CANOpen Master

straton user guide – Rev. 8

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Content

1. Install Editor and Runtime

Download and install from https://straton-plc.com/telechargements/

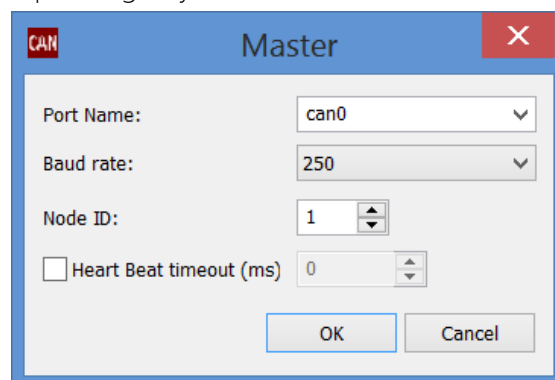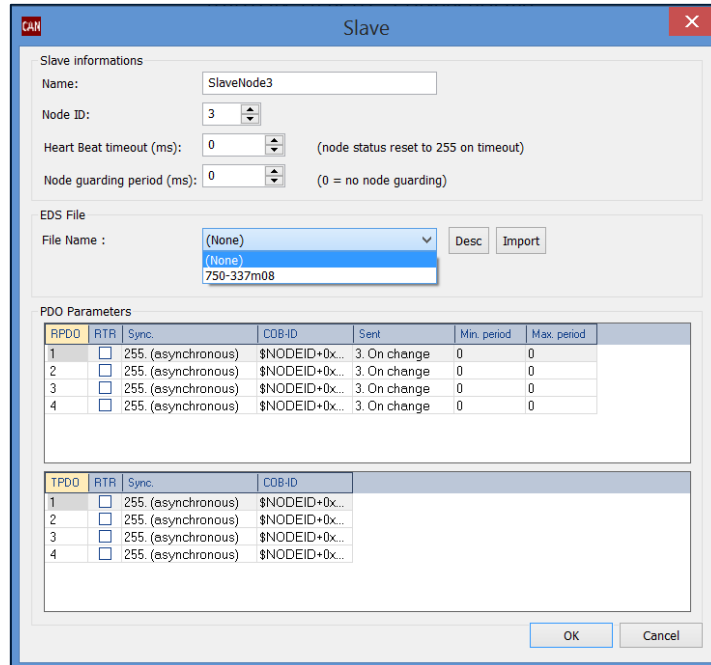# 2. Driver configuration

Open the IO Drivers window (⊞), insert a new configuration (⊟) and select the CANopen bus driver.
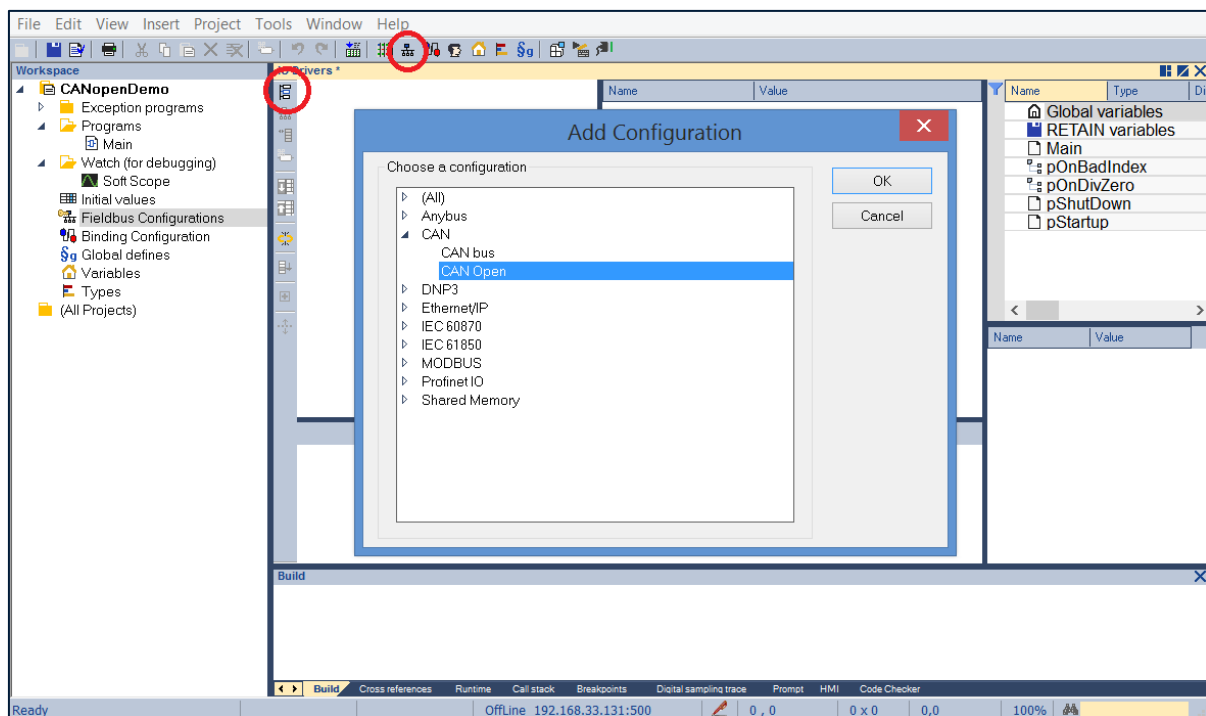
Insert a Master/Port (⊞) corresponding to your CAN controller.

Insert a Slave/Datablock (⬛) and enter the corresponding CAN information.

Select the CANopen device in the EDS area, if your device is not listed here select "Import" and select the corresponding EDS file.

Create the PDO mapping:
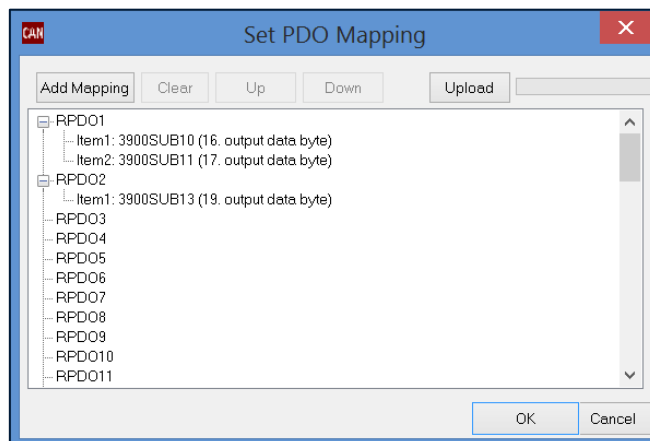
▸   Right click on the CANopen port to select the PDO mapping tool:

Using "Add Mapping" command you can select the CANopen object to be connected to the PDO.

IMPORTANT: if the EDS file does not exist or is empty, or if there is no object which can be mapped in the EDS file, this dialog won't appear.

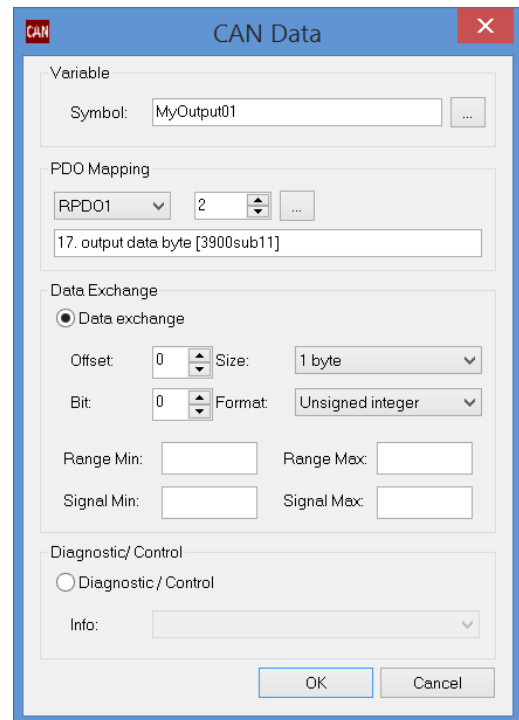Using Insert variable button (⬚) connected each object to a straton variable.

Repeat for each PDO and each object.

Additionally connect some Diagnostic/Control variable available in the straton application to make advance diagnostic or control on the CANopen Fieldbus.

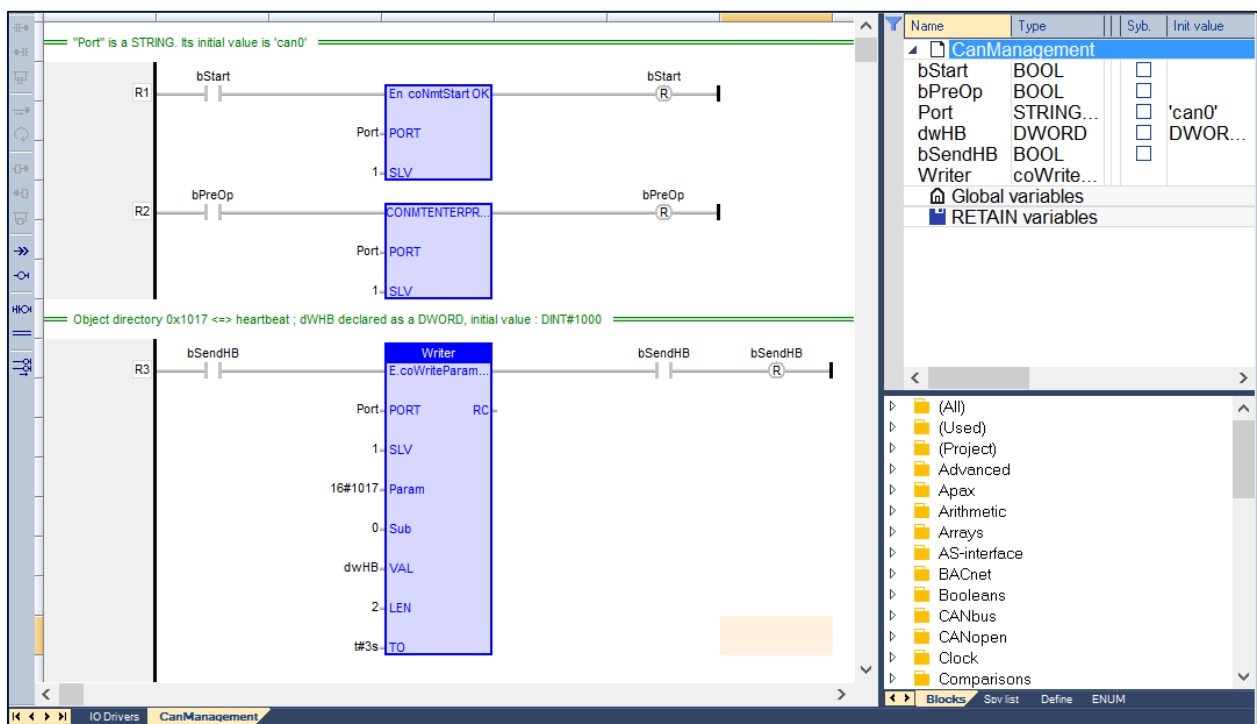Create the main program to manage the CANopen network.

3. Download the application

Download the application to the runtime:

▶ Select the communication parameters in menu Tools/Communication Parameters

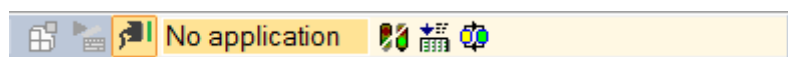▶ Establish the connection through menu Project/Online

RESULT IS:

The download is successful and application starts correctly.

The runtime is not started or communication parameters are wrong.

The application is not yet downloaded or an error occurs during startup. More detail can be found in the output view.

4. Error codes of Return Check

Functions blocks coSendPdoMap and coWriteParam have a DINT output called RC. The possible values are:

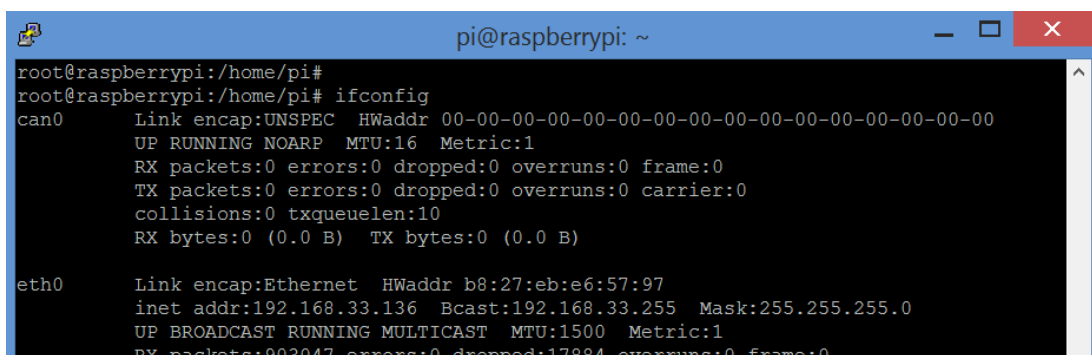| Value	Meaning
0	OK
-1	Bad parameters
-2	Timeout
>0	Error code in the received CANopen message(refer to standard)

5. Frequently Asked Questions

WHAT ARE THE "PORT NAMES" FOR THE CAN PORT?

The settings of the CAN port are OEM dependent, the following parameter are available for the runtime:

- **Kvaser CAN :** T5CANKvaser
- **Grid Connect :** T5CanGridConnect
- **PEAK :** T5CanGridConnect
- **IXXAT :** T5CanIxxat

If the runtime is embedded on a device, then this parameter must be the name of the CAN port, for example it can be "can0"