

CANopen®

Virtual Fluid Lab VFL

CANopen
Modification: 000

**Protocol
Description**



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Preface

This documentation describes the intended use of the product within a superordinate control system. It will help you to get acquainted with the provided communication interface and assist you in obtaining maximum benefit in the possible applications for which it is designed.

The specifications given in this documentation represent the state-of-the-art of the product at the time of publishing. Modifications to technical specifications, illustrations and dimensions are therefore possible.



The electronic document version contains many **active cross-references**, which are written in italics.

HYDAC FILTERTECHNIK GMBH

Technical documentation

Industriegebiet

D-66280 Sulzbach / Saar

-Germany-

Phone: +49(0)6897 / 509-01

Fax: +49(0)6897 / 509-300

Quick Start

General information

General product information, definition of the scope of applications, symbols used, as well as abbreviations.

Quick guide

In this chapter, the experienced users will find the factory pre-set process data signals as well as the device's own specifications supported by the measurement system.

Process data

Description of all signals provided as process data by the measurement system.

Parameter

Adjustable parameters for the communication or the functions of the measurement system.

Protocol description CANopen

Description of the report used This chapter describes principles and examples which help to facilitate the communication with the measurement system.

Subsequent Chapters

All chapters subsequent to the protocol description provide additional and useful information for the commissioning and application of the measurement system.

1. General information

This protocol description, including the illustrations contained therein, is subject to copyright protection. Use of this document by third parties in contravention of copyright regulations is forbidden. Reproduction, translation as well as electronic and photographic archiving and modification require the written permission of the manufacturer. Offenders will be liable for damages.

Before commissioning the product, please read the related operating instructions as well as this protocol description. Ensure that the unit described, hereinafter referred to as the measuring system, is suitable for your application.



Before each startup, installation or replacement, the measurement system including related accessories has to undergo a visual check for damage.



If the instrument is not handled correctly, or if the operating instructions and specifications are not adhered to, damage to property and/or personal injury can result.

1.1. Scope of applications

This protocol description exclusively applies to the following measurement system series for differential and dynamic pressure measurement without increased demands upon functional safety. The products covered by this description can be identified by means of the following model code structure:

- CANopen: **Vx VFL.0/-V-C4D020**
 - Only the positions in the model code marked by "x" can be freely occupied using the attributes listed in the data sheet.

The products are components of a system or machine, labelled with affixed nameplates.

The following documentation should therefore always be read together:

- The operator's system and machine-specific operating manuals
- The related instruction manual
- This protocol description for CANopen

1.2. Exclusion of liability

This protocol description was prepared to the best of our knowledge. Nevertheless and despite the greatest care, it cannot be excluded that mistakes could have crept in. Therefore please understand that in the absence of any provisions to the contrary hereinafter our warranty and liability – for any legal reasons whatsoever – are excluded in respect of the information in this operating manual.



In the event of translation, only the original version of the protocol description in German is legally valid.

In particular, we shall not be liable for loss of profit or other financial losses. This exclusion of liability does not apply in cases of intent or gross negligence. Moreover, it does not apply to defects which have been deceitfully concealed or whose absence has been guaranteed, nor in cases of culpable harm to life, physical injury and damage to health. If we negligently breach any material contractual obligation, our liability shall be limited to foreseeable damage. Claims due to the Product Liability shall remain unaffected.

1.3. Symbols

In the following section we have listed all symbols used and their meaning.

	The symbol means that the circumstances described here are forbidden (<i>general prohibition sign according to DIN EN ISO 7010</i>).
	The symbol means that death, serious personal injury or severe damage to property could occur if the precautions stated here have not been adhered to or have not been taken (<i>general warning sign according to EN ISO 7010</i>).
	The symbol indicates important information or features and application suggestions for the product used.
	The symbol means that appropriate ESD-protective measures must be observed according to DIN EN 100 015-1. (Cause of a potential equalisation between body and device-mass as well as the housing-mass by means of a high-impedance resistance (approx. 1 MΩ) e.g. with a standard ESD wrist strap).

1.4. Abbreviations used and definitions

List of abbreviations used and glossary of terms which are not common.

Abbreviation	Description
ACC	Accelerometer
ASCII	American Standard Code for Information Interchange
Baud rate	Communication speed of the bus system [bit/s]
CAN	Controller Area Network
CANopen	CAN based communication protocol for automation tasks

Abbreviation	Description
CiA	CAN international users' and manufacturers' IN CiA (EU trademark 00 710 98 46) (EU trademark 00 710 98 46)
DIN	Deutsches Institut für Normung e.V. (DIN - German Institute for Standardisation)
DLC	Data Length Code ; data length in a CAN message
ECU	Electronic Control Unit Superordinate control, e. g. PLC or mobile control unit
EDS	Electronic Data Sheet electronically readable description of the CANopen OD
EC	European Community
EMC	Electro Magnetic Compatibility
EN	European standard
ESD	Electro Static Discharge
Flash	Permanent memory for application software and persistent data
GYRO	Gyroscope
VFL	Virtual Fluid Lab
IEC	International Electrotechnical Commission
ISO	International Organization for Standardization
J1939	CAN based communication protocol for vehicle manufacturing (SAE J1939)
LSS	Layer Setting Services Protocol for the setting of the node ID, the BAUD rate and the LSS address
MEMS	Micro-Electro-Mechanical System
NEC	National Electrical Code
NMT	Network Management ; management of the network accounts
Node ID	CANopen Node address
OD	Object Dictionary ; Object dictionary of all communication objects provided by the product
PC	Personal Computer
PDO	Process Data Object Object for the transmission of process data
RAM	Random Access Memory ; volatile, fast memory
RMS	Root Mean Square
RPDO	Receive PDO ; process data received by the CAN nodes

Abbreviation	Description
Rx / Tx	Rx: Receiver / Tx: Transmitter; Direction of the data flow from the perspective of a superordinate controller Tx: ECU → Device, Rx: Device → ECU
SAE	Society of Automotive Engineers
SDO	Service Data Object Object for the access to the CANopen OD
PLC	Programmable Logic Controller
SRDO	Safety-Relevant Data Object Object for the safe transmission of values for CANopen Safety
TPDO	Transmit PDO; process data sent from the CAN node
UL	Underwriters Laboratories
VDC	Direct current
VDE	Verein Deutscher Elektrotechniker (German Electrical Engineer Association)

1.5. General document structure

This document has a defined structure. Subsequent to each chapter title, there will be a short description of the chapter content.

It is not only our aim to show the users an efficient way to find a specific response to their inquiry, but also to provide the users with less prior knowledge with the required information to ensure successful use of the product.

1.5.1. Chapter structure

The general structure is divided into the following essential chapters.

- **2 Fundamentals** and basics

General information explaining the function principle of a measuring system equipped with a communication interface.

- **3 Product** interface

All the product specific characteristics are described here. Certain sections of this description may repeat and differ at the same time in the protocol description if the measurement system described herein deviates from the general protocol description or if the properties of the protocol description are complemented.

➤ **4 Protocol description** CANopen

The general protocol description provides you with all information required for a successful communication. It explains, for instance, how the process data is transmitted with this specific communication protocol. In addition, it explains how to change the measurement system configuration settings.

1.5.2. Notes on using this documentation efficiently

In order to get quick access to particular subjects, this document is linked with active cross-references (hyperlinks). These are formatted in *italics*.

This chapter *3.1 Quick* guide is designed to lead you to responses to the most frequently asked questions as quickly as possible.

Symbols and abbreviations are explained in chapters *1.3 Symbols* and *1.4 Abbreviations used and definitions*.

The display of numeric figures is explained in chapter *2.2 Display* of numeric figures.

Technical English terms are placed between quotation marks ("..").

1.6. Changes in technical terms in the context of "political correctness"

HYDAC Filtertechnik GmbH continuously strives to respect human rights and every individual's dignity in any context. However, when it comes to communication technology, one technical term is still very common: "Master – Slave".

In order to avoid this archaic and discriminating expression, the term has been replaced wherever possible in this documentation, using the following substitution: "Master – Device" ("Device" replacing "Slave"). The only exceptions are terms which are used in this form in official documentation. These exceptions are only used to make it easier for the reader to understand the connection between this documentation and the official documents.

2. Fundamentals and basics

The following sections will explain general, non-product specific information for a better understanding of the functioning principle of a measurement system with a communication interface.

2.1. General communication characteristics

In general, the measurement systems are the end-nodes within a communication network. They do not take control of their superordinate network themselves. However, these devices are able to generate and send information spontaneously. This means that the measurement systems mainly serve as a data source - they generate process data.

The following types of information can be generated and processed by the measurement system:

- *Process data* current actual or nominal values
- *Parameters* System data for the device identification or configuration
- *Events* Information on particular events, such as errors

The information types listed here are explained in more detail in the following chapters.

2.2. Display of numeric figures

The figures without additional markings are displayed as numeric figures with decimals (number basis 10). For a more simple display of data blocks, however, hexadecimal representation is also very commonly used (number basis 16). In our document, the hexadecimals are generally marked by an "h" as a suffix.

Decimal numbers, when displayed in a mixed representation, are marked with the additional suffix "d".

Binary numbers (number basis 2) are marked by suffix "b".

- **12h** 12 hexadecimal → 18 decimal
- **A2h** A2 hexadecimal → 162 decimal
- **16d** 16 decimal → 10 hexadecimal
- **66** 66 decimal → 42 hexadecimal
- **10b** 10 binary → 2 decimal

Note

In other documentations, i.e. EDS files, you will also frequently encounter the format "**0x1042**". Here, the prefix "0x" marks the subsequent number as a hexadecimal.

When describing the entries in the OD (see chapter 4.5 *The Object Dictionary*). The index is always shown in hexadecimal notation, but without any particular markings.

2.3. Bit order

The measurement systems use the "LittleEndian" format for the transmission of their numeric values. In this representation of numeric values, the lowest bit (LSB; "least significant bit") will be stored and added the lowest data block address.

2.3.1. Counting principle for bit and byte position in the data block

In practice, there are different ways of counting in order to define the position of a particular date within a data block. For this documentation, the following way of counting has been defined:

- Bit positions within a continuous data block start with 0.
- Byte positions within a data block start with 0.

2.3.2. Representation of a 16 bit integer number within a data block

The following example will explain the storage position of the "Little Endian" format. For this purpose, the transmission of an *INTEGER16*, e.g. of a 16 bit signed integer number, is shown in the data block of a CAN message (8 bytes).

The value to be transmitted will be shown as a hexadecimal number in order to show more clearly how the number is assigned to the bytes within the data block.

Numerical value decimal	4711d						
Numerical value hexadecimal	1267h						
Numerical value binary	0001 0010 0110 0111						
Data bytes of the CAN message							
Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
<i>INTEGER16</i>	No orientation restrictions						

Using the "Little Endian" bit order, the least significant byte of the numeric value (**67h** in our example) is copied to the least significant byte of the data block (marked blue). At the same time, the least significant bit (LSB) is located in the least significant bit of the first byte (marked red). For better clarity, the data ranges which are not used, byte 2 to 7, are not shown.

Byte 0	Byte 1	Data bytes of the CAN message
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	Bit position
67h	12h	Content hexadecimal
0 1 1 0 0 1 1 1	0 0 0 1 0 0 1 0	Content binary

2.3.3. Display of a 32 bit integer number within the data block

In the following example, the transmission of an *INTEGER32*, e.g. of a 32 bit signed integer numeric value, within a data block of a CAN message (8 bytes) is shown in the "Little Endian" format.

Numerical value decimal				-2011871471d			
Numerical value hexadecimal				88154711h			
Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
<i>INTEGER32</i>				No orientation restrictions	No orientation restrictions	No orientation restrictions	No orientation restrictions
11h	47h	15h	88h	No orientation restrictions	No orientation restrictions	No orientation restrictions	No orientation restrictions

2.4. Data types

For all data types, the display of numeric values described in the chapter 2.3 *Bit* order is applicable to the storage within data blocks.

2.4.1. INTEGER

INTEGER is the term for signed whole numbers whose data length may vary. Negative figures will be specified by a two's complement [NOT(<numeric value>)1]. The data length is specified in bits and is added as a suffix right after the data type identifier. If the most significant bit is an INTEGER figure 1, this will be negative.

Therefore, INTEGER16 means it is a signed whole number whose data length is 16 bits.

Data type	Length [Bit]	Min.	Max.
INTEGER8	8	-128	+127
INTEGER16	16	-32.768	+32.767
INTEGER32	32	-2147483648	2147483647

For the illustration of data in a data block of more than 1 byte of length, the bit order has to be paid attention to; see chapter 2.3 *Bit* order.

2.4.2. UNSIGNED

UNSIGNED specifies unsigned whole numbers. This means that only positive figures can be displayed using this data type. The data length in bytes is added as a suffix.

UNSIGNED32 is a whole numeric value without a sign and with a data length of 32 bits.

Data type	Length [Bit]	Min.	Max.
UNSIGNED8	8	0	+255
UNSIGNED16	16	0	+65.535
UNSIGNED32	32	0	4294967295

For the illustration of data in a data block of more than 1 byte of length, the bit order has to be paid attention to; see chapter 2.3 *Bit order*.

2.4.3. BOOLEAN

The data type BOOLEAN is used to illustrate binary signals. These are signals which are not able to adopt more than two logical states. The data length in the memory may vary. If an individual binary signal is stored in the memory, the data type is usually an *UNSIGNED8*. Should the binary signal be a part of a BITFIELD, the data length is 1 bit.

Va- lue	DE	EN	Meaning
0	FALSCH	FALSE	Signal or property is not active.
1	WAHR	TRUE	Signal or property is active.
(≠ 0)			Thus, each bit of the BITFIELD corresponds with a signal of the data type BOOLEAN.

2.4.4. BITFIELD

The data type UNSIGNED is often used for the display of bitfields. In this case, each bit of the date has its own signification, although in many cases, not all bit positions are used. Each bit of the BITFIELD therefore corresponds with a signal of the data type *BOOLEAN*. The significance of each individual bit is explained in the related description.

Status signals are often displayed as a bitfield. The representation of the content of a bitfield is usually in binary format, i.e. bit-oriented.

The relevant characteristic is active if the bit which is related to the characteristic is active, which means it has the binary numeric value of 1 (TRUE).



In case of a bitfield, a few indications can be set synchronously. Therefore, for the evaluation of an individual indication, an appropriate masking should be applied for the bit field.

The comparison with a simple constant may fail when having a combination of indications.

Bit positions which are unused may take on fixed values (0/1), depending on internal application states, or shift between the states. For a reliable evaluation, these bit positions should therefore be ignored.

Example of a BITFIELD

7	6	5	4	3	2	1	0	Bit	
								Temperature compensation inactive	BOOLEAN
								Device in movement	BOOLEAN
								Reserved	
								Serious error	BOOLEAN
								Reserved	
								Reserved	
								Reserved	
								Reserved	

Example of the contents and the signification

0000 0010b = 02h = 2d → indication "device in movement" is active.

0000 1010b = 0Ah = 10d → indication "device in movement" is active and "severe error" are active at the same time.

2.4.5. REAL32

REAL32 is a signed floating point number with a data length of 32 bits. These types of numbers are subdivided into one signed bit (1 bit), one mantissa (23 bits) and one exponent (8 bits). With this numeric value, the non-negative integer numbers can be displayed with sufficient accuracy. The representation below corresponds with IEEE754.

Data type	Length [Bit]	Min.	Max.
REAL32	32	-3,40282347E38	+3,40282347E38

2.4.6. ARRAY

ARRAY is a data type containing a variety of different entries/values. In an ARRAY, the entries are all of the same data type. The value entries in an ARRAY have the same signification but do not have the same content, i.e. a list of all the recently recorded device error numbers. For the individual entries, the simple data types described above, such as UNS/GNED32, are used.

In the protocol described here, the first entry of the ARRAY indicates the number of existing entries. In an ARRAY, a maximum of 255 entries is allowed. This entry always has a sub-index of 0 and is handled in a special way.

The individual value entries are accessed via a sub-index. The first sub-index for a value entry is 1. If a sub-index is accessed which is of higher value than the content of the sub-index 0 (number of valid ARRAY entries) an error message will occur.

2.4.6.1. Example ARRAY

The following example shows the structure of an ARRAY in the OD, see chapter *The Object Dictionary*.

Index	Sub	Value	Name	Type	Access	Data type
1003h			<i>Pre-defined error field</i>	ARRAY		
1003h	0	4	Number of errors	VAR	rw	UNSIGNED8
1003h	1	1001	Standard error field 1	VAR	ro	UNSIGNED32
1003h	2	2002	Standard error field 2	VAR	ro	UNSIGNED32
1003h	3	3003	Standard error field 3	VAR	ro	UNSIGNED32
1003h	4	4004	Standard error field 4	VAR	ro	UNSIGNED32

2.4.7. RECORD

A RECORD is a data type containing a variety of different entries/values. In some programming languages this data type is also referred to as a **structure**. In contrast to an ARRAY, in the case of a RECORD, the individual entries may consist of different data types. The value entries in a RECORD therefore have different meanings and contents, i.e. *Device code*. For the individual entries, the simple data types described above, such as *UNSIGNED32*, are used.

In the protocol described, the first entry of the RECORD defines the highest existing sub-index in the existing sections of a record. This entry always has a sub-index of 0 and is handled in a special way. The number of entries may be smaller than this value, as not all of the sub indices need to be used. In a RECORD, a maximum of 255 entries is allowed.

The individual value entries are accessed via a sub-index. The first sub-index for a value entry is 1. If a sub-index is accessed which is of higher value than the content of the sub-index 0 (number of valid RECORD entries), an error message will occur. The same applies when accessing a "gap" in the RECORD (a non-defined sub-index).

2.4.7.1. Example RECORD

The following example shows the structure of a RECORD in the OD.

See chapter 4.5°*The Object Dictionary*.

Index	Sub	Value	Name	Type	Access	Data type
1018h			<i>Identity object</i>	RECORD		
1018h	0	4	Highest sub-index supported	VAR	const	UNSIGNED8
1018h	1	218	Vendor ID	VAR	ro	UNSIGNED32
1018h	2	928037	Product code	VAR	ro	UNSIGNED32
1018h	3	8	Revision number	VAR	ro	UNSIGNED32
1018h	4	4711	Serial number	VAR	ro	UNSIGNED32

2.4.7.2. Example RECORD with a "definition gap"

The following example shows the structure of an RECORD with a "gap" in the definition of the entries, see chapter 4.5.4.8 *TPDO communication parameter*. In the example, the sub-index 4 is not defined and the number of the highest value sub-index = 5.

Index	Sub	Value	Name	Type	Access	Data type
1800h			<i>TPDO communication parameter 1</i>	RECORD		
1800h	0	5	Highest sub-index supported	VAR	const	UNSIGNED8
1800h	1	180h+ Node-ID	COB ID	VAR	rw	UNSIGNED32
1800h	2	254	Transmission type	VAR	rw	UNSIGNED8
1800h	3	0	Inhibit time	VAR	rw	UNSIGNED16
1800h	5	1000	Event timer	VAR	rw	UNSIGNED16

2.4.8. STRING

A STRING is a particular data type used to visualise texts. A STRING consists of a variety of individual characters which generally represent one letter. In the memory, however, the individual characters are represented by a numeric value.

In the protocol described here, the STRING is represented by the data type VISIBLE_STRING.

The code, i.e. the relation between the letters and the numeric values in the memory, will be described in chapter 7.1 *ASCII Table*.

2.4.8.1. Example STRING

Representation of the STRING "save" and its assignment to the user data bytes as part of a SDO command, see chapters 4.6.1 *SDO* and **Store parameters**.

Byte 4	Byte 5	Byte 6	Byte 7
73h "s"	61h "a"	76h "v"	65h "e"
	73h = 115d → s		
	61h = 97d → a		
	76h = 118d → v		
	65h = 101d → e		

3. Product interface

Below, the actual communication characteristics of the measurement system will be explained in a more detailed way. The structure of messages for the transmission of information, their functional context as well as their chronological sequence will be explained in a more detailed way in chapter 4 *Protocol description CANopen*.

3.1. Quick guide

This chapter is designed to give the user quick answers to frequently occurring questions. For this purpose, the information is presented in the most compact way and provides cross-references to the related chapters for detailed information.

3.1.1. CANopen default settings

The signals in the measurement system which are typically pre-set for the process value transmission are explained below. Default settings depend on the model code and may deviate from the settings explained herein, particularly in devices with a modification (see user manual chapter "Model code" → "Modification number"). The individual signal properties are described in chapter 3.3 *Process data*

Range	Properties	Default settings
General Settings	Baud rate	250 kbit/s
	Node ID	1
	Power ON Status	Operational
TPDO1	Transmission Type	254
	Event Timer	1000 ms
	Byte 0, 1, 2, 3	Rest lifetime (VFL operating data) Real32
	Byte 4	VFL Status UNSIGNED8 BITFIELD
TPDO2	Transmission Type	254
	Event Timer	1000 ms
	Byte 0, 1, 2, 3	Operating hours (VFL operating data) Real32
	Byte 4, 5	Pressure value INT16

3.1.2. Device profile

VFL VD and VFL V1/4 support systems support the CANopen device profile "**CiA 404 Device profile for measuring devices and closed-loop controllers**". The exact measurement system-specific implementation of the device profile is described in chapter 3.5.3 *Device profile-specific* parameters.

3.1.3. Important functions

Below please see a list of the most frequent changes to measurement systems required by users.

3.1.3.1. Changing the device address (node ID)

In order to change the active device address, a particular order of actions has to be adhered to:

- **Set the device to network status "Pre-Operational"**
 - see chapter 4.4°*Network Management*
 - "Enter pre-operational" see chapter 4.4.2 *NMT*
- **Enter desired device address into Object 2003.2**
 - see object *Node ID*
 - see chapter 4.6.1°*SDO*
- **Save changes to non-volatile device memory**
 - see description *Store parameters*
 - see object *Save LSS parameters*
- **Restart device**
 - see chapter 4.4°*Network Management*
 - "Reset node" see chapter 4.4.2 *NMT*
 - or cut device power supply and reconnect "power cycle"
- **Alternative option for changing the node ID**
 - see chapter 4.7°*Layer setting services (LSS) Protocol*
 - see chapter 4.7.7°*Example: setting the node ID and Baud rate via LSS*

CAN-Trace example change device address

The following example refers to a measurement system with an active device address 1 which is supposed to be changed to 10h (16d).

```

CAN-ID (hex)
|   Direction: Tx (ECU → Device) ; Rx (Device → ECU)
|   |   Data Length
|   |   |   Data Bytes (hex)
|   |   |
+--- + - + - - - - - - - -
NMT command "Enter Pre-Operational"
0000 Tx 2 80 01
Object 2003.2 „Set Pending Node-ID“ = 10h
0601 Tx 8 2F 03 20 02 10 00 00 00
0581 Rx 8 60 03 20 02 00 00 00 00
Object Function 1010.4 "StoreLSSParameter" ("save")
0601 Tx 8 23 10 10 04 73 61 76 65

```

```

0581 Rx 8 60 10 10 04 00 00 00 00 00
NMT command "Reset Node"
0000 Tx 2 81 01
→ Device reinitialisation in process

"Boot-up" message with device address 10h
0710 Rx 1 00

```

3.1.3.2. Changing the Baud rate

In order to change the Baud rate, a certain order of actions has to be adhered to. This process is very similar to changing the Node ID. Both changes may also be carried out simultaneously. For this purpose, the object of the Node ID also has to be changed in the second step.

Please note: after the Baud rate has been changed, it is also necessary to change it in the receiver's messages.

Sequence of actions Baud rate:

- **Set the device to network status "Pre-Operational"**
 - see chapter 4.4°*Network Management*
 - "Enter pre-operational" see chapter 4.4.2 *NMT*
- **Enter desired Baud rate into Object 2004.2**
 - see object *Baud* rate
 - see chapter 4.6.1°*SDO*
 - (option: additional change to Node ID, see object *Node ID*)
- **Save changes to non-volatile device memory**
 - see description ***Store parameters***
 - see object ***Save LSS parameters***
- **Restart device**
 - see chapter 4.4°*Network Management*
 - "Reset node" see chapter 4.4.2 *NMT*
 - or cut device power supply and reconnect "power cycle"
- **Alternative option for changing the Baud rate**
 - see chapter 4.7°*Layer setting services (LSS) Protocol*
 - see chapter 4.7.7°*Example: setting the node ID and Baud rate via LSS*

CAN trace example change Baud rate

The following example refers to a measurement system with an active device address 1. The Baud rate is to be changed to 125 kbit/s.

```

CAN-ID (hex)
|     Direction: Tx (ECU → Device); Rx (Device → ECU)
|     |     Data Length

```

```

|       |   | Data Bytes (hex)
|       |   |
+--- +--+ +- - - - - - - - -
NMT command "Enter Pre-Operational"
0000 Tx 2 80 01
Object 2004.2 "Set Pending Baudrate" = 4 (125 kbit/s)
0601 Tx 8 2F 04 20 02 04 00 00 00
0581 Rx 8 60 04 20 02 00 00 00 00
Object function 1010.4 "StoreLSSParameter" ("save")
0601 Tx 8 23 10 10 04 73 61 76 65
0581 Rx 8 60 10 10 04 00 00 00 00
NMT command "Reset Node"
0000 Tx 2 81 01
→ Device reinitialisation in process

"Boot-up" message with device address 1h
0701 Rx 1 00

```

3.1.3.3. Save settings

In order to save configurations permanently in the measurement system, the "*Store*" functions enabled should be activated explicitly after having changed the parameters. These functions are explained in chapter 4.5.4.3 *Storage and restoring (general communication objects)*.

3.1.3.4. Reset to default settings

Reset to default settings is performed via "*Loading and storage parameters*" from the OD range 4.5.4 *Communication profile area*.

Inquiry of function parameters "*Restore default parameters*" all parameters will be loaded (except the settings for Node ID and Baud rate). In order to make the settings apply, the device has to be reset; see chapter 4.4.2 *NMT*.

3.1.3.5. Changing the transmission type for process data

The related communication parameters of the PDO define how and when the process data is transmitted.

For **RPDO** - Process data received by the measurement system

- 4.5.4.6 *RPDO communication parameter*
- 4.6.2.1 *Event driven*
- 4.6.2.2 *SYNC*
- 4.6.2.4 *Overview diagram PDO mapping*

For **TPDO** - Process data sent by the measurement system

- 4.5.4.8 *TPDO communication parameter*
- 4.6.2.1 *Event driven*

- 4.6.2.2 SYNC
- 4.6.2.4 Overview diagram PDO mapping

3.1.3.6. Changing the content of the process data

The content of the process data is administrated via the "PDO Mapping" see chapter 4.6.2.3 *PDO Mapping* and 4.6.2.4 *Overview diagram PDO mapping*.

To change the mapping, a defined process has to be adhered to, see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

3.1.4. What to do if no process data has been recognised

As CANopen offers high flexibility, unfortunately there are also many different causes for measurement system process data not being transmitted or received. In the following, a few points are listed which should be checked if no data or no plausible data is being transmitted.

- **Network status "Pre-Operational"**

A measuring system in the "Pre-Operation" state does not send **any** process data, see chapter 4.4.1 *Overview network conditions*.

The current network state can be read out from the "Heartbeat" protocol's data while this is active, see chapter 4.4.3 *Heartbeat*.

- **SYNC based PDO communication**

If, for the transmission of a PDO the SYNC service is active, the measurement system will either **send** a PDO only **after receiving** one or several **SYNC messages** or further process a received signal. No PDO will be exchanged without any SYNC messages.

Further information on how the SYNC processing is carried out and how it is activated is explained in the following chapters:

4.6.2.2 SYNC

4.5.4.8 TPDO communication parameter.

- **PDO COB-ID/CAN-ID parameter settings**

Via which CAN ID a PDO will be transmitted is defined by the PDO's COB ID. The parameters for this will be explained in the following chapters: for RPDO 4.5.4.6 and for TPDO 4.5.4.8.

The configuration options at the COB ID decide if a PDO will be sent at all and if the sender and the receiver work with the same ID.

- **PDO transmission active**

The indication "invalid" in the COB ID (bit 31) of a PDO decide if a PDO is sent/received at all, see object *TPDO.COB-ID*.

- **CAN ID correctly evaluated**

The PDO's CAN ID is usually calculated from the current Basis CAN ID and the current *Node ID* of the measurement system, see object *TPDO.COB-ID*.

It can easily happen that the receiver is still configured to respond to the "old" CAN ID, despite having changed the node ID of the measurement system. It may

therefore occur that messages sent via the "new" CAN ID are ignored by the PDO.

- **Evaluation of process data**

The correct evaluation of the process data is slightly more complicated. When it has been ensured that the desired PDO has been received, the desired *Process value* has to be copied from the *CAN data block* and needs to be interpreted correctly.

If the measurement system still has its factory default settings, the pre-setting of the process data is described in chapter 3.1.1 *CANopen default settings*.

If the measurement system already has an individual configuration, the mechanisms described in chapter 4.6.2 *PDO* will apply. Chapter 4.6.2.4 *Overview diagram PDO mapping* provides a good overview for this purpose.

3.2. Product description

The Virtual Fluid Lab is a new smart sensor for filter monitoring. The differential pressure (VD) or the dynamic pressure (V1/4) at a filter element is measured to determine its load state and ultimately assess a remaining service life.

Since hydraulic media change their viscosity depending on the temperature, the Virtual Fluid Lab performs a temperature compensation. For this purpose, the fluid temperature must be transmitted to the Virtual Fluid Lab. The temperature signal is transmitted here to the **Receive Process Data Object (RPDO)**.



The following please find the most important information on this product. The information listed herein is non-formal and is provided solely for the purpose of helping readers to understand the context. A more detailed description of the product properties is available in the associated operating manual.

In case of doubt, the information given in the operating manual always applies.

3.2.1. "VFL Operating data" operating data

The Virtual Fluid Lab, series VD and V1/4, provide their nominal measured variable "VFL operating data" as process values (TPDO1 and TPDO2).

- *Signal "Rest lifetime"* – TPDO1
- *Signal "Operating hours"* – TPDO2

3.2.2. "Pressure value" pressure

The Virtual Fluid Lab, series VD and V1/4, provide their nominal measured variable "Pressure value" as the process value (TPDO2).

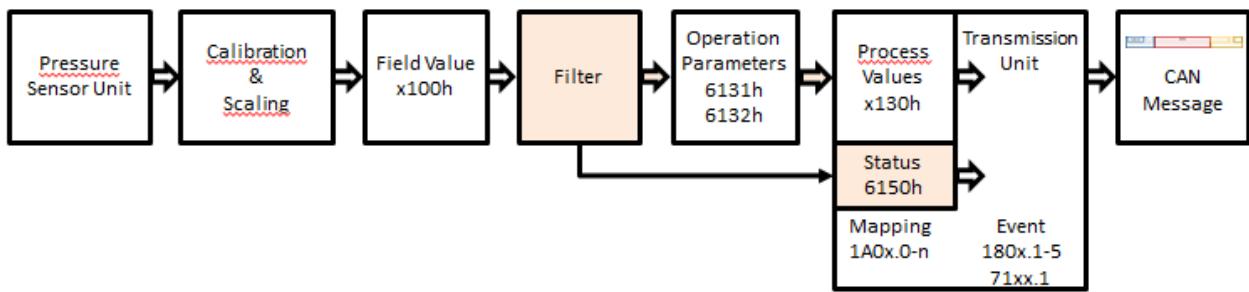
- 3.3.4 *"Pressure value" signal*

3.2.3. Input signal "external temperature value" Fluid temperature

In addition to the process values "VFL operating data" and "Pressure values", the measurement systems provide the input signal "Fluid temperature" as a process value (RPDO1).

- 3.3.6 Status "Pressure value"

The status of the signal "Pressure" gives information on the validity of this signal. The status is structured as a bit field. For the intended use of the measurement system, the "Pressure" status should always be evaluated in combination with the "Pressure" process value signal (see operating instructions).



Signal properties	Value	Additional information		
Measurement range min.	-	<i>BITFIELD</i> ; Bit 0/FALSE/inactive	value	
Measurement range max.	-	<i>BITFIELD</i> ; Bit value /TRUE/active		
Resolution	-			
Offset	-			
Data type	<i>UNSIGNED8</i>	<i>BITFIELD</i> see chapter 3.3.3.1		
Data length	8	Bit		
Mappable	<i>TPDO</i>	yes		
Process value index	6150.0	<i>Pressure status</i>		
Default settings	-			

3.2.3.1. Design of the BITFIELD status "Pressure"

In the following, the meaning of the identifiers of a BITFIELD are described.

7	6	5	4	3	2	1	0	Bit
								Not valid
								Positive overload over 100%
								Negative overload
								Reserved
								Reserved
								Reserved
								Reserved
								Reserved

- Input signal "external temperature value"

3.2.4. Input signal "VFL reset"

In addition to the process values "VFL operating data" and "Pressure difference value", the measurement systems provide the input signal "VFL reset" as a process value (RPDO2).

- 3.3.7 *Input signal "VFL reset"*

3.3. Process data

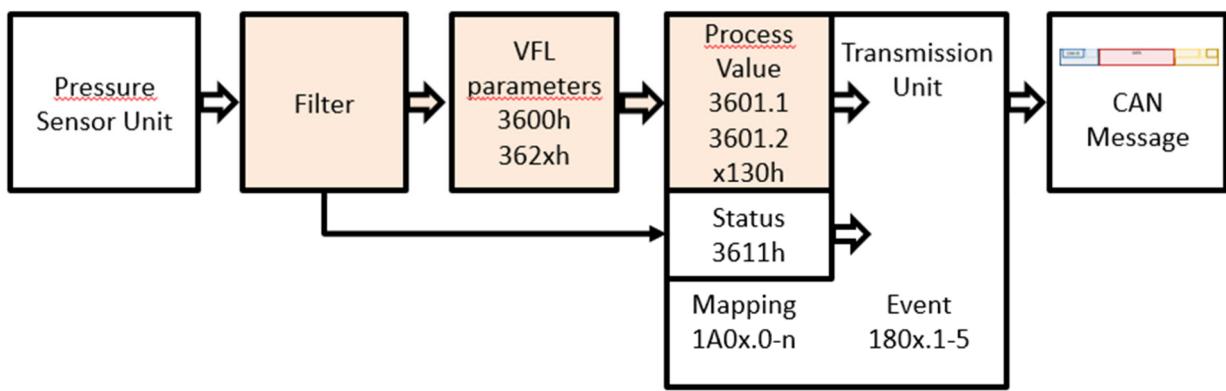
Further information on the properties or the parameterisation of process data can be found in chapter 4.6.2 *PDO*.

3.3.1. Structure of the signal description

All signals provided by the measurement system are described in the same way. The important measurands for the evaluation and conversion of the signal are listed in a table.

For each signal, a signal flow diagram shows which *Process value parameter objects* are responsible for signal processing. In the following, an example of this type of diagram is shown, explaining the tasks of the individual signal processing steps.

Signal flow diagram shown below is shown as an example of the signal processing as *REAL32*. In addition, the representation can be displayed as *INTEGER32* values. In these cases, the object address deviates from the representations.



- Sensor Unit

The sensor unit reports the raw values of the sensor cell which is relevant for the signal as a sensor value and makes it available for further signal processing.

- Filter

On this signal level, the processed signal values are now converted and filtered to become the relevant process signal.

- VFL parameters

These parameters are specific to the manufacturer and determine the function of the algorithm to calculate the remaining filter life.

- Transmission Unit

If one of the following events occurs, the value of the *PDO* is sent or received and processed depending on the preset *Transmission Type*.

1. The *Event Timer* has expired (cyclical transmission).
2. One or more *SYNC objects* have been received (synchronous transmission).

	<p>The cross-references are indicated as shown below:</p> <p>Signal description Reference to the chapter which gives a short explanation of the relevant signal. A more detailed description can be found in the related operation manual.</p> <p>Signal characteristics Refers to the chapter describing the characteristics necessary for evaluation, e.g. evaluation of the measuring range.</p> <p>Status information Refers to the chapter which explains the exact structure of a status value belonging to a signal (mainly a BITFIELD).</p>
--	--

The following table explains the meaning of the individual signal properties of a signal description.

Signal properties	Description
Measurement range min.	The smallest physical value displayable by the signal.
Measurement range max.	The greatest physical value displayable by the signal.

Signal properties	Description				
Resolution	<p>The physical value of an individual bit of the numeric value.</p> <p>Definition of the conversion between the numeric value of the data type and the physical size of the signal.</p> <p>Example:</p> <p>Numerical value: 4711d</p> <p>Resolution: 0,01 °/bit</p> $4711d * 0,01 °/Bit = 47,11 °$				
Offset	<p>Eventually existing zero offset of the numeric value.</p> <p>An offset is mainly used if the data type of the transmitted numeric value is unsigned.</p> <p>Example:</p> <p>Numerical value: 61d</p> <p>Measurement range: -40 bis +210 °C</p> <p>Resolution: 0,01 °C/bit</p> <p>Offset: -40 °C</p> $(61d * 1 °C/Bit) + (-40 °C) = 21 °C$				
Data type	Data type of the numeric signal value during transmission, see chapter 2.4 <i>Data types</i> and 2.3 <i>Bit order</i> .				
Data length	Length of the data type used for the transmission in bits.				
Mappable	<p>Defines if and which way the signal can be transmitted via CANopen <i>Process data object</i>.</p> <p>TPDO, RPDO or SRDO.</p>				
Process value index	<p>Index number of the object with the current process value for the visualisation on a PDO.</p> <p>Example:</p> <table style="margin-left: 20px;"> <tr> <td>3601.[1]</td> <td><i>Rest lifetime</i></td> </tr> <tr> <td>3601.[2]</td> <td><i>Operating hours</i></td> </tr> </table>	3601.[1]	<i>Rest lifetime</i>	3601.[2]	<i>Operating hours</i>
3601.[1]	<i>Rest lifetime</i>				
3601.[2]	<i>Operating hours</i>				
Default settings	<p>Describes if and via which <i>Process data object</i> the signal will be transmitted during emission:</p> <p>TPDO, RPDO or SRDO.</p>				

3.3.2. Signal "Operating data"

The Virtual Fluid Lab (VFL) delivers the signals "Rest Lifetime" and "Operating hours".

The remaining service life "Rest lifetime" is output in the unit of hours. Only the value 9999 (index 3600.8) is output here at the start of the filter element cycle. A continuously correcting

estimate only occurs once the remaining service life falls below 30% of the estimated total service life. Once the remaining service life reaches the value of 0, it is not counted down any further. At the latest now, the filter element should be replaced and the calculation reset.

Signal description	3.2.1 "VFL Operating data" operating data	
Status information	3.3.3 "VFL status" "VFL status"	

3.3.2.1. Signal "Rest lifetime"

Signal properties	Value	Additional information
Measurement range min.	0	[h] hours
Measurement range max.	9999	[h] hours
Resolution	-	-
Offset	-	-
Data type	REAL32 INTEGER32	Floating-point number Signed integer
Data length	32	
Mappable	TPDO	yes
Process value index	3601.1 3602.1	<i>Rest lifetime</i> REAL32 <i>Rest lifetime</i> INTEGER32
Default settings	TPDO1	Byte 0, 1, 2, 3 Rest lifetime

3.3.2.2. Signal "Operating hours"

Signal properties	Value	Additional information
Measurement range min.	0	[h] hours
Measurement range max.	According to INT32/REAL32	[h] hours
Resolution	-	-
Offset	-	-
Data type	REAL32 INTEGER32	Floating-point number Signed integer
Data length	32	
Mappable	TPDO	yes
Process value index	3601.2 3602.2	<i>Operating hours</i> REAL32 <i>Operating hours</i> INTEGER32
Default settings	TPDO2	Byte 0, 1, 2, 3 Operating hours

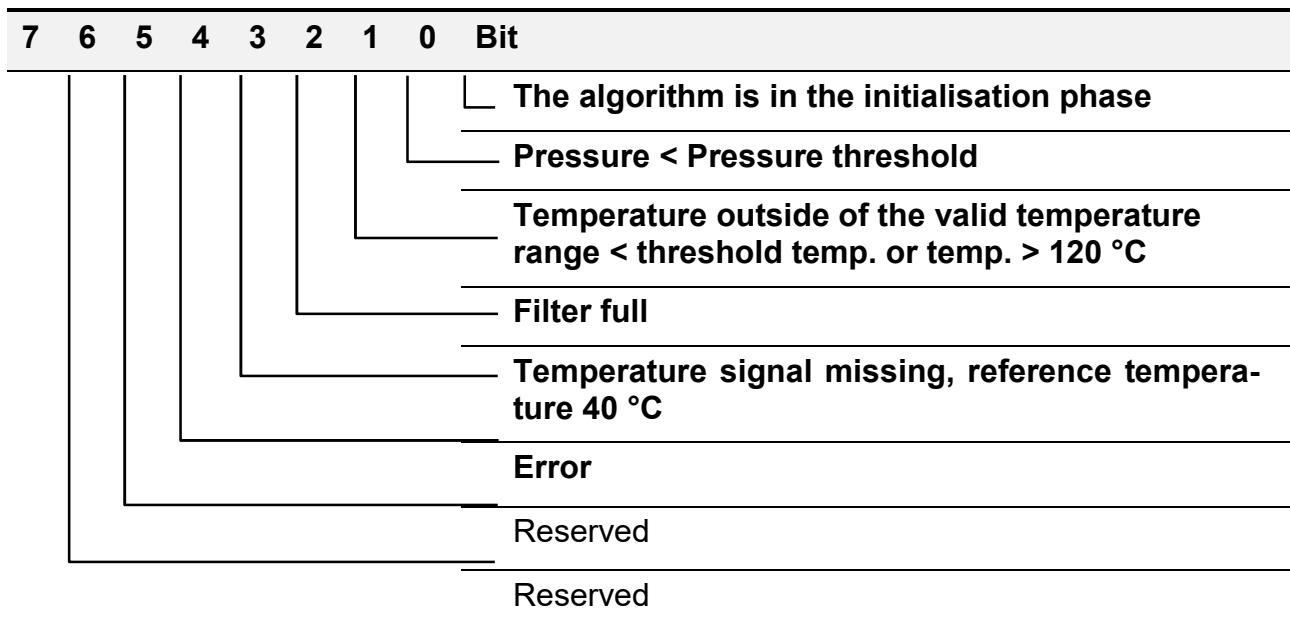
3.3.3. "VFL status"

The status of the signal "VFL status" gives information on the validity of this signal. The status is structured as a bit field. For the intended use of the measurement system, the VFL status should always be evaluated in combination with the "remaining service life" process value signal (see operating instructions).

Signal properties	Value	Additional information		
Measurement range min.	-	<i>BITFIELD</i> ; 0/0	Bit value	FALSE/inactive
Measurement range max.	-	<i>BITFIELD</i> ; 0/1	Bit value	/TRUE/active
Resolution	-			
Offset	-			
Data type	<i>UNSIGNED8</i>	<i>BITFIELD</i> see chapter 3.3.3.1		
Data length	8	Bit		
Mappable	<i>TPDO</i>			
Process value index	3611.0	<i>VFL Status</i>		
Default settings	<i>TPDO1</i>	Byte 4 VFL Status		

3.3.3.1. Design of BITFIELD "VFL status"

In the following, the meaning of the identifiers of a BITFIELD are described.



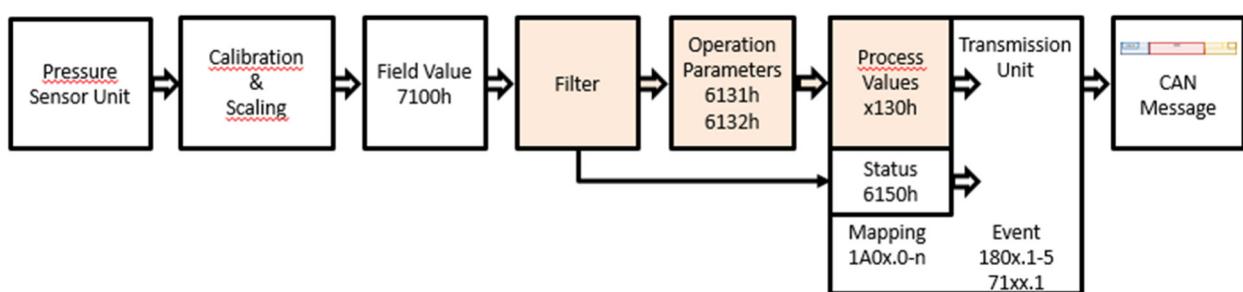
NOTICE

Status messages in the status 0, 1, 2, 3 may temporarily occur.

If status 4 is set, the connection to the temperature signal should be checked. If status 5 occurs, please contact our Support department

3.3.4. "Pressure value" signal

The Virtual Fluid Lab (VFL) provides the current process value "Pressure" (AI input PV) for reading.



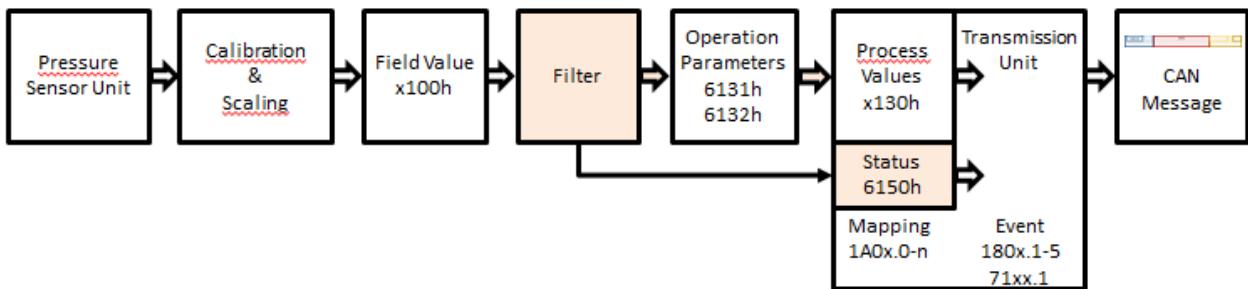
Signal description 3.2.2 "Pressure value" pressure "Pressure value" pressure

Signal properties	Value	Additional information
Measurement range min.	0	[bar] / [psi]
Measurement range max.	e.g. 600 e.g. 5000	[bar] depending on the design (0 .. 600) [psi] depending on the design (0 .. 5000)

Signal properties	Value	Additional information
Resolution	-	-
Offset	-	-
Data type	INTEGER16 REAL32 INTEGER32	Signed integer Floating point number Signed integer
Data length	16/32	Dependent on the data type used
Mappable	TPDO	yes
Process value index	7130.0 6130.0 9130.0	Pressure value INTEGER16 Pressure value REAL32 Pressure value INTEGER32
Default settings	TPDO2	Byte 4, 5 Pressure value

3.3.5. Status "Pressure value"

The status of the signal "Pressure" gives information on the validity of this signal. The status is structured as a bit field. For the intended use of the measurement system, the "Pressure" status should always be evaluated in combination with the "Pressure" process value signal (see operating instructions).

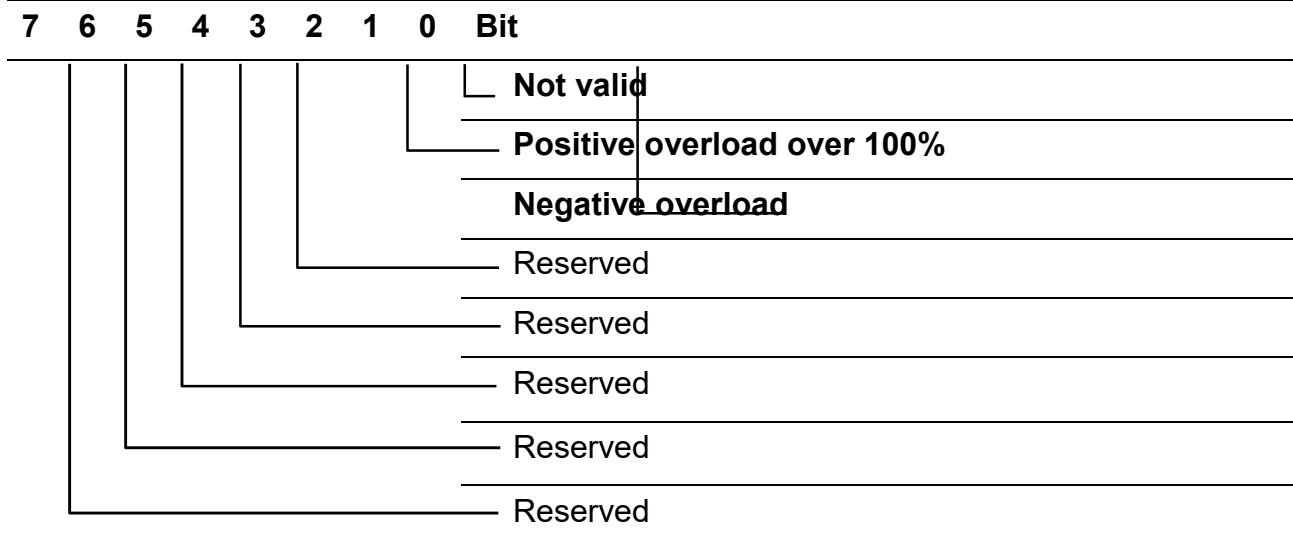


Signal properties	Value	Additional information
Measurement range min.	-	<i>BITFIELD</i> ; Bit value 0/FALSE/inactive
Measurement range max.	-	<i>BITFIELD</i> ; Bit value /TRUE/active
Resolution	-	
Offset	-	
Data type	UNSIGNED8	<i>BITFIELD</i> see chapter 3.3.3.1
Data length	8	Bit
Mappable	TPDO	yes
Process value index	6150.0	<i>Pressure status</i>

Signal properties	Value	Additional information
Default settings	-	

3.3.5.1. Design of the BITFIELD status "Pressure"

In the following, the meaning of the identifiers of a BITFIELD are described.

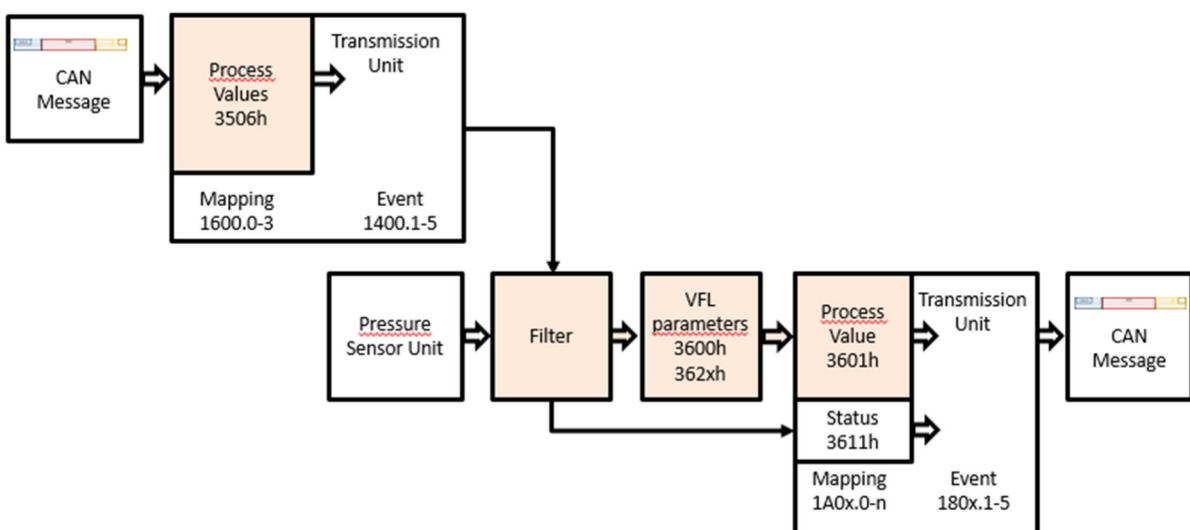


3.3.6. Input signal "external temperature value"

This measurement system provides additional signals in the form of input signals in addition to its nominal measured variable "Operating data".

A signal "External fluid temperature" is used as RPDO1 to optimise the signal "Rest lifetime".

For the application of this input signal, one or several process parameter objects should be represented ("mapped") on the RPDO1 object.



Signal description 3.2.3 *Input signal "external temperature value"*
 Fluid temperature

Signal properties	Value	Additional information
Measurement range min.	Depending on the temperature sensor	[°C] / [°F]
Measurement range max.	Depending on the temperature sensor	[°C] / [°F]
Data type	REAL32 <i>INT16</i> <i>INT32</i>	Floating point Integer Integer
Data length	32/16	Bit
Mappable	RPDO	yes
Process value index	3506 3507 3509	<i>External temperature value REAL32</i> <i>External temperature value INT16</i> <i>External temperature value INT32</i>
Default settings	RPDO1	

3.3.7. Input signal "VFL reset"

This measurement system provides additional signals in the form of input signals in addition to its nominal measured variable "Operating data".

The filter remaining lifetime calculation can be reset via an RPDO.

For the application of this input signal, the process parameter object should be mapped on the RPDO2 object.

Signal properties	Value	Additional information
Data type	INT32	Integer
Data length	32	Bit
Mappable	RPDO	yes
Process value index	35FF	VFL reset
Default settings	RPDO2	

Notice:

The reset command received with an RPDO is not acknowledged, i.e. the user does not receive any feedback as to whether the reset occurred.

The process data "Operating data" can also be reset via an SDO. See chapter 3.5.2.6 *VFL reset*.

D

3.3.8. Additional signals "Device temperature"

This measurement system used provides additional signals in the form of additional measurement channels in addition to its nominal measured variable. However, these signals do not map any process data in the conventional sense. These signals are auxiliary measured variables, which are not part of the data sheet.

Signal description 3.5.5.1 "Device temperature" signal

Status description 3.5.5.2 "Device Temperature" status

3.4. Functionally safe process data

The measurement systems described in this documentation (see chapter 1.1 Scope of applications) do not support functionally safe communication.

3.5. Parameter

In CANopen applications, parameters are comparable with the objects in an "object dictionary". Thus, all parameters of the measurement system are written to via the OD (see chapter 4.5 *The Object Dictionary*).

The parameters described in this chapter are additional devices, device-specific parameters or parameters, whose behaviour deviates from the general protocol description.

3.5.1. Configuration parameters

This chapter will explain configuration parameters, specific for this measurement system. The following description will expand or replace the listed parameter descriptions in the general protocol description, see chapter 4.5.4 *Communication profile area*.

Parameters for the visualisation and management of errors will be explained separately in an extra chapter 3.7.3 *General error management*.

Name	Index	Sub	Type	Acc	PDO
Device Type	1000h	0	UNSIGNED32	ro	

Default setting = 0, since no device profile is used

Analogue input error	1029h	3	UNSIGNED8	rw
----------------------	-------	---	-----------	----

"Error behavior "Analogue input error"; Error behaviour in case of an internal device error.

Description of the error behaviour. See chapter 4.5.4.1 Error management (General communication objects) Object: *Error behavior*

3.5.1.1. Save management and restore the VFL parameter

The measurement systems of the series VFL VD and V1/4 offer two additional indices to VFL parameters in addition to the standard parameters. See chapter *4.5.4.3 Storage and restoring (general communication objects)*.

Name	Index	Sub	Type	Acc	PDO
Save VFL parameters	1010h	5	<i>UNSIGNED32</i>	rw	
Saves all changeable VFL parameters.					
Restore VFL default parameters	1011h	5	<i>UNSIGNED32</i>	rw	
Restores all default settings of VFL parameters.					

3.5.2. Manufacturer-specific configuration parameters

This chapter describes manufacturer-specific configuration parameters of the measurement system. The following descriptions will expand on or replace the listed parameter descriptions in the general protocol description.

This range of parameter is used in different forms in the measurement system. The management of the node ID and baud rate, the stocking of default settings for the DS 404 process value configuration as well as the management of additional values of our measurement systems.

The generally applicable manufacturer-specific parameters can be found in chapter *4.5.5 manufacturer-specific profile area*.

3.5.2.1. Management of node ID and baud rate

The measurement systems of the series VFL VD and V1/4 offer, in addition to LSS, two methods for managing the node ID. For reasons of compatibility to our predecessor products, the objects 2001h and 2002h are still available. In addition, the currently standard process used at HYDAC Filtertechnik is made available via the objects 2003h and 2004h. See chapter *4.5.5.1 Node ID and Baud rate*.

Both processes are synchronised with each other so that changes after one of the two processes are copied to the objects of the respective other process.

Name	Index	Sub	Type	Acc	PDO
Node ID	2001h		<i>UNSIGNED32</i>	rw	

Compatibility with the series HDA 4000/7000.

To change the node ID, this must be written into the object together with the character string "set". After the change is made, this must be permanently saved, See *StoreLSSParameter* and the measurement system must be restarted.

Example: setting the node ID 5h via "*SDO download*"

Byte 4	Byte 5	Byte 6	Byte 7
<data>	<data>	<data>	<data>
Node-ID	"s"	"e"	"t"
05h	73h	65h	74h

Baud rate	2002h	<i>UNSIGNED32</i>	rw
------------------	--------------	-------------------	----

Compatibility with the series HDA 4000/7000.

To change the node ID, this must be written into the object together with the character string "set". After the change is made, this must be permanently saved, See *StoreLSSParameter* and the measurement system must be restarted.

Example: setting the *Baud rate 125 bit/s* (Index 4h) via "*SDO download*"

Byte 4	Byte 5	Byte 6	Byte 7
<data>	<data>	<data>	<data>
Baudrate	"s"	"e"	"t"
04h	73h	65h	74h

Node ID	2003h	<i>ARRAY</i>
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Active node-ID	01	<i>UNSIGNED8</i>	ro
-----------------------	-----------	------------------	----

Pending node-ID	02	<i>UNSIGNED8</i>	rw
------------------------	-----------	------------------	----

Current process for changing the node ID. See chapter 4.5.5.1 *Node ID and Baud rate*.

Baud rate	2004h	<i>ARRAY</i>
------------------	--------------	--------------

Active baudrate	01	<i>UNSIGNED16</i>	ro
------------------------	-----------	-------------------	----

Pending baudrate	02	<i>UNSIGNED16</i>	rw
-------------------------	-----------	-------------------	----

Current process for changing the baud rate. See chapter 4.5.5.1 *Node ID and Baud rate*.

3.5.2.2. Description of the manufacturer-specific parameters

The device provides the plant-side default of the parameters to configure the "Pressure" process value in the index range 21xxh. These values are copied into the object entries 6xxxh, 7xxxh and 9xxxh when resetting the measurement system to default settings. See chapter 4.5.4.3 *Storage and restoring (general communication objects)*.

Name	Index	Sub	Type	Acc	PDO
AI default input scaling 1 PV	2121h		ARRAY		
AI default input scaling 1 PV 1		01	INTEGER32	ro	
Default setting; lower value for scaling the process value for the "Pressure" signal. Default for the object entries 6121h, 7121h, 9121 h when calling up the function " <i>Restore default parameters</i> ".					
AI default input scaling 2 PV	2123h		ARRAY		
AI default input scaling 2 PV 1		01	INTEGER32	Ro	
Default setting; upper value for scaling the process value for the "Pressure" signal. Default for the object entries 6123h, 7123h, 9123 h when calling up the function " <i>Restore default parameters</i> ".					
AI default physical unit PV	2131h		ARRAY		
AI default physical unit PV 1		01	UNSIGNED32	Ro	
Default setting; physical unit for the "Pressure" signal Default for the object input 6131h when calling up the function " <i>Restore default parameters</i> ".					
AI default decimal digits PV	2132h		ARRAY		
AI default decimal digits PV 1		01	UNSIGNED8	ro	
Default setting; number of decimal places of the "Pressure" signal Default for the object input 6132h when calling up the function " <i>Restore default parameters</i> ".					
Limitation FV	2300h		ARRAY		
AI Limitation FV 1		01	UNSIGNED8	rw	
Limitation of the "Pressure" field value. The limitation serves to avoid measured values below the lower measuring range limit due to tolerances, long-term drift, cavitation and similar effects.					
Value: 0	no limitation.				
1	the field value and process value derived from this is limited to the lower measuring range limit				

3.5.2.3. Description of the manufacturer-specific parameters

Manufacturer-specific parameters determine the function of the algorithm for calculating the remaining filter life.

Name	Index	Sub	Type	Acc	PDO
VFL parameter	3600h		RECORD		
Parameter 1		1	REAL32	rw	
Pressure threshold from which the algorithm is active					
Default setting: e.g. 0.5 [bar] at measured variable of 5 [bar]. (Depending on the sensor's measured variable)					
Parameter 2		2	REAL32	rw	
Temperature threshold from which the algorithm is active					
Default setting: 35 [°C]					
Parameter 3		3	REAL32	rw	
Final pressure value at which the filter element is considered blocked					
Default setting depending on the measured variable, e.g. 5 [bar] at measured variable VD 5 or V1/4 5					
Parameter 4		4	REAL32	rw	
Viscosity of the operating medium used at 40°C in [cSt]					
Default setting: 45					
Parameter 5		5	REAL32	rw	
Viscosity of the operating medium used at 100°C in [cSt]					
Default setting: 6,7					
Parameter 6		6	REAL32	const	
Reserved					
Parameter 7		7	REAL32	const	
Reserved					
Parameter 8		8	REAL32	const	
Reserved					
Parameter 9		9	REAL32	rw	
Maximum service life after which the filter element is detected as full					
Default setting: 6000					
Parameter 10		10	REAL32	rw	
Duration of the sensor breaking-in phase in operating hours					
Default setting: 50					

Parameter 11	11	REAL32	rw
Sampling rate of the pressure signal in seconds			
Default setting: 3			
Parameter 12	12	UNSIGNED16	const
Reserved			
Parameter 13	13	UNSIGNED16	const
Reserved			
Parameter 14	14	INTEGER16	rw
Number of measured values per measurement cycle			
Default setting: 500			
Parameter 15		BOOLEAN8	const
Reserved			

3.5.2.4. Description of the manufacturer-specific parameters for "Device temperature"

The device provides the plant-side default of the parameters to configure the "Device temperature" signal in the index range 4x00h.

Name	Index	Sub	Type	Acc.	PDO
MS input MV 1	4610	1	REAL32	ro	TP
	4710	1	INT16	ro	TP
	4910	1	INT32	ro	TP

Current signal value: device temperature

Signal description 3.3.8 Additional signals "Device temperature"

Signal characteristics 3.5.5.1 "Device temperature" signal

MS input MV 2	4610	2	REAL32	ro	TP
	4710	2	INT16	ro	TP
	4910	2	INT32	ro	TP

Example for an eventually existing manufacturer-specific measurement channel.

Name	Index	Sub	Type	Acc.	PDO
MS input scaling 1 MV 1	4611	1	REAL32	ro	
	4711	1	INT16	ro	
	4911	1	INT32	ro	

Lower measuring range limit of the device temperature. The value indication is represented in the unit of the measurement channel:

-25 -25 °C as the lower temperature measurement range

MS input scaling 2 MV 1	4612	1	REAL32	ro	
	4712	1	INT16	ro	
	4912	1	INT32	ro	

Upper measuring range limit of the device temperature. The value indication is represented in the unit of the measurement channel:

100 +100 °C as the upper temperature measurement range

MS status	4613	1	UNSIGNED8	ro	TP
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Status information of the device temperature

Status characteristics 3.5.5.2 "Device Temperature" status

MS decimal digits MV 1	4614	1	UNSIGNED8	rw	
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Numbers of decimal places of the device temperature

MS physical unit MV 1	4617	1	UNSIGNED32	ro	
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Physical unit of the device temperature. The unit will be provided as SI unit according to CiA 303-2.

Standard physical units are:

002D0000h °C

00AC0000h °F

3.5.2.5. Description of the manufacturer-specific parameters for "external fluid temperature"

The device provides the plant-side default of the parameters to configure the "Fluid temperature" signal in the index range 3x00h.

Name	Index	Sub	Type	Acc	PDO
External temperature decimals	3500h	0	UNSIGNED8	rw	

This entry specifies the number of decimal places of the received temperature signal. Example: value on 1 means an input of 370 is interpreted as 37.0 °C.

Default setting: = 0

External temperature unit	3501h	0	UNSIGNED32	rw
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This entry specifies the physical unit of the "Temperature" signal.

0x002d000 = 2949120 = °C (default setting)

0xac0000 = 11272192 = °F

3.5.2.6. VFL reset

The process data "Operating data" (index 3601h) can be reset in this object.

Name	Index	Sub	Type	Acc	PDO
VFL reset	35FFh	0	UNSIGNED32	WO	

Please note that the filter remaining service life algorithm must be restarted after a filter element has been changed. For this purpose, the value 0x00736572 is written onto index 0x35FF. The remaining service life now again shows the value 9999 and the operating hours shows the value 0.

If an invalid signature is written on the entry 0x35FF, 0x00, the device responds with the abort code *CanNotTransferOrNotStored* (0x08000020)

Notice:

The process data "Operating data" can also be reset via an RPDO2. See chapter 3.3.7 *Input signal "VFL reset"*

3.5.3. Device profile-specific parameters

VFL VD and V1/4 measurement systems support the device profile "CiA 404 Device profile for measuring devices and closed-loop controllers".

The process data transmitted during reset to default settings of the measurement system are described in chapter 3.1.1 *CANopen default settings*.

Certain objects have a generally applicable and device profile-specific section. Such objects (as for example the object *Error behavior*) only describe the section which is defined via the device profile. The definitions which are generally applicable are described in chapter 4.5.4 *Communication profile area*.



The objects from the device profile CiA 404 "Device profile for measurement devices and closed-loop controllers" which are not listed below, are not supported by the measurement system.

The device profile documentation version, serving as a basis for the implementation of the measurement system, can be taken from the operation manual.

Name	Index	Sub	Type	Acc	PDO
Device Type	1000h	0	UNSIGNED32	ro	
Bit 0-15	contains the device profile	019Ah → CiA 404			
Bit 16-31	contains profile-specific information	0002h → Analogue input			
Error register	1001h	0	UNSIGNED8	ro	TP
Device error status	This error status is also part of the EMCY message, see chapter 4.4.5 EMCY.				
Bit 0	Generic error				
Bit 4	Communication error				
Bit 7	Manufacturer specific				
As soon as a communication error or manufacturer-specific error has occurred, the generic error is set.					
Error behavior	1029h		ARRAY		
For general information, see chapter 4.5.4.1 Error management (General communication objects).					
Communication error	1029h	1	UNSIGNED8	rw	
Device behaviour in case a communication error occurs.					
Analogue input error	1029h	3	UNSIGNED8	rw	
"Error behavior "Analogue input error"; Error behaviour in case of an internal device error.					
Description of the error behaviour. See chapter 4.5.4.1 Error management (General communication objects) Object: <i>Error behavior</i>					
AI input FV	6100h	1	REAL32	ro	TP
	7100h	1	INTEGER16	ro	TP
	9100h	1	INTEGER32	ro	TP
The device provides the current field value <i>Analogue Input Field Value 1</i> .					
0 % = 0; 100 % = 5000					
This object provides the converted value of an analogue input, which is not yet scaled to the physical unit of the measured variable.					
AI Sensor Type	6110h	1	UNSIGNED16	ro	
0x5a = 90 = Sensor type pressure					
AI autocalibration	6111h	1	UNSIGNED32	WO	
Sets the scaling unit so that the process value "Pressure" = 0 (calibration, absolute)					
AI operating mode	6112h	1	UNSIGNED8	const	
1 = Normal Operation					

Name	Index	Sub	Type	Acc	PDO
AI ADC sample rate	6114h	1	UNSIGNED32	rw	

Sampling rate in microseconds: $0x3e8 = 1000$

The sampling rate determines the interval at which a new measured value is processed. This time has an impact, especially in connection with the filter constant and the trigger handling.

AI input scaling 1 FV	6120h	1	REAL32	ro
	7120h	1	INTEGER16	ro
	9120h	1	INTEGER32	ro

Our value of the field value. This is used to scale the "Pressure" process value.

Value: 0

AI input scaling 1 PV	6121h	1	REAL32	ro
	7121h	1	INTEGER16	ro
	9121h	1	INTEGER32	ro

Our value to scale the process value "Pressure"

value: 0 = 0 bar

AI input scaling 2 FV	6122h	1	REAL32	ro
	7122h	1	INTEGER16	ro
	9122h	1	INTEGER32	ro

Upper value of the field value. This is used to scale the "Pressure" process value.

Value: 5000

AI input scaling 2 PV	6123h	1	REAL32	ro
	7123h	1	INTEGER16	ro
	9123h	1	INTEGER32	ro

Upper value for scaling the process value "Pressure"

value: e.g. 600 = for sensor with a measuring range up to 600 bar

AI input offset	6124h	1	REAL32	rw
	7124h	1	INTEGER16	rw
	9124h	1	INTEGER32	rw

Offset for scaling 0

AI autozero	6125h	1	UNSIGNED32	WO
	7125h	1	UNSIGNED32	WO

Sets the offset so that the PV (process value) results in 0 (relative output)

write $0x6f72657a$

Name	Index	Sub	Type	Acc	PDO
AI input PV	6130h	1	UNSIGNED32	ro	TP
	7130h	1	INTEGER16	ro	TP
	9130h	1	INTEGER32	ro	TP

Current process value "Pressure" [bar] / [psi] – depending on the design

Signal description 3.2.2 "Pressure value" pressure

Signal characteristics 3.3.4 "Pressure value" signal

Status characteristics 3.3.5 Status "Pressure value"

AI physical unit PV	6131h	1	UNSIGNED32	rw
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The following physical units of the process value can be set:

0x004e0000 = 5111808 = bar

0xab0000 = 11206656 = psi

Note:

A unit change automatically leads to a change in the scaling values of the process value 6121h and 6123h.

AI decimal digits PV	6132h	1	UNSIGNED8	rw
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Decimal places

The transferred integer value 1234 with 2 decimal places means 12.34.

This applies to all 16 bit and 32 bit signed integers, such as: (indices 71xxh, 91xxh)

Example: Sensor sends 0-2500 digits. Decimal places = 1 means 0-250 bar

If you convert to 2 decimal places, you get 0-25.00.

If you then change 6123h (AI Scaling 2 PV 1) from 2500 to 25000, you again get 0-250.00 bar!

AI interrupt delta input PV	6133h	1	REAL	rw
	7133h	1	INTEGER16	rw
	9133h	1	INTEGER32	rw

This entry is used to control the PDO transmission.

If the current *ProcessValue* deviates from the last one transmitted by more than the *InterruptDeltaPV*, it is transmitted. This prevents constant transmissions where the contents are very similar. So that this mechanism is activated, *TransmissionType* must be set to *ProfileSpecific*. See chapter 3.6.3 device-specific PDO events

If *InterruptDeltaPV* is set to 0, then this mechanism is deactivated.

AI interrupt lower limit input PV	6134h	1	REAL32	rw
	7134h	1	INTEGER16	rw
	9134h	1	INTEGER32	rw

Name	Index	Sub	Type	Acc	PDO
<p>This entry serves to control the PDO transmission If the current <i>ProcessValue</i> falls below the <i>InterruptLowerLimit</i> limit value, it is transmitted. In order to avoid constant transmissions because the measured value is fluctuating around the limit value, the actual value must rise above the limit again by at least 1% of the preset measuring range, before another transmission is made for a fall in value. In order for this mechanism to be activated, <i>TransmissionType</i> must be set to <i>ProfileSpecific</i>. See chapter 3.6.3 device-specific PDO events</p>					
<p>AI interrupt upper limit input PV</p>					
<p>6135h 1 REAL32 rw</p>					
<p>7135h 1 INTEGER16 rw</p>					
<p>9135h 1 INTEGER32 rw</p>					
<p>This entry serves to control the PDO transmission If the current <i>ProcessValue</i> exceeds the <i>InterruptUpperLimit</i> limit value, it is transmitted. In order to avoid constant transmissions because the measured value is fluctuating around the limit value, the actual value must exceed the limit again by at least 1% of the preset measuring range, before another transmission is made for this event. In order for this mechanism to be activated, <i>TransmissionType</i> must be set to <i>ProfileSpecific</i>. See chapter 3.6.3 device-specific PDO events</p>					
<p>AI interrupt hysteresis input PV 1</p>					
<p>6136h 1 REAL32 rw</p>					
<p>7136h 1 INTEGER16 rw</p>					
<p>9136h 1 INTEGER32 rw</p>					
<p>Hysteresis to lower and upper value pressure Default: always 1% of the upper limit for pressure (e.g. 6 for the sensor with 600 bar)</p>					
<p>AI span start</p>					
<p>6148h 1 REAL32 rw</p>					
<p>7138h 1 INTEGER16 rw</p>					
<p>9138h 1 INTEGER32 rw</p>					
<p>Default: 0 (sensor lower limit) This value is adjustable. If the current <i>ProcessValue</i> falls below the limit value, a bit is set in the status. See chapter 3.3.3.1 <i>Design of BITFIELD "VFL status"</i>.</p>					
<p>AI span end</p>					
<p>6149h 1 REAL32 rw</p>					
<p>7139h 1 INTEGER16 rw</p>					
<p>9139h 1 INTEGER32 rw</p>					
<p>Default: pressure sensor upper limit (e.g. 600 for the sensor with 600 bar) This value is adjustable. If the current <i>ProcessValue</i> exceeds the limit value, a bit is set in the status. See chapter 3.3.3.1 <i>Design of BITFIELD "VFL status"</i>.</p>					

Name	Index	Sub	Type	Acc	PDO
AI status	6150h	1	UNSIGNED8	ro	TP

See chapter 0

Signal "Operating hours"

Signal properties	Value	Additional information
Measurement range min.	0	[h] hours
Measurement range max.	According to INT32/REAL32	[h] hours
Resolution	-	-
Offset	-	-
Data type	REAL32 INTEGER32	Floating-point number Signed integer
Data length	32	
Mappable	TPDO	yes
Process value index	3601.2 3602.2	<i>Operating hours</i> REAL32 <i>Operating hours</i> INTEGER32
Default settings	TPDO2	Byte 0, 1, 2, 3 Operating hours

"VFL status"

AI filter type	61A0h	1	UNSIGNED8	rw
Filter type Default value 0 = no filter; 1 = Moving average (deep pass filter); 2 = Repeating average (arithmetic average)				
AI filter constant	61A1h	1	UNSIGNED16	rw
Filter constant				

3.5.4. Process value parameter

This chapter describes all manufacturer-specific process value parameters. The following descriptions will expand on or replace the listed parameter descriptions in the general protocol description.

In this case, the manufacturer-specific process value parameters are used to calculate the remaining service life.

3.5.4.1. Number of the process data object supported by the device.

- **TPDO "sent process data"** **2**
- **RPDO "received process data"** **2**

3.5.4.2. Description of manufacturer-specific process value parameters



The cross-references are indicated as shown below:

Signal description Reference to the chapter which gives a short explanation of the relevant signal. A more detailed description can be found in the related operating manual.

Signal characteristics Refers to the chapter describing the characteristics necessary for evaluation, e.g. evaluation of the measuring range.

Status information Refers to the chapter which explains the exact structure of a status value belonging to a signal (mainly a BITFIELD).

Name	Index	Sub	Type	Acc	PDO
VFL operating data	360x		RECORD		
Amount of the provided operating data: 2					
Index 3601 as REAL32					
Index 3602 as INT32					
Rest lifetime	3601	1	REAL32	ro	TP
	3602	1	INT32	ro	TP
Current remaining lifetime in hours					
Default setting: initial value 9999					
Signal description 3.2.1 "VFL Operating data" operating data					
Status characteristic values 3.3.3 "VFL status"					
Signal characteristic values <i>Signal "Rest lifetime"</i>					
Operating hours	3601	2	REAL32	ro	TP
	3602	2	INT	ro	TP
Current operating hours in hours					
Default setting: initial value 0					
Signal description 3.2.1 "VFL Operating data" operating data					
Signal characteristic values <i>Signal "Operating hours"</i>					
VFL status	3611		UNSIGNED8	ro	TP
Status of the signal "Rest lifetime"					
Signal description 3.2.1 "VFL Operating data" operating data					
Status characteristic values 3.3.3 "VFL status"					
Signal characteristic values <i>Signal "Rest lifetime"</i>					

Pressure value	7130	INTEGER16	ro	TP
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Current pressure in bar or psi

Signal description 3.2.2 "Pressure value" pressure

Signal characteristic values 3.3.4 "Pressure value" signal

3.5.4.3. Description of the "External temperature value" parameter

The device provides the plant-side default of the parameters to configure the "Fluid temperature" signal in the index range 3x00h.

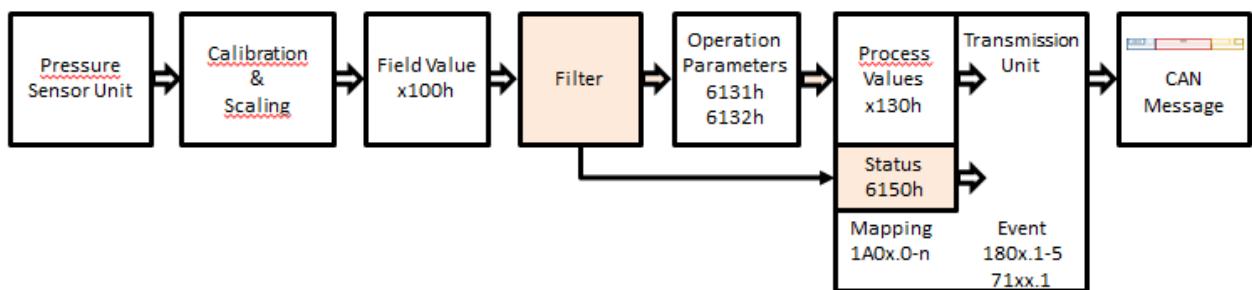
Name	Index	Sub	Type	Acc	PDO
External temperature value	3506h		REAL32	rww	RP
	3507h		INT16	rww	RP
	3509h		INT32	rww	RP

External fluid temperature as an input signal in °C or °F

Signal description 3.2.3 Input signal "external temperature value" temperature
Fluid

Signal characteristic values 3.3.6 Status "Pressure value"

The status of the signal "Pressure" gives information on the validity of this signal. The status is structured as a bit field. For the intended use of the measurement system, the "Pressure" status should always be evaluated in combination with the "Pressure" process value signal (see operating instructions).



Signal properties	Value	Additional information
Measurement range min.	-	BITFIELD; Bit value 0/FALSE/inactive
Measurement range max.	-	BITFIELD; Bit value /TRUE/active
Resolution	-	
Offset	-	
Data type	UNSIGNED8	BITFIELD see chapter 3.3.3.1
Data length	8	Bit

Mappable	TPDO	yes
Process value index	6150.0	<i>Pressure status</i>
Default settings	-	

3.5.4.4. Design of the BITFIELD status "Pressure"

In the following, the meaning of the identifiers of a BITFIELD are described.

7 6 5 4 3 2 1 0 Bit

Not valid
Positive overload over 100%
Negative overload
Reserved

Input signal "external temperature value"

3.5.4.5. Description of the parameter "VFL reset"

After every filter element change, the filter remaining service life calculation must be reset. This is done via the parameter "VFL reset".

Chapter 3.3.7 *Input signal "VFL reset"* can be reset via an RPDO2

Chapter 3.5.2.6 *VFL reset* can be reset via an SDO

3.5.5. Additional manufacturer-specific measurement channels

The VFL VD and V1/4 measurement system series do not provide any additional internal manufacturer-specific measurement channels.

3.5.5.1. "Device temperature" signal

The additional signal of these measurement systems is provided as an auxiliary signal.

Signal properties	Value	Additional information
Measurement range min.	-25 -13	[°C] for sensors with a bar variant [°F] for sensors with a psi variant
Measurement range max.	100 212	[°C] for sensors with a bar variant [°F] for sensors with a psi variant
Resolution	1	[°C/Bit] or [°F/Bit] <u>Note:</u> only applies to INT16 / INT32 with decimal place = 0
Offset	-	-
Data type	<i>REAL32</i>	Floating point
Data length	32	Bit
Mappable	<i>TPDO</i>	ro
Process value index	4610.1 4710.1 4910.1	<i>Device temperature</i> REAL32 <i>Device temperature</i> INTEGER16 <i>Device temperature</i> INTEGER32
Default settings	-	-

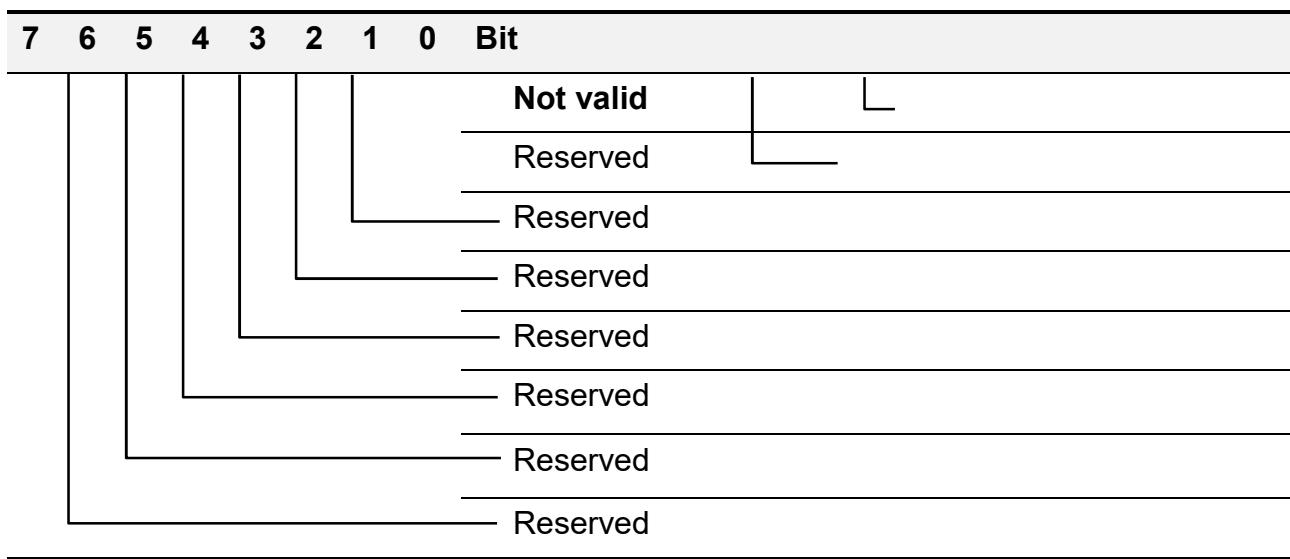
3.5.5.2. "Device Temperature" status

The status of the "Device temperature" gives information on the validity of this signal. The status is structured as a bit field.

Signal properties	Value	Additional information
Measurement range min.	-	BITFIELD; Bit value 0 /FALSE/inactive
Measurement range max.	-	BITFIELD; Bit value 1 /TRUE/active
Resolution	-	
Offset	-	
Data type	<i>INSIGNED8</i>	BITFIELD
Data length	8	Bit
Mappable	<i>TPDO</i>	yes
Process value index	4613.1	Device temperature status
Default settings	-	-

Design of BITFIELD status "Device temperature"

In the following, the meaning of the identifiers of a BITFIELD are described.
The bit 0 is set if the value is not valid due to an error in the measured value detection.



3.6. Events

Events are information which can occur either spontaneously or time-controlled. They generally contain additional information on the current device status or of its status change.

3.6.1. Error messages

The following table describes the EMCY error numbers (*EMCY-EC*) supported and sent by the measurement system. The general description of the function principle and the structure of the error messages is explained in chapter 4.4.5 *EMCY*.

The error register (see 4.4.5 *EMCY*) transmitted via byte 2 of the EMCY is described below:

- General
 - Object: *Error Register*
 - Chapter: 4.5.4.1 *Error management (General communication objects)*
- Manufacturer-specific
 - Chapter: 3.5.1 *Configuration parameters*

EMCY-EC	Error designation	Description
0000h	No error	Device reports return to error-free operation
	Manufacturer-specific	0
8120h	CAN in "error passive"	<p>The device internal CAN controller has changed to the CAN status "error passive".</p> <p>This error can occur during normal network operation and disappear again; which is evidence for problems in the network.</p>

EMCY-EC	Error designation	Description
	<i>Manufacturer-specific</i>	0
8140h	Recover from Bus-off	The device internal CAN controller has changed to the CAN error status "bus-off". Evidence for problems in the network.
	<i>Manufacturer-specific</i>	0
FF00h	device-specific error	General device-specific error The occurred error is specified more in detail in the manufacturer-specific section of the error message.
	<i>Manufacturer-specific</i>	Low-Word of the <i>Manufacturer status register</i>

Example for an EMCY error message:

ID [hex]	Daten [hex]
081	20 81 11 00 00 00 00 00
EMCY	[8120, 11] Manufacturer spec.

EMCY-EC 8120h CAN in error passive

Error Register 81h (10000001b) → Bit 0 a. 4 set: "Generic" & "Communication"

Manufacturer-specific 0000h general error

3.6.2. Device state

The measurement system supports the heartbeat protocol; for a description, see chapter 4.4.3 *Heartbeat*.

3.6.3. device-specific PDO events

The device supports the device profile-specific results in CiA 404. See ***AI interrupt delta input PV*** (Indices: x133h, x134h, x135h, x136h)

Device profile-specific results are only active with an active "Transmission type" 255. See ***Transmission type***.

General information on PDO events:

- 4.5.4.6 *RPDO communication parameter*
- 4.5.4.8 *TPDO communication parameter*
- 4.6.2.1 *Event driven*

3.7. Error management

Errors are recognised, administrated and provided by the measurement system in several different ways. On the one hand, there are errors occurring during processing of the process

data and on the other hand, there are general device errors. All kinds of errors are provided as parameters (objects in the OD) and can be read out at any time; see chapter 4.6.1 SDO.

3.7.1. Error behaviour

It depends on the error type and the device configuration of the error behaviour, how the measurement system will react to an occurring error.

For process data errors, a corresponding error marker is set in the associated status. See chapter 3.3.3 "VFL status".

In addition, the measurement system changes its operating status (see chapter 4.4 Network Management) depending on the setting of the error behaviour. See *Analogue input error*.

In the case of general device errors, such as communication or configuration errors, it is possible to configure which operation mode the measurement system should take on if an error occurs via the parameter **Error behavior**.

3.7.2. Process data error

The process data errors are made available as status signals. The signals should always be evaluated together with their related process values.

The status signal 3.3.3 "VFL status" should always be evaluated together with the following process values:

- 0
-
- *Signal "Operating data"*

The status signal 3.3.5 Status "Pressure value" should always be evaluated together with the following process values:

- 3.3.4 "Pressure value" signal

3.7.3. General error management

In addition to process-data related status errors, general error objects are also provided by the measurement system. The characteristics or additions diverging from the general implementation are described in the following.

Supported:

- General error register: *Error register*
- Specific error register: *Manufacturer status register*
- Error memory: *Pre-defined error field*

Name	Index	Sub	Type	Acc	PDO
Manufacturer status register	1002h	0	UNSIGNED32	ro	TP
Describes the device status					
Error codes					
F: Device is functional for the customer					
E: Error is sent via EMCY message					
Bit no.	Value	F	E	Description	NOTICE
0	0001	X	X	Error while loading the user settings	This error can only be removed by storing/restoring and subsequent reinitialisation of the device (Power off / Power on).
1	0002			Error in loading the factory settings	Device always starts in production mode
2	0004			reserved	
3	0008			Error while loading the hardware settings	Device always starts in production mode
4	0010	X	X	Error while detecting the pressure value	The pressure value is faulty (VFL status bit 5 is set)
5	0020	X	X	Error recording fluid temperature	The fluid temperature value is faulty
6	0040	X	X	Error loading the VFL settings	This error can only be rectified by reinitialisation of the device (Power off / Power on) or by resetting the filter service life calculation (VFL status bit 5 is set)
7	0080			reserved	
8	0100	X	X	Overflow of the receive queue of the CAN controller	This error can only be removed by reinitialisation of the device (Power off / Power on)
9 .. 13	-			Reserved	
14	4000			The CAN node cannot be started	Device always starts in production mode

Bit no.	Value	F	E	Description	NOTICE			
15	-			Reserved				
16	10000	X		Error loading the printed circuit board settings	Not sent with an EMCY message			
Name				Index	Sub	Type	Acc	PDO
Pre-defined error field				1003h		ARRAY		
General see chapter 4.5.4.1 <i>Error management (General communication objects)</i> .								
Standard error field 1 ...				1003h	1 [1003.0]	... UNSIGNED32	ro	
General see chapter 4.5.4.1 <i>Error management (General communication objects)</i> .								

3.7.4. Error events

Errors causing the change of the general error register (see object: *Error register*) are also sent as a particular error event; see chapter:

- 3.6.1 *Error messages*
- 4.4.5 *EMCY*

3.8. LSS Protocol support

All measurement systems of the VFL VD and V1/4 series support the LSS protocol in the way described in chapter 4.7 *Layer setting services (LSS) Protocol*.

4. Protocol description CANopen

Below, please find the description of the CANopen protocol used by the measurement system. Device-specific settings and behaviour are described in the different subsections in chapter 3 *Product interface*.

4.1. General

The various original documents which have been used for the implementation of the device can be found in the operation manual.



The following description makes **no claim** to be complete, its only aim is to facilitate work for the user with the CANopen device by HYDAC Filtertechnik GmbH. In the case of further information should be required, the documents of the CiA, which are referred to in this document and in the related user manual, are applicable.

4.2. Hardware properties

CAN is a Bus system. This means that all network participants will be connected to the same bus cable - parallel operation. On the contrary, the Ethernet, which is usually used in office communication, only connects one participant with one other at one time. For the connection between several participants, additional hardware, i.e. a switch, is necessary. This effort is **not necessary** using CAN. How the network has to be organised is described in the following chapter 4.2.3 *Topology*.

CAN mainly has 2 signal lines: CAN-H and CAN-L. Data transmission is performed via these two lines, see chapter 4.2.2 *Signal level*.

Each **network participant is equal** in a CAN network, which means that each of the participants is able and allowed to send messages. If a participant sends, all the others receive the message and decide on their own if it is relevant for them or not.

In the case of a **competing access** of several participants, CAN will start **prioritising messages**. This will avoid collisions to occur, as in other systems. The prioritising of messages is carried out via the CAN ID, where the CAN ID 0 has the highest priority, see chapter 4.3.2 *Meaning of the CAN ID*.

A network participant is not allowed to send, before a message has not been transmitted completely. If two participants start sending at the same time, the participant having the higher priority message will always "win". The structure of a message is described in chapter 4.3.1 *Structure principle of a CAN data message*.

Transmission of information is bit-oriented in CAN networks and has a recessive and a dominant signal status. The dominant signal status is enabled to overwrite the recessive one. As one participant, which is sending, will directly read back each written bit, it can also recognise its own message has been overwritten, and will immediately discontinue further data transmission.

The participant who has interrupted transmission, will try to reinitialise its transmission after the higher prioritised message has been sent. In doing this, no messages will be lost.

4.2.1. Wire connections

CAN does not require any complicated wire connections. For the connection of the network participants one drilled pair of wires should be used. The pair of wires serves for the transmission of the signals CAN-H and CAN-L. Non-drilled cables should be avoided. The recommended core diameter depends on the length and has an average between 0.34 and 0.6 mm².

Almost all CAN connections provide an additional CAN_GND und CAN_SHLD. CAN_GND corresponds with a signal mass and can be used to bring the reference potential of the network participants to one common level. CAN_SHLD serves as a connection of a shielding for the signal line. Generally, the CAN signal lines do not require any shielding.



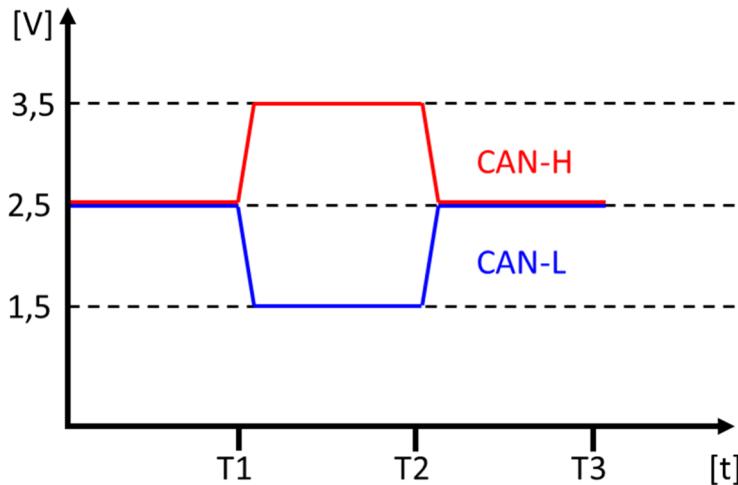
Potential loss between network participants should be avoided. They may damage the wire connections or the electronic unit. The connection CAN_GND is not intended for equipotential bonding.

4.2.2. Signal level

For the transmission, a symmetric voltage signal is used. This signal type has no direct reference with a signal mass, but only the voltage difference between both signal lines will be evaluated. This type of signal transmission has significant benefits in the case of interfering signals, as these will affect both signal lines equally and will be excluded at the subtraction.

In the event of a dominant signal the signal line CAN-H will move to a higher voltage level and the CAN-L signal line will move to a lower voltage level.

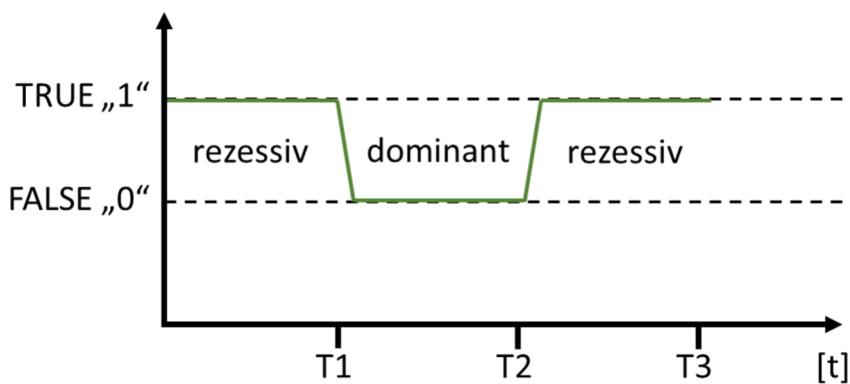
4.2.2.1. Diagram signal level CAN-high-speed



- In the event of a recessive signal status, the difference voltage is ~ 0V.
- In the event of a dominant signal status, the difference voltage is ~ 2V.

This diagram explains why a dominant signal status is able to overwrite a recessive one. This mechanism is used for the prioritisation of messages; see chapters 4.2 Hardware properties and 4.3.2 Meaning of the CAN ID.

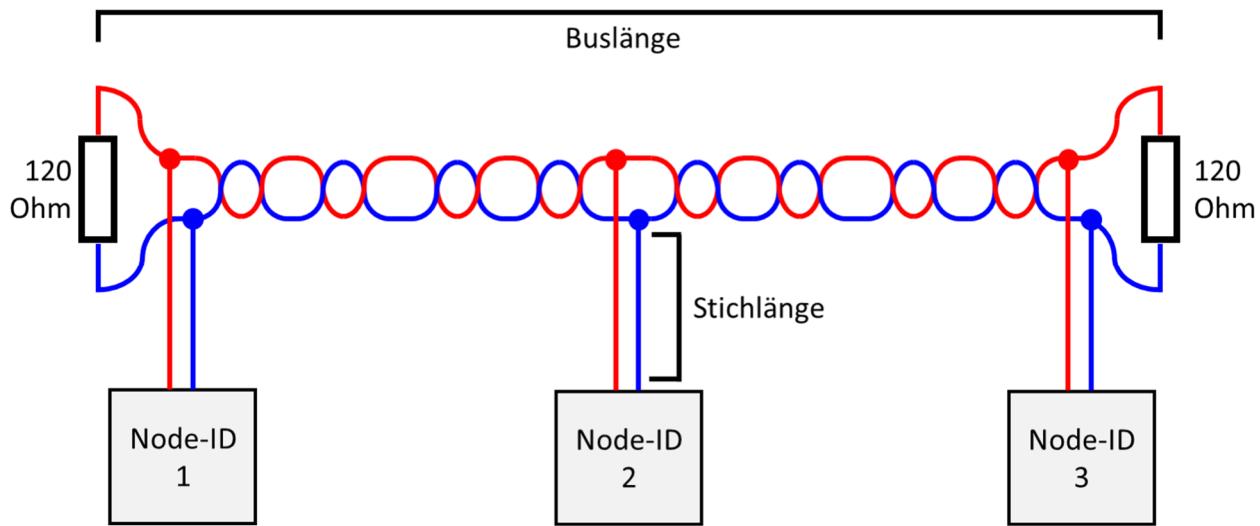
4.2.2.2. Diagram signal logic



4.2.3. Topology

As explained in chapter 4.2 *Hardware* properties, the topology of CAN is the Bus. This means, the CAN has a direct connection line, which reaches from the first to the last participant. Each individual participant is directly connected to the signal lines **CAN-H** and **CAN-L**. At both ends of the main bus (the longest direct connection line) the bus line has to be terminated using a resistance of 120 Ohm.

For the length of the main bus as well as for the length of the individual stub cable between the bus and the network participants, the maximum line lengths, described in chapter 4.2.5 *Transmission speed*, should be strictly adhered to.



If the max. line lengths are not adhered to or if the bus lines are not terminated properly, this may lead to interference during transmission, see chapter 4.3.4 *Troubleshooting*.



A CAN network can usually include up to 32 network participants.

4.2.4. Standard pin connections

The following two connector types with the pin connection shown below are very often used with CAN. The pin connection corresponds with the requirements of the CiA 303-1.

Which connector plug the used device is equipped with, should be taken from the relevant data sheet.

- M12*1 5 pole plugs for sensors and actuators
- DSUB 9 pole socket for controllers (PC or PLC).

Plug connector	Pin	Description
	1	CAN_SHLD <i>Shielding</i>
	2	CAN_V+ optional supply voltage
	3	CAN_GND <i>CAN Signal mass</i>
	4	CAN_H <i>Signal line dominant "High"</i>
	5	CAN_L <i>Signal line dominant "Low"</i>
	1	
	2	CAN_L <i>Signal line dominant "Low"</i>
	3	CAN_GND <i>CAN Signal mass</i>
	4	
	5	CAN_SHLD <i>Shielding</i>
	6	
	7	CAN_H <i>Signal line dominant "High"</i>
	8	
	9	CAN_V+ optional supply voltage

4.2.5. Transmission speed

The transmission speed of CAN can be selected in particular areas. It is indicated in **bit/s** and also referred to as **Baud rate**. The Baud rate of a device can be changed by means of its OD parameter; see chapter 3.1.3.2 *Changing the Baud rate* and object: *Baud rate*.

A distinctive feature for CAN is that the Baud rate has a high impact on the maximum length of the wiring; see chapter 4.2.1 *Wire connections*. The length of the bus as well as of the stub cables depends on the transmission speed; see chapter 4.2.3 *Topology*. The table below explains the dependences:

Bit rate [kbit/s]	Bus length [m]	Stitch length [m]	Bit length [μ s]
1000	25	0,3	1
800	50	0,5	1,25
500	100	0,8	2
250	250	1,5	4
125	500	3	8
50	1000	5	20
20	2500	7	50
10	5000	10	100

4.3. Data communication

The basic information for the data exchange between two or more network participants is given below.

As explained in chapter 4.2 *Hardware* properties, all participants of a CAN network are able to send messages. A message which is sent is also received by each participant. For this reason, the messages are referred to as "broadcasts", which means it can be compared with a radio station sending an information, a news programme for instance, which all radio receivers are enabled to hear/to receive.

The type of message is defined by means of the CAN-ID (see chapter 4.3.2 *Meaning of the CAN ID*) and the receiver is able to set a filter, to define which message it wants to receive - just like setting (filtering) a frequency aiming to receive a particular radio station.

4.3.1. Structure principle of a CAN data message

The data message is the most important message in a CAN network. It is used for the exchange of data/information, as the name might suggest, between the network participants.



A data message consists of three sections:

- HEADER - The message head synchronises between the network participants and informs the receiver about the content and the length of the message.
- DATA - This section is for the user data, i.e. the information which is supposed to be transmitted from the sender to the receiver.
- FOOTER – Contains the checksum, a message confirmation as well as an identifier which marks the end of the entire message.

A particular feature of CAN message is that they can also represent a valid information without the user data. How many user data bytes a message may contain, is informed by the DLC of the HEADER. This section defines the amount of data bytes in the area of the DATA and can receive the applicable values 0-8. This involves that the max. length of the user data is 8 bytes or 64 bit.

Example for a CAN message without user data; DLC = 0:



The length of the entire message depends on two factors: The number of user data in the first place and the length of the CAN ID in the second; see chapter 4.3.2 *Meaning of the CAN ID*.

The shortest possible message (11 bit CAN ID, DLC = 0) has a bit length of 47 bit. This message would require 188 µs for a Baud rate of 250 kbit/s and a maximum of 4800 messages of this type could be transmitted per second (~90 % Bus load).

For the longest possible message (29 bit CAN-ID, DLC = 8) the length of the message at 250 kbit/s (4 µs /bit) would result as follows: Message length = 129 bit, transmission time per message = 516 µs (~0,5 ms) and approx. 1760 messages per second (~90 % Bus load).

The structure of other message types, such as "Error frame" or "Remote frame", will not be explained herein, as they either play a subordinate role or because they are handled by the device-internal communication controller.

4.3.2. Meaning of the CAN ID

As described in the chapter 4.2 *Hardware properties*, CAN is able to prioritise incoming messages. The CAN ID is decisive for that. It is sent within the first section of the HEADER, as has been treated in chapter 4.3.1 *Structure principle of a CAN data message*. As the network participant may not send before complete transmission of a message, the CAN ID

can be used to prioritise, applying the mechanism of the recessive and the dominant signal statuses (see chapter 4.2.2 *Signal level*).



The priority of a message depends on the value of the CAN ID.

- The lower the CAN ID, the higher the priority of the message.
- CAN ID = 0 has the highest possible priority.

CAN does not know any direct address of the participants. The CAN ID defines, which importance a message has, thus, the CAN ID 0 identifies the NMT message for example - the network management; see chapter 4.4 *Network Management*.

Whereas CANopen takes the opportunity to structure the CAN ID and to combine the importance (service ID) with the participant's address; i.e. the CAN ID of the first process data object is defined by 180h + Node ID.



In CANopen, the synonym COB ID is often used instead of CAN ID. The COB ID can either be the CAN ID itself, or the combination of the basic CAN ID and the Node ID, which develops to become a concrete CAN ID during the life time of the device; i. e. object *COB-ID emergency message*.

Below, the most important CANopen services and the assignment to its CAN ID are listed:

Dienst	CAN ID	Note
NMT	0	<p><i>Network management</i></p> <p>The <i>NMT Master</i> must always be able to reach all the participants for the management of the network. For this purpose, this service has the highest possible CAN priority.</p>
SYNC	80h	<i>Synchronisation signal</i>
EMCY	80h+Node-ID	<i>Error event</i>
SRDO	101h – 180h	<p><i>Safety-relevant data object</i></p> <p>see chapter 1.1°Scope of applications</p>
PDO	181h – 57Fh	<i>Process data object</i>
SDO	581h – 67Fh	<i>Access to OD parameters via service objects</i>
LSS	7E4h – 7E5h	<i>Layer setting services</i>

4.3.3. Meaning of the Node ID

As explained in chapter 4.3.2 *Meaning of the CAN ID*, no particular network participant can be addressed directly using exclusively the CAN ID. As it is, however, vital in automation to address one particular participant in the network, the **Node ID** has been generated to become the **address of the participant**.

- The Node Id of a participant always has to be clear within the network, which means, it may not exist more than once.
- The valid value range of the Node ID is 01h to 7Fh (1d to 127d), i. e. there can only be max. 127 different participants within one CANopen network.

There are different ways to change the Node ID:

- Default settings: 3.1.1 *CANopen default* settings
- 3.1.3.1 *Changing the device address (node ID)*
- 4.7 *Layer setting services (LSS) Protocol*
- Object: *Node ID*

4.3.4. Troubleshooting

CAN has its own error management, which is composed of 3 different error statuses. The change between the different error statuses is managed via internal error counters (TEC: Send, REC: receive error counter). A more detailed description of the bus behaviour can be found in the ISO 11898-1.

If a participant recognises an error when sending, or if one of the recipients reports a transmission error by means of sending back a particular error message, the sender will repeat sending its failed message as soon as possible.

- **Error active**

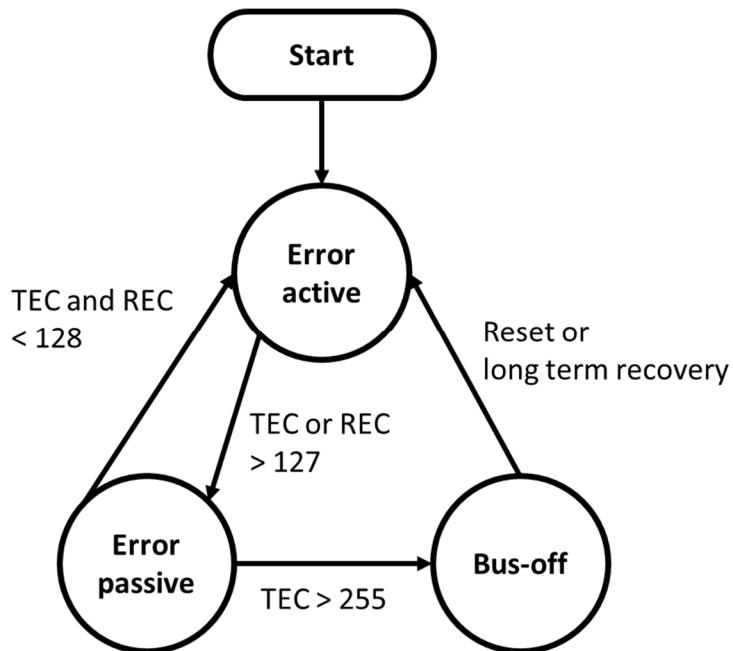
Is the "normal" operation condition of a network participant. In this condition, a participant is able to send messages as well as to inform other participants actively about communication errors which it has detected.

- **Error passive**

The participant is in a "temporary" error condition. In this condition, messages can still be sent and received. After sending a message, however, the participant will maintain a certain delay before sending the next message. This gives the participants, which do not show any interference the opportunity to send their messages earlier. This mechanism is supposed to reduce network traffic if there is one interfering participant.

- **Bus-off**

The participant is in an error condition. It is neither able to send nor to acknowledge any messages. This state can only be left if the participant is actively reset or if no errors have occurred at the bus within a certain delay. After their return, the error counters have been reset and the participant has returned to the "error active" status.



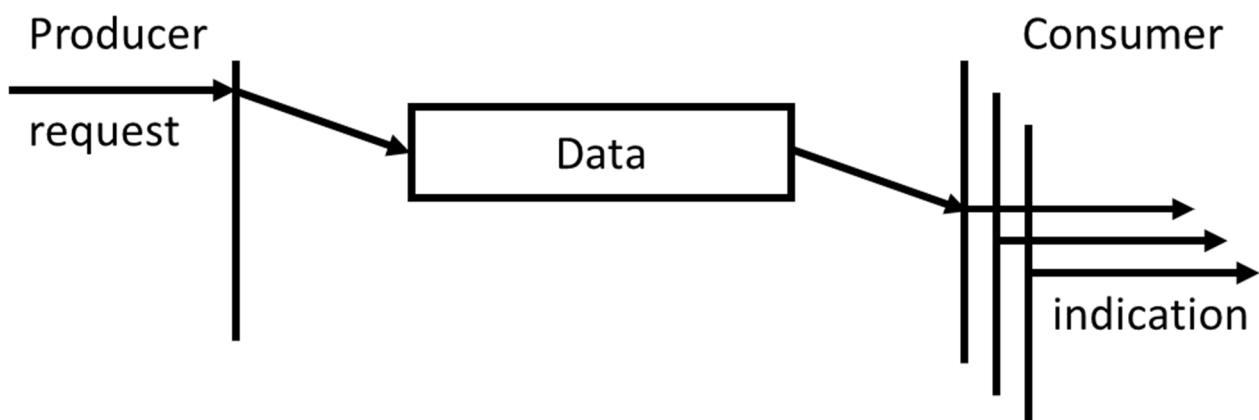
4.3.5. Communication types

As described in chapter 4.3 *Data* communication CAN uses data packages for the transmission of information. To make the communication process run smoothly, there are different models of how the data flow between two network participants should be organised.

The most frequently used communication types with CANopen are described below. The left side of the diagrams always represents the information source which generates the messages and sends them. In the central section of the diagram is the transmission via the network and the right section represents one or more receivers.

4.3.5.1. Producer - Consumer

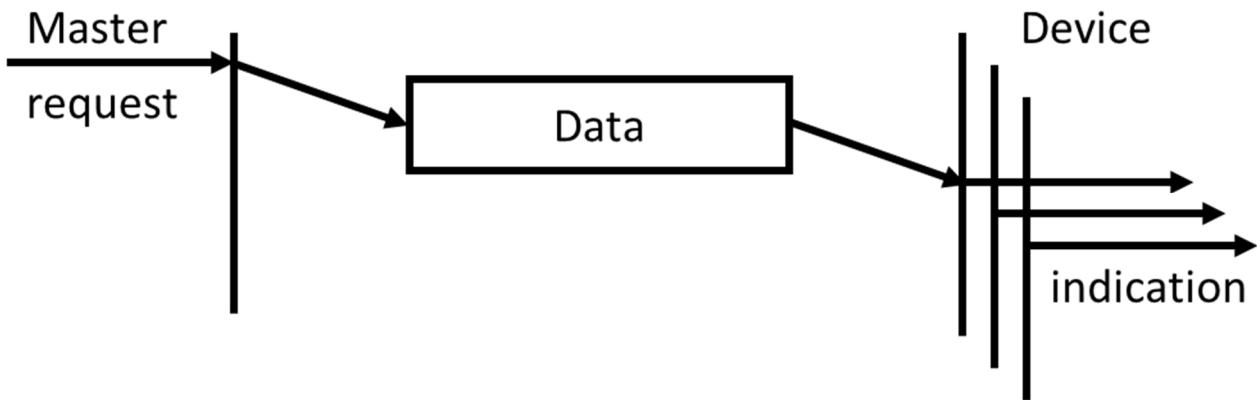
In the "producer - consumer" model describes how a participant generates information which one or more participants can receive and process. The advantage of this model is that it is not necessary for each individual participant to be informed about the same circumstances, instead, any participant for whom the information is of interest, will receive the information at the same time in one data transmission.



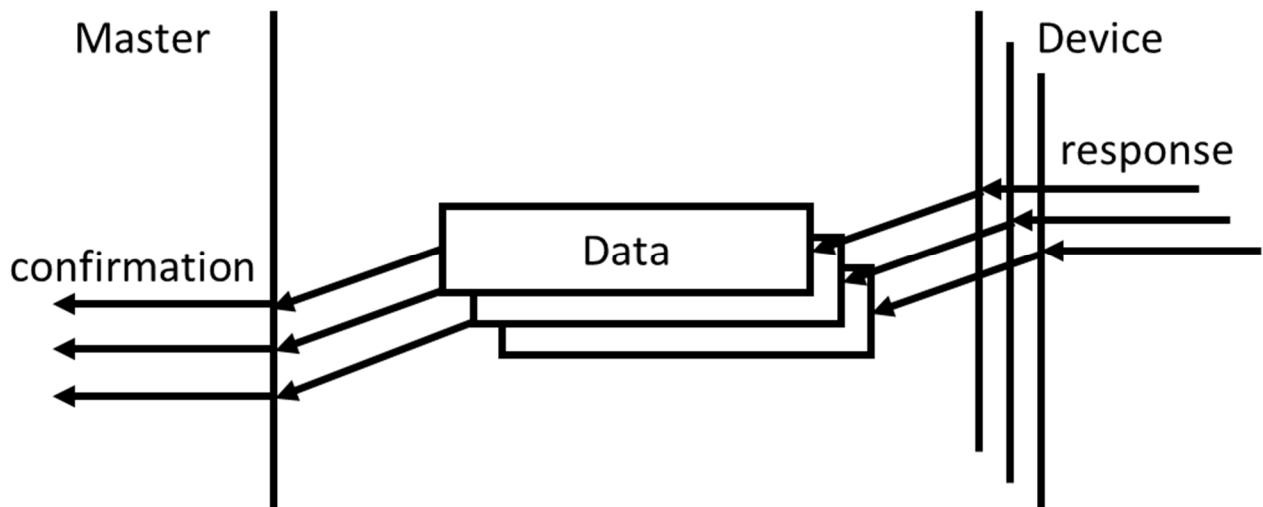
4.3.5.2. Master – Device

Similar to the "Producer – Consumer" model, the "Master – Device" model (see chapter 1.6 *Changes in technical terms in the context of "political correctness"*) is enabled to reach several receivers at a time. In this particular case, however, there is only one firmly defined "producer", the master, who informs or advises all other participants ("devices"). Which participant works as a master, is defined during the architecture phase of the system design period.

This model can, for instance, be used by a CANopen manager to administrate the network by acting as a NMT master. See chapter 4.4.2 *NMT*. It is also used for the synchronisation of the process data; see chapter 4.6.2.2 *SYNC*.



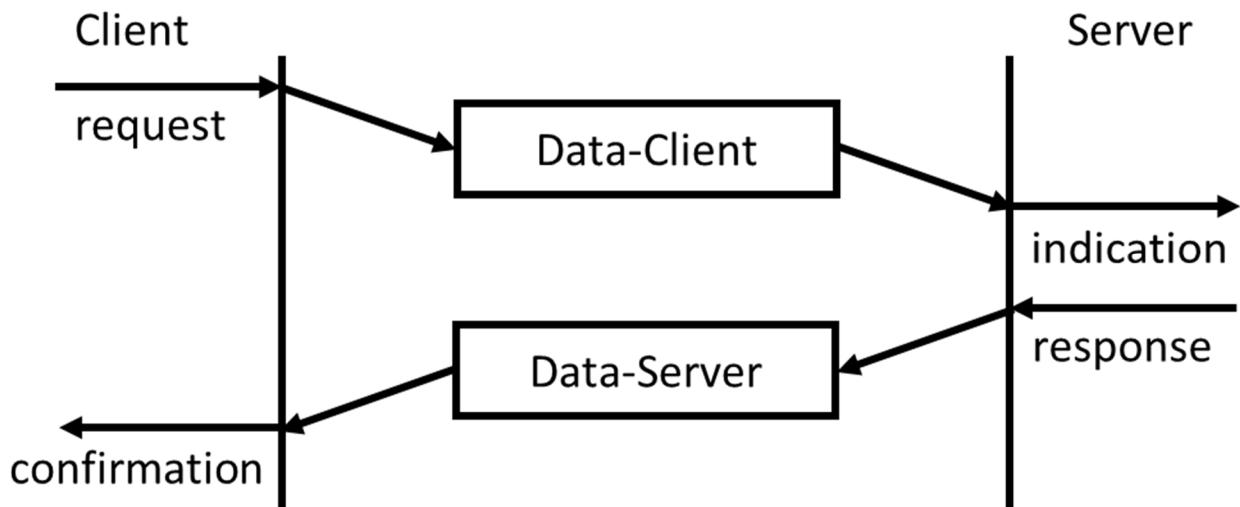
In some "master - device" implementations, the "master-request" will be responded to by the participants ("devices") through a "response". This procedure is used with the LSS protocol, for example. In doing this, the LSS master will be informed that one or several LSS devices have performed the required status change; see chapter 4.7 *Layer setting services (LSS) Protocol*.



4.3.5.3. Request – Response / Client – Server

The "Request – Response" model enables one particular participant to inquire an information from another particular participant. The client communicates to the recipient (server), usually by means of data from the data package, what information it wants to inquire (data request). Theoretically, such a request may also consist of just a message without the data. See chapter 4.3.1 *Structure principle of a CAN data message* DLC = 0.

The recipient takes on the function of a server, administrating a pool of data or services, which can be requested directly from that pool by a client. An example from our daily practice could also be requesting a website on the internet by entering an URL address into the "internet browser". The request is comparable with the entry of the address and the response is the page that is subsequently loaded and displayed.



From the point of view of CANopen, this type of communication is used when accessing the OD, see chapters 4.5 *The Object Dictionary* and 4.6.1 *SDO*.

4.4. Network Management

In automation of machines, it is crucial to keep the communication under control. The CANopen manager is responsible for this task. This manager is usually represented by a superordinate control, e. g. a PLC or a mobile control unit.

There are several different operating conditions which can be taken on by the different participants, controlled by the CANopen manager. Depending on the operating condition of a participant, it can provide (or not provide) certain services autonomously; see chapter 4.4.1 *Overview network conditions*. The administration of the network condition is carried out via the service of "network control"; see chapter 4.4.2 *NMT*.

The two most important conditions are:

➤ Pre-Operational

This condition serves to parametrise a participant suitable for a specific application. See chapters 4.6.1 *SDO* and 4.5 *The Object Dictionary*. In addition, further services are carried out, such as for example: 4.4.3 *Heartbeat*.

A participant takes on that condition automatically after start-up and usually remains in this state, until a command for status change has been received explicitly. The participant's start-up behaviour can be controlled via the object "*NMT startup*".

Important note: In this state, **no process data** can be received or sent.

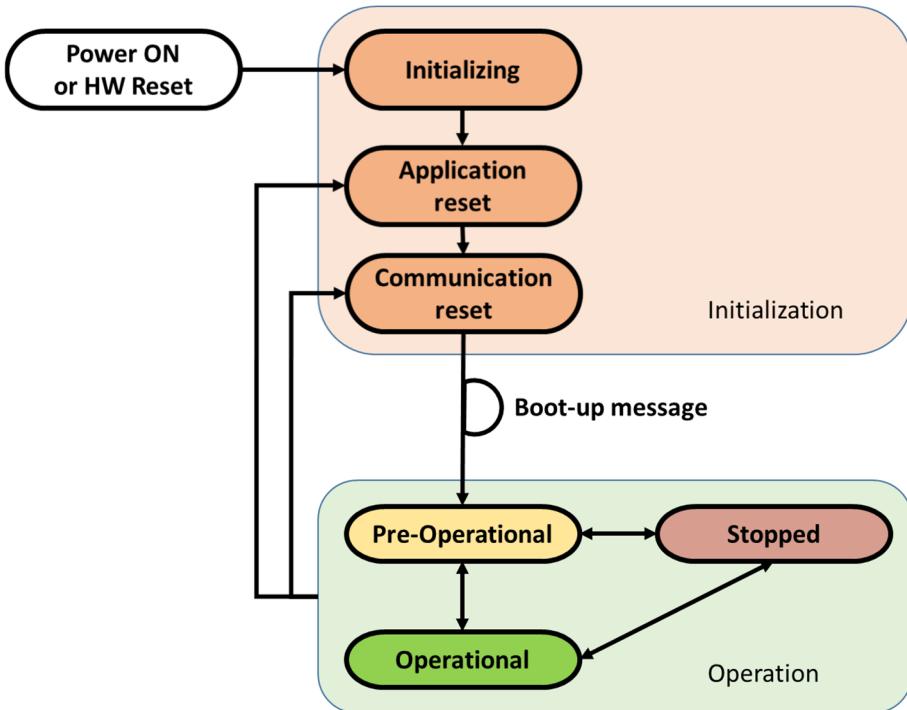
➤ Operational

The condition of "operational" is the normal operating condition of a participant. Almost all CANopen communication services can be used. This condition only enables the participants to receive and to process the process data and to generate and send their own process data, see chapters 4.6.2 PDO and 4.6.3 SRDO.

In this operating condition, the parameters can also be read, however, the option of changing parameters is limited, see 4.6.2.3 PDO Mapping.

4.4.1. Overview network conditions

In general, the conditions are subdivided into the categories: initialisation and operation of a participant. The initialisation phase is gone through automatically after applying the supply voltage. After successful initialisation, the participant sends a "Boot-Up" message by means of which the *Node ID* of a participant can be identified; see also chapter 4.4.3 Heartbeat.



After successful initialisation, there are 3 different operating conditions available. The most important conditions "pre-operational" and "operational" were already explained in chapter 4.4 Network Management.

In the "stopped" condition, only the network (see 4.4.2 NMT) and error services (see 4.4.3 Heartbeat) are active, whereas all the other services are not available.

The following table provides an overview of what services are available in the different operating conditions:

Service ID	Pre-Operational	Operational	Stopped
PDO		X	
SRDO		X	

Service ID	Pre-Operational	Operational	Stopped
SDO	X	X	
SYNC	X	X	
TIME	X	X	
EMCY	X	X	
Heartbeat	X	X	X
LSS	X		X
NMT	X	X	X

4.4.2. NMT

The administration of the network conditions is carried out via the "network control" service. For this purpose, there is a defined NMT master which gives the command (using a NMT message) to each individual participant (device) to change their state, NMT = Network Management.

The "Network Control" service is performed via the *Master – Device* communication model. The CANopen Manager (controller) generally takes over the role of the NMT Master

As this service makes the decisions on the interaction between the participants in the network, it has been assigned the most important priority; see chapter 4.3.2 *Meaning of the CAN ID* and 4.3.1 *Structure principle of a CAN data message*.

The NMT message has a data length of 2 bytes, each of which has a particular signification which is documented below.

Field name	Content	Meaning	
CAN ID	0	CAN ID of the message	
DLC	2	Data length of the message in bytes	
BYTE 0	Command	01h	Start node Participant is supposed to switch to "Operational" state.
		02h	Stop node Participant is supposed to switch to "Stopped" state.
		80h	Enter Pre-Operational Participant is supposed to switch to "Pre-operational" state.
		81h	Reset node Participant is supposed to be reinitialised.

Field name	Content	Meaning	
		82h	Reset communication Participant is supposed to restart its communication layer.
BYTE 1	Node ID	0d	Message is being processed by all participants.
		1-127d	Node ID of the participant to be changed.

Example for a signal from the NMT Master telling all network participants to change to operating state "Operational" → NMT "Start all nodes".

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	Node ID						
000h _{Tx}	01h	00h						

4.4.3. Heartbeat

The heartbeat protocol serves one participant to inform all the participants within the network about its current operating state.

This service is implemented according to the 4.3.5.1 *Producer - Consumer* model.

The message needs to be activated explicitly and is sent on a cyclical basis. Via the object "*Producer* heartbeat time" the heartbeat can be activated and the repeat rate can be configured.

Should the heartbeat consumer report the absence of a heartbeat message, it will inform its superordinate application software about this event. The application should then react in the appropriate way.

The message has a data length of one byte, which reports the current state of the participant.

Field name	Content	Meaning	
COB ID	700h + Node-ID	CAN ID of the message der Nachricht errechnet im Betrieb aus der Basis CAN-ID und der Node-ID des Teilnehmers.	
DLC	1	Data length of the message in bytes	
BYTE 0	Status	00h	Boot-up The participant reports a system start.
		04h	Stopped Participant is in the "Stopped" mode.
		05h	Operational

Field name	Content	Meaning
		Participant is in the "Operational" mode.
	7Fh	Pre-Operational
		Participant is in the "Pre-operational" mode.

Example for a heartbeat signal of a device with Node ID = 1 which currently is in the operation mode "*Pre-Operational*".

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	Status							
701h Rx	7Fh							

4.4.4. Example NMT behaviour

In the following example for the CAN protocol, one individual participant having the Node ID = 1 is connected to a CANopen manager (*NMT Master*) and is re-initialised at the beginning of the recording (power ON)

Description of the subsequent process:

- After successful initialisation the device sends its "boot-up" message.
- After a defined time ,the manager starts all the participants.
 - The device starts sending its process data *TPDO1*.
- after having waited a further defined period, the manager sends an additional signal to change to "*Pre-Operational*".
 - The device terminates the sending of process data.
- The manager writes onto the object 5300 in the device (node ID = 1).
 - The device confirms that the writing access has been successful.
- after having waited a further defined period, the manager sends an additional signal to change to "*Stopped*".
 - The manager again attempts to write onto the object 5300 in the device (node ID = 1).
 - The inquiry is not responded by the device.


```

NMT command "stop, all nodes".
0000 Tx 2 02 00
Heartbeat Node-ID = 1, Status = "Stopped"
0701 Rx 1 04
0701 Rx 1 04
SDO Download Request, 5300.0 = 1
0601 Tx 8 2F 00 53 00 01 00 00 00
→ Not received any SDO Download Response; Node 1 in "stopped"
0701 Rx 1 04

```

4.4.5. EMCY

By means of EMCY messages, the device can inform other participants in the network when it has detected an error itself.

EMCY messages are implemented according to the "producer/consumer" model; see chapter 4.3.5.1 *Producer - Consumer*.

An EMCY message is sent only once. Sending is performed, whenever an error has been recognised in the device.

Has the error been recognised for the first time, the corresponding bit of the error register (see object "*Error register*") is set. If all the bit in the error register have been erased, the EMCY message with the error number 0000h is sent. This particular EMCY serves as an identifier in order to signalise that all error states have been set back and that the device has returned to trouble-free operation.

An EMCY message has a length of 8 bytes. The first bytes contain the "emergency error code" (EMCY-EC) (2 bytes), specified in the CiA 301 and the *Error register* (1 byte) of the device. The remaining 5 bytes are manufacturer and also mostly device-specific.

In order to avoid an accumulation of EMCY messages (for instance in the event of a faulty CANbus connection), a minimum waiting delay between two EMCY messages can be defined "*Inhibit time EMCY*".

How the device should behave when an error has occurred, can be defined via the object "*Error behavior*". An action might be the change of the activated operation mode; see chapter 4.4.1 *Overview network conditions*.

Field name	Content	Meaning
COB ID	80h + Node-ID	CAN ID of the message is calculated during operation from the basic CAN ID and the Node ID of the participant.
DLC	8	Data length of the message in bytes
BYTE 0, 1	emergency error code "EMCY-EC"	Error number of the EMCY event The error numbers supported by the device are described in chapter 3.6.1 <i>Error messages</i> . Data type: <i>UNSIGNED16</i>

Field name	Content	Meaning
BYTE 2	<i>Error register</i> "ErReg"	The content of the object "Error Register" is copied into the message when an EMCY event occurs. Data type: <i>UNSIGNED8</i>
BYTE 3 - 7	Manufacturer specific error field (MSEF)	Manufacturer and device-specific additional misinformation. Description of the content of this data field. See chapter 3.6.1 <i>Error messages</i> . In many of our devices, the first 2 bytes of this data field contain the information of both lowest bytes (Low-WORD) of the object "Manufacturer status register" when an error occurs. Data type: manufacturer-specific

Below, EMCY messages of a HYDAC Filtertechnik GmbH linear position transmitter is shown as an example with Node ID = 1:

- The network connection between the CANopen manager and the device has been disturbed.
 - EMCY-EC 8120h → *CAN in "error passive"*
 - *Error Register* 11h → Bit "Generic" & "Communication error" is set
 - MSEF 00h → no additional information
- Linear position sensor motion detected outside of the measuring range limits.
 - EMCY-EC FF00h → *device-specific error*
 - *Error Register* 91h → Bit "Generic" & "device-specific error" is set
→ Bit "Communication error" is still set
 - MSEF 10h → Measuring range override recognised
- Linear position sensor has been moved back to its valid measuring range.
 - EMCY-EC 0000h → *No Error*
 - *Error Register* 00h → "no error"
 - MSEF 00h → no additional information

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	EMCY-EC		ErReg	manufacturer-specific error field (MSEF)				
	LowBy	HighBy						
081h _{Rx}	20h	81h	11h	00h	00h	00h	00h	00h
081h _{Rx}	00h	FFh	91h	10h	00h	00h	00h	00h
081h _{Rx}	00h	00h	00h	00h	00h	00h	00h	00h

4.5. The Object Dictionary

The "object dictionary" (OD) is the data base of the device. Not only all the settings and device properties, but also all the process values are stored here. The individual values can be read, and partly also written to via SDO commands (see chapter 4.6.1 *SDO*).

The individual entries in the OD are referred to as objects. An object can either represent an individual value or a combined data entry. Combined data entries are, for instance, arrays or structures; see chapter 2.4.6 *ARRAY* and 2.4.7 *RECORD*.

There are objects, which may only be changed under particular system conditions, or which enter into effect in the event of particular system condition changes only, see chapter 4.4.2 *NMT*.

The OD is subdivided into different sections. The most important and applicable for all devices are listed below; see chapter 4.5.4 and following. Device-specific entries are described in the chapter 3.5 *Parameter*. The classification is made via pre-defined object index sections, see CiA 301.



The HYDAC standards for the structure of an OD are explained below. There may be deviations from these standards, depending on the device. In the event of a deviation, they are described in chapter 3.5 *Parameter*.

4.5.1. General

In this chapter, the general characteristics of the OD will be explained - how can a particular object be selected, which access limitations are there and which different properties do objects have in this context.



The abstract term of "object" is replaced by the more defined term of "parameter", mainly for the OD in the context of product description (see chapter 3.5 *Parameter*).

In the context of CANopen the term "object" does not only include an entry in the OD, but may also refer to a communication object; see chapter 4.6.1 *SDO* or 4.6.2 *PDO*.

4.5.1.1. Addressing

Each entry in the OD is addressed via an object index. The index value identifies the concrete object. If the object represents the combined data type, the index will be subdivided into further sub-indices. A specific value from this type of structure will therefore be addressed via the indication of the index and the sub-index.



The notation of an **object index** will always be represented by **hexadecimals**, whereas the **sub-index** will be represented by **decimals**.

At first, the index of the main object will be indicated and divided by a "." the index of the relevant sub-object. Addressing a particular object will, thus, be represented as follows:

<index>.<subindex>

1018.2 → Identity object.Product code = 928037 s. 4.5.3 OD Example

When accessing a single object in the OD, the sub-index 0 always has to be indicated additionally for the addressing; see chapter 4.6.1 SDO.

1005.0 → COB-ID SYNC = 128 (80h)

In one device, it is not required to have all the indices continuously and addressable. Gaps are usual in the OD. When accessing a non-defined object, the related error message will be issued.

4.5.1.2. Object access types

Also referred to as "access" or "acc." below.



Changes to the object are always performed in the volatile device memory (RAM). In order to permanently save changes, a storing function has to be activated; see chapter 4.5.1.3 *Objects serving as functions*.

4.5.1.3. Objects serving as functions

Some objects are similar with function calls. For calling up a function which is assigned to an object, the object is usually assigned a particular activation value. The writing process consequently provokes the assigned function.



An important example for this is the feature "**Store parameters**", which should be activated for the permanent storage of object changes.

4.5.1.4. Object serving as process data content

Some entries in the OD can be used for the transmission via a process value (PDO). The main advantage is that, doing this, the content of the object does not have to be requested explicitly via a SDO command any more, but is permanently available in the context of process data transmission.

The object properties "*mappable*" defines that the content of the object can be transmitted via a PDO; see chapters *4.6.2 PDO* and *4.6.2.3 PDO Mapping*.

In the different object tables, all the objects which are able to be transmitted as a process value, are marked in the "PDO" column as follows, i.e. object "*Error register*".

Type	Acc.	PDO
JNSIGNED8	ro	TP

TP Objekt can be mapped on a **TPDO** (Transmit).

RP Objekt can be mapped on a **RPDO** (Receive).

4.5.2. Overview OD areas

The highlighted areas are crucial and will be described more in detail in the chapters below.

Index area	Description	
0000h	Reserved	
0001h	025Fh	Datatypes
0260h	0FFFh	Reserved
1000h	1FFFh	Communication profile area Communication objects
2000h	5FFFh	Manufacturer-specific profile area manufacturer-specific functions
6000h	9FFFh	Standardized profile area Objects which are not defined via a device.
A000h	AFFFh	Network variables

Index area	Description	
B000h	BFFFh	System variables
C000h	FFFFh	Reserved

4.5.3. OD Example

Below table shows the general structure of the OD in a device. It has been generated as an extract, based on the inclination sensor HIT (HE-926037-0008.eds).

The column "value" corresponds with the possible content of an object which can be read out via of the addressing <index>.<subindex> by means of a *SDO commands* from an existing device.

The columns "Name", "Object type", "Access", "Data type" provide a more detailed description of the properties of the entry; see also chapter 4.5.7 *EDS Electronic Data Sheet*.

Index	Sub	Value	Name	Type	Access	Data type
...				
1005h		128	COB-ID SYNC	VAR	rw	UNSIGNED32
1008h		HIT1000	Manufacturer device name	VAR	const	STRING
...				
1018h	0	4	Highest sub-index supported	VAR	Const	UNSIGNED8
1	218		Vendor ID	VAR	ro	UNSIGNED32
2	928037		Product code	VAR	ro	UNSIGNED32
3	8		Revision number	VAR	ro	UNSIGNED32
4	4711		Serial number	VAR	ro	UNSIGNED32
1029h	0	3
1	1
2	1
3	1
1400h	0	5
1	513

4.5.4. Communication profile area

Object index range: 1000h – 1FFFh

In the section "Communication profile area", all the settings which are necessary for the communication with the device are listed. This includes manufacturer-related or device-related information (e.g. the serial number), current error reports and the settings for the process data transmission.

The "Communication profile area" is subdivided into different sub-areas. The essential areas for this protocol description are described in the following sub-chapters.

The general area describing all the parameters for communication, see CiA 301 "General communication objects (object index range: 1000h – 1029h)" has been subdivided into the following 4 sections for better readability.

4.5.4.1. Error management (General communication objects)

Object index range: 1000h – 1029h

In this section, the objects from the section "General communication objects" are summarised. These provide information on the device status (e.g. error management).

A small number of these objects are specifically defined in the device profiles. This is relevant for the following objects:

- Error register 1001h
- Error behaviour 1029h

Name	Index	Sub	Type	Acc.	PDO
Error register	1001h	0	UNSIGNED8	ro	TP

Device error status This error status is also part of the EMCY message, see chapter 4.4.5 EMCY.

Bit 0 **Generic error**

Indicates a general device failure, this could be an error during evaluation of the measurement signal, for example.

Bit 1 Current not supported

Bit 2 Voltage not supported

Bit 3 Temperature not supported

Bit 4 **Communication error**

Becomes active when an error has been recognised during CAN communication.

Bit 5 **Device profile specific** s. Comment

Bit 6 Reserved

Bit 7 **manufacturer-specific**

Is activated if a manufacturer-specific error exists; see **Manufacturer status register**

Note: Parts of the register's signification will be individually defined by the device profiles; see chapter 3.5.3 *Device profile-specific* parameters.

Manufacturer status register	1002h	0	UNSIGNED32	ro	TP
-------------------------------------	--------------	---	------------	----	----

Name	Index	Sub	Type	Acc.	PDO
This object is an expanded error state compared with the "Error register". The lowest 16 bits (bit 0 - 15) contain the device-specific error identifiers. In the case of an error, these 16 bit will be implemented in the error memory as an additional information as well.					

The higher bits (bit 16 - 31) can contain additional status information.

If an EMCY message occurs (see chapter 4.4.5 EMCY), the lower level 16 bits (bit 0 - 15) of the "Manufacturer status register" will be transmitted in the manufacturer-specific part of the message.

The detailed description of each individual bit's meaning can be found in the device-specific part of this documentation 3.7.3 General error management.

Pre-defined error field	1003h	ARRAY			
--------------------------------	--------------	--------------	--	--	--

The error list shows the errors which have occurred in the device and which were signalled via EMCY message (see CiA 301). The object is a combined data type in the form of a list (ARRAY). The individual entries are described below.

The content of this object is not stored in the persistent memory of the device and will therefore be erased after device restart.

Number of errors	1003h	0	UNSIGNED8	rw
-------------------------	--------------	----------	------------------	-----------

The current number of error messages saved in the error memory. If no error has been detected, the content is 0. The maximum size of the list depends on the device configuration, however, for most products, the list is set to have max. 10 entries.

By setting the object to 0, any error memory that may exist is deleted. Values which are different from 0 may not be written into the object.

Standard error field 1 ...	1003h	1	... [1003.0]	UNSIGNED32	ro
-----------------------------------	--------------	----------	---------------------	-------------------	-----------

When sending an EMCY, the device will add the related error to the error list.

The content of each entry is composed of the "emergency error code" (EMCY-EC) (16 bit) and the lower 16 bit of the "Manufacturer status register" (MSR-LW).

Bit: 31 – 16 | 15 – 0 (UNSIGNED32)
EMCY-EC | MSR-LW

sub-index 1 contains the most recently occurred error, sub-index 2 contains the previously occurred error. At the same time, the content of sub-index 0 defines the last valid entry in this list. Example: 1003.0 = 3 → 1003.1, 1003.2 and 1003.3 contain valid error entries.

The history is able to register a device-specific amount of errors, however, at least one error memory is available. If the number of error entries in the list is exceeded, the oldest entry will be overwritten.

The content of the error history list will always be deleted at device start-up.

Inhibit time EMCY	1015h	0	UNSIGNED16	rw
--------------------------	--------------	----------	-------------------	-----------

Name	Index	Sub	Type	Acc.	PDO
Configurable delay between two <i>EMCY</i> messages.					
If several <i>EMCY</i> messages occur within the pre-set time period, a new <i>EMCY</i> message will not be sent before the time has elapsed. The <i>EMCY</i> error code sent corresponds with an error which has been detected within that time span.					
If an <i>EMCY</i> event occurs which immediately disappears, no <i>EMCY</i> message will be sent.					
0	No delay activated for <i>EMCY</i> messages.				
>0	Delay time as a multiple of 100 µs				
Error behavior	1029h		ARRAY		
Definition of the device behaviour when an error occurs; see chapter <i>4.4 Network Management</i> .					
Behaviour in case of an upcoming error					
0	If an error occurs, the device changes to "pre-operational" network state, if its current state has been "Operational".				
1	No change in the network state when an error occurs.				
2	The device changes to the network state "stopped" if an error occurs.				
Highest sub-index supported	1029h	0	UNSIGNED8	const	
Number of the several error behaviours which are configurable at the device. The number depends on the device profile. It must, however, be at least 1 (1029.1 is always defined).					
Communication error	1029h	1	UNSIGNED8	rw	
Device behaviour in case a communication error occurs.					
profile-specific or manufacturer-specific error	1029h	2 ff.	***	rw / const	
Note:					
Sub-index 2 and higher defines device error behaviours which are device-specific or device profile-specific. Their definition and behaviour will generally correspond with the description in chapter <i>Error behavior</i> .					
If the measurement system used supports these type of parameters, they are described in chapter <i>3.5.3 Device profile-specific parameters</i> .					

4.5.4.2. Device identifier (General communication objects)

Object index range: 1000h – 1029h

In this section, the objects, providing device-specific information, such as serial number, device part number or software version, are summarised in the chapter "General communication objects".

A small number of these objects are specifically defined in the device profiles. This is relevant for the following objects:

- Device type 1000h

Name	Index	Sub	Type	Acc.	PDO
Device Type	1000h	0	UNSIGNED32	ro	

Bit 0-15 contains the device profile, i. e. 019h → CiA 410

Bit 16-31 device or device-specific additional information

Anmerkung: The signification of bit 16-31 will be partly defined individually by the device profiles; see chapter 3.5.3 *Device profile-specific* parameters.

Manufacturer device name	1008h	0	STRING	ro
---------------------------------	--------------	---	--------	----

Readable device name as a character string, which is generally the model code; i. e. "HPT 1448-F11-0600-000".

A "segmented" access is necessary in order to read this object, see chapter 4.6.1.3 *SDO Upload (segmented) [read]*.

Manufacturer hardware version	1009h	0	STRING	ro
--------------------------------------	--------------	---	--------	----

Current hardware version number, which corresponds with the series index from the serial number as is printed on the type label → i.e. "1".

Manufacturer software version	100Ah	0	STRING	ro
--------------------------------------	--------------	---	--------	----

Current device software with version number, e.g. "Hptco2 V03.02".

A "segmented" access is necessary in order to read this object, see chapter 4.6.1.3 *SDO Upload (segmented) [read]*.

Identity object	1018h		RECORD	
------------------------	--------------	--	--------	--

Each individual device worldwide can be clearly identified by means of this "Identity object".

Highest sub-index supported	1018h	0	UNSIGNED8	const
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The "Identity Object" has 4 device-specific features which, in combination with one another, enable clear identification of the relevant specific device.

Vendor ID	1018h	1	UNSIGNED32	ro
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Clear manufacturer identification: 0000 00DAh → HYDAC Filtertechnik GmbH

Product code	1018h	2	UNSIGNED32	ro
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Product identification number: HYDAC part number, i. e. 926037

Revision number	1018h	3	UNSIGNED32	ro
------------------------	--------------	---	------------	----

Device revision number, as listed in the HYDAC serial number

Serial number	1018h	4	UNSIGNED32	ro
----------------------	--------------	---	------------	----

Device serial number; generally the last two numbers subsequent to the revision number of the HYDAC serial number which is printed on the type label.

4.5.4.3. Storage and restoring (general communication objects)

Object index range: 1010h – 1011h

This chapter summarises the two objects which describe the functions for loading the default settings and for permanent writing of changes to the device storage; see chapter 4.5.1.3 *Objects serving as functions*.

The following particularities need to be considered:



If the function "Store parameters" has not been carried out, changes to the object contents will be lost in the event of a "Reset Node" or if the power supply has been interrupted.



While reconstructing, the factory settings will be copied into a particular area of the device software, into the non-volatile memory. The current values in the volatile memory (RAM) will **not** be changed for this purpose. Thus, a device restart is necessary to activate the reconstructed values.

Name	Index	Sub	Type	Acc.	PDO
Store parameters	1010h		ARRAY		

In order to store changes permanently, one of the sub-entries of the object should be described; see chapter 4.5.1.3 *Objects serving as functions*.

The character string "save" is the function activating value for all "store" functions.



When accessing as a *UNSIGNED32* value , the character string "save" will be represented by the numerical value 65766173h.

Caution: When performing the SDO command, please observe the order of the steps, see chapters 2.3 *Bit order* and 4.6.1 *SDO*.

Byte 4	Byte 5	Byte 6	Byte 7
73h	61h	76h	65h
"s"	"a"	"v"	"e"

Highest sub-index supported	1010h	0	UNSIGNED8	const
------------------------------------	--------------	----------	------------------	--------------

Number of supported sub-entries of the object.

Four different functions for the separate storage of parameter sections are supported.

Name	Index	Sub	Type	Acc.	PDO
Save all parameters	1010h	1	UNSIGNED32	rw	

Storage without limitation of the parameter section.



Particular: Changes in "Node ID" and "Baud rate" will be maintained when opening this function. For permanent storage of these settings, call up the function "**Save LSS parameters**".

Save communication parameters	1010h	2	UNSIGNED32	rw
--------------------------------------	--------------	----------	------------	----

Permanently saves all changeable objects from the "communication profile area (1000-1FFF)" to the non-volatile memory of the device.

Save application parameters	1010h	3	UNSIGNED32	rw
------------------------------------	--------------	----------	------------	----

Permanently saves all changeable objects from the "standardised profile area (6000-9FFF)" to the non-volatile memory of the device.

Save LSS parameters	1010h	4	UNSIGNED32	rw
----------------------------	--------------	----------	------------	----

Permanently saves the first section of the changeable objects from the "manufacturer-specific profile area (2000-20FF)" to the non-volatile memory of the device.



Changes to the "Node ID" and "Baud rate" are saved permanently only if this function is activated. The change, however, will only become effective after device restart.

Restore default parameters	1011h	ARRAY
-----------------------------------	--------------	-------

To restore factory settings, this should be written onto one of the sub-entries of this object, see chapter 4.5.1.3 *Objects serving as functions*.

The character string "load" is the function activating value for all "Restore" functions.

When accessing as a *UNSIGNED32* value, the character string "load" will be represented by the numerical value 64616F6Ch.

Caution: When performing the SDO command, please observe the order of the steps, see chapters 2.3 *Bit order* and 4.6.1 *SDO*.

Byte 4	Byte 5	Byte 6	Byte 7
0x6C	0x6F	0x61	0x64
"l"	"o"	"a"	"d"

Highest sub-index supported	1011h	0	UNSIGNED8	const
------------------------------------	--------------	----------	-----------	-------

Name	Index	Sub	Type	Acc.	PDO
Number of supported sub-entries of the object.					
Four different functions, which are separated depending on parameter sections, are supported for restoring the factory settings.					
Restore all default parameters	1011h	1	UNSIGNED32	rw	
Restoring without limitation of the parameter section.					
 Particularity: Settings in "Node ID" and "Baud rate" will be maintained when opening this function. For restoring of these settings, call up the function "RestoreLssParameters".					
Restore communication default parameters	1011h	2	UNSIGNED32	rw	
Restores all factory settings from the "Communication profile area (1000-1FFF)" section.					
Restore application default parameters	1011h	3	UNSIGNED32	rw	
Restores all factory settings from the "Standardised profile area (6000-9FFF)" section.					
Restore LSS default parameters	1011h	4	UNSIGNED32	rw	
Restores the factory settings for the first part of the "Manufacturer-specific profile area (2000-20FF)".					

4.5.4.4. Communication parameters (General communication objects)

Object index range: 1000h – 1029h

In this section, the objects which provide information on the device itself or on the device status (e.g. error management) are summarised. In addition, the basic settings for transmission services and functions for permanent storage of settings are contained herein.

Name	Index	Sub	Type	Acc.	PDO
COB-ID SYNC	1005h	0	UNSIGNED32	rw	
Message ID for the identification of the synchronous message during synchronous process data transmission; see chapter 4.6.2.2 SYNC. This message should be assigned a high priority, in order to keep the latency caused by other messages low.					
Standard settings: 80h (128d)					

Name	Index	Sub	Type	Acc.	PDO
COB-ID emergency message	1014h	0	UNSIGNED32	rw	

Message ID for sending the *EMCY message* (Emergency).

If the COB-ID is set via a *SDO command* to a particular CAN-ID, the mechanism for the automatic expansion of the COB-ID by an active Node ID is deactivated. In this case, the predetermined CAN ID will always be used for the transmission of an EMCY, regardless of the Node ID. If the COB ID is set = 0, the default settings will become effective again.

Standard settings: \$NODEID+80h.

Producer heartbeat time	1017h	0	UNSIGNED16	rw
--------------------------------	--------------	---	------------	----

Activate/deactivate heartbeat "Producing"

The device is able to send heartbeat messages on a cyclic basis; see chapter 4.4.3 *Heartbeat*.

- 0** No heartbeat messages will be sent
- >0** Time interval in [ms] for cyclic heartbeat messages

4.5.4.5. CANopen safety objects

Object index range: 1300h – 13FFh

The devices described in this documentation (see chapter 1.1 *Scope of applications*) do not support functionally safe communication.

4.5.4.6. RPDO communication parameter

Object index range: 1400h – 15FFh

This range defines in which way a RPDO (i.e. process data received from the device) will be transmitted.

Whether this measurement system supports RPDO communication is defined by the amount of process data objects in the specified part of this documentation. See chapter 3.5.4.1 *Number of the process data object* supported by the device..

For a general description of the PDO transmission; please see chapter 4.6.2 *PDO*.

To change the PDO mapping, a defined process has to be adhered to; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

	The max. amount of possible RPDO is firmly defined by the device, see chapter 3.5.4.1 <i>Number of the process data object supported by the device..</i>
	The first "RPDO communication parameter" has the index 1400, the second one has 1401 and so on. The following section describes the first object, the structure of further possible objects corresponds with this description.

Name	Index	Sub	Type	Acc.	PDO
RPDO communication parameter 1	1400h		<i>RECORD</i>		
<hr/>					
Highest sub-index supported	1400h	0	UNSIGNED8	const	
<hr/>					
The "RPDO communication parameter" Object supports max. 5 (CiA 301 max: 6) different sub entries which do not forcibly have to be definded.					
COB ID	1400h	1	UNSIGNED32	rw	
<hr/>					

COB-ID for the calculation of the operating CAN ID under which the RPDO will be accepted and received.

If the COB-ID is set via a *SDO command* to a particular CAN-ID, the mechanism for the automatic expansion of the COB-ID by an active Node ID is deactivated. In this case, the predetermined CAN ID will always be used for the transmission of an RPDO, regardless of the Node ID. If the COB ID is set = 0, the default settings will become effective again.

By setting Bit 31 of the COB-ID, the RPDO can be deactivated, it will no longer be received afterwards; i. e. \$NODEID+80000200h.

Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	Bit	
31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5
Invalid	Reserved	Extended																								0
0	0	0																								11 Bit CAN-ID
0	0	1																								29 Bit CAN-ID

Extended **0: 11 Bit CAN-ID** 1: 29 Bit CAN-ID

Invalid **0: PDO ist aktiv** 1: PDO ist nicht aktiv

Name	Index	Sub	Type	Acc.	PDO
Standard settings: \$NODEID+200h.					
Transmission type	1400h	2	UNSIGNED8	rw	

This parameter defines the transmission type.

- 0 acyclic synchronous
- 1 synchron with each SYNC
- 2 synchronous with every 2nd SYNC
- n - 240 synchronous with every nth SYNC
- 254 event-controlled manufacturer-specific event options
- 255 event-controlled device-specific event options

For 254 and 255, see chapters 4.6.2.1 *Event driven* and 3.6.3 *device-specific PDO events*.

Standard default settings: 254

Inhibit time	1400h	3	UNSIGNED16	rw
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Minimum delay for the RPDO processing as a multiple of 100 µs. The value 0 will deactivate this blocking period.

The value may be device-specific; see chapter 3.5.1 *Configuration* parameters.

Event timer	1400h	5	UNSIGNED16	rw
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Monitoring interval for RPDO processing. When the timer is set (> 0) the time between two RPDOs will be measured and reported to the device software, if exceeded.

The time is defined as a multiple of 1 ms.

4.5.4.7. RPDO mapping parameter

Object index range: 1600h – 17FFh

This range defines which actual process value parameter objects will be transmitted within one of the available RPDOs.

Whether this measurement system supports RPDO communication is defined by the amount of process data objects in the specified part of this documentation. See chapter 3.5.4.1 *Number of the process data object* supported by the device..

Objects which are used for transmission are indicated by the object characteristic "PDOMapping" = 1 (TRUE), see chapter 4.5.1.4 *Object serving as process data content*.

For a description of the PDO transmission, please see chapter 4.6.2 *PDO*.

For a detailed description of the "PDO mapping" structure, see chapter 4.6.2.3 *PDO Mapping*.

To change the PDO mapping, a defined process has to be adhered to; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

	The max. amount of possible RPDO is firmly defined by the device, see chapter 3.5.4.1 <i>Number of the process data object supported by the device..</i>
	The first "RPDO mapping parameter" has the index 1600, the second one has 1601 and so on. The following section describes the first object, the structure of further possible objects corresponds with this description.

Name	Index	Sub	Type	Acc.	PDO
RPDO mapping parameter 1	1600h		<i>RECORD</i>		

Each available RPDO has its own structure for the definition of the process value parameter objects to be transmitted by this PDO.

The "RPDO mapping parameter" object usually supports up to 8 + 1 different sub-entries. The first entry defines the amount of valid sub-entries, which means, the values to be transmitted subsequently (process value parameters).

Number of mapped objects in PDO	1600h	0	UNSIGNED8	rw
--	--------------	----------	------------------	-----------

The value of this object defines how many of the subsequent sub-entries are valid, which means, how many process value parameter objects will be transmitted in this RPDO.

If the content of this object is set to = 2, for instance, the first two of the subsequent sub-index objects must have a valid *Process value parameter object reference*. In that structure, the entries need to be filled in a strictly sequential order and without leaving any gaps.

If the object is set to = 0 (1600.0 = 0) the transmission of the RPDO is deactivated.

Important note: Before there can be changes to the PDO mapping, the PDO transmission has to be deactivated; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

Name	Index	Sub	Type	Acc.	PDO
1st object to be mapped	1600h	1	UNSIGNED32		rw

First reference object for the definition of the process value parameter object which will be transmitted by the RPDO; "Number of mapped objectsW" ≥ 1 .

The byte position in the *Data block of the CAN message* of the RPDO is byte 0. The required data length in the CAN data block depends on the *Data length of the data type* of the referenced process value parameter object.

Which process value parameter object will actually be referenced, is encoded in the object content, that is why it is subdivided into 3 sections:

1A00h	1	UNSIGNED32 [32 Bit]
Object reference	Object index [16 Bit]	sub-index [8 Bit]
Example	5200	01

Example: **1600.1 = 52000110h → 5200.1 [INTERGER16]**

Name	Index	Sub	Type	Acc	PDO
Velocity values X	5200h	1	INTEGER16	rww	RP

Graphic representation of that context; see chapter 4.6.2.4 Overview diagram PDO mapping.

2nd object to be mapped	1600h	2	UNSIGNED32	rw
---	--------------	----------	-------------------	-----------

"Number of mapped objects" ≥ 2 ; Reference to the second process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the RPDO is calculated depending on the previous object.

nth object to be mapped	1600h	n: [3, 7]	UNSIGNED32	rw
---	--------------	------------------	-------------------	-----------

"Number of mapped objects" $\geq n$; Reference to the n-th process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the RPDO is calculated depending on the previous object.

8th object to be mapped	1600h	8	UNSIGNED32	rw
---	--------------	----------	-------------------	-----------

"Number of mapped objects" ≥ 8 ; Reference to the eighth process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the RPDO is calculated depending on the previous object.

4.5.4.8. TPDO communication parameter

Object index range: 1800h – 19FFh

This range defines in which way a TPDO (i.e. process data sent by the device) will be transmitted.

For a general description of the PDO transmission; please see chapter 4.6.2 *PDO*.

To change the PDO mapping, a defined process has to be adhered to; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

	The max. amount of possible TPDO is firmly defined by the device, see chapter 3.5.4.1 <i>Number of the process data object supported by the device..</i>
	The first "TPDO communication parameter" has the index 1800, the second one has 1801 and so on. The following section describes the first object, the structure of further possible objects corresponds with this description.

Name	Index	Sub	Type	Acc.	PDO
TPDO communication parameter 1	1800h		<i>RECORD</i>		
Each available TPDO has its own structure for the definition of its individual transmission type.					
Highest sub-index supported	1800h	0	UNSIGNED8	const	
The "TPDO communication parameter" object supports max. 5 (CiA 301 max: 6) different sub entries which do not forcibly have to be definded.					

Name	Index	Sub	Type	Acc.	PDO
COB ID	1800h	1	UNSIGNED32	rw	

COB-ID for the calculation of the operating CAN ID under which the TPDO will be sent.

If the COB-ID is set via a *SDO command* to a particular CAN-ID, the mechanism for the automatic expansion of the COB-ID by an active Node ID is deactivated. In this case, the predetermined CAN ID will always be used for the transmission of an TPDO, regardless of the Node ID. If the COB ID is set = 0, the default settings will become effective again.

By setting Bit 31 of the COB-ID, the TPDO can be deactivated, it will no longer be transmitted afterwards; i. e. \$NODEID+C0000180h.

Extended **0: 11 Bit CAN-ID** 1: 29 Bit CAN-ID

No RTR 0: RTR permitted **1: RTR access not permitted** (automatically set when writing)

Invalid **0: PDO ist aktiv** 1: PDO ist nicht aktiv

Standard settings: \$NODEID+40000180h.

Note: RTR Communication should no longer be used according to CiA and is therefore deactivated, which means, it can no longer be set.

Transmission type 1800h 2 UNSIGNED8 rw

This parameter defines the transmission type.

- | | | |
|---------|--|-------------|
| 0 | acyclic | synchronous |
| | Internal signal processing not synchronous with SYNC; Transmission of the message synchronous with SYNC. | |
| 1 | Internal signal processing not synchronous with SYNC; Transmission of the message synchronous with any SYNC. | |
| 2 | Transmission of the message synchronous with any second SYNC. | |
| n - 240 | Transmission of the message synchronous with any nth SYNC. | |
| 254 | (FEh) Event-controlled manufacturer-specific event options | |
| 255 | (FFh) Event-controlled device-specific event options | |
| | For 254 and 255, see chapters 4.6.2.1 <i>Event driven</i> and
3.6.3 <i>device-specific PDO events</i> . | |

Standard default settings: 254

Name	Index	Sub	Type	Acc.	PDO
Inhibit time	1800h	3	UNSIGNED16	rw	

In the case of an active "Transmission type" 254 or 255, this parameter defines the minimum waiting delay before a TPDO is sent after an event has occurred. The amount of sent TPDO can consequently be reduced in the case of a frequently occurring event.

- 0 The value 0 deactivates the minimum waiting delay.
- >0 The time is defined as a multiple of 100 µs.

Event timer	1800h	5	UNSIGNED16	rw
-------------	-------	---	------------	----

In the case of an active "Transmission type" 254 or 255, this parameter defines the time interval for triggering a "timer event" which leads to sending the TPDO.

If the device has device-specific events, the TPDO will be sent at the latest by the expiry of that time period, if no other events will occur; see chapters 4.6.2.1 *Event driven* and 3.6.3 *device-specific PDO events*.

- 0 Sending of the TPDO is deactivated.
- >0 The event interval as a multiple of 1 ms.

4.5.4.9. TPDO mapping parameter

Object index range: 1A00h – 1BFFh

This range defines which actual process value parameter objects will be transmitted within one of the available TPDOs.

Objects which are used for transmission are indicated by the object characteristic "*PDOMapping*" = 1 (TRUE), see chapter 4.5.1.4 *Object serving as process data content*.

For a description of the PDO transmission, please see chapter 4.6.2 *PDO*.

For a detailed description of the "PDO mapping" structure, see chapter 4.6.2.3 *PDO Mapping*.

To change the PDO mapping, a defined process has to be adhered to; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

	The max. amount of possible TPDO is firmly defined by the device, see chapter 3.5.4.1 <i>Number of the process data object supported by the device..</i>
	The first "TPDO mapping parameter" has the index 1A00, the second one has 1A01 and so on. The following section describes the first object, the structure of further possible objects corresponds with this description.

Name	Index	Sub	Type	Acc.	PDO
TPDO mapping parameter 1	1A00h		<i>RECORD</i>		

Each available PDO has its own structure for the definition of the process value parameter objects to be transmitted by this PDO.

The "TPDO mapping parameter" object usually supports up to 8 + 1 different sub-entries. The first entry defines the amount of valid sub-entries, while the following entries define the values to be transmitted subsequently (process value parameters).

Number of mapped objects in PDO	1A00h	0	UNSIGNED8	rw
--	--------------	----------	------------------	-----------

The value of this object defines how many of the subsequent sub-entries are valid, which means, how many process value parameter objects will be transmitted in this PDO.

If the content of this object is set to = 2, for instance, the first two of the subsequent sub-index objects must have a valid *Process value parameter object reference*. In that structure, the entries need to be filled in a strictly sequential order and without leaving any gaps.

If the object is set to = 0 (1A00.0 = 0) the transmission of the PDO is deactivated.

Important note: Before there can be changes to the PDO mapping, the PDO transmission has to be deactivated; see chapter 4.6.2.5 *Process flow sequence to change the "PDO mapping"*.

Name	Index	Sub	Type	Acc.	PDO
1st object to be mapped	1A00h	1	UNSIGNED32		rw

First reference object for the definition of the process value parameter object which will be transmitted by the TPDO; "Number of mapped objectsW" ≥ 1 .

The byte position in the *Data block of the CAN message* of the TPDO is byte 0. The required data length in the CAN data block depends on the *Data length of the data type* of the referenced process value parameter object.

Which process value parameter object will actually be referenced, is encoded in the object content, that is why it is subdivided into 3 sections:

1A00h	1	UNSIGNED32 [32 Bit]		
Object reference		Object index [16 Bit]	sub-index [8 Bit]	Data length [8 Bit]
Example		6010	00	10h

Example: **1A00.1 = 60100010h → 6010.0 [INTERGER16]**

Name	Index	Sub	Type	Acc	PDO
Slope long16	6010h	0	INTEGER16	ro	TP

1A00.1 = 60040020h → 6004.0 [INTERGER32]

Name	Index	Sub	Type	Acc	PDO
Position value	6004h	0	INTEGER32	ro	TP

Graphic representation of that context; see chapter 4.6.2.4 Overview diagram PDO mapping.

2nd object to be mapped	1A00h	2	UNSIGNED32	rw
---	--------------	----------	-------------------	-----------

"Number of mapped objects" ≥ 2 ; Reference to the second process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the TPDO is calculated depending on the previous object.

nth object to be mapped	1A00h	n: [3, 7]	UNSIGNED32	rw
---	--------------	------------------	-------------------	-----------

"Number of mapped objects" $\geq n$; Reference to the n-th process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the TPDO is calculated depending on the previous object.

8th object to be mapped	1A00h	8	UNSIGNED32	rw
---	--------------	----------	-------------------	-----------

"Number of mapped objects" ≥ 8 ; Reference to the eighth process value parameter object to be transmitted.

The position in the *Data block of the CAN message* of the TPDO is calculated depending on the previous object.

4.5.4.10. NMT master objects

Object index range: 1F80h – 1F89h

The objects defining the network behaviour of the devices are described herein.

Name	Index	Sub	Type	Acc.	PDO
NMT startup	1F80h	0	UNSIGNED32	rw	

Defining the start behaviour of the device; see also chapter *4.4 Network Management*.

Bit 2 0: Device remains in the "Pre-Operational" state after successful initialisation and waits for a "Start Node" command.

1: Device automatically switches to "Operational" state after successful initialisation.

Note: This behaviour does not correspond with the definition in the CiA 302 Part 2, the logic has been inverted with respect to the behaviour described therein.

Bit 3 1: always needs to be set.

Bit x 0: all further bit may not be set.

0000 0008h → 8d device waits in "Pre-Operational" (common default settings)

0000 000Ch → 12d Device automatically switches to "Operational" state.

4.5.5. manufacturer-specific profile area

Object index range: 2000 – 5FFF

manufacturer-specific objects are usually device-specific as well. In this chapter the objects are described, which are normally always supported by the devices.

4.5.5.1. Node ID and Baud rate

The management of the two most important CANopen device settings is unfortunately not exactly specified in the CiA 301. The most common implementation used by HYDAC Filtertechnik GmbH is described below.



Some older devices and devices which are part of the HPT 1000 and HTT 1000 series by HYDAC Filtertechnik GmbH have functions for the configuration of the Node ID and Baud rate which may differ from the functions in the description below.

Possible differences are described in the device-specific part of the documentation in chapter *3.5.2 Manufacturer-specific configuration parameters*.

In addition, the devices provide the configuration of the Node ID and Baud rate via the LSS protocol, see chapter *4.7 Layer setting services (LSS) Protocol*.

Name	Index	Sub	Type	Acc.	PDO
Node ID	2001h		ARRAY		

Object for the device address management; see chapter 4.4 *Network Management*.

The standard setting of the device address is described in chapter 3.1.1 *CANopen default settings*.

Note:

Some of the HYDAC Filtertechnik GmbH sensors (e.g. pressure or temperature) may still support an older implementation of the node ID object 2001h. If the implementation should differ, please see chapter 3.5.2 *Manufacturer-specific configuration parameters*.

Highest sub-index supported	2001h	0	UNSIGNED8	ro
------------------------------------	--------------	----------	-----------	----

For the management of the device address, there are two objects available.

Active node-ID	2001h	1	UNSIGNED8	ro
-----------------------	--------------	----------	-----------	----

Currently active device address; read only

Pending node-ID	2001h	2	UNSIGNED8	rw
------------------------	--------------	----------	-----------	----

Desired change of device address

Changes of this entry will not take effect until they have been saved into the non-volatile memory (see chapters **Store parameters** and **Save LSS parameters**) and the device has been restarted "Reset Node" command or its power supply has been cut.

The values of the objects 2001.1 and 2001.2 are identical under normal operation. Should there be a request for a new device address when the changes have not yet become active, the two objects will be assigned different values.

Baud rate	2002h	ARRAY
------------------	--------------	-------

Object for the device Baud rate; see chapter 4.2.5 *Transmission speed*.

The values of this object correspond with the DS 305 "Layer Setting Services and Protocols".

- | | |
|---|---|
| 0 | 1000 kbit/s |
| 1 | 800 kbit/s |
| 2 | 500 kbit/s |
| 3 | 250 kbit/s |
| 4 | 125 kbit/s |
| 5 | 100 kbit/s CiA 305: reserved (not supported by each device) |
| 6 | 50 kbit/s |
| 7 | 20 kbit/s |
| 8 | 10 kbit/s |

The standard configuration of the Baud rate is described in chapter 3.1.1 *CANopen default settings*.

Note:

Some of the HYDAC Filtertechnik GmbH sensors (e.g. pressure or temperature) may still support an older implementation of the Baud rate object 2002h. If the implementation should differ, please see chapter 3.5.2 *Manufacturer-specific configuration parameters*.

Name	Index	Sub	Type	Acc.	PDO
Highest sub-index supported	2002h	0	UNSIGNED8	ro	
For the management of the Baud rate, there are two objects available.					
Active baudrate	2002h	1	UNSIGNED16	ro	
Currently active Baud rate; read only					
Pending baudrate	2002h	2	UNSIGNED16	rw	
Desired change of Baud rate					
Changes of this object will not take effect until they have been saved into the non-volatile memory (see chapters <i>Store parameters</i> and <i>Save LSS parameters</i>) and the device has been restarted " <i>Reset Node</i> " command or its power supply has been cut.					
Checksum	2010h	0	UNSIGNED32	ro	
The checksum of the current device software.					

4.5.5.2. Additional manufacturer-specific measurement channels

Some devices offer additional measurement channels which complete the standard measurement variables, such as pressure in a pressure sensor, which increases the benefit of the device. Additional manufacturer-specific measurement channels are able to provide "real" measurement signals with a defined specification in the data sheet, such as accuracy or temperature coefficient, but also internal signals, such as the device temperature.



The device-specific section of the documentation under chapter 3.5.5 *Additional manufacturer-specific measurement channels*. also provides information on whether a device has manufacturer-specific measurement channels or which measured variable corresponds to which "sub-index" or which channel settings are actually supported by the respective measurement channel.

The process values of the additional manufacturer-specific measurement channels can be transferred via a *TPDO*.

However, this type of measurement channels will not be supported at all or at least not fully supported by each device, which means, the objects listed below may be only partly available or not at all. If these objects, however, are provided by a device, their significance corresponds with the description below. The function principle of the objects is based on the device profile CiA 404.

The table shows an example for a device with an additional, manufacturer-specific measurement channel. In devices with several channels, only the amount of "sub-indices" is higher – 3610.1 would represent the first channel, 3610.2 would be the second channel, and so on.

To enable easy further processing, the signal value of an additional manufacturer-specific measurement channel will be provided multiple and simultaneously as *Process value*, in objects with varying *Data types*:

- **36xy.z** *REAL32* → first signal value: **3610.1** ...
- **37xy.z** *INTEGER16* → first signal value: **3710.1** ...
- **39xy.z** *INTEGER32* → first signal value: **3910.1** ...

The configuration parameter options are shown using the REAL32-Objects (**36xy.z**). The object structure of the other data types corresponds with the structure of this data type, however, the objects may partly be omitted.

Name	Index	Sub	Type	Acc.	PDO
MS input MV	3610		ARRAY		
The object provides the signal values/measured values of the additional manufacturer-specific measurement channels.					
Highest sub-index supported	3610	0	UNSIGNED8	ro	
The number of "sub-index" objects corresponds with the number of the manufacturer-specific measurement channels provided by the device.					
MS input MV 1	3610	1	REAL32	ro	TP
Current signal value of the first manufacturer-specific device measurement channel.					
MS input MV 2	3610	2	REAL32	Ro	TP
Example for an eventually existing manufacturer-specific measurement channel.					
MS input scaling 1 MV	3611		ARRAY		
Lower measurement range limit of an additional manufacturer-specific measurement channel. The value indication is represented in the unit of the measurement channel, i.e.:					
-40	-40 °C as the lower temperature measurement range				
0	0 bar the lower pressure measurement range				
Highest sub-index supported	3611	0	UNSIGNED8	ro	
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS input scaling 1 MV 1	3611	1	REAL32	ro	
Lower measurement range limit of the first additional manufacturer-specific measurement channel.					
... further "sub-index" entries possible					
MS input scaling 2 MV	3612		ARRAY		

Name	Index	Sub	Type	Acc.	PDO
Upper measurement range limit of an additional manufacturer-specific measurement channel. The value indication is represented in the unit of the measurement channel, i.e.: 125 +125 °C as the upper temperature measurement range 600 600 bar as the upper pressure measurement range					
Highest sub-index supported	3612	0	UNSIGNED8		ro
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS input scaling 2 MV 1	3612	1	REAL32		ro
Upper measurement range limit of the first additional manufacturer-specific measurement channel. ... further "sub-index" entries possible					
MS status	3613		ARRAY		
Status information for an additional manufacturer-specific measurement channel. The significance of a status word depends on the device.					
Highest sub-index supported	3613	0	UNSIGNED8		const
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS status 1	3613	1	UNSIGNED8	ro	TP
Status information for the first additional manufacturer-specific measurement channel. ... further "sub-index" entries possible					
MS decimal digits MV	3614		ARRAY		
Number of decimals of the additional manufacturer-specific measurement channel.					
Highest sub-index supported	3614	0	UNSIGNED8		const
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS decimal digits MV 1	3614	1	UNSIGNED8	rw	
Number of decimals of the first additional manufacturer-specific measurement channel. ... further "sub-index" entries possible					
MS input offset	3615		ARRAY		
Zero-offset (value offset) of the additional manufacturer-specific measurement channel.					
Highest sub-index supported	3615	0	UNSIGNED8		const
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS input offset 1	3615	1	REAL32	rw	

Name	Index	Sub	Type	Acc.	PDO
Zero-offset (value offset) of the first additional manufacturer-specific measurement channel.					
... further "sub-index" entries possible					
MS autozero	3616		ARRAY		
Use the current signal value of the additional manufacturer-specific measurement channel as offset.					
When performing a default offset adjustment, the content of the object "MS input offset" will be set to the current, corresponding signal value (current content of the object "MS input MV") at the moment of opening this object.					
This object is a <i>Function object</i> and is activated via writing the <i>Character String</i> "zero" (6F72657Ah); see chapter 4.5.1.3 <i>Objects serving as functions</i> .					
Highest sub-index supported	3616	0	UNSIGNED8	const	
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS autozero	3616	1	UNSIGNED32	WO	
Activate default zero-offset (value offset) of the first additional manufacturer-specific measurement channel.					
... further "sub-index" entries possible					
MS physical unit MV	3617		ARRAY		
Inquire physical unit of the additional manufacturer-specific measurement channel. The unit will be provided as SI unit according to CiA 303-2.					
Standard physical units are:					
004E0000h	bar				
00AB0000h	PSI				
002D0000h	°C				
00AC0000h	°F				
Highest sub-index supported	3617	0	UNSIGNED8	const	
Corresponds with the number of the manufacturer-specific device measurement channels.					
MS physical unit MV 1	3617	1	UNSIGNED32	ro	
Inquire physical unit of the first additional manufacturer-specific measurement channel.					
... further "sub-index" entries possible					

4.5.6. Standardized profile area

Object index range: 6000h – 9FFFh

For a general description of a device profile, please read the corresponding publication by CiA (i.e. "CiA 410 Device profile for inclinometer").

See chapter 3.1.2 *Device profile* of the device-specific section in the documentation to learn which device profile is supported by the used device.

If a device should show deviations from a device profile, the related explanation can be found in chapter 3.5.3 *Device profile-specific* parameters.

4.5.7. EDS Electronic Data Sheet

The "Electronic data sheet", abbreviation: "EDS file" / "EDS", is a machine readable description of the OD, see chapter 4.5 *The Object Dictionary*. All objects supported by the device are listed herein. Each object has a multi-line entry for its own description.

In the headline of the EDS, general information is given on the file itself and also for the device which is described by the file.

The individual objects are listed in blocks and will always be launched by an object index. Each index has its individual description block. If the index has several different sub-entries (sub-index) these have their own description block automatically as well.

4.5.7.1. Description of the most important EDS entries

Below, the most important entries and the related most important meanings of an EDS file are listed.

Identifier	Content	Description
[<objektindex>]	[1000]	Object index of the following description block; [1000] → <i>DeviceType</i> . see chapter 4.5.1.1° <i>Addressing</i>
	[1003sub4]	→ 1003.4 Sub-entry of the object " <i>Pre-defined error field</i> "
ParameterName		Object name
ObjectType		Object property This entry defines which property this object entry has.
	07h	VAR Object is a variable
	08h	ARRAY Object is a data structure of the Array type and therefore, it consists of further entries having the same data type.
	09h	RECORD Object is a data structure of the Record/Structure type and therefore, it consists of further entries having different data types.
DataType		Object data type In objects of the "ObjectType = 7h", the data type defines how the object is going to be stored in the memory. This information is important for reading and writing the object; see chapter 4.6.1 <i>SDO</i> .

Identifier	Content	Description		
	0002h	<i>INTERGER8</i>	signed integer 8 bits	
	0003h	<i>INTERGER16</i>	signed integer 16 bit	
	0004h	<i>INTERGER32</i>	signed integer 32 bit	
	0005h	<i>UNSIGNED8</i>	unsigned integer 8 bits	
	0006h	<i>UNSIGNED16</i>	unsigned integer 16 bit	
	0007h	<i>UNSIGNED32</i>	unsigned integer 32 bit	
	0008h	<i>REAL32</i>	Floating point 32 bit	
	0009h	<i>STRING</i>	Character String	
AccessType	ro, rw, rwr, rww, wo, const	Object see chapter 4.5.1.2 <i>Object access types</i>	access	authorisation
DefaultValue		Object content at delivery (pre-configuration)		
PDOMapping	0 / 1	Can the object be used as a process data value? see chapters 4.5.1.4 <i>Object serving as process data content</i> and 4.6.2.3 <i>PDO Mapping</i>		
BaudRate_xxx _10 .. _1000	0 / 1	Definition of the <i>Baud rates</i> supported by the device. Is the actual value "= 1" (TRUE) set, the Baud rate will be set accordingly.		
NrOfRXPDO	0 ... 64	Max number of <i>RPDO objects</i> supported by the device.		
NrOfTXPDO	0 ... 64	Max number of <i>TPDO Objects</i> supported by the device.		
LSS_Supported	0 / 1	Is the <i>LSS Protocol</i> supported by the device? "= 1" (TRUE) the device supports LSS		

4.5.7.2. EDS file example

The following is an extract of an EDS file. The individual object 1001.0 "*Error register*" and the *RECORD* object 1018 "*Identity object*" are listed as object examples.

```
[FileInfo]
FileName=HE-926037-0008.eds
...
[DeviceInfo]
VendorName=HYDAC Filtertechnik GMBH
ProductNumber=926037
...
[1001]
```

```
ParameterName=Error register
ObjectType=0x7
DataType=0x5
AccessType=ro
PDOMapping=1
...
[1018]
ParameterName=Identity object
ObjectType=0x9
[1018sub0]
ParameterName=Highest sub-index supported
ObjectType=0x7
DataType=0x5
AccessType=const
DefaultValue=4
[1018sub1]
ParameterName=Vendor-ID
ObjectType=0x7
DataType=0x7
AccessType=ro
DefaultValue=218
```

4.6. Application data

CANopen provides different types of data communication. Each of these communication types will not be available at each operation condition; see chapter 4.4.1 *Overview network conditions*.

4.6.1. SDO

SDO, abbr. for "Service data object" offers the opportunity for direct access to the individual objects in the OD; see chapter 4.5 *The Object Dictionary*.

It is possible to have read only and read/write access to the object. During access, the object address serves as an indicator, which object the access should be given to; see chapter 4.5.1.1 *Addressing*.

Whether access will be permitted or not to a particular object, can be determined from the object authorisation (see chapter 4.5.1.2 *Object access types*) and from the current operation status of the device. See chapter 4.4.1 *Overview network conditions*.

The data type of the object (see chapter 4.5.7 *EDS Electronic Data Sheet* and *DataType*) controls the process of the SDO communication. All objects whose data type is 32 bit and shorter can be read or written to directly by means of a single SDO command "expedited", i.e. *INTEGER32* or *REAL32*. Objects whose data type is longer than 32 bit have to be read or written to via a sequence of interrelated commands "segmented".

For the SDO the Client/Server access is used as a communication type, see chapter 4.3.5.3 *Request – Response*. The server is always the network participant, whose objects will be accessed - which is the device to write on in this case. The client is usually a superordinate control intending to parameterise or configure the device, for instance.

The client communicates a "request" command to the server, saying what it is intending to do and the server always responds by sending a "response" command, indicating whether the access has been successful or if an error has occurred, see chapter *4.6.1.5 SDO abort transfer (abort)*.

4.6.1.1. Structure of the SDO command

Below, please find a description of the general structure of all SDO messages. The commands depends on the used access type.



The particular COB-ID of the SDO corresponds to the "Pre defined Connection Set" defined in the CiA 301 and cannot be altered.

In below examples, Node ID = 1 will always be used on the server side (device).

Field name	Content	Meaning
COB ID	600h + Node-ID	COB-ID des SDO-Request (Client→Server) [Tx: ECU → Device] The CAN ID is calculated during operation from the basic CAN ID and the Node ID. Example: Node-ID = 1; 600h + 1h = 601h
COB ID	580h + Node-ID	COB-ID of the SDO response (Server→Client) [Rx: Device → ECU] Example: Node-ID = 1; 580h + 1h = 581h
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code The command code is crucial for the definition of the data communication process. The command word is bit-encoded and marks the function, the error state and in parts the amount of user data in the current message.
BYTE 1, 2	Index	Object index of the object to be accessed; see 4.5.1.1 Addressing and 2.3 Bit order. Data type: <i>UNSIGNED16</i>
BYTE 3	Sub index	sub-index of the sub-entry; if no sub-entry exists, this entry will be set to 0. Data type: <i>UNSIGNED8</i>
BYTE 4 - 7	Data	User data, error information or 0

Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
Com- mand	Index		Sub- index	Data			
Low- byte	High- byte						

4.6.1.2. SDO Upload (expedited) [read]

If the client (control) intends to read an object from the server (device), this access can be initiated using the "SDO upload request" command.

For this purpose, the client transfers the *Object address* it intends to read to the server and receives the data or an error message, which have been read from the object, in return.

However, the response from the server may vary, depending on the data length of the object to be read out. If the **data length is <= 32 Bit** the command processing will take place in the so-called "**expedited**" mode, i.e. the response from the server directly contains the data of the requested object, as explained below.

If the data length of the object to be read out is **> 32 bit**, the communication is carried out in the so-called "**segmented**" mode. The distinction is made via the command recognition of the "server response"; see chapter *4.6.1.3 SDO Upload (segmented) [read]*.

When showing the object address or the data on the data section of the message, the *Bit order* has to be adhered to.

The example shows a SDO read access to the object [1018.2 "Product code"](#). The addressed object is a *UNSIGNED32* value and can therefore be read out in the "expedited" mode. The content of the object is the part number of the device.

- Part number = 926037d → **E2155h**.
- CMD SDO Command code
- **IdxLB** Object **index Low-Byte** (Byte 1, 2: *UNSIGNED16*)
- **IdxHB** Objekt**index High-Byte**
- **SIdx** Objekt-**Subindex**

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	IdxLB	IdxHB	SIdx	Data 1	Data 2	Data 3	Data 4
601h _{Tx}	40h	18h	10h	02h	00h	00h	00h	00h
581h _{Rx}	43h	18h	10h	02h	55h	21h	0Eh	00h

SDO command codes (CMD) **SDO Upload (expedited) [read]**

Command	Direction	Description
40h	Request	Reading out object from given index
4Fh	Response	1 byte has been read out successfully
4Bh	Response	2 byte has been read out successfully
47h	Response	3 byte has been read out successfully
43h	Response	4 byte has been read out successfully
41h	Response	Object is readable, but its data length is longer than 32 bits (4 Bytes). see chapter <i>4.6.1.3°SDO Upload (segmented) [read]</i>

Command	Direction	Description
80h	Response	Errors, see chapter 4.6.1.5 SDO abort transfer (abort)

D

4.6.1.3. SDO Upload (segmented) [read]

A few of the objects of the devices will be represented by data types of more than 32 Bits of length. These objects often contain *STRING variables*. In order to read such an object, a sequence of interrelated SDO commands is required. Each step of the sequence always follows the "*Request – Response*" concept of data communication. This process is also referred to as the SDO "segmented" upload.

The sequence will be initiated by a standard read request, see chapter 4.6.1.2 *SDO Upload (expedited) [read]*. The server recognises if the object to be read has more than 32 bit of data length by means of the *Object address*. This is why it responds to the client using a particular SDO response, which contains the length of the data of the addressed object in bytes, instead of the read object data. After sending, the server waits for further "requests" by the client for inquiring the data of the addressed object.

The first data block has to be requested explicitly by the client from the server using a "SDO upload segmented request". The server responds using a "SDO upload segmented response" whose command code indicates that either further data need to be requested, or that the end of the sequence has been reached.

The "SDO upload segmented response" has a structure which deviates from other SDO commands (see chapter 4.6.1.1 *Structure of the SDO command*). It does not contain any *Object address*, but only the command code and the user data.

Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
Com- mand				Data			

As long as the client has not received any response having a set end code, it should inquire the missing data blocks using another request.

The received data have to be put together at the side of the client, to become a composed data block. The order of the arriving data is strictly sequential. Individual data blocks will not be repeated.

The server can terminate the communication using a *SDO abort command*. If an abort has been reported, the inquiry can be reinitiated using a read request.

One request remains "open" until either

- the end of the sequence is displayed,
- or the abort has been terminated by the server,
- or it has been reinitiated using a read request.

The below example shows how the object 100A "Manufacturer software version" is to be read out. This object has a *STRING* which may comprise more than 4 characters (32 bit).

Note: for a better comparison with the *ASCII encoding*, blanks have been added between the individual characters of the character string, which are not a part of the character string's content.

Character string: H 1 t c o V 9 0 . 0 2

ASCII: 48 6C 75 63 6F 20 20 20 56 39 30 2E 30 32

The sequence starts with an "upload request" and will be responded by the server using the code "segmented upload response". The length of the entire data block is reported using 0Eh → 14d Byte.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	IdxLB	IdxHB	SIdx	Data 1	Data 2	Data 3	Data 4
601h _{Tx}	40h	0Ah	10h	00h	00h	00h	00h	00h
581h _{Rx}	41h	0Ah	10h	00h	0Eh	00h	00h	00h

In the next step, the client inquires the first block of the data sequence. However, during this inquiry, the object address will not be repeated. The server sends the first 7 characters of the object content "H1tco ". The lowest value bit of the response command is not set and shows the client, that further data will follow.

601h _{Tx}	60h	00h						
581h _{Rx}	00h	48h	6Ch	74h	63h	6Fh	20h	20h

The client knows from the last response that further data need to be requested. The amount of data can be checked additionally by the client, as it has been informed on the total data length when receiving the first response.

In order to check the sequence order the client "toggles" Bit 4 of the request command with each new request: 60h → 70h → 60h → 70h ... The server itself checks the switching of the bit and reflects the current value to its response (response command recognition).

In this special example, the end of the total data block has been reached after having transferred the second "segmented" response ($14 / 7 = 2$). All user data bytes of the response are entirely used and the missing 7 characters will be transferred "V90.02". The software version is now complete → "Hltco V90.02".

601h Tx	70h	00h						
581h Rx	11h	20h	56h	39h	30h	2Eh	30h	32h

SDO command codes (CMD) **SDO Upload (segmented)** [read]

Command	Direction	Description
40h	Request	Reading out object from given index see chapter 4.6.1.2° <i>SDO Upload (expedited)</i> [read]
41h	Response	The object can be read and has the data length transferred in the data field in bytes; data type <i>UNSIGNED32</i> .
60h	Request	First "segmented" upload request and subsequently, after every second request. 60h → 70h → 60h → 70h ...
70h	Request	Second "segmented" upload request and following 70h → 60h → 70h ...
00h	Response	7 data bytes valid and read, transmission end not reached; response to request 60h.
10h	Response	7 data bytes valid and read, transmission end not reached; response to request 70h.
11h	Response	7 data bytes valid and read, transmission end has been reached; response to request 70h.
X3h	Response	6 data bytes valid and read, transmission end has been reached; X is 0 (03h) for request 60h and 1 (13h) for request 70h
X5h	Response	5 data bytes valid and read, transmission end has been reached; X is 0 (05h) for request 60h and 1 (15h) for request 70h
X7h	Response	4 data bytes valid and read, transmission end has been reached; X is 0 (07h) for request 60h and 1 (17h) for request 70h

Command	Direction	Description
X9h	Response	3 data bytes valid and read, transmission end has been reached; X is 0 (09h) for request 60h and 1 (19h) for request 70h
XBh	Response	2 data bytes valid and read, Transmission end has been reached; X is 0 (0Bh) for request 60h and 1 (1Bh) for request 70h
XDh	Response	1 data bytes valid and read, transmission end has been reached; X is 0 (0Dh) for request 60h and 1 (1Dh) for request 70h
80h	Response	Errors, see chapter 4.6.1.5 SDO abort transfer (abort)

CAN protocol example for reading out the object 1008.

1008.0 Manufacturer device name = "HLT 1300-R2-L06-F11-0100-0250-000"

```

CAN-ID (hex)
|   Direction: Tx (ECU → Device); Rx (Device → ECU)
|   |   Data Length
|   |   |   Data Bytes (hex)
|   |   |   |
+--- + - + - - - - - - - -
0601 Tx 8 40 08 10 00 00 00 00 00 00 SDO upload request
0581 Rx 8 41 08 10 00 21 00 00 00 00 SDO upload response
          segmented, data length 21h
0601 Tx 8 60 00 00 00 00 00 00 00 00 1st segmented request
0581 Rx 8 00 48 4C 54 20 31 33 30 1st segmented response
          HLT 130
0601 Tx 8 70 00 00 00 00 00 00 00 00 2nd segmented request
0581 Rx 8 10 30 2D 52 32 2D 4C 30 2nd segmented response
          0-R2-L0
0601 Tx 8 60 00 00 00 00 00 00 00 00 3rd segmented request
0581 Rx 8 00 36 2D 46 31 31 2D 30 6-F11-0
0601 Tx 8 70 00 00 00 00 00 00 00 00 4th segmented request
0581 Rx 8 10 31 30 30 2D 30 32 35 100-025
0601 Tx 8 60 00 00 00 00 00 00 00 00 5th segmented request
0581 Rx 8 05 30 2D 30 30 30 00 00 00 5th segmented response
          Ende, 5 Byte gültig
          (CMD:X5h)
          0-000

```

4.6.1.4. SDO expedited Download (write)

If the client (control) intends to store a value having 32 bit or lower on the server (device/measurement system), it will send an "SDO expedited download request" to the server. This request contains the data to be written and will receive a positive or negative confirmation from the server.

When showing the object address or the data on the data section of the message, the *Bit order* has to be adhered to.

In the example, the object 1010.4 "**Save LSS parameters**" will be opened by means of the character string "save" in order to activate the Function for storage of the changes at the OD.

This object is a *UNSIGNED32* value. If an integer value is entered, the character string "save" [ASCII code: 73h 61h 76h 65h] is shown as follows 65766173h – the *Bit order* has to be adhered to.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	IdxLB	IdxHB	SIdx	Data 1	Data 2	Data 3	Data 4
601h _{Tx}	23h	10h	10h	04h	73h "s"	61h "a"	76h "v"	65h "e"
581h _{Rx}	60h	10h	10h	04h	00h	00h	00h	00h

In another example, the object 1017 "Producer heartbeat time" is activated and set to a repeat rate of 500 ms (1F4h). This object is displayed as a *UNSIGNED16* value.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	IdxLB	IdxHB	SIdx	Data 1	Data 2	Data 3	Data 4
601h _{Tx}	2Bh	17h	10h	00h	F4h	01h	00h	00h
581h _{Rx}	60h	17h	10h	00h	00h	00h	00h	00h

Command indications SDO expedited Download (write)

Command	Direction	Description
2Fh	Request	Write 1 byte
2Bh	Request	Write 2 byte
27h	Request	Write 3 byte
23h	Request	Write 4 byte
60h	Response	Object saved successfully
80h	Response	Errors, see chapter 4.6.1.5 SDO abort transfer (abort)

4.6.1.5. SDO abort transfer (abort)

If the server detects an error while processing a request command, it will report it to the client sending an "SDO abort transfer" response.

The data field of the SDO command serves to transmit a cancel code (error number). The numeric value is shown as a *UNSIGNED32* and the *Bit order* is to be adhered to.

The command code is always **80h**.

This example shows the attempt to write a value into the object 7654 "*manufacturer-specific profile area*". As this object is not existing on that device, the SDO command is cancelled by means of a cancel response.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	IdxLB	IdxHB	SIdx	Data 1	Data 2	Data 3	Data 4
601h _{Tx}	2Bh	54h	76h	00h	66h	06h	00h	00h
581h _{Rx}	80h	54h	76h	00h	00h	00h	02h	06h

Abort code	Description
0503 0000h	Toggle bit not alternated.
0504 0000h	SDO protocol timed out.
0504 0001h	Client/server command specifier not valid or unknown.
0504 0002h	Invalid block size (block mode only).
0504 0003h	Invalid sequence number (block mode only).
0504 0004h	CRC error (block mode only).
0504 0005h	Out of memory.
0601 0000h	Unsupported access to an object.
0601 0001h	Attempt to read a write only object.
0601 0002h	Attempt to write a read only object.
0602 0000h	Object does not exist in the object dictionary.
0604 0041h	Object cannot be mapped to the PDO.
0604 0042h	The number and length of the objects to be mapped would exceed PDO length.
0604 0043h	General parameter incompatibility reason.
0604 0047h	General internal incompatibility in the device.
0606 0000h	Access failed due to an hardware error.
0607 0010h	Data type does not match, length of service parameter does not match

Abort code	Description
0607 0012h	Data type does not match, length of service parameter too high
0607 0013h	Data type does not match, length of service parameter too low
0609 0011h	Sub-index does not exist.
0609 0030h	Invalid value for parameter (download only).
0609 0031h	Value of parameter written too high (download only).
0609 0032h	Value of parameter written too low (download only).
0609 0036h	Maximum value is less than minimum value.
060A 0023h	Resource not available: SDO connection
0800 0000h	General error
0800 0020h	Data cannot be transferred or stored to the application ...
0800 0021h	... because of local control.
0800 0022h	... because of the present device state.
0800 0023h	Object dictionary dynamic generation fails or no object dictionary is present.
0800 0024h	No data available

4.6.2. PDO

Process data are the core information in a control system. They identify the nominal and actual values of different participants.

The PDO transfer protocol is implemented according to *Producer-Consumer* data model.

Basically, there are two types of process data which differ from one another with respect to their direction of communication. For CANopen, the direction is always defined from the point of view of the end nodes.

- **TPDO** Process data which are generated by the device (end nodes) and made available to other participants in the network. **Transmit Process Data Object** – which means send process data. This is how the actual measurement values of a measurement system, for instance, are sent to other network participants as a TPDO.
- **RPDO** Process data generated by a different participant, which are sent to the device. **Receive Process Data Object** – which means receive process data. This type of process data are often nominal values, but may also represent additional input signals, which can be further processed by the receiver.
- **Number of PDOs** The number of PDOs is device-specific and explained in chapter 3.5.4.1 *Number of the process data object supported by the device..*

The process data for transmission, pre-set by default on delivery of the device, are described in chapter 3.1.1 *CANopen default settings*.

Which process data will be transmitted and which way, is managed by parameters in the OD. This system is referred to as *PDO Mapping*. The devices often are assigned a *Preconfiguration* of the transmitted process data by the manufacturer.



Without a valid configuration of a PDO, no process data will be sent or received; see chapter 4.6.2.3 *PDO Mapping*

As the configuration can be changed by the user, it is certainly possible that a particular device may send process data which deviates from the standard behaviour.

There are two major setting areas which are important for the transmission of a PDO.

- The parameters defining how the object is going to be transmitted, i.e. cyclically or synchronously.
 - 4.5.4.6 *RPDO communication parameter*
 - 4.5.4.8 *TPDO communication parameter*
- The parameters defining what information (objects) will be transmitted.
 - 4.5.4.9 *TPDO mapping parameter*
 - 4.5.4.7 *RPDO mapping parameter*

4.6.2.1. Event driven

In general, there are two ways of transmitting process data:

- An event in the device triggers the transmission.
- The device receives a synchronisation message, see chapter 4.6.2.2 *SYNC*.

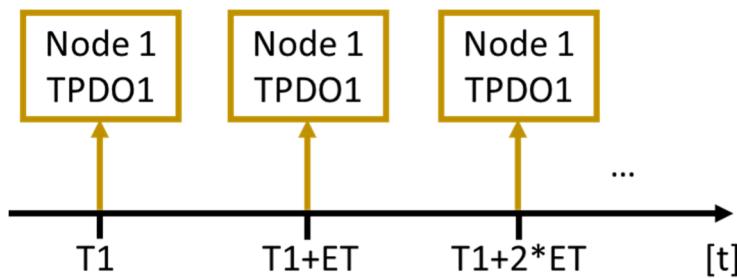


The use of RTR ("remote frame request") based events is not recommended.

The most common way of event controlled transmission is the periodic transmission, based on a settable and fixed cycle time, see object "*Event timer*". Which transmission type to use is defined by the "".

Devices meeting the requirements of a device profile, sometimes provide additional event types. For example, the CiA 404 "Device profile for measuring devices" offers the opportunity to trigger the sending of a TPDO when a measured value has been exceeded. If a device offers additional event variants, these are described in chapter 3.6.3 *device-specific PDO events*.

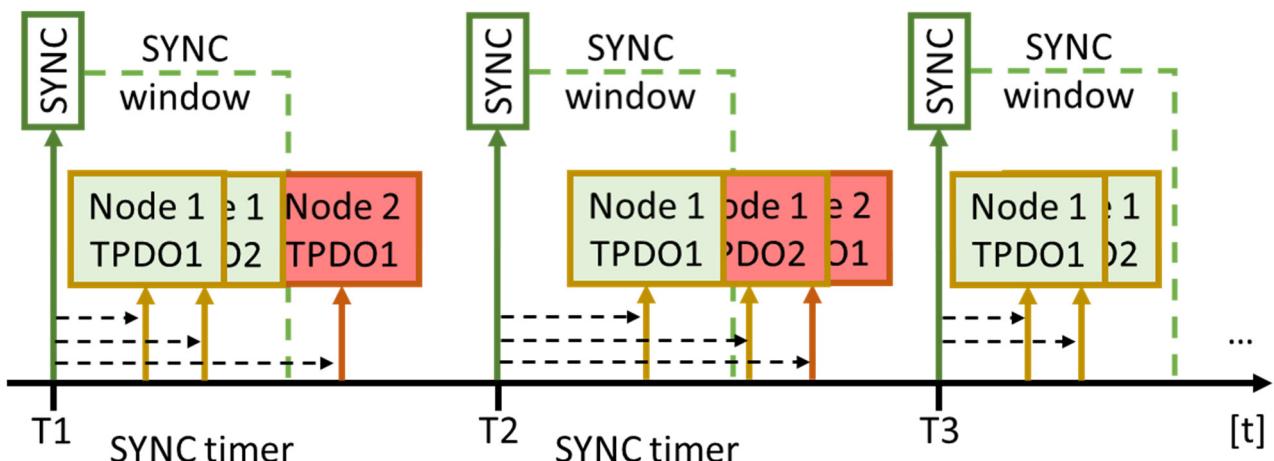
In case the event-controlled transmission of the PDO and the *Event timer*(ET) are active, the PDO will be transmitted after expiry of the "event time" at the latest, if no other device event has occurred.



4.6.2.2. SYNC

For tasks in automation technology, it is often necessary to perform processes synchronously. If, for instance, the engine power shall be measured, it is also necessary to measure its speed and torque at the same time. The synchronised transmission of the PDO is one solution for this.

The SYNC protocol is implemented according to the *Master-Device* data model and used for the synchronisation of the *PDO transmission* which works on the basis of this data model itself.



Subsequent to receiving the SYNC message, the SYNC device should start its internal signal processing. After having processed the signal, a PDO will immediately be generated and sent. The SYNC device monitors a time frame within which a received PDO message is valid. Messages received after the time frame has expired will be discarded.

The SYNC processing can be configured via the object "Transmission type" from the "xPDO communication parameter" section. Generating a PDO message does not need to be carried out after each SYNC, but can also be defined as a multiple of the SYNC. Via this mechanism, the transmission can be divided into important or informative PDOs.

The usual time intervals for SYNC range within a few 10 ms. For example, a rapidly changing pressure value can be transmitted with every SYNC (e.g. every 10 ms), whereas a slowly changing temperature value can be transmitted every 100 SYNC ($100 * 10 \text{ ms} = 1 \text{ s}$). This is a good solution for the regulation of the bus load.

The message basically just consists of the CAN ID without the data. This type of transmission causes the lowest bus load in order to achieve the synchronisation of the process data.

Field name	Content	Meaning
COB ID	080h	The COB ID directly represents the used CAN ID. The value can be changed via the object "COB-ID SYNC".
DLC	0 / 1	Data length of the message in bytes Standard application: 0 → no transmission of user data
BYTE 0	Counter	Optional The SYNC producer can send a <i>UNSIGNED8</i> counter [1, 240] which is used by the SYNC consumer to recognise the first valid SYNC when "SYNC start" is set. In most cases, the SYNC message is sent without the counter.

Example for a standard SYNC signal

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	Counter							
080h _{Tx}								

4.6.2.3. PDO Mapping

The PDO mapping is a complex process in which several areas of the OD work together. The following example shows how process data are "mapped" onto a TPDO. In this particular case, this example shows how the measurement signal "statical inclination" from an inclinometer by HYDAC Filtertechnik GmbH is transmitted via the TPDO1.

The area "*PDO communication parameter*" defines when a PDO is supposed to be transmitted and the area "*PDO mapping parameter*" defines which objects from the OD will copy or read that particular PDO message.



In order to change the mapping of a PDO, a process flow sequence has to be strictly adhered to; see chapter *4.6.2.5 Process flow sequence to change the "PDO mapping"*.

For each event triggering the transmission of a PDO, the current content of the "mapped" objects will always be copied from the OD into the message (*TPDO*) or copied from the message into the objects (*RPDO*).

The CAN ID transmitting the PDO object is defined by the parameter COB ID from the area „communication parameter“. It is calculated during runtime from the basis address and the

device's node ID → in the example: Basis = 180h (TPDO1), Node-ID = 1 → 180h + 1 = 181h.

The number of objects used in the PDO is defined by the first entry of the "mapping parameter", objekt: "*Number of mapped objects in PDO*".

Which particular objects will be connected with the PDO message, is listed in the following sub-entries of the "*xPDO mapping parameter*". Each of these entries are references addressing one particular object via the index and the sub-index, see chapter *The individual entries are references addressing one particular object via the index and the sub-index, see chapter 4.5.1.1 Addressing*.

The codification design of a process value parameter object reference is described in the object "*1st object to be mapped*" of the chapter *4.5.4.9 TPDO mapping parameter*. A good graphical overview of the interaction between the several *OD segment* when setting up a *PDO CAN message* is shown in chapter *4.6.2.4 Overview diagram PDO mapping*.

The space requirements in the PDO correspond with the data length of the *Data type* in the object. The position of the subsequent object in the PDO is immediately after. It may for example happen that a following signal starts in the middle of a data byte if one the previous data bytes does not have a data length divisible by 8.

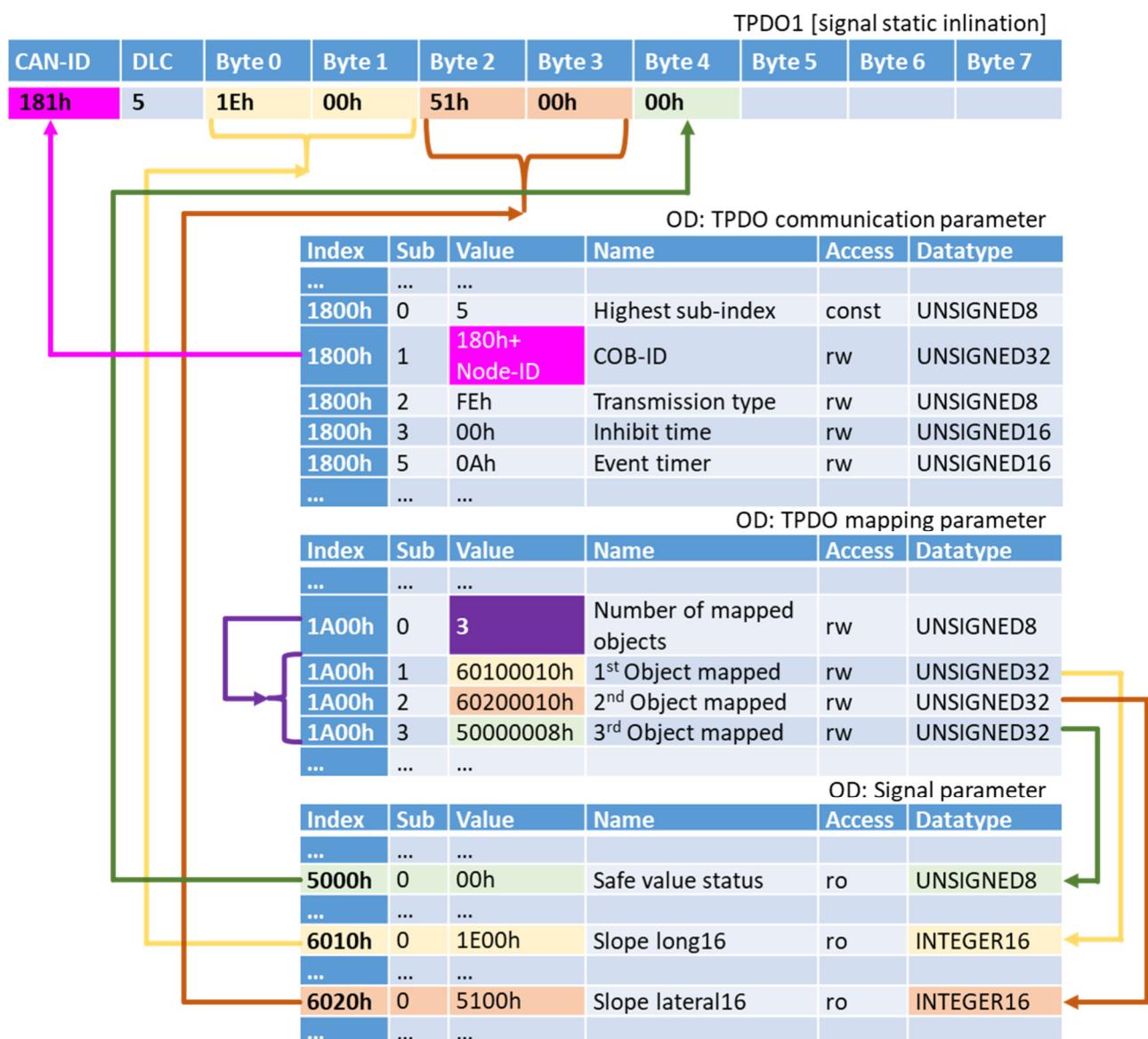
The length of a PDO CAN message is calculated from the sum of the individual data lengths of the process value parameter objects used. In the *Overview diagram below* these are 2 values with 16 bits each (2 bytes) and a value with 8 bits (1 byte). The result of this is the length of the PDO:

$$(2 * 2 \text{ Bytes}) + 1 \text{ Byte} = 5 \text{ Bytes} \rightarrow \text{DLC} = 5.$$

A PDO is always limited to the length of a *CAN message*, which means 8 bytes (64 bits). If transmission of more than 8 Bytes is required, a further PDO has to be defined. The device manufacturer, however, defines the max. amount of PDOs in their software, see chapter *3.5.4.1 Number of the process data object supported by the device..*

4.6.2.4. Overview diagram PDO mapping

The below diagram graphically explains the context between the structure of the PDOCAN message and the different *Segments of the OD*; see chapter 4.6.2.3 *PDO Mapping*.



4.6.2.5. Process flow sequence to change the "PDO mapping"

If the PDO mapping of a device is supposed to be changed, this can only be carried out following strict procedures. Should the procedure described below not be adhered to, the device will respond to the access sending the corresponding error message, see chapter 4.6.1.5 SDO abort transfer (*abort*).

Individual objects for the management of the "*PDO Mapping*" can be accessed via SDO commands, see chapter 4.6.1 SDO.

- **Switching device to "Pre-Operational" mode**
 - 4.4.1 *Overview network conditions*.
 - 4.4.2 *NMT*.
- **Declare the PDO as invalid**, for this purpose, bit 31 of the COB ID has to be set to 1.
 - TPDO.COB ID Bit 31 = set 1, e.g. 1800.1 = C00000180h
 - RPDO.COB ID Bit 31 = set 1 e.g. 1400.1 = 800000200h180h
- **Deactivate the number of object references used in the PDO**, for this, the number has to be set to 0.
 - see object: RPDO. "*Number of mapped objects in PDO*"
 - see object: RPDO. "*Number of mapped objects in PDO*"
- **Set new object references in the area "xPDO mapping parameter"**; → Memorise the number of new entries for the next step.
 - see chapter 4.6.2.3°*PDO Mapping*
 - see chapter 4.5.4.7°*RPDO mapping parameter*
 - see chapter 4.5.4.9°*TPDO mapping parameter*
- **Set the number of object references used in the PDO to a new value**.
- **Set PDO back to valid**, for this, bit 31 of the COB-ID is set to 0 or the object = 0 is set in order to activate the standard behaviour, i.e. TPDO1: \$NODEID+180h.
 - TPDO.COB ID
 - RPDO.COB ID
- **Save changes permanently on the device**
 - see chapter 4.5.1.3°*Objects serving as functions*
 - see object "*Save communication parameters*"
- **Switching device to "Operational" mode**
 - 4.4.1 *Overview network conditions*.
 - 4.4.2 *NMT*.

4.6.2.6. Configure example protocol PDO1

In the following protocol, the PDO1 of a device is configured as follows:

- COB-ID = 181h
- Transmission type = event-controlled (manufacturer-specific)
- Inhibit time = 0
- Event timer = 200 ms
- PDO Mapping with 3 object references
 - 6010.0 INTEGER16
 - 6020.0 INTEGER16
 - 5000.0 UNSIGNED8

```
CAN-ID (hex)
|   Direction: Tx (ECU → Device); Rx (Device → ECU)
|   |   Data Length
|   |   |   Data Bytes (hex)
|   |   |
+--- +--+ +-- -- -- -- -- -- -- --
Heartbeat status = "Operational"
0701 Rx 1 05
0701 Rx 1 05
NMT command "enter pre-operational node-id=1"
0000 Tx 2 80 01
SDO write 4 byte command 1800.1 = C0000181h
→ deenable PDO1 transmission
0601 Tx 8 23 00 18 01 81 01 00 C0
0581 Rx 8 60 00 18 01 00 00 00 00
SDO write 1 byte command 1800.2 = FEh (254d)
0601 Tx 8 2F 00 18 02 FE 00 00 00
0581 Rx 8 60 00 18 02 00 00 00 00
SDO write 2 byte command 1800.3 = 00h
0601 Tx 8 2B 00 18 03 00 00 00 00
0581 Rx 8 60 00 18 03 00 00 00 00
SDO write 2 byte command 1800.5 = C8h (200d)
0601 Tx 8 2B 00 18 05 C8 00 00 00
0581 Rx 8 60 00 18 05 00 00 00 00
SDO write 1 byte command 1A00.0 = 00h
→ deenable PDO1 mapping
0601 Tx 8 2F 00 1A 00 00 00 00 00
0581 Rx 8 60 00 1A 00 00 00 00 00
SDO write 4 byte command 1A00.1 = 60100010h
0601 Tx 8 23 00 1A 01 10 00 10 60
0581 Rx 8 60 00 1A 01 00 00 00 00
SDO write 4 byte command 1A00.2 = 60200010h
```

0601 Tx 8 23 00 1A 02 10 00 20 60
0581 Rx 8 60 00 1A 02 00 00 00 00
SDO write 4 byte command 1A00.3 = 50000008h
0601 Tx 8 23 00 1A 03 08 00 00 50
0581 Rx 8 60 00 1A 03 00 00 00 00
SDO write 1 byte command 1A00.0 = 03h
→ enable TPDO1 Mapping
0601 Tx 8 2F 00 1A 00 03 00 00 00
0581 Rx 8 60 00 1A 00 00 00 00 00
SDO write 4 byte command 1800.1 = 0h
→ enable TPDO1 transmission, standard COB-ID active
0601 Tx 8 23 00 18 01 00 00 00 00
0581 Rx 8 60 00 18 01 00 00 00 00
SDO write 4 byte command 1010.1 = 65766173h ("save")
→ Store parameters. Save all parameters
0601 Tx 8 23 10 10 01 73 61 76 65
0581 Rx 8 60 10 10 01 00 00 00 00
Heartbeat Status = "Pre-Operational"
0701 Rx 1 7F
NMT command "start node-id=<all>"
0000 Tx 2 01 00
TPDO1
0181 Rx 5 2A 01 55 00 00
TPDO1
0181 Rx 5 2A 01 55 00 00
Heartbeat Status = "Operational"
0701 Rx 1 05

4.6.3. SRDO

The devices described in this documentation (see chapter 1.1 Scope of applications) do **not** support any **functionally safe communication**.

4.7. Layer setting services (LSS) Protocol

Via the LSS protocol, several specific LSS services in the device can be addressed. The main function of these services is to configure the most important communication parameters – *Baud rate* and *Node ID* – without having specific knowledge of the *OD*. The LSS protocol is described in detail in the CiA 305.

Whether a device supports the LSS protocol or not, can be recognised from the *EDS* parameter "*LSS_Supported*" and is described in chapter 3.8 *LSS Protocol support*.

The following please find the most important information on this product summarised as an overview.

The access via LSS is supported to the following parameters:

- *Node ID*
- *Baud rate*
- LSS address - corresponds with *Identity Object 1018h*

LSS address: This address controls the access to one particular device. It corresponds with the indications of the *OD.Identity Object*:

- Vendor-ID *UNSIGNED32*
- Product Code *UNSIGNED32*
- Revision number and *UNSIGNED32*
- Serial number *UNSIGNED32*

The measuring system supports the following LSS services:

- | | |
|--|---|
| • Switch mode services | enable switching mode |
| ○ <i>Switch state selective</i> | LSS-Status
Address one particular device |
| ○ <i>Switch state global</i> | address all devices |
| • Configuration services | change device configuration |
| ○ <i>Configure Node ID</i> | configure Node ID |
| ○ <i>Configure bit timing parameters</i> | Configure Baud rate |
| ○ <i>Activate bit timing parameters</i> | enable Baud rate |
| ○ <i>Store configured parameters</i> | save changes |
| • Inquiry services | inquire device information |
| ○ <i>Inquire LSS address</i> | inquire LSS address |
| ○ <i>Inquire Node ID</i> | inquire Node ID |

- **Identification services** identify device or devices
 - *LSS identify remote slave*
Identification of devices within a certain array
 - *LSS identify slave*
Response of all devices to the previous command
 - *LSS identify non-configured remote slave*
Identification of non-configured devices, Node ID = FFh
 - *LSS identify non-configured slave*
Response of all devices to the previous command
- **Fastscan** Detect non-configured devices

4.7.1. LSS Communication model

Via the LSS protocol, a LSS master (control) can require particular services on a *LSS device* (device). The LSS protocol is mainly based on the *Master – Device* communication model. However, some LSS services classify the commands as *Request* and respond by using a *Response*.

With the LSS protocol, only **one single** device can be configured at a time. If there are several devices in the network at the same time, each one has to be separately switched to the configuration mode via its *LSS address*.



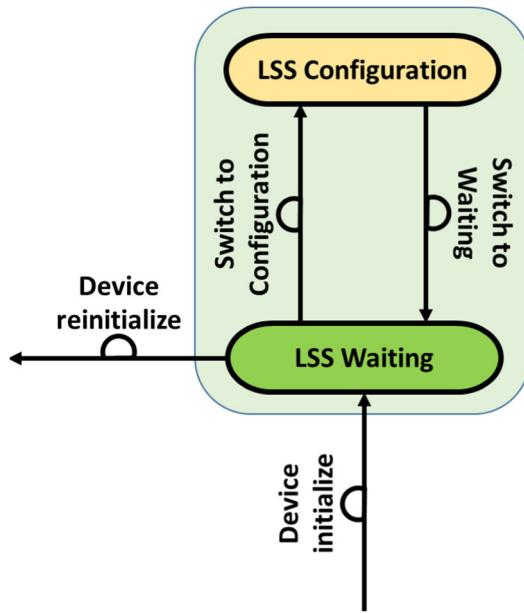
To simplify the configuration of a device via the LSS protocol, it is helpful to connect only one device to the LSS master (control) at a time. In this case, the command "*switch mode global*" for *status switch* can be used.

4.7.1.1. LSS status diagram

In order to process the communication in the device (*LSS consumer*), it can take on two different operational modes.

LSS Waiting: after device start-up, see also chapter 4.4 *Network Management*, the device automatically takes on this mode. In this state, the device accepts the LSS "Switch mode services" commands as well as LSS "Identification services".

LSS Configuration: the device takes on this mode after having received a "Switch Mode" command. **Only one device at a time** may take on this device mode. Parameters can only be read and written and changes can only be stored permanently if the operating mode "LSS Configuration" is active. For this purpose, the LSS "Configuration" and the LSS "Inquire" commands are available.



4.7.1.2. LSS command structure

The structure of the *CAN command message* is similar to a *SDO protocol-message*: Two COB IDs are used for sending and receiving here as well. Another similarity is that the first byte of the message is used as a command code. The COB ID of the LSS command, however, is strictly defined and does not depend on the Node ID of the device.

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device) [Tx: ECU → Device]
COB ID	7E4h _{Rx}	COB-ID of the LSS response (device → controller) [Rx: Device → ECU]
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code <i>UNSIGNED8</i> The command code serves to distinguish the different LSS services and their responses.
BYTE 1 - 7	Data	User data Data length and content depend on the related LSS service command.

4.7.2. LSS Switch commands

This command serves for switching the active *LSS condition*. Only if the "LSS configuration" mode is active, the device can be parameterised by means of other commands. This state may not be taken on by more than one device within the network at a time.

4.7.2.1. LSS Switch state global

If only one single device is connected to the master (control), its *LSS condition* can be switched directly without the knowledge of its *LSS address*. The command is not responded to by the device.



If more than one device is connected to the control, all devices will switch to another mode when receiving this command. This means, in the case the "LSS configuration" mode should be active, this might lead to undefined behaviour.

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code 04h Switch state global service
BYTE 1	Mode	To be enabled <i>LSS condition</i> 00h enable status "LSS Waiting" 01h enable status "LSS configuration"
BYTE 2 - 7	Reserved	

The example shows how a device is switched to the "LSS configuration" mode.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	Mode				Reserved		
7E5h _{Tx}	04h	01h						

4.7.2.2. LSS Switch state selective

If several devices are connected to the CAN network, each device has to be addressed and parameterised separately. For this purpose, the master (control) has to send 4 consecutive messages in total. Each message contains a parameter of the *LSS address*.

Field name	Content	Meaning	
COB ID	7E5h _{TX}	COB-ID of the LSS command (controller→device)	
DLC	8	Data length of the message in bytes	
BYTE 0	Command	Command code 40h – 43h	UNSIGNED8 Request Response
		Please follow the commands list below.	
BYTE 1 – 4	Data	LSS address individual parameters	UNSIGNED32 The data to be transmitted depends on the command, see below list of commands.
BYTE 5 – 7	Reserved		

Context between the command code and the LSS address data transmission. The individual request commands should be sent to the device in ascending order.

Command	Direction	Data	Description
40h	Request	UNSIGNED32	send vendor ID
41h	Request	UNSIGNED32	send product code
42h	Request	UNSIGNED32	send revision number
43h	Request	UNSIGNED32	send serial number
44h	Response	Reserved	No response data

Please see below how a device is switched to "*LSS configuration*" mode using a defined *LSS address*. For this purpose, 4 *Command requests*, carrying the particular LSS address data, will be sent to the device in consecutive order. After the command sequence has expired, the device responds by means of a *response commands*.

The LSS address used in the example:

Vendor-ID	DAh
Product Code	E2155h
Revision Number	80000h
Serial Number	12345678h

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{Tx}	40h	DAh	00h	00h	00h			
7E5h _{Tx}	41h	55h	21h	0Eh	00h			
7E5h _{Tx}	42h	00h	00h	08h	00h			
7E5h _{Tx}	43h	78h	56h	34h	12h			
7E4h _{Tx}	44h							

4.7.3. LSS configuration commands

Via the "LSS Configurations" command, the parameters of a device can be read and changed as well. These commands, however, can only be used if the device is in the *LSS condition "LSS configuration"*.

4.7.3.1. Configure Node ID

The *Node ID* of a device can be changed using this command. The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "LSS configuration" mode at a time.

To save the new node ID the "Store configuration" command has to be carried out afterwards.

In order to activate the new node ID, the *NMT command „Reset communication“* or "Reset Node" has to be inquired. Without a device "reset", the current node ID remains active..

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 11h "Configure Node ID"

Field name	Content	Meaning	
BYTE 1	Node ID	Required Node-ID Value range: 1 – 127 and 255 ("non-configured")	<i>UNSIGNED8</i>
BYTE 2 – 7	Reserved		

Response

Field name	Content	Meaning	
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)	
DLC	8	Data length of the message in bytes	
BYTE 0	Command	Command code The command code is identical for request and for response. 11h "Configure Node ID"	<i>UNSIGNED8</i>
BYTE 1	Error Code	Error number 0 Node-ID successfully applied 1 invalid Node ID value 255 device-specific error → "Specific Error"	<i>UNSIGNED8</i>
BYTE 2	Specific Error	Device-specific error number 0 Error Code ≠ 255	<i>UNSIGNED8</i>
BYTE 3 – 7	Reserved		

The following section shows how to set the node ID 0Ah (10d) successfully in the device by means of the LSS command "Configure Node-ID".

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data					Reserved
7E5h _{Tx}	11h	0Ah						
7E4h _{Rx}	11h	00h	00h					

4.7.3.2. Configure bit timing

The *Baud rate* of a device can be changed using this command. The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "*LSS configuration*" mode at a time.

To save the new Baud rate ID the "*Store configuration*" command has to be carried out afterwards.

To activate the new Baud rate, the *NMT command "Reset communication"* or „*Reset Node*“ can be inquired afterwards, or the LSS command „*Activate bit timing parameters*“ is can be used.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning	
COB ID	7E5h _{Tx}	COB-ID of the LSS command (device → controller)	
DLC	8	Data length of the message in bytes	
BYTE 0	Command	Command code The command code is identical for request and for response . 13h "Configure bit timing"	<i>UNSIGNED8</i>
BYTE 1	Table selector	Active baud rate table 0 Standard CiA Baud rate table	<i>UNSIGNED8</i>
BYTE 2	Table index	Baud rate table index Active baud rate see object "Baud rate" 0 1000 kbit/s 1 800 kbit/s 2 500 kbit/s 3 250 kbit/s 4 125 kbit/s 5 reserved 6 50 kbit/s 7 20 kbit/s 8 10 kbit/s	<i>UNSIGNED8</i>
BYTE 3 – 7	Reserved		

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code <i>UNSIGNED8</i> The command code is identical for request and for response . 13h "Configure bit timing"
BYTE 1	Error Code	Error number <i>UNSIGNED8</i> 0 Node-ID successfully applied 1 Baud rate index not supported 255 device-specific error → "Specific Error"
BYTE 2	Specific Error	Device-specific error number <i>UNSIGNED8</i> 0 Error Code ≠ 255
BYTE 3 – 7	Reserved	

The following section shows how to set the Baud rate 500 kbit/s, Index = 2 successfully in the device by means of the LSS command "Configure bit timing".

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	Data		Reserved				
7E5h _{Tx}	13h	00h	02h					
7E4h _{Rx}	13h	00h	00h					

4.7.3.3. enable bit timing parameters

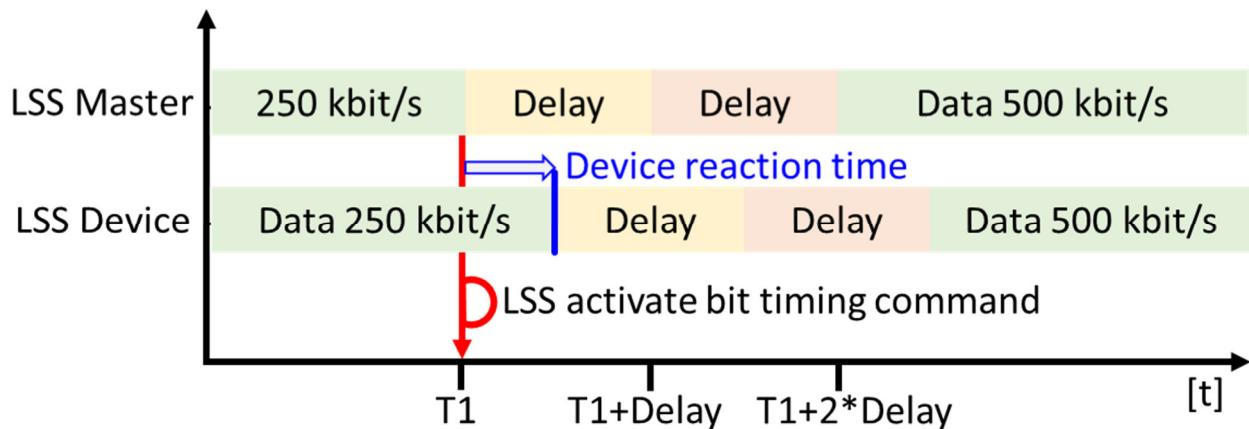
A slightly complex procedure is required to activate a new Baud rate after having changed and stored it. The command "activate bit timing" must be processed almost exactly at the same time by all the network participants, in order to switch all participants to the new Baud rate and, thus, avoiding that communication errors may occur.

The command is not responded to by the device.

Switchover procedure:

- The command transmits a waiting delay.
- All the participants have to wait two times for this delay to expire before they can send their information using the new Baud rate.
- The first half of the delay serves for de-initialisation of all participants. Within this time range, all the participants should terminate the sending of their messages; "device reaction time".

- The waiting delay should be chosen in such a way that even the network participant having the longest reaction time has terminated the sending of messages within the first phase.
- The first phase serves as reinitialisation. After the second phase has expired, messages may be sent with the new Baud rate.



Process diagram "enable bit timing"

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code 15h Switch state global service
BYTE 1	Delay	waiting period Delay for switchover in [ms]; see <i>Switchover diagram</i>
BYTE 2 – 7	Reserved	

The example instructs all participants in "*LSS configuration*" to activate the newly configured Baud rate.

The LSS master defines the delay of 2 s before → 2000d [ms] → 07D0h

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Delay			Reserved		
7E5h _{Tx}	15h	D0h	07h					

4.7.3.4. Store configuration

This command enables to store changes to the *Node ID* and the *Baud rate* permanently on the device. The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "LSS configuration" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 17h "Store configuration"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 17h "Store configuration"
BYTE 1	Error Code	Error number UNSIGNED8 0 storage carried out successfully 1 command is not supported 2 Storage access denied 255 device-specific error → "Specific Error"
BYTE 2	Specific Error	Device-specific error number UNSIGNED8 0 Error Code ≠ 255
BYTE 3 – 7	Reserved	

The following section shows how to store recent changes in the device permanently with the LSS command "store configuration".

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{TX}	17h							
7E4h _{RX}	17h	00h	00h					

D

4.7.4. LSS Inquire command

With the help of the "LSS inquire command", the individual sections of the *LSS address* as well as the recent node ID of all devices which are currently in the "*LSS configuration*" mode can be inquired.

If several devices are active at the same time, all of them will respond almost synchronously. The order of the responses cannot be predefined, however. For this reason, only one device at a time should be in the "*LSS configuration*" mode.

4.7.4.1. Inquire Identity Vendor-ID

The CiA manufacturer code as is defined in the "*OD.Identity Object Vendor-ID (1018.1)*" via this command. The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "*LSS configuration*" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{TX}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Ah "Inquire Vendor-ID"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Ah "Inquire Vendor-ID"
BYTE 1 – 4	Vendor ID	Manufacturer's code UNSIGNED32 CiA manufacturer's code corresponds with the object " <i>OD.Identity Object.Vendor-ID</i> "
BYTE 5 – 7	Reserved	

The following example shows how the CiA manufacturer code (HYDAC Filtertechnik GmbH: DAh) of the device is queried.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{Tx}	5Ah							
7E4h _{Rx}	5Ah	DAh	00h	00h	00h			

4.7.4.2. Inquire Identity Product-Code

Via this command, the manufacturer-specific product code, as it is defined in the "*OD.Identity Object.Product code (1018.2)*", can be inquired. The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "*LSS configuration*" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Bh "Inquire Product-Code"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Bh "Inquire Product-Code"
BYTE 1 – 4	Product code	Product code UNSIGNED32 Manufacturer-specific product code corresponds with the object " <i>OD.Identity Object.Product code</i> ".
BYTE 5 – 7	Reserved	

The following example shows how to request the manufacturer-specific product code (Example: E2155h) of the device.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{Tx}	5Bh							
7E4h _{Rx}	5Bh	55h	21h	0Eh	00h			

4.7.4.3. Inquire Identity Revision-Number

This command serves to inquire the product revision number as it is defined in the "*OD.Identity Object.Revision number (1018.3)*". The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "LSS configuration" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

D Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code <i>UNSIGNED8</i> The command code is identical for request and for response . 5Ch "Inquire Revision-Number"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code <i>UNSIGNED8</i> The command code is identical for request and for response . 5Ch "Inquire Revision-Number"
BYTE 1 – 4	Revision-Number	Revision number <i>UNSIGNED32</i> Product revision number corresponds with the object " <i>OD.Identity Object.Revision number</i> "
BYTE 5 – 7	Reserved	

The following example shows how to request the product revision number (Example: 80000h) of the device.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{Tx}	5Ch							
7E4h _{Rx}	5Ch	00h	00h	08h	00h			

4.7.4.4. Inquire Identity Serial-Number

This command serves to inquire the device serial number as it is defined in the "*OD.Identity Object.Serial number (1018.4)*". The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "*LSS configuration*" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Dh "Inquire Serial-Number"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Dh "Inquire Serial-Number"
BYTE 1 – 4	Serial number	Serial Number UNSIGNED32 Device serial number corresponds with the object " <i>OD.Identity Object.Serial number</i> "
BYTE 5 – 7	Reserved	

The following example shows how to request the device serial number (Example: 1EDDh).

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		Data			Reserved		
7E5h _{Tx}	5Dh							
7E4h _{Rx}	5Dh	DDh	1Eh	00h	00h			

4.7.4.5. Inquire Node ID

This command serves to inquire the currently active node ID as it is defined in the "OD.Node-ID.Active node-ID (2001.1)". The command is implemented according to *Request response model*.

Please observe: Only one device may be in the "*LSS configuration*" mode at a time.

The commands "request" or "response" have different structures. The structures of both messages are shown below.

Request

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Eh "Inquire Node-ID"
BYTE 1 – 7	Reserved	

Response

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 The command code is identical for request and for response . 5Eh "Inquire Node-ID"
BYTE 1	Node ID	Active Node ID UNSIGNED32 Currently active Node ID of the device see object "OD.Node-ID.Active node-ID"

Field name	Content	Meaning
BYTE 2 – 7	Reserved	

The following example shows how to request the device's currently active node ID (example: 01h).

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	Data						Reserved
7E5h _{Tx}	5Eh							
7E4h _{Rx}	5Eh	01h						

4.7.5. LSS Identify commands

The LSS identity commands serve to find out how many devices with LSS protocol support are currently connected to the CAN network.

4.7.5.1. Identify remote slave

If more devices are connected to the CAN network, the number of devices with LSS protocol support can be determined. For this purpose, the master (control) has to send 6 consecutive messages in total. The messages contain parameters of the *LSS address*. In order to set a limit to the selection of the devices, the manufacturer and product code are firmly defined. The selection is limited using a pre-defined value range for the revision and serial number.

If devices exist which correspond with the LSS address section which is pre-defined by the command sequence, these can respond with the "*Identify slave*" command.

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code UNSIGNED8 46h – 4Bh Request Please follow the commands list below.
BYTE 1 – 4	Data	LSS address individual parameters UNSIGNED32 The data to be transmitted depends on the command, see below list of commands.
BYTE 5 – 7	Reserved	

Relationship between the command code and the LSS address section transmission. The individual request commands should be sent to the device in ascending order.

Command	Direction	Data	Description
46h	Request	<i>UNSIGNED32</i>	Define vendor ID
47h	Request	<i>UNSIGNED32</i>	Define product code
48h	Request	<i>UNSIGNED32</i>	Define revision number minimum
49h	Request	<i>UNSIGNED32</i>	Define revision number maximum
4Ah	Request	<i>UNSIGNED32</i>	Define serial number minimum
4Bh	Request	<i>UNSIGNED32</i>	Define serial number maximum

Please see below how a device is switched to "*LSS configuration*" mode using a defined *LSS address*. For this purpose, 4 *Command requests*, carrying the particular LSS address data, will be sent to the device in consecutive order. After the command sequence has expired, a device responds with the "*Identify slave*" command.

The LSS address used in the example:

Vendor-ID	DAh
Product Code	E2155h
Revision Number	80000h Range: 40000h – 80000h
Serial Number	12345678h Range: 1000h – 50000000h

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD	Data					Reserved	
7E5h _{Tx}	46h	DAh	00h	00h	00h			
7E5h _{Tx}	47h	55h	21h	0Eh	00h			
7E5h _{Tx}	48h	00h	00h	04h	00h			
7E5h _{Tx}	49h	00h	00h	08h	00h			
7E5h _{Tx}	4Ah	00h	10h	00h	00h			
7E5h _{Tx}	4Bh	00h	00h	00h	50h			
7E4h _{Rx}	4Fh							

4.7.5.2. Identify slave

Possible response to the previous command by the device, see chapter 4.7.5.1 *Identify remote slave*.

Field name	Content	Meaning
COB ID	7E4h _{Rx}	COB-ID of the LSS command (device → controller)
DLC	8	Data length of the message in bytes

Field name	Content	Meaning	
BYTE 0	Command	Command code 4Fh "LSS identify slave protocol"	<i>UNSIGNED8</i>
BYTE 1 – 7	Reserved		

4.7.5.3. Identify non-configured remote slave

Command for the recognition of non-configured devices with LSS protocol support within the network. Devices which are classified as "non-configured" are the ones whose "pending node ID" (see *OD.Node-ID*) is invalid, e.g. = FFh.

Non-configured devices can respond using the command "*Identify non-configured slave*".

Field name	Content	Meaning	
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)	
DLC	8	Data length of the message in bytes	
BYTE 0	Command	Command code 4Ch "LSS identify non-configured remote slave"	<i>UNSIGNED8</i>
BYTE 1 – 7	Reserved		

Example of a response of a non-configured device to the LSS master request for identification.

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD					Reserved		
7E5h _{Tx}	4Ch							
7E4h _{Rx}	50h							

4.7.5.4. Identify non-configured slave

Possible response of a non-configured device to a LSS master request "Identify non-configured remote slave"; see chapter 4.7.5.3 *Identify non-configured remote slave*.

Field name	Content	Meaning	
COB ID	7E4h Rx	COB-ID of the LSS command (device → controller)	
DLC	8	Data length of the message in bytes	
BYTE 0	Command	Command code	UNSIGNED8
		50h "LSS identify non-configured slave"	
BYTE 1 – 7	Reserved		

4.7.6. LSS Fastscan

With the fastscan protocol, a LSS master can identify the *LSS address* of unknown and non-configured devices. In the beginning of such a requests, all non-configured devices have to be in the "*LSS Waiting*" mode.

The inquiry will be initiated by the LSS master by a particular request ("Bit Check" = 128) in order to mark the start of the request sequence. This inquiry should be confirmed by all LSS devices which have not yet been configured by response "*Identify slave*". By means of this response, the LSS master recognises that further LSS devices need to be configured.

That is to say, the fastscan protocol performs a search for existing LSS addresses. For this purpose, all sections of the *LSS address* are inquired bit by bit and sequentially. LSS devices with matching address sections confirm the related request positively by sending the response "*Identify slave*". If the recently inquired address section does not match, no response will be sent by the LSS device. In this case, the LSS master waits for a defined time, corrects the address section it has already received and requests the next address section. Therefore, up to 132 (4 * 32bit + 4) single requests are required in order to detect the LSS address of a certain LSS device.

If a LSS device has been clearly identified, it will automatically switch to the "*LSS configuration*" state after the sequence has expired and confirm that the process has been successful by "*Identify slave*". The LSS device can now be configured by the LSS master accordingly by means of the LSS features described above.

Please see the CiA 305 for a more detailed description.

Field name	Content	Meaning
COB ID	7E5h _{Tx}	COB-ID of the LSS command (controller→device)
DLC	8	Data length of the message in bytes
BYTE 0	Command	Command code 51h "LSS Fastscan"
BYTE 1 – 4	IDNumber	Inquiry Currently inquired address sequence of the <i>LSS address</i> .
BYTE 5	Bit Check	Bit position Current bit positions to be checked within the currently active LSS address section of the inquiry. The LSS device checks all the superordinate bit, including this bit position, for equality of the transmitted IDnumber compared with the LSS address sequence currently to be checked. Example: Bit Check = 28d Check Bit 31, 30, 29, 28 Special case Bit Check = 128d (80h); IDNu, Sub, Next = 0 → Start Fastscan
BYTE 6	LSS Sub	LSS-Adress Index Current section of the <i>LSS address</i> to be checked. 0 Vendor-ID 1 Product code 2 Revision number 3 Serial number
BYTE 7	LSS Next	Next LSS-Adress Index Value range, see LSS Sub.

Example: Start LSS fastscan with a non-configured LSS device

	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
CANID	CMD		IDNumber		BitChk	Sub	Next	
7E5h _{Tx}	51h		0000000h		80h	0h	0h	
7E4h _{Rx}	4Fh							

4.7.7. Example: setting the node ID and Baud rate via LSS

The following example shows how a LSS master switches one particular device to the "LSS-Configuration" state via the "global switch" command. Subsequently, a new *Node ID* (2) and *Baud rate* (250 kbit/s) will be defined. These will be stored permanently on the device and finally, the device will be restarted with the new settings.

```

CAN-ID (hex)
|   Direction: Tx (ECU → Device); Rx (Device → ECU)
|   |   Data Length
|   |   |   Data Bytes (hex)
|   |   |
+--- +- + +- - - - - - - - -
LSS-Master "Switch mode global" according to "LSS-Configuration"
07E5 Tx 8 04 01 00 00 00 00 00 00
LSS-Master "Configure Node ID"; Node-ID = 2
07E5 Tx 8 11 02 00 00 00 00 00 00
LSS-Device positive Response
07E4 Rx 8 11 00 00 00 00 00 00 00
LSS-Master "Configure bit timing"; Baud rate Index=3 (250 kbit/s)
07E5 Tx 8 13 00 03 00 00 00 00 00
LSS-Device positive Response
07E4 Rx 8 13 00 00 00 00 00 00 00
LSS-Master "Store configuration"
07E5 Tx 8 17 00 00 00 00 00 00 00
LSS-Device positive Response
07E4 Rx 8 17 00 00 00 00 00 00 00
LSS-Master "Switch mode global" according to "LSS-Waiting"
07E5 Tx 8 04 00 00 00 00 00 00 00
NMT-Master "Reset all Node"
0000 Tx 2 81 00
Boot-up Node-ID = 2
0702 Rx 1 00
TPDO1 messages from Node-ID = 2
0182 Rx 5 A9 04 FE FD 01
0182 Rx 5 A9 04 FE FD 01

```

5. Software tools

In the following, please find a description for all tools helpful for using CAN based device communication.

5.1. HMG 4000

The HMG 4000 portable data recorder is a mobile measurement and data gathering device for measuring tasks for hydraulic and pneumatic systems and machines in industrial sectors as well as mobile sectors.

The HMG 4000 can record the signals of up to 38 sensors at once. For this purpose, HYDAC ELECTRONIC offers special sensors that are automatically detected by the HMG 4000 with configurable settings for the measured variable, measuring range and unit. In addition to this, the HMG 4000 is also able to process sensors with the standard analogue output signals, such as 0 – 10 VDC or 4 – 20 mA.

A very useful feature of the measurement device is the processing of CAN signals. The HMG 4000 is able to visualise and record process data of devices in the form of process values. This can be very useful, especially when signals from analogue sensors need to be recorded with CAN information simultaneously. This means it is possible to put information about the transmission performance of a combustion engine in relation to the pressure values in the hydraulic unit of a work function in a machine.

However, the HMG 4000 not only offers the possibility to record process values. It also has the ability to configure devices with a CAN communication interface. The "CAN Tools" function of the HMG 4000 is able to modify the "*Object dictionary*" via *EDS files* and configure the *Node ID* and the *Baud rate* via the *LSS Protocol*. In addition to this, it is able to evaluate and report incoming messages via the CAN connection. This makes the HMG 4000 a robust and handy measurement device with "outdoor" quality. This makes the HMG 4000 a robust and handy measurement device, providing nearly all the features of standard CAN analysers and configurators in "outdoor" quality., providing nearly all the features of standard CAN analysers and configurators.

The following contains a few important notes regarding the handling of CAN devices in conjunction with the HMG 4000. Further information can be found in the device's operating manual.

<https://www.hydac.com> Section: Download / Electronic

5.1.1. HMG 4000 pin assignment

The HMG 4000 has 11 * M12 5 pin connections in the form of socket connectors. All connections provide a power supply of 12 VDC / 200 mA (total current max. 500 mA). The CAN connection is the socket marked with "K" and is made of red plastic. The assignment of the CAN connection corresponds with the requirements of the CiA 303-1, see chapter 4.2.4 *Standard pin connections*.

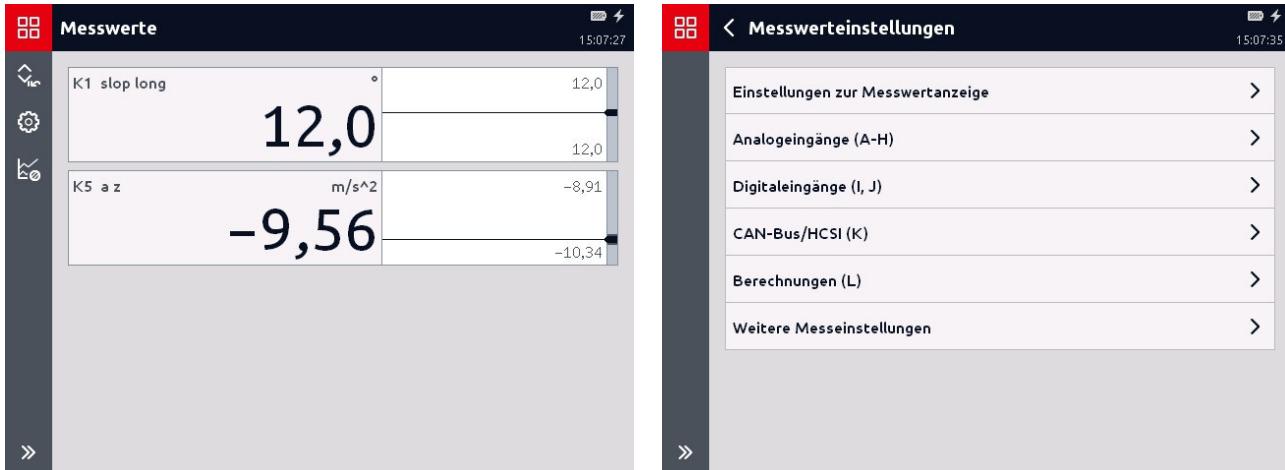


Buchse		Farbe	Kanal	Pin 1	Pin 2	Pin 3	Pin 4	Pin 5
A ... G		schwarz	A ... G	+UB	n.c.	Signal	GND	HSI
H				+UB	n.c.	Signal	GND	HSI
		schwarz	H	n.c.	PT 100 Force +	PT 100 Sense +	PT 100 GND	n.c.
I/J		blau	I / J	+UB	Digital- IN I	Digital- IN J	GND	n.c.
CAN/HCSI		rot	K	n.c.	+UB	GND	CANH	CANL
P		gelb	---	+UB	n.c.	GND	Q/C	n.c.

5.1.2. PDO Process values as measurements

The HMG 4000's "measured values" feature enables data ranges from a PDO to be visualised as a measured value. For this purpose, the channels "CAN-Bus/HCSI (K)" are available in the settings for the measured values.

In below example, the process data "signal static inclination" and "signal acceleration" are shown from an inclination sensor by HYDAC Electronic GmbH. The settings required for the measurement of the "signal static inclination (K1 slope long)" is explained more in detail.



This symbol enables access to the measured values of channel settings.



Tapping this symbol expands the function bar at the left of the screen, where short explanatory notes describe the function of each symbol.



This symbol opens a sub-function and in this particular case, opens up the channel range "CAN-Bus/HCSI (K)". After opening, a list of max. 28 single channels becomes available.

Each single channel represents exactly one *Signal or process value*, which generally corresponds with only one section of a *PDO message*. Each channel can be activated separately and configured individually.



The settings of the CAN interface are common for all channels. The HMG 4000 function "measured values" has its own CAN setting parameters which are independent of other areas in the HMG 4000.

The mode "**evaluate messages**" has to be active in order to enable the evaluation of signals from CAN messages.

The **Baud rate** has to correspond with the device which is being evaluated.

The "**Internal terminating resistor**" should always be activated when the HMG 4000 is not connected to an existing CAN network – for instance, when a particular device is directly connected to the measurement device. The internal terminating resistor should, however, be deactivated, when the measurement device is connected to an existing, correctly terminated network.

Under the same circumstances, it is also necessary to have the function "**active silent monitoring, confirm messages**" activated. The "passive monitoring" should be used when the HMG 4000 is connected to an existing CAN network and is supposed to monitor and display messages emerging here.



After opening an individual channel, its settings can be changed as well as viewed.



Channel characteristics	Description
Message type	The option "CANopen-PDO" is available for the evaluation of <i>Process data</i> . For other tasks, there are message type options available for J1939 or also for proprietary CAN messages.
Name	The channel name can be assigned individually.

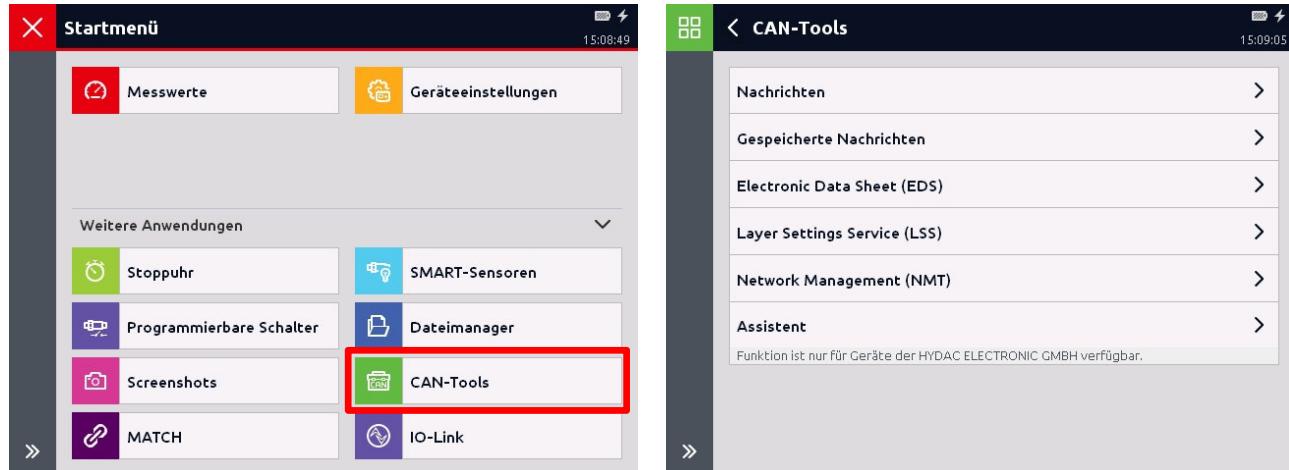
Channel characteristics	Description
Measurement range	<p>This feature serves to describe the value range and, therefore, the scaling of the process value to be displayed.</p> <p>In a sub-menu point, the number of decimal places, the max. and min. value of the measurement range and the physical unit can be entered.</p> <p>The information on the measurement range can be found in the menu process data in the product description.</p> <p>see chapter : <i>3.3 Process data</i> <i>4.5.4.9 TPDO mapping parameter</i></p>
Resolution	<p>The resolution defines the value of a single bit of the digital value transmitted with the PDO which includes the "increment" (resolution) of the scales process value.</p> <p>(Digital value * resolution) - Offset = Process value</p> <p>Example: 0,01 °/bit 0001h = 0,01°; 0005h = 0,05°; 04B0h = 12,00°</p> <p>The information on the resolution and the offset can be found in the menu process data in the product description.</p> <p>see chapter : <i>3.3 Process data</i> <i>4.5.4.9 TPDO mapping parameter</i></p>
Offset	Zero offset of the process value, see resolution.
COB ID	<p>CAN ID of the PDO message as <i>Hexadecimal value</i>.</p> <p>This value has to correspond with the CAN ID of the PDO which is going to be interpreted. As each measurement channel of the HMG 4000 is independent, the CAN ID has to be predetermined the same way as the message will be transmitted. An automatic calculation via the <i>Node ID</i> is not possible.</p> <p>see chapter : <i>4.5.4.6 RPDO communication parameter</i> <i>4.5.4.8 TPDO communication parameter</i></p> <p>Example: TPDO1.COB-ID 1800.1 \$NODEID+40000180h Active Node ID 5 Measured value COB-ID 185h</p>

Channel characteristics	Description	
Number type	The digital value of the process value transmitted with the PDO. The data length of the digital value is defined via the channel setting "bit length".	
	Unsigned integer	<i>UNSIGNED</i>
	Signed integer	<i>INTEGER</i>
	Floating point number	<i>REAL</i>
	The information on the data type can be found in the menu process data in the product description.	
	see chapter :	
	3.3 Process data	
	4.5.4.9 TPDO mapping parameter	
Bit position	The bit position defines the position of the digital value's first bit within the data range of <i>CAN Message</i> .	
	The bit position of a process value is defined via the PDO mapping. The counting method for the bit position starts with 0, which means the first bit within the CAN message's data range has the bit positon 0.	
	see chapter :	
	4.6.2.3 PDO Mapping	
	4.6.2.4 Overview diagram PDO mapping	
Bit length	The bit length defines the number of data bits occupied by the digital value within the data range of <i>CAN Message</i> .	
	The information on the data type can be found in the menu process data in the product description.	
	see chapter :	
	3.3 Process data	
	4.5.4.9 TPDO mapping parameter	

5.1.3. Functions of the HMG 4000 "CAN tools"

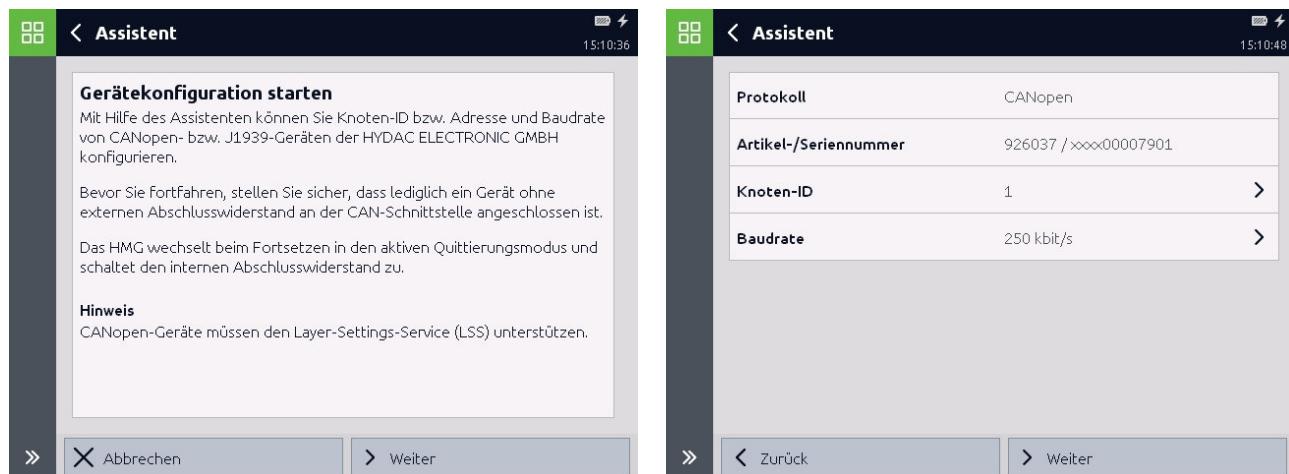
The HMG 4000 offers suitable features for many of the characteristics described in this protocol description.

The most important features are briefly explained in the following chapters.



5.1.3.1. Wizard

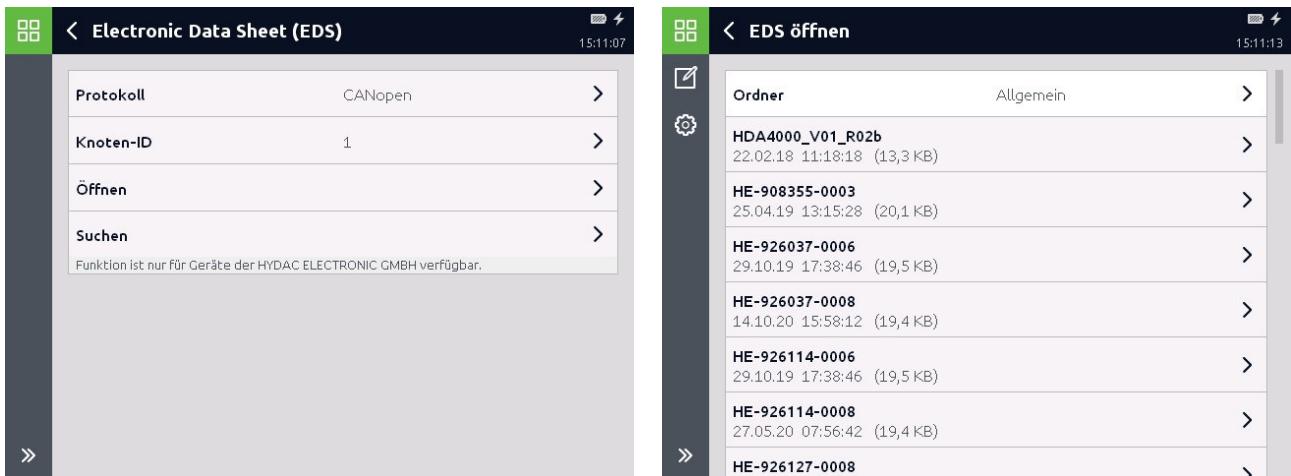
The "wizard" offers the ability to change the most important CANopen settings, such as *Baud rate* and *Node ID*, without detailed knowledge of the device. The wizard uses *LSS Protocol* for that purpose. Using this universal protocol, all devices supporting LSS can be recognised and configured.



As described in chapter 4.7.1 *LSS Communication* model, only one device should be connected to the HMG 4000 at a time while this function is used. Via the button "next", the search for a LSS capable device is started and its *LSS address* is read. The *Baud rate* and *Node ID* can subsequently be changed.

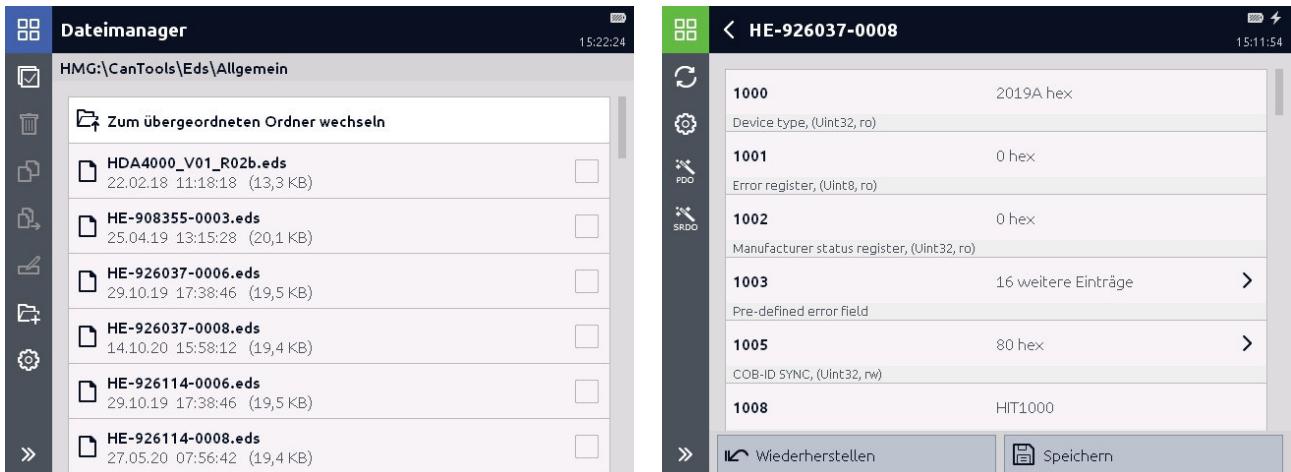
5.1.3.2. Electronic Data Sheet (EDS)

Via the function "Electronic Data Sheet (EDS)", objects of the device "Object dictionary (OD)" can be changed as well as imported.



While using this function, several devices may be connected at the same time. This is why it is inevitable to preselect the *Node ID* (node ID) of the device you wish to use before importing any data.

The suitable file for the device used can now be selected from a list of EDS files available on the HMG 4000. The files often contain the manufacturer's part number as an identifier in the file name. In a first step, available files have to be copied into the "file manager" in the HMG 4000 directory "CanTools\Eds\General". After "open", all the objects will be loaded from the OD and visualised as a list.



Object entries can now be changed as well as viewed. In order to store them on the device permanently, the function "memory" must be used. This function performs the *Object function "Save all parameters"*.

Note: If the node ID or the Baud rate are changed directly in the EDS window, the function "Save LSS parameters" also has to be changed via the EDS window, as described in chapter 4.5.4.3 *Storage and restoring (general communication objects)*.



The PDO wizard is a special feature. With this function, the *PDO Mapping* can be configured very easily. The PDO wizard leads you through all the objects of the "*communication*" and "*mapping parameter*" step by step.



The SRDO wizard is another special feature. This special wizard helps you carry out the more complicated configurations of safety-relevant process values. Whether such values are supported by this device used is described in chapter 3.4 *Functionally safe process data*.

TPDO1 Konfiguration

Zusammenfassung
Auf Basis Ihrer Angaben wurde folgende PDO Konfiguration generiert.

1800, 01	40000181 hex
1800, 02	FE hex
1800, 03	0
1800, 05	10
1A00, 00	3
1A00, 01	60100010 hex
1A00, 02	60200010 hex
1A00, 03	50000008 hex

Die Kommunikations- und Mapping-Parameter müssen nun zurück ins Gerät übertragen werden. Bitte bestätigen Sie Ihre Konfiguration durch Betätigen der Schaltfläche "Übernehmen".

Aufgrund der Konfiguration wird das Gerät automatisch in den NMT Zustand "Pre-operational" gesetzt.

» X Abbrechen ✓ Übernehmen

SRDO1 Konfiguration

Zusammenfassung
Auf Basis Ihrer Angaben wurde folgende SRDO Konfiguration generiert.

1301, 01	01 hex
1301, 02	100
1301, 03	20
1301, 05	00000101 hex
1301, 06	00000102 hex
1381, 00	2
1381, 01	60040020 hex
1381, 02	40040020 hex
13FF, 01	D9AD hex
13FE, 00	A5 hex

Die Kommunikations- und Mapping-Parameter müssen nun zurück ins Gerät übertragen werden. Bitte bestätigen Sie Ihre Konfiguration durch Betätigen der Schaltfläche "Übernehmen".

» X Abbrechen ✓ Übernehmen

5.1.3.3. Messages

The function "messages" offers the opportunity to list CAN messages which are connected to the CAN chronologically or grouped according to CAN ID. The received messages can be interpreted and represented via the HMG 4000 by order of importance, see chapter 4.3.2 *Meaning of the CAN ID*. Data flow direction R (=Rx) received by the HMG; T (=Tx) sent by the HMG.

Nachrichten

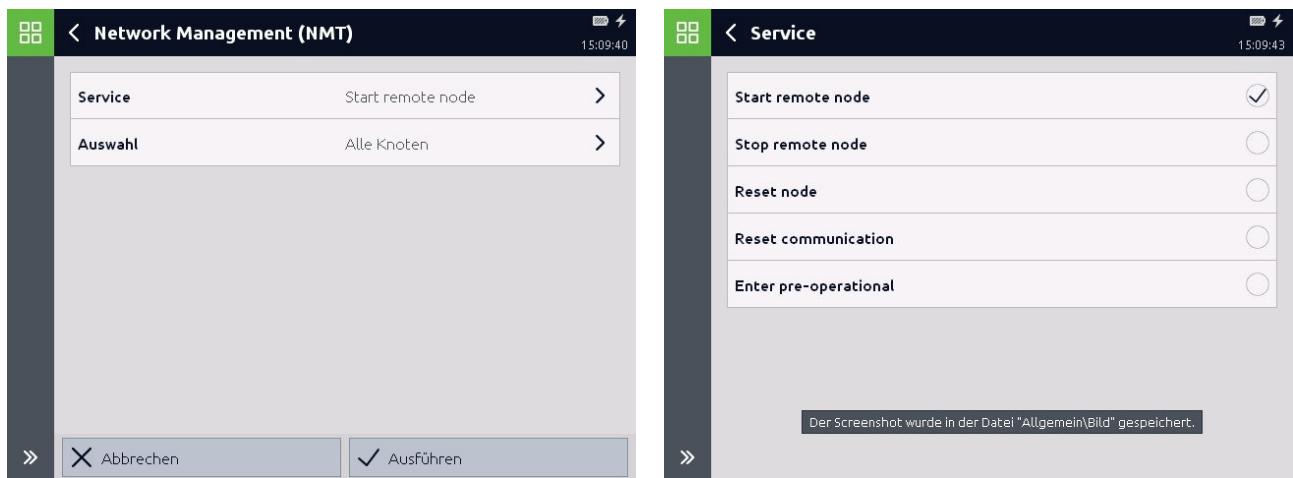
	ID [hex]	Daten [hex]	Zykluszeit [ms]	Anzahl
R	081 EMCY	00 00 00 00 00 00 00 00 [0000, 00] Manufacturer spec.	0	1
R	181 PDO	F0 FF 3A 00 00 Data, 5 Byte F0 FF 3A 00 00	10	16181
R	281 PDO	08 00 07 00 2A FC Data, 6 Byte 08 00 07 00 2A FC	10	16181
R	381 PDO	07 00 CE FF 0C 00 Data, 6 Byte 07 00 CE FF 0C 00	10	16181
R	481 PDO	E9 FF 21 00 E0 Data, 5 Byte E9 FF 21 00 E0	10	16181
R	581 SDO Server	60 10 10 01 00 00 00 00 [1010, 01] Init Download	9818	25
R	701 NMT	05 Operational	1000	77
T	000 NMT Master	81 00 Reset node, node 1 .. 127	0	1
T	601 SDO Client	23 10 10 01 73 61 76 65 [1010, 01] Init Download Exp., 4	9509	25



In addition, messages can be defined by the user which can be spontaneously or periodically sent from the HMG 4000 to further CAN participants.

5.1.3.4. Network Management (NMT)

With the sub-functions of the function "*Network Management*", the HMG 4000 can "simulate" the tasks of a *CANopen Masters* by providing the most important *NMT messages*.



Using the functions provided, the *NMT status* of the connected network participants can be changed.

5.2. PCAN-View

A widely used PC-based program for the visualisation of CAN messages is PCAN view by PEAK-System Technik GmbH.



PEAK-System Technik GmbH
Otto-Röhm-Straße 69
64293 Darmstadt
Germany

<http://www.peak-system.com/>

All rights to the product PCAN-View belong to the company PEAK-System Technik GmbH. In the following, a short insight is given into how easily CAN commands can be sent and received using this program. In addition to this, the program has further useful features which are worth discovering.

For more detailed information on the product itself or further products by this manufacturer, please do not hesitate to contact the manufacturer directly.

Empfangen						Trace	PCAN-USB
	CAN-ID	Typ	Länge	Daten	Zykluszeit	Anzahl	
701h		1	05		1000,0	777	
181h		5	E4 FF 3A 00 00		10,0	77691	
281h		6	09 00 04 00 2C FC		10,0	77691	
381h		6	D4 FF C5 FF 2A 00		10,0	77691	
481h		5	E2 FF 34 00 E0		10,0	77691	

Senden								
	CAN-ID	Typ	Länge	Daten	Zykluszeit	Anz...	Trigger	Kommentar
000h		2	81 00		Warte	1	Manuell	NMT Reset Node
000h		2	02 00		Warte	0		NMT Stop Node
000h		2	00 00		Warte	1	Manuell	NMT Start Node
000h		2	80 00		Warte	1	Manuell	NMT Enter Pre-Operational
601h		8	40 01 20 01 01 00 00 00		Warte	4	Manuell	SDO Read "active Node-ID" 2001.1
601h		8	2F 01 20 02 10 00 00 00		Warte	3	Manuell	SDO Write "pending Node-ID" 2001.2
601h		8	23 10 10 04 73 61 76 65		Warte	1	Manuell	SDO Write "StoreLSSParameter" 1010.4
080h		0			□ 10	646	Zeit	SYNC-Master

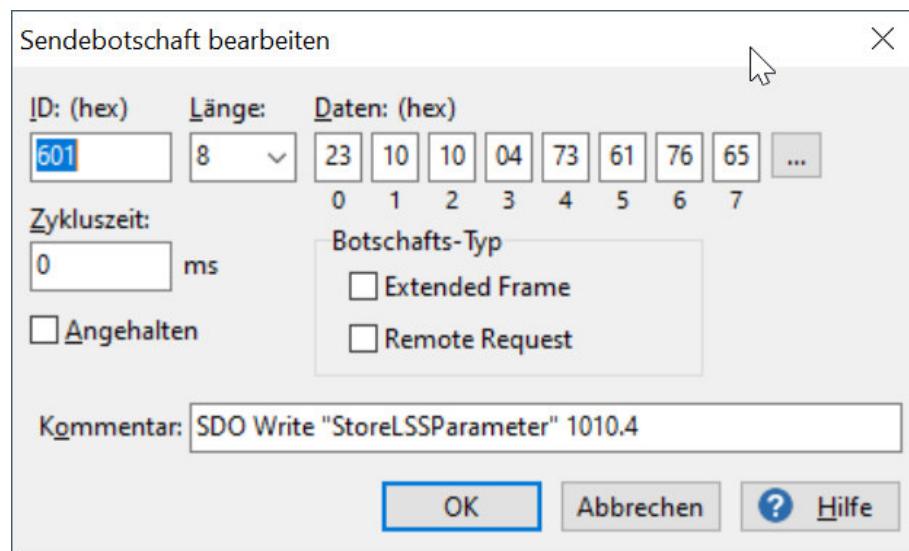
Verbunden mit Hardware PCAN-USB | Bitrate: 250 kBit/s | Status: OK | Overruns: 0 | QXmtFull: 0

In the "receive" section, all the messages currently waiting at the CAN are visualised and grouped according to *CAN ID*. In addition, the menu function "Trace" offers a chronological protocol of the messages. These protocols can also be stored in files.

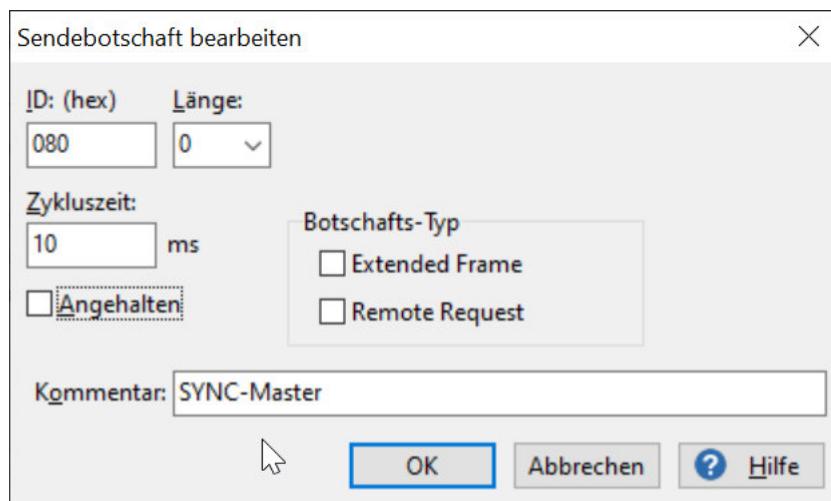
In the "**Send**" section, there is also the opportunity to send *CAN message*. Several messages can be generated for this purpose, which can be spontaneously or periodically sent.

Example for the definition of a *CAN message* of a "SDO expedited Download" command from the object "StoreLSSParameter", which enables changes to the node ID or Baud rate

of a device to be stored permanently. This message writes the *Character String "save"* having 4 bytes into the object 1010.4 in order to trigger the *Object function*. The structure of an SDO command is described in chapter 4.6.1.1 *Structure of the SDO command*.



In order to create a periodically sent CAN message, as is necessary, for instance to simulate an *SYNC Master*, a cycle time of > 0 ms has to be assigned to the message.



6. Contact data

HYDAC FILTERTECHNIK GMBH

Industriegebiet

D-66280 Sulzbach/Saar

Germany

Web: www.hydac.com

Email: Filter@hydac.com

Phone: +49 (0)6897 509-01

Fax.: +49 (0)6897 509-300

HYDAC Service

If you have any questions concerning repair work, please do not hesitate to contact HYDAC SYSTEMS & SERVICES GMBH:

HYDAC SYSTEMS & SERVICES GMBH

Friedrichsthaler Str. 15,

66540 Neunkirchen

Germany

Tel.: +49 (0)6897 509-01

NOTE

The information in this manual relates to the operating conditions and applications described. For applications or operating conditions not described, please contact the relevant technical department.

If you have any questions, suggestions or encounter any problems of a technical nature, please contact your HYDAC representative.

7. Appendix

The appendix provides useful additional information.

7.1. ASCII Table

Below is a list of the portrayable characters of the ASCII character set. By summing the horizontal and vertical identification code, the numeric value belonging to the particular character can be determined. The ASCII character encoding forms the basis of most of the character sets used for a standardised representation of the most important characters.

Particular language-specific special characters, such as the **ß** which is part of the German written language, cannot be displayed using ASCII encoding. For the representation of these characters, there are special international character sets which will not be referred to herein, as special characters are not supported by the devices.

Examples

- Vertical: 30 + Horizontal: 2 = **32d** (20h), this is the numerical value for **blank /<space>**.
- Vertical: 60 + Horizontal: 5 = **65d** (41h), this is the numerical value for **A** as a capital letter.

7.1.1. ASCII table in decimal representation

+	0	1	2	3	4	5	6	7	8	9
00										
10										
20										
30										
			<space>	!	“	#	\$	%	&	‘
40	()	*	+	,	-	.	/	0	1
50	2	3	4	5	6	7	8	9	:	;
60	<	=	>	?	@	A	B	C	E	E
70	F	G	H	I	J	K	L	M	N	O
80	P	Q	R	S	T	U	V	W	X	Y
90	Z	[\]	^	_	`	a	B	c
100	d	e	f	g	h	i	j	k	l	m
110	n	o	P	q	r	s	t	u	v	w
120	x	y	z	{		}	~			

7.1.2. ASCII table in hexadecimal representation

Example.: "zero" → 7Ah, 65h, 72h, 6Fh

+	0	1	2	3	4	5	6	7	8	9	A	W	C	D	E	F
00																
10																
20		!	"	#	\$	%	&	'	()	*	+	,	-	.	/
30	0	1	2	3	4	5	6	7	8	9	:	;	<	=	>	?
40	@	A	B	C	E	E	F	G	H	I	J	K	L	M	N	O
50	P	Q	R	S	T	U	V	W	X	Y	Z	[\]	^	_
60	'	a	B	c	d	e	f	g	h	i	j	k	l	m	n	o
70	P	q	r	s	t	u	v	w	x	y	z	{		}	~	