

**KOLLMORGEN**

**Seidel**

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**CANopen communication profile  
for servo amplifiers of the  
SERVOSTAR™ 400/600 series**

Technical Description, Commissioning Instructions

Edition 08.01

**Previous editions**

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**Technical changes to improve the performance of the equipment  
may be made without prior notice !**

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**Abbreviations used in this manual**

The abbreviations used in this manual are explained in the table below.

<b>Abbrev.</b>	<b>Meaning</b>
BTB/RTO	Ready to operate (standby)
COB-ID	Communication Object Identifier
EEPROM	Electrically erasable/programmable memory
EMC	Electromagnetic compatibility
ISO	International Standardization Organization
LED	Light-emitting diode
MB	Megabyte
NSTOP	Limit switch for CCW (left) rotation
PC	Personal Computer with 80x86 processor
PDO	Process Data Object

<b>Abbrev.</b>	<b>Meaning</b>
PSTOP	Limit switch for CW (right) rotation
RAM	Volatile memory
RES	Resolver
ROD	Incremental position encoder
RPDO	Receive PDO
SDO	Service Data Object
PLC	Programmable logic controller
SW/SETP.	Setpoint
TPDO	Transmit PDO

**Symbols used in this manual**

	danger to personnel from electricity and its effects		general warning general instructions mechanical hazard
	see Chapter ... (cross-reference)		special emphasis

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## I General

### I.1 About this manual

This manual describes the commissioning, range of functions and software protocol of the SERVOSTAR™ 400/600 servo amplifiers with the CANopen communication profile. It forms part of the complete documentation for the SERVOSTAR™ 400/600 family of servo amplifiers.

The installation and commissioning of the servo amplifier, as well as all standard functions, are described in the corresponding installation manuals.

#### Other parts of the complete documentation for the digital servo amplifier series:

Title	Publisher
Online-Help for commissioning software DRIVE.EXE	Danaher Motion
Assembly/Installation/Commissioning Instructions SERVOSTAR™ 400/600	Danaher Motion

#### Additional documentation:

Title	Publisher
CAN Application (CAL) for Industrial Applications	CiA e.V.
Draft Standards 301 (from Version 4.0), 401	CiA e.V.
CAN Specification Version 2.0	CiA e.V.
ISO 11898 ... Controller Area Network (CAN) for high-speed communication	

This manual is intended for the following qualified personnel:



**Wiring:** *Professionally qualified electrical technicians*  
**Programming:** *Software developers, project-planners*

Training and familiarization courses are available on request.

### I.2 Application of this manual

Specific examples for individual chapters can be found in the applications section (⇒ VI.1 and VI.2) of this manual.

### I.3 Permitted use (“Use as directed”) of the CANopen interface

Please observe the chapter “Permitted use” in the commissioning manual for the servo amplifier.

The interface is a component part of the SERVOSTAR™ 400/600 series of digital servo amplifiers. The CANopen interface serves only for the connection of the servo amplifier to a master via the CAN-bus.

The servo amplifiers are components that are built into electrical apparatus or machinery, and can only be commissioned and operated as integral components of such apparatus or machinery.



***We can only guarantee the conformity of the servo amplifier with the following standards for industrial areas when the components that we specify are used, and the installation regulations are followed:***

<i>EC EMC Directive</i>	<i>89/336/EEC</i>
<i>EC Low-Voltage Directive</i>	<i>73/23/EEC</i>

## I.4 Basic features implemented through CANopen

When working with the position controller that is integrated in SERVOSTAR™ 400/600 digital servo amplifiers, the following functions are available:

### **Setup and general functions:**

- homing, set reference point
- jogging, with a variable speed
- provision of a digital setpoint for speed and torque control

### **Positioning functions:**

- execution of a motion task from the motion block memory of the servo amplifier
- execution of a direct motion task
- absolute trajectory

### **Data transfer functions:**

- transmit a motion task to the motion block memory of the servo amplifier  
A motion task consists of the following elements:
  - » position setpoint (absolute task) or path setpoint (relative task)
  - » speed setpoint
  - » acceleration time, braking time, rate-of-change/jolt limiting (in preparation)
  - » type of motion task (absolute/relative)
  - » number of a following task (with or without pause)
- read a motion task from the motion block memory of the servo amplifier
- read actual values
- read the error register
- read the status register
- read/write control parameters

## I.5 System requirements

- servo amplifier SERVOSTAR™ 400/600
- master station with a CAN-bus interface (e.g. PC with CAN interface)

## I.6 Transmission rate and procedure

- bus connection and bus medium: CAN-standard ISO 11898 (CAN high-speed)
- transmission rate: max. 1Mbit/s  
possible settings for the servo amplifier:  
10, 20, 50, 100, 125, 250, 333, 500 (default), 666, 800, 1000 kbit/s

### I.7 Bus cable

In accordance with ISO 11898 you should use a bus cable with a characteristic impedance of 120Ω. The usable cable length for reliable communication is reduced as the transmission rate is increased. The following values that we have measured can be used as a guide. They should not, however, be interpreted as limiting values:

<b>Cable data:</b>	characteristic impedance	100 ... 120Ω
	cable capacitance	max. 60 nF/km
	lead resistance (loop)	159.8 Ω/km

**Cable length, dependent on the transmission rate**

Transmission rate: kbit/s	Max. cable length: m
1000	20
500	70
250	115

Longer transmission distances may be achieved with a lower cable capacitance (max. 30 nF/km) and lower lead resistance (loop, 115 Ω/km).

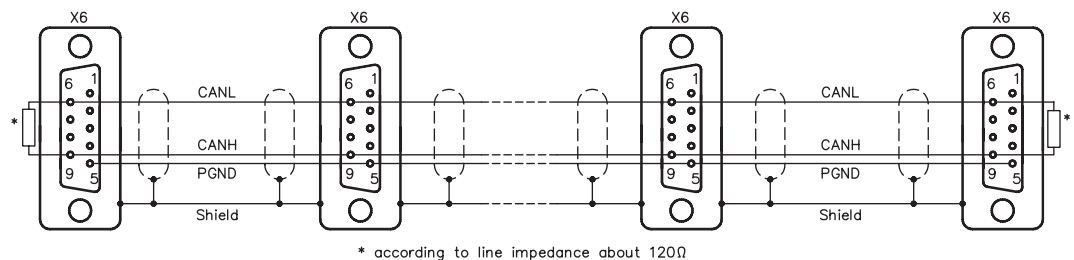
(characteristic impedance 150 ± 5Ω ⇒ termination resistance 150 ± 5Ω).

For EMC reasons, the SubD connector housing must fulfill the following requirements:

- metal or metallic housing
- provision for connecting the cable shielding in the housing, with a large contact area.

The Seidel company can supply special clamp-sleeve connectors (Order No. 90650), that can easily be made up for bus operation.

In addition, an adapter can be used for the option slot (Option -2CAN-, Order No. 101174), which provides options for pass-through wiring and the attachment of 120Ω termination resistors. The pin assignments correspond to the CANopen standard DS 301.



### I.8 Response to BUSOFF communication faults

The communication fault BUSOFF is directly monitored and signalled by Level 2 (CAN controller). This message may have various causes.

A few examples:

- telegrams are transmitted, although there is no other CAN node connected
- CAN nodes have different transmission rates
- the bus cable is faulty
- faulty cable termination causes reflections on the cable.

A BUSOFF is only signalled by the SERVOSTAR™ 400/600 if another CAN node is connected and at least one Object was successfully transmitted to start off with. The BUSOFF condition is signalled by the error message F23. If the output stage is enabled for the execution of a motion task at the moment when this fault occurs, then the drive is braked to a stop, using the emergency stop ramp, and the output stage is disabled.

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## II Installation / Commissioning

### II.1 Assembly, Installation



*Only install and wire up the equipment in a de-energized condition, i.e. neither the mains/line supply voltage nor the 24V auxiliary voltage nor the operating voltage of any other connected equipment may be switched on.*

*Take care that the switchgear cabinet is safely disconnected (lockout, warning signs etc.). The individual voltages are switched on for the first time during commissioning. Never disconnect the electrical connections to the servo amplifier while it is live. This could destroy the electronics.*

*Residual charges in the capacitors can still have dangerous levels several minutes after switching off the supply power. Measure the voltage in the DC-link circuit and wait until the voltage has fallen below 40V.*

*Even when the motor is not running, power and control cables can still be live.*

- Assemble the servo amplifier as described in the installation instructions for SERVOSTAR™ 400/600. Observe all safety instructions in the installation instructions that belong to the servo amplifier. Follow all the notes on mounting position, ambient conditions, wiring, and fusing.
- The connections for the motor, controls and power, as well as advice on system layout for EMC conformance, can be found in the installation instructions for the servo amplifier.

#### II.1.1 Connection methods

**Supply power, motor, analog setpoints, digital control signals, CAN connection**  
see installation instructions for SERVOSTAR™ 400/600.

#### II.1.2 Setting the station address

The station address (instrument address on the CAN-Bus) for the servo amplifier can be set in three different ways:

- by using the pushbuttons on the front panel  
(see installation instructions for SERVOSTAR™ 400/600)
- In the commissioning software DRIVE.EXE, on the screen page “Basic settings”
- Using the ASCII command sequence: ADDR nn ⇒ SAVE ⇒ COLDSTART (nn = address)

The address range can be expanded from 1 ... 63 to 1 ... 127 by using the ASCII-Object MDRV.

#### II.1.3 Setting the transmission rate

The CAN transmission rate can be set in three different ways:

- by using the pushbuttons on the front panel  
(see installation instructions for SERVOSTAR™ 400/600)
- In the commissioning software DRIVE.EXE, on the screen page “Basic settings”
- Using the ASCII command sequence: CBAUD bb ⇒ SAVE ⇒ COLDSTART  
(bb = transmission rate in kbit/s)

Possible transmission rates are: 20, 50, 100, 125, 250, 333, 500 (default), 666, 800, 1000 kbit/s.

## II.2

## Commissioning



*Only professional personnel with extensive knowledge of control and drive technology are allowed to commission the servo amplifier.*

Check assembly /  
installation

Check that all the safety instructions in the installation instructions for the servo amplifier and this manual have been observed and implemented. Check the setting for the station address.

Connect PC, start  
commissioning software

Use the commissioning software DRIVE.EXE to set the parameters for the servo amplifier.

Commission  
the basic functions

Start up the basic functions of the servo amplifier and optimize the current and speed controllers. This section of the commissioning is described in detail in the QuickStart manual.

Save  
parameters

When the parameters have been optimized, save them in the servo amplifier.

Start up bus  
communication

The altered parameters will only become effective after a software-reset (warm boot). To do this, change to the screen page "Status" and operate the reset button.

Requirement: the software protocol described in Chapter IV must be implemented in the master.

Adjust the transmission rate of the SERVOSTAR™ 400/600 to match the master.

Test the  
communication

Recommendation : request the Emergency Object.



**Caution !**

*Make sure that any unintended movement of the drive cannot endanger machinery or personnel.*

Commission the  
position controller

Commission the position controller, as described in the QuickStart manual.

### III CANopen communication profile

This chapter describes the basic services and Communication Objects of the CANopen communication profile DS 301, which are used in the SERVOSTAR™ 400/600.

**It is assumed that the basic operating functions of the communication profile are known, and available as reference documentation.**

#### III.1 General description of CAN

The transmission method that is used here is defined in ISO 11898 (Controller Area Network CAN for high-speed communication).

The Layer-1/2 protocol (Physical Layer/Data Link Layer) that is implemented in all CAN modules provides, amongst other things, the requirements for data.

Data transport or data request is made by means of a data telegram (Data Frame) with up to 8 bytes of user data, or by a data request telegram (Remote Frame).

Communication Objects are labelled by an 11-bit Identifier (ID) that also determines the priority of Objects.

A Layer-7 protocol (Application Layer) was developed, to decouple the application from the communication. The service elements that are provided by the Application Layer make it possible to implement an application that is spread across the network. These service elements are described in the CAN Application Layer (CAL) for Industrial Applications.

The communication profile CANopen and the drive profile are mounted on the CAL.

The basic structure of a Communication Object is shown in the following diagram:

S O M	COB-ID	R T R	CTRL	Data Segment	CRC	A C K	EOM
-------------	--------	-------------	------	--------------	-----	-------------	-----

SOM	Start of message
COB-ID	COB Identifier (11-bit)
RTR	Remote Transmission Request
CTRL	Control Field (e.g. Data Length Code)
Data Segment	0 ... 8 byte (Data-COB) 0 byte (Remote-COB)
CRC	Cyclic Redundancy Check
ACK	Acknowledge slot
EOM	End of message



### III.3.1 Basic data types

#### III.3.1.1 Unsigned Integer

Data in the basic data type UNSIGNEDn define exclusively positive integers.

The value range is from  $0 \dots 2^n - 1$ . The bit sequence  $b = b_0 \dots b_{n-1}$  defines the value

$$\text{UNSIGNED}_n(b) = b_{n-1} 2^{n-1} + \dots + b_1 2^1 + b_0 2^0$$

Example: the value  $266 = 10A_h$  is transmitted in the data type UNSIGNED16, in the form of two octets (1<sup>st</sup> octet =  $0A_h$ , 2<sup>nd</sup> octet =  $01_h$ ).

Transmission syntax for the data type UNSIGNEDn

Octet number	1.	2.	3.	4.	5.	6.	7.	8.
UNSIGNED8	$b_7..b_0$							
UNSIGNED16	$b_7..b_0$	$b_{15}..b_8$						
UNSIGNED24	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$					
UNSIGNED32	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$				
UNSIGNED40	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$			
UNSIGNED48	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$		
UNSIGNED56	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$	$b_{55}..b_{48}$	
UNSIGNED64	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$	$b_{55}..b_{48}$	$b_{63}..b_{56}$

#### III.3.1.2 Signed Integer

Data in the basic data type INTEGERn define both positive and negative integers.

The value range is from  $-2^{n-1} - 1 \dots 2^{n-1} - 1$ . The bit sequence  $b = b_0..b_{n-1}$  defines the value

$$\text{INTEGER}_n(b) = b_{n-2} 2^{n-2} + \dots + b_1 2^1 + b_0 2^0 \text{ with } b_{n-1} = 0$$

Negative numbers are represented as 2's complement, which means:

$$\text{INTEGER}_n(b) = -\text{INTEGER}_n(b) - 1 \text{ with } b_{n-1} = 1$$

Example: the value  $-266 = \text{FEF6}_h$  is transmitted in the data type INTEGER16, in the form of two octets (1<sup>st</sup> octet =  $\text{F6}_h$ , 2<sup>nd</sup> octet =  $\text{FE}_h$ ).

Transmission syntax for the data type INTEGERn

Octet number	1.	2.	3.	4.	5.	6.	7.	8.
INTEGER8	$b_7..b_0$							
INTEGER16	$b_7..b_0$	$b_{15}..b_8$						
INTEGER24	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$					
INTEGER32	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$				
INTEGER40	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$			
INTEGER48	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$		
INTEGER56	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$	$b_{55}..b_{48}$	
INTEGER64	$b_7..b_0$	$b_{15}..b_8$	$b_{23}..b_{16}$	$b_{31}..b_{24}$	$b_{39}..b_{32}$	$b_{47}..b_{40}$	$b_{55}..b_{48}$	$b_{63}..b_{56}$

### III.3.2 Mixed data types

Mixed data types combine basic data types (INTEGERn, UNSIGNEDn, REAL). Two types of mixed data are distinguished:

- STRUCT  
This data type is composed of elements with different data types.
- ARRAY  
This data type is composed of elements of the same data type.

### III.3.3 Extended data types

Extended data types are derived from basic data types and mixed data types. The types of extended data that are supported are defined below.

#### III.3.3.1 Octet String

The data type *OCTET\_STRING* is defined with the data type *ARRAY*. *Length* is the length of the octet string.

ARRAY[length] OF UNSIGNED8                      OCTET\_STRINGlength

#### III.3.3.2 Visible String

The data type *VISIBLE\_STRING* can be defined with the data type *UNSIGNED8* or the data type *ARRAY*. Permissible values are 00<sub>h</sub> and the range from 20<sub>h</sub> to 7E<sub>h</sub>. The data are interpreted as 7 bit ASCII code (as per ISO 646-1973(E)). *Length* is the length of the visible string.

UNSIGNED8    VISIBLE\_CHAR  
ARRAY[length] OF VISIBLE\_CHAR                      VISIBLE\_STRINGlength

### III.4 Communication Objects

Communication Objects are described with the help of service elements and protocols. Two basic types of service elements are distinguished:

- Unconfirmed services
- Confirmed services

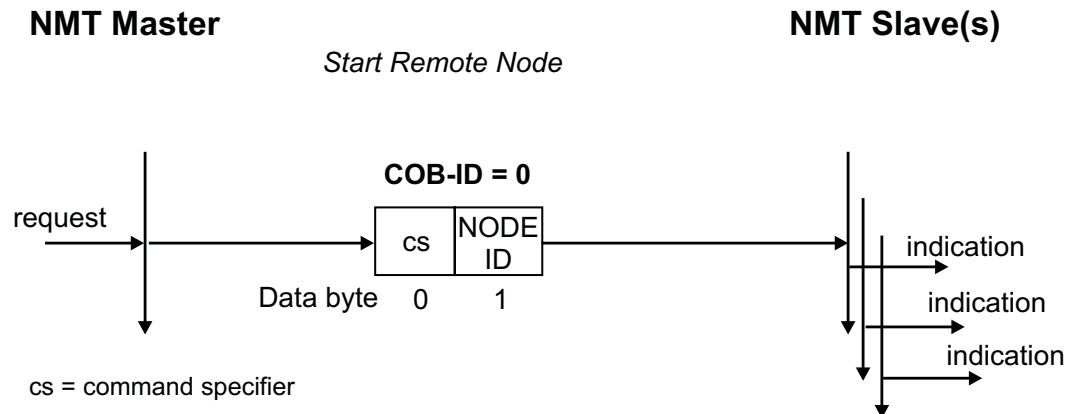
All services require faultless operation of the *Data Link* and *Physical Layer*.

SERVOSTAR™ 400/600 supports Communication Objects that are described in detail in the following sections:

- Network Management Objects (NMT)
- Synchronization Object (SYNC)
- Time Stamp Object (TIME)
- Emergency Object (EMCY)
- Process Data Object (PDO)
- Service Data Object (SDO)
- Nodeguard

### III.4.1 Network Management Objects (NMT)

The NMT telegram looks like this:



The drive supports the following network management functions:

- cs = 129, reset node:** causes a cold-start of the drive.  
This deletes all parameters saved in the RAM and loads the values stored in the EEPROM or the default values.
- cs = 1, start remote node:** starts the CAN node.  
I.e. the PDOs of the drive are enabled for operation.  
From this moment, transmit-PDOs will be transmitted under event-control, and cyclical process data operation can commence.
- cs = 2, stop remote node:** stops the CAN node, I.e. the drive no longer responds to any received PDOs or transmits any PDOs.

### III.4.2 Synchronization Object (SYNC)

This is a periodic *Broadcast Object* and provides the basic clock for the bus. SYNC has a high priority, to ensure constant time intervals. The usage of this protocol is explained in the application section of this manual.

### III.4.3 Time-Stamp Object (TIME)

This communication Object is not supported by SERVOSTAR™.

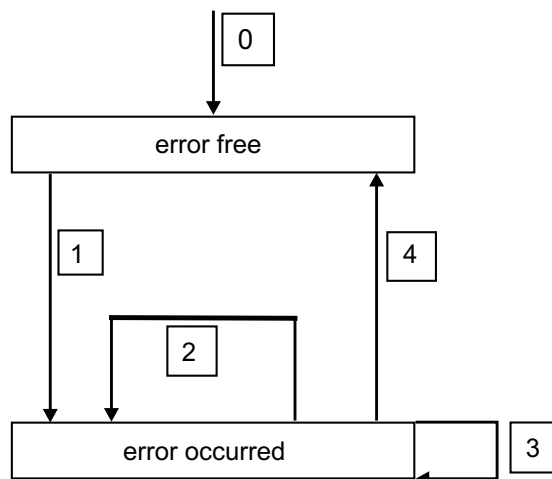
### III.4.4 Emergency Object (EMCY)

EMCY is event-triggered and generated by an internal fault/error situation. This Object is transmitted afresh for every error. Since the error codes are device-dependent, they are described in the Chapter *CANopen Drive Profile* (⇒ chapter IV).

### III.4.4.1 Application of the Emergency Object

The reaction in the event of an error or fault depends on the error class and is therefore variable. For this reason, the reaction is described with the aid of an error status machine. The error conditions *error-free* and *error occurred* are distinguished. The following transitions are defined:

0. After initialization, the error-free status is taken up if no errors are detected. No error signal is generated in this condition.
1. The SERVOSTAR™ detects an internal error and indicates this in the first three bytes of the emergency telegram (*error code* in Bytes 0,1 and *error register* in Byte 2). Since the SERVOSTAR™ can distinguish between different types of error, Byte 3 of the manufacturer-specific error field is used to indicate the error category.
2. One error has been reset, but not all. The *EMCY* telegram contains error code 0000<sub>h</sub> and the error register indicates the remaining errors that are present. The manufacture-specific area is set to zero.
3. A new error has occurred. The SERVOSTAR™ remains in the *error status* and transmits an *EMCY* Object with the corresponding error code. The new error code is entered in Bytes 0 and 1.
4. All errors have been reset. The *EMCY* telegram contains the error code 0000<sub>h</sub>, the error register does not indicate any other errors. The manufacture-specific area is set to zero.



### III.4.4.2 Composition of the Emergency Object

The Emergency Object is composed of 8 bytes, divided as follows:

Byte	0	1	2	3	4	5	6	7
Content	Emergency error code (⇒ IV.1)		Error register (Object 1001 <sub>h</sub> )	Category	Reserved			

If an Emergency Object is generated, the error condition is then signaled to the status machine (*error free* / *error occurred*) by the generation of a second Emergency Object. Only the first four bytes are relevant in this case (*Emergency Error code* , *Error register*, *Category*). Byte 0/1 contains the *Error Reset code* (0000<sub>h</sub>) and Byte 2 indicates if a possible further error is present. If the error register contains 00<sub>h</sub>, the error status is *error-free*.

Byte 3 contains the category. The interpretations of the error numbers (*error code*) and the error categories are described in the section *Emergency Messages* (⇒ IV.1). The error register is defined through Object 1001<sub>h</sub> *Error register*.

### III.4.5 Service Data Object (SDO)

SDOs are used to implement access to the Object Dictionary. The SDOs are required for parameterization and for status polling. Access to an individual Object is made with a multiplexer via the Index and Sub-index of the Object Dictionary. The following communication protocols are supported by SERVOSTAR™ 400/600:

- Initiate SDO Download Protocol
- Download SDO Segment Protocol
- Initiate SDO Upload Protocol
- Upload SDO Segment Protocol
- Abort SDO Transfer Protocol

The definitions of the individual communication services and protocols can be found in DS301. Examples of the usage of SDOs can be found in the application section of this manual.



**Note!**

**Since an SDO is a confirmed service, the system must always wait for the SDO response telegram before it is allowed to transmit a new telegram.**

#### III.4.5.1 Composition of the Service Data Object

An SDO consists of the following components:

Byte	1	2	3	4	5	6	7	8
Content	r/w	Index		Sub-index	Data			

1. The control byte (Byte 1):  
The control byte determines whether the SDO has write or read access to the entry in the Object Dictionary. A description of the complete Object Dictionary for SERVOSTAR™ 400/600 can be found in Section VI.3.

Data exchange with the SERVOSTAR™ 400/600 is governed by the *CMS multiplexed domain protocols* standard, as described in the CAN standard DS 202.

To read data, the control byte must be written in the manner shown below:

Bit	7	6	5	4	3	2	1	0
Content	ccs*=1		X	n*		e*	s*	

\* ccs ⇒ client command specifier (ccs = 1 ⇒ initiate download request)

n ⇒ only valid for e = s = 1

if this is so, n contains the number of bytes that do not contain data

X ⇒ free data

So, with four bytes in the user data field, a value of 0010 0011 (binary) or 23<sub>n</sub> will be transmitted in the control byte.

The servo amplifier sends back a corresponding response byte:

Bit	7	6	5	4	3	2	1	0
Content	scs*=3			X				

\* scs ⇒ server command specifier (scs = 3 ⇒ initiate download response)

X ⇒ free data



### III.4.5.6 Abort SDO Protocol

The Abort SDO protocol breaks off SDO transmission, and indicates the error that caused the break in transmission through an abort code (error code). The error code is in the format of an UNSIGNED32 value. The following table shows possible reasons for an abort SDO.

<b>Abort Code</b>	<b>Description</b>
0503 0000 <sub>h</sub>	<i>Toggle bit</i> was not toggled
0504 0000 <sub>h</sub>	<i>Timeout</i> for SDO protocol
0504 0001 <sub>h</sub>	Client/server command - invalid or unknown Identifier
0504 0002 <sub>h</sub>	Unrecognized block size (block mode only)
0504 0003 <sub>h</sub>	Unrecognized block number (block mode only)
0504 0004 <sub>h</sub>	CRC error (block mode only)
0504 0005 <sub>h</sub>	Out of memory
0601 0000 <sub>h</sub>	Access to this Object is not supported
0601 0001 <sub>h</sub>	Attempted read access to a write-only Object
0601 0002 <sub>h</sub>	Attempted write access to a read-only Object
0602 0000 <sub>h</sub>	Object does not exist in Object Dictionary
0604 0041 <sub>h</sub>	Object cannot be mapped to a PDO
0604 0042 <sub>h</sub>	Size and number of mapped Objects exceed permissible PDO length
0604 0043 <sub>h</sub>	General parameter incompatibility
0604 0047 <sub>h</sub>	General device incompatibility
0606 0000 <sub>h</sub>	Access infringement caused by hardware error
0607 0010 <sub>h</sub>	Data type incompatible, length of service parameter is incompatible
0607 0012 <sub>h</sub>	Data type incompatible, length of service parameter is too long
0607 0013 <sub>h</sub>	Data type incompatible, length of service parameter is too short
0609 0011 <sub>h</sub>	Sub-index does not exist
0609 0030 <sub>h</sub>	Outside value range for the parameter (only for write access)
0609 0031 <sub>h</sub>	Parameter value too high
0609 0032 <sub>h</sub>	Parameter value too low
0609 0036 <sub>h</sub>	Maximum value is lower than minimum value
0800 0000 <sub>h</sub>	General error/fault
0800 0020 <sub>h</sub>	Data cannot be transmitted or saved
0800 0021 <sub>h</sub>	Data cannot be transmitted or saved because device is under local control
0800 0022 <sub>h</sub>	Data cannot be transmitted or saved because of device status
0800 0023 <sub>h</sub>	Dynamic generation of the Object Dictionary not possible or already available (e.g Object Dictionary is created from a file, and an error occurs because of a defect in the file)

Abort Codes not listed above are reserved.

### III.4.6 Process Data Object (PDO)

PDOs are used for real-time data communication. PDOs can, for instance, be used to set up controllers similar to analog drives. Instead of +/-10VDC setpoints and ROD feedback, digital speed setpoints and position feedback are attained via PDOs in this case.

Transmission is carried out unconfirmed without a protocol "overhead". This communication Object uses the unconfirmed communication service.

PDOs are defined via the Object Dictionary for the SERVOSTAR™ 400/600, whereby pre-defined PDOs can be selected (mapping of pre-defined PDOs) or composed by the user (mapping of variables). Mapping is made during the configuration phase, with the help of SDOs. The lengths and mapping numbers for the PDOs are defined by the drive profile DS 402.

The definition of the PDO service and protocol can be found in DS301. Examples of the usage of PDOs can be found in the application section of this documentation.

Basically, two types of PDOs can be distinguished, depending on the direction of transmission:

- Transmit-PDOs (TPDOs) (SERVOSTAR™ ⇒ Master)  
The TPDOs transmit data from SERVOSTAR™ to control system (e.g actual value Objects, instrument status).
- Receive-PDOs (RPDOs) (Master ⇒ SERVOSTAR™)  
The RPDOs receive data from control system to SERVOSTAR™ (e.g setpoints).

SERVOSTAR™ 400/600 supports two independent PDO channels for each direction of transmission. The channels are labeled by the channel numbers 1 to 4.

There are three parameters each for the configuration of each of the four possible PDOs, and they can be set up through the corresponding SDOs:

1. Selection parameters, to select the two PDOs in each direction to be used for process data operation from a number of possible PDOs (SDOs 2600<sub>h</sub> to 2603<sub>h</sub>, 2A00<sub>h</sub> to 2A03<sub>h</sub>).
2. Mapping parameter, to determine which data are available (mapped) in the selected PDO, and for entering the mapping of the PDO for the freely configured PDOs (Nos. 37 to 40).
3. Communication parameters, that define whether the PDOs operate in synchronized mode, or event-driven (SDOs 1400<sub>h</sub> to 1403<sub>h</sub>, 1800<sub>h</sub> to 1803<sub>h</sub>).

Furthermore, individual bits of the TPDOs can be masked, so that an automatic generation of the transmit-trigger can be controlled by individual bit event in TPDOs.

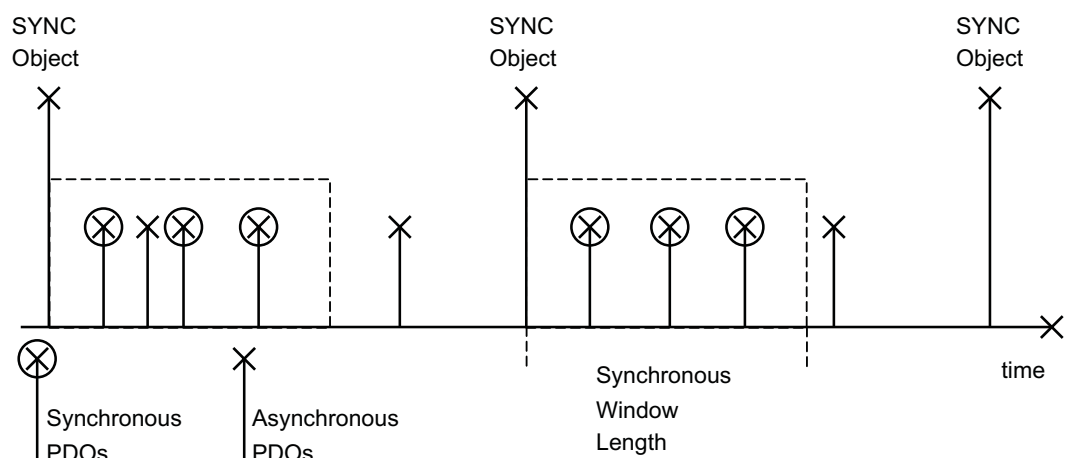
### III.4.6.1

#### Transmission modes

The following PDO transmission modes are distinguished:

- Synchronous transmission
- Asynchronous transmission

The pre-defined SYNC Object is transmitted periodically (bus clock), to synchronize the drives. Synchronous PDOs are transmitted within a pre-defined time window immediately following the SYNC Object.



The transmission modes are set up with the aid of the PDO communication parameters.



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## IV CANopen Drive Profile

### IV.1 Emergency Messages

*Emergency messages* are triggered by internal equipment errors. They have a high ID-priority, to ensure quick access to the bus. An *Emergency message* contains an error field with pre-defined error/fault numbers (2 bytes), an error register (1byte), the error category (1 byte) and additional information ( $\Rightarrow$  chapter III). The higher-value byte of the error number describes the error category, and the lower-value byte provides the error number in this category.

Error numbers from  $xx00_n$  to  $xx7F_n$  are defined in the communication or drive profile. Error numbers from  $xx80_n$  to  $xxFF_n$  have manufacturer-specific definitions. The error category can be used to classify the significance of any errors that occur. The following error categories are defined:

- 1: Errors that can only be cleared by a reset (*COLDSTART* command, or Bit 7 in the control word  $\Rightarrow$  IV.4.2.1). These errors are also indicated by blinking of the LED display in the front panel. (Fxx, xx = error number)
- 2: Errors that can be cleared by Bit 11 in the control word ( $\Rightarrow$  IV.4.2.1).
- 3: Error messages that may appear when a PDO is processed.
- 4: Faults, that **cannot** be cleared by the user.
- 5: Operating errors/warnings.

The following table describes the various *Error Codes*:

Error Code	Category	Description
0000 <sub>h</sub>	—	Error reset or no error (mandatory)
1000 <sub>h</sub>	—	Generic error (mandatory)
1080 <sub>h</sub>	5	No BTB/RTO (status <i>not ready for operation</i> )
2330 <sub>h</sub>	2	Earth short (F22)
3100 <sub>h</sub>	1	No mains/line-BTB (F16)
3110 <sub>h</sub>	1	Overvoltage in DC-bus/DC-link (F02)
3120 <sub>h</sub>	1	Undervoltage in DC-bus/DC-link (F05)
3130 <sub>h</sub>	1	Supply line phase missing (with PMODE = 2) (F19)
4110 <sub>h</sub>	1	Ambient temperature too high (F13)
4210 <sub>h</sub>	1	Heat sink temperature too high (F01)
4310 <sub>h</sub>	1	Motor temperature too high (F06)
5111 <sub>h</sub>	1	Fault in ±15V auxiliary voltage (F07)
5380 <sub>h</sub>	1	Fault in A/D converter (F17)
5400 <sub>h</sub>	1	Fault in output stage (F14)
5420 <sub>h</sub>	1	Ballast (chopper) (F18)
5441 <sub>h</sub>	1	Operating error for AS-option (F27)
5530 <sub>h</sub>	1	Serial EEPROM (F09)
5581 <sub>h</sub>	1	Flash EEPROM (F10)
6010 <sub>h</sub>	4	Watchdog (software reset, F32)
6181 <sub>h</sub>	4	BCC error (table)
6182 <sub>h</sub>	4	BCC error (system macro)
6183 <sub>h</sub>	4	BCC error (serial EEPROM)
6184 <sub>h</sub>	4	FPGA error
6185 <sub>h</sub>	4	Fault/error (table)
6281 <sub>h</sub>	4	User software BCC (macro, F32)
6282 <sub>h</sub>	4	Faulty user software (macro, F32)
6320 <sub>h</sub>	3	Parameter error
7111 <sub>h</sub>	1	Braking error/fault (F11)
7122 <sub>h</sub>	1	Commutation error (F25)
7181 <sub>h</sub>	5	Could not enable SERVOSTAR™
7182 <sub>h</sub>	5	Command only possible in <i>disabled</i> status
7303 <sub>h</sub>	1	Feedback device error (F04)
8053 <sub>h</sub>	1	Handling error (F21)
8181 <sub>h</sub>	2	Response monitoring activated
8182 <sub>h</sub>	1	CAN <i>bus off</i> (F23)
8281 <sub>h</sub>	5	Status machine not in <i>operation enable</i> condition
8282 <sub>h</sub>	5	wrong mode setting
8331 <sub>h</sub>	1	I <sup>2</sup> t (torque fault, F15)
8480 <sub>h</sub>	1	Overspeed (F08)
8611 <sub>h</sub>	2	Lag/following error
8681 <sub>h</sub>	5	Invalid motion task number
8682 <sub>h</sub>	2	External trajectory error (F28) (only with Sercos)
FF01 <sub>h</sub>	4	Serious exception error (F32)
FF02 <sub>h</sub>	3	Error in PDO elements
FF03 <sub>h</sub>	5	Operating mode
FF04	1	Slot error (F20)
FF06	2	Warning display as error (F24)
FF07	2	Homing error (drove onto HW limit switch) (F26)
FF08	2	Sercos error (F29)
FF11	1	Sercos

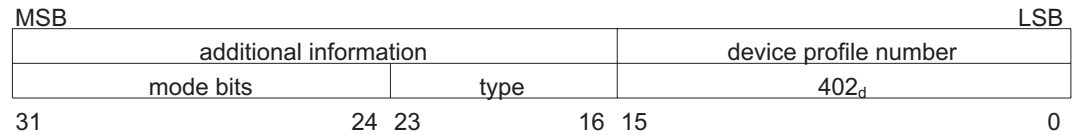
## IV.2 General definitions

This chapter describes Objects with a general validity (e.g. SDO 1000<sub>h</sub> *Device Type*). The next section explains the free configuration of Process Data Objects (“free mapping”).

### IV.2.1 General Objects

#### IV.2.1.1 SDO 1000<sub>h</sub>: Device Type (DS301)

This Object describes the device type (servo drive) and device functionality (DS402 drive profile). It is laid out as follows:



Number of the device profile: 402<sub>d</sub> (drive profile)  
 Type: 02 (servo drive)  
 Mode bits: 0 (manufacturer-specific)

Object description:

<b>Index</b>	1000 <sub>h</sub>
<b>Name</b>	device type
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	M

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	no

### IV.2.1.2 SDO 1001<sub>h</sub>: Error Register (DS301)

If an error bit is set in the manufacturer independent error register, then more detailed information is made available in SDO 1003<sub>h</sub>. This Object is part of the Error Object (Emergency Message).

Object description:

<b>Index</b>	1001 <sub>h</sub>
<b>Name</b>	Error register
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8
<b>Category</b>	M

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED8
<b>Default value</b>	no

The following describes the bit assignment for the error register. A bit that is set indicates an error/fault event.

Bit	Description	Bit	Description
0	generic error	4	communication error
1	current	5	device profile specific
2	voltage	6	reserved
3	temperature	7	manufacturer-specific

### IV.2.1.3 SDO 1002<sub>h</sub>: Manufacturer Status Register (DS301)

This Object contains the manufacturer-specific status register, which also contains SERVOSTAR™ warnings (see also ASCII Object DRVSTAT).

Object description:

<b>Index</b>	1002 <sub>h</sub>
<b>Name</b>	Manufacturer Status Register
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8
<b>Category</b>	M

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED8
<b>Default value</b>	no

The following table shows the bit assignment for the status register:

Bit	Description
0	Warning 1: I <sup>2</sup> t-threshold exceeded
1	Warning 2: full ballast power reached
2	Warning 3: lag/following error
3	Warning 4: response monitoring activated
4	Warning 5: power supply phase missing
5	Warning 6: software limit-switch 1 has been activated
6	Warning 7: software limit-switch 2 has been activated
7	Warning 8: faulty motion task started
8	Warning 9: no reference point set at start of motion task
9	Warning 10: PSTOP activated
10	Warning 11: NSTOP activated
11	Warning 12: motor default values were loaded
12	Warning 13: expansion board not functioning correctly
13	Warning 14: motor phase
14	Warning 15: erroneous VCT entry selected
15	Warning 16: reserve
16	motion task active
17	reference point set
18	actual position = home position
19	In Position
20	position latch made (positive edge)
21	reached Position 0
22	reached Position 1
23	reached Position 2
24	reached Position 3
25	reached Position 4
26	finished initialization
27	reached Position 5
28	speed = 0
29	safety relay has been activated
30	output stage enabled
31	error present

#### IV.2.1.4 SDO 1003<sub>h</sub>: Predefined Error Field (DS301)

This Object contains the last error event that was reported by an error telegram. Only the most recent error is displayed.

1. The value in Sub-index 00<sub>h</sub> shows the number of recorded errors.
2. The most recent error is shown in Sub-index 01<sub>h</sub>.
3. If the value 0 is written to Sub-index 02<sub>h</sub>, the error is deleted from the error list (caution: error will not be acknowledged!).
4. The error number has the data type UNSIGNED32 and is composed of a 16-bit error number and a manufacturer-specific information field.  
The manufacturer-specific information field is not used by SERVOSTAR™ 400/600.  
The possible error numbers are described in the chapter “Error Message” (⇒ IV.1).  
The data field is composed as follows:

MSB	LSB
Information field	Error number

Object description:

<b>Index</b>	1003 <sub>h</sub>
<b>Name</b>	Error Field
<b>Object code</b>	ARRAY
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Sub-index</b>	00 <sub>h</sub>
<b>Description</b>	Number of errors
<b>Category</b>	M
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	0 ... 254
<b>Default value</b>	no

<b>Sub-index</b>	01 <sub>h</sub>
<b>Description</b>	Standard error field (⇒ IV.1)
<b>Category</b>	M
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	no

### IV.2.1.5 SDO 1004<sub>h</sub>: Number of supported PDOs (DS301)

This Object is only supported to provide compatibility with older versions of the CANopen Standards DS 301.

The structure of the parameter is as follows:

Sub-index	MSB	LSB
0	no. of supported RPDOs	no. of supported TPDOs
1	no. of supported synchronous RPDOs	no. of supported synchronous TPDOs
2	no. of supported asynchronous RPDOs	no. of supported asynchronous TPDOs

Object description:

<b>Index</b>	1004 <sub>h</sub>
<b>Name</b>	no. of supported PDOs
<b>Object code</b>	ARRAY
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Sub-index</b>	00 <sub>h</sub>
<b>Description</b>	no. of supported PDOs
<b>Category</b>	O
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	00 <sub>h</sub> ... 1FF01FF <sub>h</sub>
<b>Default value</b>	00020002 <sub>h</sub>

<b>Sub-index</b>	01 <sub>h</sub>
<b>Description</b>	no. of synchronous PDOs
<b>Category</b>	O
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	00 <sub>h</sub> ... 1FF01FF <sub>h</sub>
<b>Default value</b>	00 <sub>h</sub>

<b>Sub-index</b>	02 <sub>h</sub>
<b>Description</b>	no. of asynchronous PDOs
<b>Category</b>	O
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	00 <sub>h</sub> ... 1FF01FF <sub>h</sub>
<b>Default value</b>	00020002 <sub>h</sub>

This only shows the assignment when the SERVOSTAR™ 400/600 has started up. Afterwards, the PDOs can be configured through the communication parameters 1400<sub>h</sub> to 1403<sub>h</sub>, 1800<sub>h</sub> to 1803<sub>h</sub>.

### IV.2.1.6 SDO 1005<sub>h</sub>: COB-ID of the SYNC Message (DS301)

This Object can be used to change the COB-ID for the SYNC message.

Object description:

<b>Index</b>	1005 <sub>h</sub>
<b>Name</b>	COB-ID for the SYNC message
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	80000080 <sub>h</sub>

The structure of the parameter is as follows:

MSB								LSB			
X	0/1	0	00 <sub>h</sub>				11-bit identifier				
31	30	29	28					11	10	0	

Only Bits 0 ... 10, 29 and 30 have any significance:

Bit	Value	Meaning
31	X	—
30	0	Device not generating SYNC message
	1	Device generating SYNC message
29	0	11 Bit ID
	1	29 Bit ID
28 ... 11	X	Bit 11 ... 28 of 29-bit SYNC COB-ID
10 ... 0	X	Bit 0 ... 10 of SYNC COB-ID

### IV.2.1.7 SDO 1006<sub>h</sub>: Communication Cycle Period (DS301)

This Object can be used to define the period (in  $\mu$ s) for the transmission of the SYNC telegram.

Object description:

<b>Index</b>	1006 <sub>h</sub>
<b>Name</b>	Period of the communication cycle
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	00 <sub>h</sub>

#### IV.2.1.8 SDO 1007<sub>h</sub>: Synchronous Window Length (DS301)

This Object defines the length of the time window (in  $\mu\text{s}$ ) for synchronous PDOs.

Object description:

<b>Index</b>	1007 <sub>h</sub>
<b>Name</b>	Time window for synchronous messages
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	00 <sub>h</sub>

#### IV.2.1.9 SDO 1008<sub>h</sub>: Manufacturer Device Name (DS301)

The device name consists of four ASCII characters in the form *SDxx*, whereby *xx* stands for the current in the output stage (e.g. SD06).

Object description:

<b>Index</b>	1008 <sub>h</sub>
<b>Name</b>	Manufacturer Device Name
<b>Object code</b>	VAR
<b>Data type</b>	Visible String
<b>Category</b>	Optional

Value description:

<b>Access</b>	const
<b>PDO mapping</b>	not possible
<b>Value range</b>	no
<b>Default value</b>	no

#### IV.2.1.10 SDO 100A<sub>h</sub>: Manufacturer Software Version (DS301)

The interface software version consists of four ASCII characters (e.g. 3.00).

Object description:

<b>Index</b>	100A <sub>h</sub>
<b>Name</b>	Manufacturer Software Version
<b>Object code</b>	VAR
<b>Data type</b>	Visible String
<b>Category</b>	Optional

Value description:

<b>Access</b>	const
<b>PDO mapping</b>	not possible
<b>Value range</b>	no
<b>Default value</b>	no

### IV.2.1.11 SDO 100B<sub>h</sub>: Node-ID (DS301)

The station address of the SERVOSTAR™ 400/600 can be read out through the Object *Node-ID*. The station address can be altered through the ASCII-Object *ADDR*. The address range (value range) that has to be set depends on the ASCII-Object *MDRV*, and the station address can be set within the range 1 ... 63 or 1 ... 127.

**If the expanded address range is used, then the commissioning software can no longer be networked over the CAN-bus.**

Object description:

<b>Index</b>	100B <sub>h</sub>
<b>Name</b>	Node-ID
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	Optional

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	1 ... 127 (1 ... 63)
<b>Default value</b>	1

### IV.2.1.12 SDO 100C<sub>h</sub>: Guard Time (DS301)

The arithmetical product of the SDOs 100C<sub>h</sub> *Guard Time* and 100D<sub>h</sub> *Lifetime Factor* is the response monitoring time. The Guard Time is given in milliseconds. The response monitoring is activated with the first *Nodeguard* Object (⇒ III.4.7). If the value of the Object *Guard Time* is set to zero, then the response monitoring is inactive.

Object description:

<b>Index</b>	100C <sub>h</sub>
<b>Name</b>	Guard Time
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED16
<b>Category</b>	Value description:

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED16
<b>Default value</b>	0

#### IV.2.1.13 SDO 100D<sub>h</sub>: Lifetime Factor (DS301)

The arithmetical product of the SDOs 100C<sub>h</sub> *Guard Time* and 100D<sub>h</sub> *Lifetime Factor* is the response monitoring time. The response monitoring is activated with the first *Nodeguard* Object ( $\Rightarrow$  III.4.7). If the value of the Object *Guard Time* is set to zero, then the response monitoring is inactive.

Object description:

<b>Index</b>	100D <sub>h</sub>
<b>Name</b>	Lifetime Factor
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8
<b>Category</b>	Mandatory

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	0 ... 255
<b>Default value</b>	0

#### IV.2.1.14 SDO 100E<sub>h</sub>: COB-ID Node Guarding (DS301)

This Object defines the COB-ID for the Node Guarding protocol.

Object description:

<b>Index</b>	100E <sub>h</sub>
<b>Name</b>	Node Guarding identifier
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	700 + node-ID

#### IV.2.1.15 SDO 100F<sub>h</sub>: Number of supported SDOs (DS301)

This Object describes the number of SDOs that are supported by the device.

Object description:

<b>Index</b>	100F <sub>h</sub>
<b>Name</b>	Number of supported SDOs
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	01 <sub>h</sub>

### IV.2.1.16 SDO 1010<sub>h</sub>: Store Parameters (DS301)

This object can be used to save communication- and mapping parameter.

Object description

<b>Index</b>	1010 <sub>h</sub>
<b>Name</b>	store parameters
<b>Object code</b>	ARRAY
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description

<b>Sub-index</b>	0 <sub>h</sub>
<b>Description</b>	Number of entries
<b>Access</b>	r
<b>PDO Mapping</b>	not possible
<b>Value range</b>	2
<b>Default value</b>	2

<b>Sub-index</b>	1 <sub>h</sub>
<b>Description</b>	save all parameters
<b>Access</b>	r/w
<b>PDO Mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	0

this sub-index is reserved

<b>Sub-index</b>	2 <sub>h</sub>
<b>Description</b>	save communication parameters
<b>Access</b>	r/w
<b>PDO Mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	0

this sub-index must be used to save communication- and mapping parameters. A writing access with the signature `save` must be made, thus the value below has to be written:

MSB		LSB	
[e]	[v]	[a]	[s]
65 <sub>h</sub>	76 <sub>h</sub>	61 <sub>h</sub>	73 <sub>h</sub>

**IV.2.1.17 SDO 1012<sub>h</sub>: COB-ID for Time Stamp Message (DS301)**

This Object can be used to define the COB-ID for the *Time Stamp* message.

Object description:

<b>Index</b>	1012 <sub>h</sub>
<b>Name</b>	COB-ID time stamp message
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	100 <sub>h</sub>

**IV.2.1.18 SDO 1013<sub>h</sub>: High-Resolution Time Stamp (in preparation)(DS301)**

This Object can be used to read or write a time value.

Object description:

<b>Index</b>	1013 <sub>h</sub>
<b>Name</b>	high-resolution time stamp
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	00 <sub>h</sub>

**IV.2.1.19 SDO 1014<sub>h</sub>: COB - ID for Emergency Message (DS301)**

This Object can be used to define the COB-ID for the *Emergency* message.

Object description:

<b>Index</b>	1014 <sub>h</sub>
<b>Name</b>	COB-ID emergency message
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Category</b>	O

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	80 <sub>h</sub> + Node - ID

### IV.2.1.20 SDO 1018<sub>h</sub>: Identity Object (DS301)

The *Identity* Object contains general device information.

Object description:

<b>Index</b>	1018 <sub>h</sub>
<b>Name</b>	Identity Object
<b>Object code</b>	RECORD
<b>Data type</b>	Identity

Value description:

<b>Sub-index</b>	00 <sub>h</sub>
<b>Description</b>	Number of entries
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	1 ... 4
<b>Default value</b>	4

<b>Sub-index</b>	01 <sub>h</sub>
<b>Description</b>	Vendor ID*
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	6A <sub>H</sub>

\* 00 00 00 6A<sub>h</sub>

<b>Sub-index</b>	02 <sub>h</sub>
<b>Description</b>	Product Code*
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	no

\* Rated current of the amplifier

<b>Sub-index</b>	03 <sub>h</sub>
<b>Description</b>	Revision Number*
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	no

\* Bits 16 ... 31 = firmware version, Bits 15 ... 0 = CANopen

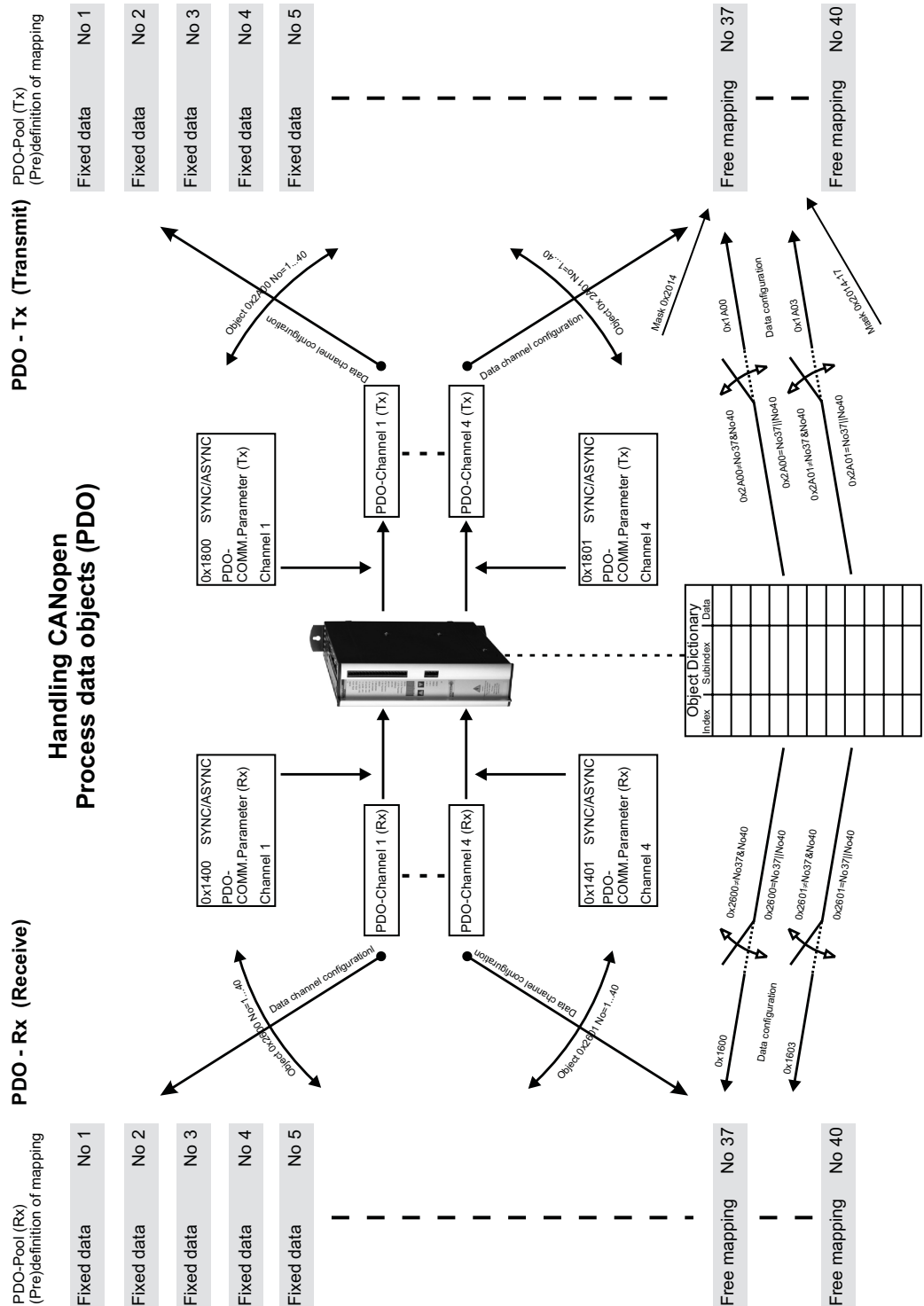
<b>Sub-index</b>	04 <sub>h</sub>
<b>Description</b>	Serial Number
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Value range</b>	UNSIGNED32
<b>Default value</b>	no

### IV.3 PDO mapping

Since SERVOSTAR™ 400/600 supports more than one operating mode, different PDOs are required for the transmission and received directions, depending on the application.

The first method of handling of freely configurable PDOs was *more-or-less free mapping*. With this type of free mapping, predefined PDOs are selected with the aid of an index from the PDO library. The contents of these PDOs cannot be reconfigured at a later stage. However, *more-or-less free mapping* turned out to be too rigid for the increasing number of extremely variegated applications. As a result, *completely free mapping* was introduced additionally for PDOs, whereby the user can also alter the contents of the PDO (⇒ III.4.6).

The following diagram “Handling CANopen Process Data Objects” illustrates the use of PDOs.



## IV.3.1 Receive-PDOs (RPDO)

The SDOs 2600<sub>h</sub> to 2603<sub>h</sub> can be used to select RPDOs. The configuration of the RPDOs is made through the SDOs 1400<sub>h</sub> to 1403<sub>h</sub> (communication parameter) and 1600<sub>h</sub> to 1603<sub>h</sub> (mapping parameter). These Objects have channel-linked operation, i.e.

- RPDO Channel 1: 2600<sub>h</sub>, 1400<sub>h</sub>, 1600<sub>h</sub>
- RPDO Channel 2: 2601<sub>h</sub>, 1401<sub>h</sub>, 1601<sub>h</sub>
- RPDO Channel 3: 2602<sub>h</sub>, 1402<sub>h</sub>, 1602<sub>h</sub>
- RPDO Channel 4: 2603<sub>h</sub>, 1403<sub>h</sub>, 1603<sub>h</sub>

The SDOs 1600<sub>h</sub> to 1603<sub>h</sub> can only be read, in order to disclose the Object configuration within the PDOs.



### Exception:

If one or more PDOs 37 to 40 are selected, then the Object configuration for the relevant RPDO channel must be made through the SDOs 1600<sub>h</sub> to 1603<sub>h</sub> (write access).

The following PDOs have been defined:

PDO Number	Mapping Object Index	Sub-index	Mapping Object Name
1	6040 <sub>h</sub>	—	control word
2 ... 20	—	—	reserved
21	3100 <sub>h</sub>	01 <sub>h</sub> ..08 <sub>h</sub>	ASCII-Object
22	6040 <sub>h</sub>	—	control word
	2060 <sub>h</sub>	00 <sub>h</sub>	current or speed setpoint
23 ... 31	—	—	reserved
32	2060 <sub>h</sub>	00 <sub>h</sub>	current or speed setpoint
33	2022 <sub>h</sub>	04 <sub>h</sub>	incremental position setpoint
	2022 <sub>h</sub>	04 <sub>h</sub>	incremental position setpoint
34	2022 <sub>h</sub>	01 <sub>h</sub>	position
	2022 <sub>h</sub>	02 <sub>h</sub>	velocity
	2022 <sub>h</sub>	03 <sub>h</sub>	type of motion task
35	2022 <sub>h</sub>	05 <sub>h</sub>	motion block number (Caution: in the device status <i>Operation Enable</i> it will start immediately)
36	—	—	reserved
37 ... 40	xxxx <sub>h</sub>	xx <sub>h</sub>	freely definable PDO
41 ... 64	—	—	reserved

### IV.3.1.1 Description of the predefined Receive-PDOs

#### IV.3.1.1.1 PDO Control Word (1)(DS402)

The PDO control word (Default-PDO) consists of the control word (UNSIGNED16). This PDO can only be used to operate the status machine ( $\Rightarrow$  IV.4.1), and is available for use in all modes. After switch-on, this PDO is mapped to RPDO 1.

The table shows the mapping of the PDO control word:

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01 <sub>h</sub>	60400010 <sub>h</sub>	control word

### IV.3.1.1.2 PDO Receive ASCII channel (21)

With the help of the ASCII channel (Default-PDO), all the parameters and commands can be transmitted to the SERVOSTAR™. Up to 8 ASCII characters can be sent in one PDO. Commands or parameters that require more than 8 characters must be segmented. All commands and parameters are terminated by the ASCII code *CR LF* (0xD<sub>h</sub>, 0xA<sub>h</sub>). The unused bytes in the PDO are filled with the ASCII code *NUL* (0x0<sub>h</sub>), because otherwise every surplus character would be interpreted as a new command.

The table describes the mapping of the PDO *Receive ASCII channel*:

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01..08 <sub>h</sub>	31000208 <sub>h</sub>	ASCII chars. 1 to 8

This Object **only** supports transmission type 255 (asynchronous).

### IV.3.1.1.3 PDO Current/Speed Setpoint (22)

The PDO current or speed setpoint is formed from the control word (UNSIGNED16) and the setpoint (SIGNED16). This PDO must only be used in the *Digital speed* or *Digital current* mode. It will be recognized as a speed or current setpoint, depending on the mode that is set (digital current or digital speed). The PDO is executed immediately. A repeated transmission of the PDO with various setpoint values does not require an intermediate halt of the drive. After switch-on, this PDO is mapped to RPDO 2.

**Current normalization:** 3280 = peak current of the controller  
1640 = rated current of the controller

e.g.. rated current = 3A, setpoint = 1.0A ⇒ 547 increments

**speed normalization:**

e.g. speed = 3000 rpm ⇒ setpoint = 479430

The table shows the mapping for the *Setpoint* PDO:

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01 <sub>h</sub>	60400010 <sub>h</sub>	control word
02 <sub>h</sub>	20600020 <sub>h</sub>	current/speed setpoint

### IV.3.1.1.4 PDO Setpoint 2 (32)

The PDO *Setpoint 2* is a time- and data-optimized PDO. It contains just one 32-bit setpoint. This setpoint can only be used in the *Digital speed* or *Digital current* mode. It will be recognized as a speed or current setpoint, depending on the mode that is set (digital current or digital speed). The PDO is executed immediately. A repeated transmission of the PDO with various setpoint values does not require an intermediate halt of the drive. After switch-on, this PDO is mapped to RPDO 2.

The table shows the mapping for the PDO *Setpoint 2*:

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01 <sub>h</sub>	20600020 <sub>h</sub>	current/speed setpoint

### IV.3.1.1.5 PDO Trajectory (33)

The *Trajectory* PDO is a time- and data-optimized PDO. This PDO must only be used in the Trajectory mode. The *Trajectory* PDO must always be transmitted at constant time intervals (to be set with the *PTBASE* command), otherwise there may be irregularities in the speed characteristic. This PDO consists of two components: the incremental actual position values for two axes. The assignment of the data for the axes, which must both be set to the same COB-ID for this RPDO (Sub-index 01<sub>h</sub> of the corresponding communication parameters), is made through the SDO 2721<sub>h</sub>.

**Example of the calculation of the absolute position:**

$$\text{Position} = \frac{\text{incremental position value}}{2^{20}}$$

The maximum difference between two incremental positions is given by the final limit speed that is set (ASCII-command VLIM) – see example.

**Example of the maximum incremental position difference:**

$$\begin{aligned} \text{max.achievable final speed} / 1000 \frac{\text{rev}}{\text{min}} &= 0.016667 \frac{\text{rev}}{\text{ms}} \\ |\text{incr.pos.}(t_2) - \text{incr.pos.}(t_1)| &\leq 2^{20} \times 0.016667 = 17475 \end{aligned}$$

Depending on the amplifier parameters that have been set, there may be a larger or smaller lag/following error. If the error message *contouring error* appears and the axis is stopped with the emergency ramp, there are several possible reasons:

- The selected incremental position difference is too large (see above).
- The contouring error window has been set too small (SDO 2020<sub>h</sub> Sub-index 03<sub>h</sub>)
- The amplifier parameters have not been set up optimally.

The table shows the mapping of the *Trajectory* PDO:

Sub-index	Value	Description
00 <sub>h</sub>	2 <sub>h</sub>	number of entries
01 <sub>h</sub>	20220420 <sub>h</sub>	incremental position
02 <sub>h</sub>	20220420 <sub>h</sub>	incremental position

This Object does **not** support transmission type 255 (asynchronous).

### IV.3.1.1.6 PDO Motion Block (34)

The *Motion Block* PDO is put together from the position (SIGNED32, weighted), speed (UNSIGNED16) and the type of motion tasks (UNSIGNED16).

The PDO starts a motion block from the volatile motion block memory (motion block number = 0) and can only be used in the Position mode.

The table shows the mapping for the *Motion Block* PDO:

Sub-index	Value	Description
00 <sub>h</sub>	3 <sub>h</sub>	number of entries
01 <sub>h</sub>	20220120 <sub>h</sub>	position
02 <sub>h</sub>	20220210 <sub>h</sub>	speed
03 <sub>h</sub>	20220310 <sub>h</sub>	motion task type (absolute/relative)

This Object **only** supports transmission type 255 (asynchronous).

#### IV.3.1.1.7 PDO Start Motion Block (35)

The *Start Motion Block* PDO is formed by the motion task number (UNSIGNED16).

The PDO starts a motion block from the volatile memory (motion block number = 0, 192 ... 255) or from the permanent memory (motion block number = 1 ... 180).

This PDO can only be used in the *Position* mode.

The table shows the mapping of the *Start Motion Block* PDO:

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01 <sub>h</sub>	20220510 <sub>h</sub>	motion task number

This Object **only** supports transmission type 255 (asynchronous).

#### IV.3.1.1.8 PDO Free Definition (37 to 40)

If these PDOs are selected, then Objects can be freely added. The SDOs 1600<sub>h</sub> to 1603<sub>h</sub> (mapping parameters) are used for this purpose. Up to 8 individual Objects can be mapped into a single PDO.

An example of PDO mapping and communication configuration can be found in the appendix.

(⇒ VI.1)

## IV.3.1.2 Object Description

### IV.3.1.2.1 SDO 1400<sub>h</sub> to 1403<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> receive-PDO communication parameter (DS301)

Sub-index	Description
00 <sub>h</sub>	number of entries
01 <sub>h</sub>	PDO COB-ID*
02 <sub>h</sub>	transmission type**
03 <sub>h</sub>	inhibit time
04 <sub>h</sub>	CMS priority group

\* After selecting a PDO higher than 2600<sub>h</sub> to 2603<sub>h</sub>, here you can define the COB-identifier that the amplifier responds to (if a different setting is required from the default value).

\*\* For selecting SYNC, event-triggering etc.

### IV.3.1.2.2 SDO 1600<sub>h</sub> to 1603<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> receive-PDO mapping parameter (DS301)

Sub-index	Description
00 <sub>h</sub>	number of configured Objects
01 <sub>h</sub> ... 08 <sub>h</sub>	description of the configured Objects

### IV.3.1.2.3 SDO 2600<sub>h</sub> to 2603<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> receive-PDO select

This Object is used to select a predefined receive-PDO. The SDOs 1400<sub>h</sub> to 1403<sub>h</sub> 1<sup>st</sup> to 4<sup>th</sup> receive-PDO parameter and 1600<sub>h</sub> to 1603<sub>h</sub> 1<sup>st</sup> to 4<sup>th</sup> receive-PDO mapping can then be used to define the characteristics of this PDO.

This Object enables variable mapping of predefined PDOs. The possible PDOs for selection are listed in the table in Chapter IV.3.1.

Object description:

<b>Index</b>	2600 <sub>h</sub> ... 2603 <sub>h</sub>
<b>Name</b>	1 <sup>st</sup> ... 4 <sup>th</sup> receive-PDO select
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	0 ... 255
<b>Default value</b>	0

#### IV.3.1.2.4 SDO 2721<sub>h</sub>: Configuration of receive-PDO 33

This Object influences the processing of the eight data bytes received for the PDO *Trajectory* (No. 33). The bytes of the PDO are interpreted as an incremental setpoint for the next movement, as follows: with the value *LOW* (= 0), the bytes 0 – 3 (Sub-index 01<sub>h</sub> of the PDO mapping) are used, and with the value *HIGH* (= 1), the bytes 4 – 7 (Sub-index 02<sub>h</sub> of the PDO mapping) are used.

Object description:

<b>Index</b>	2721 <sub>h</sub>
<b>Name</b>	PDO 33 data select
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	0, 4
<b>EEPROM</b>	no
<b>Default value</b>	0

## IV.3.2 Transmit-PDOs (TPDO)

The SDOs 2A00<sub>h</sub> to 2A03<sub>h</sub> can be used to select TPDOs. The configuration of the PDOs is made with the SDOs 1800<sub>h</sub> to 1803<sub>h</sub> (communication parameter) und 1A00<sub>h</sub> to 1A03<sub>h</sub> (mapping parameter). These Objects have channel-linked operation, i.e.

- TPDO Channel 1: 2A00<sub>h</sub>, 1800<sub>h</sub>, 1A00<sub>h</sub>
- TPDO Channel 2: 2A01<sub>h</sub>, 1801<sub>h</sub>, 1A01<sub>h</sub>
- TPDO Channel 3: 2A02<sub>h</sub>, 1802<sub>h</sub>, 1A02<sub>h</sub>
- TPDO Channel 4: 2A03<sub>h</sub>, 1803<sub>h</sub>, 1A03<sub>h</sub>

The SDOs 1A00<sub>h</sub> to 1A03<sub>h</sub> can only be read, in order to disclose the Object configuration within the PDOs.

### Exception:

**If one or more PDOs 37 to 40 are selected, then the Object configuration for the relevant TPDO channel must be made through the SDOs 1A00<sub>h</sub> to 1A03<sub>h</sub> (write access).**

The following PDOs have been defined:

PDO Number	Mapping Object Index	Sub-index	Mapping Object Name
1 (01 <sub>h</sub> )	6041 <sub>h</sub>	—	status word
2..20 (02 <sub>h</sub> ..14 <sub>h</sub> )	—	—	reserved
21 (15 <sub>h</sub> )	3102 <sub>h</sub>	01 <sub>h</sub> ..08 <sub>h</sub>	ASCII Object
22 (16 <sub>h</sub> )	6041 <sub>h</sub>	—	status word
	2070 <sub>h</sub>	01 <sub>h</sub>	actual position (20 bits/turn)
	2070 <sub>h</sub>	02 <sub>h</sub>	speed (1 bit = 1875/262144 [revs/min])
23 (17 <sub>h</sub> )	6041 <sub>h</sub>	—	status word
	1002 <sub>h</sub>	—	manufacturer-specific status register
24..31 (18 <sub>h</sub> ..1F <sub>h</sub> )	—	—	reserved
32 (20 <sub>h</sub> )	2070 <sub>h</sub>	01 <sub>h</sub>	actual position (20 bits/turn)
	2070 <sub>h</sub>	02 <sub>h</sub>	speed (1 bit = 1875/262144 [revs/min])
33 (21 <sub>h</sub> )	2070 <sub>h</sub>	03 <sub>h</sub>	incremental actual position value
	2070 <sub>h</sub>	11 <sub>h</sub>	2nd enhanced status register
34..35 (22 <sub>h</sub> ..23 <sub>h</sub> )	—	—	—
36 (24 <sub>h</sub> )	—	—	reserved
37..40 (25 <sub>h</sub> ..28 <sub>h</sub> )	xxxx <sub>h</sub>	—	freely definable TPDOs
41..64 (29 <sub>h</sub> ..40 <sub>h</sub> )	—	—	reserved

### IV.3.2.1 Description of the predefined Transmit-PDOs

#### IV.3.2.1.1 PDO status word (1)(DS402)

The *status word* PDO (default PDO) is formed by the status word (UNSIGNED16).

This PDO can only be used to disclose the state of the status machine (⇒ IV.4.1). The PDO is mode-independent.

After switch-on, this PDO is mapped to TPDO 1.

The table shows the mapping for the *status word* PDO.

Sub-index	Value	Description
00 <sub>h</sub>	1 <sub>h</sub>	number of entries
01 <sub>h</sub>	60410010 <sub>h</sub>	status word

### IV.3.2.1.2 PDO Transmit ASCII channel (21)

As soon as ASCII characters have been transferred to the ASCII transmission buffer, they are transmitted to the master (control system) with the help of this PDO (default PDO). This always takes place when commands or parameters have been transmitted with the aid of the PDO *Receive ASCII channel* ( $\Rightarrow$  IV.3.1.1.2).

The table shows the mapping for the PDO *Transmit ASCII channel*.

Sub-index	Value	Description
00 <sub>h</sub>	8 <sub>h</sub>	number of entries
01 <sub>h</sub> ..08 <sub>h</sub>	31020208 <sub>h</sub>	ASCII chars. 1 ... 8

This Object **only** supports transmission type 255 (asynchronous).

### IV.3.2.1.3 PDO Actual Position (22)

The *Actual Position* PDO is formed from the status word (UNSIGNED16), actual position (UNSIGNED24) and speed in revs/minute (UNSIGNED24). This PDO can be used to disclose the position in the *Digital speed* or *Digital current* mode.

After switch-on, this PDO is mapped to TPDO 2.

The table shows the mapping for the PDO *Actual Position*:

Sub-index	Value	Description
00 <sub>h</sub>	3 <sub>h</sub>	number of entries
01 <sub>h</sub>	60410010 <sub>h</sub>	status word
02 <sub>h</sub>	20700118 <sub>h</sub>	actual position (20 bits/turn)
03 <sub>h</sub>	20700218 <sub>h</sub>	speed *

\* Resolution: 1 bit = 1875 / 262144 revs/min

### IV.3.2.1.4 PDO Enhanced Status (23)

The Enhanced Status PDO is formed by the status word (UNSIGNED16) and the manufacturer specific status register (UNSIGNED32). This PDO can additionally be triggered by an event in the status register area. The PDO is mode-independent.

The table shows the mapping for the PDO *Enhanced Status*:

Sub-index	Value	Description
00 <sub>h</sub>	2 <sub>h</sub>	number of entries
01 <sub>h</sub>	60410010 <sub>h</sub>	status word
02 <sub>h</sub>	10020020 <sub>h</sub>	manufacturer specific status register

### IV.3.2.1.5 PDO Actual Position 2 (32)

The PDO *Actual Position 2* is a time- and data-optimized PDO (see PDO 21). It contains the actual position (UNSIGNED24) and the revs/minute (UNSIGNED 24). This PDO can be used to disclose the position in the *Digital speed* or *Digital current* mode.

This PDO can **only** be requested with the **SYNC Object**.

The table shows the mapping for the PDO *Actual Position 2*:

Sub-index	Value	Description
00 <sub>h</sub>	2 <sub>h</sub>	number of entries
01 <sub>h</sub>	20700118 <sub>h</sub>	actual position (20 bits/turn)
02 <sub>h</sub>	20700218 <sub>h</sub>	speed *

\* Resolution: 1 bit = 1875 / 262144 revs/min

This Object **only** supports transmission types 1 to 240 (cyclically synchronous).

### IV.3.2.1.6 PDO Incremental Actual Position (33)

The PDO *Incremental Actual Position* is a data-optimized Object that can **only** be requested with a **SYNC Object**.

**Calculation of the absolute position:**

$$\text{Position} = \frac{\text{incremental actual position}}{2^{20}}$$

The table shows the mapping for the PDO *Incremental Actual Position*:

Sub-index	Value	Description
00 <sub>h</sub>	2 <sub>h</sub>	number of entries
01 <sub>h</sub>	20700320 <sub>h</sub>	incremental actual position
02 <sub>h</sub>	20701120 <sub>h</sub>	enhanced status register for PDO 33

This Object **only** supports transmission types 1 to 240 (cyclically synchronous).

### IV.3.2.1.7 PDO Free Definition (37 to 40)

If these PDOs are selected, then Objects can be freely added. The SDOs 1A00<sub>h</sub> to 1A03<sub>h</sub> (mapping parameters) are used for this purpose. Up to 8 individual Objects can be mapped into a single PDO.



**Caution:**

*Even if Objects are “event-triggered” and not called over the CAN bus, they will still be monitored. 16 mapped Objects can therefore place a heavy processing load on the CPU. To avoid this, only map those objects which are really needed, or increase the “inhibit time” accordingly (e.g. to 400 ms). An excessive CPU loading can cause a long response time for an SDO data service (average response time > 40 ms).*

### IV.3.2.2 Object Description

#### IV.3.2.2.1 SDO 1800<sub>h</sub> to 1803<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> transmit-PDO communication parameter (DS301)

Sub-index	Description
00 <sub>h</sub>	number of entries
01 <sub>h</sub>	PDO COB-ID *
02 <sub>h</sub>	transmission type
03 <sub>h</sub>	inhibit time **
04 <sub>h</sub>	CMS priority group

\* After selecting a PDO higher than 2A00<sub>h</sub> to 2A03<sub>h</sub>, here you can define the COB-identifier that the amplifier responds to (if a different setting is required from the default value).

\*\* This sets a waiting time that must be observed after a PDO has been transmitted, before a new transmission can be made (only important for event-triggered PDOs).

#### IV.3.2.2.2 SDO 1A00<sub>h</sub> to 1A03<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> transmit-PDO mapping parameter (DS301)

Sub-index	Description
00 <sub>h</sub>	number of configured Objects
01 <sub>h</sub> ... 08 <sub>h</sub>	description of the configured Objects

#### IV.3.2.2.3 SDO 2A00<sub>h</sub> to 2A03<sub>h</sub>: 1<sup>st</sup> to 4<sup>th</sup> transmit-PDO select

This Object is used to select a predefined transmit-PDO.

The SDOs 1800<sub>h</sub> to 1803<sub>h</sub> 1<sup>st</sup> to 4<sup>th</sup> transmit-PDO parameter and 1A00<sub>h</sub> to 1A03<sub>h</sub> 1<sup>st</sup> to 4<sup>th</sup> transmit-PDO mapping can then be used to define the characteristics of this PDO.

This Object enables variable mapping of predefined PDOs. The possible PDOs for selection are listed in the table in Chapter IV.3.2.

Object description:

<b>Index</b>	2A00 <sub>h</sub> to 2A03 <sub>h</sub>
<b>Name</b>	1 <sup>st</sup> to 4 <sup>th</sup> transmit-PDO select
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8

Value description:

<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Value range</b>	0 ... 255
<b>Default value</b>	0

#### IV.3.2.2.4 SDO 2014<sub>h</sub> to 2017<sub>h</sub>: Mask 1 to 4 for transmit-PDOs

In order to reduce the bus loading with event-triggered PDOs, masking can be used to switch off the monitoring for individual bits in the PDO. In this way it can be arranged, for instance, that actual position values are only signaled once per turn.

This Object masks the PDO-channel 1 for TPDOs with the numbers 37 to 40. If only two bytes have been defined in a PDO, then it masks just two bytes, although 4 bytes of mask information have been transmitted.

An activated bit in the mask means that monitoring is active for the corresponding bit in the PDO.

<b>Index</b>	0x2014 <sub>h</sub> to 0x2017 <sub>h</sub>
<b>Name</b>	tx_mask 1 to 4
<b>Object code</b>	ARRAY
<b>Number of elements</b>	2
<b>Data type</b>	UNSIGNED32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	tx_mask1 to 4_low
<b>Mode</b>	independent
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	—
<b>EEPROM</b>	no
<b>Default value</b>	FFFFFFFF <sub>h</sub>

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	tx_mask1 to 4_high
<b>Mode</b>	independent
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	—
<b>EEPROM</b>	no
<b>Default value</b>	FFFFFFFF <sub>h</sub>

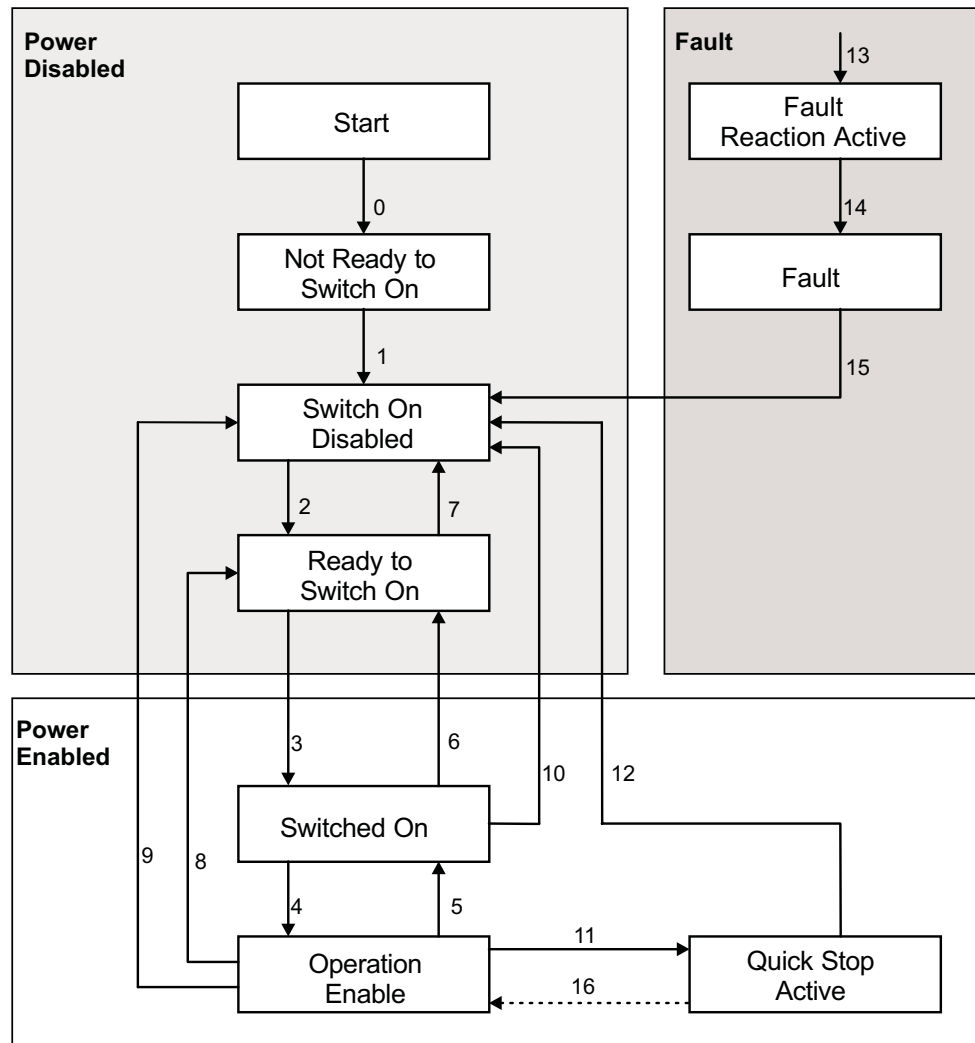
## IV.4 Device control (dc)

The device control of the SERVOSTAR™ can be used to carry out all the motion functions in the corresponding modes. The control of the SERVOSTAR™ 400/600 is implemented through a mode-dependent status machine. The status machine is controlled through the control word (⇒ IV.4.2.1).

The mode setting is made through the Object "Modes of Operation" (⇒ VI.3). The states of the status machine can be revealed by using the status word (⇒ IV.4.2.2).

IV.4.1 Status machine (DS402)

IV.4.1.1 States of the status machine



State	Description
Not Ready for Switch On	SERVOSTAR™ is not ready to switch on, there is no operational readiness (BTB/RTO) signalled from the controller program.
Switch On Disable	SERVOSTAR™ is ready to switch on, parameters can be transferred, the DC-link voltage can be switched on, motion functions cannot be carried out yet.
Ready to Switch On	DC-link voltage must be switched on, parameters can be transferred, motion functions cannot be carried out yet.
Switched On	DC-link voltage must be switched on, parameters can be transferred, motion functions cannot be carried out yet, output stage is switched on (enabled).
Operation Enable	No fault present, output stage is enabled, motion functions are enabled.
Quick Stop Active	Drive has been stopped with the emergency ramp, output stage is enabled, motion functions are enabled, response depends on SDO 605A <sub>n</sub> (⇒ VI.3)
Fault Reaction Active	not supported at present
Fault	not supported at present

#### IV.4.1.2 Transitions of the status machine

The state transitions are affected by internal events (e.g. switching off the DC-link voltage) and by the flags in the control word (bits 0,1,2,3,7).

Transition	Event	Action
0	Reset	Initialization
1	Initialization completed successfully. SERVOSTAR™ is ready to operate.	none
2	Bit 1 <i>Disable Voltage</i> and Bit 2 <i>Quick Stop</i> are set in the control word ( <i>Shutdown</i> command). DC-link voltage is present.	none
3	Bit 0 is also set ( <i>Switch On</i> command)	Output stage is switched on (enabled), provided that the hardware enable is present (logical AND). Drive has torque.
4	Bit 3 is also set ( <i>Enable Operation</i> command)	Motion function is enabled, depending on the mode that is set.
5	Bit 3 is canceled ( <i>Disable Operation</i> command)	Motion function is inhibited. Drive is stopped, using the relevant ramp (mode-dependent). The present position is maintained.
6	Bit 0 is canceled ( <i>Shutdown</i> command)	Output stage is disabled. Drive has no torque.
7	Bits 1/2 are canceled ( <i>Quick Stop / Disable Voltage</i> command)	none
8	Bit 0 is canceled ( <i>Shutdown</i> command)	Output stage is disabled. Drive has no torque.
9	Bit 1 is canceled ( <i>Disable Voltage</i> command)	Output stage is disabled. Drive has no torque.
10	Bits 1/2 are canceled ( <i>Quick Stop / Disable Voltage</i> command)	Motion function is enabled, depending on the mode that is set.
11	Bit 2 is canceled ( <i>Quick Stop</i> command)	Drive is stopped with the emergency braking ramp. The output stage remains enabled. Setpoints are canceled (motion block number, digital setpoint, speed for jogging or homing). Bit 2 must be set again before any further motion tasks can be performed.
12	Bit 1 is canceled ('Disable Voltage' command)	Output stage is disabled. Drive has no torque.
13	not supported at present	none
14	not supported at present	none
15	not supported at present	none
16	Bit 2 is set	Motion function is enabled again.



#### **Caution !**

***If the servo amplifier is operated through the control word / status word, then no control commands may be sent through another communication channel (RS232, CANopen, ASCII channel, Option board).***

## IV.4.2 Object description

### IV.4.2.1 SDO 6040<sub>h</sub>: Control word (DS402)

The control commands are built up from the logical combination of the bits in the control word and external signals (e.g enable output stage). The definitions of the bits are shown below:

<b>Index</b>	0x6040 <sub>h</sub>
<b>Name</b>	control word
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED16

<b>Mode</b>	all
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	—
<b>Value range</b>	0 ... 65535
<b>EEPROM</b>	no
<b>Default value</b>	0

#### Bit assignment in control word

Bit	Name	Bit	Name
0	Switch on	8	Pause/halt
1	Disable Voltage	9	reserved
2	Quick Stop	10	reserved
3	Enable Operation	11	Acknowledge lag/following error and response monitoring
4	Operation mode specific	12	Reset position
5	Operation mode specific	13	Manufacturer-specific
6	Operation mode specific	14	Manufacturer-specific
7	Reset Fault (only effective for faults)	15	Manufacturer-specific

#### Commands in the control word

Command	Bit 7 Fault Reset	Bit 3 Enable Operation	Bit 2 Quick Stop	Bit 1 Disable Voltage	Bit 0 Switch on	Transitions
Shutdown	X	X	1	1	0	2, 6, 8
Switch on	X	X	1	1	1	3
Disable Voltage	X	X	X	0	X	7, 9, 10, 12
Quick Stop	X	X	0	1	X	7, 10, 11
Disable Operation	X	0	1	1	1	5
Enable Operation	X	1	1	1	1	4, 16
Fault Reset	1	X	X	X	X	15

Bits marked by an X are irrelevant.

**Mode-dependent bits in control word**

The following table shows the mode-dependent bits in the control word. Only manufacturer-specific modes are supported at present. The individual modes are set by SDO 6060<sub>h</sub> *Modes of operation*.

Operation mode	No.	Bit 4	Bit 5	Bit 6
Position	FF <sub>h</sub>	reserved	reserved	reserved
Digital speed	FE <sub>h</sub>	reserved	reserved	reserved
Digital current	FD <sub>h</sub>	reserved	reserved	reserved
Analog speed	FC <sub>h</sub>	reserved	reserved	reserved
Analog current	FB <sub>h</sub>	reserved	reserved	reserved
Trajectory	FA <sub>h</sub>	reserved	reserved	reserved
Homing	F9 <sub>h</sub>	Start homing	reserved	reserved
Jogging	F8 <sub>h</sub>	reserved	reserved	reserved
Profile Position Mode (pp)	01 <sub>h</sub>	new_set_point	change_set_immediately	absolute / relative
Profile Velocity Mode (pv)	03 <sub>h</sub>	reserved	reserved	reserved
Homing Mode (hm)	06 <sub>h</sub>	homing_operation_start	reserved	reserved

**Description of the remaining bits in the control word**

The remaining bits in the control word are described below.

**Bit 8 Pause** If Bit 8 is set, then the drive halts (pauses) in all modes. The setpoints (speed for homing or jogging, motion task number, setpoints for digital mode) for the individual modes are retained.

**Bit 9,10** These bits are reserved for the drive profile (DS402).

**Bit 11 Acknowledge error** Setting Bit 11 acknowledges the response monitoring and/or the contouring error.

**Bit 12** Reset the position, taking account of the reference offset. (See also Homing type 6 in SDO 2024<sub>h</sub>, Sub-index 01<sub>h</sub>)

**Bit 13, 14, 15** These bits are manufacturer-specific, and reserved at present.

**IV.4.2.2****SDO 6041<sub>h</sub>: status word (DS402)**

The momentary state of the status machine can be read out with the aid of the status word (⇒ IV.3.2.1.1).

<b>Index</b>	0x6041 <sub>h</sub>
<b>Name</b>	Status word
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED16

<b>Mode</b>	all
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	—
<b>Value range</b>	0 ... 65535
<b>EEPROM</b>	yes
<b>Default value</b>	0

**Bit assignment in the status word**

Bit	Name	Bit	Name
0	Ready to switch on	8	Manufacturer-specific (reserved)
1	Switched on	9	Remote (not supported)
2	Operation enable	10	Target reached
3	Fault (in preparation)	11	Internal limit active (not supported)
4	Disable voltage	12	Operation mode specific (reserved)
5	Quick stop	13	Operation mode specific (reserved)
6	Switch on disabled	14	Manufacturer-specific (reserved)
7	Warning	15	Manufacturer-specific (reserved)

**States of the status machine**

State	Bit 6 switch on disable	Bit 5 quick stop	Bit 3 fault	Bit 2 operation enable	Bit 1 switched on	Bit 0 ready to switch on
Not ready to switch on	0	X	0	0	0	0
Switch on disabled	1	X	0	0	0	0
Ready to switch on	0	1	0	0	0	1
Switched on	0	1	0	0	1	1
Operation enabled	0	1	0	1	1	1
Fault	not supported at present					
Fault reaction active	not supported at present	X	X	X	X	15
Quick stop active	0	0	0	1	1	1

Bits marked by X are irrelevant

**Description of the remaining bits in the status word**

**Bit 4: voltage\_disable** The DC-link voltage is present if this bit is canceled.

**Bit 7: warning** There are several possible reasons for Bit 7 being set and this warning being produced. The reason for this warning can be revealed by using the SDO 1002<sub>n</sub> *manufacturer-specific status register*. (⇒ IV.2.1.3)

**Bit 8: Toggle-bit mode** Jogging, Homing ,Position, Positioning (pp), Homing (hm)  
The toggle-bit is always changed (i.e. set or reset) when a motion block has been successfully executed (incrementally precise in the target position!). The bit is not toggled if a motion block is canceled (e.g. through the STOP command or a lag/following error). The evaluation of the toggle-bit can be performed in combination with Bit 10 *target reached* (SDO 6041<sub>n</sub>) and Bit 16 *motion block active* (SDO 1002<sub>n</sub>). Evaluation of this bit makes sense if no change in Bit 10 or 16 would be visible, because of the motion block data (very short or identical motion blocks).

**Bit 9: remote** is not supported at present

**Bit 10: target\_reached** This is set when the drive has reached the target position.

**Bit 11: internal\_limit\_active** is not supported at present

### IV.4.2.3 SDO 6060<sub>h</sub>: modes\_of\_operation (DS402)

This Object is used to set the mode, which can be read out by SDO 6061<sub>h</sub>. Two types of operating mode can be distinguished:

#### manufacturer-specific operating modes

These modes of operation have been optimized to the functionality of the equipment.

#### operating modes as per CANopen drive profile DSP402

These operating modes are defined in the CANopen drive profile DSP402.

After the mode has been changed, the corresponding setpoint must be set once more (for instance, the homing velocity in the mode homing\_setpoint). If the position or jogging mode is stored, then the Homing mode is set after a RESET of the servo amplifier.

**An operating mode only becomes valid when it can be read by SDO 6061<sub>h</sub>.**



#### **WARNING:**

***Never change the mode while the motor is running!***

***When the amplifier is enabled, a mode change is only permissible at zero speed.***

***Set the speed setpoint to 0 before changing over.***

<b>Index</b>	0x6060 <sub>h</sub>
<b>Name</b>	mode of operation
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER8

<b>Mode</b>	all
<b>Access</b>	w
<b>PDO mapping</b>	possible
<b>Unit</b>	—
<b>Value range</b>	—
<b>EEPROM</b>	no
<b>Default value</b>	—

Mode	decimal	hex.	Comments
	-10 ... -128	F8 <sub>h</sub> ... 80 <sub>h</sub>	reserved
Electrical gearing	-9	F7 <sub>h</sub>	—
Jogging	-8	F8 <sub>h</sub>	—
Homing	-7	F9 <sub>h</sub>	—
Trajectory	-6	FA <sub>h</sub>	—
Analog current	-5	FB <sub>h</sub>	—
Analog speed	-4	FC <sub>h</sub>	—
Digital current	-3	FD <sub>h</sub>	—
Digital speed	-2	FE <sub>h</sub>	—
Position	-1	FF <sub>h</sub>	mode required for motion tasks
—	0	0	reserved as per DSP402
Positioning (pp)	1	1 <sub>h</sub>	as per DSP402
Speed (vl)	2	2 <sub>h</sub>	not supported
Speed (pv)	3	3 <sub>h</sub>	as per DSP 402
Torque (tq)	4	4 <sub>h</sub>	as per DSP 402 (not supported at present)
—	5	5 <sub>h</sub>	reserved
Homing (hm)	6	6 <sub>h</sub>	as per DSP 402
Interpolation	7	7 <sub>h</sub>	as per DSP 402 (not supported)
—	8 ... 127	8 <sub>h</sub> ... 7F <sub>h</sub>	reserved

#### IV.4.2.4 SDO 6061<sub>h</sub>: mode\_of\_operation\_display (DS402)

This Object can be used to read the mode that is set by SDO 6060<sub>h</sub>. An operating mode only becomes valid when it can be read by SDO 6061<sub>h</sub> (see also SDO 6060<sub>h</sub>).

<b>Index</b>	0x6061 <sub>h</sub>
<b>Name</b>	mode_of_operation_display
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER8

<b>Mode</b>	all
<b>Access</b>	w
<b>PDO mapping</b>	possible
<b>Unit</b>	—
<b>Value range</b>	—
<b>EEPROM</b>	no
<b>Default value</b>	—

### IV.5 Factor Groups (fg)(DS402)

#### IV.5.1 General Information

##### IV.5.1.1 Factors

There is a possibility to convert between physical dimensions and sizes, and the internal units used in the device (increments). Several factors can be implemented. This chapter describes how these factors influence the system, how they are calculated and which data are necessary to build them.

**Normalized parameters are denoted by an asterisk \*.**

##### IV.5.1.2 Relationship between Physical and Internal Units

The factors defined in the factor group set up a relationship between device-internal units (increments) and physical units.

The factors are the result of the calculation of two parameters called dimension index and notation index. The dimension index indicates the physical dimension, the notation index indicates the physical unit and a decimal exponent for the values. These factors are directly used to normalize the physical values.

The notation index can be used in two ways:

- For a unit with decimal scaling and notation index < 64, the notation index defines the exponent/decimal place of the unit.
- For a unit with non-decimal scaling and notation index > 64, the notation index defines the sub-index of the physical dimension of the unit.

## IV.5.2 Object Description

IV.5.2.1 SDO 608B<sub>h</sub>: velocity\_notation\_index (DS402)

<b>Index</b>	0x608B <sub>h</sub>
<b>Name</b>	velocity_notation_index
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER8

<b>Mode</b>	all
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	-128 ... 127
<b>EEPROM</b>	no
<b>Default value</b>	0

This Object determines the notation for SDO 6081<sub>h</sub> *profile\_velocity*. In combination with SDO 608C<sub>h</sub> *velocity\_dimension\_index*, the following *basic units* can be represented:

physical dimension	units	velocity dimension index	velocity notation index
manufacturer-specific	incr/sec	0	0
revolution	revs/min	11	73

IV.5.2.2 SDO 608C<sub>h</sub>: velocity\_dimension\_index (DS402)

<b>Index</b>	0x608C <sub>h</sub>
<b>Name</b>	velocity_dimension_index
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED8

<b>Mode</b>	all
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	0 ... 255
<b>EEPROM</b>	no
<b>Default value</b>	0

This Object determines the dimension for SDO 6081<sub>h</sub> *profile\_velocity*. In combination with SDO 608B<sub>h</sub> *velocity\_notation\_index*, the following *basic units* can be represented:

physical dimension	units	velocity dimension index	velocity notation index
manufacturer-specific	incr/sec	0	0
revolutions	revs/min	11	73

### IV.5.2.3 SDO 6093<sub>h</sub>: position\_factor (DS402)

The position factor converts the target position into the internal data format of the SERVOSTAR™ 400/600 (increments).

The position controller can be run with the resolution set to 20 bits/turn or 16 bits/turn (see SDO 35D1<sub>h</sub> and the ASCII command PRBASE). The numerator and the feed constant can be used to set up any value of scaling.

$$\text{position\_factor} = \frac{\text{position\_encoder\_resolution} \times \text{gear\_ratio}}{\text{feed\_constant}}$$

- **position\_encoder\_resolution**  
resolution of the position controller is  $2^{20}$  or  $2^{16}$
- **gear\_ratio**  
transmission ratio for the gearing that is used
- **feed\_constant**  
the feed constant of the output side of the drive gearing

<b>Index</b>	0x6093 <sub>h</sub>
<b>Name</b>	position_factor
<b>Object code</b>	ARRAY
<b>Number of elements</b>	2
<b>Data type</b>	UNSIGNED32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	numerator
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	increments [incr]
<b>Value range</b>	0 ... ( $2^{32}-1$ )
<b>EEPROM</b>	no
<b>Default value</b>	$2^{20}$

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	feed_constant
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	0 ... ( $2^{32}-1$ )
<b>EEPROM</b>	no
<b>Default value</b>	10000

**Example:** One turn is to be equivalent to 10000 increments. The gear ratio is 1.

$$\text{position\_factor} = \frac{2^{20} \text{ incr}}{10000 \text{ incr}}$$

- ⇒ **Numerator:**  $2^{20}$       **Feed constant:** 10000
- ⇒ Setpoint provision in [incr/turn] for SDO 607A<sub>h</sub> (target\_position).

#### IV.5.2.4 SDO 6094<sub>h</sub>: velocity\_encoder\_factor (DS402)

The velocity\_encoder\_factor converts the target speed (revs/min) or velocity (incr/sec) into the internal data format of the SERVOSTAR™ 400/600 (increments).

The velocity\_encoder\_factor is calculated as:

$$\text{velocity\_encoder\_factor} = \frac{\text{velocity\_encoder\_resolution} \times \text{gear\_ratio} \times \text{position\_unit} \times \text{Fvelocity}(\text{notation\_index})}{\text{feed\_constant} \times \text{velocity\_unit} \times \text{sec} \times \text{Fposition}(\text{notation\_index})}$$

- **velocity\_encoder\_resolution** the resolution of the speed  $2^{20}$
- **gear\_ratio** the transmission ratio for the gearing that is used
- **position\_unit** in meters
- **Fposition(notation\_index)** in dimension\_index = 1, notation\_index = 0 [m]
- **feed\_constant** the feed constant for the output side of the drive gearing
- **velocity\_unit** in [m/s]
- **Fvelocity (notation\_index)** in dimension\_index = 13, notation\_index = 0 [m / s]

(see also SDO 606B<sub>h</sub> *velocity\_notation\_index* and SDO 606C<sub>h</sub> *velocity\_dimension\_index*)

<b>Index</b>	0x6094 <sub>h</sub>
<b>Name</b>	velocity_encoder_factor
<b>Object code</b>	ARRAY
<b>Number of elements</b>	2
<b>Data type</b>	UNSIGNED32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	numerator
<b>Mode</b>	pv
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	increments [incr]
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>EEPROM</b>	no
<b>Default value</b>	0

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	divisor
<b>Mode</b>	pv
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	seconds [s]
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>EEPROM</b>	no
<b>Default value</b>	0

**Example:** The speed-setpoint provision is to be made in revolutions per minute (revs/min). The transmission ratio and feed constant are 1.

$$\text{velocity\_encoder\_factor} = \frac{2^{20}}{1} \frac{1}{1} \frac{\text{incr}}{\text{s}}$$

Expanded for revs/min:

$$\text{velocity\_encoder\_factor} = \frac{2^{20}}{1} \frac{1}{1} \frac{[\text{m}]}{[\text{m/s}]} \frac{\text{incr}}{\text{s}} \times \frac{1}{60[\text{s/min}]} = \frac{2^{20}}{60} \frac{\text{incr}}{\text{s}}$$

⇒ **Numerator** :  $2^{20}$       **Divisor** : 60

⇒ Setpoint provision in [revs/min] for SDO 60FF<sub>h</sub> *target\_velocity / velocity units*

⇒ Setpoint provision in [incr/s] for SDO 6081<sub>h</sub> *Profile\_velocity / speed units*

**Note:** Since the speed controller operates internally with a resolution of  $2^{20}$  bits/turn, regardless of the resolution of the encoder system, the following expression is used to calculate the operating mode pv (for revolutions per minute):

$$\text{increments} = \frac{262144}{1875} \times \text{speed setpoint}[\text{min}^{-1}]$$

This incremental setpoint provision should be used for cyclical applications (for example, position control, 4ms cycle). The advantages are: no rounding error, lower CPU loading.

The above calculation is valid if **divisor or numerator is set to 0**.

The *velocity\_encoder\_factor* also affects SDO 6081<sub>h</sub> *profile\_velocity*. In order to be able to use this factor for the position mode (pp) as well, the internal gearing factors PGEARI and PGEARO must be equal (PGEARI = PGEARO; SDO 2020<sub>h</sub> Sub-index: 08<sub>h</sub>, 09<sub>h</sub>). If the **divisor or numerator is set to 0**, then the internal scaling is used: *increments per cycle (250 μs)*.

#### IV.5.2.5 SDO 6097<sub>h</sub>: acceleration\_factor (DS402)

The *acceleration\_factor* converts the acceleration [unit: /s<sup>2</sup>] into the internal format of the SERVOSTAR™ 400/600.

At present, the numerator and divisor are read-only. The values are set to 1. If the *acceleration\_factor* is 1, then the ramp settings (SDO 6083<sub>h</sub> *profile\_acceleration* and SDO 6084<sub>h</sub> *profile\_deceleration*) will be provided as acceleration times [ms] required to reach the target speed (SDO 6081<sub>h</sub> *profile\_velocity*).

<b>Index</b>	0x6097 <sub>h</sub>
<b>Name</b>	acceleration_factor
<b>Object code</b>	ARRAY
<b>Number of elements</b>	2
<b>Data type</b>	UNSIGNED32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	numerator
<b>Mode</b>	pp, pv
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Unit</b>	increments [incr]
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>EEPROM</b>	no
<b>Default value</b>	0

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	divisor
<b>Mode</b>	pp, pv
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Unit</b>	—
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>EEPROM</b>	no
<b>Default value</b>	0

## IV.6 Manufacturer-specific Current and Speed Mode

### IV.6.1 SDO 2060<sub>h</sub>: Digital current or speed setpoint

<b>Index</b>	2060 <sub>h</sub>
<b>Brief description</b>	digital current/speed setpoint
<b>Unit</b>	A or /min
<b>Access</b>	r/w
<b>PDO mapping</b>	possible (pre-mapped to selectable RPDO 22)
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

#### Description:

This Object is used for the transfer of digital setpoint values which are evaluated according to the digital mode that has been set (mode FD<sub>h</sub> = digital current, mode FE<sub>h</sub> = digital speed, adjustable via SDO 6060<sub>h</sub>). The normalizations are as follows:

$$\text{Current: } I[\text{A}] = \frac{\text{digital current setpoint}}{1640} \times I_{\text{max}}$$

$$\text{Speed: } n[\text{min}^{-1}] = \frac{1875}{262144} \times \text{digital speed setpoint}$$

A new setpoint only becomes valid after a fresh *Enable Operation* (via SDO 6040<sub>h</sub>, control word)



*The SERVOSTAR™ 400/600 position controller is switched off while speed or current control is activated.*

## IV.7 Setup data for manufacturer-specific Jogging/Homing mode

### IV.7.1 SDO 2024<sub>h</sub>: Setup operation for the Position mode (SERVOSTAR™)

<b>Index</b>	2024 <sub>h</sub>
<b>Brief description</b>	parameters for homing and jogging
<b>Object code</b>	RECORD
<b>Number of elements</b>	7

#### Description:

This Index is used to enter parameters which are important for the homing and jogging modes of operation.

**Description of the Sub-indices:**

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	homing type
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Value range</b>	0..6
<b>Default value</b>	0

Description: This Index is used to set the type of homing movement.  
The following settings are possible:

Value	Meaning
0	The reference mark is set to be at the present position. The actual position that is signaled is then the same as the preset reference offset.
1	Homing to reference switch, followed by search of the resolver zero mark.
2	Homing to limit switch, followed by search of the resolver zero mark.
3	Homing to reference switch, without subsequent search of the resolver zero mark.
4	Homing to limit-switch, without subsequent search of the resolver zero mark.
5	Homing within a single turn of the motor to the resolver zero mark. The direction of movement is given by the Sub-index 02 <sub>h</sub> , whereby: 0: negative direction of motion 1: positive direction of motion 2: motor turns in the direction which gives the shortest path to the resolver zero mark within a single turn.
6	The reference mark is set to the value of the reference offset at the present setpoint position of the position controller. The new actual position retains the same distance to the setpoint position as before.

Please note:

For homing types 1 and 3, a digital input must be configured as the zero-position input (Home position). For homing types 2 and 4, a digital input must be configured as a hardware limit-switch.

For homing types 1 to 5, the setting of the index pulse offset for the ROD output is taken into account (ASCII command ENCZERO), i.e. the zero point is positioned so that both the output of the index pulse and the display of the 0-position take place at the point of the index pulse offset.

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	homing direction
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Value range</b>	0 ... 2
<b>Default value</b>	0

Description: This Index is used to define the movement direction for homing types 1 to 5. The values have the following interpretation:  
0: negative direction of motion  
1: positive direction of motion  
2: the motor turns in the direction which gives the shortest path to the resolver zero mark within a single turn (only relevant for homing type 5).

<b>Sub-index</b>	03 <sub>h</sub>
<b>Brief description</b>	velocity for homing
<b>Unit</b>	µm/s
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to define the velocity for homing movements.

<b>Sub-index</b>	04 <sub>h</sub>
<b>Brief description</b>	acceleration ramp for homing/jogging
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 32767
<b>Default value</b>	10

Description: This Index is used to set the acceleration ramp for homing and jogging. The ramp has a trapezoidal form. The time that is set refers to the preset velocities homing and jogging movements.

<b>Sub-index</b>	05 <sub>h</sub>
<b>Brief description</b>	braking ramp for homing/jogging
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 32767
<b>Default value</b>	10

Description: This Index is used to set the acceleration ramp for homing and jogging. The ramp has a trapezoidal form. The time that is set refers to the preset velocities homing and jogging movements.  
The emergency stop ramp (ASCII parameter DECSTOP) is used as the braking ramp for homing movements to a hardware limit-switch.

<b>Sub-index</b>	06 <sub>h</sub>
<b>Brief description</b>	reference offset
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to set the reference offset, i.e. the actual position value displayed when homing has been completed (SDO 2070<sub>h</sub>, Sub-index 06<sub>h</sub>).

<b>Sub-index</b>	07 <sub>h</sub>
<b>Brief description</b>	velocity for jogging t
<b>Unit</b>	µm/s
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to define the jogging velocity.

## IV.8 Positioning data for the positioning mode (SERVOSTAR™)

### IV.8.1 SDO 2020<sub>h</sub>: Position controller

<b>Index</b>	2020 <sub>h</sub>
<b>Brief description</b>	parameter for position controller
<b>Object code</b>	RECORD
<b>Number of elements</b>	10

#### Description:

This Index is used to enter all the general parameters for the *Position* mode.

#### Description of the Sub-indices:

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	axis type
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Value range</b>	0, 1
<b>Default value</b>	0

Description: Describes the type of mechanical axis.

**Value 0:** Linear axis. Positions are counted from a defined reference mark. This must be defined by making a homing movement or setting a reference point. The movement of the axis will be restricted by software limit-switches, if they have been configured.

**Value 1:** Rotary axis. A reference position is not required. The position is set to 0 at the start of each motion block or jogging mode. Movement is not limited by software limited switches.

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	In-Position window
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	4000 <sub>h</sub>

Description: Defines a target window for positioning. Bit 19 of the manufacturer-specific status register is set when the window limits are reached, and the selected output goes *High* (if the corresponding configuration was implemented).

<b>Sub-index</b>	03 <sub>h</sub>
<b>Brief description</b>	maximum contouring error
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	40000 <sub>h</sub>

Description: Defines a maximum value for the contouring (lag) error. The drive will be stopped if the contouring error exceeds this value. Bit 2 of the manufacturer-specific status register is used to indicate an excessive contouring error. The contouring error will not be monitored if the value is set to 0.

<b>Sub-index</b>	04 <sub>h</sub>
<b>Brief description</b>	position register 1
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: Depending on the configuration, if the position goes above or below the preset position value, either a threshold bit (Bit 22 of the manufacturer-specific status register) will be set or the axis will be stopped. (going below software-limit switch 1 : Bit 5 = 1 in the manufacturer-specific status register).

<b>Sub-index</b>	05 <sub>h</sub>
<b>Brief description</b>	position register 2
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: Depending on the configuration, if the position goes above or below the preset position value, either a threshold bit (Bit 23 of the manufacturer-specific status register) will be set or the axis will be stopped. (going above software-limit switch 2 : Bit 6 = 1 in the manufacturer-specific status register).

<b>Sub-index</b>	06 <sub>h</sub>
<b>Brief description</b>	position register 3
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: Depending on the configuration, if the position goes above or below the preset position value, a threshold bit (Bit 24 of the manufacturer-specific status register) will be set.

<b>Sub-index</b>	07 <sub>h</sub>
<b>Brief description</b>	Position register 4
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: Depending on the configuration, if the position goes above or below the preset position value, a threshold bit (Bit 25 of the manufacturer-specific status register) will be set.

<b>Sub-index</b>	08 <sub>h</sub>
<b>Brief description</b>	resolution / denominator of the gearing ratio
<b>Unit</b>	revs (turns)
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	1 ... $(2^{32}-1)$
<b>Default value</b>	1

Description: The ratio of the values of Sub-indices 08<sub>h</sub> and 09<sub>h</sub> provides the mechanical resolution of the axis in µm/turn.

<b>Sub-index</b>	09 <sub>h</sub>
<b>Brief description</b>	resolution / numerator of the gearing ratio
<b>Unit</b>	µm
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	1 ... $(2^{32}-1)$
<b>Default value</b>	1

Description: The ratio of the values of Sub-indices 08<sub>h</sub> and 09<sub>h</sub> provides the mechanical resolution of the axis in µm/turn.

<b>Sub-index</b>	0A <sub>h</sub>
<b>Brief description</b>	count direction
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Value range</b>	0, 1
<b>Default value</b>	1

Description: The value gives the count direction for current, speed, and position control. A value of 1 means that the positive count direction has been selected. If a positive setpoint is provided, the motor shaft rotates in a clockwise direction (looking at the shaft end).

## IV.8.2 SDO 2022<sub>h</sub>: Position data for Position mode

<b>Index</b>	2022 <sub>h</sub>
<b>Brief description</b>	motion task parameter
<b>Object code</b>	RECORD
<b>Number of elements</b>	12

### Description:

This Index is used to enter all the parameters that refer to a direct motion task or a motion task which is stored in the controller. (See ASCII command *ORDER*)

### Description of the Sub-indices:

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	position
<b>Mode</b>	position
<b>Access</b>	r/w
<b>PDO mapping</b>	possible (pre-mapped to selectable RPDO 34)
<b>Data type</b>	INTEGER32
<b>Unit</b>	increments or $\mu\text{m}$
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>EEPROM</b>	no
<b>Default value</b>	0

Description: This Index is used to enter the target position (absolute motion task) or the distance to be moved (relative motion task). The choice is defined by Bit 0 of the motion task type. Bit 13 of the motion task type defines whether the given value is to be interpreted as an increment or as an SI value.

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	weighted velocity setpoint
<b>Mode</b>	position
<b>Access</b>	r/w
<b>PDO mapping</b>	possible (pre-mapped to selectable RPDO 34)
<b>Data type</b>	INTEGER16
<b>Unit</b>	increments/s or $\mu\text{m/s}$
<b>Value range</b>	-32768 ... 32767
<b>EEPROM</b>	no
<b>Default value</b>	0

Description: This Index is used to enter the target velocity for motion tasks. It is weighted by Sub-index 0D<sub>h</sub>. If the value is defined as an SI unit by motion task type Bit 13 = 1, then the incremental velocity  $v_i$

$$\text{is given by } v_i = v_{\text{SI}} \times \frac{\text{PGEARO}}{\text{PGEARI} \times 4000},$$

whereby PGEARO (SDO 2020<sub>h</sub>, Sub-index 08<sub>h</sub>) contains the number of increments that must be moved to cover a distance of PGEARI (SDO 2020<sub>h</sub>, Sub-index 09<sub>h</sub>). It must be noted here that one revolution of the motor corresponds to  $2^{20}$  increments = 1048576.

<b>Sub-index</b>	03 <sub>h</sub>
<b>Brief description</b>	motion task type
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Unit</b>	—
<b>Value range</b>	0 ... FFFF <sub>h</sub>
<b>EEPROM</b>	no
<b>Default value</b>	0

Description: This Index is used to set motion parameters for the motion task.  
The interpretation of the bits is shown in the following tables.

Bit	Value	Meaning
0	0x0001 <sub>h</sub>	Bit for type of relative/absolute motion block (see table 2)
1	0x0002 <sub>h</sub>	Bit for type of relative motion block (see table 2)
2	0x0004 <sub>h</sub>	Bit for type of relative motion block (see table 2)
3	0x0008 <sub>h</sub>	=0 No following (next) motion block available. Drive stops when target position has been reached. =1 Following motion block available. Next motion block starts automatically when target position has been reached. The number of the next motion block is given by the command <i>O FN</i> .
4	0x0010 <sub>h</sub>	Bit for type of next motion block (see table 3)
5	0x0020 <sub>h</sub>	Bit for type of next motion block (see table 3)
6	0x0040 <sub>h</sub>	Bit for type of next motion block (see table 3)
7	0x0080 <sub>h</sub>	Bit for type of next motion block (see table 3)
8	0x0100 <sub>h</sub>	Bit for type of next motion block (see table 3)
9	0x0200 <sub>h</sub>	reserved
10	0x0400 <sub>h</sub>	reserved
11	0x0800 <sub>h</sub>	reserved
12	0x1000 <sub>h</sub>	=0 Acceleration and deceleration are given as acceleration/deceleration time (in msec) from 0 to target velocity (or reversed). =1 Acceleration and deceleration are given mm/sec <sup>2</sup> . (see also commands: <i>O ACC1</i> , <i>O ACC2</i> , <i>O DEC1</i> , <i>O DEC2</i> ).
13	0x2000 <sub>h</sub>	=0 Target position and target velocity are interpreted as increments. There is no conversion of the values. =1 Before the start of the motion block, the target position and target velocity are converted into increments. The conversion uses the parameters <i>PGEARI</i> and <i>PGEARO</i> . (see also commands: <i>O S</i> , <i>O V</i> , <i>PGEARI</i> , <i>PGEARO</i> )
14	0x4000 <sub>h</sub>	=0 When the motion block starts, the velocity for the motion block is taken as the target velocity. =1 The target velocity is provided as an analog value (SW1) at the start of the motion block. The analog SW1 value is read at the start of the motion block, and taken as the target velocity. (scaling: 10V=VSCALE1). The sign of the SW1 voltage is ignored.
15	0x8000 <sub>h</sub>	Bit 3 for type of relative motion block (see separate table)

**Type of relative/absolute motion block**

Bit 0	Bit 1	Bit 2	Bit 15	Meaning
0	x	x	x	Absolute motion block: the position given in the motion block is taken as the target position.
1	0	0	x	Relative motion block: the position given in the motion block is taken as the distance to be moved. The target is calculated according to the status of the IN-POSITION signal: IN-POSITION=1: new target position = last target position + movement distance IN-POSITION=0: new target position = actual position + movement distance
1	1	0	x	Relative motion block: the position given in the motion block is taken as the distance to be moved. new target position = last target position + movement distance
1	0	1	x	Relative motion block: the position given in the motion block is taken as the distance to be moved. new target position = actual position + movement distance
1	1	1	0	Relative motion block: the position given in the motion block is taken as the distance to be moved. new target position = positive latch position + movement distance (see also <i>LATCH32</i> command)
1	1	1	1	Relative motion block: the position given in the motion block is taken as the distance to be moved. new target position = negative latch position + movement distance (see also <i>LATCH32N</i> command)

**Type of next motion block**

Bit 4 NOBRAKE	Bit 5 FOL_IO	Bit 6 HI/LO	Bit 7 FTIME	Bit 8 VTARG	Meaning
0	0	0	0	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. Afterwards, the next motion block is started.
1	0	0	0	0	Flying changeover to the next motion task at the target position. The drive moves with the target velocity up to the target position of the first motion block. It then changes over to the next motion block at full speed.
1	0	0	0	1	Flying changeover to the next motion task at the target position. The changeover point for the next motion task is advanced, so that the drive already has the target velocity for the next next motion block when it reaches the target position of the first motion block.
0	1	0	0	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. The next motion block is started when the pre-defined input (function INxMODE=15) goes <i>LOW</i> .
0	1	1	0	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. The next motion block is started when the pre-defined input (function INxMODE=15) goes <i>HIGH</i> .
0	0	0	1	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. The next motion block is started when the pre-programmed delay time (O_FT) has elapsed.
0	1	0	1	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. The next motion block is started when the pre-defined input (function INxMODE=15) goes <i>LOW</i> , or the pre-programmed delay time (O_FT) has elapsed.
0	1	1	1	0	Changeover to next motion task with braking. The drive brakes to the target position of the first motion block. The next motion block is started when the pre-defined input (function INxMODE=15) goes <i>HIGH</i> or the pre-programmed delay time (O_FT) has elapsed.

<b>Sub-index</b>	04 <sub>h</sub>
<b>Brief description</b>	trajectory
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	possible (pre-mapped to selectable RPDO 33)
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: Under development

<b>Sub-index</b>	05 <sub>h</sub>
<b>Brief description</b>	motion task number
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	possible (pre-mapped to selectable RPDO 35)
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 180, 129 ... 255
<b>Default value</b>	0

Description: This Index gives the number of the selected motion task. Motion tasks 1 to 180 are EEPROM motion blocks, and motion tasks 192 to 255 are RAM motion blocks. The RAM motion blocks are loaded with the first 64 EEPROM motion blocks when the servo amplifier is switched on or reset. Motion block 0 is also a RAM motion block, which is used as a copy buffer for motion tasks, and also to hold the motion task data for a direct motion task (RPDO 34).

<b>Sub-index</b>	06 <sub>h</sub>
<b>Brief description</b>	run-up time (acceleration)
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 65535
<b>Default value</b>	0

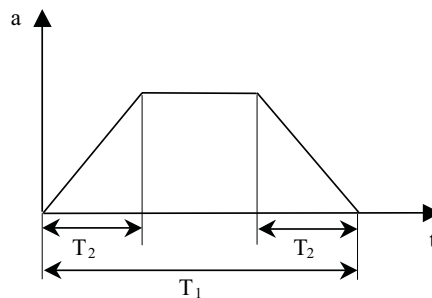
Description: This Index is used to define the total time taken to run up to the target velocity for the motion task. The value chosen for Sub-index 08<sub>h</sub> sets the form of the acceleration ramp.

<b>Sub-index</b>	07 <sub>h</sub>
<b>Brief description</b>	braking time (deceleration)
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 65535
<b>Default value</b>	0

Description: This Index is used to define the total time taken to brake down to velocity 0 (standstill) at the target position. The value chosen for Sub-index 09<sub>h</sub> sets the form of the deceleration ramp.

<b>Sub-index</b>	08 <sub>h</sub>
<b>Brief description</b>	jolt (acceleration) limiting (under development)
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 65535
<b>Default value</b>	0

Description: This Index sets the form of the acceleration ramp. The value chosen must be smaller than half of the run-up time (Sub-index 06<sub>h</sub>). The following diagram illustrates the relationships:



$T_1$  corresponds to the Sub-index 06<sub>h</sub> and  $T_2$  to Sub-index 08<sub>h</sub>.

If  $T_2 = 0$ , then a trapezoidal acceleration ramp is used.

If  $T_2 = \frac{T_1}{2}$  then an approximately  $\sin^2$  ramp is used.

<b>Sub-index</b>	09 <sub>h</sub>
<b>Brief description</b>	jolt (deceleration) limiting (under development)
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	0 ... 65535
<b>Default value</b>	0

Description: This Index defines the form of the braking/deceleration ramp. The value chosen must be smaller than half of the braking time (Sub-index 07<sub>h</sub>). Jolt (deceleration) limiting functions in the same way as jolt (acceleration)

<b>Sub-index</b>	0A <sub>h</sub>
<b>Brief description</b>	number of the next motion task
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	0 ... 180, 192 ... 255
<b>Default value</b>	0

Description: This Index is used to set the number of the next motion task. The setting of Sub-index 03<sub>h</sub>, Bit 3, decides whether this is used to continue.

<b>Sub-index</b>	0B <sub>h</sub>
<b>Brief description</b>	start delay for next motion task
<b>Unit</b>	ms
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	1 ... 65535
<b>Default value</b>	0

Description: This Object is used to set a delay time for the start of the next motion task. To do this, the function must be enabled through Sub-index 03<sub>h</sub>, Bit 7.

<b>Sub-index</b>	0C <sub>h</sub>
<b>Brief description</b>	copy a motion task
<b>Unit</b>	—
<b>Access</b>	w
<b>PDO mapping</b>	not possible
<b>Data type</b>	2 x UNSIGNED16
<b>Value range</b>	0 ... 180, 192... 255
<b>Default value</b>	0, 0

Description: This Object can be used to copy motion tasks. The number that appears first in the CAN telegram defines the source motion task, the following number defines the target motion task.

<b>Sub-index</b>	0D <sub>h</sub>
<b>Brief description</b>	velocity weighting factor
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED16
<b>Value range</b>	0 ... 65535
<b>Default value</b>	1

Description: This Object sets a multiplying factor for the velocity given in the RPDO motion block.

<b>Sub-index</b>	0E <sub>h</sub>
<b>Brief description</b>	velocity for direct motion task
<b>Unit</b>	increments / 250μs, or dependent on resolution
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Object defines the velocity for the direct motion task (motion block 0). The type of motion task then determines whether the velocity is evaluated in increments or in SI units.

## IV.9 Latch function

### IV.9.1 SDO 2026<sub>h</sub>: Latch enable

<b>Index</b>	2026 <sub>h</sub>
<b>Brief description</b>	enable the latch function for CAN
<b>Object code</b>	RECORD
<b>Number of elements</b>	1

Description of the Sub-index:

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	enable the latch function for CAN
<b>Unit</b>	—
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Data type</b>	UIINTEGER8
<b>Value range</b>	0, 1
<b>Default value</b>	1

Description:

SERVOSTAR™ 400/600 provides the option of acquiring an actual position with high precision (acquisition time < 1 μs) via a latch input (input 2, IN2MODE 26, can also be configured through SDO 3565<sub>h</sub>, Sub-index 01<sub>h</sub>). SDO 2026<sub>h</sub> can be used to decide whether a latching pulse is reported via CAN. A value of 0 means it is inhibited.

## IV.10 Manufacturer-specific actual values

### IV.10.1 SDO 2070<sub>h</sub>: Actual values

<b>Index</b>	2070 <sub>h</sub>
<b>Brief description</b>	actual values
<b>Object code</b>	RECORD
<b>Number of elements</b>	16

**Description:**

This Index makes relevant actual values available from the SERVOSTAR™ 400/600.

**Description of the Sub-indices:**

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	actual position
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	possible (pre-mapped to selectable TPDO 22, TPDO 32)
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... 16777215
<b>Default value</b>	0

Description: This Index is used to read the motor position within 16 turns/revolutions. One turn is resolved with 20 bits, in increments.  
So: 1 turn ⇒ 2<sup>20</sup> increments ⇒ 1048576 increments

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	actual speed
<b>Unit</b>	min <sup>-1</sup>
<b>Access</b>	r
<b>PDO mapping</b>	possible (pre-mapped to selectable TPDO 22, TPDO 32)
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... 1677215
<b>Default value</b>	0

Description: This Index is used to read the motor speed.  
The actual speed is given by:  

$$n[\text{min}^{-1}] = 1875 / 262144 \times (\text{speed value as read})$$

<b>Sub-index</b>	03 <sub>h</sub>
<b>Brief description</b>	incremental actual position
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	possible (pre-mapped to selectable TPDO 33)
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index can be used to read the incremental value for the actual position.  
One turn is resolved with 20 bits, in increments.  
So: 1 turn ⇒ 2<sup>20</sup> increments ⇒ 1048576 increments

<b>Sub-index</b>	04 <sub>h</sub>
<b>Brief description</b>	read the 16-bit position latch
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	possible
<b>Data type</b>	INTEGER16
<b>Value range</b>	-(2 <sup>15</sup> ) ... (2 <sup>15</sup> -1)
<b>Default value</b>	0

Description: This Index is used to read the 16-bit position stored in the latch.  
The position is given as increments within a single turn.  
The output is not affected by the gearing factor or the Factor Groups.

<b>Sub-index</b>	05 <sub>h</sub>
<b>Brief description</b>	read the 32-bit position latch
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> ) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index is used to read the 32-bit position stored in the latch.  
The position is given as increments within a single turn.  
The output is not affected by the gearing factor or the Factor Groups.

<b>Sub-index</b>	06 <sub>h</sub>
<b>Brief description</b>	SI actual position
<b>Unit</b>	µm
<b>Access</b>	r
<b>PDO mapping</b>	possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1)..(2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index can be used to read the actual position in SI units.  
The ratio of distance actually travelled to motor revolutions is given by

$$S_{SI} = S_{inkr} \times \frac{PGEARI}{PGEARO}$$

whereby PGEARO (SDO 2020<sub>h</sub>, Sub-index 08<sub>h</sub>) contains the number of increments that must moved to cover a distance of PGEARI (SDO 2020<sub>h</sub>, Sub-index 09<sub>h</sub>). It must be noted that one turn of the motor corresponds to 2<sup>20</sup> = 1048576 increments.

<b>Sub-index</b>	07 <sub>h</sub>
<b>Brief description</b>	SI actual velocity
<b>Unit</b>	µm/s
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index can be used to read the actual speed in SI units.

<b>Sub-index</b>	08 <sub>h</sub>
<b>Brief description</b>	lag/following error
<b>Unit</b>	µm
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index can be used to read out the momentary lag error, measured in SI units.

<b>Sub-index</b>	09 <sub>h</sub>
<b>Brief description</b>	rms (effective) current
<b>Unit</b>	mA
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... 2 * rated current [mA]
<b>Default value</b>	0

Description: The Index can be used to read out the momentary rms (effective) current.

<b>Sub-index</b>	0A <sub>h</sub>
<b>Brief description</b>	speed
<b>Unit</b>	min <sup>-1</sup>
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to read out the momentary speed measurement.

<b>Sub-index</b>	0B <sub>h</sub>
<b>Brief description</b>	heat sink temperature
<b>Unit</b>	°C
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to read out the heat sink temperature.

<b>Sub-index</b>	0C <sub>h</sub>
<b>Brief description</b>	internal temperature
<b>Unit</b>	°C
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to read the internal temperature of the servo amplifier.

<b>Sub-index</b>	0D <sub>h</sub>
<b>Brief description</b>	DC-link (DC-bus) voltage
<b>Unit</b>	V
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to read out the momentary DC-bus voltage.

<b>Sub-index</b>	0E <sub>h</sub>
<b>Brief description</b>	ballast power
<b>Unit</b>	W
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	0

Description: This Index is used to read out the momentary ballast power.

<b>Sub-index</b>	0F <sub>h</sub>
<b>Brief description</b>	I <sup>2</sup> t loading
<b>Unit</b>	%
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index is used to read out the I<sup>2</sup>t loading.

<b>Sub-index</b>	10 <sub>h</sub>
<b>Brief description</b>	operating time
<b>Unit</b>	min
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	INTEGER32
<b>Value range</b>	-(2 <sup>31</sup> -1) ... (2 <sup>31</sup> -1)
<b>Default value</b>	0

Description: This Index is used to read out the operating time (hours) counter of the servo amplifier.

<b>Sub-index</b>	11 <sub>h</sub>
<b>Brief description</b>	enhanced status for TPDO 33
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>Default value</b>	—

Description:

Bit	Value	Description
0	0x00000001	status input 1
1	0x00000002	status input 2
2	0x00000004	status input 3
3	0x00000008	status input 4
4	0x00000010	reserved
5	0x00000020	reserved
6	0x00000040	reserved
7	0x00000080	reserved
8	0x00000100	reserved
9	0x00000200	reserved
10	0x00000400	reserved
11	0x00000800	reserved
12	0x00001000	reserved
13	0x00002000	reserved
14	0x00004000	reserved
15	0x00008000	reserved
16	0x00010000	task active (position control)
17	0x00020000	homing/reference point set
18	0x00040000	home position
19	0x00080000	In-Position
20	0x00100000	position latched
21	0x00200000	free
22	0x00400000	signal position 1
23	0x00800000	signal position 2
24	0x01000000	signal position 3
25	0x02000000	signal position 4
26	0x04000000	initialization finished
27	0x08000000	free
28	0x10000000	motor standstill
29	0x20000000	safety relay
30	0x40000000	output stage enabled
32	0x80000000	error present

## IV.11 Profile Velocity Mode (pv)(DS402)

### IV.11.1 General Information

The *profile velocity* mode enables the processing of velocity setpoints and the associated accelerations.

### IV.11.2 Objects that are defined in this section

Index	Object	Name	Type	Access
606C <sub>h</sub>	VAR	velocity_actual_value	INTEGER32	r
60FF <sub>h</sub>	VAR	target_velocity	INTEGER32	r/w

### IV.11.3 Objects that are defined in other sections

Index	Object	Name	Type	Section
6040 <sub>h</sub>	VAR	control word	INTEGER16	dc (⇒ IV.4)
6041 <sub>h</sub>	VAR	status word	UNSIGNED16	dc (⇒ IV.4)
6063 <sub>h</sub>	VAR	position_actual_value*	INTEGER32	pc (⇒ IV.12)
6083 <sub>h</sub>	VAR	profile_acceleration	UNSIGNED32	pp (⇒ IV.14)
6084 <sub>h</sub>	VAR	profile_deceleration	UNSIGNED32	pp (⇒ IV.14)
6086 <sub>h</sub>	VAR	motion_profile_type	INTEGER16	pp (⇒ IV.14)
6094 <sub>h</sub>	ARRAY	velocity_encoder_factor	UNSIGNED32	fg (⇒ IV.5)

### IV.11.4 Object Description

#### IV.11.4.1 SDO 606C<sub>h</sub>: velocity\_actual\_value\* (DS402)

The Object *velocity\_actual\_value* represents the actual speed. The scaling of the value depends on the factor *velocity\_encoder\_resolution* (SDO 6096<sub>h</sub>).

<b>Index</b>	0x606C <sub>h</sub>
<b>Name</b>	velocity_actual_value
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	pv
<b>Access</b>	r
<b>PDO mapping</b>	possible
<b>Unit</b>	velocity units
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>Default value</b>	—
<b>EEPROM</b>	no

#### IV.11.4.2 SDO 60FF<sub>h</sub>: target\_velocity

The speed setpoint (*target\_velocity*) represents the setpoint for the ramp generator. The scaling of this value depends on the factor *velocity\_encoder\_resolution* (SDO 6096<sub>h</sub>).

<b>Index</b>	0x60FF <sub>h</sub>
<b>Name</b>	target_velocity
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	pv
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	increments
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>Default value</b>	—
<b>EEPROM</b>	no

### IV.12 Position Control Function (pc)(DS402)

#### IV.12.1 General Information

This section describes the actual position values that are associated with the position controller of the drive. They are used for the *profile position* mode.

#### IV.12.2 Objects that are defined in this section

Index	Object	Name	Type	Access
6063 <sub>h</sub>	VAR	position_actual_value*	INTEGER32	r
6064 <sub>h</sub>	VAR	position_actual_value	INTEGER32	r

#### IV.12.3 Objects that are defined in other sections

Index	Object	Name	Type	Section
607A <sub>h</sub>	VAR	target_position	INTEGER32	pp (⇒ IV.14)
607B <sub>h</sub>	VAR	position_range_limit	INTEGER32	pp (⇒ IV.14)
607C <sub>h</sub>	VAR	home-offset	INTEGER32	hm (⇒ IV.13)
6093 <sub>h</sub>	VAR	position_factor	UNSIGNED32	fg (⇒ IV.5)
6094 <sub>h</sub>	ARRAY	velocity_encoder_factor	UNSIGNED32	fg (⇒ IV.5)
6096 <sub>h</sub>	ARRAY	acceleration_factor	UNSIGNED32	fg (⇒ IV.5)
6040 <sub>h</sub>	VAR	control word	INTEGER16	dc (⇒ IV.4)
6041 <sub>h</sub>	VAR	status word	UNSIGNED16	dc (⇒ IV.4)

## IV.12.4 Object Description

### IV.12.4.1 SDO 6063<sub>h</sub>: position\_actual\_value\* (DS402)

The Object *position\_actual\_value* provides the momentary actual position in increments. The resolution is 16 bits or 20 bits per turn (see *PRBASE* command).

<b>Index</b>	0x6063 <sub>h</sub>
<b>Name</b>	position_actual_value
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	pc, pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	increments (1 turn = 16 bit / 20 bit)(see <i>PRBASE</i> )
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>Default value</b>	—
<b>EEPROM</b>	no

### IV.12.4.2 SDO 6064<sub>h</sub>: position\_actual\_value (DS402)

The Object *position\_actual\_value* provides the actual position. The resolution (manufacturer-specific units: see SDOs 2020<sub>h</sub> 08<sub>h</sub>/09<sub>h</sub> or as per drive profile DSP402: see SDO 607A<sub>h</sub>) can be altered by the gearing factors of the position controller.

**Note: this Object should not be defined (mapped) in a synchronous TPDO.**

<b>Index</b>	0x6064 <sub>h</sub>
<b>Name</b>	position_actual_value
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	pc, pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	position units
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>Default value</b>	—
<b>EEPROM</b>	no

## IV.13 Homing Mode (hm)(DS402)

### IV.13.1 General Information

This section describes the various parameters which are required to define a homing mode.

### IV.13.2 Objects that are defined in this section

Index	Object	Name	Type	Access
607C <sub>h</sub>	VAR	home_offset	INTEGER32	r/w
6098 <sub>h</sub>	VAR	homing_method	INTEGER8	r/w
6099 <sub>h</sub>	ARRAY	homing_speeds	UNSIGNED32	r/w
609A <sub>h</sub>	VAR	homing_acceleration	UNSIGNED32	r/w

### IV.13.3 Object that are defined in other sections

Index	Object	Name	Type	Section
6040 <sub>h</sub>	VAR	control word	INTEGER16	dc (⇒ IV.4)
6041 <sub>h</sub>	VAR	status word	UNSIGNED16	dc (⇒ IV.4)

## IV.13.4 Object Description

### IV.13.4.1 SDO 607C<sub>h</sub>: home\_offset (DS402)

The reference offset (*home\_offset*) is the difference between the zero position for the application and the zero point of the machine. All subsequent absolute motion tasks take account of the reference offset.

<b>Index</b>	0x607C <sub>h</sub>
<b>Name</b>	home_offset
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	hm
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	user-defined
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>Default value</b>	0
<b>EEPROM</b>	yes

IV.13.4.2 SDO 6098<sub>h</sub>: homing\_method (DS402)

<b>Index</b>	0x6098 <sub>h</sub>
<b>Name</b>	homing_method
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER8
<b>Mode</b>	hm
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	position units
<b>Value range</b>	-128 ... 127
<b>Default value</b>	0
<b>EEPROM</b>	yes

The following homing methods are supported:

Method as per DSP402	Brief description: Homing	ASCII command
-128..-4	reserved	—
-3	move to mechanical stop, with zeroing	NREF = 7
-2	set reference point at present position, allowing for lag/following error	NREF = 6
-1	homing within a single turn (direction of rotation depends on distance)	NREF = 5, DREF= 2
0	reserved	—
1	homing to negative limit switch, with zeroing, negative direction of motion	NREF = 2, DREF= 0
2	homing to positive limit switch, with zeroing, positive direction of motion	NREF = 2, DREF= 1
3..7	not supported	—
8	homing to reference switch, with zeroing, positive direction of motion	NREF = 1, DREF= 1
9..11	not supported	—
12	homing to reference switch, with zeroing, negative direction of motion	NREF = 1, DREF= 0
13..14	not supported	—
15..16	reserved	—
17	homing to negative limit switch, without zeroing, negative direction of motion	NREF = 4, DREF= 0
18	homing to negative limit switch, without zeroing, positive direction of motion	NREF = 4, DREF= 1
19..23	not supported	—
24	homing to reference switch, without zeroing, positive direction of motion	NREF = 3, DREF= 1
25..27	not supported	—
28	homing to reference switch, without zeroing, negative direction of motion	NREF = 3, DREF= 0
29..30	not supported	—
31..32	reserved	—
33	homing within a single turn negative direction of rotation	NREF = 5, DREF= 0
34	homing within a single turn positive direction of rotation	NREF = 5, DREF= 1
35	set reference point at present position	NREF = 0
36..127	reserved	—

#### IV.13.4.2.1 Description of the homing methods

Choosing a homing method by writing a value to homing\_method (SDO 6098<sub>h</sub>) will clearly establish:

- the homing signal (P-Stop, N-Stop, reference switch)
- the direction of actuation

and where appropriate

- the position of the index pulse.

The reference position is give by the reference offset (SDO 607C<sub>h</sub>). The manufacturer-specific parameter *ENCZERO* (SDO 3537<sub>h</sub>, Sub-index 01<sub>h</sub>) can be used to adapt the initial position of the motor for homing to match the index pulse for homing with zeroing.

A detailed description of the types of homing movement can be found in the description of the commissioning software DRIVE.EXE.

#### IV.13.4.3 SDO 6099<sub>h</sub>: homing\_speeds (DS402)

<b>Index</b>	0x6099 <sub>h</sub>
<b>Name</b>	homing_speeds
<b>Object code</b>	ARRAY
<b>Number of elements</b>	1
<b>Data type</b>	UNSIGNED32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	speed_during_search_for_switch
<b>Mode</b>	hm
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	velocity units
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>EEPROM</b>	yes
<b>Default value</b>	2 <sup>20</sup>

#### IV.13.4.4 SDO 609A<sub>h</sub>: homing\_acceleration (DS402)

<b>Index</b>	0x609A <sub>h</sub>
<b>Name</b>	homing_acceleration
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Mode</b>	hm
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	acceleration units
<b>Value range</b>	0 ... (2 <sup>32</sup> -1)
<b>Default value</b>	0
<b>EEPROM</b>	yes

## IV.13.5 Homing Mode Sequence

The homing movement is started by setting Bit 4 (positive edge). The successful conclusion is indicated by Bit 12 in the status word (see SDO 6041<sub>h</sub>). Bit 13 indicates that an error occurred during the homing movement. In this case, the error code must be evaluated (error register: SDOs 1001<sub>h</sub>, 1003<sub>h</sub>, manufacturer status: SDO1002<sub>h</sub>).

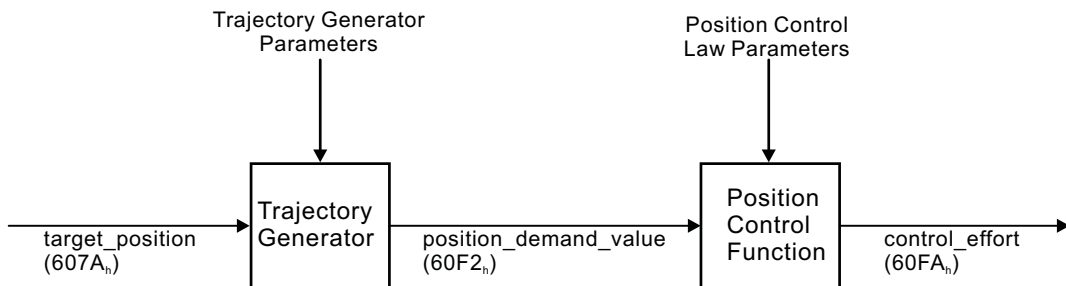
Bit 4	Meaning
0	homing inactive
0 ⇒ 1	start homing movement
1	homing active
0 ⇒ 1	interruption of homing movement

Bit 13	Bit 12	Meaning
0	0	reference point not set, or homing movement not yet finished
0	1	reference point set, homing movement finished
1	0	homing movement could not be successfully concluded (lag error)
1	1	impermissible state

## IV.14 Profile Position Mode (pp)

### IV.14.1 General Information

The overall structure for this mode is shown in this figure.:



The special handshake procedure for the control word and status word is described in Section IV.14.4.1.

### IV.14.2 Objects that are defined in this section

Index	Object	Name	Type	Access
607A <sub>h</sub>	VAR	target_position	INTEGER32	r/w
607B <sub>h</sub>	ARRAY	position_range_limit	INTEGER32	r/w
6081 <sub>h</sub>	VAR	profile_velocity	UNSIGNED32	r/w
6083 <sub>h</sub>	VAR	profile_acceleration	UNSIGNED32	r/w
6084 <sub>h</sub>	VAR	profile_deceleration	UNSIGNED32	r/w
6085 <sub>h</sub>	VAR	quick_stop_deceleration	UNSIGNED32	r/w
6086 <sub>h</sub>	VAR	motion_profile_type	INTEGER16	r/w

### IV.14.3 Objects that are defined in other sections

Index	Object	Name	Type	Section
6040 <sub>h</sub>	VAR	control word	INTEGER16	dc (⇒ IV.4)
6041 <sub>h</sub>	VAR	status word	UNSIGNED16	dc (⇒ IV.4)
605A <sub>h</sub>	VAR	quick_stop_option_code	INTEGER16	dc (⇒ IV.4)
6093 <sub>h</sub>	ARRAY	position_factor	UNSIGNED32	fg (⇒ IV.5)
6094 <sub>h</sub>	ARRAY	velocity_encoder_factor	UNSIGNED32	fg (⇒ IV.5)
6097 <sub>h</sub>	ARRAY	acceleration_factor	UNSIGNED32	fg (⇒ IV.5)

### IV.14.4 Object description

#### IV.14.4.1 SDO 607A<sub>h</sub>: target\_position (DS402)

The Object *target\_position* defines the target position for the drive. The target position is interpreted as a relative distance or an absolute position, depending on Bit 6 of the control word.

The type of relative movement can be further defined by the manufacturer-specific parameter 2022<sub>h</sub> Sub-index 03<sub>h</sub>.

The mechanical resolution is set by the gearing factors SDO 6093<sub>h</sub> Sub-index 01<sub>h</sub> and 02<sub>h</sub>.

<b>Index</b>	0x607A <sub>h</sub>
<b>Name</b>	target_position
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER32
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	user-defined
<b>Value range</b>	$-(2^{31}-1) \dots (2^{31}-1)$
<b>Default value</b>	—
<b>EEPROM</b>	no

#### IV.14.4.2 SDO 607B<sub>h</sub>: position\_range\_limit (DS402)

The Object *position\_range\_limit* is used to define the start and end of the range of movement for a modulo axis. The start of the range is defined by Sub-index 01<sub>h</sub> *min\_position\_range\_limit* (ASCII *SRND*) and the end by Sub-index 02<sub>h</sub> *max\_position\_range\_limit* (ASCII *ERND*). This functionality can only be used after a re-configuration of the instrument. To do this, SDO 2020<sub>h</sub> Sub-index 01<sub>h</sub> must have the value 2 applied, and then the configuration procedure can be started (⇒ VI.4).

<b>Index</b>	0x607B <sub>h</sub>
<b>Name</b>	position_range_limit
<b>Object code</b>	ARRAY
<b>Number of elements</b>	2
<b>Data type</b>	INTEGER32

<b>Sub-index</b>	01 <sub>h</sub>
<b>Brief description</b>	min_position_range_limit
<b>Mode</b>	pp, pc
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	position units
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>EEPROM</b>	yes
<b>Default value</b>	$-2^{31}$

<b>Sub-index</b>	02 <sub>h</sub>
<b>Brief description</b>	max_position_range_limit
<b>Mode</b>	pp, pc
<b>Access</b>	r/w
<b>PDO mapping</b>	not possible
<b>Unit</b>	position units
<b>Value range</b>	$(-2^{31}) \dots (2^{31}-1)$
<b>EEPROM</b>	yes
<b>Default value</b>	$2^{31}-1$

#### IV.14.4.3 SDO 6081<sub>h</sub>: profile\_velocity (DS402)

The *profile\_velocity* is the final velocity that should be reached after the acceleration phase of a motion task. The scaling used depends on the setting of the *velocity\_encoder\_factor* (SDO 6094<sub>h</sub>). The application of the setpoint depends on the operation mode (pp, pv) that is set.

<b>Index</b>	0x6081 <sub>h</sub>
<b>Name</b>	profile_velocity
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Mode</b>	pp, pv
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	speed units
<b>Value range</b>	$0 \dots (2^{32}-1)$
<b>Default value</b>	10
<b>EEPROM</b>	no

#### IV.14.4.4 SDO 6083<sub>h</sub>: profile\_acceleration (DS402)

The acceleration ramp (*profile\_acceleration*) is given in units that are defined by the user. The processing and interpretation of the acceleration setpoint can be made in two ways:

- **Internal gearing factors PGEARI = PGEARO (see SDOs 2020<sub>h</sub> 08<sub>h</sub>/09<sub>h</sub>, ASCII command PGEARI/PGEARO)**

The acceleration ramp is interpreted as the acceleration time [ms] or rate of acceleration [ $\text{incr/s}^2$ ] referred to the target velocity (SDO 6081<sub>h</sub> *profile\_velocity*). The scaling for this value depends on SDO 6097<sub>h</sub> *acceleration\_factor*.

**Note:** only the acceleration time is supported as a unit at present!

- **Internal gearing factors PGEARI <> PGEARO (see SDOs 2020<sub>h</sub> 08<sub>h</sub>/09<sub>h</sub>, ASCII command PGEARI/PGEARO)**

The acceleration ramp is interpreted as the acceleration time [ms] or rate of acceleration [ $\text{length units/s}^2$ ] referred to the target velocity. The scaling for this value depends on the gearing factors that are set (see description of the ASCII commands *PGEARI* and *PGEARO*) and the basic unit that is set [ms] or [ $\text{length unit/s}^2$ ]. The selection of the basic unit is made through Bit 12 in the control word for the motion task (SDO 2022<sub>h</sub>03<sub>h</sub>, ASCII command *O\_C*).

The type of acceleration ramp can be selected as a linear ramp or a  $\sin^2$  ramp (see SDO 6086<sub>h</sub>).

<b>Index</b>	0x6083 <sub>h</sub>
<b>Name</b>	profile_acceleration
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	acceleration units
<b>Value range</b>	0 ... ( $2^{32}-1$ )
<b>Default value</b>	0

#### IV.14.4.5 SDO 6084<sub>h</sub>: profile\_deceleration (DS402)

The braking/deceleration ramp is handled in the same way as the acceleration ramp (see SDO 6083<sub>h</sub>).

<b>Index</b>	0x6084 <sub>h</sub>
<b>Name</b>	profile_deceleration
<b>Object code</b>	VAR
<b>Data type</b>	UNSIGNED32
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	acceleration units
<b>Value range</b>	0 ... ( $2^{32}-1$ )
<b>Default value</b>	0

#### IV.14.4.6 SDO 6086<sub>n</sub>: motion\_profile\_type (DS402)

The type of acceleration ramp can be selected by this Object as a linear or as sin<sup>2</sup> ramp.

<b>Index</b>	0x6086 <sub>n</sub>
<b>Name</b>	motion_profile_type
<b>Object code</b>	VAR
<b>Data type</b>	INTEGER16
<b>Mode</b>	pp
<b>Access</b>	r/w
<b>PDO mapping</b>	possible
<b>Unit</b>	none
<b>Value range</b>	(-2 <sup>15</sup> )..(2 <sup>15</sup> -1)
<b>Default value</b>	—
<b>EEPROM</b>	yes

profile code	profile type
-32768 ... -1	manufacturer-specific (not supported)
0	linear (trapezoidal)
1	sin <sup>2</sup>
2 ... 32767	profile-specific extensions (not supported)

#### IV.14.5 Functional Description

Two different ways to apply *target\_positions* to a drive are supported by this device profile.

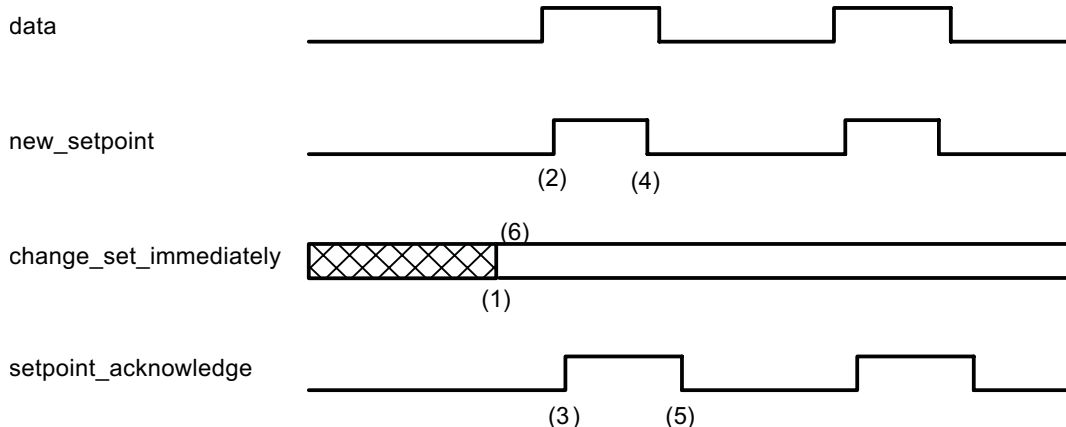
Set of setpoints:

After reaching the *target\_position*, the drive device immediately processes the next *target\_position*, which results in a move where the velocity of the drive normally is not reduced to zero after achieving a setpoint. With SERVOSTAR™ 400/600, this is only possible if trapezoidal ramps are used.

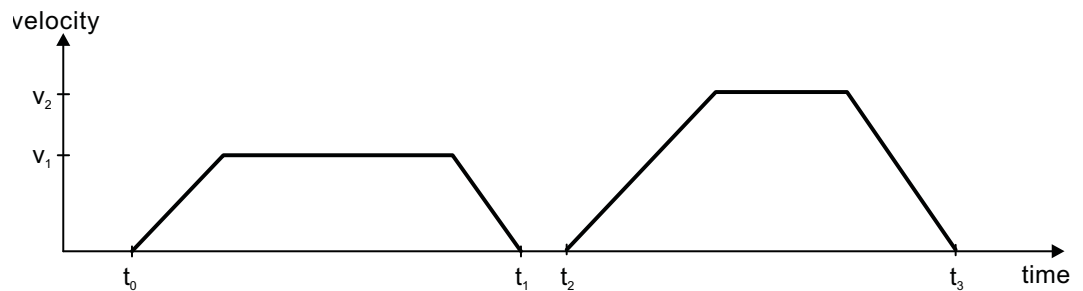
Single setpoints:

After reaching the *target\_position*, the drive device signals this status to a host computer and then receives a new setpoint. After reaching a *target\_position*, the velocity is normally reduced to zero before starting a move to the next setpoint.

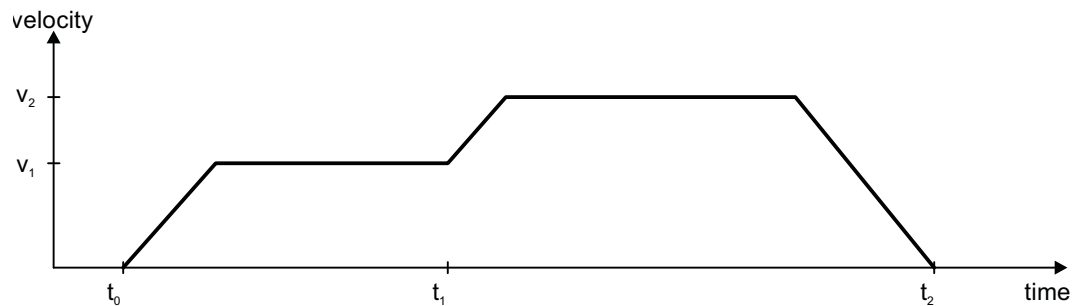
The two modes are controlled by the timing of the bits for *new\_setpoint* and *change\_set\_immediately* in the control word, and *setpoint\_acknowledge* in the status word. These bits allow the setting up of a request-response mechanism in order to prepare a set of setpoints while another set is still being processed in the drive unit. This minimizes reaction times within a control program on a host computer.



The figures show the difference between the *set of setpoints* mode and the *single setpoint* mode. The initial status of the bit *change\_set\_immediately* in the control word determines which mode is used. To keep these examples simple, only trapezoidal moves are used. If the bit *change\_set\_immediately* is "0" (continuously drawn line in Figure 1) a single setpoint is expected by the drive (1). After data is applied to the drive, a host signals that the data is valid by changing the bit *new\_setpoint* to "1" in the control word (2). The drive responds with *setpoint\_acknowledge* set to "1" in the status word (3) after it has recognized and buffered the new valid data. Now the host can release *new\_setpoint* (4) and subsequently the drive will signal through *setpoint\_acknowledge* = "0" its ability to accept new data again (5). In Figure 2 this mechanism results in a velocity of zero after ramping down to reach a target\_position  $X_1$  at  $t_1$ . After signalling to the host, that the setpoint has been reached as described above, the next target\_position is processed at  $t_2$  and reached at  $t_3$ .



With *change\_set\_immediately* set to "1" (6), symbolized by the dashed line in Figure 1, the host instructs the drive to apply a new setpoint immediately after reaching the previous one. The relative timing of the other signals is unchanged. This behavior causes the drive to process the next setpoint  $X_2$  in advance, and to hold its velocity when it reaches the target\_position  $X_1$  at  $t_1$ . The drive then moves immediately to the next target\_position  $X_2$  that has already been calculated.



**Bits in the control word:**

- Bit 4 *new\_set\_point* (positive edge!)
- Bit 5 *change\_set\_immediately*
- Bit 6 *absolute/relative*

**Bits in the status word:**

- Bit 12 *setpoint acknowledge*
- Bit 13 *lag/following error*

**Notes on motion task type *relative*:**

If Bit 6 is set, then the motion task type is *relative*, and activated according to the last target position or actual position. If other types of relative motion are required, these must be activated in advance through SDO 2022<sub>h</sub> Sub-index 03<sub>n</sub> *position data for position mode* (see also SDO 2022<sub>h</sub> Sub-index 03<sub>h</sub> or ASCII Object O\_C).

**Notes on *profile position mode*:**

Functional description for the *profile position mode*

The drive profile DSP402 distinguishes between two methods of moving to a target position. These two methods are controlled by the bits for *new\_setpoint* and *change\_set\_immediately* in the control word, and *setpoint\_acknowledge* in the status word. These bits can be used to prepare a motion task while another is still being carried out (handshake).

- **Moving to several target positions without an intermediate halt**

After the target position has been reached, the drive moves immediately to the next target position. This requires that new setpoints are signalled to the drive. This is done through a positive transition of the *new\_setpoint* bit. In this case, the *setpoint\_acknowledge* bit must not be set (see also *Handshake DSP402*).

The velocity is not reduced to zero when the first setpoint is reached.
- **Moving to a single target position**

The drive moves to the target position, whereby the velocity is reduced to zero. Reaching the target position is signaled by the bit for *target\_reached* in the status word.

## V The Object Channel

### V.1 Object Description

#### V.1.1 SDO > 3500<sub>h</sub>: Manufacturer-specific Object Channel

The Object Dictionary has been expanded beyond Index 3500<sub>h</sub> (reserved Object range 3500<sub>h</sub> ... 3900<sub>h</sub>) for all Device Objects that can be described in up to 4 bytes of user data.

This range can be dynamically extended, i.e. if extensions are made, new device parameters that fulfil the above-mentioned format are **automatically** added to the table for the core firmware.

SDO 3500<sub>h</sub> (Sub-index 01<sub>h</sub>, read) can be used to show the total number of Objects in the Object Channel (⇒ VI.3).

Each Object in this range is described with the aid of 8 Sub-indices. The structure is built up as follows:

<b>Index</b>	> 3500 <sub>h</sub>
<b>Name</b>	Object-dependent
<b>Object code</b>	VAR
<b>Data type</b>	RECORD

<b>Sub-index</b>	00 <sub>h</sub>
<b>Description</b>	number of entries
<b>Unit</b>	—
<b>Access</b>	—
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED8
<b>Value range</b>	0 ... 2 <sup>8</sup> -1
<b>EEPROM</b>	—
<b>Default value</b>	—

<b>Sub-index</b>	01 <sub>h</sub>
<b>Description</b>	read/write a parameter
<b>Unit</b>	see corresponding ASCII command
<b>Access</b>	see corresponding ASCII command
<b>PDO mapping</b>	not possible
<b>Data type</b>	see corresponding ASCII command
<b>Value range</b>	see corresponding ASCII command
<b>EEPROM</b>	see Sub-index 04 <sub>h</sub>
<b>Default value</b>	see corresponding ASCII command

<b>Sub-index</b>	02 <sub>h</sub>
<b>Description</b>	read lower limit value
<b>Unit</b>	see corresponding ASCII command
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	see corresponding ASCII command
<b>Value range</b>	see corresponding ASCII command
<b>EEPROM</b>	—
<b>Default value</b>	—

<b>Sub-index</b>	03 <sub>h</sub>
<b>Description</b>	read upper limit value
<b>Unit</b>	see corresponding ASCII command
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	see corresponding ASCII command
<b>Value range</b>	see corresponding ASCII command
<b>EEPROM</b>	—
<b>Default value</b>	—

<b>Sub-index</b>	04 <sub>h</sub>
<b>Description</b>	read the default value
<b>Unit</b>	see corresponding ASCII command
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	see corresponding ASCII command
<b>Value range</b>	see corresponding ASCII command
<b>EEPROM</b>	—
<b>Default value</b>	—

<b>Sub-index</b>	05 <sub>h</sub>
<b>Description</b>	read the parameter format
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	see corresponding ASCII command
<b>Value range</b>	see corresponding ASCII command
<b>EEPROM</b>	—
<b>Default value</b>	—

**Description:**

The following parameter formats are possible:

0	Function (no parameter)
1	Function (INTEGER32 parameter)
2	Function (INTEGER32 parameter with weighting 3)
3	INTEGER8
4	UINTEGER8
5	INTEGER16
6,13	UINTEGER16
7	INTEGER32
8,12	UINTEGER32
9,10	INTEGER32 (weighting 3)

**Warning:**

*Parameters with parameter format 0 are read-only!*

<b>Sub-index</b>	06 <sub>h</sub>
<b>Description</b>	read the parameter check data
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... 2 <sup>32</sup> -1
<b>EEPROM</b>	—
<b>Default value</b>	—

**Description:**

0x00010000 After an alteration the variable must be saved and the controller must be reset.

0x00020000 Variable is saved in the serial EEPROM.

0x00200000 Variable is read-only, must not be written to over the bus.

<b>Sub-index</b>	07 <sub>h</sub> / 08 <sub>h</sub>
<b>Description</b>	reserved
<b>Unit</b>	—
<b>Access</b>	r
<b>PDO mapping</b>	not possible
<b>Data type</b>	UNSIGNED32
<b>Value range</b>	0 ... 2 <sup>32</sup> -1
<b>EEPROM</b>	—
<b>Default value</b>	—

Number	ASCII command	Data format	Weighting	Status	EEPROM
3500	MAXSDO	INTEGER32	—	—	—
3501	ACC	INTEGER16	—	—	yes
3502	ACCR	INTEGER16	—	—	yes
3503	ACTFAULT	INTEGER8	—	Disabled + Reset	yes
3504	ACTIVE	INTEGER8	—	—	no
3505	ADDR	UNSIGNED8	—	—	yes
3506	AENA	INTEGER8	—	—	yes
3507	ANCNFG	INTEGER8	—	Disabled + Reset	yes
3508	ANDB	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3509	ANIN1	INTEGER32	—	—	no
350A	ANIN2	INTEGER32	—	—	no
350B	ANOFF1	INTEGER16	—	—	yes
350C	ANOFF2	INTEGER16	—	—	yes
350D	ANOUT1	INTEGER8	—	Disabled + Reset	yes
350E	ANOUT2	INTEGER8	—	Disabled + Reset	yes
350F	ANZERO1	—	—	—	—
3510	ANZERO2	—	—	—	—
3511	AVZ1	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3512	CALCHP	—	—	Enabled	—
3513	CALCRK	—	—	Enabled	—
3514	CALCRP	—	—	Disabled + Reset	—
3515	CBAUD	INTEGER16	—	Disabled + Reset	yes
3516	reserved				
3517	CDUMP	—	—	—	—
3518	CLRFAULT	—	—	—	—
3519	CLRHR	—	—	—	—

Number	ASCII command	Data format	Weighting	Status	EEPROM
351A	CLRORDER	INTEGER16	—	Disabled	—
351B	CLRWARN	UNSIGNED8	—	Disabled + Reset	yes
351C	CONFIG	—	—	—	—
351D	CONTINUE	—	—	Enabled	—
351E	CTUNE	—	—	Enabled	—
351F	CUPDATE	—	—	Disabled	—
3520	DAOFFSET1	INTEGER16	—	—	yes
3521	DAOFFSET2	INTEGER16	—	—	yes
3522	DEC	INTEGER16	—	—	yes
3523	DECDIS	INTEGER16	—	—	yes
3524	DECR	INTEGER16	—	—	yes
3525	DECSTOP	INTEGER16	—	—	yes
3526	DEVICE	—	—	—	no
3527	DICONT	INTEGER32	☒	—	no
3528	DIFVAR	—	—	—	—
3529	DIPEAK	INTEGER32	☒	—	no
352A	DIR	INTEGER8	—	Disabled + Reset	yes
352B	DIS	—	—	Enabled	—
352C	DREF	INTEGER8	—	—	yes
352D	DRVSTAT	INTEGER32	—	—	no
352E	DR_TYPE	INTEGER16	—	—	no
352F	DUMP	—	—	—	—
3530	EN	—	—	Disabled	—
3531	ENCCAPT	INTEGER8	—	Disabled	yes
3532	ENCIN	INTEGER32	—	Disabled + Reset	yes
3533	ENCLINES	INTEGER16	—	Disabled + Reset	yes
3534	ENCMODE	INTEGER8	—	—	yes
3535	ENCOUT	INTEGER16	—	—	yes
3536	reserved				
3537	ENCZERO	INTEGER16	—	—	yes
3538	EXTMUL	INTEGER16	—	—	yes
3539	EXTPOS	INTEGER8	—	Disabled + Reset	yes
353A	EXTWD	INTEGER32	—	—	yes
353B	FBTYP	INTEGER8	—	Disabled + Reset	yes
353C	FILTMODE	UNSIGNED8	—	Disabled + Reset	yes
353D	FOLDMODE	INTEGER8	—	Disabled + Reset	yes
353E	GEARI	INTEGER16	—	—	yes
353F	GEARMODE	INTEGER8	—	Disabled	yes
3540	GEARO	INTEGER16	—	—	yes
3541	GET	—	—	—	—
3542	GP	INTEGER32	☒	—	yes
3543	GPFBT	INTEGER32	☒	—	yes
3544	GPFFT	INTEGER32	☒	—	yes
3545	GPFFV	INTEGER32	☒	—	yes
3546	GPTN	INTEGER32	☒	—	yes
3547	GPV	INTEGER32	☒	—	yes
3548	GV	INTEGER32	☒	—	yes
3549	GVFBT	INTEGER32	☒	—	yes
354A	GVFILT	INTEGER8	—	—	yes
354B	GVFR	INTEGER32	☒	—	yes
354C	GVT2	INTEGER32	☒	—	yes
354D	GVTN	INTEGER32	☒	—	yes

Number	ASCII command	Data format	Weighting	Status	EEPROM
354E	HACOFFS	INTEGER16	—	—	Encoder
354F	HFACT1	INTEGER16	—	—	Encoder
3550	HASOFFS	INTEGER16	—	—	Encoder
3551	HDUMP	—	—	—	—
3552	HICOFFS	INTEGER16	—	—	yes
3553	HIFACT1	INTEGER16	—	—	Encoder
3554	HISOFFS	INTEGER16	—	—	Encoder
3555	HRESET	—	—	—	—
3556	HSAVE	—	—	—	—
3557	HVER	—	—	—	no
3558	I	INTEGER32	<input checked="" type="checkbox"/>	—	no
3559	I2T	INTEGER32	—	—	no
355A	I2TLIM	INTEGER8	—	—	yes
355B	ICMD	INTEGER32	<input checked="" type="checkbox"/>	—	no
355C	ICONT	INTEGER32	<input checked="" type="checkbox"/>	—	yes
355D	ID	INTEGER32	<input checked="" type="checkbox"/>	—	no
355E	IDUMP	—	—	—	—
355F	IMAX	INTEGER32	<input checked="" type="checkbox"/>	—	no
3560	IN	—	—	—	—
3561	IN1	INTEGER8	—	—	—
3562	IN1MODE	INTEGER8	—	Disabled + Reset	yes
3563	IN1TRIG	INTEGER32	—	—	yes
3564	IN2	INTEGER8	—	—	no
3565	IN2MODE	INTEGER8	—	Disabled + Reset	yes
3566	IN2TRIG	INTEGER32	—	—	yes
3567	IN3	INTEGER8	—	—	no
3568	IN3MODE	INTEGER8	—	Disabled + Reset	yes
3569	IN3TRIG	INTEGER32	—	—	yes
356A	IN4	INTEGER8	—	—	no
356B	IN4MODE	INTEGER8	—	Disabled + Reset	yes
356C	IN4TRIG	INTEGER32	—	—	yes
356D	INPOS	—	—	—	—
356E	IPEAK	INTEGER32	<input checked="" type="checkbox"/>	—	yes
356F	IPEAKN	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3570	IQ	INTEGER32	<input checked="" type="checkbox"/>	—	no
3571	ISCALE1	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3572	ISCALE2	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3573	K	—	—	Enabled	no
3574	KC	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3575	KEYLOCK	INTEGER8	—	—	yes
3576	reserved				
3577	L	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3578	LATCH16	INTEGER16	—	—	—
3579	LATCH16N	INTEGER16	—	—	no
357A	LATCH32	INTEGER32	—	—	—
357B	LATCH32N	INTEGER32	—	—	no
357C	LATCHX32	INTEGER32	—	—	no
357D	LATCHX32N	INTEGER32	—	—	no
357E	LED1	INTEGER8	—	—	—
357F	LED2	INTEGER8	—	—	—
3580	LED3	INTEGER8	—	—	—
3581	LEDSTAT	INTEGER16	—	—	—

Number	ASCII command	Data format	Weighting	Status	EEPROM
3582	LIST	—	—	—	no
3583	LOAD	—	—	—	no
3584	MAXTEMPE	INTEGER16	—	—	yes
3585	MAXTEMPH	INTEGER16	—	—	yes
3586	MAXTEMPM	INTEGER32	☒	—	yes
3587	MBRAKE	INTEGER8	—	Disabled + Reset	yes
3588	MDBCNT	—	—	—	—
3589	MDBGGET	—	—	—	—
358A	MDBSET	INTEGER16	—	—	—
358B	MDUMP	—	—	—	—
358C	reserved				
358D	MH	—	—	Enabled	—
358E	MICONT	INTEGER32	☒	—	yes
358F	MIPEAK	INTEGER32	☒	—	yes
3590	reserved				
3591	MJOG	—	—	Enabled	—
3592	MVANGLP	INTEGER16	—	—	yes
3593	MKT	INTEGER32	☒	—	yes
3594	reserved				
3595	MLGC	INTEGER32	☒	—	yes
3596	MLGD	INTEGER32	☒	—	yes
3597	MLGP	INTEGER32	☒	—	yes
3598	MLGQ	INTEGER32	☒	—	yes
3599	MNUMBER	INTEGER16	—	Disabled	yes
359A	MONITOR1	INTEGER16	—	—	no
359B	MONITOR2	INTEGER16	—	—	no
359C	MPHASE	INTEGER16	—	Disabled	yes
359D	MPOLES	INTEGER8	—	Disabled	yes
359E	MRD	—	—	Enabled	—
359F	reserved				
35A0	MRESBW	INTEGER16	—	—	yes
35A1	MRESPOLES	INTEGER8	—	Disabled	yes
35A2	MSG	INTEGER8	—	—	yes
35A3	MSPEED	INTEGER32	☒	—	yes
35A4	reserved				
35A5	MTANGLP	INTEGER16	—	—	yes
35A6	reserved				
35A7	MVANGLB	INTEGER32	—	—	yes
35A8	MVANGLF	INTEGER16	—	—	yes
35A9	M_RESET	—	—	Disabled	—
35AA	NONBTB	INTEGER8	—	—	yes
35AB	NOTCHBW	INTEGER32	☒	—	yes
35AC	NOTCHHZ	INTEGER32	☒	—	yes
35AD	NREF	INTEGER8	—	—	yes
35AE	O1	INTEGER8	—	—	no
35AF	O1MODE	INTEGER8	—	Disabled + Reset	yes
35B0	O1TRIG	INTEGER32	—	—	yes
35B1	O2	INTEGER8	—	—	no
35B2	O2MODE	INTEGER8	—	Disabled + Reset	yes
35B3	O2TRIG	INTEGER32	—	—	yes
35B4	OPMODE	INTEGER8	—	—	yes
35B5	OPTION	INTEGER16	—	—	no

Number	ASCII command	Data format	Weighting	Status	EEPROM
35B6	OVERRIDE	INTEGER8	—	—	yes
35B7	O_ACC1	INTEGER16	—	—	no
35B8	O_ACC2	INTEGER16	—	—	no
35B9	O_C	INTEGER16	—	—	no
35BA	O_DEC1	INTEGER16	—	—	no
35BB	O_DEC2	INTEGER16	—	—	no
35BC	O_FN	INTEGER16	—	—	no
35BD	O_FT	INTEGER16	—	—	no
35BE	O_P	INTEGER32	—	—	no
35BF	O_V	INTEGER32	—	—	no
35C0	PBAL	INTEGER32	—	—	no
35C1	PBALMAX	INTEGER32	—	—	yes
35C2	PBALRES	INTEGER8	—	—	yes
35C3	PBAUD	INTEGER32	<input checked="" type="checkbox"/>	—	no
35C4	PDUMP	—	—	—	—
35C5	PE	INTEGER32	—	—	no
35C6	PEINPOS	INTEGER32	—	—	yes
35C7	PEMAX	INTEGER32	—	—	yes
35C8	PFB	INTEGER32	—	—	no
35C9	PFB0	INTEGER32	—	—	no
35CA	PGEARI	INTEGER32	—	Disabled + Reset	yes
35CB	PGEARO	INTEGER32	—	Disabled + Reset	yes
35CC	PIOBUF	—	—	—	no
35CD	PMODE	INTEGER32	—	Disabled + Reset	yes
35CE	PNOID	INTEGER32	—	—	no
35CF	POSCNFG	INTEGER8	—	Disabled + Reset	yes
35D0	PPOTYP	INTEGER8	—	—	yes
35D1	PRBASE	INTEGER8	—	Disabled + Reset	yes
35D2	PRD	INTEGER32	—	—	no
35D3	PROMPT	INTEGER16	—	—	no
35D4	PSTATE	—	—	—	no
35D5	PTBASE	INTEGER8	—	—	yes
35D6	PTMIN	INTEGER16	—	—	yes
35D7	PV	INTEGER32	—	—	no
35D8	PVMAX	INTEGER32	—	—	yes
35D9	PVMAXN	INTEGER32	—	—	yes
35DA	reserved				
35DB	reserved				
35DC	READNIMP	—	—	—	—
35DD	READY	INTEGER8	—	—	no
35DE	RECDONE	INTEGER8	—	—	no
35DF	RECING	INTEGER8	—	—	no
35E0	RECOFF	—	—	—	—
35E1	RECRDY	INTEGER8	—	—	no
35E2	REFIP	INTEGER32	<input checked="" type="checkbox"/>	—	yes
35E3	REFPOS	INTEGER32	—	—	no
35E4	REMOTE	INTEGER8	—	—	no
35E5	RESPHASE	INTEGER16	—	—	yes
35E6	RK	INTEGER16	—	—	yes
35E7	ROFFS	INTEGER32	—	—	yes
35E8	RS232T	INTEGER16	—	—	yes
35E9	RSTVAR	—	—	Disabled	no

Number	ASCII command	Data format	Weighting	Status	EEPROM
35EA	S	—	—	—	—
35EB	SAVE	—	—	—	—
35EC	SBAUD	INTEGER8	—	—	yes
35ED	SCAN	—	—	—	—
35EE	SDUMP	—	—	—	—
35EF	SERIALNO	INTEGER32	—	—	no
35F0	SETREF	—	—	—	—
35F1	SETROFFS	—	—	—	—
35F2	SLEN	INTEGER8	—	—	yes
35F3	SLOTIO	INTEGER32	—	—	no
35F4	SPHAS	INTEGER8	—	—	no
35F5	SPSET	INTEGER16	—	—	yes
35F6	SSIGRAY	INTEGER8	—	Disabled	yes
35F7	SSIINV	INTEGER8	—	Disabled	yes
35F8	SSIMODE	INTEGER8	—	—	yes
35F9	SSIOUT	INTEGER8	—	Disabled	yes
35FA	SSTAT	—	—	—	no
35FB	STAT	INTEGER16	—	—	no
35FC	STATIO	—	—	—	no
35FD	STATUS	—	—	—	no
35FE	STOP	—	—	Enabled	—
35FF	STOPMODE	INTEGER8	—	Disabled + Reset	yes
3600	SWCNFG	UNSIGNED16	—	Disabled + Reset	yes
3601	SWCNFG2	UNSIGNED16	—	Disabled + Reset	yes
3602	SWE0	INTEGER32	—	—	yes
3603	SWE0N	INTEGER32	—	—	yes
3604	SWE1	INTEGER32	—	—	yes
3605	SWE1N	INTEGER32	—	—	yes
3606	SWE2	INTEGER32	—	—	yes
3607	SWE2N	INTEGER32	—	—	yes
3608	SWE3	INTEGER32	—	—	yes
3609	SWE3N	INTEGER32	—	—	yes
360A	SWE4	INTEGER32	—	—	yes
360B	SWE4N	INTEGER32	—	—	yes
360C	SWE5	INTEGER32	—	—	yes
360D	SWE5N	INTEGER32	—	—	yes
360E	T	INTEGER32	☒	Enabled	—
360F	TASK	—	—	—	no
3610	TEMPE	INTEGER32	—	—	no
3611	TEMPH	INTEGER32	—	—	no
3612	TEMPM	INTEGER32	—	—	no
3613	TRJSTAT	INTEGER32	—	—	no
3614	TRUN	—	—	—	yes
3615	reserved				
3616	UID	INTEGER16	—	—	yes
3617	UVLTMODE	INTEGER8	—	Disabled + Reset	yes
3618	V	INTEGER32	—	—	no
3619	reserved				
361A	VBUS	INTEGER32	—	—	no
361B	VBUSBAL	INTEGER16	—	—	yes
361C	VBUSMAX	INTEGER32	—	—	yes
361D	VBUSMIN	INTEGER16	—	—	yes

Number	ASCII command	Data format	Weighting	Status	EEPROM
361E	VCMD	INTEGER32	<input checked="" type="checkbox"/>	—	no
361F	VDUMP	—	—	—	—
3620	VELO	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3621	VJOG	INTEGER32	—	—	yes
3622	VLIM	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3623	VLIMN	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3624	VMAX	INTEGER32	<input checked="" type="checkbox"/>	—	no
3625	VMIX	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3626	VMUL	INTEGER32	—	—	yes
3627	VOSPD	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3628	VREF	INTEGER32	—	—	yes
3629	VSCALE1	INTEGER16	—	—	yes
362A	VSCALE2	INTEGER16	—	—	yes
362B	\	UNSIGNED8	—	—	—
362C	DILIM	INTEGER8	—	Disabled + Reset	yes
362D	DENA	INTEGER8	—	—	yes
362E	IN2PM	INTEGER8	—	—	yes
362F	KTN	INTEGER32	<input checked="" type="checkbox"/>	—	yes
3630	INPT	INTEGER16	—	—	yes
3631	UCOMP	INTEGER32	—	—	yes
3632	COLDSTART	—	—	Disabled	—
3633	reserved				
3634	UID1	INTEGER32	—	—	yes
3635	SETVCT	INTEGER16	—	—	no
3636	WPOS	INTEGER8	—	Disabled + Reset	no
3637	SRND	INTEGER32	—	—	yes
3638	ERND	INTEGER32	—	—	yes
3639	MDRV	INTEGER8	—	—	yes
363A	BCC	INTEGER16	—	—	no
363B	FPGA	INTEGER8	—	Disabled + Reset	yes
363C	REFMODE	INTEGER8	—	—	yes
363D	VLO	INTEGER32	<input checked="" type="checkbox"/>	—	yes
363E	WMASK	INTEGER32	—	—	no
363F	WPOSE	INTEGER32	—	—	no
3640	WPOSP	INTEGER32	—	—	no
3641	WPOSX	INTEGER32	—	—	no
3642	MOVE	INTEGER16	—	Enabled	—
3643	POSRSTAT	INTEGER32	—	—	no
3644	P1	INTEGER32	—	—	yes
3645	P2	INTEGER32	—	—	yes
3646	P3	INTEGER32	—	—	yes
3647	P4	INTEGER32	—	—	yes
3648	P5	INTEGER32	—	—	yes
3649	P6	INTEGER32	—	—	yes
364A	P7	INTEGER32	—	—	yes
364B	P8	INTEGER32	—	—	yes
364C	P9	INTEGER32	—	—	yes
364D	P10	INTEGER32	—	—	yes
364E	P11	INTEGER32	—	—	yes
364F	P12	INTEGER32	—	—	yes
3650	P13	INTEGER32	—	—	yes
3651	P14	INTEGER32	—	—	yes

Number	ASCII command	Data format	Weighting	Status	EEPROM
3652	P15	INTEGER32	—	—	yes
3653	P16	INTEGER32	—	—	yes
3654	PTARGET	INTEGER32	—	—	yes
3655	ACTRS232	INTEGER8	—	—	no
3656	ROFFS2	INTEGER32	—	—	yes
3657	FW	INTEGER32	<input checked="" type="checkbox"/>	—	no
3658	reserved				
3659		INTEGER32	—	—	yes
365A	VCOMM	INTEGER32	—	—	yes
365B	MTMUX	INTEGER16	—	—	no
365C	ROFFS0	INTEGER32	—	—	yes
365D	REFLS	INTEGER32	—	—	yes
365E	BOOT	—	—	—	yes
365F		INTEGER32	—	—	yes
3660		INTEGER32	—	—	yes
3661	reserved				
3662	reserved				
3663	reserved				
3664	reserved				
3665	reserved				
3666	reserved				
3667	reserved				
3668	reserved				
3669	reserved				
366A	reserved				
366B	reserved				
366C	reserved				
366D	reserved				
366E	TBRAKE	INTEGER16	—	—	yes
366F	TBRAKE0	INTEGER16	—	—	yes
3670	CMDDLY	INTEGER16	—	—	yes
3671	reserved				
3672	DRVCNFG	INTEGER32	—	—	yes

## VI Appendix

### VI.1 Commissioning examples

All values are hexadecimal. The axis-related values always refer to Station1.

#### VI.1.1 Important configuration parameters for CAN bus operation

The following parameters are important for CAN operation:

- 1. CBAUD (SDO 3515<sub>h</sub> Sub-index 01<sub>h</sub>):** transmission rate for the CAN bus
- 2. ADDR (SDO 3505<sub>h</sub> Sub-index 01<sub>h</sub>):** The *ADDR* command defines the fieldbus address of the amplifier. After making a change to the address, all the parameters must be saved in the EEPROM, and the amplifier must be switched off and on again.
- 3. AENA (SDO 3506<sub>h</sub> Sub-index 01<sub>h</sub>):** This can be used to define the state of the software enable when the amplifier is switched on. The software enable provides an external control with the facility of enabling or disabling the output stage through software control. On instruments that function with an analog setpoint (OPMODE=1,3), the software enable is set automatically when the amplifier is switched on, so that these instruments are immediately ready to operate (provided that the hardware enable is present). For all other instruments, the software enable is set to the value of *AENA* at switch-on. The variable *AENA* also has a function for the reset of the amplifier after a fault (via digital input 1 or through the ASCII command *CLRFAULT*). For errors that can be reset through software, after the error/fault has been cleared, the software enable is set to the state of *AENA*. In this way, the response of the amplifier for a software reset is analogous to the switch-on behavior.
- 4. DRVCNFG (SDO 3672<sub>h</sub> Sub-index 01<sub>h</sub>):** The configuration variable *DRVCNFG* can be used to activate various additional CANopen functions in the amplifier.
 

Bit0	=1	CANopen switch-on telegram, 0 bytes long
	=0	CANopen switch-on telegram, 8 bytes long
Bit1	=1	enable and disable affect the CANopen status machine. The CANopen status machine follows the internal status of the servo amplifier. If this status changes (e.g. hardware disable) the CANopen status machine is automatically updated (with a corresponding Emergency Message).
	=0	the CANopen status machine is not affected.
Bit2	=1	SDO length is checked, an Emergency Object is generated if the SDO length is incorrect
	=0	the SDO length is not checked.
Bit3	=1	all communication- and mapping parameters can be saved with SDO 1010 <sub>h</sub> , sub-index 02 <sub>h</sub> (⇒ IV.2.1.16) This saved mapping is selected at switch-on of the amplifier.
	=0	At switch-on of SERVOSTAR™ 400/600, the default mapping configuration is set.
- 5. MDRV (SDO 3639<sub>h</sub>, sub-index 01<sub>h</sub>):** with this variable, the multidrive mode for the setup-software can be engaged (MDRV = 1). In this case only the first three RPDOs and TPDOs are available. If all four RPDOs and TPDOs are required, MDRV must be set to 0.

## VI.1.2 Basic testing of the connection to the SERVOSTAR™ 400/600 controls

When the SERVOSTAR™ 400/600 is switched on, an Emergency Message is transmitted over the bus with 0 or 8 data bytes (contents 0), depending on the setting of Bit 2 of the DRVCNFG parameter. The telegram continues to be transmitted, as long as it has not yet found a suitable receiver in the bus system.

If a CAN master is unable to recognize this message, then the following measures can be taken to test communication:

- Check the bus cable: correct characteristic impedance, correct termination resistors at both ends?
- With a multimeter: check the quiescent level of the bus cables CAN-H and CAN-L against CAN-GND (approx. 2.5 V).
- With an oscilloscope: check the output signals on CAN-H and CAN-L at the SERVOSTAR™ 400/600. Are signals being transmitted on the bus? The voltage difference between CAN-H and CAN-L for a logical "0" is approx. 2-3 V.
- Does signal transmission stop if the master is connected? Check the master hardware.
- Check the master software!

## VI.1.3 Example of operating the Status Machine

After the SERVOSTAR™ 400/600 is switched on and the boot-up message has been detected, communication via SDOs can be initiated. For example: all the parameters can be read out or written to, or the status machine for the drive can be controlled.

In the other examples it is assumed that functions are available for reading and writing SDOs, which appear as follows:

SDO-read (UINT Index, USHORT Sub-index);

SDO-write (UINT Index, USHORT Sub-index, ULONG value);

The state of the status machine can be obtained through the following query:

SDO-read (6041<sub>h</sub>, 00<sub>h</sub>)

Directly after switch-on, a value will then be returned, such as 0040<sub>h</sub>. This corresponds to the status *Ready to switch on* (⇒ IV.4.1.1).

The following data would then be visible on the CAN bus:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	40	41	60	00 <sub>h</sub>	40 00 00 00	
581	40	41	60	00 <sub>h</sub>	40 00 00 00	reply telegram
	2 bytes of data				status	

If the supply power is present and the hardware enable is at the *High* level (24 V to DGND) then SDO-write (6040<sub>h</sub>, 00<sub>h</sub>, 0x7) can be used to switch the drive to the state *Switched on*. If this is successful, there will be a positive acknowledgement in the SDO reply (control byte 0 in the data field = 60<sub>h</sub>).

Switch on

The messages then appear as follows:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	40	60	00 <sub>h</sub>	07 00 00 00	control word
581	60	40	60	00 <sub>h</sub>	00 00 00 00	response telegram

control word = 0x0007      Meaning: Bit 0, Bit 1, Bit 2 set ⇒ Switch On,  
*Disable Voltage off, Quick Stop off*

Status query 2

The new status can then be queried again, and returns the following result:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	40	41	60	00 <sub>h</sub>	—	query status
581	4B	41	60	00 <sub>h</sub>	23 00 00 00	response telegram

Status = 0x0023      Meaning: Bit 0, Bit 1, Bit 5 set ⇒ ready to Switch On,  
 Switched On, Quick Stop

#### VI.1.4 Example of PDO usage

Using all four possible PDOs in operation:

1. RPDO: PDO trajectory for one axis
2. RPDO: PDO control word and mode changeover
1. TPDO: PDO enhanced status
2. TPDO: PDO with incremental actual position, speed and operating mode display

Procedure:

Since the first RPDO is not available from the drive in the pre-defined form as required (⇒ IV.3.1) it must be assembled. First, it is necessary to check whether the entries for the incremental setpoint provision are available in mappable form.

This is the case with SDO 2022<sub>h</sub> Sub-index 04<sub>h</sub>. So the 1st RPDO is selected:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	26	00 <sub>h</sub>	25 00 00 00	select PDO 37 as 1 <sup>st</sup> RPDO
581	60	00	26	00 <sub>h</sub>	00 00 00 00	response telegram

The freely mappable RPDO 37 has thus been selected. In the next step, data must be attached to this PDO. This is done through the mapping parameter for the first RPDO:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	00	16	00 <sub>h</sub>	00 00 00 00	delete data for 1 <sup>st</sup> RPDO
581	60	00	16	00 <sub>h</sub>	00 00 00 00	response telegram
601	23	00	16	01 <sub>h</sub>	20 04 22 20	data for first entry of the 1 <sup>st</sup> RPDO SDO 2022 <sub>h</sub> Sub-index 04 <sub>h</sub> , data length: 32 bit
581	60	00	16	01 <sub>h</sub>	00 00 00 00	response telegram

The data content of the first PDO has now been defined, and it includes 4 bytes of user data.

Next, the communication parameters can be defined:

The system must react to COB-ID 201<sub>h</sub> as standard. So Sub-index 01<sub>h</sub> must remain set to the default value. But the drive must react to every SYNC Object, so a value of 1 must be applied to Sub-index 2:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	14	02 <sub>h</sub>	01 00 00 00	reaction to every SYNC
581	60	00	14	02 <sub>h</sub>	00 00 00 00	response telegram

The 2<sup>nd</sup> RPDO is to have two components: the CANopen control word (SDO 6040<sub>h</sub> Sub-index 00<sub>h</sub>) and the SDO for changing the operating mode (SDO 6060<sub>h</sub> Sub-index 00<sub>h</sub>).

The selection of the 2<sup>nd</sup> RPDO is made as follows:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	26	00 <sub>h</sub>	26 00 00 00	select PDO 38 as 2 <sup>nd</sup> RPDO
581	60	01	26	00 <sub>h</sub>	00 00 00 00	response telegram

The mapping is defined next:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	01	16	00 <sub>h</sub>	00 00 00 00	delete data for 2 <sup>nd</sup> RPDO
581	60	01	16	00 <sub>h</sub>	00 00 00 00	response telegram
601	23	01	16	01 <sub>h</sub>	10 00 40 60	data for first entry of the 2 <sup>nd</sup> RPDO SDO 6040 <sub>h</sub> Sub-index 00 <sub>h</sub> , data length: 16 bit
581	60	01	16	01 <sub>h</sub>	00 00 00 00	response telegram
601	23	01	16	02 <sub>h</sub>	08 00 60 60	data for second entry of the 2 <sup>nd</sup> RPDO SDO 6060 <sub>h</sub> Sub-index 00 <sub>h</sub> , data length: 8 bit
581	60	01	16	02 <sub>h</sub>	00 00 00 00	response telegram

This Object has to be evaluated immediately, so the communication parameters can remain at their default values.

The first TPDO is already available in the drive, it just has to be selected.

PDO 23 is selected:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	2A	00 <sub>h</sub>	17 00 00 00	select PDO 23 as 1 <sup>st</sup> TPDO
581	60	00	2A	00 <sub>h</sub>	00 00 00 00	response telegram

The corresponding mapping can be read out by SDO 1A00<sub>h</sub>. The PDO contains 2 bytes for the CANopen status word and 4 bytes for the manufacturer status register.

The second TPDO is assembled again:

1. Selection via SDO 2A01:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	2A	00 <sub>h</sub>	25 00 00 00	select PDO 37 as 1 <sup>st</sup> TPDO
581	60	01	2A	00 <sub>h</sub>	00 00 00 00	response telegram

2. The mapping for the three components required:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	01	1A	00 <sub>h</sub>	00 00 00 00	delete data for 2 <sup>nd</sup> TPDO
581	60	01	1A	00 <sub>h</sub>	00 00 00 00	response telegram
601	23	01	1A	01 <sub>h</sub>	20 03 70 20	data for first entry of the 2 <sup>nd</sup> TPDO SDO 2070 <sub>h</sub> Sub-index 03 <sub>h</sub> , data length: 32 bit
581	60	01	1A	01 <sub>h</sub>	00 00 00 00	response telegram
601	23	01	1A	02 <sub>h</sub>	18 02 70 20	data for second entry of the 2 <sup>nd</sup> TPDO SDO 2070 <sub>h</sub> Sub-index 02 <sub>h</sub> , data length: 24 bit
581	60	01	1A	02 <sub>h</sub>	00 00 00 00	response telegram
601	23	01	1A	02 <sub>h</sub>	08 00 61 60	data for third entry of the 2 <sup>nd</sup> TPDO SDO 6060 <sub>h</sub> Sub-index 00 <sub>h</sub> , data length: 8 bit
581	60	01	1A	02 <sub>h</sub>	00 00 00 00	response telegram

Now the communication parameters can be defined:

The drive must react to every SYNC Object, so a value of 1 must be applied to Sub-index 2:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	18	02 <sub>h</sub>	01 00 00 00	2 <sup>nd</sup> TPDO: reaction to every SYNC
581	60	01	18	02 <sub>h</sub>	00 00 00 00	response telegram

## VI.1.5 Example of Homing

When the SERVOSTAR™ 400/600 is operated as a linear axis, a reference/homing point must be defined before positioning tasks can be executed. This can be done simply through *Set reference point* (control word Bit 12 = 0 -> 1 -> 0 or homing type 35 in *Homing* mode) or by starting a homing movement, either in the manufacturer-specific mode *Homing/reference* (0xF9) or in the *Homing* mode (0x6).

This example shows the procedure in the *Homing* mode.

First switch over to the *Homing movement* mode:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	60	60	00 <sub>h</sub>	F9 00 00 00	<i>Homing</i> mode
581	60	60	60	00 <sub>h</sub>	00 00 00 00	O.K. signal

In the following example, all parameters that affect the homing movement are set via the bus. If you can be absolutely certain that no-one has altered the parameters in the instrument, then this part can be omitted, since the instruments save the data in non-volatile memory. (The inputs must have been previously configured as limit switches.)

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	2A	00 <sub>h</sub>	17 00 00 00	homing to limit switch & resolver zero mark
581	60	24	20	01 <sub>h</sub>	00 00 00 00	OK
601	2F	24	20	02 <sub>h</sub>	00 00 00 00	negative direction
581	60	24	20	02 <sub>h</sub>	00 00 00 00	OK
601	2B	24	20	03 <sub>h</sub>	10 27 00 00	v = 10mm/s
581	60	24	20	03 <sub>h</sub>	00 00 00 00	OK
601	2B	24	20	04 <sub>h</sub>	32 00 00 00	accel. ramp 50ms
581	60	24	20	04 <sub>h</sub>	00 00 00 00	OK
601	23	24	20	05 <sub>h</sub>	32 00 00 00	decel. ramp 50ms
581	60	24	20	05 <sub>h</sub>	00 00 00 00	OK
601	23	24	20	06 <sub>h</sub>	30 75 00 00	reference offset 30000µm
581	60	24	20	06 <sub>h</sub>	00 00 00 00	OK

To check the bit signals that are important for the homing movement, the PDO for enhanced status (PDO 23) must be used.

First of all, PDO 23 is selected as TPDO 1:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	2A	00 <sub>h</sub>	17 00 00 00	select PDO 23 as 1 <sup>st</sup> TPDO
601	60	00	2A	00 <sub>h</sub>	00 00 00 00	response telegram

TPDO1 is thus composed of 6 bytes, whereby the first two bytes contain the CANopen status word (SDO 6041), and the other four bytes contain the manufacturer-specific status register (SDO 1002).

This assignment can be queried through the SDOs for the PDO mapping (SDO 1A00<sub>n</sub>, Sub-index 00<sub>n</sub>-02<sub>n</sub>). The PDOs are subsequently enabled through an NMT Object:

COB-ID	Command specifier (CS)	Node-ID
0	1	1

From now on, status changes for TPDO1 will be automatically reported.

The homing movement can now be started by Bit 4 of the CANopen control word:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2B	40	60	00 <sub>h</sub>	1F 00 00 00	mode
581	60	40	60	00 <sub>h</sub>	00 00 00 00	homing runs until home conditions are fulfilled

A positive edge transition of the *Reference point set* bit in the manufacturer-specific status register can be used to detect that the servo drive has calibrated (zeroed) its position system. The homing procedure is terminated by the reset of the *Motion task active* bit.

A TPDO1 could therefore look like this:

COB-ID	Data	Comment
181	05 27 00 00 0A 54	mode

The status of the homing movement can be seen from the enhanced status register, Bit 17 (*Reference point set*).

## VI.1.6

### Example of motion block processing

Switch on position control

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	60	60	00 <sub>h</sub>	FF 00 00 00	position control mode
581	60	60	60	00 <sub>h</sub>	00 00 00 00	position control switched on

Map the second receive-PDO:

(Start motion block, motion blocks for the example are already defined. 1<sup>st</sup> receive-PDO is set to the standard setting: control word.)

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	26	00 <sub>h</sub>	23 00 00 00	start motion block Object
581	60	01	26	00 <sub>h</sub>	00 00 00 00	motion block active

Switch NMT status machine to *operational*:

COB-ID	Command specifier (CS)	Node-ID
0	1	1

Access second receive-Object

COB-ID	Motion block number: Low	Motion block number: High
301	01	00

Response: none, the given motion block 1 is being processed.

Motor Quick Stop

COB-ID	Control: Low	Control: High
201	03	00

Response: none, motor is stopped with  $t_{not}$ .

Disable controller:

COB-ID	Control: Low	Control: High	Motion block number
201	03	00	1

Response: none, drive is without torque.

## VI.1.7

### Example of using the *Profile position* mode

This section shows the operation of the *Profile position* mode. For this, the PDOs are set as follows:

- First RPDO: PDO control word (No. 1)
- Second RPDO: freely mappable PDO 2 (No. 38)
- First TPDO: freely mappable PDO 1 (No. 37)
- Second TPDO: freely mappable PDO 2 (No. 38)

The telegrams have an analogous appearance to the example for PDO operation ( $\Rightarrow$  VI.1.4).

Data are placed in the freely mappable PDOs as shown in the following telegram examples:

1) second RPDO:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	01	16	00 <sub>h</sub>	00 00 00 00	2 <sup>nd</sup> RPDO: delete mapping
581	60	01	16	00 <sub>h</sub>	00 00 00 00	
601	23	01	16	01 <sub>h</sub>	20 00 7A 60	2 <sup>nd</sup> RPDO, entry 1: target_position
581	60	01	16	01 <sub>h</sub>	00 00 00 00	
601	23	01	16	02 <sub>h</sub>	20 00 81 60	2 <sup>nd</sup> RPDO, entry 2: profile_velocity
581	60	01	16	02 <sub>h</sub>	00 00 00 00	

2) first TPDO:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	00	1A	00 <sub>h</sub>	00 00 00 00	1 <sup>st</sup> TPDO: delete mapping
581	60	00	1A	00 <sub>h</sub>	00 00 00 00	
601	23	00	1A	01 <sub>h</sub>	10 00 41 60	1 <sup>st</sup> TPDO, entry 1: profile status word
581	60	00	1A	01 <sub>h</sub>	00 00 00 00	
601	23	00	1A	02 <sub>h</sub>	08 09 80 20	1 <sup>st</sup> TPDO, entry 2: TRJSTAT 3 <sup>rd</sup> byte = manuf. status 3 <sup>rd</sup> byte
581	60	00	1A	02 <sub>h</sub>	00 00 00 00	

3) second TPDO:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	01	1A	00 <sub>h</sub>	00 00 00 00	2 <sup>nd</sup> TPDO: delete mapping
581	60	01	1A	00 <sub>h</sub>	00 00 00 00	
601	23	01	1A	01 <sub>h</sub>	20 00 64 60	2 <sup>nd</sup> TPDO, entry 1: position_actual_value
581	60	01	1A	01 <sub>h</sub>	00 00 00 00	
601	23	01	1A	02 <sub>h</sub>	20 00 6C 60	1 <sup>st</sup> TPDO, entry 2: velocity_actual_value
581	60	01	1A	02 <sub>h</sub>	00 00 00 00	

The first TPDO is to be transmitted under event-control. Since this corresponds to the default value for the communication parameters, nothing has to be changed in this case. The second TPDO is to be transmitted with every SYNC from the drive:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	01	18	02 <sub>h</sub>	01 00 00 00	transmit 2 <sup>nd</sup> TPDO with every SYNC
581	60	01	18	02 <sub>h</sub>	00 00 00 00	

After the PDOs have been defined, they can be enabled through the NMT:

COB-ID	Command specifier (CS)	Node-ID
0	1	1

If the mechanical resolution is to be defined, this can only be written through SDO 6093<sub>h</sub>, Sub-index 01<sub>h</sub> and 02<sub>h</sub>. The pre-setting after switching on the drive corresponds to the drive-specific factors PGEARI and PGEARO:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	93	60	01 <sub>h</sub>	00 00 10 00	2 <sup>20</sup> increments
581	60	93	60	01 <sub>h</sub>	00 00 00 00	
601	23	93	60	02 <sub>h</sub>	A0 8C 00 00	36000 user-units
581	60	93	60	02 <sub>h</sub>	00 00 00 00	

You could use this example, for instance, for operating a rotary table with 0.01° angular resolution.

After these settings, a homing movement can be set up and initiated:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2B	40	60	00 <sub>h</sub>	0F 00 00 00	control word: enable operation
581	60	40	60	00 <sub>h</sub>	00 00 00 00	
601	2F	60	60	00 <sub>h</sub>	06 00 00 00	mode: set <i>Homing</i> mode
581	60	60	60	00 <sub>h</sub>	00 00 00 00	
601	2F	98	60	00 <sub>h</sub>	0C 00 00 00	homing type 12, negative direction
581	60	98	60	00 <sub>h</sub>	00 00 00 00	
601	23	99	60	01 <sub>h</sub>	40 19 01 00	homing velocity 72000 units/s = 2 s <sup>-1</sup>
581	60	99	60	01 <sub>h</sub>	00 00 00 00	
601	2B	40	60	00 <sub>h</sub>	1F 00 00 00	start homing movement
581	60	40	60	00 <sub>h</sub>	00 00 00 00	

After the start of the homing movement, the following telegrams could come from the 1<sup>st</sup> TPDO:

COB-ID	Byte 0	Byte 1	Byte 2
181	27	00	21
181	27	10	27
181	27	10	23
181	27	14	2B
181	27	15	2A

The following bits from Byte 2 are required to detect the end of the homing movement:

Bit 0 = 0 : homing movement completed, Bit 1 = 1 : reference point set, Bit 3 = 1 In Position.

Afterwards, the homing movement is also ended by the control word, in this case through the 1<sup>st</sup> RPDO:

COB-ID	Byte 0	Byte 1
201	0F	00

Now you can change over to the *Profile position* mode and set the ramps to be used for positioning:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	23	83	60	00 <sub>h</sub>	32 00 00 00	50ms acceleration time
581	60	83	60	00 <sub>h</sub>	00 00 00 00	
601	23	84	60	00 <sub>h</sub>	32 00 00 00	50ms deceleration time
581	60	84	60	00 <sub>h</sub>	00 00 00 00	
601	2F	60	60	00 <sub>h</sub>	01 00 00 00	<i>Profile position mode</i>
581	60	60	60	00 <sub>h</sub>	00 00 00 00	

A positioning movement can only be initiated by providing the setpoints through the 1<sup>st</sup> RPDO, followed by a start through the 2<sup>nd</sup> RPDO. This uses handshaking with *New setpoint* (control word) and *Setpoint acknowledge* (status word).

a) Setpoint:

COB-ID	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
301	F4	01	00	00	E8	03	00	00

b) Control word with *new setpoint* bit (Bit 4) set:

COB-ID	Byte 0	Byte 1
201	1F	00

c) Wait until the CANopen status word signals *Setpoint acknowledge* (Bit 12): e.g.

COB-ID	Byte 0	Byte 1	Byte 2
181	27	15	03

d) Control word is reset by the *New setpoint* bit (Bit 4):

COB-ID	Byte 0	Byte 1
201	0F	00

e) Drive removes *Setpoint acknowledge*:

COB-ID	Byte 0	Byte 1	Byte 2
181	27	01	03

Wait for the positioning to be completed:

COB-ID	Byte 0	Byte 1	Byte 2
181	27	05	0A

## VI.1.8 ASCII Communication

It makes sense to use ASCII communication through PDOs, since they can be used more efficiently in this way. This requires that the NMT status machine is in the *operational* status.

Example: Read the parameter T-tacho (see Commissioning Software Manual DRIVE.EXE).  
(All data are hexadecimal, with the ASCII characters below, in square brackets.)

Direction	COB-ID	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
Master ⇒ SERVOSTAR™	301	47 <sub>h</sub> [G]	56 <sub>h</sub> [V]	46 <sub>h</sub> [F]	42 <sub>h</sub> [B]	54 <sub>h</sub> [T]	0D <sub>h</sub> [CR]	0A <sub>h</sub> [LF]	0 <sub>h</sub> [NUL]
SERVOSTAR™ ⇒ Master	281	30 <sub>h</sub> [0]	2E <sub>h</sub> [.]	36 <sub>h</sub> [6]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]
SERVOSTAR™ ⇒ Master	281	0D <sub>h</sub> [CR]	0A <sub>h</sub> [LF]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]
SERVOSTAR™ ⇒ Master	281	2D <sub>h</sub> [-]	2D <sub>h</sub> [-]	3E <sub>h</sub> [>]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]	0 <sub>h</sub> [NUL]

Explanation: In telegram 1, the master queries the *GVFBT* parameter, terminated by the ASCII code *CR LF*. The last free byte is filled by *NUL*.

The response of the SERVOSTAR™ is made in telegram 2, with the value *0.6*, the terminating code *CR LF*, and the prompt “—>” for the next parameter or command. The segmentation of the response into three telegrams is not mandatory, but depends on the transmission rate that has been set and the internal synchronization mechanism.

## VI.1.9 Test for Sync telegrams

Aims:

1. Assign/set *Start motion block* to the PDO (1<sup>st</sup> receive-PDO)
2. Assign *Actual position* (PDO21) to PDO (1<sup>st</sup> transmit-PDO), generated with every 2<sup>nd</sup> SYNC.
3. Assign *Status word* (PDO1) to PDO (2<sup>nd</sup> transmit-PDO), generated with every 3<sup>rd</sup> SYNC.

Telegrams with the corresponding responses:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	00	26	00 <sub>h</sub>	23 00 00 00	set PDO <i>Start motion block</i> to 1 <sup>st</sup> RPDO
581	60	00	26	00 <sub>h</sub>	00 00 00 00	
601	2F	00	2A	00 <sub>h</sub>	16 00 00 00	set PDO <i>Actual position</i> to 1 <sup>st</sup> TPDO
581	60	00	2A	00 <sub>h</sub>	00 00 00 00	
601	2F	01	2A	00 <sub>h</sub>	17 00 00 00	set PDO <i>Enhanced status word</i> to 2 <sup>nd</sup> TPDO
581	60	01	2A	00 <sub>h</sub>	00 00 00 00	
601	2F	00	18	02 <sub>h</sub>	02 00 00 00	1 <sup>st</sup> TPDO triggered for every 2 <sup>nd</sup> SYNC
581	60	00	18	02 <sub>h</sub>	00 00 00 00	
601	2F	01	18	02 <sub>h</sub>	03 00 00 00	2 <sup>nd</sup> TPDO triggered for every 3 <sup>rd</sup> SYNC
581	60	01	18	02 <sub>h</sub>	00 00 00 00	

## VI.1.10 SYNC Object

COB-ID
080

Meaning: Object 181 (TPDO 1) appears at every 2<sup>nd</sup> SYNC,  
Object 281 (TPDO 2) appears at every 3<sup>rd</sup> SYNC.

## VI.1.11 Emergency Object

If, for instance, the resolver connector is disconnected, a serious error will be caused in the controller. This results in an *Emergency* telegram.

COB-ID	Emergency error		Error register	
	Low	High		
081	10	43	08	00 00 00 00
081	00	00	88	00 00 00 00

motor temperature, temperature, manufacturer specific

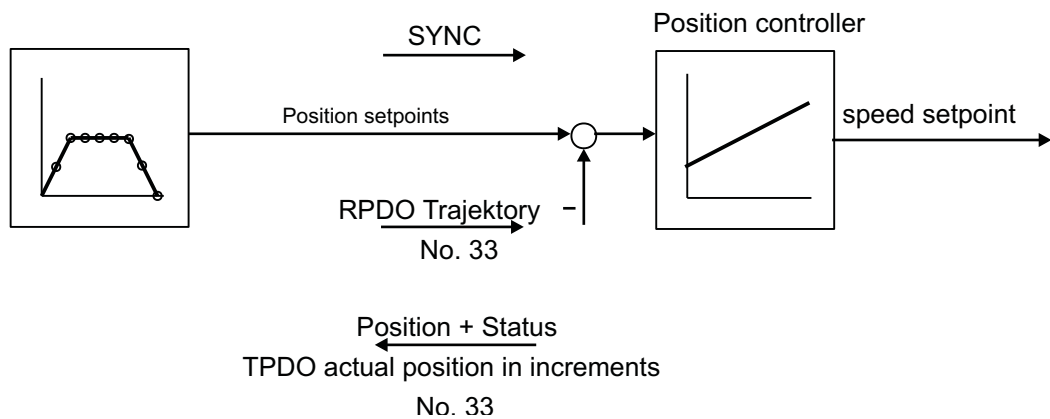
## VI.2 Special Applications

### VI.2.1 External Trajectory

#### VI.2.1.1 Position controller in the servo amplifier

This example shows the situation where 2 axes each receive position setpoints through RPDO 33 *Trajectory*.

**Controller structure for the position controller within the servo amplifier:**



### VI.2.1.1.1 Description

All data are hexadecimal. In the example, the two axes in the system have the station addresses 1 and 2.

Examples of telegrams and responses:

Conditions:

- The resolution that is to be used within one motor turn must be defined for both axes: *PRBASE* set to 16 or 20 bit resolution for 1 turn.
- The time raster for trajectory inputs must be set through the *PTBASE* parameter. Here one unit has a value of 250 microseconds: for example, *PTBASE* = 8 produces a 2 ms time raster.
- The parameters must be saved in the EEPROM.
- The saved values only become available after a reset.

The *Trajectory* PDO contains 2 trajectory setpoints, and can be transmitted simultaneously to several stations, whereby each station can extract the relevant trajectory data.

Map the second receive-PDO for both axes to RPDO 33 *Trajectory* ( $33_d = 21_h$ ):

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	26	00 <sub>h</sub>	21 00 00 00	set the <i>Trajectory</i> PDO for 1 <sup>st</sup> axis
581	60	01	26	00 <sub>h</sub>	00 00 00 00	
602	2F	01	26	00 <sub>h</sub>	21 00 00 00	set the <i>Trajectory</i> PDO for 2 <sup>nd</sup> axis
582	60	01	26	00 <sub>h</sub>	00 00 00 00	

After the *Trajectory* PDO has been mapped to the two axes, the communication parameters for both must be set so that they respond to the same Communication Object Identifier (COB-ID). The COB-ID for the first station can keep its default value of 301, the one for the second station can then be re-mapped to this setting:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
602	23	01	14	01 <sub>h</sub>	01 03 00 00	map 2 <sup>nd</sup> RPDO for 2 <sup>nd</sup> axis to 301
582	60	01	14	01 <sub>h</sub>	00 00 00 00	

Both stations will now respond to the same COB-ID 301.

SDO 2721<sub>h</sub> Sub-index 00<sub>h</sub> can then be used to define which portion of the 8 byte data field is used by each axis for its trajectory information. The value 0 selects Bytes 0 ... 3 of the data, and the value 1 selects bytes 4 ... 7.

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	21	27	00 <sub>h</sub>	00 00 00 00	1 <sup>st</sup> axis takes data from Bytes 0 ... 3
581	60	21	27	00 <sub>h</sub>	00 00 00 00	
602	2F	21	27	00 <sub>h</sub>	01 00 00 00	2 <sup>nd</sup> axis takes data from Bytes 4 ... 7
582	60	21	27	00 <sub>h</sub>	00 00 00 00	

The actual positions of the axes are to be returned as incremental actual positions to the controls. The second transmit-PDO in each case is therefore mapped to TPDO 33 *Incremental actual position* (33<sub>d</sub> = 21<sub>h</sub>):

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	2A	00 <sub>h</sub>	21 00 00 00	set the <i>Trajectory</i> PDO for 1 <sup>st</sup> axis
581	60	01	2A	00 <sub>h</sub>	00 00 00 00	
602	2F	01	2A	00 <sub>h</sub>	21 00 00 00	set the <i>Trajectory</i> PDO for 2 <sup>nd</sup> axis
582	60	01	2A	00 <sub>h</sub>	00 00 00 00	

Here it is assumed that both instruments accept new trajectory values with every SYNC command, and have to return their incremental position values. The communication parameters must be set accordingly:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	01	14	02 <sub>h</sub>	01 00 00 00	RPDO 2, axis 1, reaction for every SYNC
581	60	01	14	02 <sub>h</sub>	00 00 00 00	
602	2F	01	14	02 <sub>h</sub>	01 00 00 00	RPDO 2, axis 2, reaction for every SYNC
582	60	01	14	02 <sub>h</sub>	00 00 00 00	
601	2F	01	18	02 <sub>h</sub>	01 00 00 00	TPDO 2, axis 1, reaction for every SYNC
581	60	01	18	02 <sub>h</sub>	00 00 00 00	
602	2F	01	18	02 <sub>h</sub>	01 00 00 00	TPDO 2, axis 2, reaction for every SYNC
582	60	01	18	02 <sub>h</sub>	00 00 00 00	

In order to be able to make trajectory movements, both servo amplifiers must be operating in the appropriate mode. This is set through Index 6060<sub>h</sub>:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2F	60	60	00 <sub>h</sub>	FA 00 00 00	set trajectory mode for axis 1
581	60	60	60	00 <sub>h</sub>	00 00 00 00	
602	2F	60	60	00 <sub>h</sub>	FA 00 00 00	set trajectory mode for axis 2
582	60	60	60	00 <sub>h</sub>	00 00 00 00	

To start up the axes, the servo amplifiers must be put into the operational status (*operation enable*) and the network management functions must be started.

The network management functions enable the application of the Process Data Objects (PDOs) and are initialized by the following telegram for both axes:

Switch the NMT (Network Management) status machine to *operation enable*:

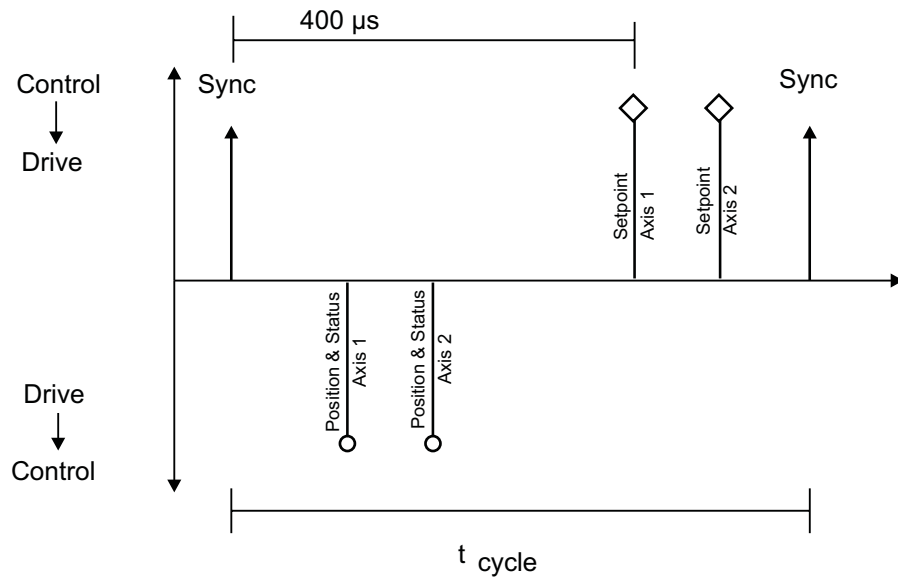
COB-ID	Command specifier (CS)	Node-ID	Comment
0	1	1	NMT enable for all axes

Next, power is applied to each servo amplifier, and they are put into the *operation enable* condition.

Control word for *operation enable*:

COB-ID	Control byte	Index		Sub-index	Data	Comment
		Low byte	High byte			
601	2B	40	60	00 <sub>h</sub>	0F 00 00 00	control word for axis 1
581	60	40	60	00 <sub>h</sub>	00 00 00 00	
602	2B	40	60	00 <sub>h</sub>	0F 00 00 00	control word for axis 2
582	60	40	60	00 <sub>h</sub>	00 00 00 00	

The configuration above now enables a cyclical sequence, as shown in the following diagram:



e.g. 2 axes

$t_{\text{cycle}}$  1 ms per axis at 1 MBaud

RPDO 2 can now be used to supply trajectory data for both axes, for instance:

COB-ID	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
301	F4	01	00	00	E8	03	00	00

In this example, the first axis receives a trajectory value of 500 increments (Bytes 0 ... 3) and the second axis receives a trajectory value of 1000 increments.

The axes accept these values, and the positioning is made when the next SYNC telegram is received.

The SYNC telegram looks like this:

COB-ID
080

Afterwards, both axes send back their incremental positions and the contents of their status registers when the SYNC Object with the COB-ID for the 2<sup>nd</sup> TPDO is received:

COB-ID	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7	Comment
181	23	01	00	00	00	00	03	44	position + manufacturer status register for axis1
182	A5	02	00	00	00	00	03	44	position + manufacturer status register for axis2

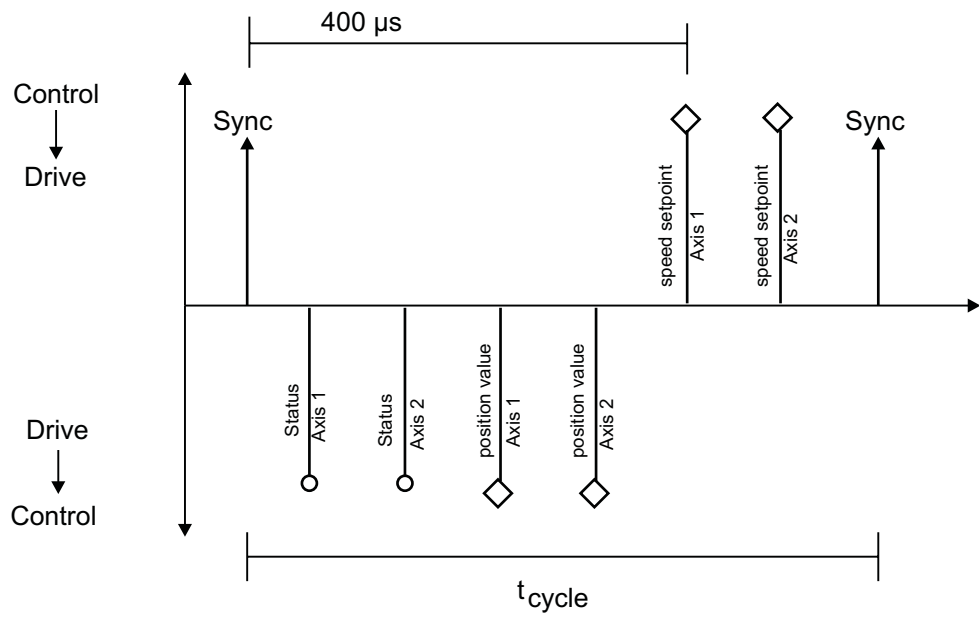
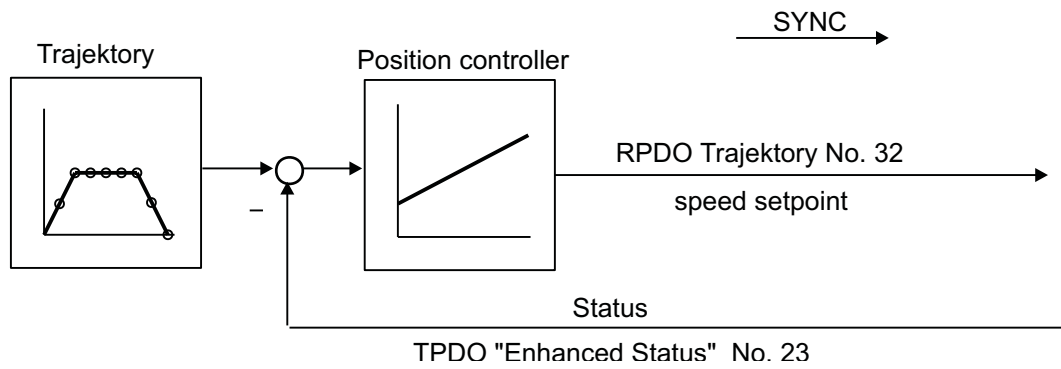
If an error occurs during operation, the axis concerned transmits an *Emergency* message, which could appear as follows:

Emergency Object

COB-ID	Emergency error		Error register	Category	
	Low	High			
081	10	43	08	01	00 00 00 00
081	00	00	08	00	00 00 00 00

motor temperature, temperature, manufacturer-specific

VI.2.1.2 Position controller in the control system



E.g. 2 axes

$t_{cycle}$  1 ms per Axis at 1 Mbaud

### VI.3 Description of the Object Dictionary

The following table describes the Dictionary.

The column *DEF* shows the corresponding profile:

**S** = SFRVOSTAR™      **3** = DS301      **4** = DS402

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
1000 <sub>h</sub>	—	3	UIINTEGER32	r	—	Device type	—
1001 <sub>h</sub>	—	3	UIINTEGER8	r	—	Error register	—
1002 <sub>h</sub>	—	3	UIINTEGER32	r	—	Manufacturer-specific status register	—
1003 <sub>h</sub>	00 <sub>h</sub>	3	UIINTEGER8	r	—	Predefined error field (number of entries)	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	Last reported error	—
1004 <sub>h</sub>	00 <sub>h</sub>	3	UNSIGNED32	r	—	Number of supported PDOs	—
	01 <sub>h</sub>	3	UNSIGNED32		—	Number of synchronous PDOs	—
	02 <sub>h</sub>	3	UNSIGNED32		—	Number of asynchronous PDOs	—
1005 <sub>h</sub>	—	3	UIINTEGER32	r	—	COB-ID SYNC message	—
1006 <sub>h</sub>	—	3	UNSIGNED32	r/w	—	Cycle time for communication	—
1007 <sub>h</sub>	—	3	UNSIGNED32		—	Time window for synchronous CAN messages	—
1008 <sub>h</sub>	—	3	Visible String	r	—	Device name	VER*
100A <sub>h</sub>	—	3	Visible String	r	—	Software version	ADDR
100B <sub>h</sub>	—	3	UIINTEGER32	r	—	Node address	—
100C <sub>h</sub>	—	3	UIINTEGER16	r/w	—	Guard time	—
100D <sub>h</sub>	—	3	UIINTEGER8	r/w	—	Lifetime factor	—
100E <sub>h</sub>	—	3	UNSIGNED32	r/w	—	Node Guarding COB Identifier	—
100F <sub>h</sub>	—	3	UNSIGNED32	r/w	—	Number of supported SDOs	—
1010 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	Store parameters	—
	01 <sub>h</sub>	3	UNSIGNED32	r/w	—	save all parameters	—
	02 <sub>h</sub>	3	UNSIGNED32	r/w	—	save communication parameters	—
1012 <sub>h</sub>	—	3	UNSIGNED32	r/w	—	COB-ID for the time stamp message (in preparation)	—
1013 <sub>h</sub>	—	3	UNSIGNED32	r/w	—	High resolution time stamp (in preparation)	—
1014 <sub>h</sub>	—	3	UNSIGNED32	r/w	—	COB-ID for the Emergency message	—
1018 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	Identity Object	—
	01 <sub>h</sub>	3	UIINTEGER32	r	—	Vendor ID	—
	02 <sub>h</sub>	3	UIINTEGER32	r	—	Product Code	—
	03 <sub>h</sub>	3	UIINTEGER32	r	—	Revision number	—
	04 <sub>h</sub>	3	UIINTEGER32	r	—	Serial number	SERIALNO
1400 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	1 <sup>st</sup> receive-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB - ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	supported by receive-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1401 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	2 <sup>nd</sup> receive-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB-ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by receive-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1402 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	3 <sup>rd</sup> receive-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB-ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by receive-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
1403 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	4 <sup>th</sup> receive-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB-ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by receive-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1600 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	1 <sup>st</sup> receive-PDO mapping parameter	—
	01 <sub>h</sub> -08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th Object	—
1601 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	2 <sup>nd</sup> receive- PDO mapping parameter	—
	01 <sub>h</sub> -08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th Object	—
1602 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	3 <sup>rd</sup> receive- PDO mapping parameter	—
	01 <sub>h</sub> -08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th Object	—
1603 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	4 <sup>th</sup> receive- PDO mapping parameter	—
	01 <sub>h</sub> -08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th Object	—
1800 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	1 <sup>st</sup> transmit-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB-ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by transmit-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1801 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	2 <sup>nd</sup> transmit-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB - ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by transmit-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1802 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/wr	—	3 <sup>rd</sup> transmit-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB - ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by transmit-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1803 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r	—	4 <sup>th</sup> transmit-PDO communication parameter	—
	01 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO COB - ID	—
	02 <sub>h</sub>	3	UIINTEGER8	r/w	—	Transmission type	—
	03 <sub>h</sub>	3	UIINTEGER16	r/w	—	Supported by transmit-PDO	—
	04 <sub>h</sub>	3	UIINTEGER8	r/w	—	Compatibility entry (CMS priority group)	—
1A00 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	1 <sup>st</sup> transmit-PDO mapping parameter	—
	01 <sub>h</sub> -08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th object	—
1A01 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	2 <sup>nd</sup> transmit-PDO mapping parameter	—
	01-08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th object	—
1A02 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	3 <sup>rd</sup> transmit-PDO mapping parameter	—
	01-08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th object	—
1A03 <sub>h</sub>	00 <sub>h</sub>	3	RECORD	r/w	—	4 <sup>th</sup> transmit-PDO mapping parameter	—
	01-08 <sub>h</sub>	3	UIINTEGER32	r/w	—	PDO mapping parameter for the n-th object	—
2014 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Mask PDOs 37..40 Channel 1	—
	01 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 0 ... 3)	—
	02 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 4 ... 7)	—
2015 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Mask PDOs 37..40 Channel 2	—
	01 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 0 ... 3)	—
	02 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 4 ... 7)	—
2016 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Mask PDOs 37..40 Channel 3	—
	01 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 0 ... 3)	—
	02 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 4 ... 7)	—

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
2017 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Mask PDOs 37..40 Channel 4	—
	01 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 0 ... 3)	—
	02 <sub>h</sub>	S	UIINTEGER32	r/w	—	Mask (Byte 4 ... 7)	—
2020 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Position controller	—
	01 <sub>h</sub>	S	UIINTEGER8	r/w	—	Axis type	POSCNFG
	02 <sub>h</sub>	S	INTEGER32	r/w	—	In-Position window	PEINPOS
	03 <sub>h</sub>	S	INTEGER32	r/w	—	Lag/following error window	PEMAX
	04 <sub>h</sub>	S	INTEGER32	r/w	—	Position register 1	SWE1
	05 <sub>h</sub>	S	INTEGER32	r/w	—	Position register 2	SWE2
	06 <sub>h</sub>	S	INTEGER32	r/w	—	Position register 3	SWE3
	07 <sub>h</sub>	S	INTEGER32	r/w	—	Position register 4	SWE4
	08 <sub>h</sub>	S	UIINTEGER32	r/w	—	Denominator for resolution	PGEARO
	09 <sub>h</sub>	S	UIINTEGER32	r/w	—	Numerator for resolution	PGEAR
	0A <sub>h</sub>	S	UIINTEGER8	r/w	—	Count direction	DIR
2022 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Position data for <i>Position</i> mode	—
	01 <sub>h</sub>	S	INTEGER32	r/w	☒	Position (motion block 0)	O_P
	02 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Weighted velocity, see ASCII VMUL (motion block 0, see also SDO 2020 <sub>h</sub> Sub-index 02 <sub>h</sub> )	O_V
	03 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Motion task type (motion block 0)	O_C
	04 <sub>h</sub>	S	INTEGER32	r/w	☒	Position for external trajectory	—
	05 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Motion task number	—
	06 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Acceleration time (motion block 0)	O_ACC1
	07 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Braking time (motion block 0)	O_DEC1
	08 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Jolt limit for acceleration time (motion block 0)	O_ACC2
	09 <sub>h</sub>	S	UIINTEGER16	r/w	☒	Jolt limiting for braking time (motion block 0)	O_DEC2
	0A <sub>h</sub>	S	UIINTEGER16	r/w	☒	Number of following task	O_FN
	0B <sub>h</sub>	S	UIINTEGER16	r/w	☒	Start delay for following task	O_FT
	0C <sub>h</sub>	S	2 x UIINTEGER16	r/w	—	Copy a motion task	OCOPY
	0D <sub>h</sub>	S	UIINTEGER16	r/w	☒	Velocity weighting factor (SDO 2020 <sub>h</sub> Sub-index 02 <sub>h</sub> )	VMUL
	0E <sub>h</sub>	S	UIINTEGER32	r/w	☒	Speed/velocity (motion block 0)	O_V
2024 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Setup operation for <i>Position</i> mode	—
	01 <sub>h</sub>	S	UIINTEGER8	r/w	—	Homing type	NREF
	02 <sub>h</sub>	S	UIINTEGER8	r/w	—	Homing direction	DREF
	03 <sub>h</sub>	S	INTEGER32	r/w	—	Velocity for homing movement	VREF
	04 <sub>h</sub>	S	UIINTEGER16	r/w	—	Acceleration ramp [jogging and homing]	ACCR
	05 <sub>h</sub>	S	UIINTEGER16	r/w	—	Braking ramp [jogging and homing]	DECR
	06 <sub>h</sub>	S	INTEGER32	r/w	—	Reference offset	ROFFS
2026 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Special Object for <i>Position</i> mode	—
	01 <sub>h</sub>	S	UIINTEGER8	r/w	—	Activate internal evaluation unit for saving actual position value	—
2050 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Aux. variable for the digital inputs	—
	01 <sub>h</sub>	S	INTEGER32	r/w	—	Trigger variable input 1	IN1TRIG
	02 <sub>h</sub>	S	INTEGER32	r/w	—	Trigger variable input 2	IN2TRIG
	03 <sub>h</sub>	S	INTEGER32	r/w	—	Trigger variable input 3	IN3TRIG
	04 <sub>h</sub>	S	INTEGER32	r/w	—	Trigger variable input 4	IN4TRIG
2051 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Configuration for threshold register	—
	01 <sub>h</sub>	S	UIINTEGER32	r/w	—	Monitoring (deactivate / activate)	WPOSE
	02 <sub>h</sub>	S	UIINTEGER32	r/w	—	Signaling type (repeated / once)	WPOSX
	03 <sub>h</sub>	S	UIINTEGER32	r/w	—	Polarity position signaling	WPOSP

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
2052 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Position threshold register ABSOLUTE (refresh time < 1ms)	POSRSTAT
	01 <sub>h</sub>	S	INTEGER32	r	—	Position register	P1
	02 <sub>h</sub>	S	INTEGER32	r	—	Position register	P2
	03 <sub>h</sub>	S	INTEGER32	r	—	Position register	P3
	04 <sub>h</sub>	S	INTEGER32	r	—	Position register	P4
	05 <sub>h</sub>	S	INTEGER32	r	—	Position register	P5
	06 <sub>h</sub>	S	INTEGER32	r	—	Position register	P6
	07 <sub>h</sub>	S	INTEGER32	r	—	Position register	P7
	08 <sub>h</sub>	S	INTEGER32	r	—	Position register	P8
	09 <sub>h</sub>	S	INTEGER32	r	—	Position register	P9
	0A <sub>h</sub>	S	INTEGER32	r	—	Position register	P10
	0B <sub>h</sub>	S	INTEGER32	r	—	Position register	P11
	0C <sub>h</sub>	S	INTEGER32	r	—	Position register	P12
	0D <sub>h</sub>	S	INTEGER32	r	—	Position register	P13
	0E <sub>h</sub>	S	INTEGER32	r	—	Position register	P14
	0F <sub>h</sub>	S	INTEGER32	r	—	Position register	P15
	10 <sub>h</sub>	S	INTEGER32	r	—	Position register	P16
2053 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	Position threshold RELATIVE (refresh time < 1ms) see also ASCII	POSRSTAT
	01 <sub>h</sub>	S	INTEGER32	r	—	Position register	P1
	02 <sub>h</sub>	S	INTEGER32	r	—	Position register	P2
	03 <sub>h</sub>	S	INTEGER32	r	—	Position register	P3
	04 <sub>h</sub>	S	INTEGER32	r	—	Position register	P4
	05 <sub>h</sub>	S	INTEGER32	r	—	Position register	P5
	06 <sub>h</sub>	S	INTEGER32	r	—	Position register	P6
	07 <sub>h</sub>	S	INTEGER32	r	—	Position register	P7
	08 <sub>h</sub>	S	INTEGER32	r	—	Position register	P8
	09 <sub>h</sub>	S	INTEGER32	r	—	Position register	P9
	0A <sub>h</sub>	S	INTEGER32	r	—	Position register	P10
	0B <sub>h</sub>	S	INTEGER32	r	—	Position register	P11
	0C <sub>h</sub>	S	INTEGER32	r	—	Position register	P12
	0D <sub>h</sub>	S	INTEGER32	r	—	Position register	P13
	0E <sub>h</sub>	S	INTEGER32	r	—	Position register	P14
	0F <sub>h</sub>	S	INTEGER32	r	—	Position register	P15
	10 <sub>h</sub>	S	INTEGER32	r	—	Position register	P16
2060 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER32	r/w	—	Speed or current setpoint	—

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
2070 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Manufacturer-specific actual values	—
	01 <sub>h</sub>	S	INTEGER24	r	☒	Actual position (rot. angle, 20-bit res./turn)	PRD
	02 <sub>h</sub>	S	INTEGER24	r	☒	Speed in incr. (1[incr.] = 1875/262144 [rpm])	—
	03 <sub>h</sub>	S	INTEGER32	r	☒	Incr. act. position (res. depends on PRBASE)	—
	04 <sub>h</sub>	S	UINTEGER16	r	☒	Stored position (HW - LATCH positive, 16-bit resolution/turn)	LATCH16
	05 <sub>h</sub>	S	INTEGER32	r	☒	Stored position (HW - LATCH positive, 32-bit resolution/turn )	LATCH32
	06 <sub>h</sub>	S	INTEGER32	r	☒	Position, dependent on gearing factors (PGEARI, PGEARO)	PFB
	07 <sub>h</sub>	S	INTEGER32	r	—	Velocity, dependent on gearing factors (PGEARI, PGEARO)	PV
	08 <sub>h</sub>	S	INTEGER32	r	☒	Lag error, dependent on gearing factors (PGEARI, PGEARO)	PE
	09 <sub>h</sub>	S	UINTEGER32	r	—	Effective (r.m.s.) current	I
	0A <sub>h</sub>	S	INTEGER32	r	☒	Speed, revs/min	V
	0B <sub>h</sub>	S	INTEGER32	r	—	Heat sink temperature	TEMPH
	0C <sub>h</sub>	S	INTEGER32	r	—	Internal temperature	TEMPE
	0D <sub>h</sub>	S	INTEGER32	r	—	DC-link (DC-bus) voltage	VBUS
	0E <sub>h</sub>	S	INTEGER32	r	—	Ballast power	PBAL
0F <sub>h</sub>	S	INTEGER32	r	—	I <sup>2</sup> t loading	I2T	
10 <sub>h</sub>	S	INTEGER32	r	—	Operating time	TRUN	
11 <sub>h</sub>	S	INTEGER32	r	☒	Enhanced status for TPDO 33	—	
2080 <sub>h</sub>	00 <sub>h</sub>	S	ARRAY	r	—	Status information	—
	01 <sub>h</sub>	S	UINTEGER8	r	☒	Input/Output/Latch	—
	02 <sub>h</sub>	S	UINTEGER8	r	☒	Collective info (Warning/Error/Reserve)	—
	03 <sub>h</sub>	S	UINTEGER8	r	☒	DRVSTAT LSB	DRVSTAT
	04 <sub>h</sub>	S	UINTEGER8	r	☒	“	DRVSTAT
	05 <sub>h</sub>	S	UINTEGER8	r	☒	“	DRVSTAT
	06 <sub>h</sub>	S	UINTEGER8	r	☒	DRVSTAT MSB	DRVSTAT
	07 <sub>h</sub>	S	UINTEGER8	r	☒	TRJSTAT LSB	TRJSTAT
	08 <sub>h</sub>	S	UINTEGER8	r	☒	“	TRJSTAT
	09 <sub>h</sub>	S	UINTEGER8	r	☒	“	TRJSTAT
0A <sub>h</sub>	S	UINTEGER8	r	☒	TRJSTAT MSB	TRJSTAT	
2081 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	Incr. actual position (bytewise/24-bit)	—
	01 <sub>h</sub>	S	INTEGER8	r	☒	Incr. position LSB	—
	02 <sub>h</sub>	S	INTEGER8	r	☒	Incremental position	—
	03 <sub>h</sub>	S	INTEGER8	r	☒	Incremental position	—
	04 <sub>h</sub>	S	INTEGER8	r	☒	Incremental position MSB	—
	05 <sub>h</sub>	S	INTEGER24	r	☒	Incremental position 24-bit	—
	06 <sub>h</sub>	S	INTEGER32	r	☒	Incremental position 32-bit	—
2082 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	32/24-bit positive latch	—
	01 <sub>h</sub>	S	INTEGER32	r	☒	32-bit latch	LATCH32
	02 <sub>h</sub>	S	INTEGER24	r	☒	24-bit latch	—
2083 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	32/24-bit negative latch	—
	01 <sub>h</sub>	S	INTEGER32	r	☒	32-bit latch	LATCH32N
	02 <sub>h</sub>	S	INTEGER24	r	☒	24-bit latch	—
2084 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	16-bit positive latch	—
	01 <sub>h</sub>	S	INTEGER16	r	☒	16-bit latch	LATCH16
2085 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r	—	16-bit negative latch	—
	01 <sub>h</sub>	S	INTEGER16	r	☒	16-bit latch	LATCH16N
2086 <sub>h</sub>	00 <sub>h</sub>	S	UINTEGER16	r	☒	Position trigger word	POSRSTAT
2600 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	1 <sup>st</sup> receive-PDO select	—

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object	
2601 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	2 <sup>nd</sup> receive-PDO select	—	
2602 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	3 <sup>rd</sup> receive-PDO select	—	
2603 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	4 <sup>th</sup> receive-PDO select	—	
2721 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	Configuration receive-PDO 33	—	
2A00 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	1 <sup>st</sup> transmit-PDO select	—	
2A01 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	2 <sup>nd</sup> transmit-PDO select	—	
2A02 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	3 <sup>rd</sup> transmit-PDO select	—	
2A03 <sub>h</sub>	00 <sub>h</sub>	S	INTEGER8	r/w	—	4 <sup>th</sup> transmit-PDO select	—	
3100 <sub>h</sub>	00 <sub>h</sub>	S	Visible String	r/w	—	ASCII character direction	—	
3500 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Start of Object Channel	—	
	01 <sub>h</sub>	S	UNSIGNED16	r	—	Total number of Objects in Object Channel	MAXSDO	
	02 <sub>h</sub>	S	UNSIGNED16	r	—	Lower limit value	—	
	03 <sub>h</sub>	S	UNSIGNED16	r	—	Upper limit value	—	
	04 <sub>h</sub>	S	UNSIGNED16	r	—	Default value	—	
	05 <sub>h</sub>	S	UNSIGNED8	r	—	Data format of Object	—	
	06 <sub>h</sub>	S	UNSIGNED32	r	—	Check data	—	
	07 <sub>h</sub>	S	—	—	—	reserved	—	
3501 <sub>h</sub>	00 <sub>h</sub>	S	RECORD	r	—	Acceleration ramp: speed control	—	
	01 <sub>h</sub>	S	UNSIGNED16	r	—	Value	ACC	
	02 <sub>h</sub>	S	UNSIGNED16	r	—	Lower limit value	—	
	03 <sub>h</sub>	S	UNSIGNED16	r	—	Upper limit value	—	
	04 <sub>h</sub>	S	UNSIGNED16	r	—	Default value	—	
	05 <sub>h</sub>	S	UNSIGNED8	r	—	Data format of Object	—	
	06 <sub>h</sub>	S	UNSIGNED32	r	—	Check data	—	
	07 <sub>h</sub>	S	—	—	—	reserved	—	
6040 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER16	w	☒	DS402 control word	—	
	00 <sub>h</sub>	4	INTEGER16	r	☒	DS402 Status	—	
	605A <sub>h</sub>		4	INTEGER16	r/w	—	Quick Stop option code	—
	6060 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER16	w	☒	Mode of Operation	—
	6061 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER16	r	☒	Display Mode of Operation	—
	6063 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r	☒	Incr. actual position	—
	6064 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r	☒	Actual position (taking account of gearing factors)	—
	606C <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r	☒	Actual speed (mode: pv)	—
	607A <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r/w	☒	Target position (mode: pp)	—
		00 <sub>h</sub>	4	ARRAY	r	—	position_range_limit	—
	607B <sub>h</sub>	01 <sub>h</sub>	4	INTEGER32	r/w	—	min_position_range_limit	—
		02 <sub>h</sub>	4	INTEGER32	r/w	—	max_position_range_limit	—
	607C <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r/w	☒	Reference offset	—
	6081 <sub>h</sub>	00 <sub>h</sub>	4	UINTEGER32	r/w	☒	Velocity (Mode: pp)	—
	6082 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	☒	Limit velocity/speed (Mode: pp)	—
	6083 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	☒	Acceleration (Mode: pp pv)	—
	6084 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	☒	Deceleration (Mode: pp pv)	—
	6086 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER16	r/w	☒	Type of motion block ramp (motion profile type)	—
	6089 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER8	r/w	☒	Notation index: position (not supported)	—
	608A <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED8	r/w	☒	Dimension index: position (not supported)	—
	608B <sub>h</sub>	00 <sub>h</sub>	4	INTEGER8	r/w	☒	Notation index: speed (not supported)	—
	608C <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED8	r/w	☒	Dimension index: speed (not supported)	—
	608D <sub>h</sub>	00 <sub>h</sub>	4	INTEGER8	r/w	☒	Notation index: acceleration (not supported)	—

Index	Sub-index	DEF	Data format	Access	PDO mapp.	Description	ASCII Object
608E <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED8	r/w	<input checked="" type="checkbox"/>	Dimension index: acceleration (not supported)	—
6093 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	—	Position factor	—
	01 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Numerator	PGEARO
	02 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	feed_constant	PGEARI
6094 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	—	Velocity factor: encoder	—
	01 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Numerator	—
	02 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Divisor	—
6097 <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	—	Acceleration factor	—
	01 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Divisor	—
	02 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Acceleration factor	—
6098 <sub>h</sub>	00 <sub>h</sub>	4	INTEGER8	r/w	<input checked="" type="checkbox"/>	Homing type	—
6099 <sub>h</sub>	00 <sub>h</sub>	4	wARRAY	r	—	Homing velocity	—
	01 <sub>h</sub>	4	INTEGER32	r/w	<input checked="" type="checkbox"/>	Homing velocity (homing to references switch)	—
609A <sub>h</sub>	00 <sub>h</sub>	4	UNSIGNED32	r/w	<input checked="" type="checkbox"/>	Homing acceleration	—
60FF <sub>h</sub>	00 <sub>h</sub>	4	INTEGER32	r/w	<input checked="" type="checkbox"/>	Speed setpoint	—

## VI.4

### New configuration of SERVOSTAR™ 400/600

In SERVOSTAR™ 400/600 there are a number of parameters, that can only be integrated into the current firmware program and produce their proper effect for the first time during the initialization phase, when the instrument is switched on. As a result, an alteration of one of these parameters means that all parameters have to be saved, and the instrument must then be restarted. This can be carried out via the CAN-bus, by using the following SDOs:

1. Write SDO 35EB<sub>h</sub> Sub-index 01<sub>h</sub>, value 0, save command
2. Write SDO 3632<sub>h</sub> Sub-index 01<sub>h</sub>, value 0, restart instrument

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## VI.5 Index

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