

Communications Manual

MC 5010

MC5005

MC5004

MCS

CANopen®

Imprint

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About this document

1 About this document

1.1 Validity of this document

This document describes:

- Communication with the drive via CANopen
- Basic services provided by the Communication structure
- Methods for accessing the parameters
- Drive from the viewpoint of the communication system

This document is intended for software developers with CAN-BUS experience, and for CAN-BUS project engineers.

All data in this document relate to the standard versions of the drives. Changes relating to customer-specific versions can be found in the attached sheet.

All data in this document relate to the firmware revision G.

1.2 Associated documents

For certain actions during commissioning and operation of FAULHABER products additional information from the following manuals is useful:

Manual	Description
Motion Manager 6	Operating instructions for FAULHABER Motion Manager PC software
Quick start guide	Description of the first steps for commissioning and operation of FAULHABER Motion Controllers
Drive functions	Description of the operating modes and functions of the drive
Technical manual	Instructions for installation and use of the FAULHABER Motion Controller
CiA 301	CANopen application layer and communication profile
CiA 402	CANopen device profile for drives and motion control

These manuals can be downloaded in pdf format from the web page www.faulhaber.com/manuals/.

1.3 Using this document

- ▶ Read the document carefully before undertaking configuration.
- ▶ Retain the document throughout the entire working life of the product.
- ▶ Keep the document accessible to the operating personnel at all times.
- ▶ Pass the document on to any subsequent owner or user of the product.

About this document

1.4 List of abbreviations

Abbreviation	Meaning
Attr.	Attribute
CAN	Controller Area Network
CiA	CAN in Automation e.V.
COB ID	Communication Object Identifier
CS	Command Specifier
EEPROM	Electrically Erasable Programmable Read-Only Memory
EMCY	Emergency
HB	High Byte
HHB	Higher High Byte
HLB	Higher Low Byte
LB	Low Byte
LHB	Lower High Byte
LLB	Lower Low Byte
LSB	Least Significant Byte
LSS	Layer Setting Service
MSB	Most Significant Byte
NMT	CANopen network management
OD	Object Dictionary
PDO	Process Data Object
PP	Profile Position
PV	Profile Velocity
ro	read only
RTR	Remote Request
rw	read-write
RxPDO	Receive Process Data Object (PDO received from the drive)
SDO	Service Data Object
PLC	Programmable Logic Controller
Sxx	Data type signed (negative and positive numbers) with bit size xx
SYNC	Synchronisation Object
TxPDO	Transmit Process Data Object (PDO sent from the drive)
Uxx	Data type unsigned (positive numbers) with bit size xx

About this document

1.5 Symbols and markers



NOTICE!
Risk of damage.

- ▶ Measures for avoidance



Instructions for understanding or optimising the operational procedures

- ✓ Pre-requirement for a requested action
- 1. First step for a requested action
 - ↪ Result of a step
- 2. Second step of a requested action
 - ↪ Result of an action
- ▶ Request for a single-step action

2 Overview

2.1 Basic arrangement of a CANopen device

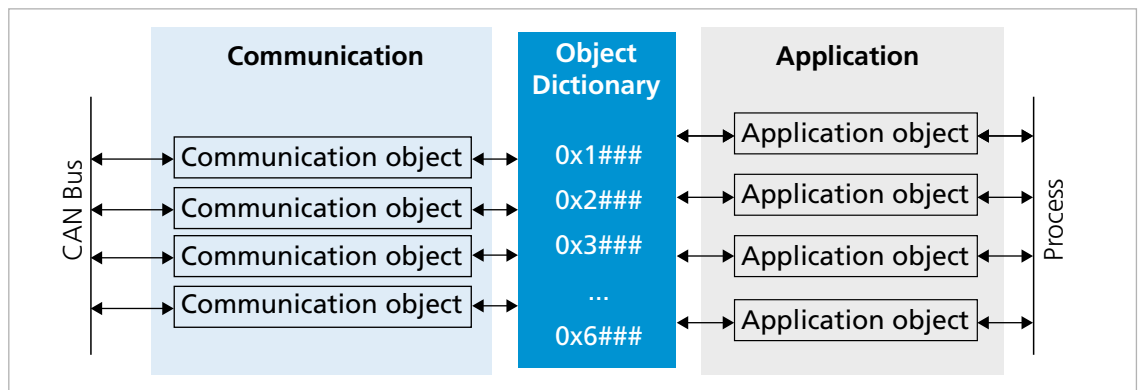


Fig. 1: Basic arrangement of a CANopen device

Communication services

The CANopen master communicates with the object dictionary via the bus system and use of the communication services (see chap. 3.2, p. 15).

Object Dictionary

The object dictionary contains parameters, set values- and actual values of a drive. The object dictionary is the link between the application (drive functions) and the communication services. All objects in the object dictionary can be addressed by a 16-bit index number (0x1000 to 0x6FFF) and an 8-bit subindex (0x00 to 0xFF).

Index	Assignment of the objects
0x1000 to 0x1FFF	Communication objects
0x2000 to 0x5FFF	Manufacturer-specific objects
0x6000 to 0x6FFF	Objects of the drive profile to CiA 402

The values of the parameters can be changed by the communication side or by the drive side.

Application part

The application part contains drive functions corresponding to CiA 402. The drive functions read parameters from the object dictionary, obtain the setpoints from the object dictionary and return actual values. The parameters from the object dictionary determine the behaviour of the drive.



No further details of the application part are given in this document. The communication with the drive and the associated operating modes are described in the separate "Drives Functions" manual.

Overview

2.2 Pre-conditions for communication

FAULHABER drives are delivered in the unconfigured state. For operation in a CAN network, a unique node number must be assigned and a Baud rate set at commissioning (see chap. 5, p. 40).

After switching on and initialising, the Motion Controller is at first in the **Pre-Operational** state. In order to be able to perform drive functions, the Motion Controller must be brought into the **Operational** state (see chap. 3.8, p. 27).

1. Connect the controller to a power supply (supply at least to the electronics).
2. Connect CAN_H, CAN_L, GND to the respective terminals of a host-side CAN connection.
3. Switch on the power and establish a connection via the configuration application.

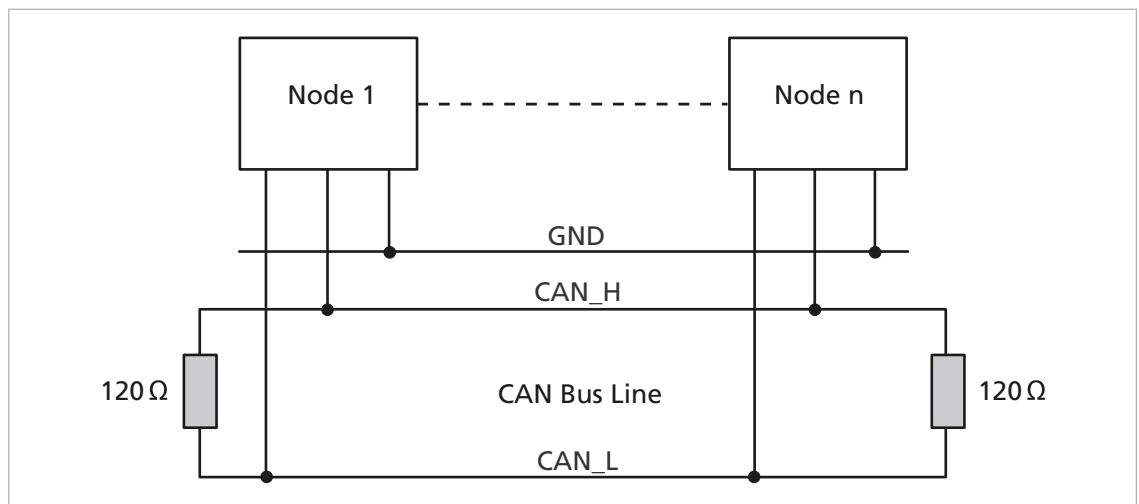


Fig. 2: Connection to the CANopen network

2.3 FAULHABER Motion Manager

We recommend that the first commissioning of a FAULHABER drive is performed using "FAULHABER Motion Manager" software.

The FAULHABER Motion Manager permits simple access to the settings and parameters of the connected motor controller. The graphical user interface allows configurations to be read, changed and reloaded. Individual commands or complete parameter sets and program sequences can be input and loaded to the controller.

Wizard functions support the user when commissioning the drive controllers. The wizard functions are arranged on the user interface in the sequence they are normally used:

- Connection wizard: Supports the user when establishing the connection to the connected controller
- Motor wizard: Supports the user when configuring an external controller to the connected motor, by selecting the respective FAULHABER motor
- Control setting wizard: Supports the user in optimising the control parameters.

The software can be downloaded free of charge from the FAULHABER Internet page.



We recommend always using the latest version of the FAULHABER Motion Manager.

The FAULHABER Motion Manager is described in the separate "Motion Manager 6" manual. The contents of the manual are also available as context-sensitive online help within the FAULHABER Motion Manager.

Overview

2.4 Saving and restoring parameters

So that changed parameters in the OD remain active in the controller when it is switched on again, the "Save" command must be executed to save them permanently in the non-volatile memory (application EEPROM) (see chap. 6.1, p. 43). When the motor is switched on, the parameters are loaded automatically from the non-volatile memory into the volatile memory (RAM)

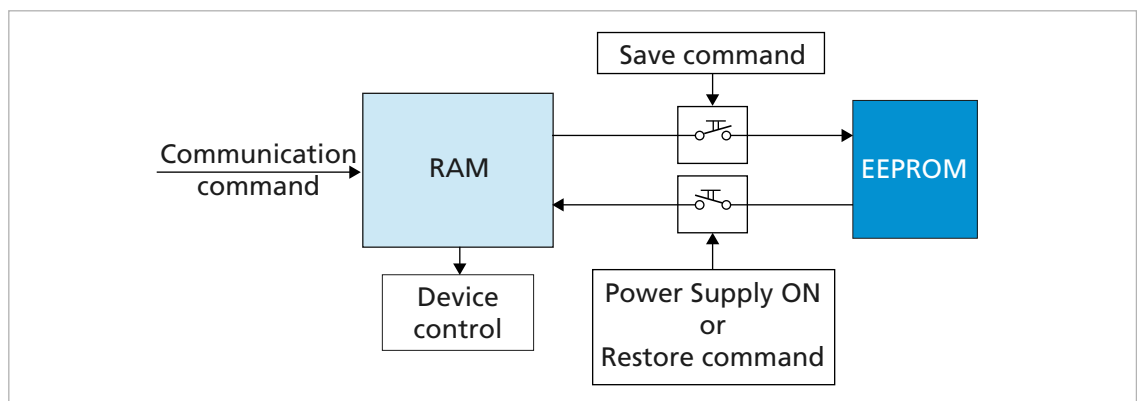


Fig. 3: Saving and restoring parameters

The following parameters can be loaded using the "Restore" command (see chap. 6.1, p. 43):


- Factory settings
- Parameters saved using the "Save" command

2.4.1 Saving parameters

The current parameter settings can be saved in the internal EEPROM (SAVE) (see Tab. 21), either completely or for individual ranges.


- ▶ Write the "Save" signature to the subindex 01 to 05 of the object 0x1010 (see Tab. 22).

2.4.2 Restoring settings

 When the drive is next switched on, the saved parameters are loaded automatically.

Factory settings or last saved parameter settings can be loaded from the internal EEPROM at any time, completely or for specific ranges (RESTORE) (see Tab. 23).

1. Write the "Load" signature to the subindex 01 to 06 of the object 0x1011 (see Tab. 24).
 - ✚ After Restore Factory (01), Restore Communication (02) and Restore Application (03), the parameters are updated only after a reset.
2. Application parameters (04), together with record 1 and record 2 of the special application parameters (05/06) can be updated with the "Reload" command.
 - ✚ The "Reload" command overwrites the values last saved as application parameters.

 If it is desired that the values currently loaded remain available after a "Restore", these must be saved to the PC using a suitable program (such as FAULHABER Motion Manager).

Overview

2.4.3 Changing the parameter set

The saved application parameters (motor data, I/O configuration, controller parameters, operating mode etc.) contain a comprehensive basic set of parameters (App) and alongside this there is a saved data area for parameters which often must be modified to cater for variations in the load situation (App1/App2):

Speed controller and filter

Index	Subindex	Name	Type	Attr.	Meaning
0x2344	0x01	Gain K_p	U32	rw	Controller Gain [As $1e^{-6}$]
	0x02	Integral time T_N	U16	rw	Controller reset time [100 μ s]
0x2346	0x01	Setpoint velocity filter time T_F	U16	rw	Filter time T_F [100 μ s]
	0x02	Setpoint Filter Enable	U8	rw	0: inactive 1: active
0x2347	0x01	Gain factor	U8	rw	Gain factor (used by the velocity controller in PP mode on the K_p) 0: The gain factor of the speed controller is reduced to 0 at the target 128: no variable gain 255: The gain factor of the speed controller is doubled at the target

Position controller

Index	Subindex	Name	Type	Attr.	Meaning
0x2348	0x00	Number of entries	U8	ro	Number of object entries
	0x01	K_v [1/s]	U8	rw	Range: 1-250

Pre-controls

Index	Subindex	Name	Type	Attr.	Meaning
0x2349	0x01	Torque/force feed forward factor	U8	rw	Factor for the torque or force control 0: 0% activation of the pre-control value 128: 100% pre-control
	0x02	Torque/Force feed forward delay	U8	rw	Setpoint delay: 0: undelayed activation 1: Activation delayed by one sampling
0x234A	0x01	Velocity feed forward factor	U8	rw	Factor for the torque or force control 0: 0% pre-control 128: 100% pre-control
	0x02	Velocity feed forward delay	U8	rw	Setpoint delay: 0: undelayed activation 1: Activation delayed by one sampling



Overview

General settings



Index	Subindex	Name	Type	Attr.	Meaning
0x6060	0x00	Modes of operation	S8	rw	Select the operating mode -4: ATC -3: AVC -2: APC -1: Voltage Mode 0: Controller not activated 1: PP 3: PV 6: Homing 8: CSP 9: CSV 10: CST
0x6081	0x00	Profile Velocity	U32	rw	Profile velocity [in user-defined scaling]
0x6083	0x00	Profile acceleration	U32	rw	Profile acceleration [$1/s^2$]
0x6084	0x00	Profile deceleration	U32	rw	Profile deceleration [$1/s^2$]
0x6086	0x00	Motion Profile Type	S16	rw	Motion profile type: 0: Linear profile 1: \sin^2 velocity
0x60E0	0x00	Positive torque limit value	U16	rw	Value of the upper limit value [in relative scaling]
0x60E1	0x00	Negative torque limit value	U16	rw	Value of the lower limit value [in relative scaling]

These parameters are stored twice. In operation the system can switch quickly between these different pre-set values.

Create an application

- ▶ SAVE application parameters 1: Write the "Save" signature to the subindex 04 of the object 0x1010.
 The current data are saved as the application parameter set 1.
- ▶ SAVE application parameters 2: Write the "Save" signature to the subindex 05 of the object 0x1010.
 The current data are saved as the application parameter dataset 2.

Activate an application

- ▶ Reload Application Parameters 1: Write the "Load" signature to the subindex 05 of the object 0x1011.
 Current data from the application parameter set 1 are activated directly.
- ▶ Reload Application Parameters 2: Write the "Load" signature to the subindex 06 of the object 0x1011.
 Current data from the application parameter set 2 are activated directly.

CANopen protocol description

3 CANopen protocol description

3.1 Introduction

CANopen

CANopen is a standard software protocol. A CAN hardware environment is required for communication using CANopen. Up to 127 nodes can be addressed within a CANopen network. The maximum transmission speed is 1 MBit/s.

CAN standardisation

The CiA defines the following aspects in CiA 301:

- communications structure
- Control and monitoring functions

CANopen device profiles have been defined for a wide range of device classes, such as:

- CiA 402 for drives
- CiA 401 for input and output devices

Structure of a CANopen telegram

A CANopen telegram has an 11-bit identifier and can contain up to 8 bytes of user data.

Tab. 1: Schematic structure of a CANopen telegram

11-bit identifier	up to 8 bytes user data							
11-bit	8-bit	8-bit	8-bit	8-bit	8-bit	8-bit	8-bit	8-bit

CANopen protocol description

3.2 Communication services

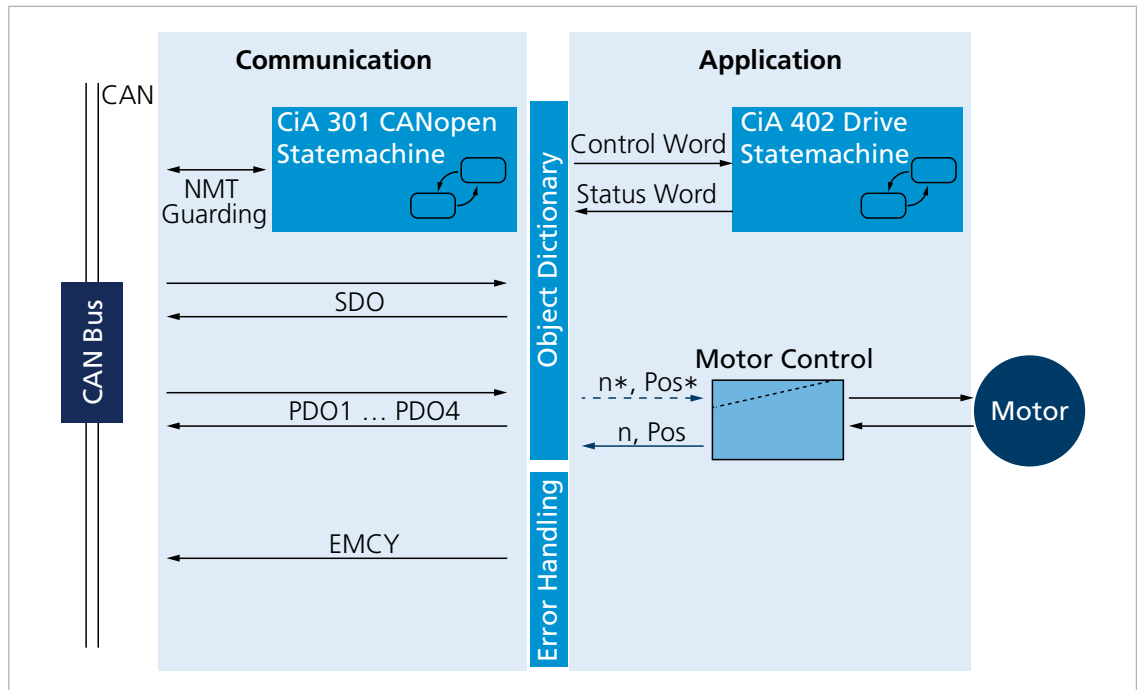


Fig. 4: Communication services of the Motion Controller

The communication part contains communication services as specified in CiA 301.

Tab. 2: Communication services to CiA 301

Communication services	Description
NMT (Network Management)	Activates nodes and monitors the current status of a node (see chap. 3.8, p. 27).
SDO (Service Data Object)	The CANopen master uses the SDO to access parameters within a node. Each SDO access reads or writes exactly one parameter. An SDO can only address one node in a network (see chap. 3.5, p. 21).
PDO (Process Data Object)	The PDO is used to access real-time data. A PDO can use a CAN message to access multiple drive parameters concurrently. The parameters sent or received in a PDO can be freely configured (see chap. 3.4, p. 18).
SYNC object	SYNC objects are used to synchronise different applications on the CAN-BUS (see chap. 3.7, p. 26).
EMCY (Emergency Object)	An emergency message is used to inform the CANopen master about errors. A CAN message conveys the error code asynchronously so that the status of the CANopen slave need not be interrogated after an error (see chap. 3.6, p. 24).

CANopen protocol description

Communications profile

FAULHABER Motion Controllers support the CANopen communications profile to CiA 301 V4:

- 4 transmission PDOs
- 4 receipt PDOs
- 1 server SDO
- Emergency object
- NMT with node guarding and heartbeat
- SYNC object



The data assignment of the PDOs is pre-set to the “PDO set for servo drive” as specified in CiA 402 V3, but can be changed by the user (dynamic PDO mapping).

CANopen protocol description

3.3 Identifier distribution

The Communication Object Identifier (COB-ID) consists of a 7-bit node address (Node-ID) and a 4-bit function code.

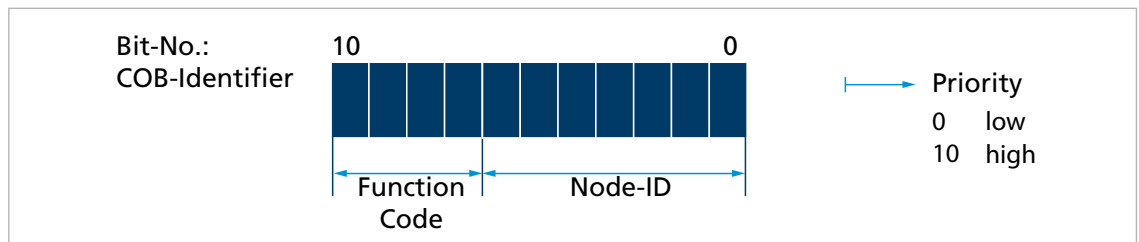


Fig. 5: Identifier distribution

The Predefined-Connection-Set defines the standard identifier for the most important objects.

Tab. 3: Standard identifier

Object	Function code (binary)	Resulting COB-ID	Object index for communication setting
NMT	0000	0	–
SYNC	0001	128 (80 h)	1005 h
EMERGENCY	0001	129 (81h) to 255 (FFh)	1014 h
PDO1 (tx)	0011	385 (181h) to 511 (1FFh)	1800 h
PDO1 (rx)	0100	513 (201h) to 639 (27Fh)	1400 h
PDO2 (tx)	0101	641 (281h) to 767 (2FFh)	1801 h
PDO2 (rx)	0110	769 (301h) to 895 (37Fh)	1401 h
PDO3 (tx)	0111	897 (381h) to 1023 (3FFh)	1802 h
PDO3 (rx)	1000	1025 (401h) to 1151 (47Fh)	1402 h
PDO4 (tx)	1001	1153 (481h) to 1279 (4FFh)	1803 h
PDO4 (rx)	1010	1281 (501h) to 1407 (57Fh)	1403 h
SDO (tx)	1011	1409 (581h) to 1535 (5FFh)	1200 h
SDO (rx)	1100	1537 (601h) to 1663 (67Fh)	1200 h
NMT error control	1110	1793 (701h) to 1919 (77Fh)	–

The COB-IDs of the PDOs, the SYNC objects and the emergency objects can be changed via the communication parameters in the object dictionary. The COB-ID of the SDO telegram cannot be changed and is always derived from the node number.



As delivered the system is configured with the node number 1. The COB-IDs are pre-set correspondingly:

- RxPDO: 201h, 301h, 401h and 501h
- TxPDO: 181h, 281h, 381h and 481h
- EMCY: 81 h
- RxSDO: 581 h
- TxSDO: 601 h

CANopen protocol description

i If the node number is changed from 255 (unconfigured CANopen node) to a value >127 using the LSS protocol, the COB-IDs which depend on this node number are automatically adjusted.

3.4 PDO (Process Data Object)

PDOs are CAN messages with up to 8 bytes user data. PDOs contain process data for controlling and monitoring the behaviour of the device. The drive makes the distinction between receipt PDOs and transmission PDOs.

- Receipt PDOs (RxPDO): are received by a drive and typically contain control data
- Transmission PDOs (TxPDO): are sent by a drive and typically contain monitoring data

PDOs are evaluated or transmitted only when the device is in the NMT *Operational* state (see chap. 3.8, p. 27).

The transmission of PDOs can be triggered in various different ways. The behaviour can be set for each PDO via the transmission type parameter of the communication parameters in the object dictionary:

Tab. 4: Types of PDO transmissions

Transmission Type	Description
Event-driven	Event-driven RxPDOs are processed immediately on receipt. Event-driven TxPDOs are sent when the statusword of the device is contained and has been changed.
Remote request (RTR)	Data are sent in response to a request message.
Synchronised	Data are sent after receipt of a SYNC object (see chap. 3.7, p. 26).

3.4.1 PDO configuration

- A maximum of 4 parameters can be mapped in one PDO.
- The data assignment of PDOs can be changed via the objects 0x1600 to 0x1603 and 0x1A00 to 0x1A03. The mapping procedure necessary for this is described in CiA 301. A suitable tool (such as FAULHABER Motion Manager or System Manager for the PLC controller than is used) is necessary for performance of the mapping procedure.
- The transmission types and COB-ID of the PDOs can be changed via the objects 0x1400 to 0x1403 and 0x1800 to 0x1803.
- The transmission type parameters can be used to change the behaviour of a PDO:

CANopen protocol description

Tab. 5: Transmission type of a PDO

Transmission Type	Meaning
0	synchronous, acyclical A PDO is sent or executed once after a SYNC object when the contents of the PDO have changed (see chap. 3.7, p. 26).
1 to 240	synchronous, cyclical A PDO is sent after every SYNC object (see chap. 3.7, p. 26). The value is then equal to the number of SYNC objects that must be received before the PDO is sent again (1 = PDO is sent for every SYNC object)
252	TxPDOs only: asynchronous <ul style="list-style-type: none"> On a SYNC signal, the contents of the TxPDO are stored On request (RTR) the TxPDO is sent to the master
253	TxPDOs only: asynchronous On request (RTR) the TxPDO is sent to the Master
255	asynchronous (event-driven)

3.4.2 PDO mapping in the standard configuration (status as delivered)

RxPDO1: Controlword

11-bit identifier	2 bytes user data	
0x200 (512d) + node ID	LB	HB

The RxPDO1 contains the 16-bit controlword to CiA DSP402. The controlword controls the state machine of the drive unit and points to the object index 0x6040 in the object dictionary. The bit distribution is described in the documentation for the drive functions.

TxPDO1: Statusword

11-bit identifier	2 bytes user data	
0x180 (384d) + node ID	LB	HB

The TxPDO1 contains the 16-bit statusword to CiA 402. The statusword indicates the status of the drive unit and points to the object index 0x6041 in the object dictionary. The bit distribution is described in the documentation for the drive functions.

RxPDO2: Controlword, target position (PP)

11-bit identifier	6 bytes user data					
0x300 (768d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The RxPDO2 contains the 16-bit controlword and the 32-bit value of the destination position (object 0x607A) for the Profile Position mode (PP).

TxPDO2: Statusword, Position Actual Value

11-bit identifier	6 bytes user data					
0x280 (640d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The TxPDO2 contains the 16-bit statusword and the 32-bit value of the actual position (object 0x6064).

CANopen protocol description

RxPDO3: Controlword, target velocity (PV)

11-bit identifier	6 bytes user data					
0x400 (1024d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The RxPDO3 contains the 16-bit controlword and the 32-bit value of the set speed (object 0x60FF) for the Profile Velocity mode (PV).

TxPDO3: Statusword, Velocity Actual Value

11-bit identifier	6 bytes user data					
0x380 (896d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The TxPDO3 contains the 16-bit statusword and the 32-bit value of the actual speed (object 0x606C).

RxPDO4: Controlword, target torque

11-bit identifier	6 bytes user data					
0x400 (1024d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The RxPDO4 contains the 16-bit controlword and the 16-bit value of the target torque (object 0x6071) for Cyclic Torque Mode (CST).

TxPDO4: Statusword, torque actual value

11-bit identifier	6 bytes user data					
0x380 (896d) + node ID	LB	HB	LLB	LHB	HLB	HHB

The RxPDO4 contains the 16-bit statusword and the 16-bit value of the actual torque (object 0x6077) for Cyclic Torque mode (CST).

3.4.3 Dealing with mapping errors

If the mapping procedure specified in CiA 301 is not complied with, one of the following SDO errors will be returned:

Tab. 6: SDO errors in response the incorrect mapping procedure

SDO error	Meaning	Cause
0x06090030	General value range error	The mapping parameter lies outside that specified in the mapping procedure.
0x06020000	Object not present in the object dictionary	The value for the number of mapped objects is greater than the number of valid entries in the respective subindexes for the mapping parameter objects.

If the number of mapped objects is 0, the PDO will be flagged internally as invalid and will not be operated.



Other mapping errors are described in the SDO error table (see chap. 3.5.2, p. 23).

CANopen protocol description

3.4.4 Dummy Mappings

RxPDOs can be configured so that more than one participant can respond to them. In this case it may be desirable that only part of the data contained in the PDO is evaluated in one of the devices.

For data that are not used locally, Dummy Mapping on one of the data types that is used can be entered in the PDO mapping table:

Index	Type
0x0002	S8
0x0003	S16
0x0004	S32
0x0005	U8
0x0006	U16
0x0007	U32

Example

An RxPDO contains the target positions for two axes.

Mapping for the node that should respond to the first target position:

- 0x160x.00 = 2
- 0x160x.01 = 0x607A0020
- 0x160x.02 = 0x00040020

Mapping for the node that should respond to the second target position:

- 0x160x.00 = 2
- 0x160x.01 = 0x00040020
- 0x160x.02 = 0x607A0020

3.5 SDO (Service Data Object)

The SDO reads and describes parameters in the OV (object dictionary). The SDO accesses the object dictionary via the 16-bit index and the 8-bit subindex. At the request of the client (PC, PLC (programmable logic controller)) the Motion Controller makes data available (upload) or receives data from the client (download).

Tab. 7: General structuring of the SDO user data

Byte0	Byte 1 to 2	Byte 3	Byte 4 to 7
Command specifier	16-bit index	8-bit subindex	4-byte parameter data

Tab. 8: Distribution of the SDO types of transmission

Type of transmission	Number of bytes	Purpose
Expedited transfer	maximum 4 bytes	Read and write individual numeric parameters
Segmented transfer	more than 4 bytes	Read text parameters (such as device name, firmware version) and transmit data blocks (such as the trace buffer)

Only the expedited transfer is described in this document. The segmented transfer is described in CiA 301.

CANopen protocol description

3.5.1 Expedited transfer

SDO messages are always size 8 bytes.

Read OD entries (Client-to-Server, Upload-Request)

11-bit identifier	8 bytes user data							
0x600 (1536d) + node ID	0x40	Index LB	Index HB	Subindex	0	0	0	0

Server-to-Client, Upload-Response

11-bit identifier	8 bytes user data							
0x580 (1408d) + node ID	CS(0x4x)	Index LB	Index HB	Subindex	LLB (D0)	LHB (D1)	HLB (D2)	HHB (D3)

The command specifier CS(0x4x) specifies the number of valid data bytes in D0 to D3 and the transfer code. The command specifier is coded as follows:

- CS = 0x4F, 1 data byte in D0
- CS = 0x4B, 2 data bytes in D0 to D1
- CS = 0x47, 3 data bytes in D0 to D2
- CS = 0x43, 4 data bytes in D0 to D3

Write OD entries (Client-to-Server, Download-Request)

11-bit identifier	8 bytes user data							
0x600 (1536d) + node ID	CS(0x2x)	Index LB	Index HB	Subindex	LLB (D0)	LHB (D1)	HLB (D2)	HHB (D3)

The command specifier CS(0x2x) specifies the number of valid data bytes in D0 to D3 and the transfer code. The command specifier is coded as follows:

- CS = 0x2F, 1 data byte in D0
- CS = 0x2B, 2 data bytes in D0 to D1
- CS = 0x27, 3 data bytes in D0 to D2
- CS = 0x23, 4 data bytes in D0 to D3
- CS = 0x22, no specification of the number of data bytes

Server-to-Client, Download-Response

11-bit identifier	8 bytes user data							
0x580 (1407d) + node ID	0x60	Index LB	Index HB	Subindex	0	0	0	0

CANopen protocol description

Abort in the event of SDO errors

SDO-abort Client-to-Server

11-bit identifier	8 bytes user data							
0x600 (1536d) + node ID	0x80	Index LB	Index HB	Subindex	ERROR 0	ERROR 1	ERROR 2	ERROR 3

SDO-abort Server-to-Client

11-bit identifier	8 bytes user data							
0x580 (1536d) + node ID	0x80	Index LB	Index HB	Subindex	ERROR 0	ERROR 1	ERROR 2	ERROR 3

3.5.2 SDO error description

If the SDO protocol on a page cannot be processed further, an SDO-Abort telegram is sent (see chap. 3.5.1, p. 22). The error types are coded as follows:

- Error0: Additional error code HB
- Error1: Additional error code LB
- Error2: Error code
- Error3: Error class

Error class	Error code	Additional code	Description
0x05	0x03	0x0000	The toggle bit is not changed
0x05	0x04	0x0001	SDO command specifier invalid or unknown
0x06	0x01	0x0000	Access to this object is not supported
0x06	0x01	0x0001	Attempt to read a write-only parameter
0x06	0x01	0x0002	Attempt to write to a read-only parameter
0x06	0x02	0x0000	Object not present in the object dictionary
0x06	0x04	0x0041	Object cannot be mapped in a PDO
0x06	0x04	0x0042	Number and/or length of the mapped objects exceed the PDO length
0x06	0x04	0x0043	General parameter incompatibility
0x06	0x04	0x0047	General internal incompatibility error in the device
0x06	0x07	0x0010	Data type or parameter length do not match or are unknown
0x06	0x07	0x0012	Data types do not match, parameter length too long
0x06	0x07	0x0013	Data types do not match, parameter length too short
0x06	0x09	0x0011	Subindex not present
0x06	0x09	0x0030	General value range error
0x06	0x09	0x0031	Value range error: Parameter value too large
0x06	0x09	0x0032	Value range error: Parameter value too small
0x06	0x09	0x0036	Value range error: Maximum value greater than minimum value
0x08	0x00	0x0000	General SDO error
0x08	0x00	0x0020	Cannot be accessed
0x08	0x00	0x0022	Cannot be accessed at current device status

CANopen protocol description

3.6 Emergency object (error message)

The emergency object informs other bus participants of errors asynchronously without requiring interrogation. The emergency object is always size 8 bytes:

11-bit identifier		8 bytes user data						
0x80 (128d) + node ID	Error0(LB)	Error1(HB)	Error-Reg	FE0 (LB)	FE1 (HB)	0	0	0

Assignment of user data:

- Error0(LB)/Error1(HB): 16-bit error code
- Error-Reg: Error register (contents of object 0x1001, see chap. 6.1, p. 43)
- FE0(LB)/FE1(HB): 16-bit FAULHABER error register (contents of object 0x2320, see Tab. 12)
- Bytes 5 to 7: unused (0)

The error register identifies the error type. The individual error types are bit-coded and are assigned to the respective error codes. The object 0x1001 allows interrogation of the last value of the error register.

Tab. 9 lists all the errors that have been reported by emergency messages, providing the respective error is included in the emergency mask for the FAULHABER error register (Tab. 13).

Tab. 9: Emergency error codes

Emergency message		FAULHABER error register 0x2320			Error register 0x1001	
Error Code	Designation	Error mask 0x2321	Bit	Designation	Bit	Designation
0x0000	No error (is sent out when an error is no longer present or has been acknowledged)	–	–	–	–	–
–	–	–	–	–	0	Generic error (is set if one of the error bits 1 to 7 is set)
0x3210	Overvoltage	0x0004	2	OverVoltageError	2	Voltage error
0x3220	Undervoltage	0x0008	3	UnderVoltageError	2	Voltage error
0x43F0	Temperature warning	0x0010	4	TempWarning	1	Current error ^{a)}
0x4310	Temperature Error	0x0020	5	TempError	3	Temperature error
0x5410	Output stages	0x0080	7	IntHW error	7	Manufacturer-specific error
0x5530	EEPROM fault	0x0400	10	Memory error	–	–
0x6100	Software error	0x1000	12	Calculation error	7	Manufacturer-specific error

CANopen protocol description

Emergency message		FAULHABER error register 0x2320			Error register 0x1001	
Error Code	Designation	Error mask 0x2321	Bit	Designation	Bit	Designation
0x7200	Measurement circuit: Current measurement	0x0200	9	CurrentMeasError	7	Manufacturer-specific error
0x7300	Sensor fault (encoder)	0x0040	6	EncoderError	7	Manufacturer-specific error
0x7400	Computation circuit: Module fault	0x0100	8	ModuleError	7	Manufacturer-specific error
0x8110	CAN overrun	0x0800	11	ComError	4	Communications error
0x8130	CAN guarding failed					
0x8140	CAN recovered from bus stop					
0x8310	RS232 overrun					
0x84F0	Deviation error (velocity controller)	0x0001	0	SpeedDeviationError	5	Drive-specific error
0x84FF	Max Speed Error	0x2000	13	DynamicError	7	Manufacturer-specific error
0x8611	Following error (position controller)	0x0002	1	FollowingError	5	Drive-specific error

- a) The current regulator keeps the motor current below the specified limit at all times. The overcurrent error bit is set if the warning temperature is exceeded. The permissible motor current is then reduced from the peak current value to the continuous current value.

Example:

An emergency message with the user data assignment in Tab. 10 is sent in the following event:

- In the Error Mask 0x2321, bit 1 (following error) is set under subindex 1 (emergency mask) (see Tab. 14).
- The control deviation value set in object 0x6065.00 for the position regulator corridor has been exceeded for an extended period as defined by the value set for the error delay time in object 0x6066.00 (see the documentation of the drive functions).

Tab. 10: Example of user data assignment to an emergency message

8 bytes user data							
0x11	0x86	0x20	0x02	0x00	0x00	0x00	0x00

CANopen protocol description

3.7 SYNC object

The SYNC object is a message without any user data. The SYNC object is used to trigger synchronous PDOs and at the same time to start processes on various items of equipment.

The identifier of the SYNC objects is set in the object dictionary under the index 0x1005 (by default 0x80).

11-bit identifier	0 bytes of user data
0x80	no user data

i In order that an SYNC object triggers a PDO, the transmission type of the PDO to be triggered must be set accordingly (see Tab. 5).

3.7.1 Triggering synchronous PDOs

Synchronous RxPDO: The command transmitted with the PDO is not executed until a SYNC object is received. The transmission types 1 to 240 of an RxPDO are identical to transmission type 0.

Synchronous TxPDO: The synchronous TxPDOs with the current data are sent immediately after a SYNC object is received.

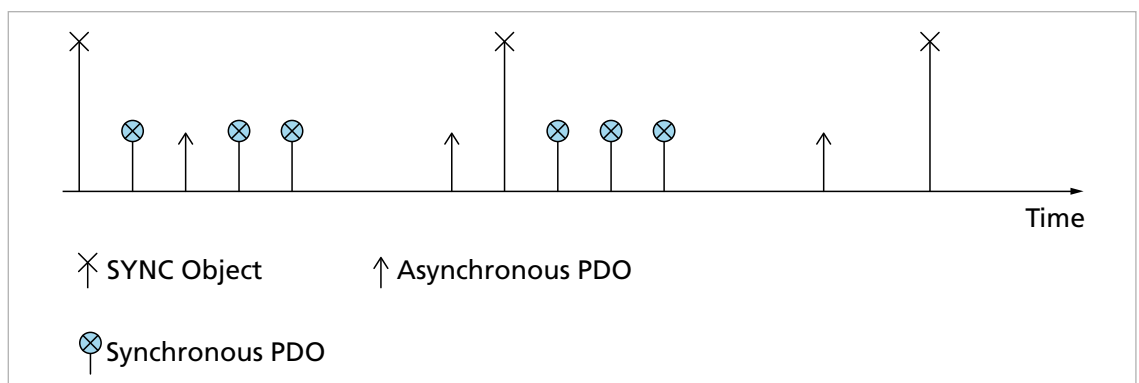


Fig. 6: TxPDO with SYNC chart

i The nodes can also be grouped by transmission types 1-240.

CANopen protocol description

3.8 NMT (Network Management)

The network management object governs the CiA 301 state machine of the CANopen device and monitors the network nodes.

After switching on and initialising, the Motion Controller is automatically set to the *Pre-Operational* state. In the *Pre-Operational* state the device can communicate only with NMT messages and via SDOs.

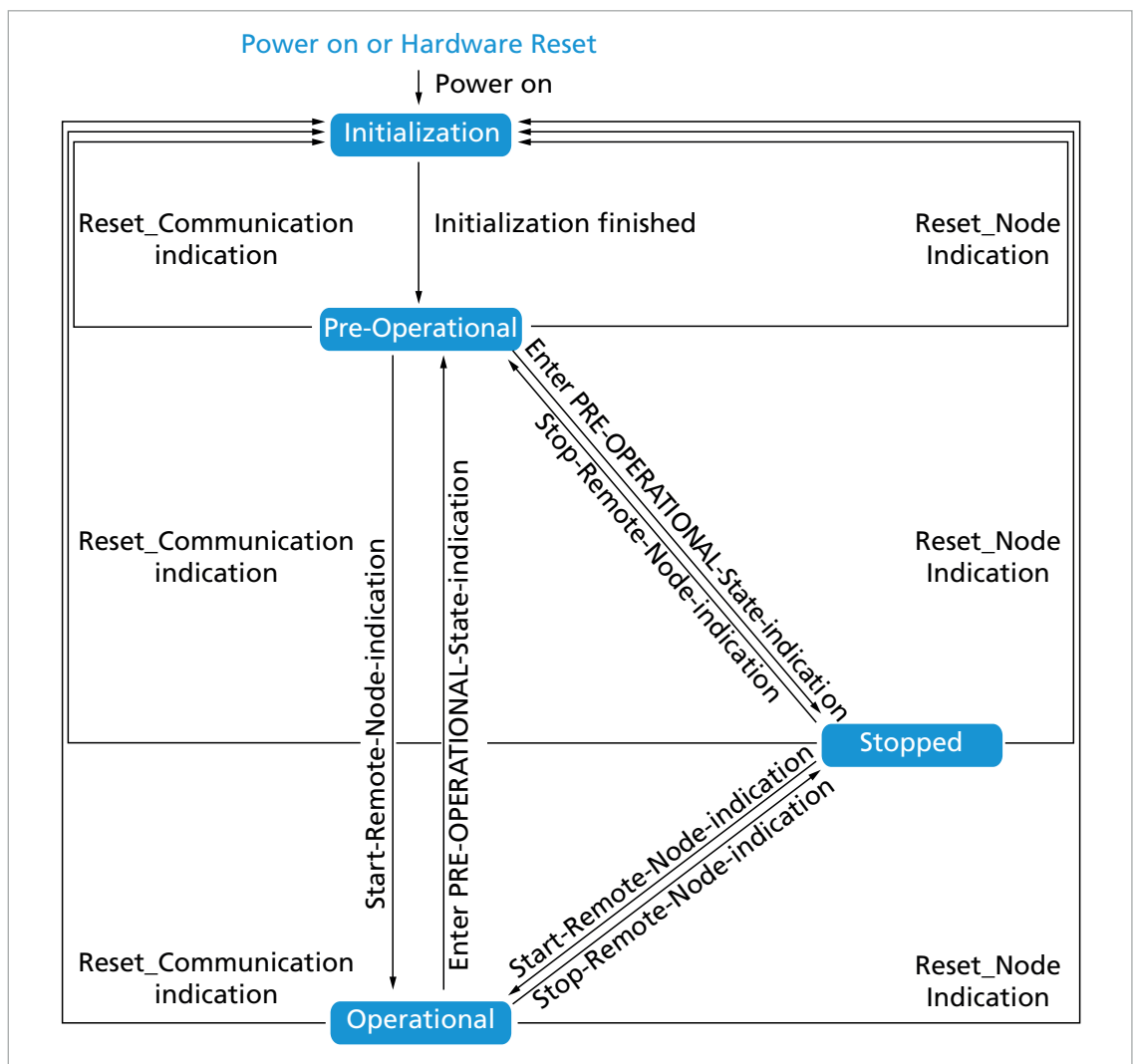


Fig. 7: CiA 301 state machine

Tab. 11: NMT changes of status

Status transition	CS	Meaning
Power on	–	The initialisation state is achieved automatically on switching on.
Initialisation finished	–	After initialisation the device is automatically in the Pre-Operational state, and it sends a boot-up message.
Start remote node indication	0x01 (1d)	This starts the device and enables transmission of PDOs.
Enter Pre-operational state indication	0x80 (128d)	Stops the transmission of PDOs, SDOs are still active.
Stop remote node indication	0x02 (2d)	The drive is set to the stopped status, SDO and PDO are switched off.

CANopen protocol description

Status transition	CS	Meaning
Reset node indication	0x81 (129d)	Performs a reset. All objects are reset to Power-On standards.
Reset communication indication	0x82 (130d)	Performs a reset of the communications functions.

i FAULHABER Motion Controllers are equipped with a standard configuration for all objects. Once commissioning is complete the application-specific settings can be saved directly in the device. In most cases no further parametrisation is necessary at the system start.

Starting a CANopen node

Start remote node:

11-bit identifier	2 bytes user data
0x000	0x01 Node ID

An entire network can also be started with a CAN message:

Start all remote nodes:

11-bit identifier	2 bytes user data
0x000	0x01 0x00

After the node or the entire network is started the device is in the *Operational* state. The device can now be operated using PDOs.

In the *Stopped* state the device is in an error state and can no longer be operated using PDOs. Under these circumstances, communication with the device is available only by NMT messages.

An NMT message always consists of 2 bytes on the identifier 0x000.

NMT message

11-bit identifier	2 bytes user data
0x000	CS Node ID

Assignment of user data:

- CS: Command specifier (see Tab. 11)
- Node ID: Node address (0 = all nodes)

i In the event of a serious communications error the Motion Controller switches by default to the *Pre-Operational* NMT status. Different behaviour can be set using the object 0x1029.

CANopen protocol description

3.8.1 Boot up

Immediately after the initialisation phase the Motion Controller sends a boot-up message. A boot-up message signals the end of the initialisation phase of a module after it has been switched on. A boot-up message is a CAN message with one data byte (byte 0 = 0x00) on the identifier of the node guarding message (0x700 + node ID).

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

3.8.2 Monitoring functions



Only one monitoring function; node guarding or heartbeat, can be used at one time.

CANopen protocol description

3.8.2.1 Node guarding

The node guarding object interrogates the instantaneous state of the device. To do this, the master sets a remote frame with a request for the guarding identifier of the node to be monitored. The node to be monitored responds with the guarding message which contains the current status of the node and a toggle bit.

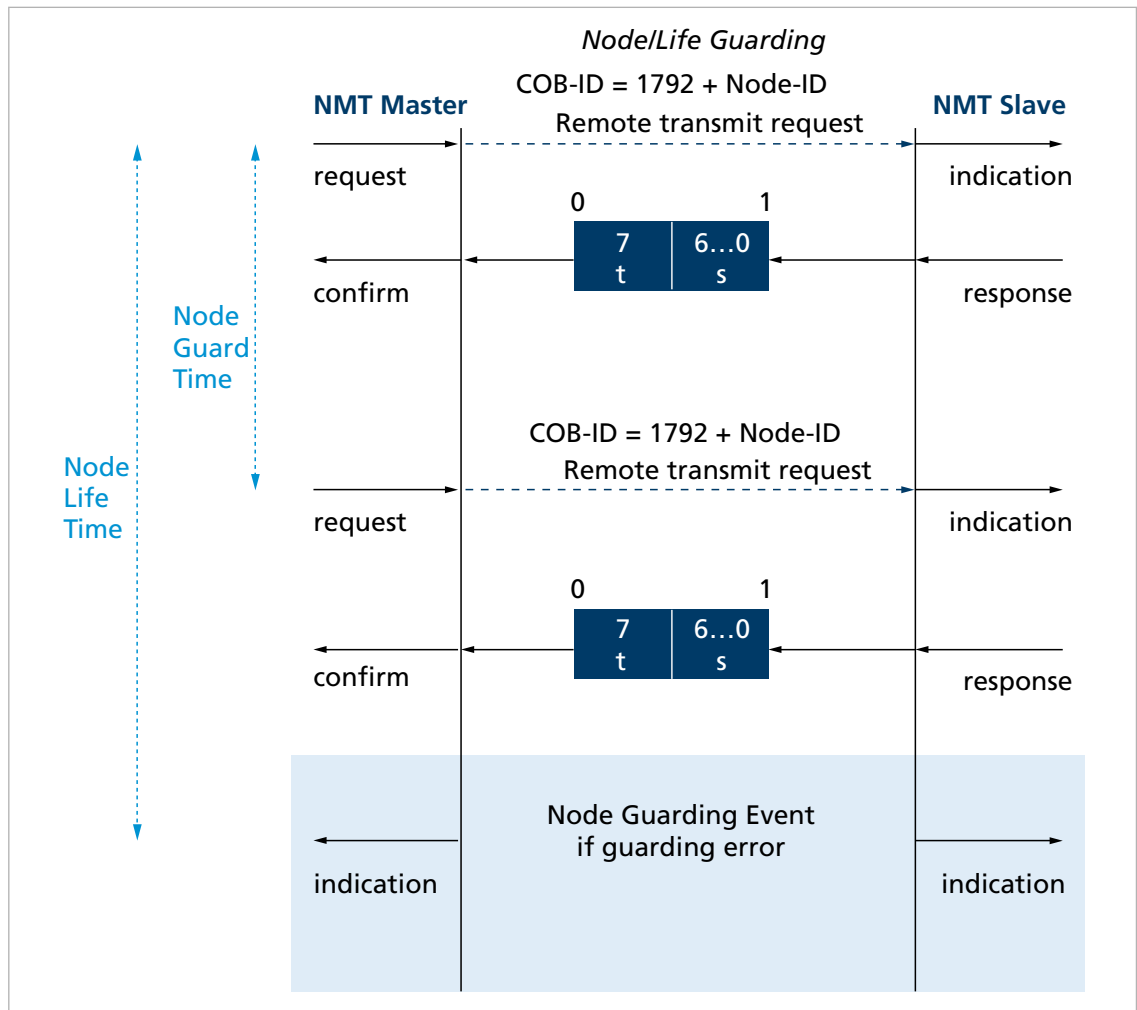


Fig. 8: Diagram of the node guarding protocol

t: Toggle bit

Initially 0, changes its value at each guarding telegram

s: Status

s = 0x04 (4d): Stopped

s = 0x05 (5d): Operational

s = 0x7F (127d): Pre-operational

If a node life time > 0 is set (objects 0x100C and 0x100D) and no node guarding request is made by the master within the set node life time, a node guarding error is set. The response to a node guarding error is set by the FAULHABER error register (object 0x2321) (see Tab. 14). The default is to send the emergency message 0x8130.

CANopen protocol description

3.8.2.2 Heartbeat

The Motion Controller can be set to act both as the heartbeat producer and also as the heartbeat consumer.

- **Heartbeat producer:** On a cyclical basis the Motion Controller sends out a message which is received by one or more heartbeat consumers in the network.
- **Heartbeat consumer:** If within the heartbeat consumer time no heartbeat message is received from the heartbeat producers that are being monitored, the Motion Controller responds with the behaviour specified in the FAULHABER error register (object 0x2320) (see Tab. 12).

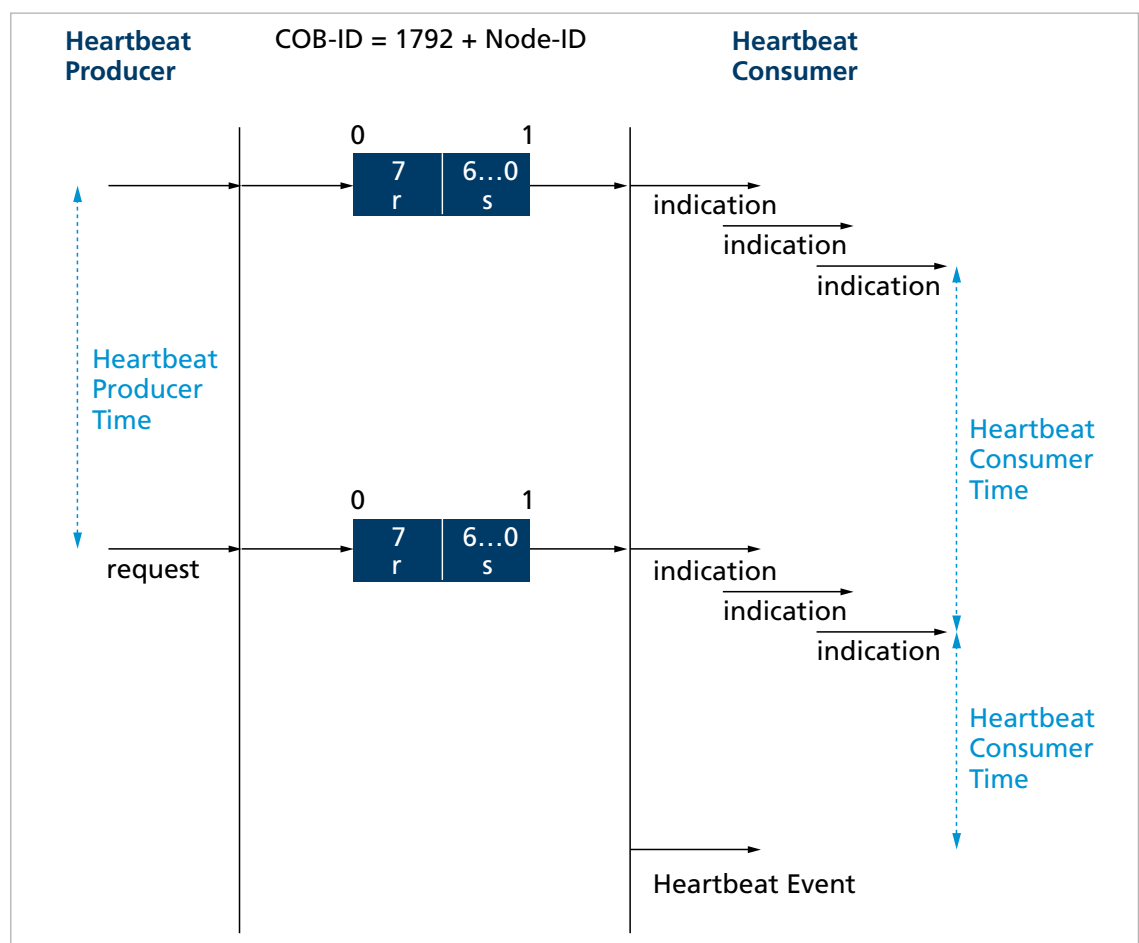


Fig. 9: Chart of the heartbeat protocol

r: Reserved

Always 0

s: Status

s = 0x00 (0d): Boot up

s = 0x04 (4d): Stopped

s = 0x05 (5d): Operational

s = 0x7F (127d): Pre-operational

CANopen protocol description

3.8.3 Setting the monitoring functions

- Only one of the two monitoring functions (node guarding, heartbeat) can be activated at one time.
- If the producer heartbeat time is > 0 (object 0x1017) the Motion Controller operates as a heartbeat producer. At intervals of the producer heartbeat time the Motion Controller sends a heartbeat message. The node guarding time is set to 0 (see chap. 3.8.2.1, p. 30).
- If the heartbeat is activated, the boot-up message after the switch-on ranks as the first heartbeat message. Further heartbeats follow at the interval for the producer heartbeat time.
- If in addition to the producer heartbeat time a heartbeat consumer time > 0 is set (object 0x1016.01), the Motion Controller operates as a heartbeat consumer. The settings for the heartbeat producer are inoperative. The node ID of the master to be monitored and the heartbeat consumer time are entered in the object 0x1016.
- The heartbeat consumer time must always be longer than the producer heartbeat time of the master.
- If within the set heartbeat consumer time the Motion Controller receives no heartbeat message from the master, a heartbeat event is triggered. The response to a heartbeat event is determined by the FAULHABER error register error mask (object 0x2321) (see Tab. 12). The default is to send the emergency message 0x8130.
- If whilst the heartbeat producer is activated an attempt is made to set a node guarding time, the SDO error 0x08000020 (no access available) is sent.

3.9 Entries in the object dictionary

The object dictionary manages the configuration parameters. The object dictionary is divided into three areas. Each object can be referenced by its index and subindex (SDO protocol).

- Communication parameters (index 0x1000 to 0x1FFF) contains communications objects to CiA 301, see chap. 6.1, p. 43)
- Manufacturer-specific area (index 0x2000 to 0x5FFF) contains manufacturer-specific objects, see chap. 6.2, p. 51)
- The standardised device profiles area (0x6000 to 0x9FFF) contains objects supported by the Motion Controller (see the documentation of the drive functions)

CANopen protocol description

3.10 Error handling

3.10.1 CAN error

CAN overrun (object lost)

If messages are lost, the controller sends the emergency message 0x8110. Bit 4 (communication error) is set in the error register and Bit 7 (CAN overrun) is set in the FAULHABER error register. The emergency message is sent out after a delay. Issuing of the emergency message (0x000) does not retract the error. The respective bits in the error register and in the FAULHABER error register are not cleared down.

CAN in error passive mode

If the CAN module of the drive is set to the *Error-Passive* state, the emergency message 0x8120 is sent. Bit 4 (communication error) is set in the error register and Bit 6 (CAN in error passive mode) is set in the FAULHABER error register. The emergency message (0x000) is sent and the error retracted once the drive is restored to the *Error-Active* state.

Recovered from bus stop

If the CAN module of the drive receives a valid message whilst set to the *Bus-Off* state, the emergency message 0x8140 is sent. The emergency message reports that the *Bus-Off* state has been exited. Bit 4 (communication error) is set in the error register and Bit 9 (Recovered from Bus-Off) is set in the FAULHABER error register. This does not retract the error. The respective bits in the error register and in the FAULHABER error register are not cleared down.



"CAN-Overrun" and "Recovered from bus off" are serious communications errors. The respective bits in the error register and in the FAULHABER error register can be cleared down only by restarting the Motion Controller. Other serious communications errors are:

- Node guarding timeouts
- Heartbeat timeouts

CANopen protocol description

3.10.2 Equipment faults

Tab. 12: FAULHABER error register (0x2320)

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2320	0x00	Fault Register	U16	ro	–	FAULHABER error register

The FAULHABER error register contains the most recent errors in bit-coded form. The errors can be masked by selection of the desired types of error via the error mask object (0x2321).

Tab. 13: Error coding

Error bit	Error message	Description
0x0001	SpeedDeviationError	Speed deviation too great
0x0002	FollowingError	Following error
0x0004	OverVoltageError	Overvoltage detected
0x0008	UnderVoltageError	Undervoltage detected
0x0010	TempWarning	Temperature exceeds that at which a warning is output
0x0020	TempError	Temperature exceeds that at which an error message is output
0x0040	EncoderError	Error detected at the encoder
0x0080	IntHW error	Internal hardware error
0x0100	ModuleError	Error at the external module
0x0200	CurrentMeasError	Current measurement error
0x0400	Memory error	Memory error (EEPROM)
0x0800	ComError	Communication errors
0x1000	Calculation error	Internal software error
0x2000	DynamicError	The current velocity is higher than the maximum speed set for the motor.
0x4000	–	Not used, value = 0
0x8000	–	Not used, value = 0

All of these errors correspond to the emergency error code (see chap. 3.6, p. 24).

The error mask describes the handling of internal errors depending on the error coding (see Tab. 13).

CANopen protocol description

Tab. 14: Error mask (0x2321)

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2321	0x00	Number of entries	U8	ro	6	Number of object entries
	0x01	Emergency Mask	U16	rw	0x00FF	Errors for which an error message is sent
	0x02	Fault Mask	U16	rw	0x0000	Errors for which the state machine of the drive switches into <i>Fault Reaction Active</i> state
	0x03	Error Out Mask	U16	rw	0x00FF	Errors for which the error output pin is set
	0x04	Disable Voltage Mask	U16	ro	0x0000	Errors which switch the drive off (not configurable)
	0x05	Disable Voltage User Mask	U16	rw	0x0000	Errors which switch the drive off (configurable)
	0x06	Quick Stop Mask	U16	rw	0x0000	Errors for which the state machine of the drive switches into <i>Quick Stop Active</i> state

Examples:


- When the fault mask (subindex 2) of object 0x2321 is set to 0x0001 the drive is switched off due to overcurrent are set to an error state.
- When the subindex 3 of object 0x2321 is set to 0, the error output (fault pin) indicates no error. When the subindex 3 of object 0x2321 is set to 0xFFFF, the error output (fault pin) indicates all errors.

Trace

4 Trace

The trace function allows recording up to 4 parameters of the controller. A trigger source is available for this in the object dictionary. This allows selection of a maximum of 4 signal sources. Two different types of recording are available:

- Trace recorder: The parameter values are written to an internal buffer and can then be read (see chap. 4.1, p. 36).
- Trace logger: On request the parameter values are requested and read continuously (see chap. 4.2, p. 39).

 The FAULHABER Motion Manager provides a user-friendly means of setting and evaluating the trace functions.

4.1 Trace recorder

The configuration and reading of data with the trace recorder is performed via the SDO.

The trace recorder is configured using the object 0x2370 in the OD.

The recorded data are read using the segmented SDO upload protocol. The object 0x2371 is available in the OD for this purpose (see chap. 4.1.2, p. 38).

4.1.1 Trace settings

The object 0x2370 is available for configuration of the trace recorder. The data sources to be recorded, the buffer size, the resolution and the trigger conditions can be set here.

Tab. 15: Trace Configuration (0x2370)

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2370	0x00	Number of entries	U8	ro	10	Number of object entries
	0x01	Trigger Source	U32	wo	0	Trigger source
	0x02	Trigger Threshold	S32	rw	0	Trigger threshold
	0x03	Trigger Delay Offset	S16	rw	0	Trigger delay
	0x04	Trigger Mode	U16	rw	0	Trigger mode
	0x05	Buffer Length	U16	rw	100	Buffer length
	0x06	Sample Time	U8	rw	1	Recording sampling rate 1: in every sampling step
	0x07	Trace Source of Channel 1	U32	wo	0	Trace source of channel 1
	0x08	Trace Source of Channel 2	U32	wo	0	Trace source of channel 2
	0x09	Trace Source of Channel 3	U32	wo	0	Trace source of channel 3
	0x0A	Trace Source of Channel 4	U32	wo	0	Trace source of channel 4

Trace

Trigger Source (0x2370.01), Trace Source 1 to 4 (0x2370.07 to 0A)

The parameters to be recorded, Trace Source 1 to Trace Source 4, must be entered into the objects 0x2370.07 to 0x2370.0A as pointers to a corresponding object entry (index and sub-index of the desired parameter). The trigger source must be entered into the object 0x2370.01 as a pointer to a corresponding object entry (index and subindex of the desired parameter).

Example:

The object 0x6064.00 (position actual value) must be recorded as the first data source: The value 0x606400 must be entered into the object 0x2370.07.

Trigger Threshold (0x2370.02)

The trigger threshold is entered into object 0x2370.02.

Depending on the settings of bits 1 to 3 in the trigger type object 0x2370.04, recording is started on the threshold set here being exceeded or undershot.

Trigger Delay Offset (0x2370.03)

The trigger delay is stated in object 0x2370.03 as a multiple of the sample time set in object 0x2370.06.

- Delay > 0: Recording is started at a time defined as the set multiple times the sample time.
- Delay < 0: Negative delays can be performed up to the length of the buffer. Recording ends at the point in the ring buffer where the recording for the current trigger would have had to start. This ensures that the values recorded before the trigger are retained.

Trigger Mode (0x2370.04)

The trigger type and the type of the data sources are determined by the object 0x2370.04. Bit 0 activates the trigger and thus providing the trigger conditions are satisfied starts the recording.

Tab. 16: Trigger Mode (0x2370.04)

Bit	Entry	Description
0 (LSB)	EN	<ul style="list-style-type: none"> ■ 0: No trigger active ■ 1: Trigger active. Is automatically reset in trigger modes 1 and 3
1	Edge 0	<ul style="list-style-type: none"> ■ 0: rising flank or trigger > threshold
2	Edge 1	<ul style="list-style-type: none"> ■ 1: falling flank or trigger < threshold
3	Edge 2	
4 to 5	Reserved	–
6	Mode 0	<ul style="list-style-type: none"> ■ 0: No trigger
7	Mode 1	<ul style="list-style-type: none"> ■ 1: Single shot ■ 2: Repeating
8 to 10	Reserved	–
11	Source type 1	<ul style="list-style-type: none"> ■ 0: An object dictionary entry is used as the source
12	Source type 2	<ul style="list-style-type: none"> ■ 1: Not currently supported
13	Source type 3	
14	Source type 4	
15 (MSB)	Trigger type	

Buffer Length (0x2370.05)

The length of the buffer (number of values) available for recording is set in object 0x2370.05. The permissible length is dependent on the data type and the number of the parameters to be recorded. In total a maximum buffer of 4 kByte is available.

Trace

Sample Time (0x2370.06)

The sampling rate is stated in object 0x2370.06 as a multiple of the controller sampling time.

4.1.2 Reading the trace buffer

The recorded data buffer can be read using the object 0x2371.

Tab. 17: Trace Buffer (0x2371)

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2371	0x00	Number of entries	U8	ro	5	Number of object entries
	0x01	Trigger State	U16	ro	0	Trigger state
	0x02	Trace Value of Channel 1	Vis string	ro	–	Signal buffer, channel 1
	0x03	Trace Value of Channel 2	Vis string	ro	–	Signal buffer, channel 2
	0x04	Trace Value of Channel 3	Vis string	ro	–	Signal buffer, channel 3
	0x05	Trace Value of Channel 4	Vis string	ro	–	Signal buffer, channel 4

The user data length of the individual data sources is dependent on the data length of the parameter to be transmitted (according to the OD entry) and the set buffer size. A memory area the size of the data length times the buffer size must therefore be provided for each data source , for reading the recorded values.



The individual data points can recorded to the highest resolution of the trace recorder.

Trigger State (0x2371.01)


Tab. 18: Trigger State (0x2371.01)

Bit	Entry	Description
0 (LSB)	Status 0	0: No trigger active
1	Status 1	1: Trigger not yet reached 2: Recording not yet completed 3: Recording completed, data are available
2 to 7	not used	–
8 to 15 (MSB)	Start index	First value in the buffer after triggering

Before the recorded data are read, the trigger state 0x2371.01 must be checked. If bit 0 and bit 1 are set (status = 3) recording is completed and the contents of the buffer can be read using the objects 0x2371.02 to 0x2371.05 via the segmented SDO upload protocol.


Trace

4.1.3 Typical execution of the trace function

1. Set the trigger type and the type of the data sources (2370.04).
2. Set the trigger source and the signals to be recorded (2370.01, 07 to 0A).
3. Set the recording length (2370.05).
4. If necessary set the sampling rate (2370.06).
5. Set the threshold value (2370.02) for the trigger.
6. Set the flank for the trigger and activate recording (2370.04).
 This completes the settings for the trace recorder.
7. Test the trigger status (2371.01) at the value 3.
8. Read the recorded content of the buffer (2371.02 to 05).

4.2 Trace logger

The trace logger uses the PDO communication service transmit data from the controller. Any TxPDO can be used as the trace PDO. Prior to use, the PDO must be loaded with the desired parameters, using the PDO mapping method (see chap. 3.4.2, p. 19). The data can then be requested cyclically using the remote request or SYNC.

 The resolution of the individual data points is dependent on the speed of transmission and processing. The resolution of the data points can be down to 1 ms.

Communications settings

5 Communications settings

FAULHABER drives are delivered as standard with a pre-set node number 1 and with automatic Baud rate detection (AutoBaud) set.



In network mode the network transmission rate in use should be set as the fixed rate.

5.1 Setting via the CAN network

For setting via the CAN network the FAULHABER Motion Manager or other configuration tool which supports the LSS protocol (Layer Setting Service and Protocol) to CiA 305 is required.



The FAULHABER Motion Manager must be installed on a PC with a supported CAN interface.

There are two ways of setting the communication parameters:

- An individual drive is connected at the CAN interface of the configuration tool:
The “LSS Switch Mode Global” without further data allows the drive to be switched to configuration mode, in order to set the node number and Baud rate.
- The drive to be configured is connected via the CAN interface within a network to the configuration tool:
The “LSS Switch Mode Selective” allows the desired drive to be addressed by inputting the LSS address (Vendor ID, Product code, Revision number, Serial number) and switched to configuration mode, in order to set the node number and Baud rate.

FAULHABER drives of the range MC V3.0 require the following input:

- Vendor ID: 327
- Product code: 48
- Revision number: 1.0
- Serial number: See the product sticker

As well as the setting of the node number and Baud rate, the LSS protocol also supports the reading of the LSS addresses of units that are connected and the reading of the node ID setting.

The identifier 0x7E5 is used (by the master) and 0x7E4 (by the slave) for LSS communication.

After configuration, the Motion Controller saves the set parameters in the EEPROM. They remain available after switching off and on again.

For a detailed description of the LSS protocol please refer to the document CiA 305.

5.1.1 Setting the node number

- Node numbers 1 to 127 can be set.
- The node ID 255 (0xFF) marks the node as unconfigured. After it is switched on, the node is in the LSS-Init status, until a valid node number is assigned. After a valid node number has been assigned to the node, the NMT initialisation continues.

Communications settings

5.1.2 Setting the Baud rate

- If the automatic Baud rate detection (AutoBaud) is active, the drive can be used in a network with any transmission rate in accordance with Tab. 19. The Baud rate of the network is detected after no more than 24 telegrams (3 per Baud rate) on the bus cable. The drive then sets itself to match the network Baud rate.
- If the automatic Baud rate detection is active, telegrams cannot be processed until the Baud rate has been detected. If the automatic Baud rate detection is active, it takes correspondingly longer to boot up the system.
- A fixed Baud rate in accordance with Tab. 19 can be set by inputting the index 0 to 8.

Tab. 19: Bit timing parameters

Baud rate	Index
1000 kBit/s	00
800 kBit/s	01
500 kBit/s	02
250 kBit/s	03
125 kBit/s	04
50 kBit/s	06
20 kBit/s	07
10 kBit/s	08
AutoBaud	09

5.1.3 Automatic adjustment of the COB-IDs

If the node number is changed from 255 (unconfigured CANopen node) to a valid node number, the COB-IDs for the Receive and Transmit PDOs (RxPDO, TxPDO) and for Emergency (EMCY) are automatically set to the default values (see chap. 6.1, p. 43, objects 0x1014.00, 0x1400.01, 0x1401.01, 0x1402.01, 0x1403.01, 0x1800.01, 0x1801.01, 0x1802.01, 0x1803.01).

The configuration must be saved using the "Save" command.

Communications settings

5.2 Setting the node number via the object dictionary

As an alternative to the LSS method via the CAN network, the node number can also be set via any interface (CAN, USB, RS232) available on the drive.

The setting is performed by writing the object 0x2400.03 in the object dictionary:

Tab. 20: CAN Baud rate index and node number

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2400	0x00	Number of entries	U8	rw	4	Number of object entries
	0x01	CAN Rate	U8	rw	9	Index of the CAN Baud rate to Tab. 19
	0x03	Node ID	U8	rw	255	Node number

The object 0x2400.01 can be used to read the current setting of the Baud rate (AutoBaud or fixed Baud rate).

A change of the node number via the object 0x2400.03 is acknowledged with the last node number. The changed node number is not loaded until a "Save " command has been executed for the application parameters followed by a "Reset" command.

Parameter description

6 Parameter description

6.1 Communication objects to CiA 301

Device Type

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1000	0x00	Device Type	U32	ro	0x00420192	Indication of the device type

Contains information on the device type, coded in two 16-bit fields:

- Byte MSB (Most Significant Byte): additional information = 0x192 (402d)
- Byte LSB (Least Significant Byte): 0x42 (servo drive, type-specific PDO mapping)

Error Register

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1001	0x00	Error Register	U8	ro	Yes	Error register

The error register contains a record of the most recent errors, in bit-coded form.

This parameter can be mapped in a PDO.

Predefined Error Field (error log)

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1003	0x00	Number of Errors	U8	rw	–	Number of errors stored
	0x01–0x08	Standard Error Field	U32	ro	–	Error codes that have occurred most recently

The error log contains the coding for the last error to occur.

- Byte MSB: Error Register
- Byte LSB: Error Code

The meaning of the error codes is described in chap. 3.6, p. 24.

Writing a 0 to the subindex 0 clears down the error log.

COB-ID SYNC

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1005	0x00	COB ID SYNC	U32	rw	0x80	CAN-object identifier of the SYNC object

Manufacturer's Device Name

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1008	0x00	Manufacturer's Device Name	Vis string	const	–	Device name

The segmented SDO record must be read to determine the manufacturer's device name.

Parameter description

Manufacturer's Hardware Version

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1009	0x00	Manufacturer's Hardware Version	Vis string	const	–	Hardware version

The segmented SDO record must be read to determine the manufacturer's hardware version.

Manufacturer's Software Version

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x100A	0x00	Manufacturer's Software Version	Vis string	const	–	Software version

The segmented SDO record must be read to determine the manufacturer's software version.

Guard Time

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x100C	0x00	Guard Time	U16	rw	0	Monitoring time for node guarding

The guard time is stated in milliseconds. The value 0 switches node guarding off (chap. 3.8.2.1, p. 30).

Life Time Factor

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x100D	0x00	Life Time Factor	U8	rw	0	Time factor for node guarding

The life-time factor multiplied by the guard time gives the life-time for the node guarding (chap. 3.8, p. 27). The value 0 switches node guarding off.

Store Parameters

Tab. 21: Saving parameters

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1010	0x00	Number of entries	U8	ro	9	Number of object entries
	0x01	Save All Parameters	U32	rw	1	Saves all parameters
	0x02	Save comm parameters	U32	rw	1	Save the communication parameters (object directory entries 0x0000 to 0x1FFF)
	0x03	Save app parameters	U32	rw	1	Save the application parameters (object dictionary entries 0x2000 to 0x6FFF)
	0x04	Save app parameters 1	U32	rw	1	Save application parameters for direct changes (set 1)
	0x05	Save app parameters 2	U32	rw	1	Save application parameters for direct changes (set 2)

The "Save Parameters" object saves the configuration parameters into the flash memory. Read access supplies information about the save options. Writing the "Save" signature to the respective subindex initiates the save procedure.

Parameter description

Tab. 22: "Save" signature

Signature	ISO 8 859 ("ASCII")	hex
MSB	e	65 h
	v	76 h
	a	61 h
LSB	s	73 h



NOTICE!

The flash memory is designed to accommodate 10,000 write cycles. If this command is executed more than 10,000 times, the correct operation of the flash memory can no longer be guaranteed.

- ▶ Avoid performing frequent saves.
- ▶ After 10,000 save cycles, replace the device.

Restore Default Parameters

Tab. 23: Restoring the parameters

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1011	0x00	Number of entries	U8	ro	6	Number of object entries
	0x01	Restore all default parameters	U32	rw	1	Restore all factory settings
	0x02	Restore comm default parameters	U32	rw	1	Restore all factory settings for communications parameters (0x0000 to 0x1FFF)
	0x03	Restore app default parameters	U32	rw	1	Restore all factory settings for application parameters (from 0x2000)
	0x04	Reload user parameters	U32	rw	1	Restore the user's last saved settings for application parameters (from 0x2000)
	0x05	Reload application parameters 1	U32	rw	1	Application parameter set 1 for direct changes
	0x06	Reload application parameters 2	U32	rw	1	Application parameter set 2 for direct changes

The object "Restore Default Parameters" loads the standard configuration parameters. The standard configuration parameters are either those as delivered or those last saved. Read access supplies information about the restore options. Writing the "Load" signature to the respective subindex initiates the restore procedure:

Tab. 24: "Load" signature

Signature	ISO 8859 ("ASCII")	hex
MSB	d	64 h
	a	61 h
	o	6Fh
LSB	l	6Ch



The status as delivered may be loaded only when the output stage is switched off.

Parameter description

COB-ID Emergency Message

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1014	0x00	COB-ID EMCY	U32	rw	0x80 + node ID	CAN object identifier of the emergency object

Consumer Heartbeat Time

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1016	0x00	Number of entries	U8	ro	1	Number of object entries
	0x01	Consumer Heartbeat Time	U32	rw	0	Heartbeat monitoring time

- Bits 0 to 15 contain the consumer heartbeat time in milliseconds. If the value is set to 0, the consumer heartbeat function is deactivated (Heartbeat)
- Bits 16 to 23 contain the node number to which the heartbeat message is sent (master node ID).
- Bits 24 to 31 are not used (spare).

Producer Heartbeat Time

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1017	0x00	Producer Heartbeat Time	U16	rw	0	Heartbeat send time interval

The object producer heartbeat time contains the producer heartbeat time interval in milliseconds. If the value is set to 0, the producer heartbeat function is deactivated (see Setting the monitoring functions).

Identity Object

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1018	0x00	Number of entries	U8	ro	4	Number of object entries
	0x01	Vendor ID	U32	ro	327	Manufacturer's code number (FAULHABER: 327)
	0x02	Product Code	U32	ro	48	Product code number
	0x03	Revision number	U32	ro	–	Version number
	0x04	Serial number	U32	ro	–	Serial number

Error Behaviour

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1029	0x00	Number of entries	U8	ro	1	Number of object entries
	0x01	Communication Error	U8	rw	0	Behaviour in the event of communication errors 0 = Pre-operational status 1 = No change of status 2 = Stopped status

In the event of a serious communications error the Motion Controller switches to the *Pre-Operational* NMT status. Subindex 1 allows the behaviour in the event of a serious communications error to be changed.

Parameter description

Server SDO Parameters

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1200	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Client to Server (rx)	U32	ro	0x600 + node ID	CAN object identifier for the server RxSDO
	0x02	COB ID Server to Client (tx)	U32	ro	0x580 + node ID	CAN object identifier for the server TxSDO

Receive PDO1 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1400	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by RxPDO1	U32	rw	0x200 + node ID	CAN object identifier for the server RxPDO1
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Receive PDO2 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1401	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by RxPDO2	U32	rw	0x300 + node ID	CAN object identifier for the server RxPDO2
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Receive PDO3 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1402	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by RxPDO3	U32	rw	0x400 + node ID	CAN object identifier for the server RxPDO3
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Receive PDO4 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1403	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by RxPDO4	U32	rw	0x500 + node ID	CAN object identifier for the server RxPDO4
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Receive PDO1 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1600	0x00	Number of Mapped Objects	U8	ro	1	Number of mapped objects
	0x01	RxPDO1 Mapping Entry 1	U32	rw	0x60400010	Pointer to the 16-bit Controlword (0x6040)
	0x02	RxPDO1 Mapping Entry 2	U32	rw	0	
	0x03	RxPDO1 Mapping Entry 3	U32	rw	0	
	0x04	RxPDO1 Mapping Entry 4	U32	rw	0	

Parameter description

Receive PDO2 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1601	0x00	Number of Mapped Objects	U8	ro	2	Number of mapped objects
	0x01	RxPDO2 Mapping Entry 1	U32	rw	0x60400010	Pointer to the 16-bit Controlword (0x6040)
	0x02	RxPDO2 Mapping Entry 2	U32	rw	0x607A0020	Pointer to the 32-bit Target Position (0x607A)
	0x03	RxPDO2 Mapping Entry 3	U32	rw	0	
	0x04	RxPDO2 Mapping Entry 4	U32	rw	0	

Receive PDO3 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1602	0x00	Number of Mapped Objects	U8	ro	2	Number of mapped objects
	0x01	RxPDO3 Mapping Entry 1	U32	rw	0x60400010	Pointer to the 16-bit Controlword (0x6040)
	0x02	RxPDO3 Mapping Entry 2	U32	rw	0x60FF0020	Pointer to the 32-bit Target Velocity (0x60FF)
	0x03	RxPDO3 Mapping Entry 3	U32	rw	0	
	0x04	RxPDO3 Mapping Entry 4	U32	rw	0	

Receive PDO4 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1603	0x00	Number of Mapped Objects	U8	ro	2	Number of mapped objects
	0x01	RxPDO4 Mapping Entry 1	U32	rw	0x60400010	Pointer to the 16-bit Controlword (0x6040)
	0x02	RxPDO4 Mapping Entry 2	U32	rw	0x60710010	Pointer to the 16-bit Target Torque (0x6071)
	0x03	RxPDO4 Mapping Entry 3	U32	rw	0	
	0x04	RxPDO4 Mapping Entry 4	U32	rw	0	

Transmit PDO1 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1800	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by TxPDO1	U32	rw	0x180 + node ID	CAN object identifier of the TxPDO1
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Parameter description

Transmit PDO2 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1801	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by TxPDO2	U32	rw	0x280 + node ID	CAN object identifier of the TxPDO2
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Transmit PDO3 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1802	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by TxPDO3	U32	rw	0x380 + node ID	CAN object identifier of the TxPDO3
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Transmit PDO4 Parameter

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1803	0x00	Number of entries	U8	ro	2	Number of object entries
	0x01	COB ID Used by TxPDO4	U32	rw	0x480 + node ID	CAN object identifier of the TxPDO4
	0x02	Transmission Type	U8	rw	255 (asynchr.)	Type of PDO transmission

Transmit PDO1 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1A00	0x00	Number of Mapped Objects	U8	rw	1	Number of mapped objects
	0x01	TxPDO1 Mapping Entry 1	U32	rw	0x60410010	Pointer to the 16-bit Statusword (0x6041)
	0x02	TxPDO1 Mapping Entry 2	U32	rw	0	
	0x03	TxPDO1 Mapping Entry 3	U32	rw	0	
	0x04	TxPDO1 Mapping Entry 4	U32	rw	0	

Transmit PDO2 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1A01	0x00	Number of Mapped Objects	U8	rw	2	Number of mapped objects
	0x01	TxPDO2 Mapping Entry 1	U32	rw	0x60410010	Pointer to the 16-bit Statusword (0x6041)
	0x02	TxPDO2 Mapping Entry 2	U32	rw	0x60640020	Pointer to the 32-bit Position Actual Value (0x6064)
	0x03	TxPDO2 Mapping Entry 3	U32	rw	0	
	0x04	TxPDO2 Mapping Entry 4	U32	rw	0	

Parameter description

Transmit PDO3 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1A02	0x00	Number of Mapped Objects	U8	rw	2	Number of mapped objects
	0x01	TxPDO3 Mapping Entry 1	U32	rw	0x60410010	Pointer to the 16-bit Statusword (0x6041)
	0x02	TxPDO3 Mapping Entry 2	U32	rw	0x606C0020	Pointer to the 32-bit Velocity Actual Value (0x606C)
	0x03	TxPDO3 Mapping Entry 3	U32	rw	0	
	0x04	TxPDO3 Mapping Entry 4	U32	rw	0	

Transmit PDO4 Mapping

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x1A03	0x00	Number of Mapped Objects	U8	rw	2	Number of mapped objects
	0x01	TxPDO4 Mapping Entry 1	U32	rw	0x60410010	Pointer to the 32-bit Position Actual value (0x6064)
	0x02	TxPDO4 Mapping Entry 2	U32	rw	0x60770010	Pointer to the 16-bit Torque Actual Value (0x6077)
	0x03	TxPDO4 Mapping Entry 3	U32	rw	0	
	0x04	TxPDO4 Mapping Entry 4	U32	rw	0	

Parameter description

6.2 Manufacturer-specific objects

FAULHABER error register

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2320	0x00	Fault Register	U16	ro	–	FAULHABER error register

The FAULHABER error register contains the most recent errors in bit-coded form. The errors can be masked by selection of the desired types of error via the error mask object (0x2321).

Error Mask

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2321	0x00	Number of entries	U8	ro	6	Number of object entries
	0x01	Emergency Mask	U16	rw	0x00FF	Errors for which an error message is sent
	0x02	Fault Mask	U16	rw	0x0000	Errors for which the state machine of the drive switches into <i>Fault Reaction Active</i> state
	0x03	Error Out Mask	U16	rw	0x00FF	Errors for which the error output pin is set
	0x04	Disable Voltage Mask	U16	ro	0x0000	Errors which switch the drive off (not configurable)
	0x05	Disable Voltage User Mask	U16	rw	0x0000	Errors which switch the drive off (configurable)
	0x06	Quick Stop Mask	U16	rw	0x0000	Errors for which the state machine of the drive switches into <i>Quick Stop Active</i> state

The statuses of the drive state machine are described in the documentation for the drive functions.

Trace Configuration

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2370	0x00	Number of entries	U8	ro	10	Number of object entries
	0x01	Trigger Source	U32	wo	0	Trigger source
	0x02	Trigger Threshold	S32	rw	0	Trigger threshold
	0x03	Trigger Delay Offset	S16	rw	0	Trigger delay
	0x04	Trigger Mode	U16	rw	0	Trigger mode
	0x05	Buffer Length	U16	rw	100	Buffer length
	0x06	Sample Time	U8	rw	1	Recording sampling rate 1: in every sampling step
	0x07	Trace Source of Channel 1	U32	wo	0	Trace source of channel 1
	0x08	Trace Source of Channel 2	U32	wo	0	Trace source of channel 2
	0x09	Trace Source of Channel 3	U32	wo	0	Trace source of channel 3
	0x0A	Trace Source of Channel 4	U32	wo	0	Trace source of channel 4

Parameter description

Trace Buffer

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2371	0x00	Number of entries	U8	ro	5	Number of object entries
	0x01	Trigger State	U16	ro	0	Trigger state
	0x02	Trace Value of Channel 1	Vis string	ro	–	Signal buffer, channel 1
	0x03	Trace Value of Channel 2	Vis string	ro	–	Signal buffer, channel 2
	0x04	Trace Value of Channel 3	Vis string	ro	–	Signal buffer, channel 3
	0x05	Trace Value of Channel 4	Vis string	ro	–	Signal buffer, channel 4

CAN Baud Rate Index and Node Number

Tab. 25: CAN Baud Rate Index and Node Number

Index	Subindex	Name	Type	Attr.	Default value	Meaning
0x2400	0x00	Number of entries	U8	rw	4	Number of object entries
	0x01	CAN Rate	U8	rw	9	Index of the CAN Baud rate to Tab. 19
	0x03	Node ID	U8	rw	255	Node number

