrical noises.

1.2 Technical Data

Features:

- On the fly processing: EtherCAT
- Two channels, 32-bit incremental encoder counters
- Encoder counting mode: CW/CCW , Pulse/Direction, A/B Phase
- Maximum counting rate: 4 MHz
- Encoder Input: A, B, C differential or single-ended signals
- Two digital input for counter latching
- Two digital output for position compare signal trigger: single, auto-increment and array compare
- Up to 200 compare values per encoder channel are supported for the array compare mode
- Position difference value for velocity calculation
- Encoder digital input filter
- Input level: 5V, 12V/24V with internal resistor
- Polarity setting by software for active high or active low encoder input
- A/B/C/I signal isolation voltage: 2500V optical isolation

1.3 Specification

Item	Specification	
Encoder Input		
Number of encoder inputs	2x encoder counter (A, B, C, differential or single-ended	
Counter resolution	32 bit	
Encoder mode	A/B Phase, CW/CCW, Pulse/Dir	
Maximum input pulse frequency	A/B Phase	4 MHz
	CW/CCW	4 MHz
	Pulse/Dir	4 MHz
Programmable digital filter	1 ~ 250 µs	
Input level	5V (default)	Logic high: 4 V ~ 5 V Logic low: 0 V ~ 2 V
	12 V (set by jumper)	Logic high: 5 V ~ 12 V Logic low: 0 V ~ 2 V
	24 V (set by jumper)	Logic high: 5 V ~ 24 V Logic low: 0 V ~ 2 V
A/B/C signal photo-isolation	2500 V_{DC}	
External Latch Input		
Channel	2	
Input level	5V (default)	Logic high: 4 V ~ 5 V Logic low: 0 V ~ 2 V
	12 V (set by jumper)	Logic high: 5 V ~ 12 V Logic low: 0 V ~ 2 V
	24 V (set by jumper)	Logic high: 5 V ~ 24 V Logic low: 0 V ~ 2 V

Item	Specification
Compare Trigger Output	
Channel	2
Trigger pulse width	2 ~ 32767 µs
Load voltage	5 ~ 48 V
Max load current	100 mA
LED Indicators	
Diagnostic LED	Power, EtherCAT status
EtherCAT	
Cycle time	200 µs
Distributed clocks	Yes
Power	
Input voltage range	+24 V_{DC}
Power consumption	Maximum 4.5W
EMS Protection	
ESD (IEC 61000-4-2)	±4 KV Contact for each channel
EFT (IEC 61000-4-4)	Signal: 1 KV Class B; Power: 1 KV Class B
Mechanism	
Casing	Plastic
Dimensions (mm)	25 × 108 × 90 (W × L × D)
Installation	DIN-Rail or Wall Mounting
Environment	
Operating temperature	-25℃ ~ 70℃
Storage temperature	-30℃ ~ 80℃
Relative humidity	10 ~ 90%, No condensation

Table 1: Technical data

1.4 Dimensions

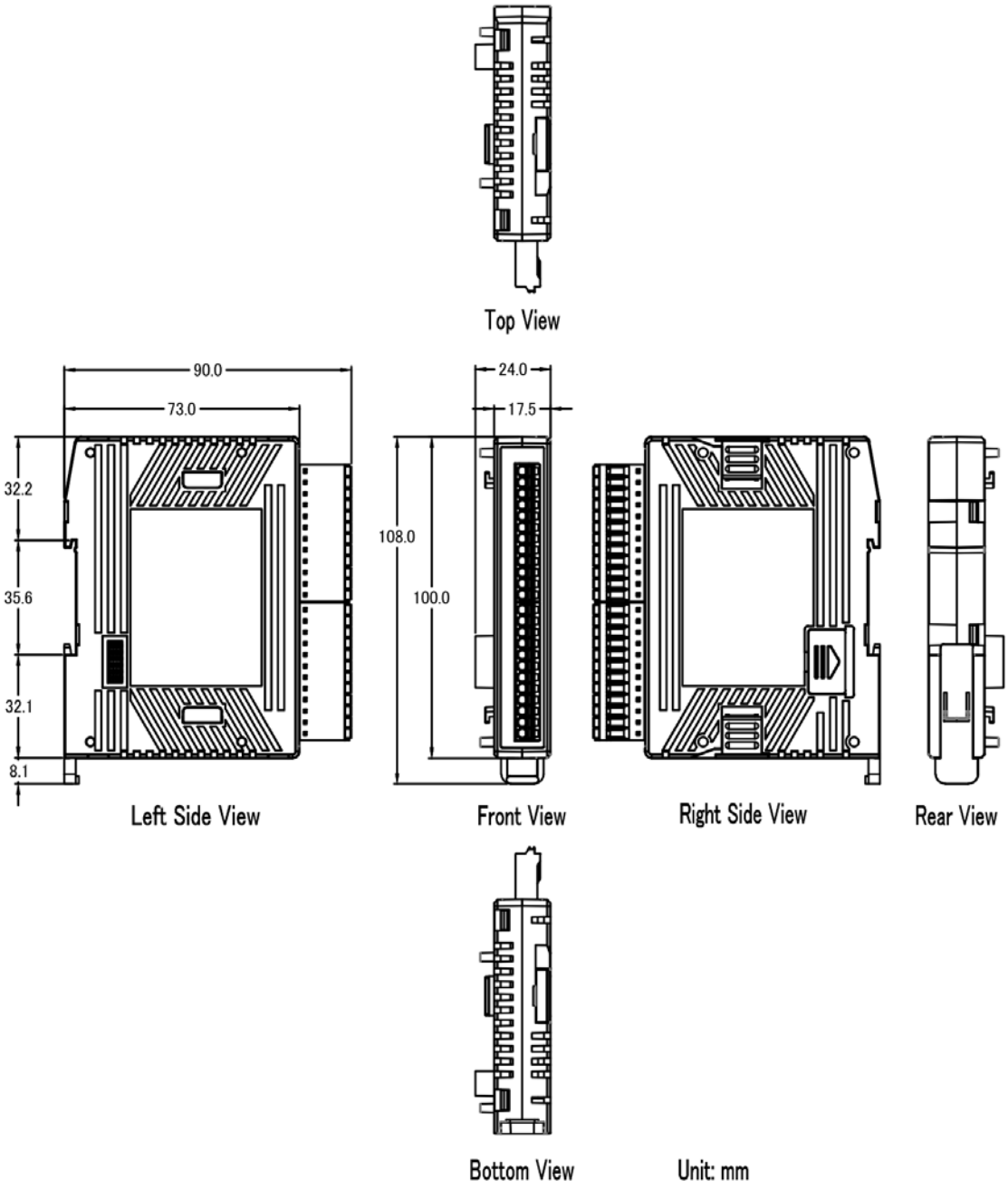


Figure 1: Dimensions of the EC4-ENC2IT

2 Scope of Delivery

The shipping package includes the following items:

- 1 x EC4-ENC2IT
- 2 x 12-pin plug-in connector
- 1 x Quick Start manual

Figure 2: EC4-ENC2IT module and Quick Start manual

Note:

If any of these items are missing or damaged, please contact your local distributor. Please keep the original retail box with all retail packaging (Styrofoam, inner boxes, fasteners, etc.) in case you need to return the product.

More Information:

- Product website:
  http://www.icpdas.com/root/product/solutions/industrial_communication/fieldbus/ethercat/motion/EC4-ENC2IT.html

- Manual:
  ftp://ftp.icpdas.com/pub/cd/fieldbus_cd/ethercat/slave/motion/EC4-ENC2IT/manual/

- XML EtherCAT Slave Information (ESI) file:
  ftp://ftp.icpdas.com/pub/cd/fieldbus_cd/ethercat/slave/motion/EC4-ENC2IT/esi/

- FAQ:
  http://www.icpdas.com/root/product/solutions/industrial_communication/fieldbus/ethercat/ethercat_faqs.html

- Technical support:
  service@icpdas.com

3 LED Definition

The EC4-ENC2A provides on the front side two diagnostic LEDs which indicates the power and EtherCAT network status. The exact meaning of the EtherCAT LED is described in the following tables:

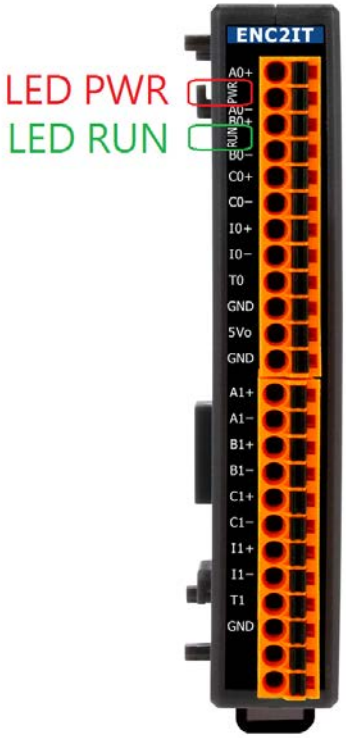


Figure 3: EC4-ENC2IT LEDs

EtherCAT LED	Color	State	Description
RUN	green		This LED indicates the operation state of the EtherCAT slave:
		Off	Device is in INIT state
		Flashing	Device is in PREOP state
		Single flash	Device is in SAFEOP state Outputs remain in safe state
		On	Device is in OP state

Table 2: EtherCAT status indicator

4 Wiring

4.1 Connection Interfaces

Figure 4: EC4-ENC2IT front view with encoder inputs

Name	Signal	Signal Description	
A0+	Input	Encoder input A0+	Encoder Channel 0
A0-	Input	Encoder input A0-	
B0+	Input	Encoder input B0+	
B0-	Input	Encoder input B0-	
C0+	Input	Encoder input C0+	
C0-	Input	Encoder input C0-	
I0+	Input	Latch input I0+	
I0-	Input	Latch input I0-	
T0	Output	Compare trigger output (DO0)	
GND		External ground for DO0	
5Vo	Output	Power supply to encoder	
A1+	Input	Encoder input A1+	Encoder Channel 1
A1-	Input	Encoder input A1-	
B1+	Input	Encoder input B1+	
B1-	Input	Encoder input B1-	
C1+	Input	Encoder input C1+	
C1-	Input	Encoder input C1-	
I1+	Input	Latch input I1+	
I1-	Input	Latch input I0-	
T1	Output	Compare trigger output DO1	
GND		External ground for DO1	

Table 3: Connection interfaces of the encoder

4.2 Internal I/O Structure

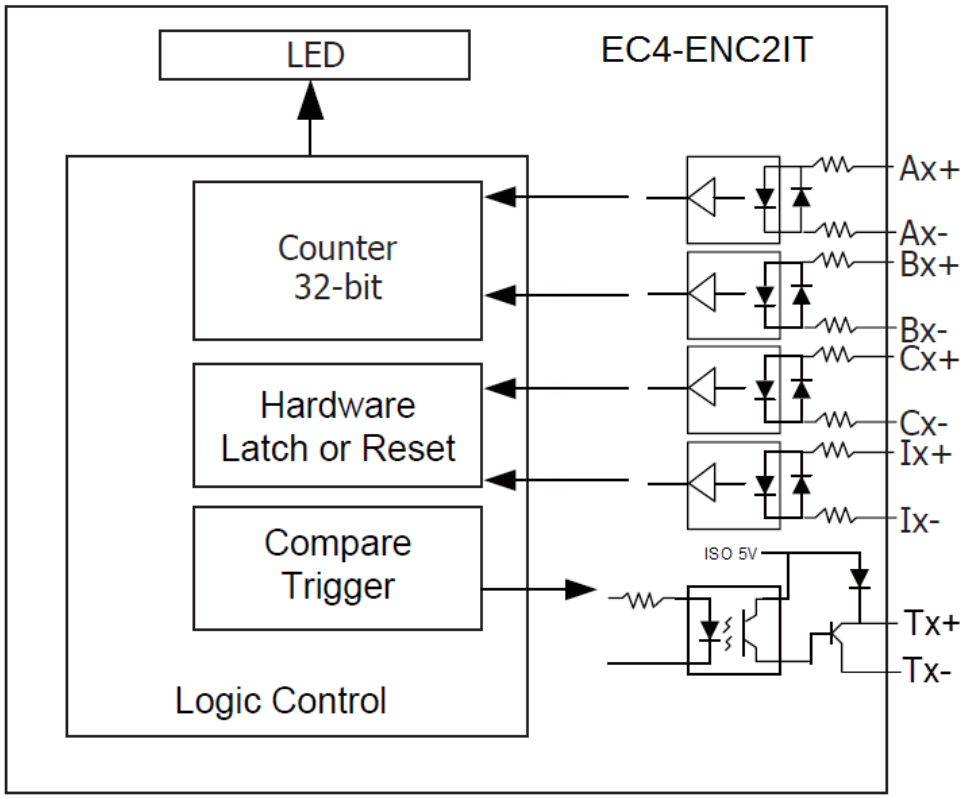


Figure 5: DIO circuit

4.3 Jumper Settings

The EC4-ENC2IT can accept encoder inputs from either differential or single-ended signals. By default it is set to support differential encoder signals as they are preferred due to their excellent noise immunity. For open collector type encoder the internal resistor needs to be enabled. The EC4-ENC2IT does not provide an internal power supply for the encoder therefore the encoder has to be connected to an external power supply.

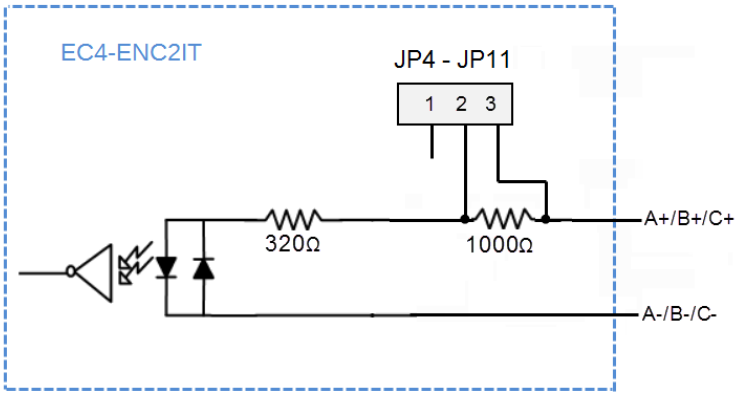


Figure 6: Encoder channel circuit

For single-ended encoder connection the EC4-ENC2IT provides an internal 1k Ohm resistor for each signal input. The internal resistor can be selected by setting the jumper of the corresponding encoder channel to the position 1-2. The housing needs to be opened in order to set the jumper. For enabling the internal resistor Table 4 lists for each encoder signal input the corresponding jumper position. Figure 7 and Figure 8 shows the basic wiring diagram for open collector connection.

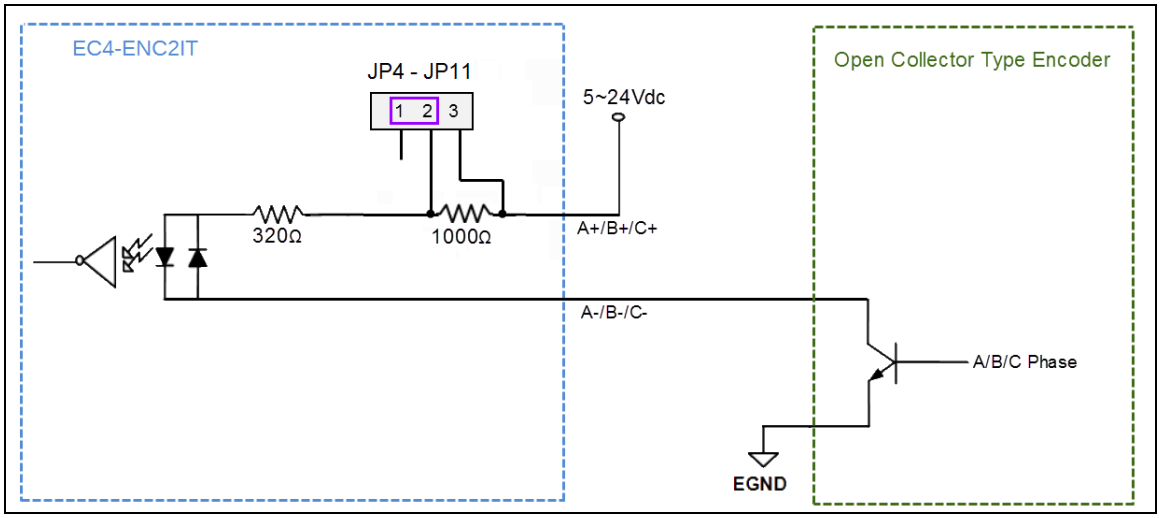


Figure 7: Open collector wiring diagram (Source Digital Input)

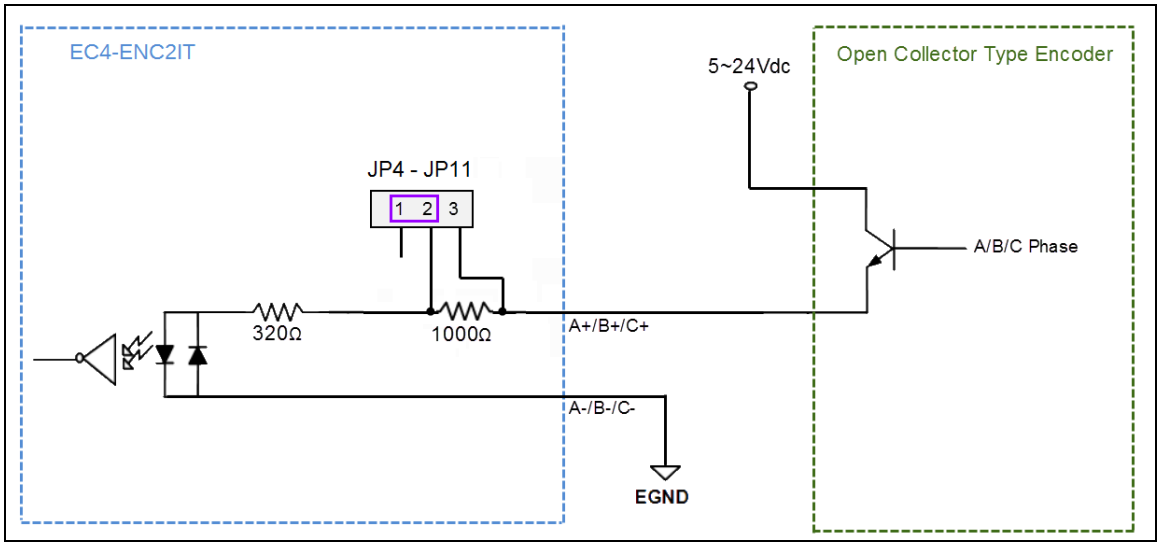


Figure 8: Open collector wiring diagram (Sink Digital Input)

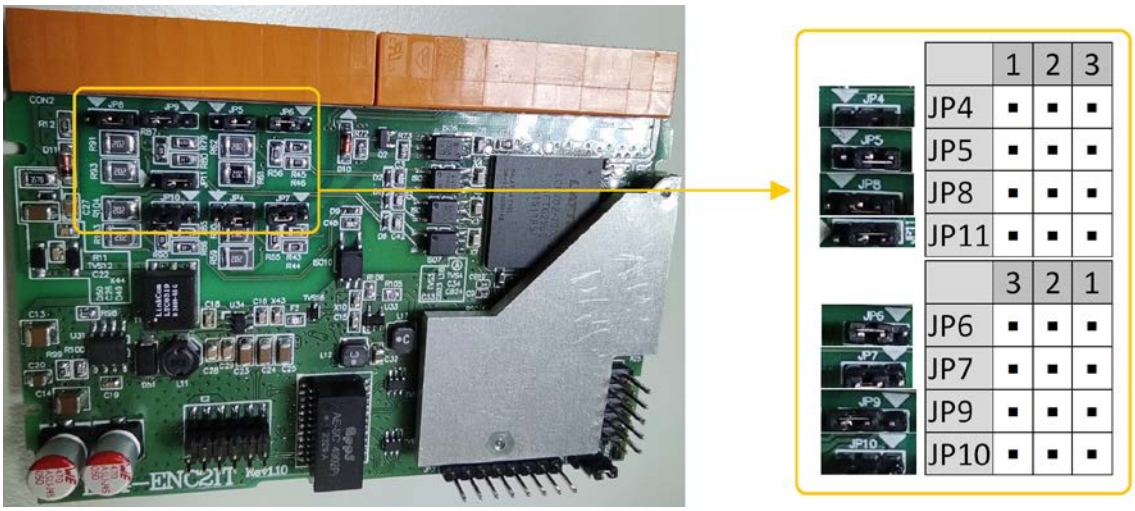


Figure 9: Jumper location

Jumper No	Channel	Jumper position 2-3	Jumper position 1-2
JP4	Encoder input A0	Differential channel	Open collector channel
JP5	Encoder input B0	Differential channel	Open collector channel
JP6	Encoder input Z0 (C0)	Differential channel	Open collector channel
JP7	Extern latch input I0 (HR0)	Differential channel	Open collector channel
JP8	Encoder input A1	Differential channel	Open collector channel
JP9	Encoder input B1	Differential channel	Open collector channel
JP10	Encoder input Z1 (C1)	Differential channel	Open collector channel
JP11	Extern latch input I1 (HR1)	Differential channel	Open collector channel

Table 4: Jumper definitions for the encoder channels

The input levels for the open collector with the internal resistor of 1 K ohm is as follows

- Input 12 V:
  - Logic High: 5 V ~ 12 V
  - Logic Low: 0 V ~ 2 V
- Input 24V:
  - Logic High: 5 V ~ 24 V
  - Logic Low: 0 V ~ 2 V

4.4 Digital Input Wiring

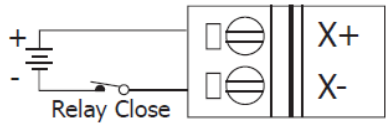
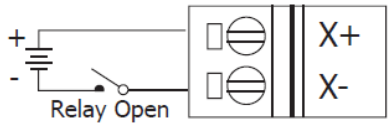
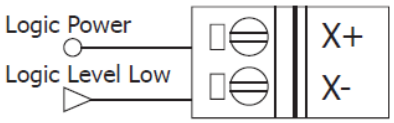
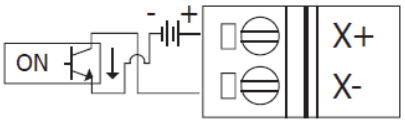
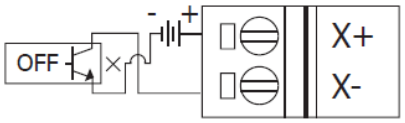
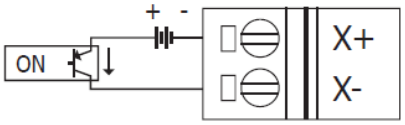
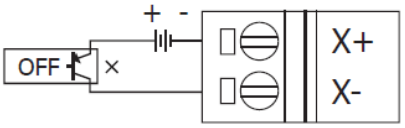
Input Type	ON State LED ON Readback as 1	OFF State LED OFF Readback as 0
Relay Contact	Relay ON	Relay OFF
		
TTL/CMOS Logic	Voltage > 4 V	Voltage < 0.8 V
		
NPN Output	Open Collector ON	Open Collector OFF
		
PNP Output	Open Collector ON	Open Collector OFF
		

Figure 10: Encoder counter (A/B), index (C) and external latch (I) input wiring

4.5 Compare Trigger Output Wiring

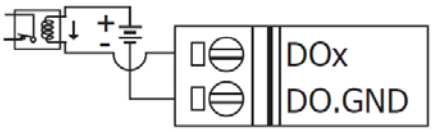
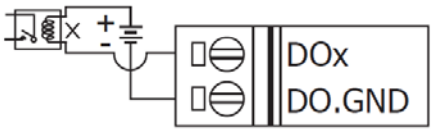
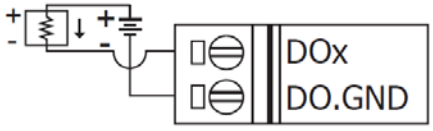
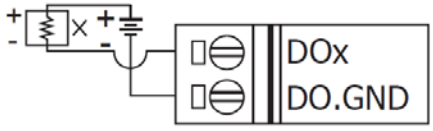
Output Type	ON State Readback as 1	OFF State Readback as 0
Drive Relay	Relay ON	Relay OFF
		
Resistance Load		
		

Figure 11: Compare trigger output wiring

5 Basics Communication

5.1 EtherCAT Cabling

The cable length between two EtherCAT devices must not exceed 100 m.

Cables and connectors
For connecting EtherCAT devices only Ethernet connections (cables + plugs) that meet the requirements of at least category 5 (CAT5) according to EN 50173 or ISO/IEC 11801 should be used. EtherCAT uses 4 wires for signal transfer.
The pin assignment is compatible with the Ethernet standard (ISO/IEC 8802-3).

5.2 EtherCAT State Machine

The state of the EtherCAT master and slave is controlled via the EtherCAT State Machine (ESM) . The state determines which functions are accessible or executable in the EtherCAT slave. State changes are typically initiated by requests of the master and acknowledged by the slave after the successful initialization. In case of an internal error, the slave automatically changes to a lower state.

The EC4-ENC2IT supports four states:
- Init (state after Reset)
- Pre-Operational
- Safe-Operational
- Operational

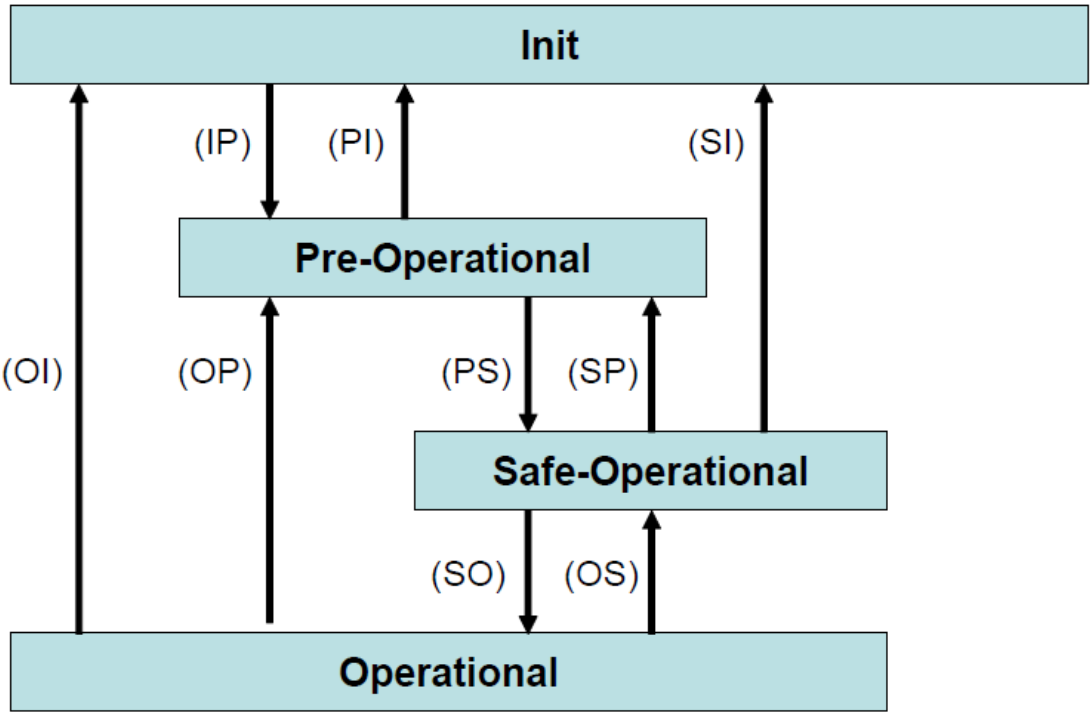


Figure 12: EtherCAT state machine

Init

After switch-on the EtherCAT slave is in the initial state. Only ESC register communication is possible, but no mailbox or process data communication. The slave initializes the service object data with default value or with values previously stored to the local memory. The EtherCAT master assigns the station address and configures the sync manager channels 0 and 1 for acyclic mailbox communication.

Pre-Operational (Pre-Op)

In Pre-Op state acyclic mailbox communication is possible, but not process data communication. In this state the EtherCAT master does the following configurations:

- Sets the sync manager 2 and 3 of the EC4-ENC2IT for process data communication (from sync manager channel 2)
- Configurates the Fieldbus Memory Management Unit
- PDO mapping or the sync manager PDO assignment
- The user has the option to save motion control related configuration data (0x8000 - 0x8020) to a non-volatile memory.

Safe-Operational (Safe-Op)

In Safe-Op state both mailbox and process data communication are enabled, but the slave keeps its outputs in a safe state, while the input data are updated cyclically. The slave will ignore the output data sent by the master and just return the current input

data (e.g. digital input, encoder value, etc.)

The sync manager watchdog expires when the master application does not provide new output process data within the configured watchdog time. In this case the slave will automatically go from operational state to ERROR-SAFEOP state.

Operational (Op)
Here both the process data object (PDO) and service data object (SDO) are fully enabled. Master sends cyclic output data and read input data. The EC4-ENC2IT supports three type of Op modes: Free Run mode, SM-Synchron and Distributed Clock (DC) mode.

5.3 Synchronization Modes

EC4-ENC2IT devices support three different modes:

- Free Run: The master cycle time and slave cycle time are independent and not synchronized.
- SM-Synchron: The master cycle time interval is not deterministic and can vary. Master and slave process data handling are synchronized. The slave only starts processing data once it received a new datagram from the master.
- Distributed Clock (DC): The cycle time and interval is fixed and deterministic. Both the master and slave cycle time are synchronized. The slave processes data at a fixed and deterministic time interval (DC cycle time). The slave expect the master to exchange process data at a fixed time interval. If the master does not send/read data within the set time interval then an synchronization error will be generated by the slave.

5.3.1 Free Run Mode

The slave operates autonomously based on its own cycle and is not synchronized with the EtherCAT cycle. The master cycle time and the slave cycle time are fully independent which means each slave device reads/writes its own process data according to its local time, independent of the master's cycle time.

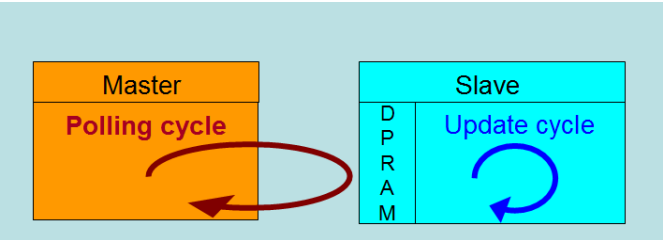


Figure 13: Master-slave cycle in Free Run mode

The following diagram shows the process timing of the slave in Free Run mode in detail:

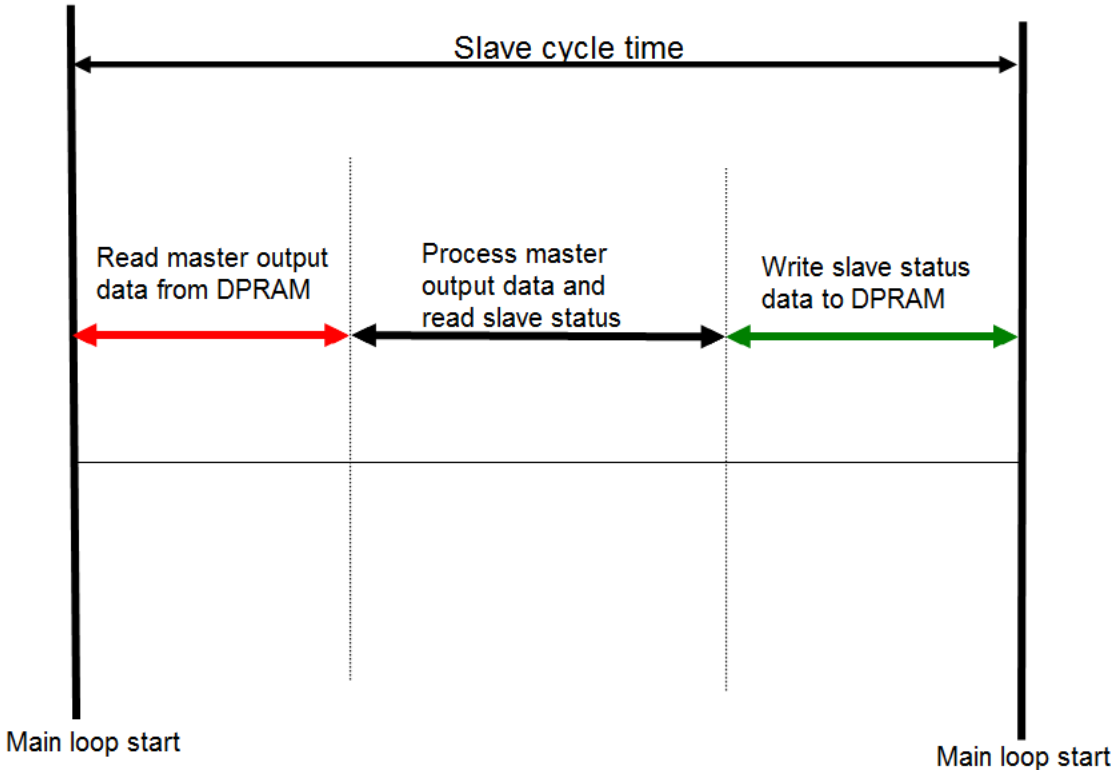
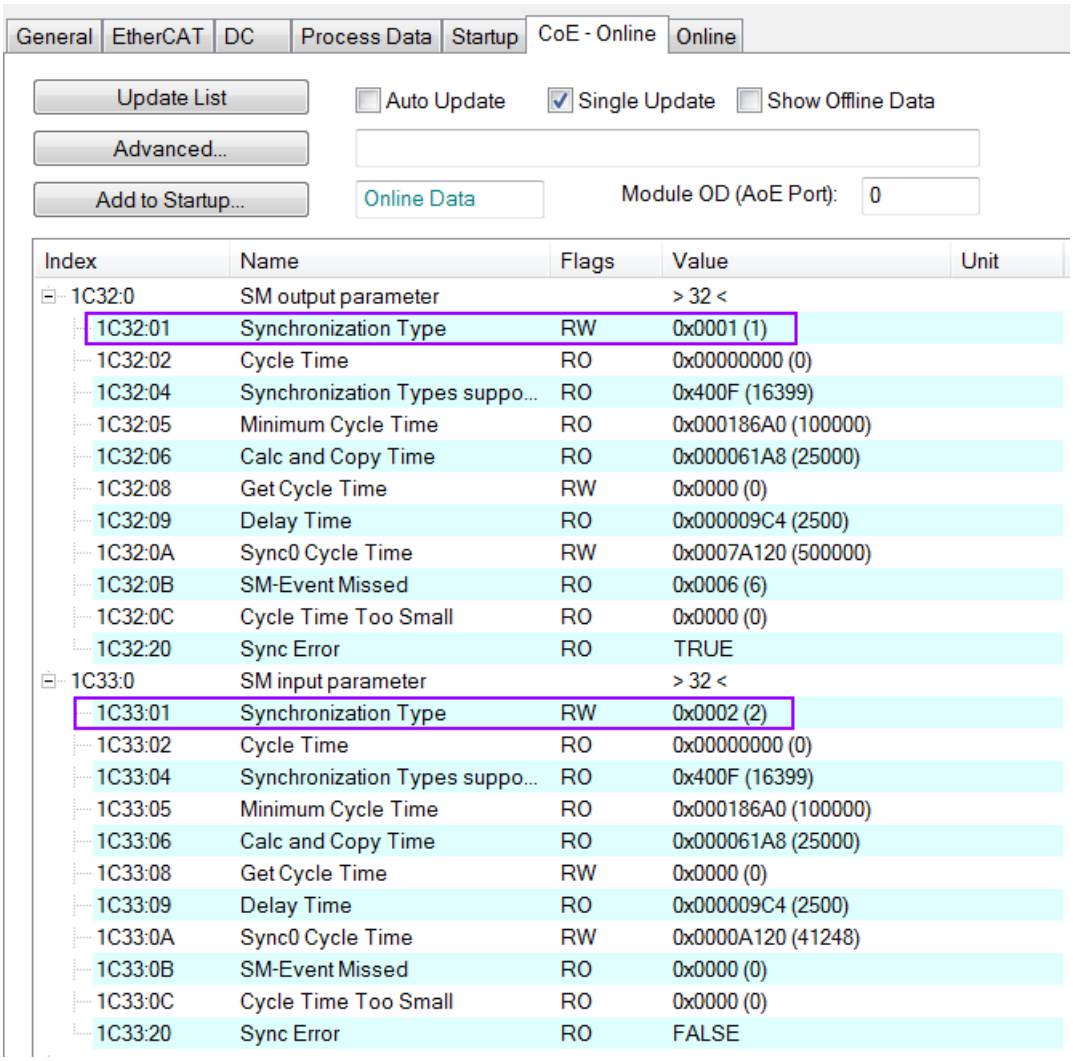


Figure 14: Slave processing sequence in Free-run mode

The slave firmware checks in each cycle time the memory of the EtherCAT slave chip (ESC) whether new output data has been received from the master. Newly received data will be processed. In the next step the encoder input status are being read from the FPGA chip. In the final step the read status are being written to the DPRAM, so that the master can retrieve the data ESC DPRAM in the next cycle time.
Free Run synchronization parameter has to be set in PREOP mode:
0x1C32.1 = 0
0x1C33.1 = 0

The setting of the Free Run synchronization parameter can be done in TwinCAT by clicking on the "CoE online" tab of the EC4-ENC2IT slave. Make sure the slave is set into PreOP mode before modifying the synchronization parameters



Index	Name	Flags	Value	Unit
1C32:0	SM output parameter		> 32 <	
1C32:01	Synchronization Type	RW	0x0001 (1)	
1C32:02	Cycle Time	RO	0x00000000 (0)	
1C32:04	Synchronization Types suppo...	RO	0x400F (16399)	
1C32:05	Minimum Cycle Time	RO	0x000186A0 (100000)	
1C32:06	Calc and Copy Time	RO	0x000061A8 (25000)	
1C32:08	Get Cycle Time	RW	0x0000 (0)	
1C32:09	Delay Time	RO	0x000009C4 (2500)	
1C32:0A	Sync0 Cycle Time	RW	0x0007A120 (500000)	
1C32:0B	SM-Event Missed	RO	0x0006 (6)	
1C32:0C	Cycle Time Too Small	RO	0x0000 (0)	
1C32:20	Sync Error	RO	TRUE	
1C33:0	SM input parameter		> 32 <	
1C33:01	Synchronization Type	RW	0x0002 (2)	
1C33:02	Cycle Time	RO	0x00000000 (0)	
1C33:04	Synchronization Types suppo...	RO	0x400F (16399)	
1C33:05	Minimum Cycle Time	RO	0x000186A0 (100000)	
1C33:06	Calc and Copy Time	RO	0x000061A8 (25000)	
1C33:08	Get Cycle Time	RW	0x0000 (0)	
1C33:09	Delay Time	RO	0x000009C4 (2500)	
1C33:0A	Sync0 Cycle Time	RW	0x0000A120 (41248)	
1C33:0B	SM-Event Missed	RO	0x0000 (0)	
1C33:0C	Cycle Time Too Small	RO	0x0000 (0)	
1C33:20	Sync Error	RO	FALSE	

Figure 15: SyncManager setting for Free-Run mode

5.3.2 SM-Synchron

In this mode both the master and the slave are synchronized but the data exchange cycle interval is not deterministic. The slave waits for the master to send a data telegram before starting to process the input and output data. In this mode the process data handling is being initiated by the master which determines the cycle time.

Once the output data sent by the master arrives at the slave it immediately starts processing the output data. In the next step the encoder input data will be written to the internal process data image of the slave. The input process data image will be read by the master in the next cycle.
SyncManager synchronization parameter:
0x1C32.1 = 0x1
0x1C33.1 = 0x22

By setting the operation mode of TwinCAT to "SM-Synchron" the SyncManager synchronization parameter are set by default to the above values.

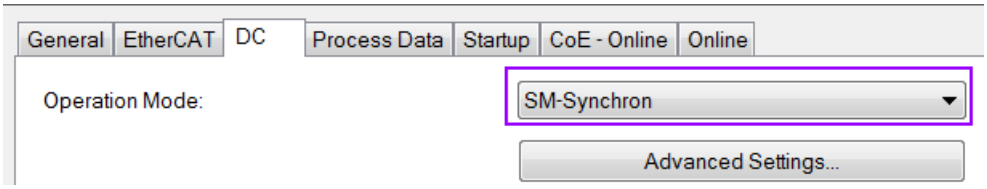


Figure 16: SM-Synchron mode selection

5.3.3 Distributed Clocks (DC Mode)

DC clock synchronization enables all EtherCAT devices (master and slaves) to share the same EtherCAT system time. The EtherCAT slaves in the network can be synchronized to each other. This enables the master to simultaneously set the output (e.g. digital output, pulse output) or to synchronously read inputs (e.g. digital input, encoder counter) of different slaves in the EtherCAT network.

For system synchronization all slaves are synchronized to one reference clock. Normally the first EtherCAT slave closest to the master with Distributed Clocks capability becomes the clock base for the master as well as for other DC slaves.

The EtherCAT slave is synchronized with the SYNC0 or SYNC1 event of the distributed clock system. After the EtherCAT network has been set into DC communication mode by the master, the ESC (EtherCAT slave chip) of each slave generates fixed time hardware interrupt which triggers the slave firmware to process the PDO data received from the master. The master cycle time and the ESC hardware interrupt time interval are fully synchronized to the first slave in the network that is used as a reference clock with the SYNC0 signal.

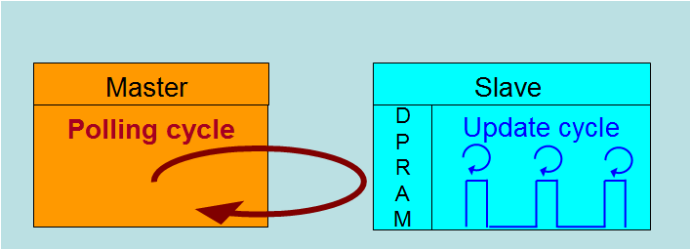


Figure 17: Master-slave cycle in DC mode

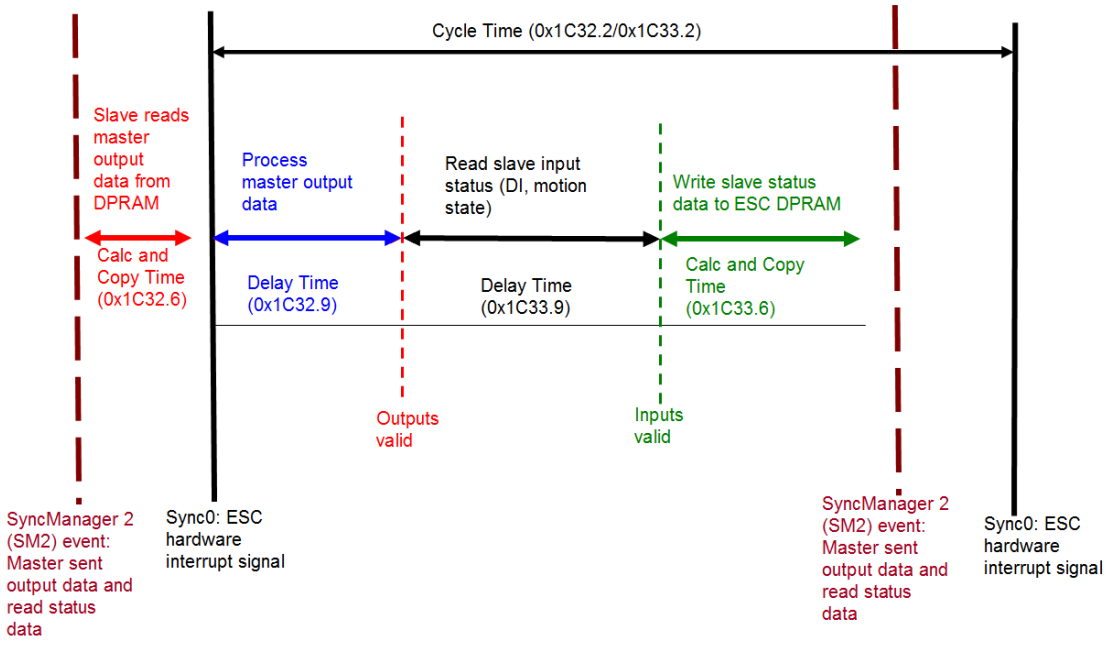


Figure 18: Internal slave processing sequence in DC mode

Once the slave receives process data (RxPDOs) from the master the SM2 event is triggered which causes the firmware to read the data from the ESC memory. The ESC interrupts the firmware at fixed time interval to process the data received from the master and write the status data to the ESC memory. Every time when the master fails to sent process data within the DC cycle time the internal sync error counter is being increase by three counts. This error counter is being decreased by one count for every successful DC cycle. Once the error counter reached the maximum count (default 4) a sync error will be generated and the slave goes into Safe OP mode (Sync Error 0x1C32:20 TRUE). The maximum count value can be set by changing the default value of the "Sync Error Counter Limit" (0x10F1:02).

Index	Name	Flags	Value
10F1:0	Error Settings		> 2 <
10F1:01	Local Error Reaction	RW	0x00000001 (1)
10F1:02	Sync Error Counter Limit	RW	0x0004 (4)

Figure 19: Sync error counter limit object

The setting of the sync manager for the output and input data is available at the TwinCAT "CoE online" tab.

Index	Name	Flags	Value
1C32:0	SM output parameter		> 32 <
1C32:01	Synchronization Type	RW	0x0002 (2)
1C32:02	Cycle Time	RO	0x00000000 (0)
1C32:04	Synchronization Types supported	RO	0x401F (16415)
1C32:05	Minimum Cycle Time	RO	0x001E8480 (2000000)
1C32:06	Calc and Copy Time	RO	0x0007A120 (500000)
1C32:08	Get Cycle Time	RW	0x0001 (1)
1C32:09	Delay Time	RO	0x000927C0 (600000)
1C32:0A	Sync0 Cycle Time	RW	0x005B8D80 (6000000)
1C32:0B	SM-Event Missed	RO	0x0000 (0)
1C32:0C	Cycle Time Too Small	RO	0x0000 (0)
1C32:20	Sync Error	RO	FALSE

Figure 20: SyncManager 2 parameters

SyncManager parameter description (time unit: nanosecond):

- Calc and Copy Time (0x1C32.6 / 0x1C33.6): Required time to copy the process data from the ESC to the local memory and calculate the output value.
- Delay Time (0x1C32.9 / 0x1C33.9): Delay from receiving the trigger to set the output or latch the input.
- Cycle Time (0x1C32.2 / 0x1C33.2): The current cycle time for the application. When using DC synchronization the value is read from register 0x9A0:0x9A3.
- 0x1C32.5 / 0x1C33.5 (Min Cycle Time): Minimum cycle time for the application. It is the total execution time of all slave application related operations.

6 Project Integration

In this chapter the integration of the EC4-ENC2IT device into a TwinCAT controlled EtherCAT network is being described. In general the EC4-ENC2IT is a standard EtherCAT slave which can be controlled by any standard EtherCAT master (e.g. Acontis, CODESYS, etc.).

6.1 ESI File

A ESI file describes the properties and functions supported by the EC4-ENC2IT. By using the ESI file an easy and abstract integration of an EtherCAT device in a project tool is realized. With the help of the ESI file a detailed knowledge of EtherCAT is not required to configure the device. The TwinCAT EtherCAT master/System Manager needs the device description files in order to generate device configuration in online or offline mode.

6.1.1 Import of ESI File

Copy the XML description file "EC4-ENC2IT.xml" of the EC4-ENC2IT device into the TwinCAT system directory and restart the TwinCAT system.
For TwinCat 3.1 copy the ESI file "EC4-ENC2IT.xml" in the following directory:
C:\TwinCAT\3.1\Config\Io\EtherCAT

Software	Default directory path
Beckhoff EtherCAT Configuration	C:\EtherCAT Configurator\EtherCAT
Beckhoff TwinCAT 3.x	C:\TwinCAT\3.x\Config\Io\EtherCAT
Beckhof TwinCAT 2.x	C:\TwinCAT\Io\EtherCAT

Table 5: ESI file target directory

6.2 Device Setup and Configuration

In this manual only the online configuration of the slave module will be discussed. For offline configuration procedure please consult the TwinCAT user manual.

The following conditions must be met before a configuration can be set up:

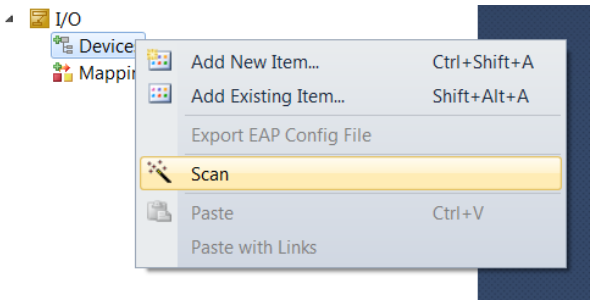
- The EC4-ENC2IT slave devices must be connected via EtherCAT cables to the EtherCAT master. In this manual TwinCAT 3.1 version is being used as the EtherCAT master and configuration tool

- The EC4-ENC2IT devices has to be connected to a power supply and ready for communication
- Set the TwinCAT in CONFIG mode.

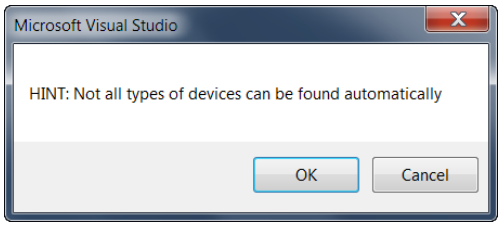
6.2.1 Scanning of the EtherCAT Device

After the TwinCAT has been set into CONFIG mode the online device search can be started.

Step 1: Right-click the “Devices” in the configuration tree to open the scan dialog. Click "Scan" to search the EC4-ENC2IT device.



Step 2: Select "OK"



Step 3: Select the Ethernet device (Ethernet chip) to which the EC4-ENC2IT is connected to. Confirm the selection with "OK".

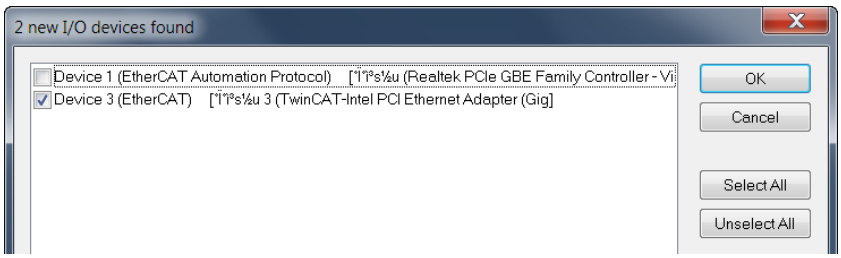
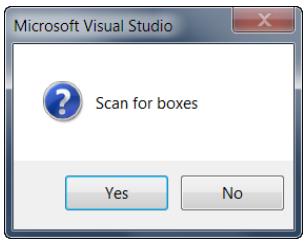
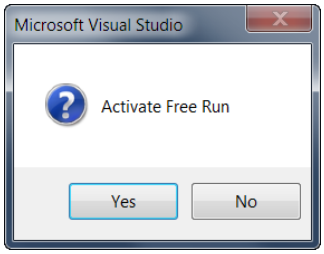


Figure 21:List of Ethernet chips detected on the EtherCAT master PC

Step 4: Start the scan process by clicking "Yes"



Step 5: Set the EC4-ENC2IT into Free-Run mode by clicking "Yes"



By default the counter and compare trigger process data for both encoder channels are displayed in the tree view:

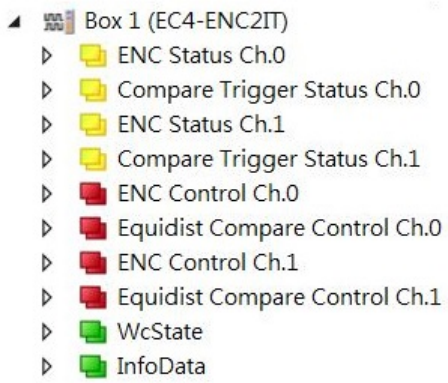


Figure 22: Default parameter selection for the EC4-ENC2IT

6.2.2 Encoder Counter Configuration

The configuration of the EC4-ENC2IT device such as the encoder mode, filter setting etc. only needs to be done once before the actual encoder counting starts. These parameters have to be accessed via the CANopen over EtherCAT (CoE) protocol and are listed in the "CoE online" tab. The CoE protocol has a lower priority than the cyclic process data object (PDO) communication. Therefore the CoE parameters will not be updated in every cycle but only when the master has spare time.

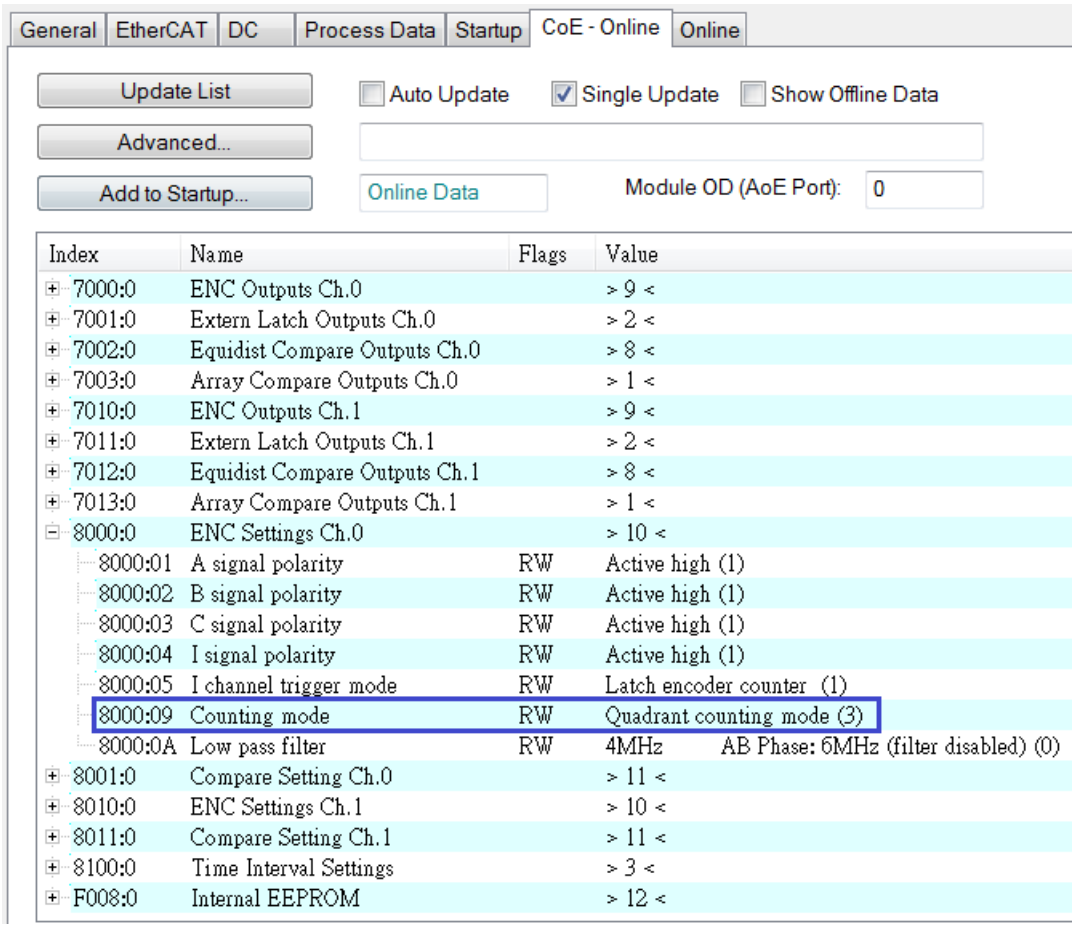
Encoder relevant CoE parameter are listed in the "Encoder setting" objects (Index 0x8000, 0x8010)

For each channel the following configuration procedure has to be done:

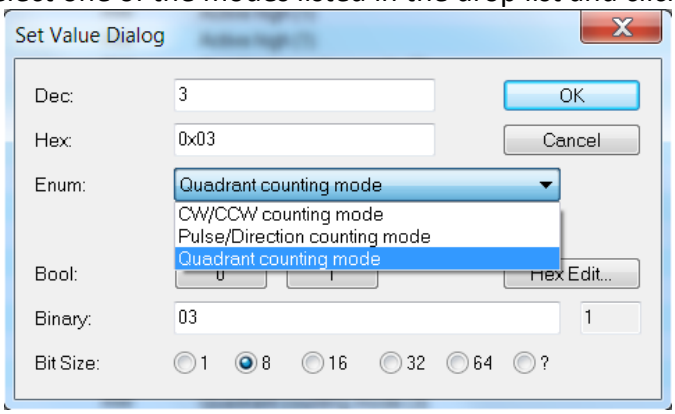
- Counting mode setting
- A/B/C signal polarity setting. The input signal may be active low or active high.
- Low pass filter clock cycle setting
- For external latch (if selected):
  - External latch "I" signal polarity setting: The input signal may be active low (falling edge trigger) or active high (rising edge trigger).
    NOTE: The "I" signal polarity can not be set for each channel individually. Both channel need to be set to the same polarity.
  - Extern latch mode setting: An latch signal can either latch the counter value or set the counter value to zero
- For compare trigger (if selected):
  - The pulse width setting of the triggered DO signal.
  - Compare DO trigger signal
  - The compare mode: equidistance incremental compare or non-equidistance compare (array of compare value) type.
  - For non-equidistance compare type:
    - List of compare position values
    - Number of compare position
    - Activate/Deactivate "I" digital input channel for enabling/disabling the position compare function

Example of setting the encoder counting mode for each channel:

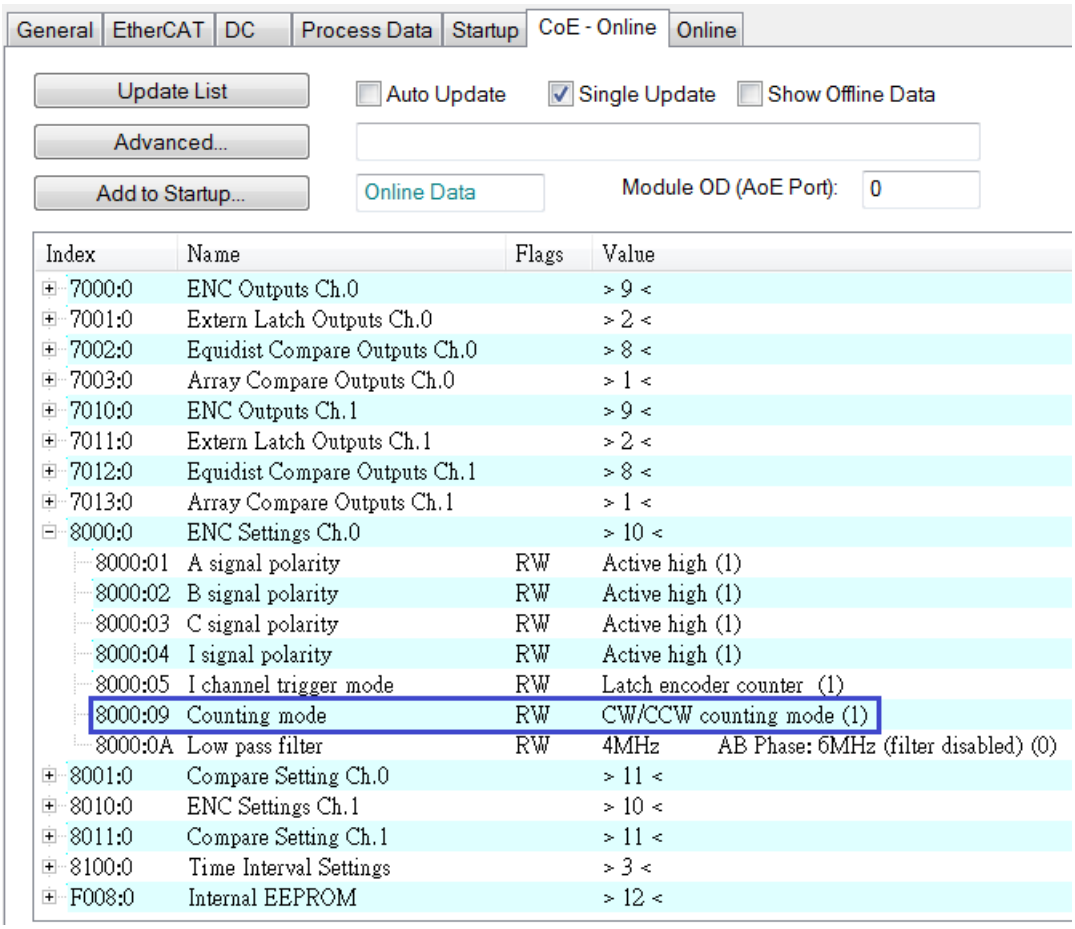
Step 1: Go to "ENC Setting Ch.0" of a channel. Extend the index tree and double click "Counting mode" with the index 8000:09 for channel 0.



Step 2: Select one of the modes listed in the drop list and click "OK"



Step 3: Once the setting has been successfully sent to the slave it will be displayed in the CoE online parameter list. In the figure below "CW/CCW counting mode" has been selected for channel 0. This value needs only to be set once and therefore does not have to be sent in every cycle time.



All the relevant encoder configurations have to be set first before the process data is being used by the application program. Once the parameters are set, the encoder counter is basically ready for operation.

If required, the configuration can be permanently save to an internal non-volatile memory of the EC4-ENC2IT. After powering on the device it will immediately be initialized according configuration setting. The procedure for saving the configuration data is being described in chapter 8.2.

6.2.3 EtherCAT Slave Process Data Assignment

The user has to select the process data which has to be transferred between the EtherCAT master and slave during each cycle (Process Data Objects, PDOs). The process data exist of two parts:

- TxPDO: Data which is being read by the master (e.g. encoder status) .
- RxPDO: Data or parameters which is being sent to the slave (e.g. reset encoder position).

Once the parameters of the process data image has been defined by the user the master will exchange the in- and output data in every cycle.

For TwinCAT the ESI file predefines PDO assignment which allows the user to quickly select the process data objects required for his application. The following list the available predefined PDO assignment categories:

- Counter + Equidist compare trigger (default selection)
- Counter + Array compare trigger
- Counter + Extern latch + Index latch
- Counter
- Counter + Extern latch + Equidist compare trigger
- Counter + Extern latch + Array compare trigger
- Counter + Index latch + Extern latch + Equidist compare trigger
- Counter + Index latch + Extern latch + Array compare trigger
- Counter + Index latch + Extern latch + Equidist compare trigger + Array compare trigger
- Counter + Index latch + Extern latch + Equidist compare trigger + Array compare trigger + Vel

By selecting one of the motion mode from the list box (Figure 23) all the relevant parameters are automatically assigned and mapped to the process data objects (TxPDO, RxPDO). If required, additional objects can be assigned to the process data by selecting the object listed under "PDO Assignment (0x1C12)" and "PDO Assignment (0x1C13)".

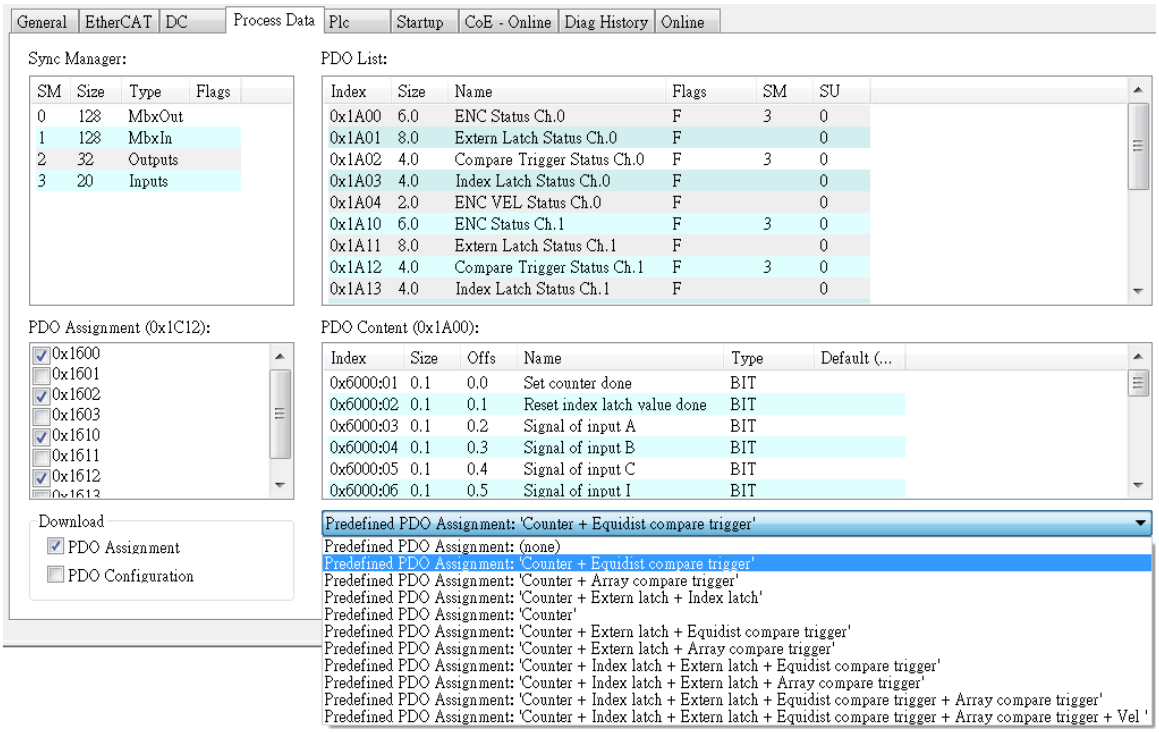


Figure 23: Predefined PDO assignment selection

The limitation of using the predefined PDO assignments is that for both encoder channel the same process data is being selected. Therefore if the projects requires that different process data objects have to be transmitted for each for each channel then the process data objects have to be selected manually. In TwinCAT the supported process data objects are listed in the "PDO Assignment (0x1C12)" and "PDO Assignment (0x1C13)" boxes. The variable of which a PDO is made up are described in Object Description and Parameterization in chapter 9.
The following section describes the procedure for selecting the PDO manually.

PDO selection procedure:

1. Click the "Process Data" tab of the EC4-ENC2IT slave
2. For RxPDO selection: click in the "Sync Manager" window the "Outputs" line and in the "PDO Assignment (0x1C12)" window select for each encoder channel the required RxPDO (see Figure 24). If the variables listed in the RxPDO are not required for the application then deselect the PDO in order to reduce the process data image size.
3. For TxPDO selection: click in the "Sync Manager" window the "Inputs" line and in the "PDO Assignment (0x1C13)" window select for each encoder channel the required TxPDO. The process data contains status variables for the encoder, latch and compare function, and signal status information.

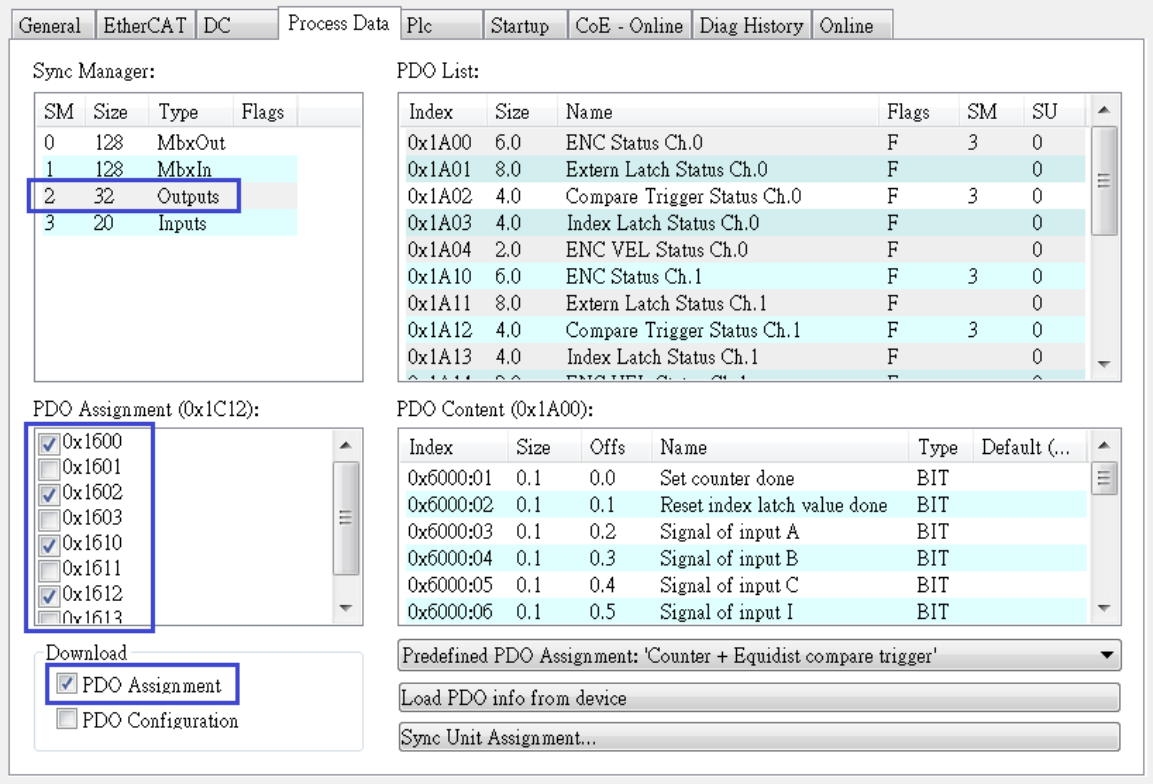


Figure 24: Predefined PDO assignment selection

Download the new PDO assignment to the Sync manager of the slave by clicking "Restart TwinCAT (Config Mode)" in the drop down menu. Make sure the check box next "PDO Assignment" is enabled.

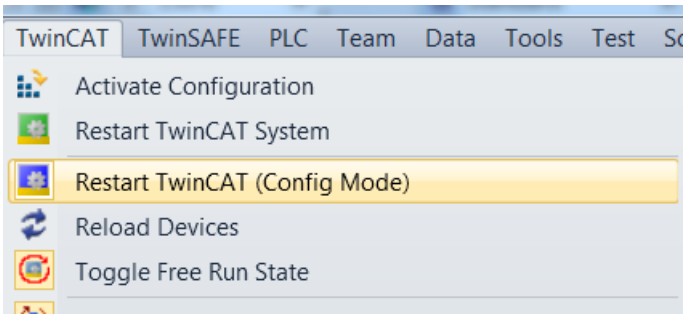


Figure 25: Download PDO assignment and restart TwinCAT

The device is now ready to be set into Free-Run or DC mode.

7 Parameter Description

7.1 Configuration Parameters

7.1.1 Counting Mode

The EC4-ENC2IT encoder counter supports three modes:

- Pulse/Direction counting mode
- Clockwise/Counterclockwise mode
- Quadrant counting mode

The encoder counter mode has to be set via CoE (0x80n0:09, n= 0;1), see Figure 26:

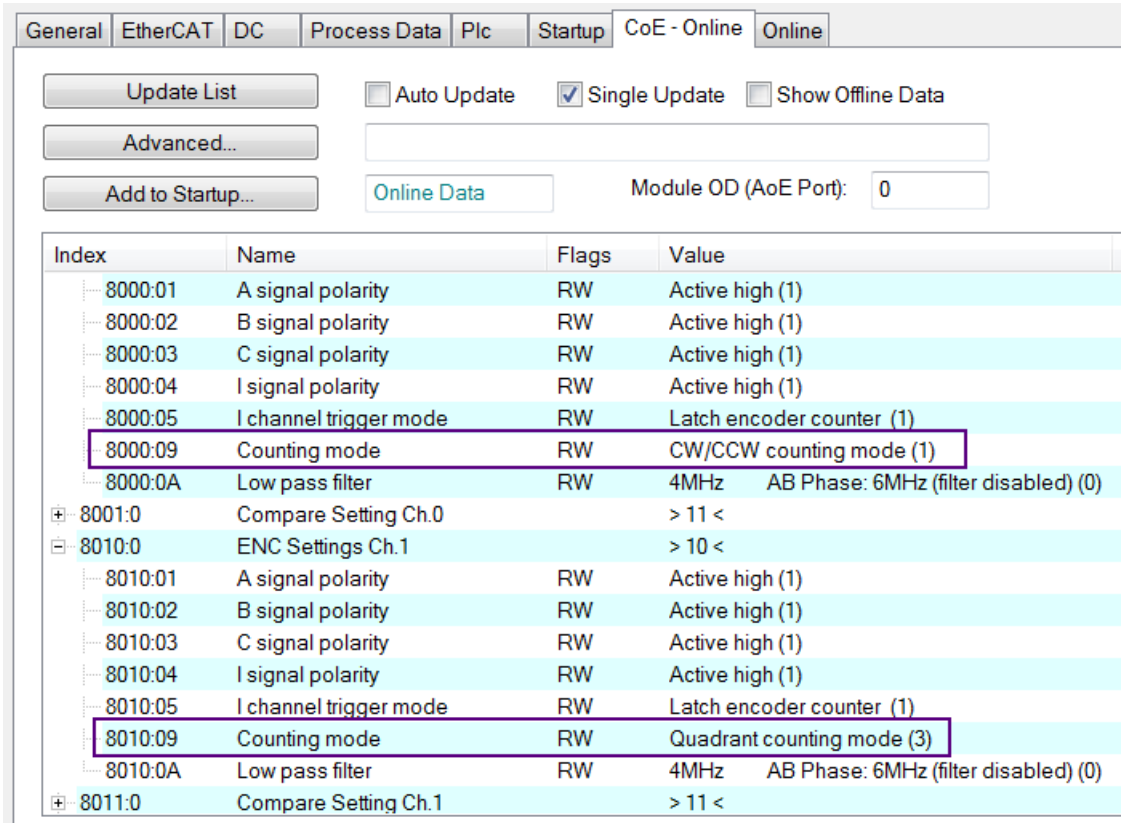


Figure 26:Configuration parameters set via CoE

In the **pulse/direction counting mode** (Figure 27) one input signal line is being used to indicate the position and a second one indicates the direction of motion, either forward or reverse. The "A" signal serves as the counter input and the "B" signal serves as the direction input (B = high: enables up count; B = low: enables down count). The EC4-ENC2IT counts the rising or falling edges of the "A" signal pulses and the "B" signal

determines the direction of the count and decides whether to increment or decrement the counter. On every active input signal "A" the position counter is incremented by one when the direction input "B" signal is high and decremented by one when the direction input "B" is low.

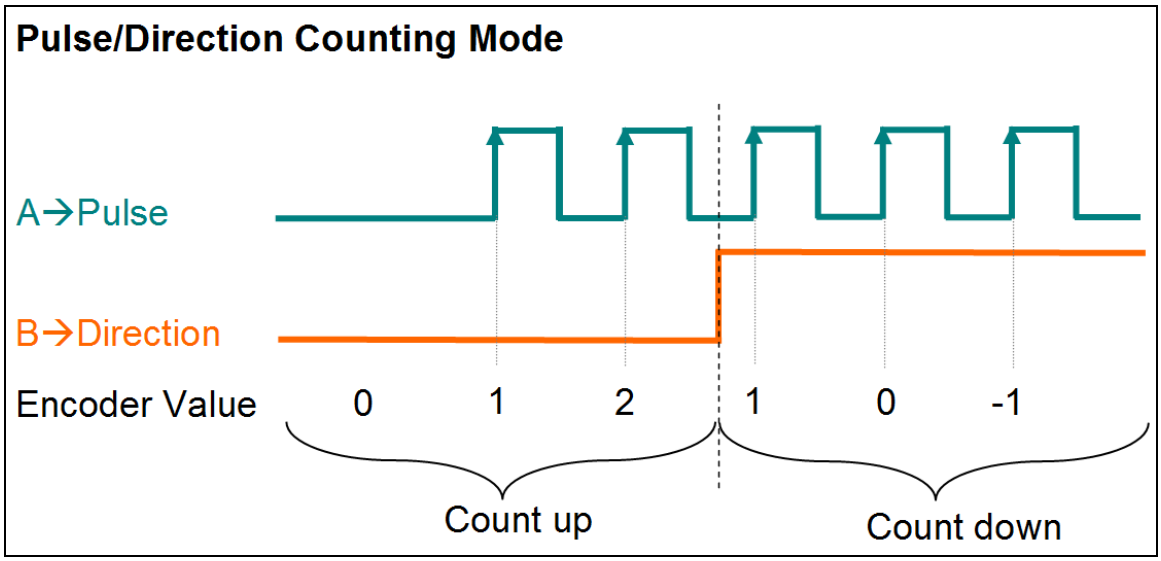


Figure 27: Pulse/Direction counting mode

In **clockwise/counterclockwise mode** (Figure 28) the "A" signal indicates a positive increments (clockwise signal) and the "B" signal a negative increments (counterclockwise signal). Therefore the encoder counter increases by one when the "A" signal is going high, while decreases by one when the "B" signal is going high.

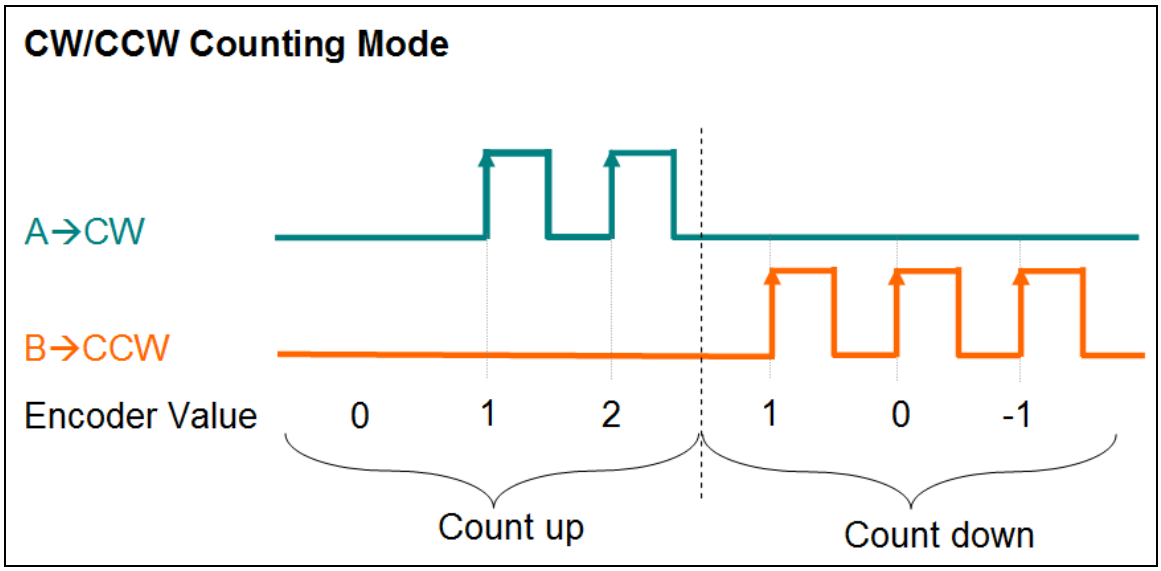


Figure 28: Clockwise/ Counterclockwise counting mode

In the **quadrant counting mode** (Figure 29) the encoder counter increments when signal "A" leads signal "B" and decrements when signal "B" leads signal "A". For example if the last input signal for both "A" and "B" was off and in the next cycle "A" is on and "B" is off then the direction is clockwise and the counter increments by one, but if "A" is off and "B" is on then the direction is counterclockwise and the counter decrements by one. Both the rising and falling edges of "A" signal and "B" signal are counted.

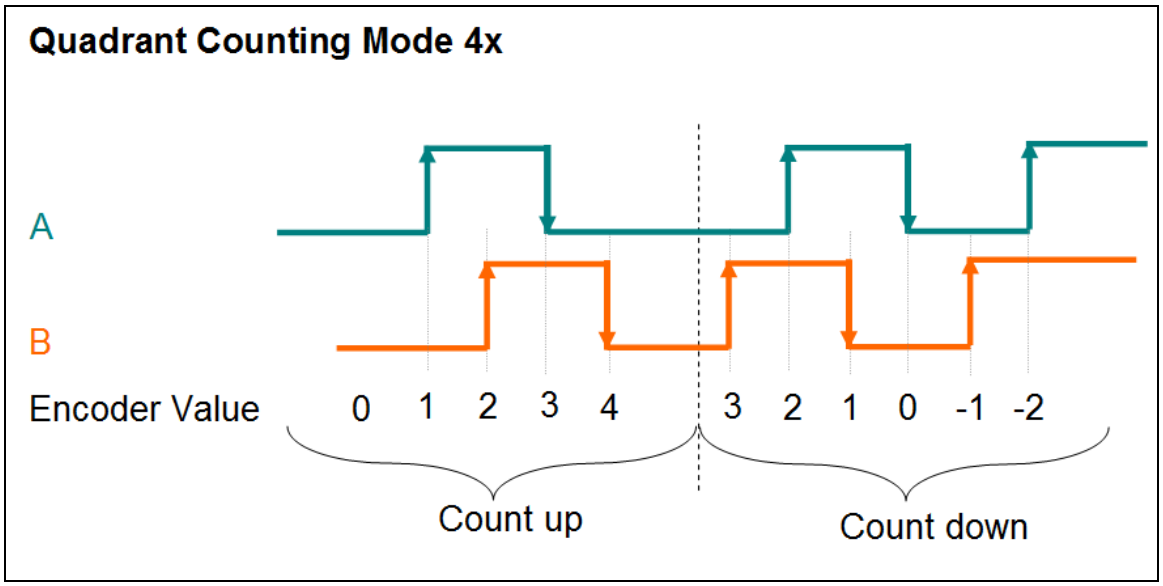


Figure 29: Quadrant counting mode

7.1.2 Signal Polarity Setting

7.1.2.1 Encoder Input Signal

The polarity of the encoder A,B,C signal indicates the active level of the signal. The active level of the encoder A, B and C signals has to be set via CoE:

- "A" signal 0x80n0:01
- "B" signal 0x80n0:02
- "C" signal 0x80n0:03

n - represents the channel number (n= 0;1)

By changing the signal polarity of "A" and/or "B" the direction of counting may change. For example:

- By changing the signal "B" polarity which indicates the direction for the pulse/direction counting mode (Figure 27) the counting direction will change.
- By changing the polarity of signal "A" for the quadrant counting mode (Figure 29) results in a change of counting direction.
- Changing the signal polarity for the clockwise/counterclockwise mode will not

change the counting direction

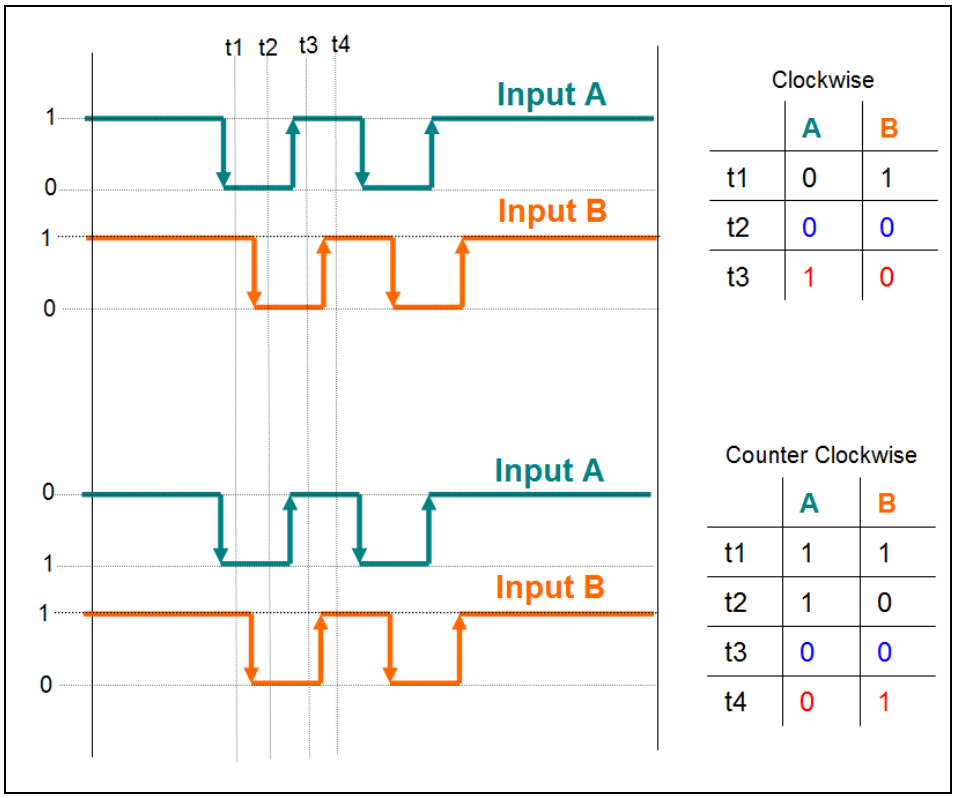


Figure 30: Polarity change of input signal "A" inverts the counting direction

7.1.2.2 Extern Latch Input Signal

The polarity of the extern latch signal (I) indicates whether a falling or rising edge will trigger a position latch or clear encoder counter action. The latch trigger edge has to be set as follows:

- Rising edge -->Active high
- Falling edge --> Active low

The trigger level of the extern latch signal has to be set via CoE (0x80n0:05, n= 0;1).
For position compare the input channel (I) can be used to directly enable/disable the compare output trigger.

NOTE: The trigger level for extern latch can not be set for each channel individually. Both channel need to be set to the same trigger level.

7.1.3 Extern Latch Mode

Two latch modes are being supported (Table 6):

- Latch current encoder position
- Reset encoder counter to zero

Latch Mode	Description
Latch encoder counter	The rising and falling edge signal at the I digital input channel triggers an encoder position latch. Both captured positions, latched at the positive and negative edge, can be accessed via process data (0x60n1:01 and 0x60n1:02, n= 0;1)
Reset encoder counter	A positive trigger signal will immediately reset the encoder counter (0x60n0:11, n= 0;1) to zero. Attention: If the compare trigger function with auto-increment has been enabled and the encoder counter has been reset to zero via the I digital input channel then it is important to reset the compare function in order to update the compare position register.

Table 6: Latch mode

The latch mode has to be set via CoE (0x80n0:05, n= 0;1).

Application for the latch function:

- Position capture
- Position measurement: the value difference between the rising and falling latched position indicates the distance the encoder counter moved between the rising and falling input signal (Figure 31).
- Homing

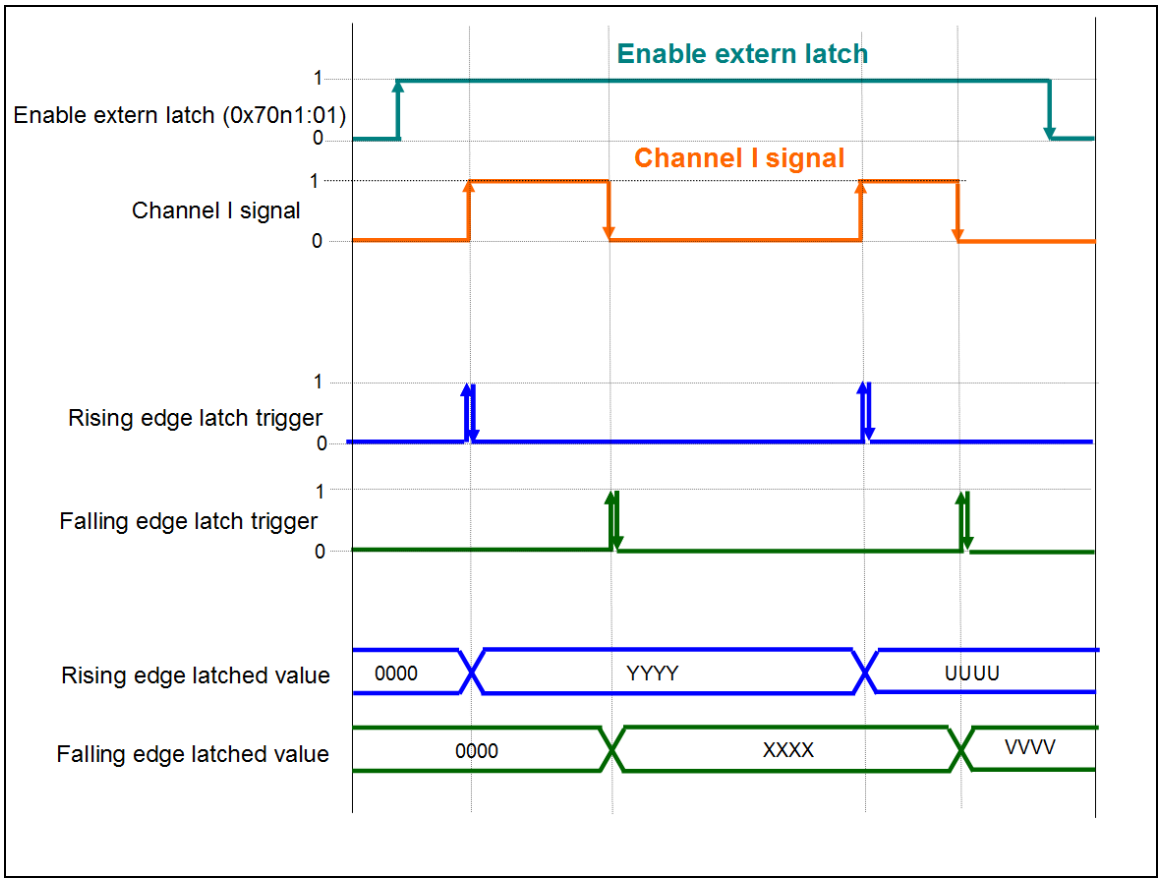


Figure 31: Rising and falling edge latch

7.1.4 Low Pass Filter Setting

Filters are for screening out noise from multiple inputs. The filter clock is used for sampling the input signal: if – and only if – two consecutive samples have the same value, the input is considered stable and the value is output from the filter. Table 7 list the filter clocks frequencies available for the EC4-ENC2IT.

Low pass filter number	Maximum Input Frequency	
	Pulse/Direction counting mode Clockwise/Counterclockwise mode	Quadrant counting mode
0	4MHz (filter disabled)	6MHz (filter disabled)
1	4MHz	1MHz
2	2MHz	500KHz
3	1MHz	250KHz
4	640KHz	160KHz
5	320KHz	80KHz
6	160KHz	40Hz
7	80KHz	20KHz
8	40KHz	10KHz

Table 7: Filter clock frequencies

The filter clock has to be set via CoE (0x80n0:0A, n= 0;1)

Make sure that the period of the filter clock is less than half of the pulse width of measured input signal (Table 8: H>2T) otherwise the encoder counter may not count all the pulses of the incoming pulse train.

Filter Setting	Filtering Status	
H > 2T	Correct	All input signals will pass the filter
T < H < 2T	Incorrect	Some valid input signals will be not pass the input filter and therefore are not being detected
H < T	Incorrect	The input signal will be filtered
H = the HIGH width of the input signal T = the period of the filtering clock		

Table 8: Low pass filter setting

7.1.5 Position Compare Configuration

The compare trigger function generates an digital output pulse when the encoder counter reaches the compare position. Position compare operations and its pulse output trigger is directly executed by hardware and therefore without any time delay. The EC4-ENC2IT supports three types of compare:

- Single position compare
- Fixed distance auto-increment compare: The next compare position will be automatically set by incrementing the current compare position with a fixed distance.
- Position compare array: Each compare position can be individually set. Up to 200 compare values are supported for each encoder channel.

The position compare setting and configuration has to be done via the SDO 0x80n1 (n= 0;1). Only one compare type can be selected for each axis. For all three position compare types the trigger pulse width and the signal type have to be set.

7.1.5.1 Compare Trigger Pulse Width

The pulse width of the output signal can be set via CoE (0x80n1:01, n= 0;1). The unit is microseconds and valid values are 1 to 32767 (Table 9).

Pulse Width Setting	Actual Pulse Width (µSec)
1	1
...	...
50 (default)	50
...	...
32766	32766
32767	32767

Table 9: Compare trigger pulse output width setting

7.1.5.2 Compare DO Trigger Signal Type

Set the active level of the signal output generated by the DO channel when a position compare event is being triggered via CoE (0x80n1:02, n= 0;1). The default value is "Normal" (0).

7.1.5.3 Compare Mode

Two types of position compare modes are supported: Equidistant compare and array compare. For enabling single position compare and fixed distance auto-increment compare select "Equidist Compare Control Ch.n" (0x16n2, n=0; 1). Select "Array Compare Control Ch.n" (0x16n3, n=0; 1) for activating position compare array mode which uses an array or list of position values which have to be entered by the user via the CoE (0x2nxx:01, n=0; 2). EC4-ENC2IT can only support one of the two modes at a time.

The compare mode can be enabled in two ways:

1. Via PDO by setting the "Enable compare" variable of the PDO 0x16n2 (n= 0;1) or the PDO 0x16n3 (n= 0;1) to TRUE and in addition
2. via digital input (I)

In order to use the digital input (I) for activating the compare output trigger the "Activate compare via DI" parameter has to be enabled via CoE (0x80n1:03, n= 0;1). It is always necessary to first switch the device into compare mode by setting the "Enable compare" variable to TRUE even if the digital input (I) is being used for activating the compare mode. Therefore the digital input can only be used for switching the compare mode on or off after the compare mode of the specified channel has been activated.

Number of Compare Position

For the "Array Compare Control" mode a maximum number of 200 position per axis is being supported. The "Max number of compare positions" variable (SDO 0x80n1:0A, n= 0;1) allows the user to set the number of compare positions to be used for the compare operation. The compare position has to be set before the compare operation starts via the service data object 0x2nxx (n=0; 2):

- Channel 0: 0x2000 to 0x20C7
- Channel 1: 0x2200 to 0x22C7

The EC4-ENC2IT will only trigger a compare output if the encoder value reaches the position value in the exact same order as they are listed in the 0x2nxx objects. The first trigger position is always determined by the "Position" variable set in object 0x2n00, the second by 0x2n01, the third by 0x2n02, etc. For each object the "DO trigger" variable can be individually set. The variable has to be set to TRUE in order for the EC4-ENC2IT to trigger a digital output when the encoder counter reaches the position value. " Array compare start index" (80n1:0A) variable starts always from the first position 0x2n00 (n=0; 2).

For example:
If the variable "Array compare end index" (0x8001:0B) is set to 10 for channel 0 then the positions stored in the objects 0x2000 to 0x200A will be used for the compare operation (Figure 32). The EC4-ENC2IT will only trigger a DO signal at a compare position if the "DO trigger" variable in the 0x2xxx objects is set to TRUE. The encoder counter has to sequentially arrive at the position 0x2000 to 0x200A, that means the counter first has to reach the 0x2000 position before the next position 0x2001 will be activated for position compare. If the encoder counter reaches the 0x2001 value before 0x2000 value then the 0x2001 position will not be triggered. In Figure 32 the "DO trigger" variables in 0x2002, 0x2006 and 0x2007 are disable and therefore no DO signal will be triggered once the encoder counter passes the compare position.
When the encoder position has reached the last compare position (here point 0x200A) then the next compare position will start again with the position stored in 0x2000.

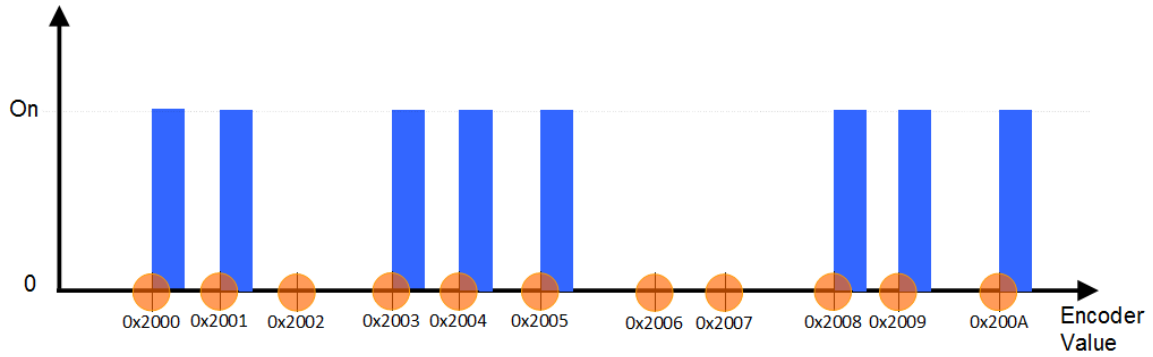


Figure 32: Array of compare positions for channel 0

7.1.6 Velocity Calculation Setting

The time interval parameters of 0x8100 have to be set first (see 9.8 for details) before starting the velocity calculation.

First, set the global time interval multiplier " Basic Multiplier " (0x8100: 01) of each channel, whose unit is 0.5 milliseconds. When it is necessary to extend or shorten the time interval of all channels, it can be adjusted by changing the value of this parameter.

Second, set the time interval multiplier "CHn Multiplier " (0x8100 : 02+n, n = 0, 1) of individual channels, then the time interval Vel_dT of each channel is configured as:

$Vel\_dT = T_{basic} \times T_{chn} \times 0.5 \times 10^{-3}$ sec, n= 0, 1.

Whereby T_{basic} represents "Basic Multiplier", T_{chn} represents "CHn Multiplier".

After that, the velocity V can be calculated from the variable Vel_dP, and the unit is pulses/sec:

V = Vel_dP / Vel_dT

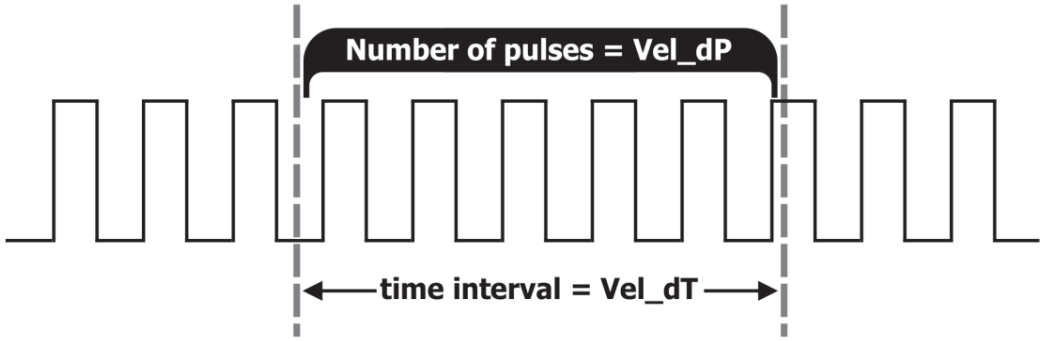


Figure 33: Variables for velocity calculation

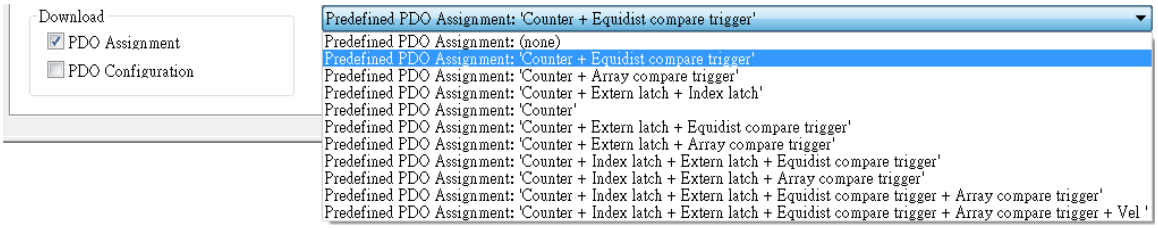
7.1.7 Repeat Signal

Set whether to extend the signal (encoder input A,B,C) of channel 0 to channel 1 via CoE (0x3000). The default value is "Disable" (0).
The usage of this function is to let the two channels refer to the same signal source, and then set the comparison trigger output respectively.

7.2 Process Data Parameter

7.2.1 Counter

If the EC4-ENC2IT is being used for reading the encoder counter only then the following PDOs have to be selected: 0x16n0 and 0x1An0 (n= 0;1). By using TwinCAT the required PDO can be selected with one click by selecting the "Counter" from the predefined PDO assignment drop box.



The following table list and describes the parameter defined in the process data objects 0x16n0 and 0x1An0:

0x16n0 (n= 0;1)		
Parameter	Object	Description
Reset index latch value	0x70n0:02	Requires 0x1An3 to be assigned to the process data. Will be discussed in a later section)
Set counter	0x70n0:04	If "Set counter" changes its value from FALSE to TRUE then the encoder counter of the EC4-ENC2IT will be set to the value of "Set counter value" (0x70n0:09) . The "Set counter done" (0x60n0:01) will change from FALSE to TRUE to indicate that the counter has successfully been set to the new value.
Set counter value	0x70n0:09	The new value to the assigned to the encoder counter. Has to be set by the user.

Table 10: 0x16n0 - Process data sent to the EC4-ENC2IT

0x1An0 (n= 0;1)		
Parameter	Object	Description
Set counter done	0x60n0:01	Indicates whether the "Encoder counter value" (0x60n0:11) has been assigned a new value. The user has to set the "Set counter" (0x70n0:04) from FALSE to TRUE in order to reset the encoder value to zero.
Reset index latch value done	0x60n0:02	Requires the 0x1An3 object to be added to the process data (will be discussed in the following section)
Signal of input A	0x60n0:03	Shows whether the "A" signal is high or low
Signal of input B	0x60n0:04	Shows whether the "B" signal is high or low
Signal of input C	0x60n0:05	Shows whether the "C" signal is high or low

0x1An0 (n= 0;1)		
Parameter	Object	Description
Signal of input I	0x60n0:06	Shows whether the "I" signal is high or low
Enable extern latch done	0x60n0:07	Requires the 0x16n1 and 0x1An1 to be added to the process data (will be discussed in the next section)
Reset extern latch value done	0x60n0:08	Requires the 0x16n1 and 0x1An1 to be added to the process data (will be discussed in the next section)
Enable equidist compare done	0x60n0:09	Requires the 0x16n2 and 0x1An2 to be added to the process data
Enable array compare done	0x60n0:0A	Requires the 0x16n3 and 0x1An2 to be added to the process data
Enable compare via DI done	0x60n0:0B	Position compare has been enabled via the digital input channel (I)
Next compare position active	0x60n0:0C	Indicates whether the "Get next compare position" (0x1An2, n= 0; 1) value is active as the next compare position.
Sync error	0x60n0:0F	This variable informs the user whether a synchronization error occurred in Distributed Clock (DC) mode during the previous cycle. The master has to make sure that within each fixed time interval a datagram is being sent to the slave otherwise a synchronization error will be displayed
TxPDO Toggle	0x60n0:10	The slaves toggles this parameter each time TxPDO data has been updated
Actual counter value	0x60n0:11	Current encoder counter value
Index latched counter value	0x60n0:12	Requires the 0x1An3 object to be added to the process data

Table 11: 0x1An0 - Process data received from the EC4-ENC2IT

The following flow diagram (Figure 34) shows the procedure for setting the encoder counter value.

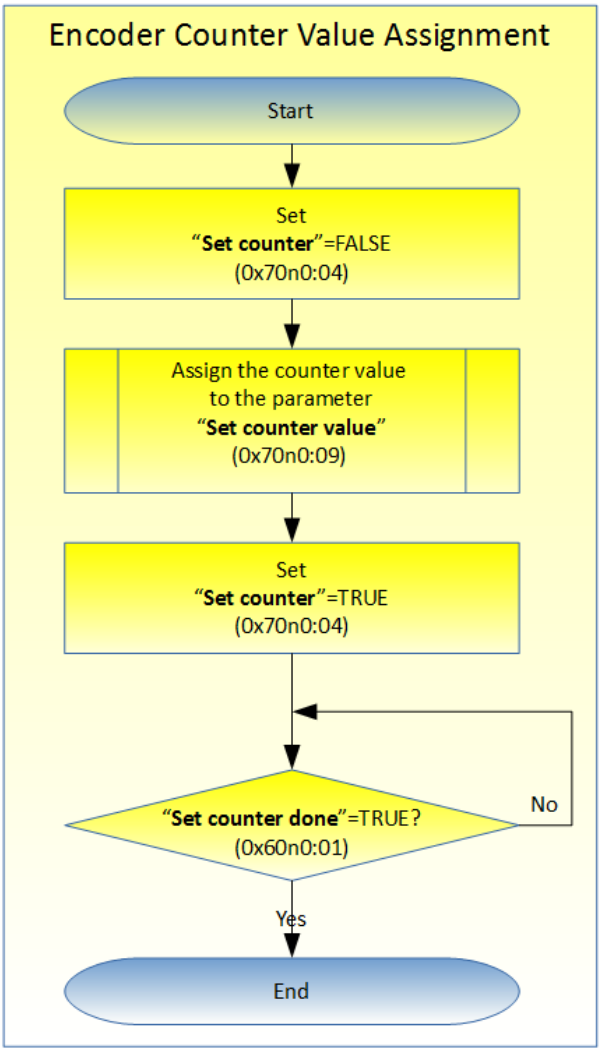


Figure 34: Encoder counter setting

7.2.2 Position Compare Trigger

The compare trigger function supports three modes: Single position compare, auto-increment position compare and array position compare.

- Single position compare: The user has to set one compare position at which a digital output signal will be triggered. The DO trigger will always be generate once the encoder counter reaches this position, regardless from which direction. The compare position can be altered by software at any time by following the procedure described in the first column of Table 15.
- Auto-increment position compare: Here the compare position will automatically be incremented by hardware once the current compare position has been reached. The compare function will trigger a signal output and increment the compare position if the current compare position has been approached from the configured direction. It

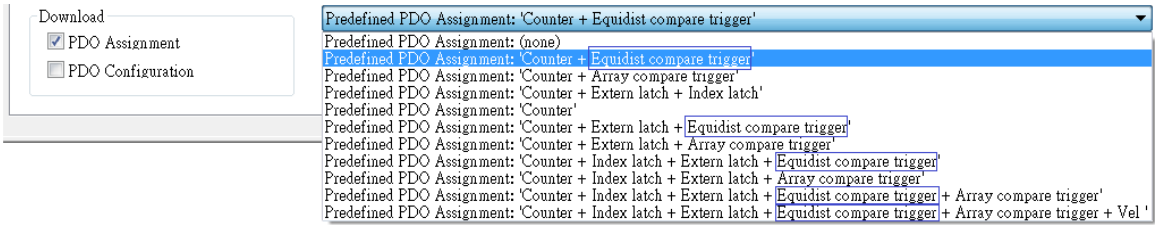
is important to reset the compare function by disabling/enabling it after the encoder counter has been set to a different value by the user.

- Array position compare: The position compare array type allows the operator to assign for each channel up to 200 position compare values in sequential order. The values has to be set via CoE (0x2nxx:01, n=0; 2). The compare function will trigger a digital output once the encoder counter has reached the position in the sequential order of the position array. Each value in the array can be individually enabled/disabled for triggering a digital output.

7.2.2.1 Equidistant Compare Mode

This mode supports two types: Single position compare and auto-increment position compare

Process data required for doing equidistant position compare control: 0x16n0, 0x16n2, 0x1An0, 0x1An2 (n= 0;1). By using TwinCAT one of the predefined PDO Assignments which contains the "Equidist compare trigger" has to be selected.



The main variables of the process data objects 0x16n0 and 0x1An0 have already been described in the previous section therefore only the equidistant compare position parameters will be listed in the following tables.

0x16n2 (n= 0;1)		
Parameter	Object	Description
Enable compare	0x70n2:01	The compare function will be activated if the "Enable compare" parameter changes its value from FALSE to TRUE. It is necessary to first set the following variables before enabling the compare function: ▪ "Set auto increment compare direction" ▪ "Set first compare position" ▪ "Set auto increment compare value" Once the compare function has been activated the "Enable equidist compare done" (0x60n0:08) value changes to TRUE. If the encoder counter (0x60n0:11) has been reset or assigned a new value then the compare function needs to be reset by assigning FALSE/TRUE to the "Enable compare" variable.

0x16n2 (n= 0;1)		
Parameter	Object	Description
Set auto increment compare direction	0x70n2:02	Indicates the direction at which the encoder counter has to approach the compare value. This variable is valid only if incremental-compare has been activated ("Set auto increment compare value" != 0) Valid values: ▪ 0: positive direction ▪ 1: negative direction
Set first compare position	0x70n2:07	Position at which the first compare output signal will be triggered EC4-ENC2IT supports two compare mode: ▪ Single compare position: In this mode the "Set first compare position" variable sets the position at which a compare output trigger will occur. ▪ Auto-increment compare: Here the "Set first compare position" indicates the first position at which a compare trigger event will be generated. The hardware will automatically set the next compare position by adding/subtracting the "Set auto increment compare value" (0x70n2:08) value to/from the "Set first compare position" value. The user can always confirm the next compare position by reading the variable "Get next compare position" (0x60n2:01). This position is only valid if the "Next compare position active" (0x600n:0C) is true.
Set auto increment compare value	0x70n2:08	The value of this variable will be automatically added to the current compare position once it has been reached from the direction setup in "Set auto increment compare direction" Disable auto-increment compare function by setting this variable to zero.

Table 12: 0x16n2 - Process data sent to the EC4-ENC2IT

0x1An0 (n= 0;1)		
Parameter	Object	Description
Enable equidist compare done	0x60n0:08	Indicates whether the compare function has been activated (TRUE) or not (FALSE).
Enable compare via DI done	0x60n0:0B	Indicates whether the position compare has been activated via digital input channel (I). This parameter will turn true if the following three conditions are met: • Use the digital input (I) for enabling compare "Activate compare via DI"= Enabled (0x80n1:03, n= 0;1) • Compare mode has been enabled: "Enable equidist compare done" (0x60n0:09, n= 0;1) is TRUE • Channel (I) has a digital input signal

Table 13: 0x1An0 - Process data received from the EC4-ENC2IT

0x1An2 (n= 0;1)		
Parameter	Object	Description
Get next compare position	0x60n2:01	Shows the value at which the next compare output will be triggered. This position is only valid if the "Next compare position active" (0x600n:0C) is TRUE.

Table 14: 0x1An2 - Process data received from the EC4-ENC2IT

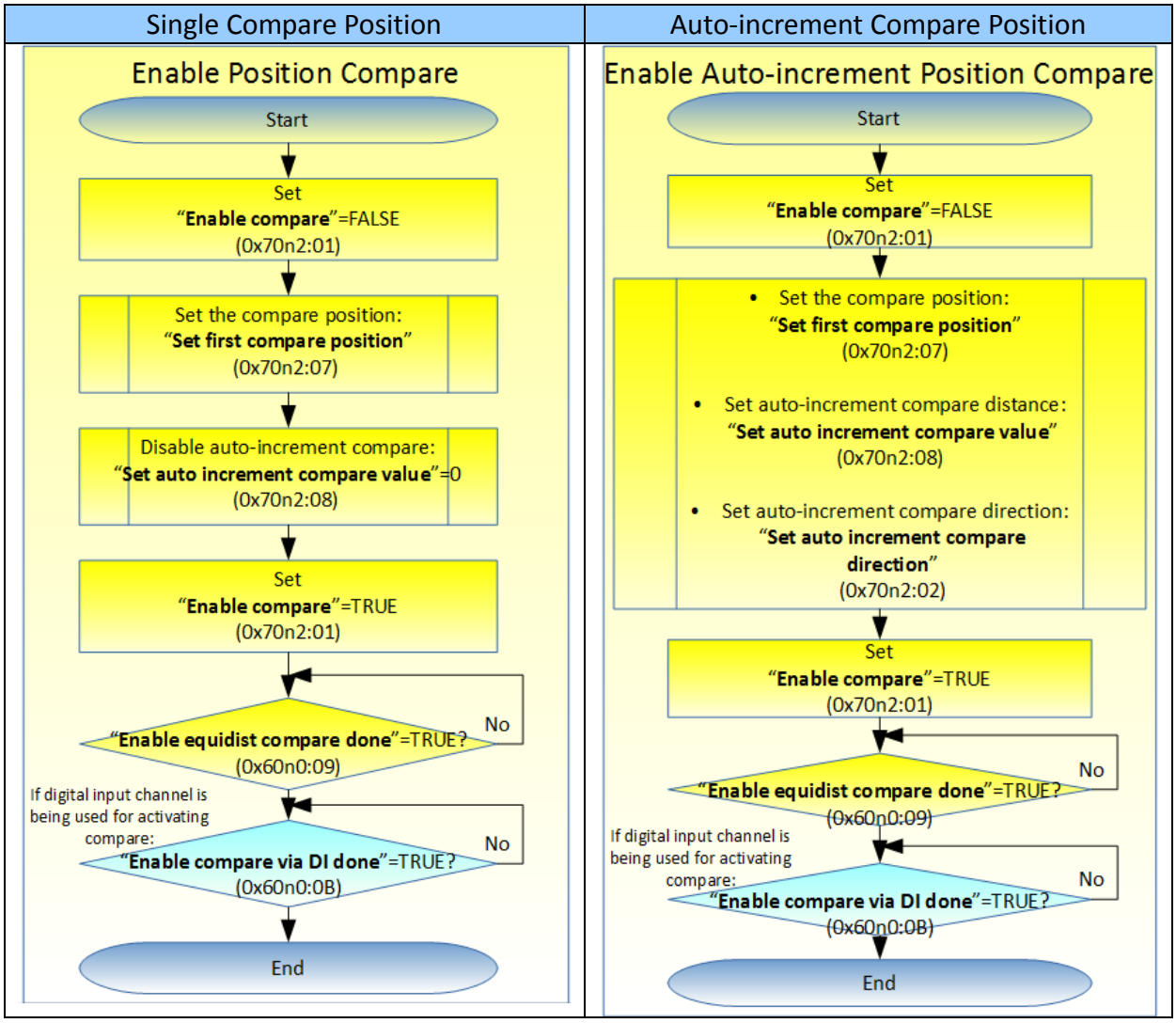
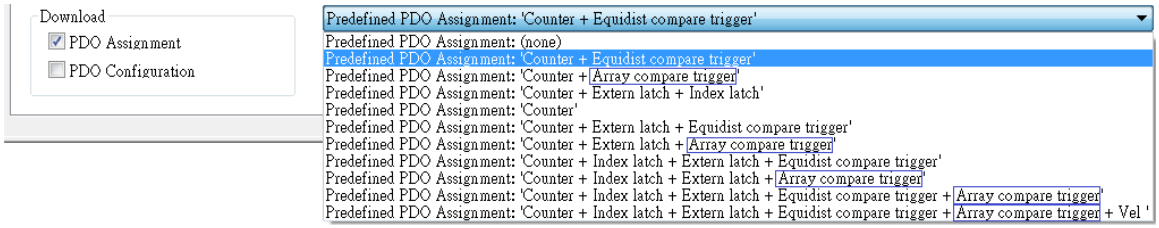


Table 15: Procedure for activating the equidistant compare function

7.2.2.2 Array Compare Mode

Process data required for doing array position compare control: 0x16n0, 0x16n3, 0x1An0, 0x1An2 (n= 0;1). By using TwinCAT one of the predefined PDO Assignments which contains the "Array compare trigger" has to be selected.



The following tables describe the PDO parameters used for the array compare mode.

0x16n3 (n= 0;1)		
Parameter	Object	Description
Enable compare	0x70n3:01	The compare function will be activated if the "Enable compare" parameter changes its value from FALSE to TRUE. The position compare values have to be set via CoE (0x2nxx:01, n=0; 2) before the "Enable compare" is set to TRUE. Once the compare function has been activated the "Enable array compare done" (0x60n0:0A) value changes to TRUE.

Table 16: 0x16n3 - Process data sent to the EC4-ENC2IT

0x1An0 (n= 0;1)		
Parameter	Object	Description
Enable array compare done	0x60n0:09	Indicates whether the compare function has been activated (TRUE) or not (FALSE).
Enable compare via DI done	0x60n0:0B	Indicates whether the position compare has been activated via digital input channel (I). This parameter will turn true if the following three conditions are met: • Use the digital input (I) for enabling compare "Activate compare via DI"= Enabled (0x80n1:03, n= 0;1) • Compare mode has been enabled: "Enable array compare done" (0x60n0:0A, n= 0;1) is TRUE • Channel (I) has a digital input signal

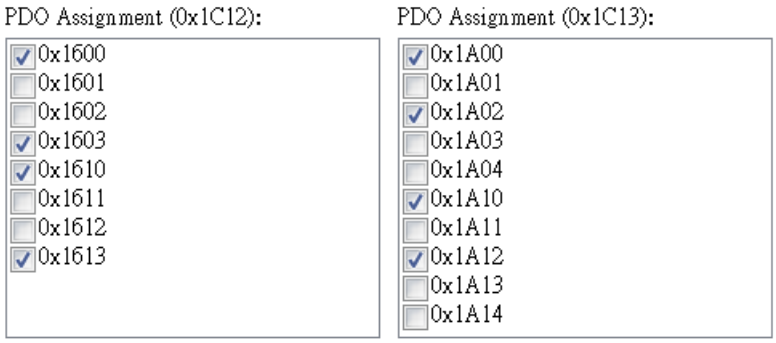
Table 17: 0x1An0 - Process data received from the EC4-ENC2IT

0x1An2 (n= 0;1)		
Parameter	Object	Description
Get next compare position	0x60n2:01	Shows the value at which the next compare output will be triggered. This position is only valid if the "Next compare position active" (0x600n:0C) is TRUE.

Table 18: 0x1An2 - Process data received from the EC4-ENC2IT

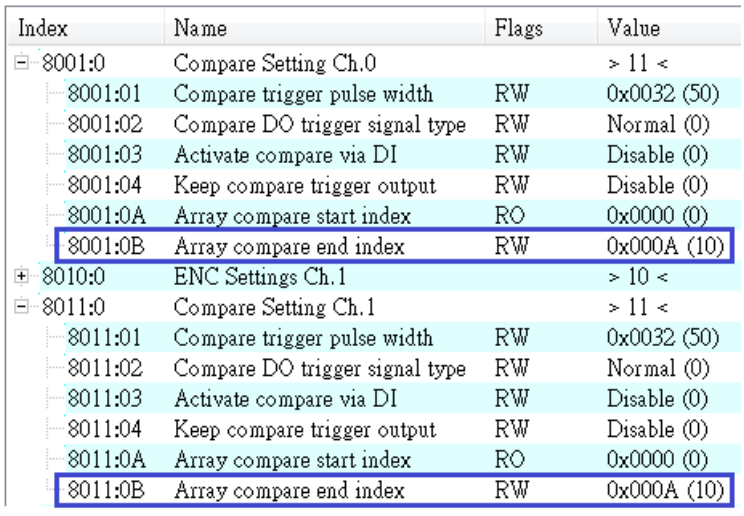
Procedure for configuring and activating the "Array compare" mode:

Step 1: Select the following PDO: 0x16n0, 0x16n3, 0x1An0, 0x1An2 (n= 0;1)



TwinCAT provides a function to directly select all necessary PDOs by clicking the "Predefined PDO Assignment" drop list as described above.

Step 2: Configure the compare properties via the SDO (0x80n1, n= 0;1). For array compare it is important to set the "Array compare end index" variable (SDO 0x80n1:0B, n= 0;1). This sets the quantity of position compare values to be used for the compare operation (Figure 35).



Index	Name	Flags	Value
8001:0	Compare Setting Ch.0		> 11 <
8001:01	Compare trigger pulse width	RW	0x0032 (50)
8001:02	Compare DO trigger signal type	RW	Normal (0)
8001:03	Activate compare via DI	RW	Disable (0)
8001:04	Keep compare trigger output	RW	Disable (0)
8001:0A	Array compare start index	RO	0x0000 (0)
8001:0B	Array compare end index	RW	0x000A (10)
8010:0	ENC Settings Ch.1		> 10 <
8011:0	Compare Setting Ch.1		> 11 <
8011:01	Compare trigger pulse width	RW	0x0032 (50)
8011:02	Compare DO trigger signal type	RW	Normal (0)
8011:03	Activate compare via DI	RW	Disable (0)
8011:04	Keep compare trigger output	RW	Disable (0)
8011:0A	Array compare start index	RO	0x0000 (0)
8011:0B	Array compare end index	RW	0x000A (10)

Figure 35: Compare mode and number of compare position

Step 3: Assign an array of position values to the 0x2nxx:01 objects (n=0; 2) via CoE. Each object stores one position value and a "DO trigger" flag which indicates whether a digital output will be triggered if the encoder value reaches this position value. The first compare value has to be stored in object 0x2n00, the second in object 0x2n01, the third in object 0x2n02, etc.. The sequence of the position values are important as the EC4-ENC2IT always considers the value stored in object 0x2n00 as the first compare position and it remains in the compare register until the encoder counter reaches this position before using the object 0x2n01 value as the next compare position.

Example:
In Figure 36 the compare values for encoder channel 0 are set to 150, 250, 350, 500, 600, 750, 900, 1000, 1200, 1300 and 1450. The "DO Trigger" flag for objects 0x2002:02, 0x2006:02 and 0x2007:02 are disabled therefore no digital output will be triggered for these positions (Figure 37).

Index	Name	Flags	Value
2000:0	Ch.0 Compare Pos.0		> 2 <
2000:01	Position	RW	150
2000:02	DO trigger	RW	Enable (1)
2001:0	Ch.0 Compare Pos.1		> 2 <
2001:01	Position	RW	250
2001:02	DO trigger	RW	Enable (1)
2002:0	Ch.0 Compare Pos.2		> 2 <
2002:01	Position	RW	350
2002:02	DO trigger	RW	Disable (0)
2003:0	Ch.0 Compare Pos.3		> 2 <
2003:01	Position	RW	500
2003:02	DO trigger	RW	Enable (1)
2004:0	Ch.0 Compare Pos.4		> 2 <
2004:01	Position	RW	600
2004:02	DO trigger	RW	Enable (1)
2005:0	Ch.0 Compare Pos.5		> 2 <
2005:01	Position	RW	750
2005:02	DO trigger	RW	Enable (1)
2006:0	Ch.0 Compare Pos.6		> 2 <
2006:01	Position	RW	900
2006:02	DO trigger	RW	Disable (0)
2007:0	Ch.0 Compare Pos.7		> 2 <
2007:01	Position	RW	1000
2007:02	DO trigger	RW	Disable (0)
2008:0	Ch.0 Compare Pos.8		> 2 <
2008:01	Position	RW	1200
2008:02	DO trigger	RW	Enable (1)
2009:0	Ch.0 Compare Pos.9		> 2 <
2009:01	Position	RW	1300
2009:02	DO trigger	RW	Enable (1)
200A:0	Ch.0 Compare Pos.10		> 2 <
200A:01	Position	RW	1450
200A:02	DO trigger	RW	Enable (1)

Figure 36: User defined compare positions

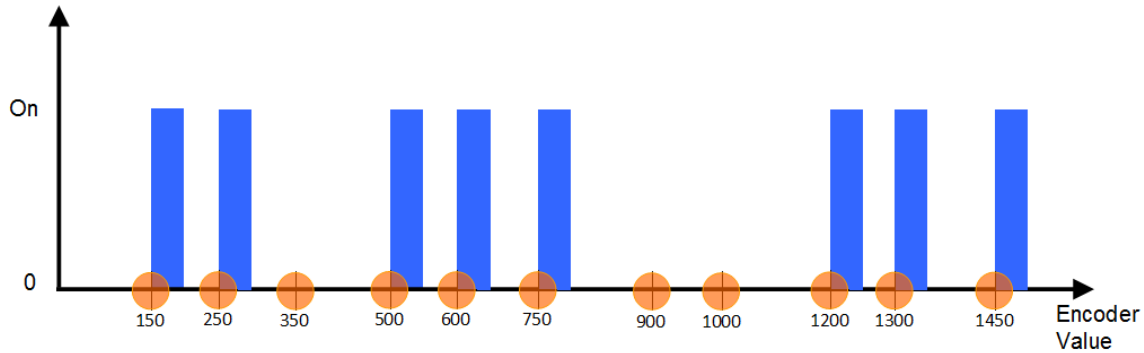


Figure 37: Compare position with DO trigger settings

Step 4: Set the slave in Op mode and enable the compare function by setting the "Enable compare" (0x70n3:01, n=0;1) variable to TRUE (Figure 38).

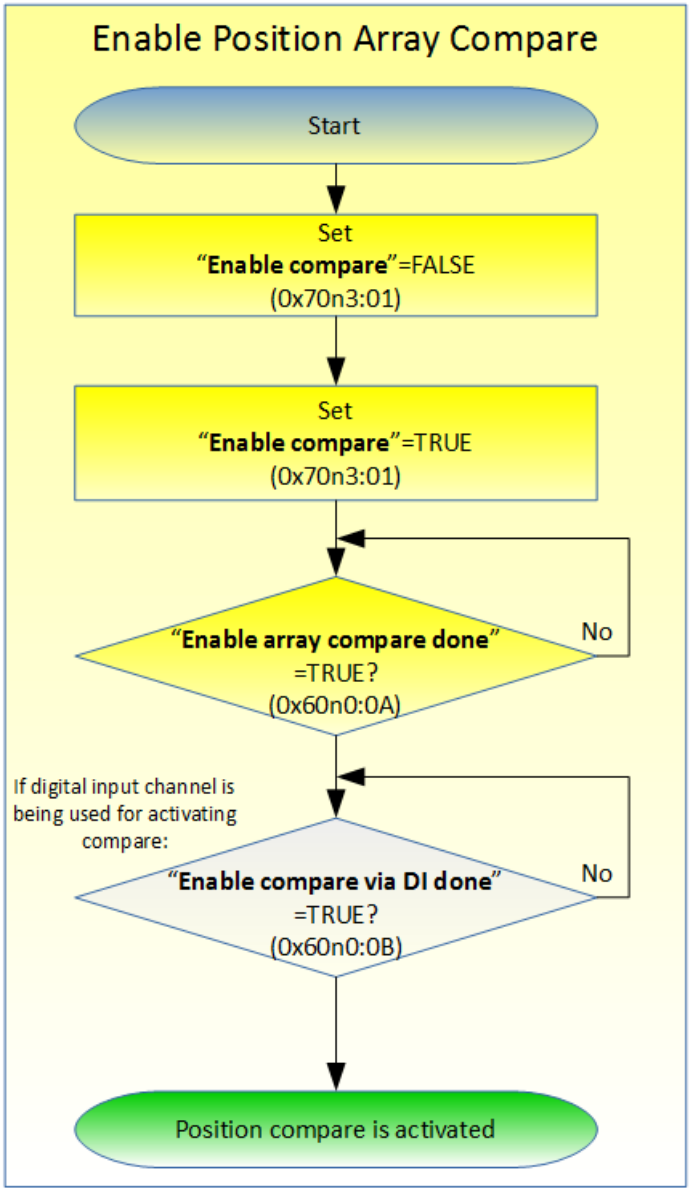


Figure 38:Procedure for activating the array compare function

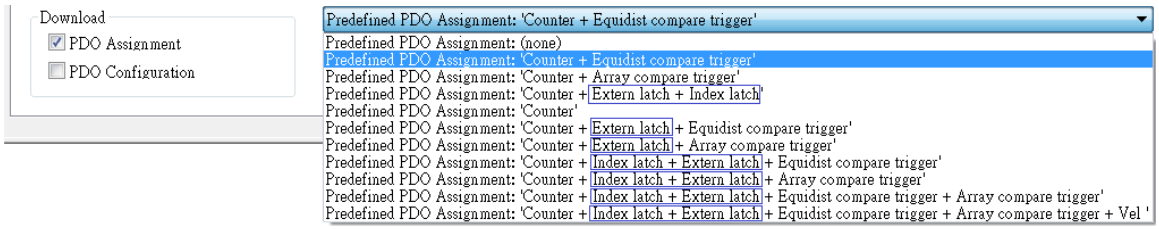
7.2.3 Index and Extern Latch

The EC4-ENC2IT has got two latch inputs for each encoder channel: Index "C" and extern "I" latch.

- Index latch: The index latch is always enabled and can not be disabled. A index signal triggers a hardware latch of the current encoder counter. The EC4-ENC2IT allows the index latched value to be reset to zero. Assign the 0x1An3 object to the process data for reading the latched counter value.
- Extern latch: The extern latch function supports two modes:
  - Reset encoder counter: The encoder counter is reset to zero once the extern "I" signal has been triggered
  - Latch encoder counter: This mode captures and stores two latch values. A rising and falling edge input signal at the "I" channel triggers a hardware latch of the current encoder value.

  The extern latch function is by default disabled and has to be enabled prior to the latch operation.
  Assign the objects 0x1An1 and 0x16n1 to the process data.

TwinCAT allows the selection of the latch object by selecting one of the predefined PDO assignment which contains the "Index latch" or "Extern latch" keywords from the list box:



The following tables describes the status and assignment parameters of both index and extern latch.

0x16n0 (n= 0;1)		
Parameter	Object	Description
Reset index latch value	0x70n0:02	When this variable turns from FALSE to TRUE then the index latch value will be cleared (set to zero). The status variable "Reset index latch value done" (0x60n0:02) will become TRUE once the action has been finished.

Table 19: 0x16n0 - Process data sent to the EC4-ENC2IT

0x16n1 (n= 0;1)		
Parameter	Object	Description
Enable extern latch	0x70n1:01	If this variable turns from FALSE to TRUE then the extern latch will be activated. The status variable "Enable extern latch done" (0x60n0:06) will become TRUE once the extern latch has been enabled. If this variable turns from FALSE to TRUE then both latch parameters "Rising edge latched value" (0x60n1:01) and "Falling edge latched value" (0x60n1:02) are reset to zero.
Reset extern latch value	0x70n1:02	If this variable turns from FALSE to TRUE then the extern latch parameters "Rising edge latched value" (0x60n1:01) and "Falling edge latched value" (0x60n1:02) will be reset to zero. The status variable "Reset extern latch counter done" (0x60n0:07) will be TRUE once the extern latch register has been reset.

Table 20: 0x16n1 - Process data sent to the EC4-ENC2IT

0x1An0 (n= 0;1)		
Parameter	Object	Description
Reset index latch value done	0x60n0:02	Indicates whether the index latch value has been reset to zero. This parameter shows the response of the slave to the "Reset index latch value" (0x70n0:02) input. The parameter is FALSE if ▪ the "Reset index latch value" (0x70n0:02) is set to FALSE ▪ the firmware is busy resetting the index latch value The parameter is TRUE if the "Reset index latch value" (0x70n0:02) has been set to TRUE and the index value has successfully been set to zero
Enable extern latch done	0x60n0:07	Indicates whether the extern "I" latch has been enabled. This parameter shows the response of the slave to the "Enable extern latch" (0x70n1:01) input.
Reset extern latch counter done	0x60n0:08	Indicates whether the extern latch register has been reset to zero. This parameter shows the response of the slave to the "Reset extern latch value" (0x70n1:02) input.

Table 21: 0x1An0 - Process data received from the EC4-ENC2IT

0x1An1 (n= 0;1)		
Parameter	Object	Description
Rising edge latched value	0x60n1:01	▪ Encoder value latched by the rising edge of the external signal at channel "I". ▪ The trigger level has to be set for both encoder channel together ("I signal polarity", 0x80n0:04) ▪ The value is valid only if • the extern latch function has been enabled ("Enable extern latch done", 0x60n0:06) • the extern latch has been set to "Latch encoder counter" mode. This has to be set via "Extern latch mode" (0x80n0:05)
Falling edge latched value	0x60n2:01	▪ Encoder value latched by the falling edge of the external signal at channel "I". ▪ The trigger level has to be set for both encoder channel together ("I signal polarity", 0x80n0:04) ▪ The value is valid only if • the extern latch function has been enabled ("Enable extern latch done", 0x60n0:06) • the extern latch has been set to "Latch encoder counter" mode. This has to be set via "Extern latch mode" (0x80n0:05)

Table 22: 0x1An1 - Process data received from the EC4-ENC2IT

0x1An3 (n= 0;1)		
Parameter	Object	Description
Index latched counter value	0x60n0:12	Encoder value latched by the index signal "C". The encoder value will be latched at a rising or falling edge of the index input signal. The trigger edge can be set for each channel individually ("C signal polarity", 0x80n0:03)

Table 23: 0x1An3 - Process data received from the EC4-ENC2IT

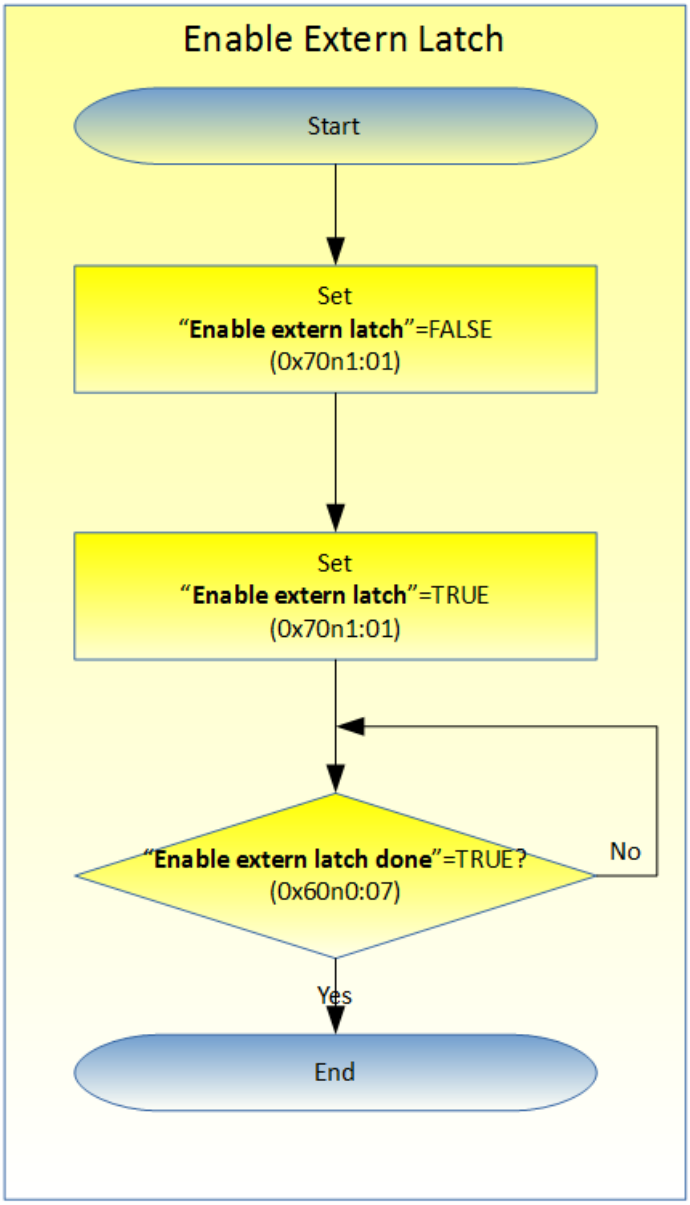


Figure 39: Activating external "I" latch

The following table (Table 24) shows the procedure for resetting the index and extern latch value to zero.

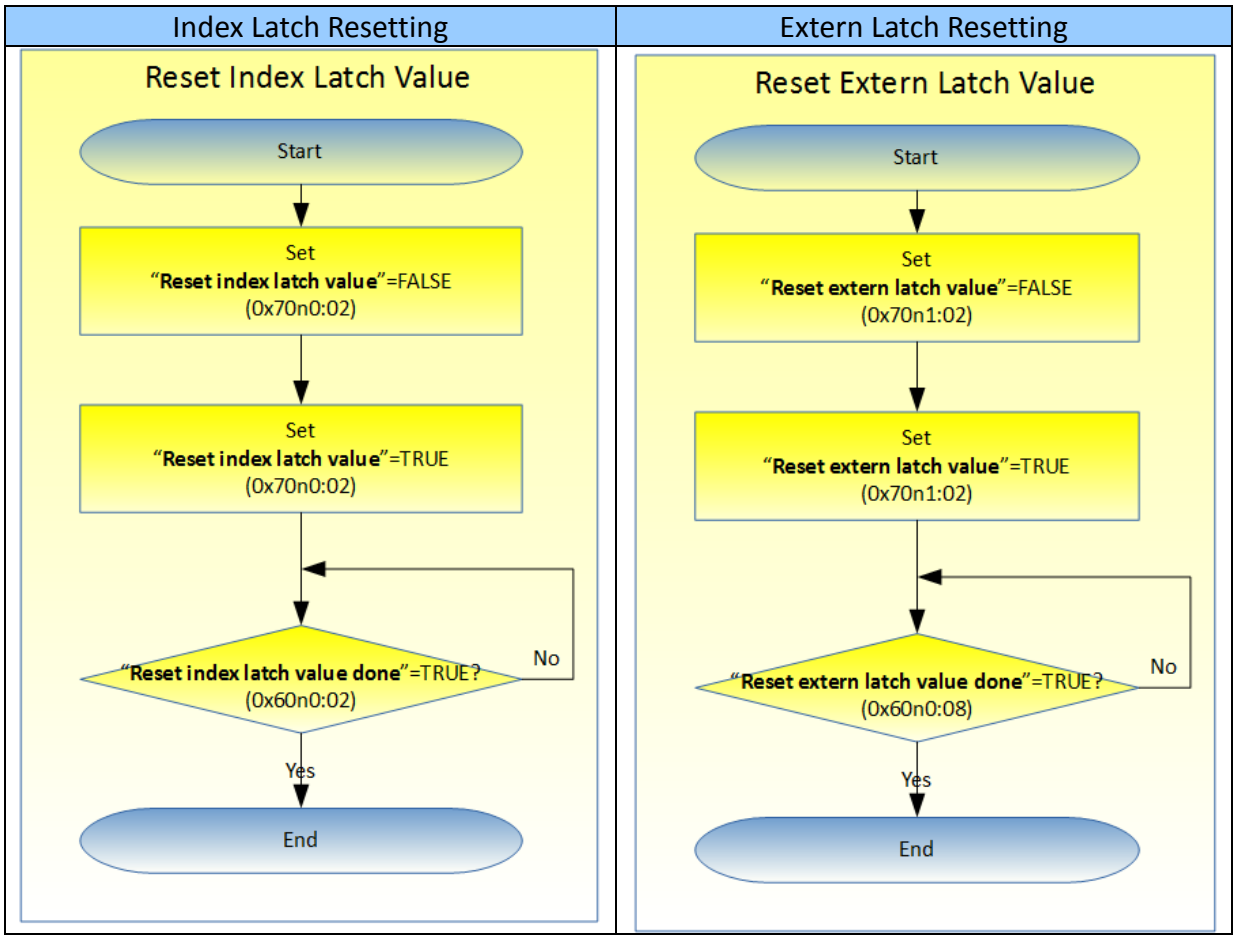
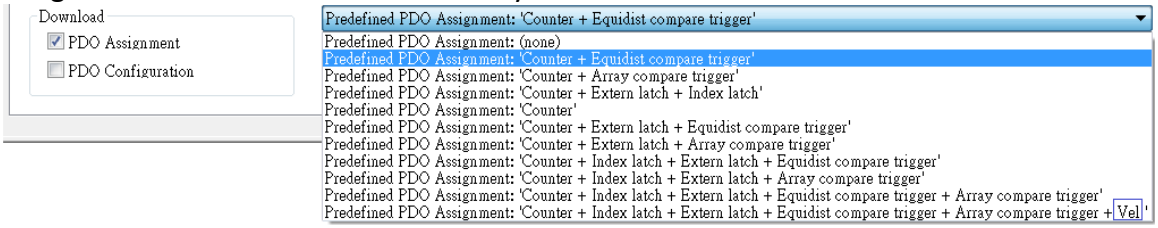


Table 24: Resetting latch register procedure

7.2.4 Velocity Calculation

The EC4-ENC2IT provides velocity calculation functionality for each encoder channel. TwinCAT allows the selection of the velocity status object by selecting a predefined PDO assignment which contains the "Vel" keywords from the list box:

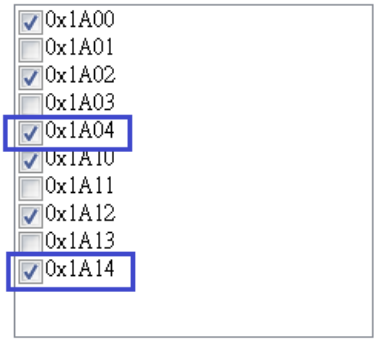


Alternatively, the user can add the velocity status object to the process data by selecting the PDO object: 0x1An4, (n= 0;1) in PDO Assignment (0x1C13).

PDO List:

Index	Size	Name	Flags	SM	SU
0x1A00	6.0	ENC Status Ch.0	F	3	0
0x1A01	8.0	Extern Latch Status Ch.0	F		0
0x1A02	4.0	Compare Trigger Status Ch.0	F	3	0
0x1A03	4.0	Index Latch Status Ch.0	F		0
0x1A04	2.0	ENC VEL Status Ch.0	F		0
0x1A10	6.0	ENC Status Ch.1	F	3	0
0x1A11	8.0	Extern Latch Status Ch.1	F		0
0x1A12	4.0	Compare Trigger Status Ch.1	F	3	0
0x1A13	4.0	Index Latch Status Ch.1	F		0
0x1A14	2.0	ENC VEL Status Ch.1	F		0

PDO Assignment (0x1C13):



The following tables describe the PDO parameter used for velocity calculation.

0x1An4 (n= 0;1)		
Parameter	Object	Description
Vel_dP	0x60n3:01	Position difference per time interval for velocity calculation

Table 25: 0x1An4 - Process data received from the EC4-ENC2IT

Vel_dP is the position difference per time interval described in chapter 7.1.6.
If the time interval basic multiplier "Basic Multiplier" (0x8100: 01) and the time interval multiplier "CHn Multiplier" (0x8100: 02+n, n = 0, 1) of a channel are both default values, the Vel_dP of the channel is the position difference per 1 millisecond.

8 CoE Interface

8.1 General Description

The CoE interface (CANopen over EtherCAT) is used for parameter management of EtherCAT devices. The CoE interface displays all the objects and parameters which are required for operating and diagnosing the EC4-ENC2IT device. Some parameters are fixed and can not be modified, they for example indicate the operating status of the device or the device properties. Encoder configuration parameters need to be set before the actual motion control starts. These parameter setting are determined by the encoder type and the setup of the system.

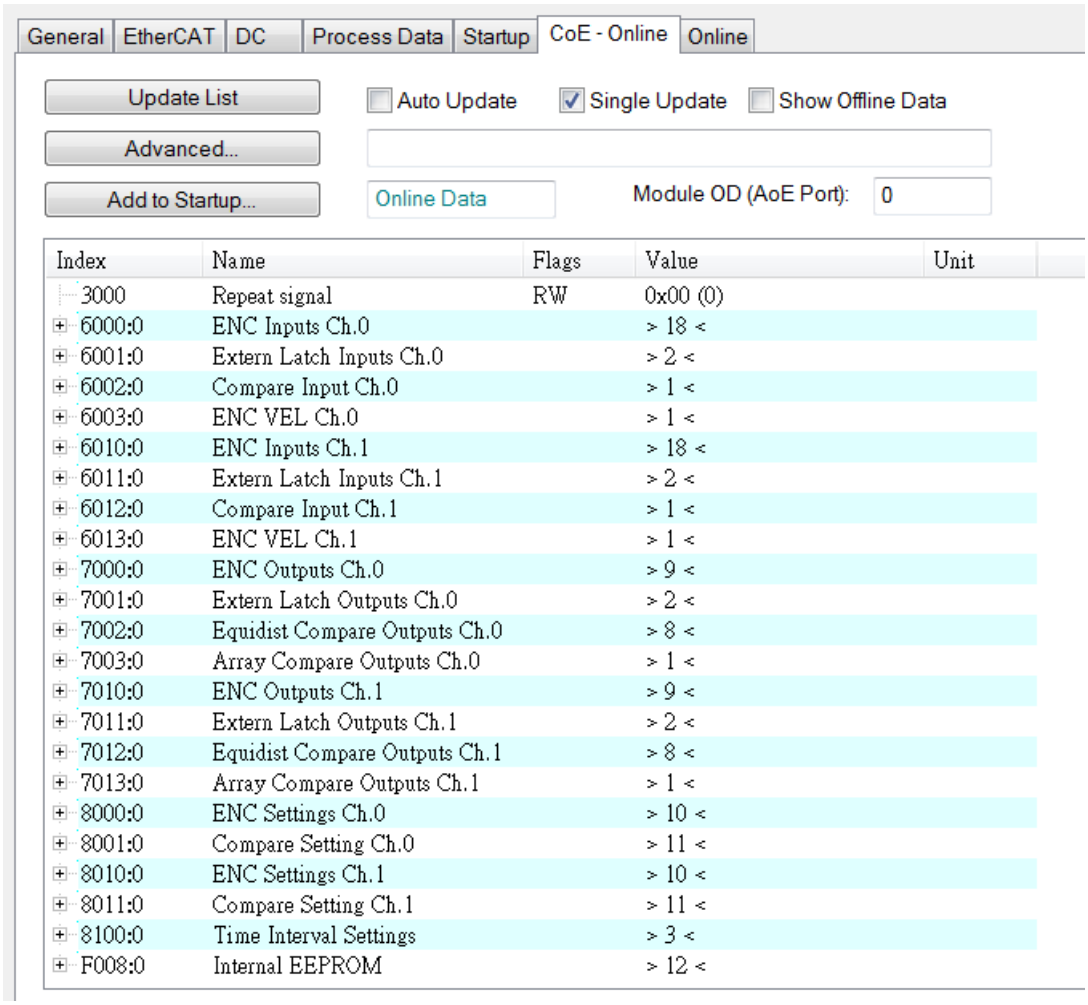
CoE parameters has to be accessed via the CAN over EtherCAT protocol. The EtherCAT master accesses the local CoE lists of the slaves via CAN over EtherCAT. The user does not need to understand the CoE protocol when using the TwinCAT System Manager for CoE parameter configuration.

The CoE parameters describe a wide range of features such as manufacturer ID, device name, process data settings and configuration parameters.

The relevant ranges of the CoE list are:

- 0x1000: Stores fixed information of the device, including name, manufacturer, serial number etc.. In addition stores information about the current and available process data configurations.
  - 0x1600: RxPDO mapping
  - 0x1A00: TxPDO mapping
- 0x2000: Stores the compare position values for the array compare mode
- 0x3000: Set whether to extend the signal of channel 0 to channel 1
- 0x8000: Stores all the configuration data which are required for the encoder counter.
- 0x6000: Input PDOs ("input" from the perspective of the EtherCAT master)
- 0x7000: Output PDOs ("output" from the perspective of the EtherCAT master)

The Figure 40 shows part of the CoE objects available for the EC4-ENC2IT device, ranging from 0x3000 to 0xF008. The parameters of the objects can be accessed by expanding the tree in the "CoE-Online" tab. The objects and their properties are described in chapter 9.



Index	Name	Flags	Value	Unit
3000	Repeat signal	RW	0x00 (0)	
6000:0	ENC Inputs Ch.0		> 18 <	
6001:0	Extern Latch Inputs Ch.0		> 2 <	
6002:0	Compare Input Ch.0		> 1 <	
6003:0	ENC VEL Ch.0		> 1 <	
6010:0	ENC Inputs Ch.1		> 18 <	
6011:0	Extern Latch Inputs Ch.1		> 2 <	
6012:0	Compare Input Ch.1		> 1 <	
6013:0	ENC VEL Ch.1		> 1 <	
7000:0	ENC Outputs Ch.0		> 9 <	
7001:0	Extern Latch Outputs Ch.0		> 2 <	
7002:0	Equidist Compare Outputs Ch.0		> 8 <	
7003:0	Array Compare Outputs Ch.0		> 1 <	
7010:0	ENC Outputs Ch.1		> 9 <	
7011:0	Extern Latch Outputs Ch.1		> 2 <	
7012:0	Equidist Compare Outputs Ch.1		> 8 <	
7013:0	Array Compare Outputs Ch.1		> 1 <	
8000:0	ENC Settings Ch.0		> 10 <	
8001:0	Compare Setting Ch.0		> 11 <	
8010:0	ENC Settings Ch.1		> 10 <	
8011:0	Compare Setting Ch.1		> 11 <	
8100:0	Time Interval Settings		> 3 <	
F008:0	Internal EEPROM		> 12 <	

Figure 40: "CoE - Online " tab

8.2 Save Data to Memory

In this section the procedure of saving configuration parameters to the non-volatile memory of the EC4-ENC2IT is being discussed.

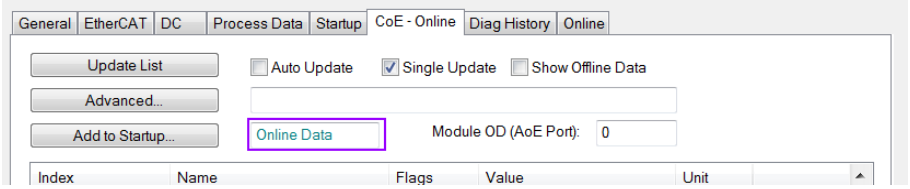
8.2.1 Save Configuration Data

The CoE objects 0x80n0, 0x80n1 (n=0;1) contain all the parameters needed to configure the EC4-ENC2IT. The 0x80n0 objects main purpose is the encoder counter and the latch channel configuration and the 0x80n1 objects is for position compare setting. TwinCAT allows the user to set the configuration parameters via the System Manager (Figure 40) or from a TwinCAT PLC via ADS (TcEtherCAT.lib library).

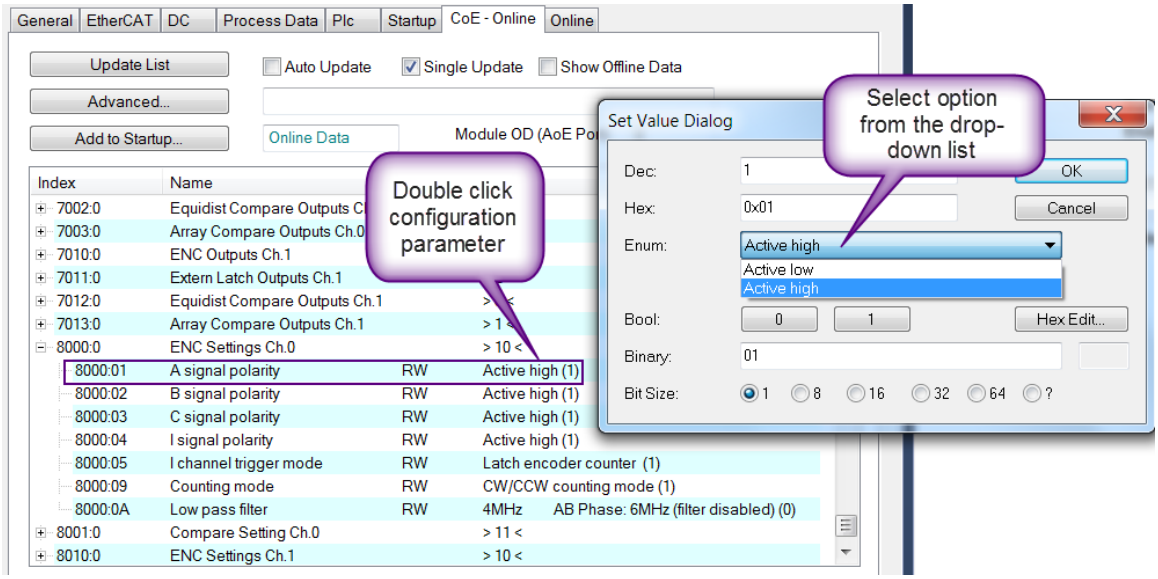
If the CoE parameters of the EC4-ENC2IT are set online, then the device does not automatically store the data to its non-volatile memory, and therefore the data will be lost once the device is switched off. The 0xF008 object provides functions to store the configuration data permanently to the non-volatile memory of the EC4-ENC2IT and the setting will be immediately available immediately after a restart.

Procedure for storing configuration data to the local EC4-ENC2IT memory:

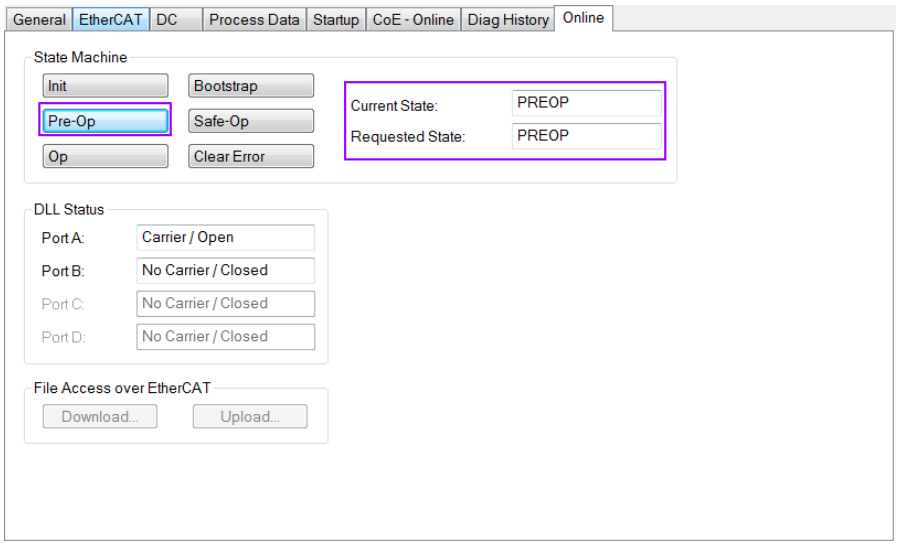
Step 1: Make sure the TwinCAT System Manager is connected to the EC4-ENC2IT and the "CoE-Online" tab is showing that the slave is online.



Step 2: Do all the necessary configuration by entering the correct parameter values for the configuration objects (0x80n0, 0x80n1 (n=0;1)). The setting is being done by double clicking the configuration parameter and selecting an option from the shown drop list box . In the following picture the signal polarity of the A signal of encoder channel 0 is being set.



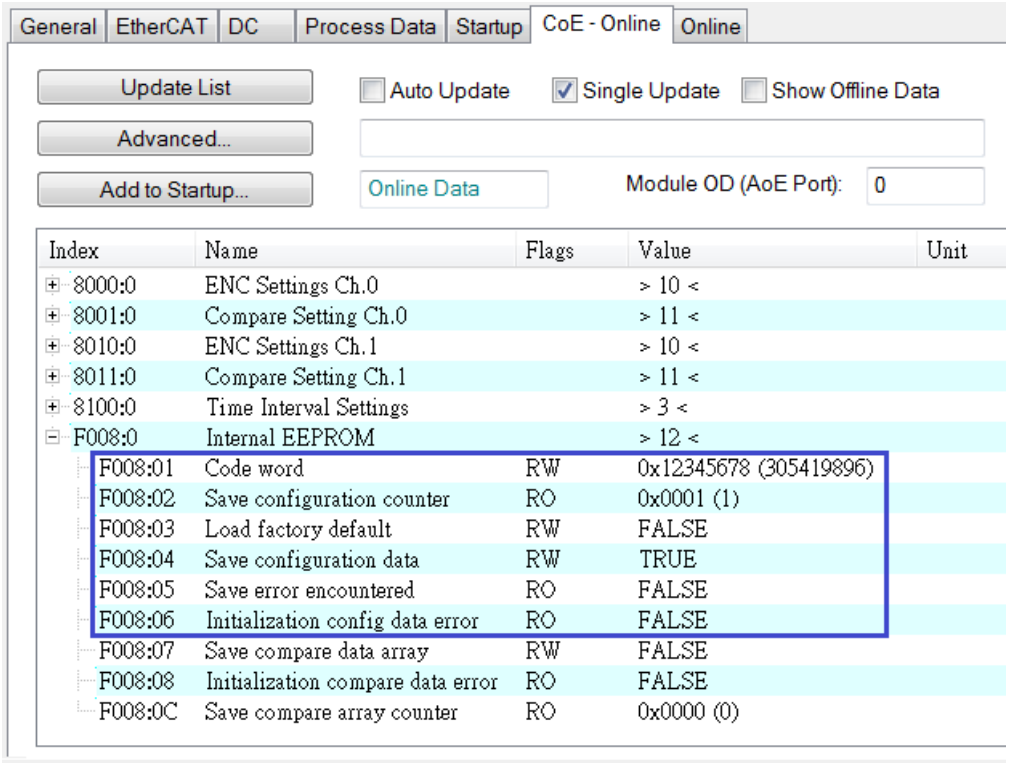
Step 3: After all the configurations have been done set the slave into Pre-Op mode. Data can only be stored to the local device if it is in Pre-Op mode. On the "Online" tab click the "Pre-OP" button to put the slave into Pre-OP mode.



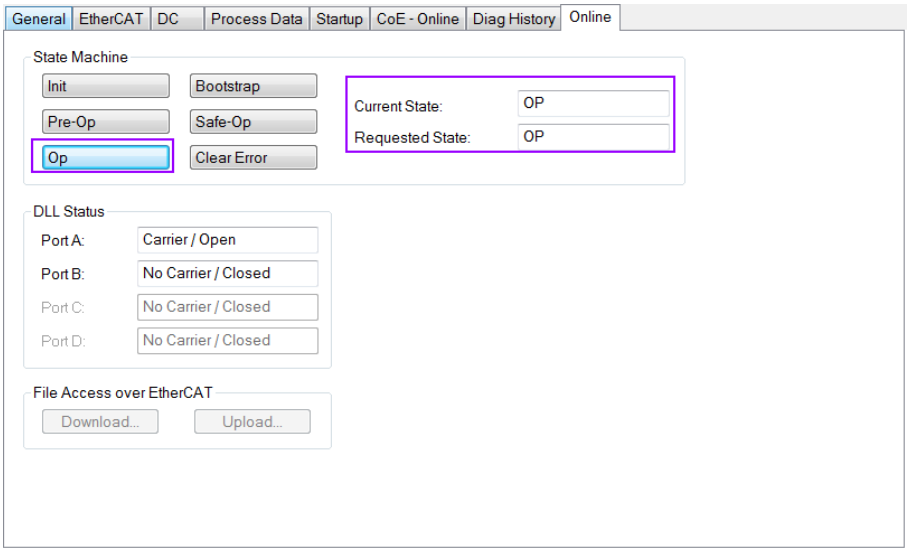
Step 4: The parameters of the 0xF008 object handles the save procedure.

1. Scroll to the end of the "CoE-Online" list and expand the tree view of the 0xF008 object
2. Enter the value 0x12345678 for the "Code Word"
3. Set the "Save configuration data" from FALSE to TRUE in order to save the configuration data (0x80n0, 0x80n1 (n=0;1)) to the internal EEPROM. The parameter "Save error encountered" (F008:05) indicates whether an error occurred during the save process.
4. In order for the configuration data to be loaded after a device restart set the "Load factory default" to FALSE. It is always possible to return to the factory default setting by setting this value back to TRUE.
5. The "Save configuration counter" (F008:02) shows how often configuration data has been stored to the local memory in the lifetime of the device.
6. If the EC4-ENC2IT has not been correctly initialized with the saved configuration data after the module has been switch on then the "Initialization config data error" (F008:06) flag shows TRUE.

   ATTENTION:
   The local memory only supports a limited number of save operations. Depending on the memory version once the save operation exceeds 10000 cycles it can no longer be guaranteed that data are reliably saved or are still readable. Therefore the "Save configuration data" (F008:04) and the "Load factory default" (F008:03) should not be continuously set from the controlling application program.



Step 5: Set the EC4-ENC2IT back into OP mode.



8.2.2 Save Position Compare Values

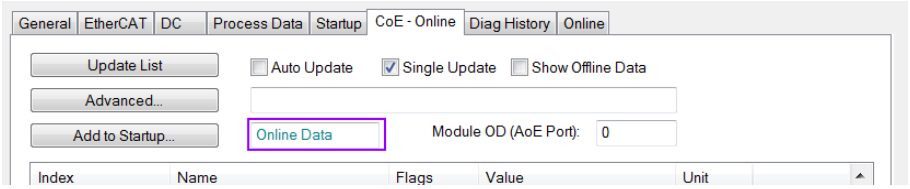
The position compare value are being used for the array compare mode. The position values have to set via the CoE (0x2nxx:01, n=0; 2). Up to 200 position per encoder

channel are supported. The EtherCAT master has to sent these values to the EC4-ENC2IT every time when the module is switch on which may take some time especially when large quantity of position compare value have to be set. In order to reduce the download time the module allows the user to directly store the value on the internal EEPROM. The module compare register will be immediately initialize with these values after it is switch on and it is ready for compare operation. With this method the value only have to be sent once which reduces the initialization time.

In the following the procedure for saving the position compare values with the help of the TwinCAT System Manager will be explained.

Procedure for storing the 0x2nxx:01 (n=0; 2) object data to the local EC4-ENC2IT memory:

Step 1: Make sure the TwinCAT System Manager is connected to the EC4-ENC2IT device and the "CoE-Online" tab is showing that the slave is online.

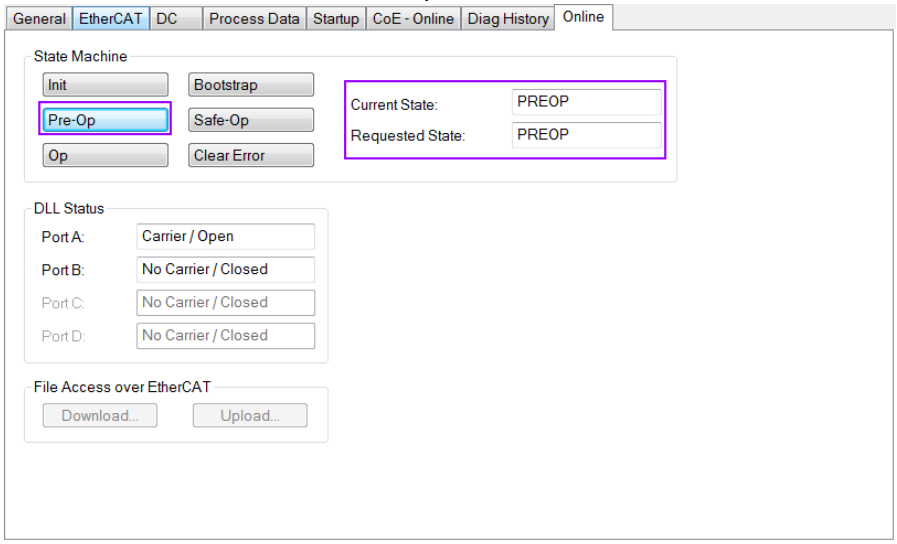


Step 2: Write the position compare values to the "Position" (0x2nxx:01, n=0; 2) parameter and set the "DO trigger" (0x2nxx:02, n=0; 2) flag.

Index	Name	Flags	Value
2000:0	Ch.0 Compare Pos.0		> 2 <
2000:01	Position	RW	150
2000:02	DO trigger	RW	Enable (1)
2001:0	Ch.0 Compare Pos.1		> 2 <
2001:01	Position	RW	250
2001:02	DO trigger	RW	Enable (1)
2002:0	Ch.0 Compare Pos.2		> 2 <
2002:01	Position	RW	350
2002:02	DO trigger	RW	Disable (0)
2003:0	Ch.0 Compare Pos.3		> 2 <
2003:01	Position	RW	500
2003:02	DO trigger	RW	Enable (1)
2004:0	Ch.0 Compare Pos.4		> 2 <
2004:01	Position	RW	600
2004:02	DO trigger	RW	Enable (1)
2005:0	Ch.0 Compare Pos.5		> 2 <
2005:01	Position	RW	750
2005:02	DO trigger	RW	Enable (1)

Step 3: After all the configurations have been done set the slave into Pre-Op mode. Data can only be stored to the local device if it is in Pre-Op mode. On the "Online"

tab click the "Pre-OP" button to put the slave into Pre-OP mode.



Step 4: The parameters of the 0xF008 object handles the save procedure.

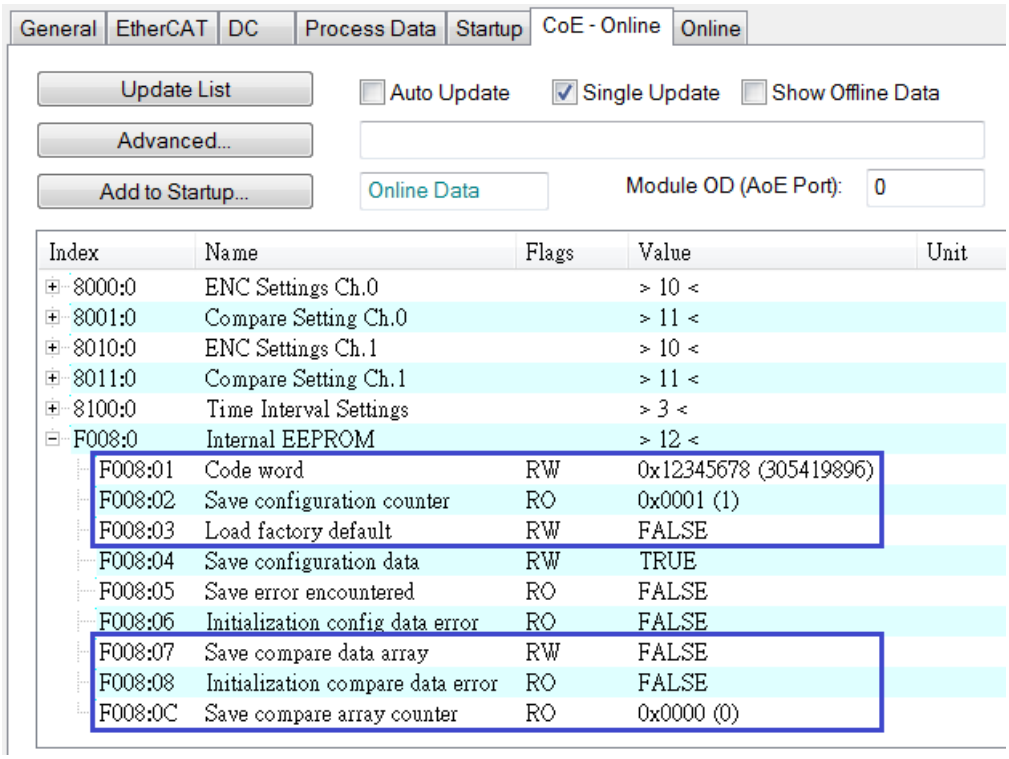
1. Scroll to the end of the "CoE-Online" list and expand the tree view of the 0xF008 object
2. Enter the value 0x12345678 for the "Code Word"
3. Set the "Save compare data array" (F008:07) from FALSE to TRUE in order to save the position compare object data (0x2nxx:01, n=0; 2) to the internal EEPROM.

   ATTENTION:
   In every save operation 200 objects for each encoder channel will be save. The save operation need some time and may exceed the timeout of the EtherCAT master. In this case it is necessary for the master to reconnect to the slave and reload the SDO to show the correct SDO data.

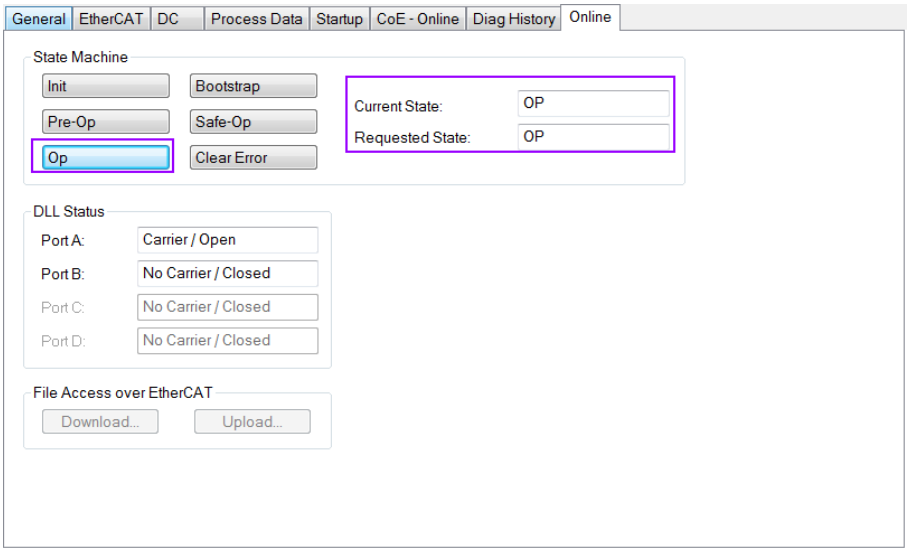
4. In order for the configuration data to be loaded after a device restart set the "Load factory default" to FALSE. It is always possible to return to the factory default setting by setting this value back to TRUE.
5. The "Save compare array counter" (F008:0C) shows how often configuration data has been stored to the local memory in the lifetime of the device.
6. If during power on the 0x2nxx:01 (n=0; 2) objects could not be correctly initialized with the saved position compare data then the "Initialization compare data error" (F008:08) flag shows TRUE.

   ATTENTION:
   The local memory only supports a limited number of save operations. Depending on the memory version once the save operation exceeds 10000 cycles it can no longer be guaranteed that data are reliably saved

or are still readable. Therefore the " Save compare data array " (F008:07) and the "Load factory default" (F008:03) should not be continuously set from the controlling application program.



Step 5: Set the EC4-ENC2IT back into OP mode.



9 Object Description and Parameterization

9.1 Standard Objects

Index 1000 Device type

Index (hex)	Name	Description	Data type	Flags	Default
1000:0	Device type	Device type of the EtherCAT slave	UINT32	RO	0x00000020

Index 1008 Device name

Index (hex)	Name	Description	Data type	Flags	Default
1008:0	Device name	Device name of the EtherCAT slave	STRING	RO	EC4-ENC2IT

Index 1009 Hardware version

Index (hex)	Name	Description	Data type	Flags	Default
1009:0	Hardware version	Hardware version of this device	STRING	RO	1.0.0 (or greater)

Index 100A Software version

Index (hex)	Name	Description	Data type	Flags	Default
100A:0	Software version	Software version of the EtherCAT slave	STRING	RO	1.0 .0 (or greater)

Index 1018 Identity

Index (hex)	Name	Description	Data type	Flags	Default
1018:0	Identity		UINT8	RO	0x04
1018:01	Vendor ID	Vendor ID of the EtherCAT slave	UINT32	RO	0x00494350
1018:02	Product code	Product code of the EtherCAT slave	UINT32	RO	0x00040E20
1018:03	Revision	Revision number of the EtherCAT slave	UINT32	RO	0x00000010
1018:04	Serial number	Serial number of the EtherCAT slave (not supported)	UINT32	RO	0x00000000

Index 10F1 Error settings

Index (hex)	Name	Description	Data type	Flags	Default
10F1:0	Error settings		UINT8	RO	0x02
10F1:01	Local error reaction	Not implemented	UINT32	RW	0x00000001
10F1:02	Sync error counter limit	For DC mode only: The Sync Error Counter is incremented with every missing Sync Management Event by three and decremented by one if an event is	UINT16	RW	0x0004

Index (hex)	Name	Description	Data type	Flags	Default
		received. If the Sync Error Counter exceeds this limit the system changes into the SAFEOP state with the 'Synchronization Lost' error. The Sync Error Counter is reset when the error was acknowledged.			

9.2 RxPDO Mapping Objects

"n" represents the channel number (0 to 1)

Index 0x16n0 ENC Control Ch.n (RxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
16n0:0	ENC Control Ch.n	Encoder control	UINT8	RO	0x09
16n0:01	Control__Gap1	Empty (1 Bit)	UINT32	RO	0x00000001
16n0:02	Control__Reset index latch value	Set index latch to zero (1 Bit)	UINT32	RO	0x70n00201
16n0:03	Control__Gap3	Empty (1 Bit)	UINT32	RO	0x00000001
16n0:04	Control__Set counter	Set encoder counter (1 Bit)	UINT32	RO	0x70n00401
16n0:05	Control__Gap5	Empty (1 Bit)	UINT32	RO	0x00000001
16n0:06	Control__Gap6	Empty (1 Bit)	UINT32	RO	0x00000001
16n0:07	Control__Gap7	Empty (2 Bit)	UINT32	RO	0x00000002
16n0:08	Control__Gap8	Empty (8 Bit)	UINT32	RO	0x00000008
16n0:09	Control__Set counter value	Assign encoder counter value (32 Bit)	UINT32	RO	0x70n00920

Index 0x16n1 Extern Latch Control Ch.n (RxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
16n1:0	Extern Latch Control Ch.n	Latch control	UINT8	RO	0x04
16n1:01	Control__Enable extern latch	Enable the extern DI channel latch (1 Bit)	UINT32	RO	0x70n10101
16n1:02	Control__Reset extern latch value	Set extern latch position to zero (1 Bit)	UINT32	RO	0x70n10201
16n1:03	Control__Gap3	Empty (6 Bit)	UINT32	RO	0x00000006
16n1:04	Control__Gap4	Empty (8 Bit)	UINT32	RO	0x00000008

Index 0x16n2 Compare Control Ch.n (RxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
16n2:0	Compare Control Ch.n	Compare control	UINT8	RO	0x08
16n2:01	Control__Enable compare	Enable compare trigger (1 Bit)	UINT32	RO	0x70n20101
16n2:02	Control__Set auto increment compare direction	Set direction of auto-increment compare (1 Bit)	UINT32	RO	0x70n20201
16n2:03	Control__Gap3	Empty (1 Bit)	UINT32	RO	0x00000001
16n2:04	Control__Gap4	Empty (1 Bit)	UINT32	RO	0x00000001
16n2:05	Control__Gap5	Empty (4 Bit)	UINT32	RO	0x00000004
16n2:06	Control__Gap6	Empty (8 Bit)	UINT32	RO	0x00000008
16n2:07	Control__Set first compare position	First compare position (32 Bit)	UINT32	RO	0x70n20720
16n2:08	Control__Set auto increment compare value	Auto increment compare value (32 Bit)	UINT32	RO	0x70n20820

Index 0x16n3 Array Compare Control Ch.n (RxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
16n3:0	Array Compare Control Ch.n	Array compare control	UINT8	RO	0x03
16n3:01	Enable compare	Enable the extern array position compare (1 Bit)	UINT32	RO	0x70n30101
16n3:02	Control__Gap2	Empty (7 Bit)	UINT32	RO	0x00000007
16n3:03	Control__Gap3	Empty (8 Bit)	UINT32	RO	0x00000008

9.3 TxPDO Mapping Objects

"n" represents the channel number (0 to 1)

Index 0x1An0 ENC StatusCh.n (TxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
1An0:0	ENC StatusCh.n	Encoder status	UINT8	RO	0x11
1An0:01	Status__Set counter done	Counter value setting finished (1 Bit)	UINT32	RO	0x60n00101
1An0:02	Status__Reset index latch value done	Index latch value set to zero finished	UINT32	RO	0x60n00201

Index (hex)	Name	Description	Data type	Flags	Default
		(1 Bit)			
1An0:03	Status__Signal of input A	Channel A input signal (1 Bit)	UINT32	RO	0x60n00301
1An0:04	Status__Signal of input B	Channel B input signal (1 Bit)	UINT32	RO	0x60n00401
1An0:05	Status__Signal of input C	Channel C input signal (1 Bit)	UINT32	RO	0x60n00501
1An0:06	Status__Signal of input I	Channel I input signal (1 Bit)	UINT32	RO	0x60n00601
1An0:07	Status__Enable extern latch done	Extern latch has been enabled (1 Bit)	UINT32	RO	0x60n00701
1An0:08	Status__Reset extern latch counter done	Extern latch counter has been set to zero (1 Bit)	UINT32	RO	0x60n00801
1An0:09	Status__Enable equidist compare done	Equidistant position compare has been enabled (1 Bit)	UINT32	RO	0x60n00901
1An0:0A	Status__Enable array compare done	Array position compare has been enabled (1 Bit)	UINT32	RO	0x60n00A01
1An0:0B	Status__Enable compare via DI done	Equidistant or array position compare has been enabled via digital input channel I (1 Bit)	UINT32	RO	0x60n00B01
1An0:0C	Status__Next compare position active	The next compare position is valid (1 Bit)	UINT32	RO	0x60n00C01
1An0:0D	Status__GapD	Empty (1 Bit)	UINT32	RO	0x00000001
1An0:0E	Status__GapE	Empty (1 Bit)	UINT32	RO	0x00000001
1An0:0F	Status__Sync error	Sync error (1 Bit)	UINT32	RO	0x60n00F01
1An0:10	Status__TxPDO Toggle	TxPDO Toggle (1 Bit)	UINT32	RO	0x60n01001
1An0:11	Status__Counter value	Encoder counter value (32 Bit)	UINT32	RO	0x60n01120

Index 0x1An1 Extern Latch Status Ch.n (TxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
1An1:0	Extern Latch Status Ch.n	Extern latch status	UINT8	RO	0x02
1An1:01	Status__Rising edge latched value	Extern latched encoder position triggered by rising edge (32 Bit)	UINT32	RO	0x60n10120

Index (hex)	Name	Description	Data type	Flags	Default
1An1:02	Status__Falling edge latched value	Extern latched encoder position triggered by falling edge (32 Bit)	UINT32	RO	0x60n10220

Index 0x1An2 Compare Trigger Status Ch.n (TxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
1An2:0	Compare Trigger Status Ch.n	Compare trigger status	UINT8	RO	0x01
1An2:01	Status__Get next compare position	Shows the next compare position (32 Bit)	UINT32	RO	0x60n20120

Index 0x1An3 Index Latch Status Ch.n (TxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
1An3:0	Index Latch Status Ch.n	Index latch status	UINT8	RO	0x01
1An3:01	Status__Index latched counter value	Index Latched encoder counter (32 Bit)	UINT32	RO	0x60n01220

Index 0x1An4 ENC VEL Status Ch.n (TxPDO-Map)

Index (hex)	Name	Description	Data type	Flags	Default
1An4:0	ENC VEL Status Ch.n	Encoder velocity status	UINT8	RO	0x01
1An4:01	Status__Vel_dP	Position difference per time interval for velocity calculation (16 Bit)	UINT32	RO	0x60n30110

9.4 Sync Manager Objects

Index 0x1C00 Sync manager type

Index (hex)	Name	Description	Data type	Flags	Default
1C00:0	Sync manager type	Using the sync managers	UINT8	RO	0x04
1C00:01	SubIndex 001	Sync-Manager Type Channel 1: Mailbox Write	UINT8	RO	0x01
1C00:02	SubIndex 002	Sync-Manager Type Channel 2: Mailbox Read	UINT8	RO	0x02
1C00:03	SubIndex 003	Sync-Manager Type Channel	UINT8	RO	0x03

Index (hex)	Name	Description	Data type	Flags	Default
		3: Process Data Write (Outputs)			
1C00:04	SubIndex 004	Sync-Manager Type Channel 4: Process Data Read (Inputs)	UINT8	RO	0x04

Index 0x1C12 RxPDO assign

Index (hex)	Name	Description	Data type	Flags	Default
1C12:0	RxPDO assign	SyncManager 2 assignment: PDO Assign Outputs	UINT8	RO	0x08
1C12:01	SubIndex 001	Default assignment: ENC Control Channel 0	UINT16	RW	0x1600
1C12:02	SubIndex 002	Default assignment: ENC Control Channel 0	UINT16	RW	0x1602
1C12:03	SubIndex 003	Default assignment: ENC Control Channel 1	UINT16	RW	0x1610
1C12:04	SubIndex 004	Default assignment: ENC Control Channel 1	UINT16	RW	0x1612
1C12:05	SubIndex 005	--	UINT16	RW	0x0000
1C12:06	SubIndex 006	--	UINT16	RW	0x0000
1C12:07	SubIndex 007	--	UINT16	RW	0x0000
1C12:08	SubIndex 008	--	UINT16	RW	0x0000

Index 0x1C13 TxPDO assign

Index (hex)	Name	Description	Data type	Flags	Default
1C13:0	TxPDO assign	SyncManager 3 assignment: PDO Assign Inputs	UINT8	RO	0x0A
1C13:01	SubIndex 001	Default assignment: ENC Status Channel 0	UINT16	RW	0x1A00
1C13:02	SubIndex 002	Default assignment: ENC Status Channel 0	UINT16	RW	0x1A02
1C13:03	SubIndex 003	Default assignment: ENC Status Channel 1	UINT16	RW	0x1A10
1C13:04	SubIndex 004	Default assignment: ENC Status Channel 1	UINT16	RW	0x1A12
1C13:05	SubIndex 005	--	UINT16	RW	0x0000
1C13:06	SubIndex 006	--	UINT16	RW	0x0000
1C13:07	SubIndex 007	--	UINT16	RW	0x0000
1C13:08	SubIndex 008	--	UINT16	RW	0x0000
1C13:09	SubIndex 009	--	UINT16	RW	0x0000
1C13:0A	SubIndex 010	--	UINT16	RW	0x0000

Index 0x1C32 Sync Manager (SM) output parameter

Index (hex)	Name	Description	Data type	Flags	Default
1C32:0	SM output parameter	Synchronization parameters for the outputs	UINT8	RO	0x20
1C32:01	Synchronization Type	Current synchronization mode: • 0: Free Run • 1: Synchronous without SM 2 event • 2: DC-Mode - Synchronous with SYNC0 Event • 3: DC-Mode - Synchronous with SYNC1 event	UINT8	RO	0x0001
1C32:02	Cycle Time	Cycle time (in ns): • Free Run: Cycle time of the local timer • Synchronous with SM 2 event: Master cycle time • DC mode: SYNC0/SYNC1 Cycle Time	UINT8	RO	0x00000000
1C32:04	Synchronization Types supported	Supported synchronization modes: • Bit 0 = 1: free run is supported • Bit 1 = 1: Synchron with SM 2 event is supported • Bit 2-3 = 01: DC mode is supported • Bit 4-5 = 10: Output shift with SYNC1 event (only DC mode)	UINT8	RO	0x8007
1C32:05	Minimum Cycle Time	Minimum cycle time (in ns)		RO	0x00000000
1C32:06	Calc and Copy Time	Minimum time between SYNC0 and SYNC1 event (in ns, DC mode only)		RO	0x00000000
1C32:08	Get Cycle Time	• 0: Measurement of the local cycle time is stopped • 1: Measurement of the local cycle time is started Set parameter to 1 in order to update the Cycle Time (1C32:02, 1C33:02) parameter with the maximum measured value		RW	0x0000
1C32:09	Delay Time	Time between SYNC1 event and output (in ns, DC mode only)		RO	0x00000000
1C32:0A	Sync0 Cycle Time			RW	0x00000000
1C32:0B	SM-Event Missed	Number of missed SM events in OPERATIONAL (DC mode only)		RO	0x0000

Index (hex)	Name	Description	Data type	Flags	Default
1C32:0C	Cycle Time Too Small	Cycle was not completed in time or the next cycle began too early		RO	0x0000
1C32:20	Sync Error	The synchronization was not correct in the last cycle (outputs were output too late; DC mode only)		RO	FALSE

Index 0x1C33 Sync Manager (SM) input parameter

Index (hex)	Name	Description	Data type	Flags	Default
1C33:0	SM input parameter	Synchronization parameters for the inputs	UINT8	RO	0x20
1C33:01	Synchronization Type	Current synchronization mode: • 0: Free Run • 1: Synchron with SM 3 Event (no outputs available) • 2: DC - Synchron with SYNC0 Event • 3: DC - Synchron with SYNC1 Event • 34: Synchron with SM 2 Event (outputs available)	UINT8	RO	0x0022
1C33:02	Cycle Time	Cycle time (in ns): • Free Run: Cycle time of the local timer • Synchronous with SM 2 event: Master cycle time • DC mode: SYNC0/SYNC1 Cycle Time	UINT8	RO	0x00000000
1C33:04	Synchronization Types supported	Supported synchronization modes: • Bit 0 = 1: free run is supported • Bit 1 = 1: Synchron with SM 2 event is supported • Bit 2-3 = 01: DC mode is supported • Bit 4-5 = 10: Output shift with SYNC1 event (only DC mode)	UINT8	RO	0x8007
1C33:05	Minimum Cycle Time	Minimum cycle time (in ns)		RO	0x00000000
1C33:06	Calc and Copy Time	Time between reading of the inputs and availability of the Inputs data for the master (in ns, only DC mode)		RO	0x00000000
1C33:08	Get Cycle Time	• 0: Measurement of the local cycle time is stopped		RW	0x0000

Index (hex)	Name	Description	Data type	Flags	Default
		• 1: Measurement of the local cycle time is started Set parameter to 1 in order to update the Cycle Time (1C32:02, 1C33:02) parameter with the maximum measured value			
1C33:09	Delay Time	Time between SYNC1 event and reading of the inputs (in ns, only DC mode)		RO	0x00000000
1C33:0A	Sync0 Cycle Time			RW	0x00000000
1C33:0B	SM-Event Missed	Number of missed SM events in OPERATIONAL (DC mode only)		RO	0x0000
1C33:0C	Cycle Time Too Small	Cycle was not completed in time or the next cycle began too early		RO	0x0000
1C33:20	Sync Error	The synchronization was not correct in the last cycle (outputs were output too late; DC mode only)		RO	FALSE

9.5 Position Compare Array

"n" represents the channel number (0; 1)
"k" represents the channel offset k= n*2
"xx" represents the position array index: any hex number between 0x00 to 0xC7
"y" represents the position array index: any decimal number between 0 to 199

Index 0x2kxx Ch.n Compare Pos.y

Index (hex)	Name	Description	Data type	Flags	Default
0x2kxx:0	Ch.n Compare Pos.xx	Array compare position parameters	UINT8	RO	0x02
0x2kxx:01	Position	The compare position at which to output a digital signal once the encoder counter reaches this position	INT32	RO	0x00000000
0x2kxx:02	DO trigger	Indicates whether or not to trigger a digital output once the encoder counter reaches the compare position value	BOOLEAN	RO	0x0

9.6 Input Data

"n" represents the channel number (0 to 1)

Index 0x60n0 ENC Inputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
60n0:0	Encoder input status Ch.n	Encoder status inputs	UINT8	RO	0x12
60n0:01	Set counter done	Assigning the counter a new value has completed. Indicates whether the "Set counter" (70n0:04) action was successful	BOOLEAN	RO	
60n0:02	Reset index latch value done	Indicates that the index latch value has been set to zero	BOOLEAN	RO	
60n0:03	Signal of input A	Signal of input A	BOOLEAN	RO	
60n0:04	Signal of input B	Signal of input B	BOOLEAN	RO	
60n0:05	Signal of input C	Signal of input C	BOOLEAN	RO	
60n0:06	Signal of input I	Signal of input I	BOOLEAN	RO	
60n0:07	Enable extern latch done	Indicates whether the external latch has been enabled	BOOLEAN	RO	
60n0:08	Reset extern latch value done	Indicates whether the external latch counter has been reset	BOOLEAN	RO	
60n0:09	Enable equidist compare done	Indicates whether the equidistant position compare function has been enabled	BOOLEAN	RO	
60n0:0A	Enable array compare done	Indicates whether the array position compare function has been enabled	BOOLEAN	RO	
60n0:0B	Enable compare via DI done	Indicates whether the equidistant or array position compare function has been enabled via digital input channel I. This parameter turns true when all three condition has been met: • "Activate compare	BOOLEAN	RO	

Index (hex)	Name	Description	Data type	Flags	Default
		via DI"= Enabled (0x80n1:03, n= 0;1) • Either "Enable equidist compare done" (0x60n0:09) or "Enable array compare done" (0x60n0:0A) is TRUE • Channel (I) has a digital input signal			
60n0:0C	Next compare position active	Indicates whether the "Get next compare position" (0x60n2:01) is valid.	BOOLEAN	RO	
60n0:0F	Sync error	The Sync error bit is only required for DC mode. It indicates whether a synchronization error has occurred during the previous cycle	BOOLEAN	RO	
60n0:10	TxPDO Toggle	The TxPDO toggle is toggled by the slave when the data of the associated TxPDO is updated	BOOLEAN	RO	
60n0:11	Counter value	The encoder counter value	INT32	RO	
60n0:12	Index Latched counter value	The index latched counter value. The trigger condition (falling or rising edge) has to be set via "C signal polarity" (80n0:03). A latch event is generated every time when the trigger condition has been met.	INT32	RO	

Index 0x60n1 Extern Latch Inputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
60n1:0	Extern Latch Inputs Ch.n	Extern latch status inputs	UINT8	RO	0x02

Index (hex)	Name	Description	Data type	Flags	Default
60n1:01	Rising edge latched value	Latched encoder position triggered by the rising edge of "I" signal	INT32	RO	
60n1:02	Falling edge latched value	Latched encoder position triggered by falling edge of "I"signal	INT32	RO	

Index 0x60n2 Compare Trigger Input Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
60n2:0	Compare Trigger Input Ch.n	Compare trigger status inputs	UINT8	RO	0x01
60n2:01	Get next compare position	Indicates the next compare position at which an output will be triggered	INT32	RO	

Index 0x60n3 ENC VEL Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
60n3:0	ENC VEL Ch.n	Encoder velocity	UINT8	RO	0x01
60n3:01	Vel_dP	Position difference per time interval for velocity calculation	INT16	RO	

9.7 Output Data

"n" represents the channel number (0 to 1)

Index 0x70n0 ENC Outputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
70n0:0	ENC Outputs Ch.n		UINT8	RO	0x09
70n0:02	Reset index latch value	Set index latch value to zero	BOOLEAN	RO	FALSE
70n0:04	Set counter	Assign encoder counter a new counter value. • By setting this Boolean from FALSE to TRUE the counter register will be assigned the value of parameter 70n0:09	BOOLEAN	RO	FALSE

Index (hex)	Name	Description	Data type	Flags	Default
		("Set counter value")			
70n0:09	Set counter value	Counter value which will be assigned to the encoder counter register (see 70n0:04)	INT32	RO	0

Index 0x70n1 Extern Latch Outputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
70n1:0	Extern Latch Outputs Ch.n		UINT8	RO	0x02
70n1:01	Enable extern latch	Enable the external "I" signal latch • By setting this Boolean from FALSE to TRUE the hardware "I" signal latch function is enabled. The encoder value (60n0:11) will be latched when the "I" input signal rises or falls • By setting this variable to FALSE the extern latch function will be disabled and the latched counter value registers (60n1:01; 60n1:02) are reset to zero	BOOLEAN	RO	FALSE
70n1:02	Reset extern latch value	Set the extern latch value to zero • By setting this Boolean from FALSE to TRUE both extern latch parameters (60n1:01; 60n1:02) are reset to zero	BOOLEAN	RO	FALSE

Index 0x70n2 Compare Outputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
70n2:0	Compare Outputs Ch.n		UINT8	RO	0x08
70n2:01	Enable compare	Enable the equidistant position compare output trigger function	BOOLEAN	RO	FALSE

Index (hex)	Name	Description	Data type	Flags	Default
		• By setting this Boolean from FALSE to TRUE the compare function will be enabled • By setting this variable to FALSE the extern latch function will be disabled • It is suggested to first set all the compare parameters (70n2:02, 70n2:07, 70n2:08) before enabling the compare trigger function • If the counter has been set to zero while the compare function is active, then the compare function has to be first disabled and then again enabled in order for the compare value to be reset			
70n2:02	Set auto increment compare direction	Set the auto-incremental direction for the compare value • 0 - positive direction • 1- negative direction	BOOLEAN	RO	FALSE
70n2:07	Set first compare position	The first compare position	INT32	RO	0
70n2:08	Set auto increment compare value	The next compare position will be automatically calculated by adding the incremental value to the current compare position (70n2:07) • Disable the auto-increment compare function by setting this parameter to zero	INT32	RO	0

Index 0x70n3 Array Compare Outputs Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
70n3:0	Array Compare Outputs Ch.n		UINT8	RO	0x01
70n3:01	Enable compare	Enable the array position compare output trigger function • By setting this Boolean from FALSE to TRUE the compare function will be enabled • By setting this variable to FALSE the extern latch function will be disabled • It is important to first set all the compare position values via the CoE (0x2nxx:01, n=0; 2) before enabling the compare trigger function • If the counter has been set to zero while the compare function is active, then the compare function has to be first disabled and then again enabled in order for the compare value to be reset	BOOLEAN	RO	FALSE

9.8 Configuration Data

ENC Parameter

Index (hex)	Name	Description	Data type	Flags	Default
3000	Repeat signal	Extend channel 0 signal (encoder input A,B,C) to channel 1: • 0: Disable • 1: Enable	UINT8	RW	0x00

Index 0x80n0 ENC Settings Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
80n0:0	ENC Settings Ch.n	Encoder settings	UINT8	RO	0x0A
80n0:01	A signal polarity	Polarity of A input signal	DT0803EN01	RW	0x01 ("Active high")
80n0:02	B signal polarity	Polarity of B input signal	DT0803EN01	RW	0x01 ("Active high")
80n0:03	C signal polarity	Polarity of C input signal	DT0803EN01	RW	0x01 ("Active high")
80n0:04	I signal polarity	Polarity of extern latch "I" input signal NOTE: The trigger level for extern latch can not be set for each channel individually. Both channel need to be set to the same trigger level.	DT0803EN01	RW	0x01 ("Active high")
80n0:05	I channel trigger mode	Extern latch setting: • Reset encoder counter or • Latch encoder counter	DT0804EN01	RW	0x01 ("Latch encoder counter ")
80n0:09	Counting mode	Counter mode selection: • CW/CCW, • Pulse/Direction, • Quadrant	DT0801EN08	RW	0x03 ("Quadrant counting mode")
80n0:0A	Low pass filter	Low pass filter setting	DT0802EN08	RW	0x00 ("4MHz AB Phase: 6MHz (filter disabled)")

"n" represents the channel number (0 to 1)

Index 0x80n1 ENC Settings Ch.n

Index (hex)	Name	Description	Data type	Flags	Default
80n1:0	Compare Setting Ch.n	Compare settings	UINT8	RO	0x0B
80n1:01	Compare trigger pulse width	Pulse width of the compare trigger output	UINT16	RW	0x32 (50)
80n1:02	Compare DO trigger signal type	Do compare trigger output signal type (Active high or active low) • Normal (0) Depends on the external wiring: Can either be active high or active low. • Reverse (1)	DT0806EN01 (BIT1)	RW	0x00 ("Normal")
80n1:03	Activate compare via DI	"Enable" indicates that the DI channel is being used for enabling / disabling the compare mode	DT0805EN01 (BIT1)	RW	0x00 ("Disable")
80n1:04	Keep compare trigger output	"Enable" indicates that the compare output can still be triggered when the EC4-ENC2IT is disconnected from master NOTE: After enabling this function, if the module is disconnected from master, the compare function can only be disabled via the digital input channel (I)	DT0805EN01 (BIT1)	RW	0x00 ("Disable")
80n1:0A	Array compare start index	• Used for position compare array: • The start index is fixed at zero	UINT16	R	0x0000
80n1:0B	Array compare end index	Used for position compare array: • Sets the number of compare positions to be used for the compare process • The first compare position always has to be stored in the first object 0x2k00 (k=0 for channel 0, k=2 for channel 1)	UINT16	RW	0x0000

"n" represents the channel number (0 to 1)

Index 0x8100 Time Interval Settings

Index (hex)	Name	Description	Data type	Flags	Default
8100:0	Time Interval Settings		UINT8	RO	0x03
8100:01	Basic Multiplier	The unit time is 0.5 ms Base Time = Basic Multiplier * 0.5 ms	UINT8	RW	0x02
8100:02	Ch0 Multiplier	Ch0 Time Interval = Base Time * Ch0 Multiplier	UINT8	RW	0x01
8100:03	Ch1 Multiplier	Ch1 Time Interval = Base Time * Ch0 Multiplier	UINT8	RW	0x01

9.9 Configuration Parameters Storage

Index 0xF008 Internal EEPROM

Index (hex)	Name	Description	Data type	Flags	Default
F008:0	Internal EEPROM	Storing CoE parameters to the internal EEPROM.	UINT8	RO	0x05
F008:01	Code Word	Password for saving CoE configuration data to the EEPROM Password: 0x12345678	UINT32	RW	0x00000000
F008:02	Save configuration counter	Shows the how often configuration data has been saved to the local non-volatile memory. Due to hardware restrictions a maximum number of 10000 save cycle times are supported.	UINT16	RO	0x0000
F008:03	Load factory default	Load factory default configuration immediately after power on. • By setting this parameter to FALSE the user set configuration data (0x8000 to 0x8020) will be loaded after power on	BOOLEAN	RW	TRUE
F008:04	Save configuration data	Save all configuration setting to local non-volatile memory. • Set to TRUE in order to save the configuration data (0x8000 to 0x8011) to the memory of the EC4-ENC2IT	BOOLEAN	RW	FALSE
F008:05	Save error encountered	Indicates whether data has been successfully written to memory	BOOLEAN	RO	FALSE
F008:06	Initialization config data error	Indicates whether an error occurred while reading configuration	BOOLEAN	RO	FALSE

Index (hex)	Name	Description	Data type	Flags	Default
		data (0x8000 to 0x8011) from the internal EEPROM after the device has been switched on			
F008:07	Save compare data array	Save all position compare array values to the local non-volatile memory. Set this parameter to TRUE in order to save the compare array data (0x2000 to 0x22C7) to the memory of the EC4-ENC2IT. ATTENTION: The saving action does takes some time which can exceed the EtherCAT timeout. If an timeout occurs the TwinCAT does not update the 0xF008 object. In this case restart TwinCAT to force an update of the 0xF008 object members.	BOOLEAN	RW	FALSE
F008:08	Initialization compare data error	Indicates whether an error occurred while reading compare array data (0x2000 to 0x22C7) from the internal EEPROM after the device has been switched on	BOOLEAN	RO	FALSE
F008:0C	Save compare array counter	Shows the how often compare array data has been saved to the local non-volatile memory. Due to hardware restrictions a maximum number of 10000 save cycle times are supported.	UINT16	RO	0x0000