

# **sysWORXX CANopen I/O modules**

## **User Manual**

Document number:  
L-1070e\_13

## **Preface**

**General description** 1

**Application planning** 15

**Mounting** 17

**Connecting** 23

**Configuring** 33

**Commissioning** 55

**Maintenance and service** 59

**Functions** 61

**Error behavior and system  
messages** 85

**General technical data** 105

**Digital I/O modules** 109

**Analog I/O modules** 139

**Appendix** 189



**The following supplement is part of this documentation:**

none

This document is valid for the devices with following revision level

Module	Order-Number	Revision level
X1	3001000	03
X1	3001010	00
X2	3001001	02
X3	3001002	01
X4	3001003	03
X5	3001004	03
X6	3001005	01

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## **Danger**

indicates that death or severe personal injury will result if proper precautions are not taken.

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## **Warning**

indicates that death or severe personal injury may result if proper precautions are not taken.

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## **Caution**

with a safety alert symbol, indicates that minor personal injury can result if proper precautions are not taken.

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## **Caution**

without a safety alert symbol, indicates that property damage can result if proper precautions are not taken.

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## **Note**

indicates that an unintended result or situation can occur if the corresponding information is not taken into account.

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If more than one degree of danger is present, the warning notice representing the highest degree of danger will be used. A notice warning of injury to persons with a safety alert symbol may also include a warning relating to property damage.

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The device/system may only be set up and used in conjunction with this documentation. Commissioning and operation of a device/system may only be performed by qualified personnel. Within the context of the safety notes in this documentation qualified persons are defined as persons who are authorized to commission, ground and label devices, systems and circuits in accordance with established safety practices and standards.

### Prescribed Usage

Note the following:



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## Disclaimer

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# Preface

## Purpose of this manual

The information provided in this manual enables you to operate the distributed I/O modules of the sysWORXX Automation Series.

## Basic knowledge required

To understand the manual, you require general experience in the field of automation engineering and a general understanding about CANopen.

## Scope of this Manual

This manual is applicable to the devices of the CANopen I/O modules of the sysWORXX Automation Series.

This manual contains a description of the devices, which were valid at the time the manual was published. We reserve the right to issue a Product Information, which contains up-to-date information about new components and new versions of components.

## Guide

The manual's navigation features outlined below support quick access to specific information:

- The manual begins with a table of contents and a list of tables.
- Important terms are explained in the glossary.
- Navigate to the most important topics in our documents using the index

## Special notes

In addition to this manual, you also might need the manual of the CANopen Master (in general a PLC device) and the manual of the CANopen configuration software you are using.

## Recycling and disposal

The modules of the sysWORXX Automation Series can be recycled due to its ecologically compatible equipment. For environmentally compliant recycling and disposal of your electronic waste, please contact a company certified for the disposal of electronic waste.

The sysWORXX I/O devices shipped out after July 1<sup>st</sup>, 2006 comply with RoHS regulations (Category 9 of the Germany law "Gesetz über das Inverkehrbringen, die Rücknahme und die umweltverträgliche Entsorgung von Elektro- und Elektronikgeräten (Elektro- und Elektronikgerätegesetz – ElektroG)\*") Vom 16. März 2005", Einordnung in die Kategorie 9) issued by the European Union.

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- The right documentation and latest drivers for use with our products
- A list of our distributors and partners for our products your inquiries

# Table of Contents

<b>1</b>	<b>GENERAL DESCRIPTION.....</b>	<b>1</b>
1.1	What are distributed I/O systems? .....	1
1.2	Main characteristics of CAN .....	1
1.3	What is CANopen? .....	3
1.4	The sysWORXX Automation Series .....	8
1.5	CANopen I/O modules .....	11
1.6	Components of the sysWORXX CANopen I/O modules .....	12
1.7	HMI elements on the sysWORXX I/O modules .....	14
<b>2</b>	<b>APPLICATION PLANNING.....</b>	<b>15</b>
2.1	Compact system design .....	15
2.2	Selection guide for I/O modules .....	15
2.3	Maximum configuration .....	16
<b>3</b>	<b>MOUNTING.....</b>	<b>17</b>
3.1	Requirements .....	17
3.2	Installing the I/O modules .....	17
3.3	Installing the wiring to the connectors .....	18
3.4	Setting the CANopen node-ID, bit rate and the terminating resistor .....	20
<b>4</b>	<b>CONNECTING .....</b>	<b>23</b>
4.1	General rules and regulations for operating the sysWORXX I/O modules.....	23
4.2	Operation of sysWORXX I/O modules on grounded reference potential.....	25
4.3	Connecting the CAN-bus.....	27
<b>5</b>	<b>CONFIGURING .....</b>	<b>33</b>
5.1	General rules for configuring CANopen networks .....	33
5.2	Basic device configuration.....	39

---

5.3	Configuring using CANopen Layer Setting Services (LSS).....	42
5.4	Configuring with using Device Configuration Files (DCF) .....	49
5.5	Store/Restore device configuration .....	51
5.6	Resetting to factory settings.....	54
<b>6</b>	<b>COMMISSIONING .....</b>	<b>55</b>
6.1	Commissioning of the sysWORXX I/O modules .....	55
6.2	Startup of the sysWORXX I/O modules .....	56
<b>7</b>	<b>MAINTENANCE AND SERVICE .....</b>	<b>59</b>
7.1	Removing and inserting I/O modules .....	59
<b>8</b>	<b>FUNCTIONS .....</b>	<b>61</b>
8.1	The Object Dictionary of the sysWORXX I/O modules .....	61
8.2	CANopen Communication Services.....	65
8.3	Internal diagnostics and monitoring functions .....	73
8.4	Manufacturer specific extensions.....	75
8.5	Device identification data .....	78
8.6	Synchronized operations .....	80
<b>9</b>	<b>ERROR BEHAVIOR AND SYSTEM MESSAGES .....</b>	<b>85</b>
9.1	Device status LEDs.....	85
9.2	Reading diagnostic data .....	90
9.3	Evaluation of diagnostic messages (CANopen Emergency messages).....	92
9.4	Error behavior .....	96
9.5	Module/Network status and device guarding .....	99
<b>10</b>	<b>GENERAL TECHNICAL DATA .....</b>	<b>105</b>
10.1	Standards and certifications.....	105
10.2	Electromagnetic compatibility .....	106
10.3	Shipping and storage conditions .....	106
10.4	Mechanical and climatic ambient conditions .....	106

---

<b>11</b>	<b>DIGITAL I/O MODULES.....</b>	<b>109</b>
11.1	CANopen IO-X1, digital input and output module 16DI + 8DO DC 24V.....	109
11.2	CANopen IO-X2, digital input module 24DI DC 24V .....	122
11.3	CANopen IO-X3, digital output module 24DO DC 24V.....	130
<b>12</b>	<b>ANALOG I/O MODULES .....</b>	<b>139</b>
12.1	CANopen IO-X4, analog input module 8AI U/I .....	139
12.2	CANopen IO-X5, analog input module 8RTD .....	150
12.3	CANopen IO-X6, analog output module 8AO U/I .....	165
12.4	CANopen IO-X7, analog input module 8TC .....	176
<b>13</b>	<b>APPENDIX .....</b>	<b>189</b>
13.1	Conversation table of node-IDs.....	189
13.2	Troubleshooting .....	190
13.3	Module Dimensions.....	193
13.4	Bus cable and termination resistors .....	194

## Table of Contents

---

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# Index of Tables

Table 1: CANopen I/O module overview .....	12
Table 2: Component overview.....	13
Table 3: Selection Guide for I/O modules .....	15
Table 4: Electrical maximum configuration.....	16
Table 5: Mounting dimensions .....	17
Table 6: System startup after certain events.....	23
Table 7: Considerations for 24VDC power supply.....	24
Table 8: Protection from external electrical interference .....	24
Table 9: Protective measures.....	26
Table 10: CAN-bus interface connector pinout.....	28
Table 11: Drop cable length (single drop line).....	30
Table 12: Drop cable length (multiple drop lines) .....	31
Table 13: CANopen tools overview .....	38
Table 14: Supported bit rates of the CANopen IO devices.....	41
Table 15: Object Dictionary entries for store / restore parameter (1010H/1011H) .....	51
Table 16: SDO abort codes for store/restore configuration .....	53
Table 17: Commissioning requirements.....	55
Table 18: Object Dictionary (Communication Profile).....	63
Table 19: TPDO transmit trigger options .....	68
Table 20: Transmission type parameter overview.....	69
Table 21: Transmission type description .....	70
Table 22: Internal runtime diagnostics and monitoring functions.....	74
Table 23: Object Dictionary entries for diagnostic and monitoring functions .....	74
Table 24: Object Dictionary entries for manufacturer specific extensions .....	76
Table 25: Parameter description for manufacturer specific extensions .....	77
Table 26: Object Dictionary entry for the Identity Object .....	78
Table 27: Parameter description Identity Object .....	79
Table 28: Description of Run-LED states .....	86
Table 29: Description of Error-LED states.....	87
Table 30: Description of configuration and hardware error signaling .....	88
Table 31: User action required for error events.....	88
Table 32: Description of Run- and Error-LED at Program Control .....	89

---

Table 33: Object Dictionary entries for error data on the sysWORXX I/O devices .....	90
Table 34: Parameter description for error data .....	91
Table 35: Error conditions for digital outputs.....	92
Table 36: Error conditions for analog inputs .....	92
Table 37: Error conditions for analog outputs .....	93
Table 38: Error conditions for power supply and diagnostics.....	93
Table 39: Structure of an Emergency message.....	93
Table 40: Supported emergency error codes.....	95
Table 41: Object Dictionary entries for the Emergency COB-ID .....	95
Table 42: Parameter description for the Emergency COB-ID .....	96
Table 43: Object Dictionary entries for configuring the error behavior .....	97
Table 44: Parameter description for configuring the error behavior .....	98
Table 45: NMT state dependent communication .....	100
Table 46: NMT commands.....	101
Table 47: Response to a node/life guarding remote frame .....	101
Table 48: Node state of a CANopen device.....	102
Table 49: Heartbeat message.....	102
Table 50: Object Dictionary entries for device guarding .....	103
Table 51: Parameter description for device guarding configuration .....	104
Table 55: Shipping and storage conditions .....	106
Table 56: Climatic ambient conditions .....	107
Table 57: Modules suitable for commercial temperature range .....	107
Table 58: Modules suitable for extended temperature range.....	107
Table 61: CANopen IO-X1 device pinout.....	111
Table 62: CANopen IO-X1 technical data part common .....	112
Table 63: CANopen IO-X1 technical data part communication .....	113
Table 64: CANopen IO-X1 technical data part I/O .....	113
Table 65: CANopen IO-X1 Object Dictionary (Device specific part) .....	117
Table 66: CANopen IO-X1 parameter description .....	119
Table 67: CANopen IO-X1 default mapping.....	119
Table 68: Accessory for CANopen IO-X1 .....	121
Table 69: CANopen IO-X2 device pinout.....	124
Table 70: CANopen IO-X2 technical data part common .....	125
Table 71: CANopen IO-X2 technical data part communication .....	125

---



---

Table 72: CANopen IO-X2 technical data part I/O .....	125
Table 73: CANopen IO-X2 Object Dictionary (Device specific part) .....	127
Table 74: CANopen IO-X2 parameter description .....	128
Table 75: CANopen IO-X2 default mapping .....	128
Table 76: Accessory for CANopen IO-X2 .....	129
Table 77: CANopen IO-X3 device pinout .....	132
Table 78: CANopen IO-X3 technical data part common .....	133
Table 79: CANopen IO-X3 technical data part communication .....	133
Table 80: CANopen IO-X3 technical data part I/O .....	134
Table 81: CANopen IO-X3 Object Dictionary (Device specific part) .....	135
Table 82: CANopen IO-X3 parameter description .....	135
Table 83: CANopen IO-X3 default mapping .....	136
Table 84: Accessory for CANopen IO-X3 .....	136
Table 85: CANopen IO-X4 device pinout .....	140
Table 86: CANopen IO-X4 technical data part common .....	142
Table 87: CANopen IO-X4 technical data part communication .....	142
Table 88: CANopen IO-X4 technical data part I/O .....	142
Table 89: CANopen IO-X4 Object Dictionary .....	146
Table 90: CANopen IO-X4 parameter description .....	148
Table 91: CANopen IO-X4 default mapping .....	148
Table 92: Accessory for CANopen IO-X4 .....	149
Table 93: CANopen IO-X5 device pinout .....	151
Table 94: Device specific LED states for CANopen IO-X5 .....	152
Table 95: CANopen IO-X5 technical data part common .....	154
Table 96: CANopen IO-X5 technical data part communication .....	154
Table 97: CANopen IO-X5 technical data part I/O .....	154
Table 98: CANopen IO-X5 Object Dictionary .....	159
Table 99: CANopen IO-X5 parameter description .....	162
Table 100: CANopen IO-X5 default mapping .....	162
Table 101: Accessory for CANopen IO-X5 .....	163
Table 102: CANopen IO-X6 device pinout .....	166
Table 103: CANopen IO-X6 technical data part common .....	168
Table 104: CANopen IO-X6 technical data part communication .....	168
Table 105: CANopen IO-X6 technical data part I/O .....	168
Table 106: CANopen IO-X6 Object Dictionary .....	171

---

## Index of Tables

---

Table 107: CANopen IO-X6 parameter description .....	173
Table 108: CANopen IO-X6 default mapping.....	173
Table 109: Accessory for CANopen IO-X6 .....	175
Table 110: CANopen IO-X7 device pinout.....	177
Table 111: Device specific LED states for CANopen IO-X7.....	178
Table 112: CANopen IO-X7 technical data part common .....	179
Table 113: CANopen IO-X7 technical data part communication.....	179
Table 114: CANopen IO-X7 technical data part I/O.....	180
Table 115: CANopen IO-X7 Object Dictionary.....	184
Table 116: CANopen IO-X7 parameter description .....	187
Table 117: CANopen IO-X7 default mapping.....	187
Table 118: Accessory for CANopen IO-X7 .....	188
Table 119: Conversion table from decimal to hexadecimal Node-ID .....	190
Table 120: CAN-bus length versus bit rate .....	194

---

# Index of Figures

Figure 1: Simple CANopen network configuration.....	7
Figure 2: Complex CANopen network configuration .....	7
Figure 3: Overview of HMI elements on the sysWORXX I/O modules .....	14
Figure 4: Installation of the sysWORXX I/O modules .....	18
Figure 5: Handling of spring-type connectors.....	19
Figure 6: Handling of screw-type connectors .....	19
Figure 7: Location of configuration switches .....	20
Figure 8: CAN-bus termination switcher.....	21
Figure 9: Electrical configuration of the sysWORXX I/O modules .....	26
Figure 10: CAN-bus cable cross-view .....	27
Figure 11: CAN-bus interface connector pinout .....	28
Figure 12: CAN-bus signal description .....	28
Figure 13: Wiring schema of galvanic isolated sysWORXX I/O devices .....	29
Figure 14: Physical layout of a CANopen network .....	30
Figure 15: Example for a node-ID setup on hardware switches .....	40
Figure 16: Restore procedure .....	52
Figure 17: Startup cycle of a sysWORXX I/O device .....	56
Figure 18: PDO linking for master/slave communication structure.....	66
Figure 19: PDO linking for peer-to-peer communication structure .....	66
Figure 20: PDO transmission types.....	67
Figure 21: PDO mapping example .....	71
Figure 22: Error state blinking cycle .....	73
Figure 23: Synchronized communication principle in CANopen.....	81
Figure 24: Object dictionary entries for SYNC.....	81
Figure 25: Parameter description for synchronous operation.....	82
Figure 26: LED blinking cycles of the sysWORXX I/O modules .....	86
Figure 27: Signaling configuration or hardware errors, example for baudrate error, see Table 30.....	87
Figure 28: The NMT state machine.....	99
Figure 29: CANopen IO-X1 device schema .....	110
Figure 30: CANopen IO-X1 block diagram .....	112
Figure 31: CANopen IO-X2 device schema .....	122

---

## Index of Figures

---

Figure 32: CANopen IO-X2 block diagram.....	124
Figure 33: CANopen IO-X3 device schema.....	130
Figure 34: CANopen IO-X3 block diagram.....	132
Figure 35: CANopen IO-X4 device schema.....	139
Figure 36: CANopen IO-X4 block diagram.....	141
Figure 37: CANopen IO-X5 device schema.....	150
Figure 38: CANopen IO-X5 block diagram (3-wire connection) .....	153
Figure 39: CANopen IO-X5 block diagram (2-wire connection) .....	153
Figure 40: CANopen IO-X6 device schema.....	165
Figure 41: CANopen IO-X6 block diagram.....	167
Figure 42: CANopen IO-X7 device schema.....	176
Figure 43: CANopen IO-X7 block diagram.....	178

# 1 General description

## 1.1 What are distributed I/O systems?

Process I/Os are often installed as a central integral in the automation system configuration. Greater distances between the process I/O and the automation system may require extensive and complex wiring, which could make the system susceptible to electromagnetic interference and thus impair its reliability. Distributed I/O forms the ideal solution for such systems. While the master CPU is located centrally the distributed I/O systems (inputs and outputs, intelligent preprocessing using intelligent CANopen slaves) operate locally at a remote location the highly efficient CANopen protocol and high data transmission rates of the CAN-bus provide a smooth flow of communication between the CPU and the distributed I/O systems

## 1.2 Main characteristics of CAN

In the following the main features of the CAN protocol as standardized by the ISO 11898-1 and ISO 11898-2 are introduced.

### **Bus Topology, message rate, and number of nodes**

CAN is based on a linear<sup>1</sup> topology usually utilizing a two-wire bus media with differential signal transmission.

Hierarchical network structures are possible using repeaters or routers. The maximum number of nodes is limited by capability of the deployed driver chips, not by the protocol itself.

Repeater can be used to increase the number of nodes on the network. The maximum network extension possible at a specific bit rate is limited by the signal propagation time<sup>2</sup> along the bus medium.

### **Message-oriented protocol**

The CAN protocol is not based on addressing the message receiver, but uses the CAN-identifier for identification of transmitted messages. Based on the CAN-identifier, each node checks whether the received message is relevant for itself. Therefore, a message can be received and accepted by one or multiple nodes at the same time (broadcasting).

### **Priority of messages, Short latency time for high-priority messages**

The CAN-identifier of a CAN message directly represents its priority with regards to bus access. This allows for preferential transmission of

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<sup>1</sup> also known as "Bus Topology"

<sup>2</sup> At 1MBit/s a network length of 40m is possible. At 80 kBit/s up to 1000m bus length is possible

important messages with a low latency time regardless of the actual busload; even in exceptional situations (transmission peaks or disturbances) the transmission is ensured.

### **Multi-master capability**

On CAN, bus access does not depend on a supervisory control unit. Each node can start transmitting a message as soon as the bus becomes idle. In case of simultaneous access of several nodes, the node that wants to transmit the message with highest priority obtains access to the bus.

Transmissions are initiated by the message source. Thus, the bus is occupied only if new messages are to be sent (event controlled transmission). This results in a significant lower average busload in comparison to a system with deterministic bus access.

### **Loss-free bus arbitration**

The CAN protocol uses the CSMA/CA<sup>1</sup> access method to guarantee the transmission of the highest prior message in case of simultaneous access attempt without destruction.

### **Short frame length**

The maximum data length of a CAN message is limited to 8 bytes to guarantee a short latency time for bus access. Short messages are important to increase reliability of transmission in a distorted environment, as the probability of a coincidence with a disturbance increases proportionally with the frame length.

Transmission of data with size higher than 8 bytes is handled by services provided with the higher layer protocol such as the SDO<sup>2</sup> in CANopen.

### **High data integrity and very short recovery time**

The CAN protocol features several complementary mechanisms for detection of corrupted messages with a very high probability including automatic re-transmission of incorrectly transmitted or received messages. Unlike node-oriented protocols, CAN provides a very short error detection, signaling and correction time.

### **Network wide data consistency**

A system wide data consistency is fundamental for data integrity in distributed systems. In process control applications the operation of several nodes need to be synchronized frequently. This requires the data and synchronization messages to be received correctly and

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<sup>1</sup> Carrier Sense Multiple Access / Collision Avoidance

<sup>2</sup> Service Data Object

simultaneously by involved nodes. Thus, locally disturbed messages must be known to be invalid by all nodes. The error signaling mechanism defined within the CAN protocol provides this basic requirement.

### **Detection and de-activation of defective nodes**

Within the CAN protocol a monitoring of the communication-specific functions is defined. If a node exceeds pre-defined error rates, measures are taken to prevent defective nodes from continuously disturbing the data communication.

### **International standardization**

The international standards ISO 11898 Part 1, 2 and 3 specify CAN as OSI-Layer 1/2 protocol. As a higher layer protocol for general industrial application, CANopen was specified by the CAN in Automation (CiA) and applied as European standard EN 50325-4.

## **1.3 What is CANopen?**

### **What is CANopen?**

CANopen is a standardized CAN-based protocol for industrial distributed automation systems. In Europe CANopen can be regarded as the de-facto standard for implementation of industrial CAN-based systems.

In 1995, the CANopen specification was handed over to the CAN in Automation (CiA) international users' and manufacturers' group and is now standardized as CENELEC EN 50325-4.

CANopen offers the following performance features:

- Transmission of time-critical process data (see *Section 8.2*) according to the producer consumer principle
- Standardized device description (data, parameters, functions, programs) in the form of the so-called "object dictionary". Access to all "objects" of a device with standardized transmission protocol (SDO protocol) according to the client-server principle. (See *Section 8.2*)
- Standardized services for device monitoring (node guarding/heartbeat), network management ("NMT messages", boot-up messages") and error control (Emergency messages) (see *Section 8.2*, 9.5)
- Standardized system services for synchronous operations (SYNC messages), central time stamp message (see *Section 8.2*, 8.6)
- Standardized functions for remote configuring of bit rate and device identification number via the bus (see *Section 5.3*)

- Standardized CAN identifier assignments based on the node-ID simplify the system configurations in the form of the so-called "predefined connection set"

### The Object Dictionary concept

The central element of the CANopen standard is the description of all device-specific functionality, parameters and data-types by an "Object Dictionary" (OD). Thereby, the Object Dictionary can be seen as a lookup table with a 16-bit Index and an 8-bit Subindex. This allows for up to 256 Subentries per Index. Each entry can hold one variable of any type (including a complex structure) and length. In the following sections the terms Object and Subindex will be used when describing such Object Dictionary entries.

All process and communication related information is stored as entries in predefined locations of the Object Dictionary. Therefore the Object Dictionary is divided in several sections containing general specifications about the device such as identification data and manufacturer, a section containing communication parameters, and a section with device specific functionality. All entries of the Object Dictionary are accessible from the "outside" via CAN using SDO communication (see *Section 8.2*). Therefore, a CANopen device is completely remote configurable, which provides the basis for the manufacturer independence targeted by CANopen.

### CANopen profiles

CANopen is based on a so-called "communication profile" that specifies basic communication mechanisms and services (CiA 301). Further profiles and frameworks exist, specifying extended functionality for use with programmable devices (CiA 302) or safety relevant communication (CiA 304).

In addition to the communication profiles there are so-called "device profiles" for important types of industrial devices, such as generic digital and analog I/O devices (CiA 401), drives (CiA 402), IEC 61131-3 programmable devices (CiA 405) or encoders (CiA 406). The device profiles are add-on specifications that describe all the communication parameters, device-specific features and Object Dictionary entries that are supported by a certain type of CANopen module. A master or configuration tool can read-access the identity object (see *Section 8.5*) of any slave node to receive the information about which device profile a module conforms to.

Sometimes an application requires the implementation of not standardized, manufacturer-specific Object Dictionary entries. This is possible due to the open structure of CANopen. Additional entries that disable or enable a certain functionality that is not covered by one of the existing device profiles can be implemented in any device, as long



as they conform to the structural layout of the Object Dictionary (see *Section 8.4*).

## **Electronic Data Sheets**

In addition, the functionalities and characteristics of each CANopen device are described in a so-called “Electronic Data Sheet” (EDS) stored in ASCII or XML format (CiA 306). The EDS offers a standardized way of specifying supported Object Dictionary entries and can be seen as a template for describing the device configuration. The actual device configuration is stored in a so-called “Device Configuration File” (DCF) and, for example, contains the resolved communication and mapping parameters for process data communication (see *Section 5.4*).

A CANopen master or configuration tool can directly load the EDS into its set of recognized devices. Once the device was found on the network, all supported Object Dictionary entries are known by the master or configuration tool.

The Device Profile specifies the minimum entries that need to be supported by a device conforming to the profile. However, the EDS might only specify objects that are specific to a certain manufacturer or sub-type of module.

Device Profiles and Electronic Data Sheets are the basic functionality needed to meet the requirement for “off-the-shelf” availability of network devices. From the communication point of view, any two nodes that conform to the same EDS are interchangeable, their Object Dictionaries are identical and they have the same communication behavior.

## **What are CANopen Slaves, CANopen Masters and CANopen Managers?**

Within a distributed system the application process is divided into several parts running on different nodes. From the applications point of view usually one node is responsible for the control and management of the distributed control system. This node (e.g. a PLC) is called application master. CANopen devices without management functions are generally supposed to be CANopen slave devices (e.g. I/O modules).

However, it is possible to operate the sysWORXX I/O modules without having a master on the network. Therefore the sysWORXX I/O modules feature a so-called “simple boot-up NMT master”<sup>1</sup> implemented as manufacturer specific extension. See *Section 8.4* for more information.

---

<sup>1</sup> The device can switch to NMT state OPERATIONAL autonomously and sends out the corresponding NMT message to start other devices as well (see *Section 9.5*).

The term CANopen Manager is used to specify more clearly the network functionality of a network-controlling device in a CANopen network:

- Definition of the Boot-Up process for each device that is to be managed.
- Configuration of unconfigured nodes during system boot-up.
- The dynamic establishment of SDO connections between devices. The SDO Manager handles dynamic SDO connections.
- The definition of dynamically allocated entries (Network Variables) in an object dictionary which can be used for the representation of I/O data e.g. on programmable nodes like PLCs.
- Provides services for downloading program data and functions for the control of programs on a device.

The PLC devices of the sysWORXX Automation Series provide CANopen Manager functionality and therefore can be used as Application Master for your CANopen network. Please refer to Section 1.4 for more information about the sysWORXX Automation Series.

### **Which devices can be connected to a CANopen network?**

CANopen devices that at least comply with the CANopen specification CiA 301 can be connected to a CANopen network.

Furthermore, all devices connected to the same CAN-bus segment have to support the same physical layer and an identical bit rate.

All sysWORXX I/O modules support high-speed CAN according to ISO 11898-2. Coupler devices and gateways may be used to extend the network size or to connect CAN-bus segments with different physical layer and/or bit rate.

Within a CANopen network each device has a so-called “node-ID”, which is used to identify a specific node. The valid range for node-IDs is from 1 to 127.

By this schema, a CANopen network can have 127 nodes theoretically. Practically, this number is limited by the CAN transceivers used, which typically support up to 100 nodes on the same bus. The CAN transceivers used on the sysWORXX I/O modules support up to 110 nodes.

To put a CANopen network into operation, two basic conditions must be fulfilled:

- All nodes must be configured to the same bit rate and
- The assigned node-IDs are unique.

The system integrator needs to ensure these conditions are fulfilled, as there are no off-shelf mechanisms that can ensure this conditions automatically.

Usually the node-ID is configured directly on the device via hardware switches (see *Section 5.2*). Alternatively, the node-ID and bit rate can be configured via the so-called "Layer Setting Service" (LSS). Please refer to *Section 5.3* for detailed information.

**Configuration of a CANopen network**

The figure below illustrates the typical configuration of a CANopen network. The CANopen masters are integrated in the corresponding device. CANopen slaves form the distributed I/O systems, which are connected to the CANopen masters via CAN-bus.



Figure 1: Simple CANopen network configuration

The PLCmodule-C14, for example, features two CAN-bus interfaces, which allows for connecting the PLC to two different CANopen networks.

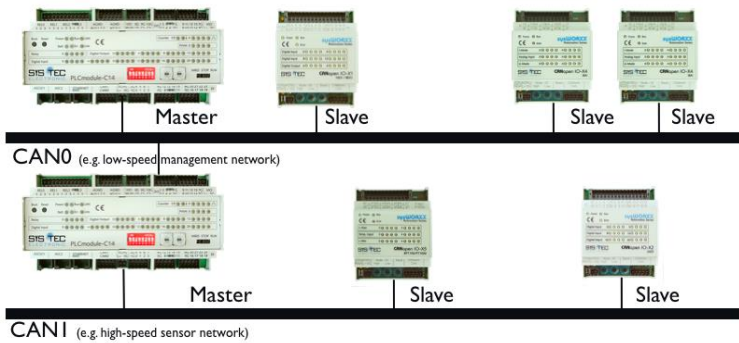


Figure 2: Complex CANopen network configuration

## 1.4 The sysWORXX Automation Series

The sysWORXX Automation Series combines harmonized devices and software tools, needed to create sophisticated industrial distributed automation solutions.

**The sysWORXX Automation Series includes:**

- IEC 61131-3 compliant controls
- CANopen I/O modules
- CANopen Human Machine Interfaces (HMI)
- Integrated IEC 61131-3 Development System
- CANopen Configuration Tools
- CAN-bus interfaces and gateways

**IEC 61131-3 controls:**

### ***PLCmodule-C14 and CANopen PLC***

The sysWORXX PLC modules are high-performance and versatile compact PLCs. They have a number of communications interfaces and a large selection of industry-proven inputs and outputs.

Feature	PLCmodule-C14	CANopen PLC
Order No.	phyPS-412-Z5	3000001
CAN-bus interface according to ISO 11898-2	2, galvanic isolated, each can be operating in CANopen Master or Slave mode	1, galvanic isolated, can be operating in CANopen Master or Slave mode
RS232	3	2
Ethernet	10baseT Ethernet interface for uplink to management PC (for program download, monitoring)	
Digital Inputs	24, isolated, 24VDC	24, 24VDC
Digital Outputs	16, isolated, 24VDC, 500mA, high-side switches	16, 24VDC, 500mA, low-side switches
PWM/PTO Outputs	2, isolated, 24VDC, 500mA, 15kHz	2, 24VDC, 500mA, 70kHz
Analog Inputs	4 channels, 0..10V, 10-bit	4 channels 0..10V and 4..20mA 12-bit or 14-bit
Counter/Encoder Inputs	3 counter (pulse/dir), isolated, 24VDC, 70kHz	2 encoder, a/b and pulse/dir, 24VDC, 70kHz 1 counter, 24VDC, 70kHz
Relay outputs	4 channels, 230VAC/3A, NO	4 channels, 230VAC/3A, NO
Power supply	24VDC	

## **Integrated IEC 61131-3 development environment**

OpenPCS is an comprehensive IEC 61131-3 workbench certified by PLCopen.

- PLCopen certified IEC 61131-3 compiler
- Sequential Function Charts (SFC)
- Continuous Function Charts (CFC)
- Ladder Diagrams (LD)
- Structured Text (ST) and Instruction List (IL) for function block programming (IL&ST Base Level certified)
- Function block libraries for configuration of sysWORXX I/O modules
- Comprehensive CANopen function block library
- Extended function library (e.g. RTC, non-volatile memory, process control, string manipulations)
- Supports multiple controllers in one project file
- Complete support of CANopen Network variables for data exchange
- Online monitoring and power-flow for easy troubleshooting
- Online change for fast debugging cycles
- Offline simulator
- Integrated OPC Server
- Device access possible via Ethernet, USB, Parallel Port or RS232
- Project documentation support

## **CANopen configuration tools**

The CANopen Configuration Suite is a powerful, intuitive and user-extendable tool chain for configuration and management of CANopen networks and devices. It includes the CANopen DeviceExplorer with Process Data Linker plug-in as well as the SYS TEC CAN-driver. Various CAN-bus interfaces of different manufactures are supported. By using the CANopen Configuration Suite your workload will be reduced significantly. Especially when the system becomes more complex. The risk of configuration errors is minimized, and the quality and reliability of the system is enhanced.

- Project-oriented management of all configuration and device data based on EDS and DCF
- Supports download of the device and network configuration via CAN-bus

- Simple and intuitive interface for all configuration tasks in your network
- Quick access to the device parameters and network structure
- Automatic PDO mapping and PDO linking
- Optional PDO linking based on Pre-Defined Connection Set – thus it is not necessary to configure every CANopen slave device
- Strip-chart visualization of PDO data
- Selective readout of the object directory from connected CANopen nodes
- Automatic scanning for CANopen nodes in the network
- Support of network variables in accordance with the CiA 302 and CiA 405 specification
- Export of all assigned network variables as IEC 61131-3 conformant variable declaration
- Script functionality with comprehensive high-level CANopen API for easy realization of automated processes and extension of functionality
- Expert console window for quick command line access to the CANopen functionality

### **CAN-bus interfaces and gateways**

#### ***USB-CANmodul1***

- Low-cost USB2.0/CAN interface in table case
- PC driver supports up to 64 devices simultaneously
- Power via USB

#### ***USB-CANmodul2***

- USB2.0/CAN interface in table case
- 2 CAN interfaces, optional one LIN possible
- PC driver supports up to 64 devices simultaneously
- High-precision transmission timer
- 8-bit I/O port (TTL-level)
- Power via USB

**USB-CANlog**

- CAN-bus data logger with USB/CAN interface
- Stand-alone operation
- 2 CAN interfaces
- Supports SD-cards up to 1GB size
- Selective Triggers and message filters
- External power-supply 9...30VDC

**CAN-Ethernet Gateway**

- Supports all higher-layer CAN protocols
- Up to 4 connections per device
- High-speed transmission of CAN messages (bulk)
- High-precision timestamps for CAN frames
- ASCII based device configuration (Telnet or RS232)
- Configurable message filters

## 1.5 CANopen I/O modules

### Definition of the sysWORXX CANopen I/O modules

The sysWORXX CANopen I/O modules are compact distributed I/O devices, with degree of protection IP20.

### Fields of application

Its compact design and its high I/O density make the sysWORXX CANopen I/O devices suitable for use in machine automation. With IP20, the sysWORXX CANopen IO-X devices are protected against the ingress of foreign particles greater diameter 12.5mm. The sysWORXX CANopen I/O modules support communication with other CANopen devices, which are compatible to CiA 301 and/or CiA 302 standard.

### CANopen I/O modules overview:

The following sysWORXX I/O devices are offered:

Name	Description	Order number
CANopen IO-X1	8 DO and 16 DI, 24VDC	3001000
CANopen IO-X1	8 DO (pulsed) and 16 DI, 24VDC	3001010
CANopen IO-X2	24 DI, 24VDC	3001001

Name	Description	Order number
CANopen IO-X3	24 DO, 24VDC 500mA	3001002
CANopen IO-X4	8 AI, 16-bit ADC	3001003
CANopen IO-X5	8 RTD, 12-bit ADC	3001004
CANopen IO-X6	8 AO, 10-bit DAC	3001005
CANopen IO-X7	8 TC, 12-bit	3001006

Table 1: CANopen I/O module overview

## Installation

The sysWORXX I/O modules were designed for DIN-rail mounting and always include the complete set of terminal plugs.

You can thus set the focus of your configuration on local requirements. The comfortable handling features of the sysWORXX I/O modules ensure quick commissioning and easy maintenance.

## 1.6 Components of the sysWORXX CANopen I/O modules

The list below introduces the vital parts and components delivered with the sysWORXX I/O modules:

Component	Function	
I/O device	<p>The I/O devices incorporates the device electronics, LED interface and socket connectors. The following subsystems are included:</p> <ul style="list-style-type: none"> <li>– Embedded microcontroller</li> <li>– Reset &amp; watchdog circuit</li> <li>– CAN-bus interface</li> <li>– Configuration units</li> <li>– Non-volatile memory for storage of configuration data</li> <li>– Device specific I/O circuitry</li> <li>– Voltage regulator for 24VDC power supply</li> <li>– LED interface</li> </ul>	
I/O plug	Removable spring-type plug	



Component	Function	
connector	connector, used to connect the sensors and actuators. The connector block can be fixed on the socket by screw. There are 3 types used: 30-pin for IO-X1 to IO-X3 24-pin for IO-X4 to IO-X6 16-pin for IO-X7	
CAN-bus connector	Removable 5-pin screw-type plug connector, used to connect the CAN-bus lines. The connector pinout complies with DS 102.	
Power supply connector	Removable 3-pin screw-type connector to connect power supply.	

Table 2: Component overview

## 1.7 HMI elements on the sysWORXX I/O modules

### Introduction

This section describes the HMI elements on the sysWORXX I/O modules.

### Overview

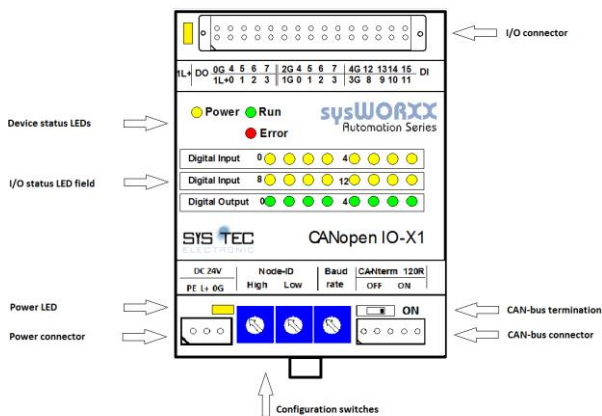


Figure 3: Overview of HMI elements on the sysWORXX I/O modules

## 2 Application planning

### 2.1 Compact system design

A compact system design in the context of the sysWORXX I/O modules means: You can adapt the configuration to meet the requirements of your application by means of combining various I/O modules by CAN-bus.

### 2.2 Selection guide for I/O modules

#### Help for the selection of I/O modules

The table below helps you to select the right I/O module for different applications:

Application	I/O module	
Evaluating signals of switches, proximity switches, digital sensors	16 DI, 24V DC	CANopen IO-X1
	24 DI, 24V DC	CANopen IO-X2
Switching solenoid valves, DC-contactors, signal lamps	8 DO, 24V DC, 0.5 A	CANopen IO-X1
	24 DO, 24V DC, 0.5 A	CANopen IO-X3
Switching/piloting proportional valves, servo drives, proportional actuators	8 AO 0...10 V; 4...20 mA; 0...20 mA	CANopen IO-X6
Voltage measurement	8 AI, ±10 V; 0...10 V	CANopen IO-X4
Current measurement	4 AI 4...20 mA; 0...20 mA	CANopen IO-X4
Measuring low to medium temperatures	8 RTD PT100, PT1000	CANopen IO-X5
Measuring medium to high temperatures (up to 1870°C)	8 thermo-couple sensors of type J, K, L, R, S, T, E	CANopen IO-X7

Table 3: Selection Guide for I/O modules

## 2.3 Maximum configuration

### Maximum number of nodes on the CAN-bus

The CAN-bus drivers used on the sysWORXX I/O modules support up to 110 nodes simultaneously connected to the same CAN-bus segment.

### Electrical maximum configuration

#### *Electronic supply L+:*

Supplies power to the internal electronic circuit of the modules.  
Supplies the digital outputs on CANopen IO-X1 and CANopen IO-X3.

There are additional connection points (1L+, 2L+, 3L+, ect.) to supply power to the outputs.



#### **Warning**

If the digital outputs are connected to the process, the additional supply points for power (1L+ ... 3L+) must be connected. Otherwise a shortcut might lead to damages on the PCB or power supply connector.

On sysWORXX I/O modules without isolated CAN-bus, L+ is connected to the supply lines of the CAN-bus (CAN\_V+).

Properties	Limitations
Electronics supply L+	1A (if additional supply points for outputs 1L+...3L+ are not used)
Digital supply 1L+ ... 3L+	4 A each supply point

Table 4: Electrical maximum configuration

### Mechanical maximum configuration

The I/O connector used supports connection of cables up to a diameter of 1mm<sup>2</sup>. Do not connect more than one cable to a single I/O point. It is recommended to use flexible cable types for wiring to the terminal block.

## 3 Mounting

### 3.1 Requirements

#### Pre-assembly

You can pre-assemble the modules on a DIN-rail before you install it on site.

#### Mounting position

The modules can be installed in any mounting position.

#### Mounting dimensions

See also Appendix Module Dimensions on page 193.

Mounting dimensions	Comment	Dimension
Mounting width		71 mm
Mounting height	with I/O terminal block assembled	96 mm
	without I/O terminal block assembled	94.8 mm
Mounting depth	starting from DIN-rail	53.58 mm

Table 5: Mounting dimensions

### 3.2 Installing the I/O modules

#### Introduction

The module features removable terminal blocks to connect to the CAN-bus, I/O wiring and power-supply. The module can be installed without terminal blocks assembled.

#### Requirements

If the devices are mounted on a DIN-rail, it must be mounted on the rack or solid surface.

#### Required tools

Slotted screwdriver with 4 mm blade.

#### Procedure

- (1) Place the module onto the DIN-rail as shown below. Use a slotted screwdriver to lift the lug (1), and then push it on until it engages with an audible click.
- (2) Slide it into the working position.

**Caution**

Do not twist the screwdriver while it is placed in the lug. It will lead to the destruction of the lug.

Do not use the enclosure as a support point for the screwdriver. Otherwise the hardware switches or the enclosure might be damaged.

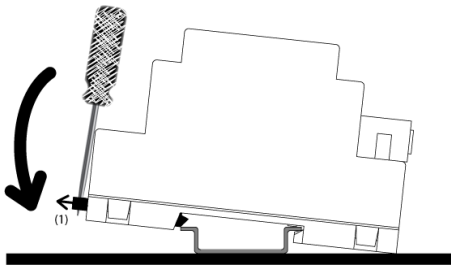


Figure 4: Installation of the sysWORXX I/O modules

**See also**

Section 6, Commissioning the sysWORXX I/O modules at page 55

### 3.3 Installing the wiring to the connectors

**Introduction**

The module has two kinds of removable terminal blocks:

- (1) Spring-clamp type for I/O and CAN-bus
- (2) Screw-type for power-supply

**Requirements**

Before you wire any of the modules, either switch off power or remove the relevant connector terminal blocks.

**Required tools**

Slotted screwdriver with 2,5 mm blade.

**Procedure for placing the connector**

- (1) Place the connector on the socket then push it on until it engages with an audible click.
- (2) If necessary fix the I/O connector by the two screws located on both sides.

## Procedure for placing the wires

Spring-clamp type (see *Figure 5*)

- (1) Push the screwdriver into the rectangular hole of the I/O point you intend to wire. Make sure not to exceed the physical dimensions of the connection point.
- (2) Insert the cable end and remove the screwdriver.

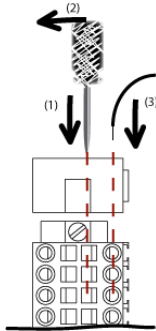


Figure 5: Handling of spring-type connectors

Screw type (see *Figure 6*)

- (1) Open the screw and insert the cable.
- (2) Close the screw.

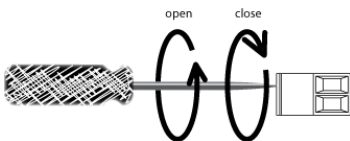


Figure 6: Handling of screw-type connectors

## See also

Section 6, Commissioning the sysWORXX I/O modules at page 55

### 3.4 Setting the CANopen node-ID, bit rate and the terminating resistor

#### Introduction

After mounting the module you need to set the CANopen node-ID and terminating resistor at the module.

- The CANopen node-ID defines the address of the node within the CANopen network. The node-ID directly represents the message priority of this particular node.
- A CAN-bus segment must be terminated at both ends, i.e. on the first and last segment node, with its characteristic impedance. Enable the integrated terminating resistor if the device is the last node on the CAN-bus (see *Section 4.3*).

#### Requirements

The set node-ID must correspond with the definition in the Device Configuration File of this device.

Configure the node-ID and bit rate before you power-on the module. If you change while the module is powered-on, the changes become effective after reset or on next power-on.

#### Required tools

Screwdriver with 2,5 mm blade

#### Setting the CANopen node-ID and CAN-bus bit rate

- (1) Set the node-ID using the hex-encoding switches (see the example below).
- (2) Set the CAN-bus bit rate using the hex-encoding switches (see the example below).

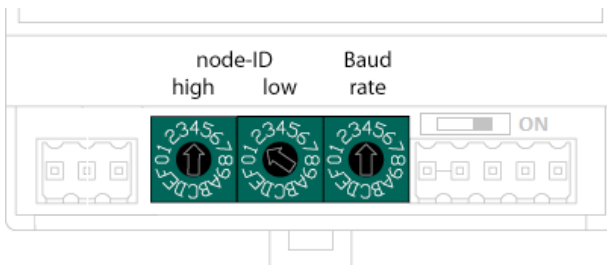


Figure 7: Location of configuration switches

For further information on how to set the node-ID and bit rate refer to *Section 5.2*.



## Enabling the terminating resistor

If this device is the first or last node on the CAN-bus, enable the internal terminating resistor.

You need to remove the CAN-bus terminal connector before you can set or remove the jumper.

- (1) To enable the termination turn the switcher on.
- (2) To disable the termination turn the switcher off.

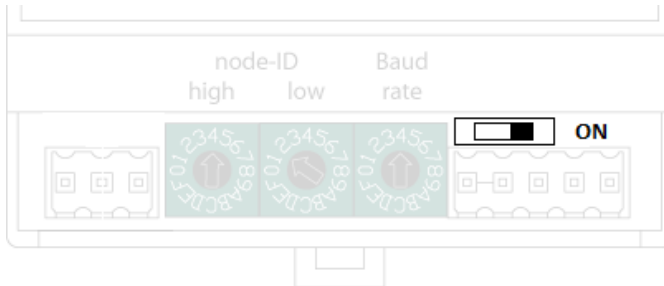


Figure 8: CAN-bus termination switch

## See also

Section 4.3, Connecting the CAN-bus

Section 5.1, General rules for configuring CANopen networks

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## 4 Connecting

### 4.1 General rules and regulations for operating the sysWORXX I/O modules

#### Introduction

The distributed I/O modules represent a component of plants or automated systems, and thus is subject to special rules and regulations based on its application.

This section provides an overview of the most important rules you have to observe when integrating the sysWORXX I/O modules into a plant or system.

#### Specific application

Observe the safety and accident prevention regulations for specific applications, for example, the machine protection directives.

#### EMERGENCY-OFF equipment/components

EMERGENCY-OFF equipment must remain effective in all operating states of the plant or system.

#### System startup after certain events

The table below shows what you have to observe when restarting a plant or system as a result of specific events.

If ...	then ...
there was a restart following a voltage drop or power-fail	dangerous operating states must not develop. If necessary, force an "EMERGENCY STOP".
there was a startup after interruption of bus communication.	the system must never perform an uncontrolled or undefined restart.

Table 6: System startup after certain events

#### 24VDC power supply

The table below shows essential aspects of the 24VDC power supply.

For ...		you need to observe ...
buildings	external lightning protection	lightning protection precautions ( e.g. lightning protection elements)
24VDC power supply cables and signal cables	internal lightning protection	
24VDC power supply	safe (electrical) isolation of the safety extra-low voltage (SELV)	
Daisy-chaining the power supply	voltage drop when daisy-chaining the power supply.	

Table 7: Considerations for 24VDC power supply

### Protection from external electrical interference

The table below shows how to protect your system against electromagnetic interference or faults.

For ...	make sure ...
all systems or plants that contain a sysWORXX I/O device	that the system is properly grounded in order to allow the EMC-conformant discharge of electromagnetic interference.
power supply, signal cables and bus cables	that the cables are properly routed and the installation is free of faults.
signal and bus cables	that cable or wire break does not lead to undefined states of the system.

Table 8: Protection from external electrical interference

## 4.2 Operation of sysWORXX I/O modules on grounded reference potential

### Introduction

This section provides information on the overall configuration of a sysWORXX I/O module on a grounded TN-S power supply. The following topics are covered:

- Disconnecting devices, short-circuit and overload protection according to VDE 0100 and VDE 0113
- Load power supplies and load circuits

### Grounded mains

The neutral of grounded mains is always bonded to ground. A short-circuit of a live conductor or grounded part of the system to ground trips the protective devices.

### Safe electrical isolation (SELV/PELV to IEC 60364-4-41)

The sysWORXX I/O modules require power supplies or power supply modules with safe electrical isolation.

### Installation with grounded reference potential

in an system with grounded reference potential, any interference current is discharged to protective earth. The terminals need to be interconnected externally (G ↔ PE.)

### Components and protective measures

Regulations stipulate the implementation of diverse components and protective measures when installing the plant. The type of components and the binding character of protective measures depends on the DIN regulation which applies to your application. The table refers to *Figure 9* below.

For ...	Reference to Figure 9	DIN VDE 0100	DIN VDE 0113
Disconnecting devices for control systems, signal generators and final control elements	①	Part 460: main switch	Part 1: mains disconnect switch

For ...	Reference to Figure 9	DIN VDE 0100	DIN VDE 0113
Short-circuit and overload protection	②	Part 725: Single-pole fusing of circuits	Part 1: grounded secondary power circuit: single-pole fusing
Line protection	⑤	Part 430: Protection of cables and lines against over-current	

Table 9: Protective measures

### Overall configuration of a sysWORXX I/O device

The *Figure 9* below shows the overall configuration of a sysWORXX I/O device (load voltage supply and grounding concept) which is operated on TN-S mains.

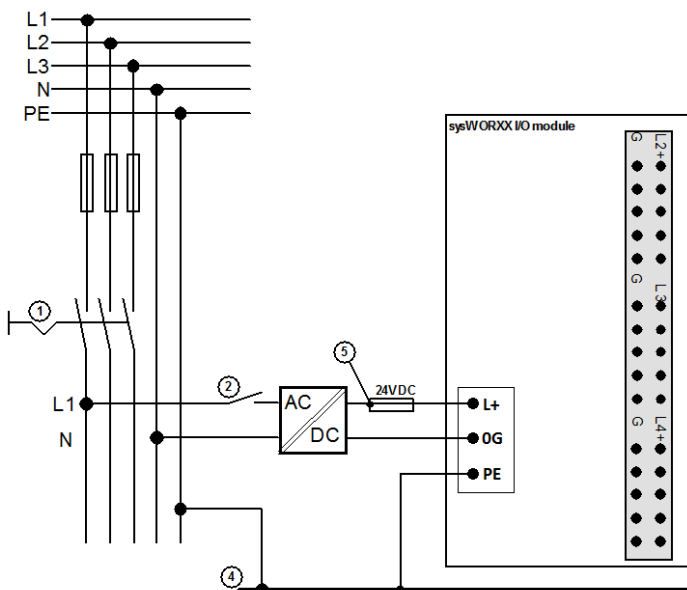


Figure 9: Electrical configuration of the sysWORXX I/O modules

- ① To disconnect devices for the control system, signal

- generators and final control elements
- ② For short-circuit and overload protection
- ③
- ④ Grounding bus bar
- ⑤ Fuses for line protection

## 4.3 Connecting the CAN-bus

### Introduction

This section provides an overview on how the sysWORXX I/O modules are connected to the CAN-bus and gives hints for wiring and cabling the bus.

### Wiring and cabling

Although CAN is supposed to be a 2-wire network an additional common ground is required for reliable operation, especially if the network spreads over a longer distance.

#### CAN-bus cable

Using screened twisted-pair cables ( $2 \times 2 \times 0,25 \text{ mm}^2$ ) with a characteristic impedance of between  $108$  and  $132 \Omega$  is recommended for the CAN-bus wiring.

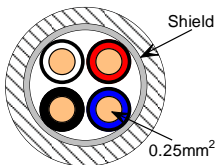


Figure 10: CAN-bus cable cross-view

SYS TEC electronic has high quality CAN-cables in its scope of delivery. Please contact our sales for a proper quotation.

**CAN-bus interface connector pinout on the sysWORXX I/O modules**

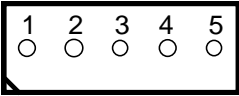


Figure 11: CAN-bus interface connector pinout

Pin	CAN-bus signal / Description
1	CAN_GND
2	CAN_L
3	n.c.
4	CAN_H
5	CAN_V+ (connected to L+ on modules without galvanic isolation, not used on modules with galvanic isolated CAN)

Table 10: CAN-bus interface connector pinout

**CAN-bus signal description**

Signal	Description
CAN_L	Bus line that is driven lower during the dominant bus state.
CAN_H	Bus line that is driven higher during the dominant bus state.
CAN_GND	This is the common ground used by the CAN nodes. This might not be needed if the nodes have a common ground anyway.
CAN_SHLD	Optional shield around CAN_L and CAN_H (not used on sysWORXX I/O modules)
CAN_V+	If a CAN node is supplied with its operating power via the CAN cable this line is connected to the positive line of the power supply. The voltage levels are not specified and depend on the application. For sysWORXX I/O modules, the used voltage should be 24V DC.
	<b>Note</b> The maximum current should not exceed the specified limit of the cable used.

Figure 12: CAN-bus signal description



The wiring schema of a sysWORXX I/O device is shown in *Figure 13*.

### Note

For reliable operation CAN\_L, CAN\_H and CAN\_GND must be wired.

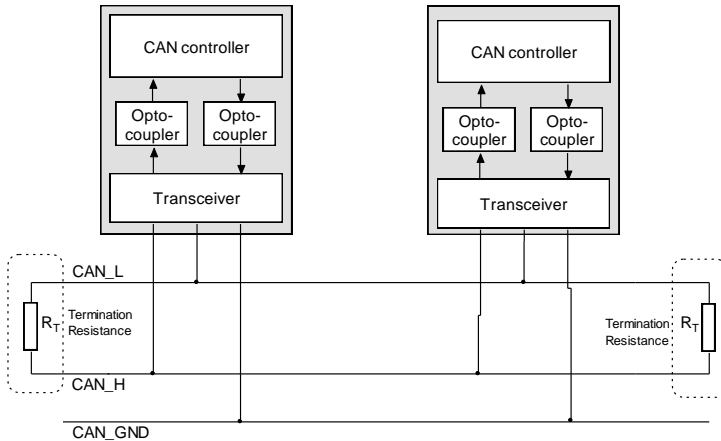


Figure 13: Wiring schema of galvanic isolated sysWORXX I/O devices

### Physical layout

Typically the layout of a CANopen network is that of a linear bus. The main trunk consisting of the CAN\_L and CAN\_H signals must have termination resistors (typically 120Ω) **at each end of the line**. Please refer to *Section 13.4* for more detailed information about cable length and termination resistance depending on the bit rate.

If Y-junctions are used, the drop lines (aka Trunk lines) must not exceed a maximum length in order to avoid reflections resulting in bus errors. This length depends on the bit rate used on the bus. The higher the bit rate the shorter the drop lines. At 1Mbps the drop line may not exceed 30cm.

A rule for estimation of the maximum allowable length of a drop cable length  $L_{dc}$  is given below.

$$L_{dc} < \frac{t_{\text{Prop\_seg}}}{50 \cdot t_p},$$

The total drop line length is calculated as following:

$$\sum_{i=1}^n L_{dc_i} < \frac{t_{\text{Prop\_seg}}}{10 \cdot t_p}$$

With:  $t_p$  Specific line propagation delay per length unit

$t_{\text{Prop\_seg}}$  Time of the propagation delay segment

This effectively leads to a reduction of the maximum trunk cable length by the sum of the actual cumulative drop cable length at a given bit rate. If the above recommendations are met, then the probability of reflection problems is considered to be fairly low. Drop lines must not have terminating resistors!

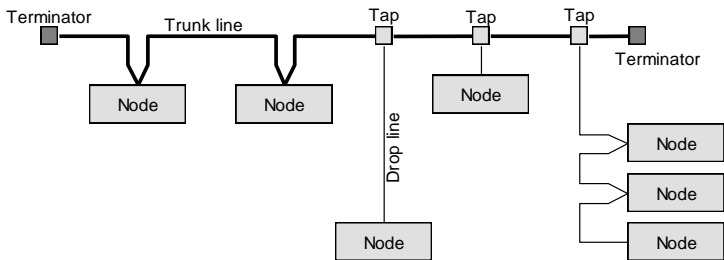


Figure 14: Physical layout of a CANopen network

The tables below show drop line length for single drop lines and star-shaped multiple drop lines for quick reference.

**Note**

The tables given below do not substitute a careful dimensioning and calculation of the application specific CAN-bus network.

Bit rate	Drop line length (single drop line)	Total length of all drop lines
1000 kbps	< 1m	< 5 m
500 kbps	< 5 m	< 25 m
250 kbps	< 10m	< 50 m
125 kbps	< 20m	< 100 m
50 kbps	< 50m	< 250 m

Table 11: Drop cable length (single drop line)

Bit rate	Drop line length (multiple drop lines, star shaped)	Drop line length (without drop lines)
1000 kbps	< 0,3 m	< 25 m
500 kbps	< 1,2 m	< 66 m
250 kbps	< 2,4 m	< 120 m

Bit rate	Drop line length (multiple drop lines, star shaped)	Drop line length (without drop lines)
125 kbps	< 4,8 m	< 310 m

Table 12: Drop cable length (multiple drop lines)

**References**

CiA 303-1

ISO 11898 part 1 and 2

**See also**

Section 13.4 on page 194

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## 5 Configuring

### 5.1 General rules for configuring CANopen networks

At the beginning of each system design the overall requirements must be evaluated. This includes, of course, the number and distribution of I/O points and implies the selection of the modules accordingly. On the communication side the evaluation should include response times, bandwidth usage, distances, as well as number and type of communication nodes.

#### Defining the system

This section focuses on how to setup the communication between devices. Thus, any needed control algorithms for PLCs are assumed to be implemented already.

At stage of system design with sysWORXX I/O modules involved, the following points should be considered:

Means:	
Participating devices	<p>A participating devices must support the same physical layer and need to be at least conformant to CiA 301 V4.02.</p> <p>Some devices have multiple input/output options (e.g. voltage or current output). These device features should be defined in advance and be configured before connecting the sensors and actors.</p> <p>3<sup>rd</sup> party devices (e.g. sensors with CANopen interface) can be integrated seamlessly if they fulfill the above requirements.</p>
	<p><b>Note</b></p> <p>Some devices (esp. some small CANopen sensors) only support configuration via LSS<sup>1</sup> and therefore must be considered as being unconfigured at first power-on. A LSS Master is required for configuration.</p> <p>All sysWORXX I/O devices support remote configuration via LSS according to CiA 305 V1.1.</p>

<sup>1</sup> Layer Setting Services according to CiA 305

<b>Means:</b>	
Distribution and selection of node-IDs	<p>Each node gets an unique node-ID between 1 and 127.</p> <p>The node-ID directly represents the message priority of this node.</p> <p>Assign a lower node-ID to nodes with high priority I/O connected (e.g. position sensors or drives). A higher node-ID (lower priority) can be assigned to nodes with I/Os connected to slow processes (e.g. temperature sensors).</p>
Bit rate / bus speed	<p>All devices on the network must support the same bit rate.</p> <p>The highest possible bit rate depends on the bus length and length of drop lines. See CiA 305-1 for detailed information. Section 13.4 shows some standard values for DC parameters for CANopen networks with less than 64 nodes.</p> <p>In general it is recommended not to run the network with a higher bit rate than required. Keeping the bus speed low reduces EMI and increases overall system stability and tolerance.</p>
Synchronized operations	<p>If an accurate timing is required by the application or parts of it (e.g. in motion control), the SYNC mechanism of CANopen is used.</p> <hr/> <p><b>Note</b></p> <p>Depending on the amount of synchronized PDO used, SYNC might produce a considerable transmission peak, as synchronized PDOs are transmitted upon reception of the SYNC message.</p> <hr/> <p>See <i>Section 8.6</i> for detailed information on how to use SYNC with the sysWORXX I/O modules.</p>
Communication structure, and device guarding	<p>Define the communication and connections (PDO) for all participating devices:</p> <ul style="list-style-type: none"> <li>• Master-Slave connections</li> <li>• Slave-Slave connections</li> <li>• Device guarding and network management issues (e.g. heartbeat) (who guards who)</li> </ul>

## Estimating the bandwidth usage

Calculating the bandwidth of a CANopen network without a simulation tool network is quite a difficult thing. However, a rough estimate bandwidth usage can be calculated as follows:

**(1) Calculate the number of data bytes transmitted (e.g. at each SYNC cycle)**

Example:

32 Digital inputs (BYTE)	→	4 bytes
4 Analog inputs (INT)	→	8 bytes
8 Digital outputs (BYTE)	→	1 byte
Total:		13 bytes

**(2) Calculate the data bandwidth required. Either based on the communication cycle or based on a worst case scenario.**

Example:

With an estimated SYNC cycle time of 13 ms and 13 data bytes, about 1000 bytes are transmitted within a second. Multiplying by 8 (to achieve bits per second) results in 8kbps.

**(3) Calculate the total bandwidth**

CAN messages not only contain data bytes but also message ID, control bits a checksum and other overhead information. Unfortunately there is no easy rule describing the relationship between data and overhead. The overhead factor may vary from 2 to 6 depending on the message length. If many short messages are used, a factor 6 could be reasonable.

Example:

Assuming an overhead factor of 4 result in a bandwidth of  $4 \cdot 8\text{kbps} = 32\text{ kbps}$ .

With a chosen bitrate of 125kbps the average bandwidth usage is:

$32\text{kbps} / 125\text{kbps} \Rightarrow 25,6\%$

About 25% is an acceptable margin for a rough estimation. In case the chosen bit rate would be 50kbps, a more detailed calculation becomes necessary.

Advanced development tools are capable of performing these calculation automatically. Please contact our support team if you need more information.

## Determine the Communication Type

Once the bit rate has been chosen it is necessary to specify the PDO communication type(s). These have different advantages and disadvantages:

- **Cyclic synchronous communication** provides an accurately predictable bus loading, and therefore a defined timing behavior.

The main idea behind the synchronized communication mode is to provide motion oriented systems (such as robots) with “parallelized” inputs and outputs. The process values are updated synchronously. To avoid jitter effects and ensure smooth movements, all inputs are read at the same time and output data is applied simultaneously. The SYNC rate parameter determines the bus load globally. Under normal conditions the guaranteed reaction time of the system is at least as long as the cycle time. One drawback is that the CAN-bus bandwidth is not used optimally, since old data (e.g. data that has not changed) is also transmitted continuously. To optimize the network and reduce the bandwidth usage, the synchronization of a PDO can be scaled. SYNC multiples (transmission types 1...240) can be assigned to PDOs, to transmit slowly changing data less often than, for instance, time-critical inputs.

### Note

Furthermore it is important to consider, that input states shorter than the SYNC cycle time will not necessarily be transmitted. If this is not possible for your application, associated PDOs must be configured for asynchronous communication.

- **Event-driven asynchronous communication** is quite the optimum in terms of reaction time and the exploitation of bus bandwidth. It uses transmission methods of “pure CAN”. However, if a large number of events occur simultaneously, the corresponding delays before a PDO with a relatively low priority can be sent increases. Proper network planning therefore need to include a worst-case analysis. Certain mechanisms, for example the inhibit time, allow for controlling the traffic. Constantly changing inputs with a high PDO priority can be prevented from blocking the bus. This is why event driven communication is disabled by default in the device profile of analog inputs, and must be enabled explicitly. The so-called “Event timer” enables re-transmission of a PDO even without prior change of the I/O state. So the PDO is not sent again before the inhibit time has elapsed, and not later than specified with the “Even timer”.
- The communication type is parameterized by the so-called “Transmission Type” (see *Section 8.2*).

While each PDO can be configured for a single transmission type only, it is possible to combine different transmission types on devices with more than one TPDO. All sysWORXX input modules feature from two to four TPDO depending on module type.



## Choosing devices and tools

Once the requirements are set, you probably need to select the devices and tools used to configure and test the devices and the network.

The following table provides an overview about the tools and services available for integration of the sysWORXX I/O devices.

Tool/device	Tasks	Scope of use
CANopen DeviceExplorer	Device configuration via direct access to Object Dictionary (SDO access) Performing network management tasks (NMT Master) Reading diagnostic data from the device Remote configuration via LSS Access and visualization of I/O data (e.g. process values) and PDOs Overall CANopen network configuration (DCF generation) and configuration download via CAN-bus Changing PDO linking/mapping and configuration of communication parameters Configuration of SYNC and heartbeat producers Generation of network documentation	Configuration Test & Commissioning Maintenance
CANinterpreter	Logging CAN-bus messages (to screen or to file). Transmission of CAN messages. CANopen protocol plug-in for direct interpretation of CANopen messages to plain text. Plug-ins for data visualization.	Test & Commissioning Operation Maintenance
OpenPCS + CANopen PLC	Implementation and integration of distributed automation	Test & Commissioning

Tool/device	Tasks	Scope of use
	applications CANopen Configuration Manager functions integrated on the PLC when running in master/manager mode Handling of CANopen network variables. Performing CANopen management tasks during operation. Performing OPC access to PLC variables.	Operation
CANopen OPC Server	Mapping of CANopen network variables to OPC items.	Operation

Table 13: CANopen tools overview

## 5.2 Basic device configuration

### Introduction

This section describes the steps for setting up the device to enable instant operation in a CANopen network (e.g. after deployment or replacement).

The basic device configuration covers:

- Setting of the node-ID
- Setting of the bit rate

Each sysWORXX IO device features three rotary HEX-encoding switches. Two are there for setting the node-ID and one for setting the CAN-bus bit rate.

After setup of bitrate and node-ID the device is ready for operation, e.g. accessible for further configuration via CAN-bus.

### Required tools

Slotted screwdriver with 3.0 mm (0.118") blade

### Procedure

#### Configuring the node-ID

Each CANopen device in a CANopen network must have an own unique node-ID from range 1 to 127. After power on the device checks the node-ID on the rotary switches. A configuration error (e.g. invalid node-ID) is displayed with a special LED blinking cycle (*see Section 9.1 on page 85 for details*).

#### Note

Changes at the hardware switches take effect only after power on or a reset of the device.

A alternative way to configure the device node-ID and bit rate is using the CANopen Layer Setting Services (LSS). Please refer to *Section 5.3 on page 42* for detailed information on how to use LSS for node-ID configuration. When LSS was used for configuration, the settings on the hardware switches are ignored. The LSS settings are deleted with resetting the module to manufacturer settings.

The node-ID is configured in hexadecimal notation. One configures the high-nibble and the other the low-nibble of the note-ID. Figure 15 shows an example with node-ID 62H (respectively 98D) configured.

**Note**

Table 119 on page 190 contains a table for node-ID conversion from decimal to hexadecimal notation.

Position FFh is reserved for resetting the device to factory settings (see Section 5.6)

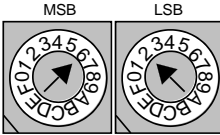


Figure 15: Example for a node-ID setup on hardware switches

**Configuring the CAN-bus bit rate**

The third hardware switch is used to select the CAN-bus bit rate.

**Note**

Changes at the hardware switches take effect only after power on or a reset of the device.

Alternatively it is possible to use the CANopen Layer Setting Services for switching the bit rate of a sysWORXX IO device or the CANopen network globally. Please refer to Section 5.3 on page 42 for detailed information on how to use LSS. When LSS was used for configuration, the set bit rate on the hardware switch is ignored. The LSS settings are deleted with resetting the module to manufacturer settings.

Table 14 shows the assignment of the CAN-bus bit rate to the position of the switch. A configuration error (wrong position) is displayed with a special LED blinking cycle (see Section 9.1 on page 85 for details). The assignment of the bit rates to the positions corresponds to the assignment used with LSS as defined in CiA 305.

**Note**

Position FH is reserved.

Switch position	Bit rate [kBit/s]
0	1000
1	800
2	500
3	250
4	125
5	100
6	50
7	20
8	10
0EH	1000, reserved for production

Table 14: Supported bit rates of the CANopen IO devices

## 5.3 Configuring using CANopen Layer Setting Services (LSS)

### Introduction

LSS offers the possibility to inquire and change certain parameters of a sysWORXX CANopen I/O node via the CAN-bus.

The following device parameters can be inquired and/or changed using LSS:

- node-ID
- CAN-bus bit rate
- LSS address (Identity Object 1018H)

The sysWORXX I/O modules feature LSS slave functionality compliant to CiA 305 V1.1.

By using LSS a sysWORXX I/O device can be configured for a CANopen network without using the configuration switches<sup>1</sup>. The configured parameters are stored to a non-volatile memory after the configuration process has been finished successfully. The configuration of bit rate and node-ID on the switches is ignored and the configuration data is load from non-volatile memory after power on.

---

#### Note

The procedure of LSS access defined in the different versions of specification CiA 305 (e.g. V1.0 to V1.1) are not fully compatible. Thus, the LSS master must provide compatibility with all versions of the LSS specification used in the devices deployed on the CANopen network.

---

### Requirements

The device identification data of the device to be configured must be known in advance. You can derive this information from the corresponding EDS. Furthermore the device serial number is needed. The device serial number is printed on a sticker placed on the module. If the sticker is missing please contact our support team for further assistance.

### Required tools

CANopen configuration tool with LSS master function (e.g. CANopen DeviceExplorer with LSS plug-in)

PC/CAN interface

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<sup>1</sup> However, before the module is accessible via LSS, valid values must be configured on the hardware switches to enable a normal startup behavior of the sysWORXX module.

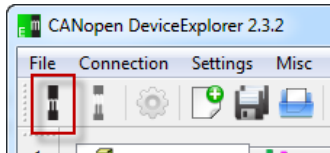
## Procedure

In the following the procedures of configuring a sysWORXX I/O device via LSS are shown. It is assumed, that the module was installed properly and is at least connected to the CAN-bus and power. Furthermore the CANopen configuration tool and PC/CAN interface was installed and configured for operation.

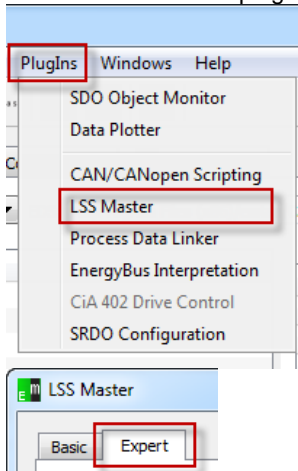
The description given below refers to the CANopen DeviceExplorer. Any other CANopen configuration tool featuring a LSS master might work as well but may differ in handling.

### Configuring a node-ID via LSS

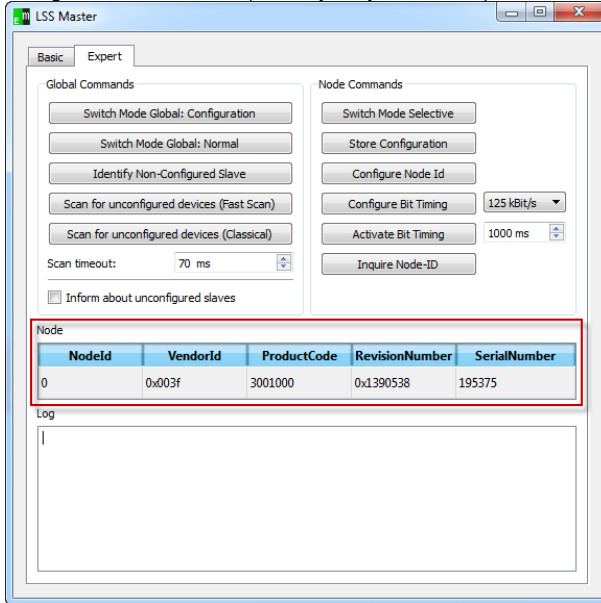
- (1) Connect to the CAN network



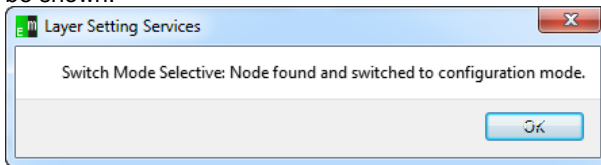
- (2) Load the LSS Master plug-in and go to the Expert tab sheet



- (3) There are two ways of selecting a node to configure it.
- a)** Add an already configured node for changing its node-ID using its LSS address (Identity Object 1018H).

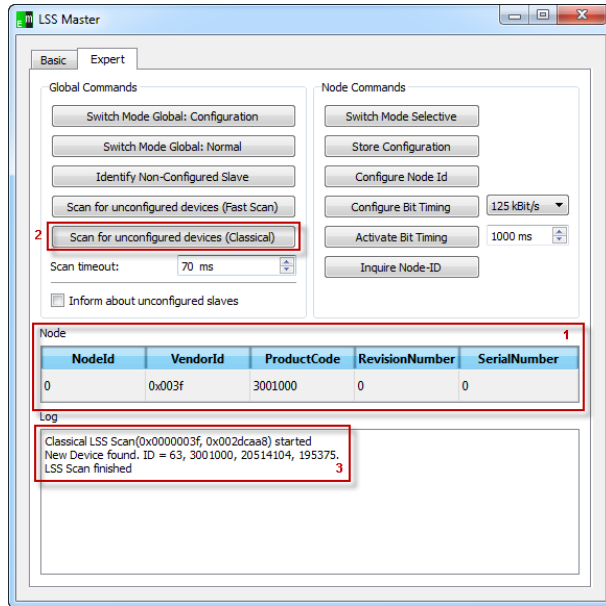


Switch the node into configuration mode by pushing the button '**Switch Mode Selective**'. If successful, the following dialog will be shown:



- b)** Scan the network for unconfigured devices according to some search criteria, to get its LSS address.





- Step 1: Set up the following data for the node to be searched:
- Vendor-ID: 0x3F for SYS TEC electronic GmbH  
(unique for all SYS TEC products)
- Product Code: 0x2DCAA8 (3001000) for sysWORXX IO-X1

**Hint:** The Product Code can be found on the type label of the sysWORXX IO-modules.

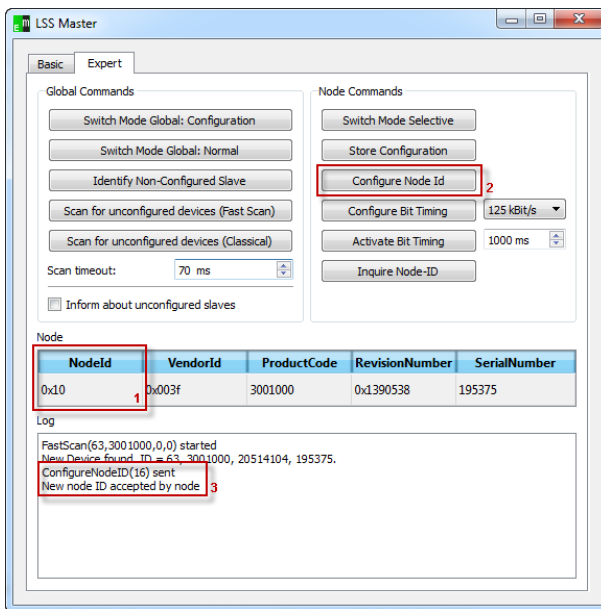
- Step 2: Push the button '**Scan for unconfigured devices (Classical)**'.

- Step 3: The data to identify the device is shown in the Log after the scan has finished successfully. Add RevisionNumber and SerialNumber to the Node-information and switch the node into configuration mode by pushing the button '**Switch Mode Selective**'. (according to a)).

- Step 1: Enter the new node-ID.

- Step 2: Confirm with '**Configure Node Id**'.

- Step 3: Check for acknowledgement.



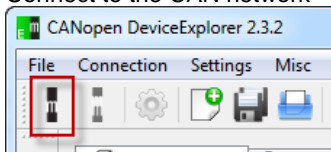
- (4) Click on '**Store Configuration**' to save the changes to non-volatile memory.  
You are done! After switching the node into normal mode it will boot up with the configured Node Id.

### Note

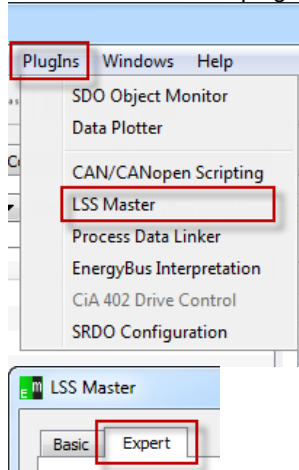
The product code of a sysWORXX IO device is equal to its order number. This means the product codes differs for each type of module and therefore enables a selective search

### Configuring the bit rate of a device via LSS

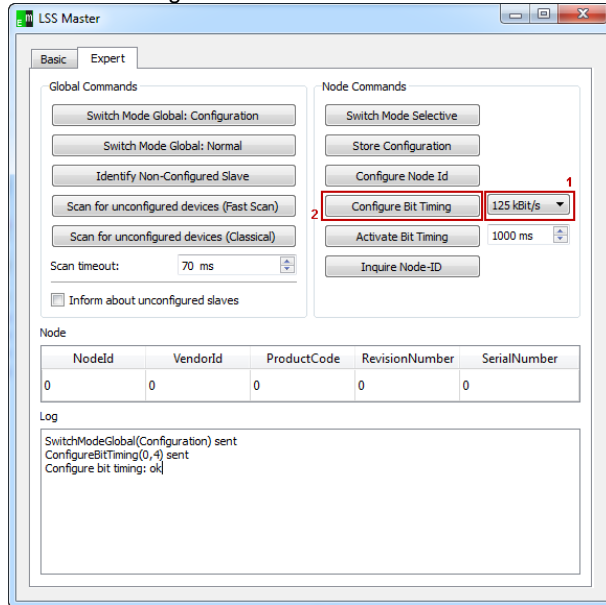
- (1) Connect to the CAN network



- (2) Load the LSS Master plug-in and go to the Expert tab sheet

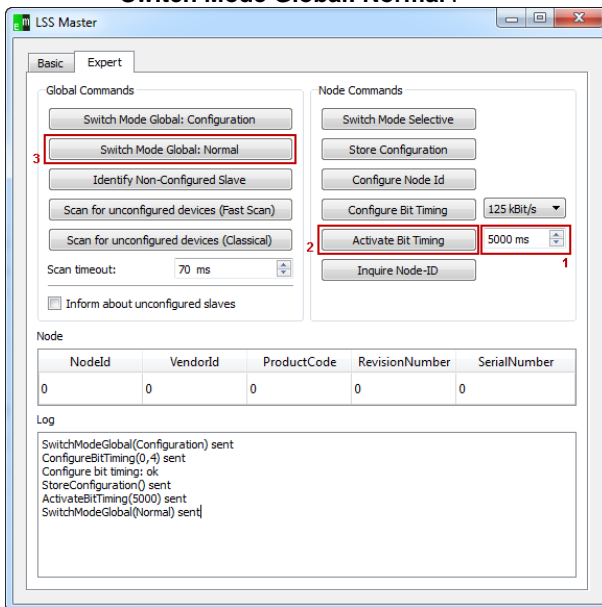


- (3) Switch the nodes into configuration mode by pushing the button **'Switch Mode Global: Configuration'**.
- (4) Step1: Choose the desired bit rate  
 Step 2: Click on **'Configure Bit Timing'** to set up the new bit timing.



Click on '**Store Configuration**' to save the changes to non-volatile memory.

- (5) Step 1: Set up the switch delay.  
**Regard:** The value must be large enough to be able to perform Step 3 after finishing Step 2.
- Step 2: Click on '**Activate Bit Timing**' to take the changes into effect.
- Step 3: Switch back the nodes into normal mode by clicking '**Switch Mode Global: Normal**'.



- (6) Disconnect from the CAN network and reconnect with the new baud rate. You are done!

### Note

Changing the bit rate of a single node does not make sense if the network consists of more than one node. Bus errors might occur. Switch the bit-rate of the CANopen network globally instead.

### Reference

CiA 305 V1.1

## 5.4 Configuring with using Device Configuration Files (DCF)

### Introduction

This section provides an overview about how to configure a sysWORXX I/O device using a Device Configuration Files (DCF).

### Requirements

You need to have the DCF in hand before you start. Use a CANopen configuration tool to create the DCF (see *Section 2.2*) or derive it from an EDS manually (not recommended!).

### Note

Some parameter modifications require a special sequence of actions (e.g. PDO mapping). The CANopen configuration tool or manager used for configuration should be able to handle this points automatically.

### Required tools

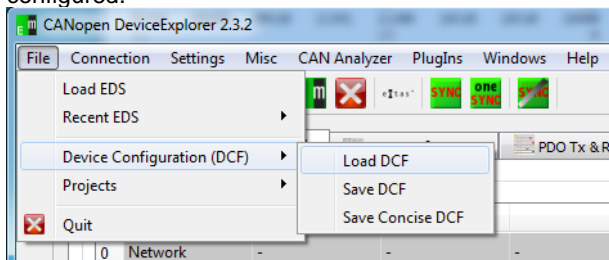
CANopen configuration tool (providing SDO access to the Object Dictionary, e.g. CANopen DeviceExplorer)

PC/CAN interface

### Procedure

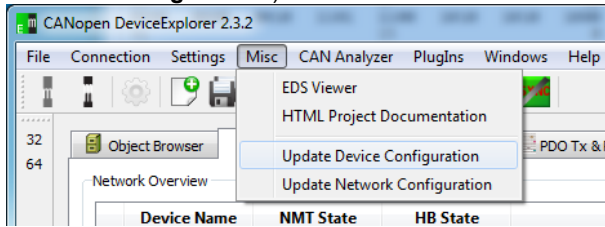
This example shows how to configure a device by using the CANopen DeviceExplorer tool (CDE), which is part of the CANopen Configuration Suite. We assume the hardware components and network (CAN-bus interface and sysWORXX I/O modules) to be ready for operation.

- (1) Open the CDE and connect to the network.
- (2) Select the node you want to configure from the NMT tab sheet.
- (3) Load the configuration file (DCF) for every device that shall be configured.



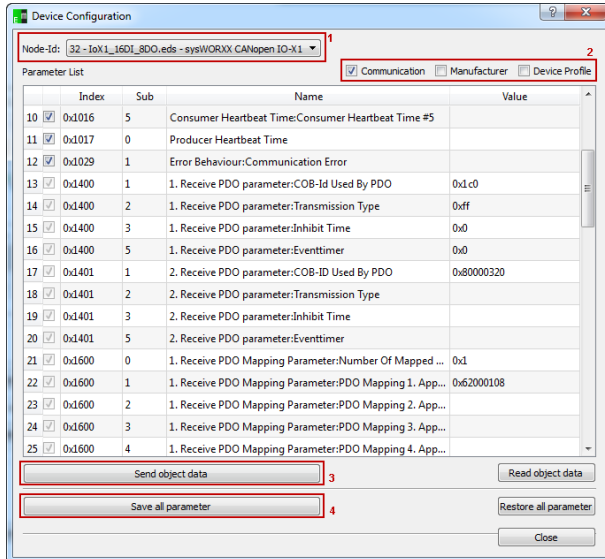
- (4) Choose whether you want to configure a single device ('**Update Device Configuration**') or the whole network ('**Update**

## Network Configuration').



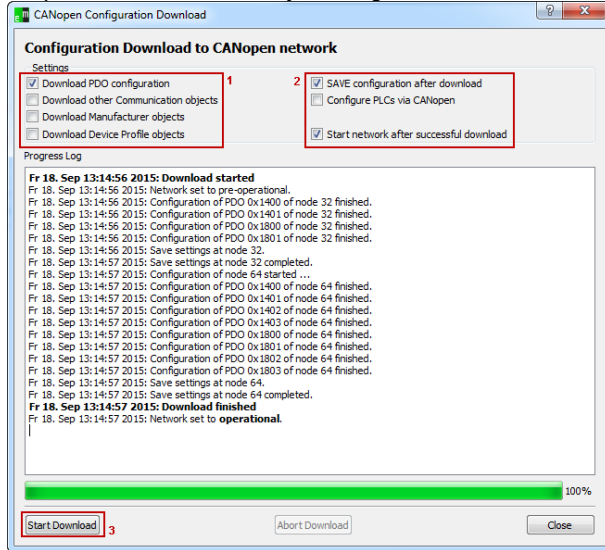
- (5) Download the configuration.
  - a) Download the configuration to a single device.
    - Step 1: Choose the device.
    - Step 2: Choose the part of the Object Dictionary.
    - Step 3: Send the data to the device by clicking on **'Send object data'**.
    - Step 4: Store the configuration to non-volatile memory by clicking on **'Save all parameter'**.

Regard: If the I/O configuration has been changed, the device needs to be reset in order to apply the changes. Go to Network tab-sheet and click on button **'Reset Node'** for resetting the node.



- b) Download the configuration to the whole network.

- Step 1: Choose the part of the Object Dictionary.  
 Step 2: Select additional options.  
 Step 3: Send the data by clicking on 'Start download'.



## 5.5 Store/Restore device configuration

### Introduction

This section describes how to store a configuration to the non-volatile memory and remotely restore the factory settings.

The store / restore of configuration data is controlled by two object entries. Index 1010H is used for storing the configuration. For restoring the factory default settings, index 1011H is used.

Object Index	Object Subindex	Object name	Data type	Read value	Write value
1010H	1	Save all parameters	Unsigned32	1	"evas"
1011H	1	Restore all default parameters	Unsigned32	1	"daol"

Table 15: Object Dictionary entries for store / restore parameter (1010H/1011H)

**Note**

The sysWORXX I/O modules only support the “Save all parameters” feature.

**Required tools**

CANopen configuration tool (providing SDO access to the Object Dictionary, e.g. CANopen DeviceExplorer)  
PC/CAN interface

**Procedure**

The storing/restoring of parameters is controlled by writing the signatures save/load into the corresponding object index/subindex.

**Saving the configuration**

Write “save” as hexadecimal value **65766173H** to Object 1010H Subindex 1 via SDO.

	Signature	MSB			LSB		
/ISO8859/ character		e	v	a	s		
hex		65 <sub>h</sub>	76 <sub>h</sub>	61 <sub>h</sub>	73 <sub>h</sub>		

If storing failed, the device responds with a SDO abort code according to *Table 16*.

**Restoring factory default settings**

Write “load” as hexadecimal value **64616F6CH** to Object 1011H Subindex 1 via SDO.

Signature		MSB		LSB	
/ISO8859/ character		d	a	o	l
hex		64 <sub>h</sub>	61 <sub>h</sub>	6F <sub>h</sub>	6C <sub>h</sub>

If restoring failed, the device responds with a SDO abort code according to *Table 16*.

The restored default values become valid after the device was reset or power cycle (see *Figure 16*).

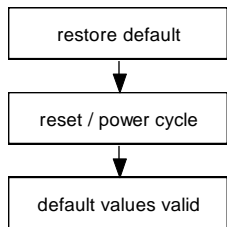


Figure 16: Restore procedure



SDO abort code	Description
0606000H	Store/Restore failed
0800002xH	Wrong signature

Table 16: SDO abort codes for store/restore configuration

## Reference

CiA 301 V4.02

## 5.6 Resetting to factory settings

### Introduction

This section describes how to restore the default factory settings locally on the device using the hardware switches.

### Required tools

Slotted screwdriver with 3.0 mm (0.118") blade

### Procedure

- (1) Set the hardware switches for node-ID to value FFH
- (2) Perform a hardware reset or power cycle.
- (3) The blinking RUN and ERROR LED indicate the end of the restore process (see *Section 9.1* for LED blinking cycles).
- (4) Set the original node-ID and perform a hardware reset or power cycle (see *Section 5.2* for basic device configuration).

### Reference

CiA 303-3

## 6 Commissioning

### 6.1 Commissioning of the sysWORXX I/O modules

#### Introduction

The procedures for commissioning your automation system are determined by the relevant plant configuration. The procedure outlined below only describes the commissioning of sysWORXX I/O modules.

#### Requirements

We assume that the following steps have been completed successfully:

Actions	Reference
The module is installed and wired	Section 3, Mounting Section 4, Connecting
The device is configured (node-ID, bit rate)	Section 5, Configuring

Table 17: Commissioning requirements

#### Commissioning

- (1) Switch on the device voltage supply (L+).
- (2) Switch on the load voltage supply (supplies) (1L+, 2L+ ... ) if applicable.

#### See also

Section 3, Mounting  
Section 4, Connecting  
Section 5, Configuring

## 6.2 Startup of the sysWORXX I/O modules

### Principle of operation

The diagram below illustrates the startup routine of a sysWORXX I/O module from application level. The module start-up and state from network level is described with the NMT state machine in *Section 9.5*. The steps described below refers to the steps the module is going through during NMT state *INITIALIZATION* (see the NMT state machine described in *Section 9.5*).

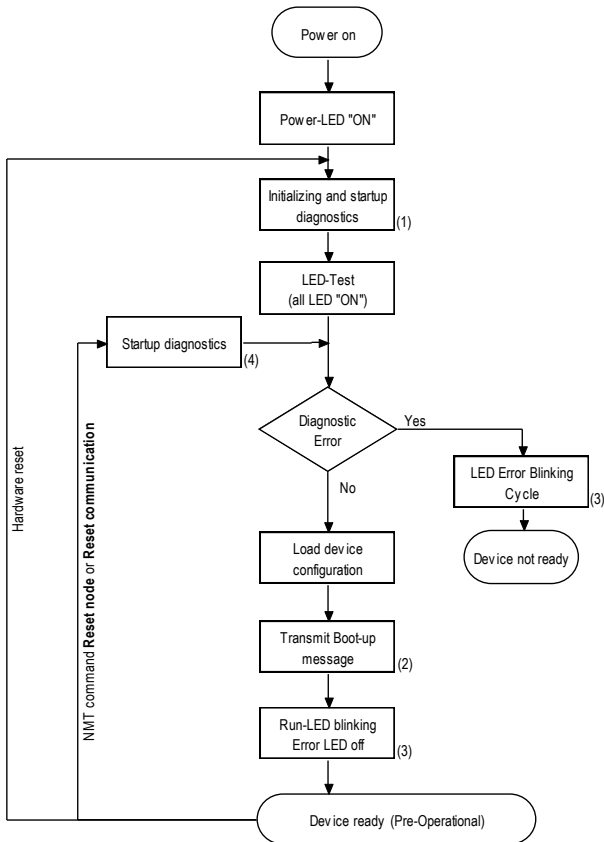


Figure 17: Startup cycle of a sysWORXX I/O device

- (1) After power-on or hardware reset the device will perform some internal diagnostic covering:  
*Flash, RAM, EEPROM, LEDs, Device configuration*

- This checks will take 2-3 seconds depending on module type.
- (2) The boot-up message is a single CAN-message with CAN-identifier *700H+node-ID* with 1 byte data containing the value 0.  
It is used to signal that a CANopen slave device has entered the NMT state Pre-operational after the NMT state INITIALIZATION (see Section 9.5).
  - (3) Please refer to Section 9.1 for detailed information about the LED blinking cycles
  - (4) After NMT command **Reset\_Node** and **Reset\_Communication** the device will perform some internal diagnostic covering: *Flash, RAM, EEPROM*  
These checks will take about 2 seconds to complete.

### Autonomous startup of CANopen network/devices

The sysWORXX I/O devices support the CANopen Minimum Boot Up. Following reset and internal initialization, the board is in state PRE-OPERATIONAL (refer to Section 9.5). Upon receipt of the NMT command message *Start\_Remote\_Node* the device switches to state OPERATIONAL (refer to Section 9.5).

In some applications the use of a full NMT master may not be necessary. However, CANopen nodes need the *Start\_Remote\_Node* message to enter the OPERATIONAL state. Therefore, all sysWORXX I/O modules feature a manufacturer specific extension, which enables them to act as a simple NMT boot-up master. Please refer to Section 8.4 for detailed information.

This side was left empty intentionally.

## 7 Maintenance and service

### 7.1 Removing and inserting I/O modules

#### Introduction

This section describes how to insert and remove I/O modules of a distributed system, which was already configured and put into operation. This might become necessary in case of defect or if the system configuration changes partly.

The sysWORXX I/O modules support insertion and removal of devices without effecting other devices (e.g. power-off).

Furthermore, the sysWORXX I/O modules support mechanisms for device monitoring (see *Section 9.5*) that enable the application master (e.g. a PLC) to detect missing devices by loss of communication, e.g. when powered-off. If this happens, the application master is responsible to perform appropriate actions (e.g. securing the machine, stop movement ect.).

After inserting a new device, the correct bit rate and node-ID must be configured (see *Section 5.2*) before it is connected to the bus.



#### Warning

An incorrect bit rate or node-ID might lead to severe communication problems and malfunction of the attached application.

After power-on of the device will perform some self diagnostics (see *Section 8.3*), which might take several seconds to complete. When the device is ready for operation, it will send out an boot-up message to notify the application master about its appearance. The application master is responsible to perform appropriate actions (e.g. configure the device).

In case an internal error was detected during the self diagnostics process, the device will not appear on the bus. Measures must be taken locally.

After successfully commissioning (see *Section 6*) the device, it needs to get configured, using a CANopen configuration tool. Some application masters provide the functionality of automatic device configuration, e.g. if a device was replaced.

#### Required tools

CAN-bus monitoring tool with CANopen protocol analyzer (e.g. CANinterpreter with CANopen extension)

CANopen configuration tool providing SDO access (e.g. CANopen DeviceExplorer)

PC/CAN interface

Slotted screwdriver with 4 mm blade

## Replacing the module

We assume that all tools are already installed on the Service-PC and the PC/CAN interface is connected and ready for operation.

- (1) Power-off the device and remove all plugs
- (2) Unmount the device and replace it with a new one. Because the sysWORXX I/O modules have removable terminal blocks, the wiring does not need to be touched.
- (3) Configure bit rate and node-ID of the new device according to your network configuration.
- (4) Connect the device to the bus.
- (5) Connect the device to the plant (I/O).
- (6) Connect the device to power supply.
- (7) When the device is powered on, it starts internal diagnostic tests that take about 2 ... 3 seconds to finish.
- (8) Check the bus for the appearance of the boot-up message.
- (9) Configure the device (e.g. PDO connections, I/O type ect.) using a CANopen configuration tool and DCF, if the application master does not provide automatic device configuration.
- (10) Set the device to state OPERATIONAL to start PDO communication, if the application master does not manage this device.

## See also

Section 9, Error behavior and system messages

Section 5, Configuring

Section 3, Mounting



## 8 Functions

### 8.1 The Object Dictionary of the sysWORXX I/O modules

#### Introduction

This section describes the communication specific part of the Object Dictionary (OD). The device specific part of the OD (6000H – 9FFFh) is described with the modules. The manufacturer specific part of the OD (2000H – 5FFFh) is described in *Section 8.4*.

#### Object Dictionary overview

Object Index	Object type / Subindex	Object name	Data type	Object mappable	Object stored via 1010H	Object restored via 1011H
1000H	Var	Device type number	Unsigned32	-	-	-
1001H	Var	Error Register	Unsigned8	-	-	-
1003H	Array	Pre-defined Error Field	Unsigned32	-	AUTO	AUTO
1005H	Var	COB-ID SYNC-Message	Unsigned32	-	X	X
1007H	Var	SYNC window length	Unsigned32	-	X	X
1008H	Var	Manufacturer Device name	String	-	-	-
1009H	Var	Manufacturer Hardware Version	String	-	-	-
100AH	Var	Manufacturer Software Version	String	-	-	-
100CH	Var	Guard Time	Unsigned16	-	X	X
100DH	Var	Life Time Factor	Unsigned8	-	X	X
1010H	Array	Store Parameter	Unsigned32	-	-	-
1011H	Array	Restore Default Parameters	Unsigned32	-	-	-
1014H	Var	COB-ID Emergency Message	Unsigned32	-	X	X

Object Index	Object type / Subindex	Object name	Data type	Object mappable	Object stored via 1010H	Object restored via 1011H
1016H	Array	Consumer Heartbeat Time <sup>1</sup>	Unsigned32	-	X	X
1017H	Var	Producer Heartbeat Time	Unsigned16	-	X	X
1018H	Record	Identity Object	Identity	-	-	-
1029H	Array	Error Behavior	Unsigned8	-	X	X
1200H	Record	1st Server SDO Parameter	SDO Parameter	-	-	-
<b>1400H</b>	<b>Record</b>	<b>RPDO1<sup>2</sup> Communication parameter</b>	<b>PDOComPar</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Largest Subindex supported	Unsigned8			
	01H	COB-ID used by PDO	Unsigned32			
	02H	Transmission Type	Unsigned8			
	03H	Inhibit Time	Unsigned16			
	05H	Event timer	Unsigned16			
1401H	Record	RPDO2 Communication parameter	PDOComPar	-	X	X
<b>1600H</b>	<b>Record</b>	<b>RPDO1 Mapping parameter</b>	<b>PDOMapPar</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number of Mapped Objects	Unsigned8			
	01H	PDO Mapping 1. App. Object	Unsigned32			
		...				
	08H	PDO Mapping 8.	Unsigned32			

<sup>1</sup> Object only available on IO-X1, IO-X3, IO-X6

<sup>2</sup> Up to 4 RPDOs are available on the sysWORXX I/O modules depending on module type.

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
		App. Object				
1601H	Record	RPDO2 Mapping parameter	PDOMapPar	-	X	X
<b>1800H</b>	<b>Record</b>	<b>TPDO1<sup>1</sup> Communication parameter</b>	<b>PDOComPar</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Largest Subindex supported	Unsigned8			
	01H	COB-ID used by PDO	Unsigned32			
	02H	Transmission Type	Unsigned8			
	03H	Inhibit Time	Unsigned16			
	05H	Event timer	Unsigned16			
1801H	Record	TPDO2 Communication parameter	PDOComPar	-	X	X
<b>1A00H</b>	<b>Record</b>	<b>TPDO1 Mapping parameter</b>	<b>PDOMapPar</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number of Mapped Objects	Unsigned8			
	01H	PDO Mapping 1. App. Object	Unsigned32			
		...				
	08H	PDO Mapping 8. App. Object	Unsigned32			
1A01H	Record	TPDO2 Mapping parameter	PDOMapPar	-	X	X
1F51H	VAR	ProgramControl (from firmware version 1.30)	Unsigned8			

Table 18: Object Dictionary (Communication Profile)

<sup>1</sup> Up to 4 TPDOs are available on the sysWORXX I/O modules depending on module type.



Light-grey shaded objects are not available on all modules.  
The device specific PDO mapping is given with the device description.

### References

CiA 301 V4.02

### See also

Section 11, Digital I/O modules

Section 12, Analog I/O modules

## 8.2 CANopen Communication Services

### Introduction

This section provides generic information about the CANopen communication services implemented on the sysWORXX I/O devices. Two services are available for data communication:

- (1) **Process Data Objects** for fast transmission of process data without protocol overhead
- (2) **Service Data Objects** for accessing the OD and transmission of service data (e.g. configuration download)

### Process Data Objects (PDO)

The Process Data Object (PDO) implements an optimized method for placing multiple process data variables from the Object Dictionary into a single CAN message of up to 8 bytes.

Because CAN supports the multi-master communication concept (any node can send a message at any time and collisions are resolved by message priority), this direct communication method allows for more efficient, higher-priority access to process data.

The process data transferred via PDOs are divided into segments with maximum of 8 bytes (maximum data-length of a CAN message). The PDOs each correspond to a CAN message. PDOs are distinguished into Receive-PDOs (RPDOs) and Transmit-PDOs (TPDOs). A RPDO contains “output data”, received from the network. TPDO contain “input data”, that are to be sent out to the network.

There are two parameter sets to configure PDOs:

- (1) **Communication Parameter Set** contains communication specific configuration (COB-ID assignment, transmission type, ect.).
- (2) **Mapping Parameter Set** contains the assignment of application objects (process data) within the PDO.

The process of configuring PDOs includes the so-called **PDO linking** (communication parameterization) and **PDO mapping** (process data assignment/placement). If a CANopen network consists of more than two nodes the use of a CANopen configuration tool makes sense to avoid configuration errors and having the PDO linking and mapping done automatically by the tool.

### PDO linking

In its default configuration (Pre-defined Connection Set), the PDO identifiers of a sysWORXX I/O device (here: slaves) are setup for communication with one central station (the master). For this kind of

communication structure the PDO communication parameters do not need to be changed.

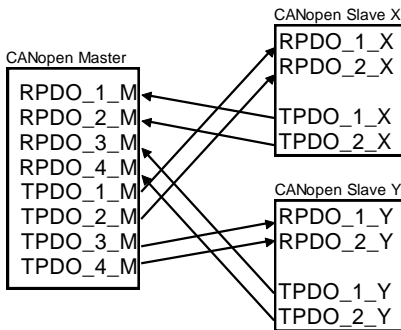


Figure 18: PDO linking for master/slave communication structure

If PDOs are used for direct data exchange between nodes (without a master involved), the identifier allocation of the devices must be adapted, so that the TPDO identifier of the producer matched with the RPDO identifier of the consumer.

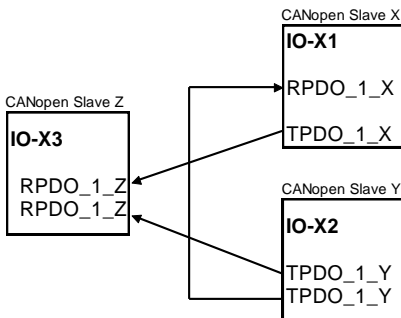


Figure 19: PDO linking for peer-to-peer communication structure

PDO Transmission Types

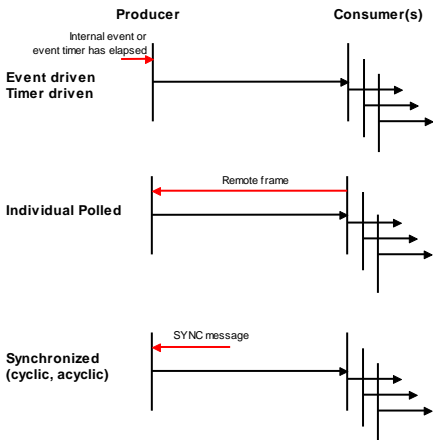


Figure 20: PDO transmission types

Transmit Trigger Options	Description
Event driven (asynchronous)	<p>The event driven or change-of-state transmission method simply transmits a PDO if the process data mapped to it changes.</p> <p>The exact meaning of “event” thereby is specified in the corresponding device profile and is partly configurable by the user. It could be <i>any</i> change to the data as well as a <i>specific</i> change (e.g. positive edge or reaching a minimum difference).</p> <p>Event driven transmission does not depend on a master that polls for the data.</p> <p>The so-called <b>Inhibit Time</b> is a configurable timeout in multiples of 100 microseconds to limit the frequency of a TPDO transmission. After starting the transmission of a TPDO the Inhibit Timer must expire before the TPDO may be transmitted again.</p> <div><p><b>Note</b></p><p>One problem of event driven communication is the lack of determinism. It is very hard to predict the worst-case scenarios of how often messages will get transmitted. By using the Inhibit Time the worst-case becomes predictable as it can be directly determined by the Inhibit Time.</p></div> <p>Further device-specific communication control mechanisms are described with the modules.</p>

Transmit Trigger Options	Description
<b>Timer driven (cyclic, asynchronous)</b>	<p>In time driven communication method a PDO is transmitted at a fixed time basis, the Event Timer. The Event Timer is a local timer running on each node and specified in milliseconds. If the Event Timer is specified with 50ms, for example, the PDO is transmitted every 50ms. Per default the Event Timers of multiple nodes are not synchronized.</p> <p><b>Note</b></p> <p>On the one hand use of time driven transmission simplifies performance and latency calculations. On the other hand, it produces more overhead than pure event-driven communication since data will get transmitted even if it did not change at all.</p>
<b>Individual polled (remote requested)</b>	<p>Although it is possible to use individual polling in CANopen, it is not recommended that this communication method is used. Individual polling uses a CAN feature called "Remote-Request" (aka RTR frame) to trigger the transmission of a TPDO remotely.</p> <p>When using RTR frames the device behavior is usually not transparent to the user. Furthermore there are CAN controllers still in use that do not support remote frames at all.</p> <p><b>Note</b></p> <p>All sysWORXX I/O devices use CAN controllers following the FullCAN principle and make sure the requested data are up-to-date.</p>
<b>Synchronized</b>	<p>The synchronized communication method uses a SYNC signal. This SYNC signal is a specific message without any data only used for synchronization purpose. Because the SYNC signal is typically produced on a fixed time basis, this triggering mode can also be regarded as using a global timer for triggering instead of using the event timer local on each node.</p> <p>Please refer to Section 8.6 for mode detailed information on how to use SYNC with the sysWORXX I/O devices.</p>

Table 19: TPDO transmit trigger options



Transmission type parameter	Cyclical	Acyclical	Synchronous	Asynchronous	RTR only
0		X	X		
1-240	X		X		
241-251	- reserved -				
252			X		X
253				X	X
254, 255				X	

Table 20: Transmission type parameter overview

Transmission type	Description
Acyclic synchronous	<p>TPDOs with <b>transmission type 0</b> will get transmitted synchronously, but not cyclically. A corresponding RPDO is only evaluated after the next SYNC message has been received. This allows, for example, to give a new target position to axis groups one by one, but these positions only become valid with reception of the next SYNC signal. For TPDOs with transmission type 0, its input data are acquired with the reception of the SYNC message and then transmitted if the data state in it has changed.</p> <p>Transmission type 0 thus combines event-driven and time driven transmission (and, as far as possible, sampling) with synchronized processing given by the reception of a SYNC signal.</p>
Cyclic synchronous	<p>A TPDO configured with <b>transmission types 1...240</b> is transmitted cyclically after every "n-time" (<math>n = 1...240</math>) reception of the SYNC message. Since transmission types for several TPDOs can be combined on a device as well as in the network, it is possible, for example, to assign a fast cycle for digital inputs (<math>n = 1</math>), whereas analog input values are transmitted in a slower cycle (e.g. <math>n = 10</math>).</p> <p>RPDOs do not generally distinguish between the transmission types 0...240. A received RPDO with a transmission type of 0 ... 240 is set valid with the reception of the next SYNC message. The synchronous cycle time (SYNC rate) is stored in Object 1006H and thereby known to the consumer. If the SYNC fails the device reacts in accordance with the definition in the device profile</p>

Transmission type	Description
	and switches, for example, its outputs into the fault state (See Object 1029H in Section 9).
RTR only	<p>TPDO with <b>transmission types 252 or 253</b> are transmitted exclusively on request by reception of a Remote Request (RTR frame).</p> <p>Transmission type 252 is for synchronous transmission. Upon reception of the SYNC message the process data of the corresponding TPDO are acquired and it gets transmitted.</p> <p>Transmission type 253 is for asynchronous transmission. The process data of the corresponding PDO are acquired continuously, and transmitted upon reception of the RTR frame.</p> <p><b>Note</b></p> <p>This type of transmission is not generally recommended, because fetching input data from some CAN controllers is only partially supported. Furthermore, some CAN controllers sometimes replies to remote frames automatically (without requesting up-to-date input data from the application). Thus, under some circumstances the polled data might not be up-to-date.</p>
Asynchronous	<p>PDOs with <b>transmission types 254 and 255</b> are asynchronous, but may also be event-driven.</p> <p>For transmission type 254 the event is manufacturer-specific, whereas for type 255 the events are defined in the device profile.</p> <p>In the simplest way, the event is the change of an input value that is transmitted with every change in the value or state. These transmission types can be coupled with the Event Timer and Inhibit Time in order to control the transmission behavior.</p>

Table 21: Transmission type description

### PDO mapping

PDO mapping describes the mapping of the application objects (process data) from the Object Directory to the PDO.

All sysWORXX I/O modules support dynamic PDO mapping, which allows for changes on the mapping, even if the node is in state OPERATIONAL.

The CANopen device profile provides a default mapping for every device type, which is applicable for most applications. The default mapping for digital I/O, for example, simply represents the inputs and outputs in their physical sequence in the RPDO and TPDO respectively.

The PDO mapping is located in the Object Directory at index 1800H and following for the RPDOs and at 1A00H and following for TPDOs.

Figure 21 shows a example for mapping of three objects to the first TPDO of a node.

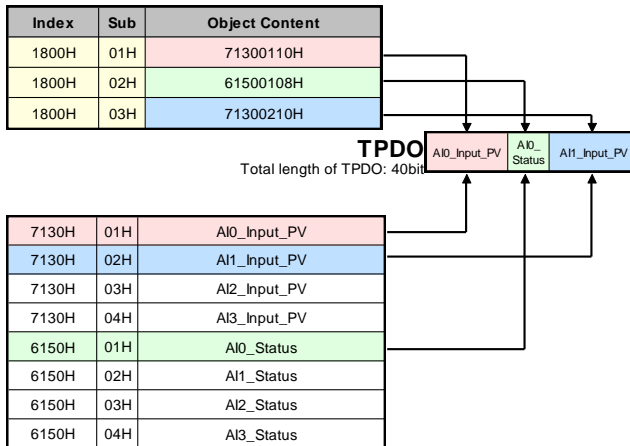


Figure 21: PDO mapping example

Usually CANopen configuration tools or configuration managers are used for changing the PDO mapping. However, under some circumstances it might become necessary to change the PDO mapping manually. Therefore the following procedure is necessary:

- (1) Disable the PDO by setting its COB-ID to 8000xxxH (xxx -> node-ID of the device to be changed)
- (2) In the Mapping Parameter Set of the PDO set the number of mapped objects to 0  
e.g. Object 1800H Subindex 00H for the first RPDO
- (3) Change the mapping entries of the PDO
- (4) Set the number of mapped back to a valid value according to the new PDO mapping.
- (5) Set the COB-ID of the PDO back to its original value.

### Dummy Mapping

A further feature of CANopen is the mapping of placeholders, or so-called "dummy entries". The data type entries stored in the object directory, which do not themselves have data, are used as placeholders. If such entries are contained in the mapping table, the corresponding data from the device is not evaluated. In this way, for instance, a number of devices could be supplied with new set values

using a single CAN telegram, or outputs on a number of nodes can be set simultaneously, even in event-driven mode.

### **Service Data Objects (SDO)**

The Service Data Object implements a direct communication channel for accessing the Object Dictionary. Service Data Objects (SDO) implement a basic client/server communication method, as point-to-point communication mode that allows for the issuing of read or write requests to the node's Object Dictionary. SDO messages contain requests or answers to/from the Object Dictionary. Because of its protocol overhead and master-driven communication principle, it is not well suited for process data communication.

A SDO connection is usually initiated by the application master, which acts as SDO client and owns all SDO communication channels. The sysWORXX I/O devices provide SDO servers, which means that at the request of a client (e.g. of the IPC or the PLC) they make data available (upload), or they receive data from the client (download).

### **References**

CiA 301 V4.02

## 8.3 Internal diagnostics and monitoring functions

### Introduction

The sysWORXX I/O modules feature two types of internal diagnostics and monitoring functionality:

- (1) Device self testing at startup (Startup diagnostics)
- (2) Device monitoring during runtime

### Device diagnostics at startup

After **power-on** or **hardware reset** the device will perform the following tests:

- Flash
- RAM
- EEPROM
- LED's,
- Device configuration

On NMT command **Reset\_Node** or **Reset\_Communication** the following components are tested:

- Flash
- RAM
- EEPROM

If one of the above mentioned tests fails for any reason, the device will go to error state and indicate this by a special blinking cycle of the Run- and Error-LED (see *Figure 22 unterhalb*). If this happens please contact our support team for further instructions.

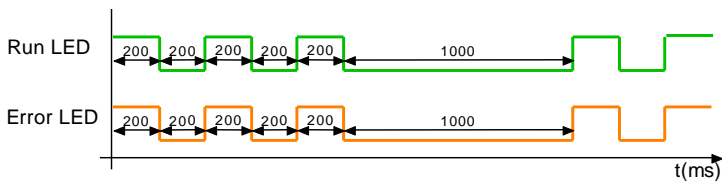


Figure 22: Error state blinking cycle

### Device monitoring during runtime

Table 22 shows the monitoring functions that are performed during runtime. These functions are accessible through the manufacturer-specific section (Object 2001H).

If any abnormal condition is detected, the device will send out an Emergency message to report the error that occurred. Please refer to

Section 9.3 for further information on how to read/evaluate Emergency messages.

Function	Description
I/O circuitry	This function monitors the I/O lines for abnormal conditions. Depending on the type of module, several error conditions are monitored (e.g. cable break, short-circuit, measurement value out of range)
Device temperature	This function monitors the temperature in the enclosure. The device temperature can be read from the Object Dictionary (Object 2001H Subindex 01H) and is given with a resolution of 0.1 degrees centigrade. $Temp(^{\circ}C) = \frac{ODvalue}{10}$
Device main voltage	This monitors the main voltage supplied to the device. The main voltage can be read from the Object Dictionary (Object 2001H Subindex 02H) and is given with a resolution of 0.1 Volts. $U_{main}(V) = \frac{ODvalue}{10}$
Runtime behavior	The sysWORXX I/O modules feature an internal watchdog to prevent undiscovered dead-locks. If a watchdog reset occurred, an Emergency message is sent out via CAN (see Section 9.3 on page 92).

Table 22: Internal runtime diagnostics and monitoring functions

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restore via 1011H
2001H	Array	Device Features	Integer16	-	-	-
	00H	Number of Entries	Unsigned8			
	01H	Device temperature	Integer16			
	02H	Device main voltage	Integer16			

Table 23: Object Dictionary entries for diagnostic and monitoring functions

## References

CiA 301 V4.02

## 8.4 Manufacturer specific extensions

### Introduction

This section describes the manufacturer specific functions implemented in the sysWORXX I/O modules.

In addition to the corresponding device profile, the following extensions are available:

- Minimal NMT boot up master (Object 2000H)
- I/O filtering (Object 2010H)
- PowerFail configuration

### Minimal NMT boot up master

The minimal NMT boot up master function enables operation of sysWORXX I/O devices without NMT master present on the network. This function handles the transmission of a NMT boot up message after a given delay time has expired.

Two object entries (Object 2000H Subindex 01H) exist to control this function. Refer to *Table 25* for detailed information. Any change of settings for this function is stored to non-volatile memory immediately after write access, independent of the common load/save mechanism provided with Object 1010H and Object 1011H. To activate the new settings, a reboot (by reset or power on) is necessary.

### Powerfail configuration

The monitoring of main voltage by power fail can be deactivated. If it is deactivated no emergency message and no reset is generated if main voltage drops under power fail level (see 9).

### I/O filtering

This function implements a bit-wise applied filter for digital inputs on the sysWORXX I/O modules. It allows for selective Enable/Disable of digital inputs.

## Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
2000H	Var	<b>NMT Boot Configuration</b>	<b>Unsigned8</b>	-	<b>Auto access<sub>1</sub></b>	<b>Auto access</b>
	00H	Number of Entries	Unsigned8			
	01H	NMT Boot enable	Unsigned8			
	02H	NMT Start Time	Unsigned16			
2001H	Array	Device Features <sup>2</sup>	Integer16	-	-	-
2002H	Var	<b>Power Fail Configuration</b> (from firmware version 1.30)	<b>Unsigned8</b>	-	<b>X</b>	<b>X</b>
	00H	Number of Entries	Unsigned8			
	01H	PowerFail Interrupt enable	Unsigned8			
2010H	Array	<b>Disable digital input 8-Bit</b>	<b>Unsigned8</b>	-	<b>X</b>	<b>X</b>
	00H	Number of Entries	Unsigned8			
	01H	DI0_DI7_Disable	Unsigned8			
	02H	DI8_DI15_Disable	Unsigned8			
	03H	DI16_DI23_Disable	Unsigned8			

Table 24: Object Dictionary entries for manufacturer specific extensions



The light-grey shaded objects are only available on module type IO-X1 and IO-X2.

## Parameter description

Parameter	Description
<b>NMT Boot enable</b>	Enable or disable the NMT boot function 0 = disable

<sup>1</sup> Value is stored to non-volatile memory immediately after write access to the Object.

<sup>2</sup> Object 2001H is described in Section 8.4, Table 23 on page 70.



Parameter	Description
	1 = enable Default value: 0
<b>NMT Start Time</b>	This index contains the delay time for the boot function. The time base is milliseconds. Default value: 500ms.
<b>Power Fail Interrupt Enable</b> (from firmware version 1.30)	Enable or disable Power Fail monitoring 0 = disable 1 = enable (default)
<b>Dlx_Dlx_Disable</b>	Byte-value, which is applied bit-by-bit to a digital input block on the device. 0 = disable 1 = enable Default value: 00H (all disabled)

Table 25: Parameter description for manufacturer specific extensions

## References

CiA 301 V4.02

## 8.5 Device identification data

### Introduction

The Identity Object provides identifying information about the node. It stores basic information about the manufacturer, the product, revision and serial number and therefore is unique for each CANopen device. This Object is mainly used for remote configuring via LSS.

### Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mappable	Object stored via 1010H	Object restored via 1011H
1018H	<b>Record</b>	<b>Identity Object</b>	<b>Identity</b>	-	-	-
	00H	Number of Entries	Unsigned8			
	01H	Vendor ID	Unsigned32			
	02H	Product Code	Unsigned32			
	03H	Revision Number	Unsigned32			
	04H	Serial Number	Unsigned32			

Table 26: Object Dictionary entry for the Identity Object

### Parameter description

Parameter	Description
<b>Vendor ID</b>	This Subindex contains the identification code of the manufacturer of the device. This value is assigned uniquely to each vendor of CANopen devices by the CiA <sup>1</sup> Users and Manufacturers Association.
<b>Product Code</b>	This Subindex contains the unique value assigned by the vendor, specifying the device type. For the sysWORXX I/O modules, this Subindex contains the order number of the device.

<sup>1</sup> CAN in Automation (<http://www.can-cia.org>)

Parameter	Description																
Revision Number	This Subindex stores the revision number of the device firmware, assigned by the vendor. The table below shows the structure of this value.																
	MSB <span style="float:right">LSB</span>																
	3124231615870																
	<table><tr><td colspan="4">Firmware</td><td colspan="4">CANopen Stack</td></tr><tr><td colspan="2">Major revision</td><td colspan="2">Minor revision</td><td colspan="2">Major revision</td><td colspan="2">Minor revision</td></tr></table>	Firmware				CANopen Stack				Major revision		Minor revision		Major revision		Minor revision	
	Firmware				CANopen Stack												
Major revision		Minor revision		Major revision		Minor revision											
e.g. The value 01030528H is to be read: Firmware version: 1.03 CANopen stack version: 5.28																	
Serial Number	This Subindex contains the serial number of the device.  The serial number can also be find on a sticker (number + barcode) placed on the enclosure.																

Table 27: Parameter description Identity Object

References

CiA 301 V4.02

## 8.6 Synchronized operations

### Introduction

This section describes the configuration of SYNC settings for the sysWORXX I/O modules and provides a brief overview on how synchronization works in CANopen networks.

In CANopen, the synchronized communication method is implemented using a SYNC signal, which is a specific message (SYNC message) without any data and high priority. SYNC is based on the Producer/Consumer principle. Typically, the SYNC producer transmits SYNC messages on a fixed time basis. The number of SYNC producers in a CANopen network is not limited. This enables setup of different groups of synchronized operating devices.

### SYNC principle in CANopen

#### **Synchronized communication for inputs (sensors)**

The sensors constantly read their input data and keep a current copy in the message transmit buffer. Upon reception of the SYNC message, all sensors stop updating the message transmit buffer and start transmitting the data. Although all messages are transmitted serially via CAN, the data received by the main controller are from the same moment of time (i.e. the moment the SYNC signal was received by the sensors).

#### **Synchronized communication for outputs (actuators)**

Once the processing unit has new values for the outputs it transmits the data serially via CAN. The actuators receiving the messages keep the received data in their receive buffers without applying the data to their outputs. Upon the reception of the next SYNC signal the data are applied to the outputs in parallel.

---

**Note**

The complete communication cycle, including transmission of input data, processing and transmission of output data, should be finished within the communication cycle period! Refer to *Figure 23* unterhalb.

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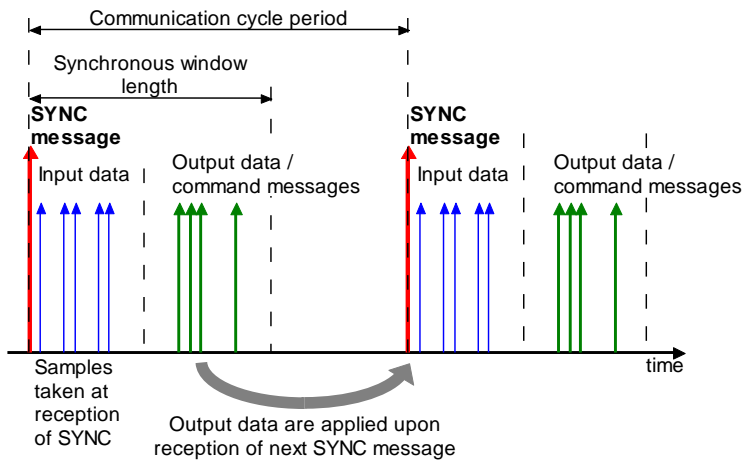


Figure 23: Synchronized communication principle in CANopen

Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
1005H	Var	COB-ID SYNC	Unsigned32	-	X	X
	00H	COB-ID SYNC	Unsigned32			
1007H	Var	Synchronous Window Length	Unsigned32	-	X	X
	00H	Synchronous Window Length	Unsigned32			

Figure 24: Object dictionary entries for SYNC

Parameter description

Parameter	Description												
COB-ID SYNC	Contains the COB-ID used by the SYNC Object along with a flag to indicate if the node generates the SYNC Object or not.  For 11-bit CAN identifier (COB-ID) the value is constructed as follows:												
	<table><tr><th>Bit</th><th>Description</th></tr><tr><td>0-10</td><td>COB-ID for SYNC Object</td></tr><tr><td>11-28</td><td>Set to 0 (reserved for 29-bit COB-ID)</td></tr><tr><td>29</td><td>Set to 0 to select 11-bit COB-ID</td></tr><tr><td>30</td><td>Set to 0 as the sysWORXX I/O devices do not support generation of SYNC messages.</td></tr><tr><td>31</td><td>Do not care (set to 0)</td></tr></table>	Bit	Description	0-10	COB-ID for SYNC Object	11-28	Set to 0 (reserved for 29-bit COB-ID)	29	Set to 0 to select 11-bit COB-ID	30	Set to 0 as the sysWORXX I/O devices do not support generation of SYNC messages.	31	Do not care (set to 0)
	Bit	Description											
	0-10	COB-ID for SYNC Object											
	11-28	Set to 0 (reserved for 29-bit COB-ID)											
29	Set to 0 to select 11-bit COB-ID												
30	Set to 0 as the sysWORXX I/O devices do not support generation of SYNC messages.												
31	Do not care (set to 0)												
	<b>Note</b>  The sysWORXX I/O modules only support 11-bit COB-ID and cannot operate as SYNC producer.												
	Default value: 80H/128												
Synchronous Window Length	This entry defines the period of time in microseconds after a SYNC Object has been transmitted on the bus in which synchronous PDOs must be transmitted.  This period must be smaller than the Communication Cycle Period (see Figure 23). Each node using the same SYNC COB-ID must have the same Synchronous Window Length.  If the node fails to transmit the PDO within the Synchronous Window Length (e.g. because higher prior messages were transmitted on the bus), this PDO is not transmitted again for this cycle.												
	<b>Note</b>  Synchronous PDO are never transmitted outside the Synchronous Window Length. This requires a careful assignment of message priorities during application planning in order to make sure all data can be transmitted in time.												
	Default value: 00H (SYNC not used)												

Figure 25: Parameter description for synchronous operation

## References

CiA 301 V4.02

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## 9 Error behavior and system messages

### 9.1 Device status LEDs

#### Introduction

This section describes the meaning and blinking cycles of the Run- and Error-LED on the sysWORXX I/O devices. The I/O status LEDs are described with the devices.

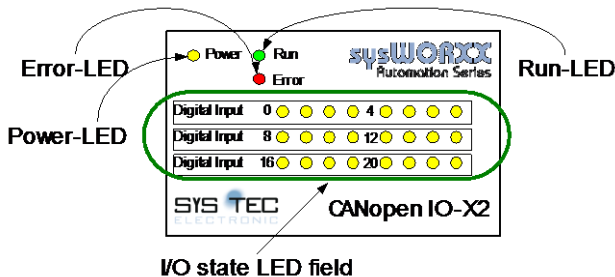
In addition to the module state, some hardware errors are displayed, too. The reason of the hardware error is displayed in the I/O state LED field (1<sup>st</sup> line). These error states are manufacturer-specific and highlighted with a light-grey background in *Table 28* and *Table 29*.

#### Status LEDs

The **Run-LED** (green) indicates the current NMT state of the sysWORXX I/O module.

The **Error-LED** (red) indicates errors that occurred (e.g. CAN-bus, configuration error).

An overview about the LED display is given below.



Description of LED states

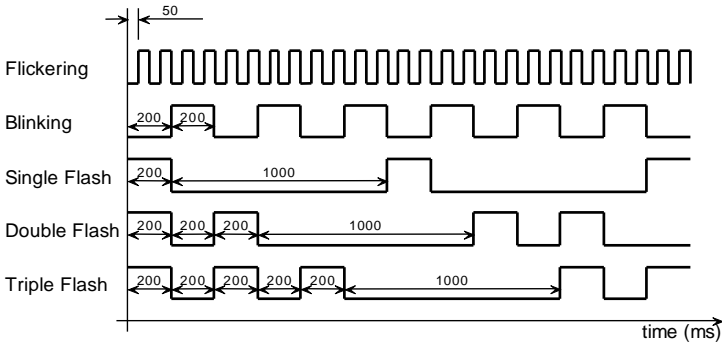


Figure 26: LED blinking cycles of the sysWORXX I/O modules

Run-LED state	NMT state	Description
Always On	OPERATIONAL	The device is in NMT state OPERATIONAL
Blinking	PRE-OPERATIONAL	The device is in NMT state PRE-OPERATIONAL
Single Flash	STOPPED	The device is in NMT state STOPPED
Flickering	OPERATIONAL or PRE-OPERATIONAL	LSS service in progress (alternate flickering with Error-LED)
Synchronous blinking with Error-LED	INITIALIZING	<b>Configuration error</b> A wrong configuration selected at hardware switches.
Synchronous Triple Flash with Error-LED	INITIALIZING	<b>Hardware error</b> Hardware error detected during internal diagnostics.

Table 28: Description of Run-LED states

Error-LED states	NMT-state	Description
Off	No error	The device is operating under normal conditions.
Flickering	OPERATIONAL or PRE-OPERATIONAL	LSS service in progress (alternate flickering with Run-

Error-LED states	NMT-state	Description
		LED)
Single Flash	OPERATIONAL or PRE-OPERATIONAL	<b>Warning limit reached</b> At least one of the error counters of the CAN controller has reached or exceeded the warning limit
Double Flash	OPERATIONAL or PRE-OPERATIONAL	<b>Error control event</b> A node guarding event or heartbeat event has occurred (see Section 9.5).
On	OPERATIONAL or PRE-OPERATIONAL	<b>Bus off<sup>1</sup></b> The CAN controller is in state bus-off (too many error frames on the bus).
Synchronous blinking with RUN LED	INITIALIZING	<b>Configuration error</b> A wrong configuration is selected with the rotary switches. see Table 30
Synchronous Triple Flash with RUN LED	INITIALIZING	<b>Hardware error</b> The internal diagnostic functions detect an hardware error during power on and the NMT command "Reset Node". see Table 30

Table 29: Description of Error-LED states

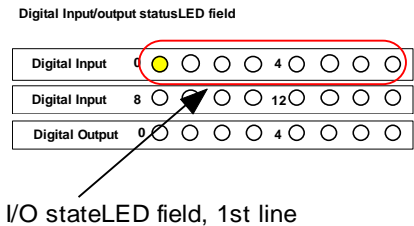


Figure 27: Signaling configuration or hardware errors, example for baudrate error, see Table 30

<sup>1</sup> After the Bus off error state has disappeared, the module sends out an Emergency message (see Section 9.3) and continues with normal operation. The NMT state (see Section 9.5) remains unchanged.

I/O stateLED 1 <sup>st</sup> line	Description
LED0	configuration error: Baudrate switch out of range (value >8)
LED1	configuration error: Node-ID switch out of range (0 or >7FH)
LED2	hardware error: serial number invalid
LED3	hardware error: CRC error, nonvolatile memory Since Software-Version V1.38 the 2 <sup>nd</sup> LED-line displays the section, where the error occurred. The following values are displayed binary coded (e.g. 0x03 is shown by LED0 and LED1 on): 0x01     Device parameters (serial number, ...) 0x02     Baudrate 0x03     Node-ID 0x04     Predefined Errorfield 0x05     OD-Entries 0x06     Boot-Master 0x07     Manufacturer calibration data
LED4	hardware error: product code invalid
LED5	hardware error: calibration data invalid

Table 30: Description of configuration and hardware error signaling

Error	Action
<b>Warning limit reached</b>	Please refer to <i>Section 13.2</i> for a detailed test procedure.
<b>Bus off</b>	Please refer to <i>Section 13.2</i> for a detailed test procedure.
<b>Configuration error</b>	Check for correct settings on the hardware switches and reset. If this doesn't help reset to factory defaults ( <i>see Section 5.6</i> ). If the error still persists contact the support for further assistance
<b>Hardware error</b>	Please contact the support for further assistance!

Table 31: User action required for error events

If Program Control (CANopen Bootloader) is active the RUN- and ERROR-LED gets a special function for monitoring program download (from firmware version V1.30):

Run-LED state	ERROR-LED state	Description
Always Triple Flash	Off	program download is running
	Single Flash	reason for bootloader is "application-signature is not set"
	Double Flash	reason for bootloader is "application-CRC is wrong"

Table 32: Description of Run- and Error-LED at Program Control

**Reference**

CiA 303-3 V1.0

## 9.2 Reading diagnostic data

### Introduction

In addition to the state LEDs the sysWORXX I/O devices feature several standardized Object Dictionary entries providing detailed information about the device state and an error history.

On some device types extended status information for I/Os are provided in the device profile section of the Object dictionary. These Objects are described with the respective device.

This section describes the diagnostic data readable via OD access during runtime. Internal diagnostics at startup and monitoring features are described in *Section 8.3 on page 73*. Emergency messages are described in *Section 9.3 on page 92*.

### Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
1001H	Var	Error Register	Unsigned8	-	-	-
	00H	Error Register	Unsigned8			
1003H	Array	Pre-Defined Error Field	Unsigned32	-	-	-
	00H	Number of Entries / Error Counter	Unsigned8			
	01H to 0AH	Standard Error Field	Unsigned32			

Table 33: Object Dictionary entries for error data on the sysWORXX I/O devices

### Parameter description

Parameter	Description
<b>Error Register</b>	<p>The error register value indicates if various types of errors have occurred. It is a part of the Emergency object, which is transmitted with the Emergency message.</p> <p>The following error values are implemented:</p> <p>00H = no error, respectively error reset  01H = generic error  11H = CAN communication error  81H = manufacturer specific error</p>

Parameter	Description						
	85H = manufacturer specific error, voltage						
<b>Error Count</b>	Contains the number of errors stored in Object 1003H. Writing the value 00H to this entry results in resetting the stored values in the Standard Error Fields, i.e. the error history (see below).						
<b>Standard Error Field</b>	<p>This Object provides an error history containing the 10 most recent errors that occurred on the node and result in the transmission of the Emergency message. Subindex 01H always contains the most recent error. If a new error occurs, it will be stored to Subindex 01H and the older values are shuffled down. Subindex 00H contains the number of errors stored in the error history.</p> <p><b>Note</b></p> <p>The complete error history (Object 1003H is stored to non-volatile memory and restored after power cycle. The error history can be erased by writing the value 0 to Subindex 0 of Object 1003H.</p> <p>This entry has the following structure:</p> <table border="1"> <tr> <td>MSB</td><td>LSB</td></tr> <tr> <td>31</td><td>16 15 0</td></tr> <tr> <td>Manufacturer specific additional information</td><td>Error code</td></tr> </table> <p>A list of error codes is given in Section 9.3.</p> <p>In the area of the additional information are stored, for example, the channel number of an input where the error occurred.</p>	MSB	LSB	31	16 15 0	Manufacturer specific additional information	Error code
MSB	LSB						
31	16 15 0						
Manufacturer specific additional information	Error code						

Table 34: Parameter description for error data

### Reference

CiA 301 V4.02

### See also

Section 11, Digital I/O modules

Section 12, Analog I/O modules

### 9.3 Evaluation of diagnostic messages (CANopen Emergency messages)

#### Introduction

Each sysWORXX CANopen I/O module features an Emergency Object (aka EMCY) to report errors via CAN (Emergency messages). This enables a remote device with Emergency Consumer Service, typically the application master (e.g. a PLC), to listen to this messages and thus react on specific errors.

Any malfunctions of the following components of a device are covered by Emergency messages:

- Digital outputs
- Analog input and outputs
- Integrated power supply and diagnostics

In general, Emergency messages are only reported once, as the reported error is considered to be existing (“still be there”) until the node uses another Emergency message to clear/reset that specific error.

#### Error conditions for digital outputs

Refers to modules:

CANopen IO-X1 and CANopen IO-X3

Error condition	Scope
short-circuit	Channel

Table 35: Error conditions for digital outputs

#### Error conditions for analog inputs

Refers to modules:

CANopen IO-X4, CANopen IO-X5 and CANopen IO-X7

Error condition	Scope
Line-break/short-circuit	Channel
Process value exceeded lower-limit of measurement range	Channel
Process value exceeded upper-limit of measurement range	Channel
Configuration error (invalid value range)	Channel

Table 36: Error conditions for analog inputs

#### Error conditions for analog outputs

Refers to module CANopen IO-X6.



Error condition	Scope
Line-break/short circuit	Channel

Table 37: Error conditions for analog outputs

## Error conditions for integrated power supply and diagnostics

Refers to all modules.

Error condition	Scope
Power-fail	Device
Overheat	Device
Configuration error	Device
Hardware error	Device

Table 38: Error conditions for power supply and diagnostics


## Emergency message structure






An Emergency message always contains 8 data bytes. The first two bytes hold the CANopen Error Code (see *Table 40*). The third byte contains a copy of the error register (see Object 1001H in *Section 9.2*) and the remaining 5 bytes contain the manufacturer specific error code.

byte 0	byte 1	byte 2	byte 3	byte 4	byte 5	byte 6	byte 7
Error Code	Error Register	Manufacturer specific error code					

Table 39: Structure of an Emergency message

## Emergency error codes

Emergency error code	Description
0000H	No error / error reset
2310H	Current at the digital output to high (overload)
3120H	Mains voltage too low, power-fail
4201H	Internal device temperature above 60°C (overheat)
5001H	Hardware reset caused by watchdog or reset button
5002H	CRC error on FLASH memory
	 <b>WARNING</b> Device not ready for operation and must be replaced! Please contact our support for further instructions.

Emergency error code	Description														
5003H	<p>CRC error on RAM</p> <hr/>  <b>WARNING</b> Device not ready for operation and must be replaced! Please contact our support for further instructions.														
5004H	<p>CRC error on EEPROM</p> <p>Behavior since Software-Version V1.38:</p> <p>Byte 0x00 of the vendor specific error field indicates the section, where the error occurred. Meaning of the values of Byte 0x00:</p> <table> <tr> <td>0x01</td><td>Device parameters (serial number, ...)</td></tr> <tr> <td>0x02</td><td>Baudrate</td></tr> <tr> <td>0x03</td><td>Node-ID</td></tr> <tr> <td>0x04</td><td>Predefined Errorfield</td></tr> <tr> <td>0x05</td><td>OD-Entries</td></tr> <tr> <td>0x06</td><td>Boot-Master</td></tr> <tr> <td>0x07</td><td>Manufacturer calibration data</td></tr> </table> <hr/>  <b>WARNING</b> Device not ready for operation and must be replaced! Please contact our support for further instructions.	0x01	Device parameters (serial number, ...)	0x02	Baudrate	0x03	Node-ID	0x04	Predefined Errorfield	0x05	OD-Entries	0x06	Boot-Master	0x07	Manufacturer calibration data
0x01	Device parameters (serial number, ...)														
0x02	Baudrate														
0x03	Node-ID														
0x04	Predefined Errorfield														
0x05	OD-Entries														
0x06	Boot-Master														
0x07	Manufacturer calibration data														
6101H	<p>Unexpected software reset</p> <hr/>  <b>WARNING</b> Device not ready for operation and must be replaced! Please contact our support for further instructions.														
6102H	<p>Stack overflow</p> <hr/>  <b>WARNING</b> Please contact our support for further instructions.														
6103H	<p>Unused software interrupt</p> <hr/>  <b>WARNING</b> Please contact our support for further instructions.														
6110H (from firmware version V1.30)	<p>reason for starting bootloader is "application-signature is not set"</p> <p>This information is not saved in Predefined Errorfield.</p>														

Emergency error code	Description	
6111H (from firmware version V1.30)	reason for starting bootloader is “application-CRC is wrong” This information is not saved in Predefined Errorfield.	
8110H	CAN overrun error. CAN message could not be transmitted.	
8120H	CAN controller in error passive mode	
8130H	Lifeguarding or heartbeat error	
8140H	CAN controller recovered from bus off	
8210H	PDO not processed due to length error	
Device specific error codes		Scope
FF03H	Sensor fraction on input	Channel; IO-X4, IO-X5, IO-X7
FF04H	Sensor overload on Input	
FF05H	Short-circuit at input	
FF06H	Chosen value range too low for configured sensor type	
FF07H	Chosen value range too high for configured sensor type	
FF08H	If channel configured as voltage input (U-mode): short circuit	Channel; IO-X6
	If channel configured as current input (I-mode): open output, no load connected, cable-break	

Table 40: Supported emergency error codes

### Object Dictionary entries

The following table describes Object 1014H, used to configure the Emergency message COB-ID of an device.

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
1014H	Var	COB-ID Emergency message	Unsigned32	-	X	X
	00H	COB-ID Emergency message	Unsigned32			

Table 41: Object Dictionary entries for the Emergency COB-ID

Parameter description

Parameter	Description	
COB-ID Emergency message	Defines the COB-ID used for the Emergency message transmitted by the node and specifies if the Emergency Object is used or not.	
	Bit	Description
	0-10	COB-ID for Emergency message
	11-28	Set to 0 (reserved for 29-bit COB-ID)
	29	Set to 0 to select 11-bit COB-ID
	30	Reserved, set to 0.
	31	Set to 0 if the node does use the Emergency Object. Set to 1 if the node does not use the Emergency Object.
	<b>Note</b> The sysWORXX I/O devices only support 11-bit identifiers (COB-IDs)	

Table 42: Parameter description for the Emergency COB-ID

Reference

CiA 301 V4.02

9.4 Error behavior

Introduction

This section describes the behavior (state-change) of a sysWORXX I/O device in case errors. This behavior is configurable by the user via Object 1029H and several device specific objects.

Emergency messages are covered by *Section 9.3* and therefore not included in this section.

Supported error conditions

The sysWORXX I/O modules perform a state-change upon the following communication errors:

- Bus off on the CAN controller
- Life guarding event occurred
- Heartbeat event occurred

Supported state changes

The following state-changes may be performed:

- NMT state-change
- Output state change (device specific)

Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mapable	Object stored via 1010H	Object restored via 1011H
1029H	Array	Error Behavior	Unsigned8	-	X	X
	00H	Number of Error Classes	Unsigned8			
	01H	Communication Errors	Unsigned8			
6206H <sup>1</sup>	Array	Error Mode Output 8-bit	Unsigned8	-	X	X
6207H <sup>1</sup>	Array	Error Value Output 8-bit	Unsigned8	-	X	X
6340H <sup>2</sup>	Array	AO Fault Mode	Unsigned8	-	X	X
7341H	Array	AO Fault Value	Integer16	-	X	X

Table 43: Object Dictionary entries for configuring the error behavior



The light-grey shaded objects are not available on all module types. Please refer to the corresponding device description for detailed information.

<sup>1</sup> Objects 6206H and 6207H are only available on modules with digital outputs (IO-X1, IO-X3)

<sup>2</sup> Objects 6340H and 7341H are only available on modules with analog outputs (IO-X6)

Parameter description

Parameter	Description								
<b>Communication Error</b>	Defines the behavior of the node when a communication error is encountered.  Valid values are:								
	<table><tr><th>Value</th><th>Description</th></tr><tr><td>00h</td><td>Switch to NMT state PRE-OPERATIONAL</td></tr><tr><td>01h</td><td>No change of NMT state</td></tr><tr><td>02h</td><td>Switch to NMT state STOPPED</td></tr></table>	Value	Description	00h	Switch to NMT state PRE-OPERATIONAL	01h	No change of NMT state	02h	Switch to NMT state STOPPED
	Value	Description							
	00h	Switch to NMT state PRE-OPERATIONAL							
	01h	No change of NMT state							
02h	Switch to NMT state STOPPED								
Default value: 00H									
<b>Error Mode Output 8-bit</b>	Device specific parameter. Described in Section 11.1								
<b>Error Value Output 8-bit</b>	Device specific parameter. Described in Section 11.1								
<b>AO Fault Mode</b>	Device specific parameter. Described in Section 12.3								
<b>AO_Fault_Value</b>	Device specific parameter. Described in Section 12.3								

Table 44: Parameter description for configuring the error behavior

Reference

- CiA 301 V4.02
- CiA 401 V2.1
- CiA 404 V1.2

## 9.5 Module/Network status and device guarding

### Introduction

This section provides information about the network management capabilities of the sysWORXX I/O modules when deployed in a CANopen network.

Each sysWORXX I/O module implements a CANopen NMT slave device. This enables a Network Management Master (e.g. a PLC) to watch over all nodes to see if they are operating within their parameters. Upon failure of a node or reception of a certain alarm/emergency message it can initiate the appropriate recovery or shutdown procedures. Therefore a so-called “NMT state machine” is implemented on the device and several options for device guarding are supported:

### Module state machine

The NMT state machine implemented sysWORXX I/O modules allows the device to be in different operating states. A NMT master can initiate state transitions by sending so-called “node control messages” to either a single node or all nodes on the network. The NMT state machine of the sysWORXX I/O devices is shown below.

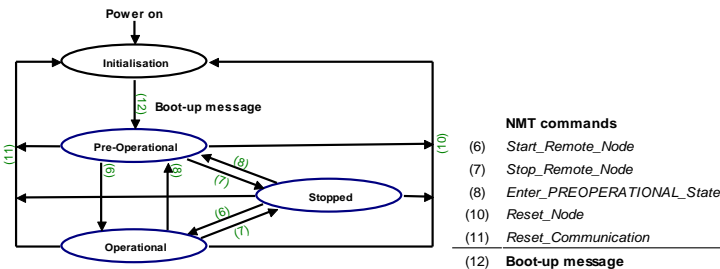


Figure 28: The NMT state machine

In state **INITIALIZATION**, the CANopen data structures (e.g. Object Dictionary) of a node is initialized by the application. This startup procedure is described in *Section 6.2* on page 56.

After **INITIALIZATION** has been completed the node automatically switches into state **PRE-OPERATIONAL**(12) and transmits the *Boot-up* message to inform the NMT master about this state change. In this state PDO communication is disabled. However, device access via SDO, NMT services and device guarding are available in this state.

After the device configuration has been completed (typically done by the application or the NMT master), the NMT command *Start\_Remote\_Node* (6) can be used to switch the node from state

PRE-OPERATIONAL into state **OPERATIONAL**. This state change results in the initial transmission of all active TPDOs to make the current process I/O state known to the network.

NMT command *Reset\_Node* (10) is used to reset node remotely. The power on values or values stored in non-volatile memory (if previously stored) are used for reset values.

In state **STOPPED** any communication except NMT, Heartbeat and Nodeguarding is disabled.

All sysWORXX I/O devices also support the NMT commands *Stop\_Remote\_Node* (7), *Enter\_PRE-OPERATIONAL\_State* (8), *Reset\_Node* (10), *Reset\_Communication* (11) to control state transitions (see *Figure 28* and *Table 46*).

	INITIALIZING	PRE- OPERATIONAL	OPERATIONAL	STOPPED
Boot-up	X			
SDO		X	X	
EMCY		X	X	
SYNC		X	X	
Heartbeat/ Node guarding		X	X	X
PDO			X	

Table 45: NMT state dependent communication

NMT command messages

The first data byte of a NMT command message always contains the NMT command. The second byte contains the node-ID of the device to be started. The value 00H for node-ID addresses all nodes in the network (Broadcast). The COB-ID is always set to 000H.

Command	Description		
Start_Remote_Node	This command is used to set one or all nodes to state OPERATIONAL. COB-ID            2 byte data		
	000H	01H	node-ID
Stop_Remote_Node	This command is used to set one or all nodes to state STOPPED. COB-ID            2 byte data		
	000H	02H	node-ID



Command	Description		
Enter_PREOPERATIONAL_State	This command is used to set one or all nodes to state PRE-OPERATIONAL.		
	COB-ID	2 byte data	
	000H	80H	node-ID
Reset_Node	This command is used to reset one or all nodes on the network.		
	COB-ID	2 byte data	
	000H	81H	node-ID
Reset_Communication	This command is used to reset the communication parameters of one or all nodes on the network.		
	COB-ID	2 byte data	
	000H	82H	node-ID

Table 46: NMT commands

## Options for device guarding

### Node guarding / Life guarding

With *node guarding* the NMT master polls all slaves for their current NMT state information. If a node does not respond within a specified time the NMT master assumes that this slave was lost and can take appropriate actions.

*Life guarding* uses the same principle as node guarding. However, with life guarding the NMT slave monitors the cyclical node guarding request of the NMT master. If the NMT slave has not been polled during its lifetime<sup>1</sup>, a remote node error is indicated through the NMT service life guarding event (see Section 9.4 on page 96).

Life guarding can be disabled on the NMT slave node by setting the Guard Time (Object 100CH) or the Life Time Factor (Object 100DH) to 0.

COB-ID	DLC	Data byte 0
700H + node-ID	1	state

Table 47: Response to a node/life guarding remote frame

State	NMT state
00H	BOOT UP
04H	STOPPED

<sup>1</sup> See Table 51 on page 100

State	NMT state
05H	OPERATIONAL
7FH	PRE-OPERATIONAL

Table 48: Node state of a CANopen device

Bit 7 of the status byte always starts with a 0 and changes its value after each transmission. The application is responsible for actively toggling this bit. This ensures that the NMT master gets the confirmation that the application on the slave is still running.

#### Note

As node/life guarding uses CAN remote frames it is not recommended to use these supervision methods. Instead, the use of Heartbeat (see below) is recommended as it offers more flexibility at reduced busload.

#### Heartbeat

With the Heartbeat method, each node by itself transmits a dedicated Heartbeat message (Heartbeat Producer) with 1-byte data containing the NMT state of the node. No NMT master is required for using Heartbeat.

##### *Heartbeat Producer*

The Heartbeat producer cyclically sends its Heartbeat message. The *Producer Heartbeat Time* is configurable via Object 1017H (16-bit value in ms) and specifies the time between two subsequent Heartbeat messages. To disable the Heartbeat producer set Object 1017H to 0.

COB-ID	DLC	Data byte 0
700H + node-ID	1	state

Table 49: Heartbeat message

The content of the status byte corresponds to that of the Node Guarding message (see *Table 48*). Contrary to the node and/or life Guarding, bit 7 of the status byte does not toggle with each transmission. It is always set to 0.

##### *Heartbeat Consumer*

The Heartbeat Consumer receives the Heartbeat messages sent from the producer. Therefore, the supervised nodes need to get registered with its node-ID and corresponding Heartbeat time.

This information is stored in the Object Dictionary at Object 1016H containing a Subindex for each Heartbeat Consumer. Up to 5 Heartbeat Consumers are available on sysWORXX I/O modules with digital or analog outputs. Devices with inputs only do not need Heartbeat Consumers, as there is no output to set into “Fault State” in case of error. The Heartbeat Consumer is activated with the first

Heartbeat message, that has been received, and a corresponding entry is registered in the OD. If the Heartbeat time configured for a producer expires without reception of the corresponding Heartbeat message, the consumer reports a Heartbeat error event resulting in the error behavior described in *Section 9.4*.

The Heartbeat consumer is disabled when the consumer Heartbeat time is set to 0.

### Object Dictionary entries

Object Index	Object type / Subindex	Object name	Data type	Object mappable	Object stored via 1010H	Object restored via 1011H
<b>100CH</b>	<b>Var</b>	<b>Guard Time</b>	<b>Unsigned16</b>	-	X	X
	00H	Guard Time	Unsigned16			
<b>100DH</b>	<b>Var</b>	<b>Life Time Factor</b>	<b>Unsigned8</b>	-	X	X
	00H	Life Time Factor	Unsigned8			
<b>1016H</b>	<b>Array</b>	<b>Consumer Heartbeat Time</b>	<b>Unsigned32</b>	-	X	X
	00H	Number of Entries	Unsigned32			
	01H-05H	Consumer Heartbeat Time	Unsigned32			
<b>1017H</b>	<b>Var</b>	<b>Producer Heartbeat Time</b>	<b>Unsigned16</b>	-	X	X
	00H	Producer Heartbeat Time	Unsigned16			

Table 50: Object Dictionary entries for device guarding

### Parameter description

Parameter	Description
<b>Guard Time</b>	Specifies the period between the node guarding requests sent to the node in milliseconds. Default value: 00H
<b>Life Time Factor</b>	Specifies the number of multiplies of the Guard Time to wait for a response from the supervised node. The <i>Node Life Time</i> is the Guard Time multiplied by the Life Time Factor. If the node does not respond within the Node Life Time, then a node/life guarding error occurs (see <i>Section 9.4</i> ). Default value: 00H

Parameter	Description								
<b>Consumer Heartbeat Time</b>	<p>Specifies the maximum time to wait for a Heartbeat message (in milliseconds) before generating a Heartbeat error event.</p> <p>The value is constructed as follows:</p> <table><tr><th>Bit</th><th>Value</th></tr><tr><td>24..31</td><td>00H</td></tr><tr><td>16..23</td><td>Node-ID</td></tr><tr><td>0..15</td><td>Consumer Heartbeat Time</td></tr></table> <p>Default value: 00H (disabled)</p> <p><b>Note</b></p> <p>The Heartbeat Consumer Time must be greater than the Heartbeat Consumer time, as there might be delays in transmission of the Heartbeat message.</p>	Bit	Value	24..31	00H	16..23	Node-ID	0..15	Consumer Heartbeat Time
Bit	Value								
24..31	00H								
16..23	Node-ID								
0..15	Consumer Heartbeat Time								
<b>Producer Heartbeat Time</b>	<p>Specifies the time between transmission of two Heartbeat messages in milliseconds.</p> <p>Default value: 00H (disabled)</p>								

Table 51: Parameter description for device guarding configuration

**Reference**

CiA 301 V4.02

# 10 General technical data

## 10.1 Standards and certifications

### Introduction

This section specifies the standards, test values and test criteria applicable to the sysWORXX CANopen I/O devices.

### CE label



The sysWORXX I/O devices meet the requirements and protective objectives of the following EC directives, which were published in the official pamphlets of the European Community:

- |            |  |
|------------|--|
| 73/23/EEC" | Electrical Equipment Designed for Use within Certain Voltage Limits" (low voltage directive) |
| 89/336/EEC | "Electromagnetic Compatibility" (EMC Directive)  |

The EC Declaration of Conformity is available to the relevant authorities at:

SYS TEC electronic GmbH  
Quality Management Dept.  
Am Windrad 2  
D-08468 Heinsdorfergrund  
GERMANY

### CAN and CANopen standards

The sysWORXX CANopen I/O devices comply with the following standards and specifications:

- |                    |   |
|--------------------|---|
| CiA DR 303-1 V1.11 | Cabling and Connector Pin Assignment  |
| CiA DR 303-2 V1.1  | Representation of SI Units and Prefixes   |
| CiA DR 303-3 V1.0  | Indicator Specification   |
| CiA DS 301 V4.02   | Application Layer and Communication Profile   |
| CiA DSP 305 V1.1   | Layer Setting Services and Protocol   |
| CiA DS 401 V2.1    | Device Profile for Generic I/O Modules  |
| CiA DS 404 V1.2    | Device Profile Measuring Devices and Closed Loop Controllers                          |
| ISO 11898-2        | Road vehicles - Controller area network (CAN) - Part 2: High-speed medium access unit |

## 10.2 Electromagnetic compatibility

### Definition

Electromagnetic compatibility refers to the capability of electrical equipment in reliably performing its dedicated function in an electromagnetic environment, without causing interference in the same environment.

The sysWORXX CANopen I/O devices meet all requirements of EMC legislation for the European market, under the condition that the electrical configuration of the devices has been carried out in compliance with the specifications and directives respectively.

## 10.3 Shipping and storage conditions

### Shipping and storage conditions

The specifications below apply to modules, which are shipped and stored in their original packaging.

Type of condition	Permissible range
Free fall	≤ 1m
Temperature	from -20 °C to +90 °C
Temperature fluctuation	<20 K/h
Barometric pressure	-1080 hPa to 660 hPa (corresponds with altitudes from -1000m to 3500m)
Relative humidity	<95 %, without condensation

Table 55: Shipping and storage conditions

## 10.4 Mechanical and climatic ambient conditions

### Climatic ambient conditions

Applicable climatic ambient conditions (only indoor use):

Ambient conditions	Fields of application	Remarks
Temperature	-20 °C to 70 °C -20 °C to 50 °C (IO-X7 only)	All mounting positions
Temperature fluctuation	<10 K/h	-
Relative humidity	<95 %	without condensation

Ambient conditions	Fields of application	Remarks
Air pressure	from -1080 hPa to 795 hPa	corresponds with an altitude of -1000m to 2000m

Table 56: Climatic ambient conditions

### Modules for operation in the range from -20°C to 50°C

The table below shows all modules suitable for operation in the range from -20°C to 50°C (only indoor use):

Designation	Order no.
CANopen IO-X7	3001006

Table 57: Modules suitable for commercial temperature range

### Modules for operation in the range from -20°C to 70°C

The table below shows all modules suitable for operation in the range from -20°C to 70°C (only indoor use):

Designation	Order no.
CANopen IO-X1	3001000
CANopen IO-X2	3001001
CANopen IO-X3	3001002
CANopen IO-X4	3001003
CANopen IO-X5	3001004
CANopen IO-X6	3001005

Table 58: Modules suitable for extended temperature range

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# 11 Digital I/O modules

## 11.1 CANopen IO-X1, digital input and output module 16DI + 8DO DC 24V

### Order No. and options

3001000	CANopen IO-X1 Galvanic isolated CAN
3001010	CANopen IO-X1 Galvanic isolated CAN, with pulsed output

### Properties

- 16 digital inputs 24VDC, galvanic isolated in groups of 4 inputs
- 8 digital outputs 24VDC/500mA, transistor, high side switch, short-circuit protected
- 8 digital pulsed output (version 3001010 only)
- CANopen device according to CiA 401 V2.1
- 24 LEDs for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Switch
- Separated power supply pin for supply of digital outputs

Module pinout

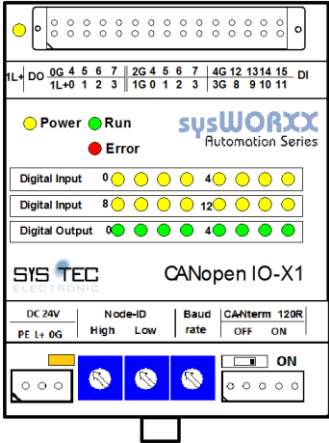


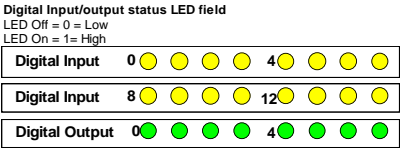
Figure 29: CANopen IO-X1 device schema

Pin	Label	Description
<b>Power supply connector</b>		
0	PEL+	
1	L+0G	+24VDC ±20%
2	0G	Ground 0 for device power supply
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+
<b>I/O connector</b>		
1*	1L+	+24VDC ( optional connection to L+)
2	0G	Ground 0 for digital outputs 0 to 7
3	0	digital output 0 24V/500mA
4	4	digital output 4 24V/500mA
5	1	digital output 1 24V/500mA
6	5	digital output 5 24V/500mA
7	2	digital output 2 24V/500mA
8	6	digital output 6 24V/500mA

Pin	Label	Description
9	3	digital output 3 24V/500mA
10	7	digital output 7 24V/500mA
11	1G	Ground 1 for digital inputs 0 to 3
13	0	digital input 0 24V to 1G
15	1	digital input 1 24V to 1G
17	2	digital input 2 24V to 1G
19	3	digital input 3 24V to 1G
12	2G	Ground 2 for digital inputs 4 to 7
14	4	digital input 4 24V to 2G
16	5	digital input 5 24V to 2G
18	6	digital input 6 24V to 2G
20	7	digital input 7 24V to 2G
21	3G	Ground 3 for digital inputs 8 to 11
23	8	digital input 8 24V to 3G
25	9	digital input 9 24V to 3G
27	10	digital input 10 24V to 3G
29	11	digital input 11 24V to 3G
22	4G	Ground 4 for digital inputs 12 to 15
24	12	digital input 12 24V to 4G
26	13	digital input 13 24V to 4G
28	14	digital input 14 24V to 4G
30	15	digital input 15 24V to 4G

Table 61: CANopen IO-X1 device pinout

LED display



Block diagram

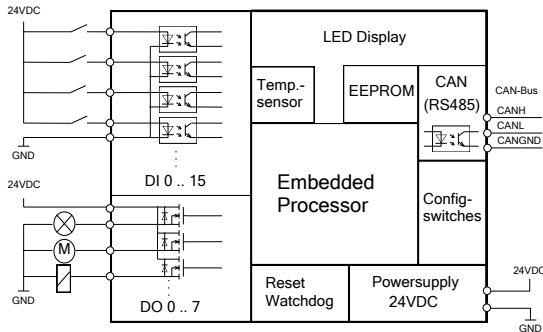


Figure 30: CANopen IO-X1 block diagram

Technical data

Common		Typical	Maximum
Power supply	V <sub>CPU</sub>	24V DC	±20%
	V <sub>IO</sub>	24V DC	±20%
Current consumption (I/Os inactive)	I <sub>CPU</sub>	0,05A	
	I <sub>IO</sub>	0,01A	
Temperature range	Storage		-20° ... +90°C
	Operation		-20° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	
Connection scheme	Removable spring-type clamp connectors		

Table 62: CANopen IO-X1 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 63: CANopen IO-X1 technical data part communication

I/O		Minimum	Maximum
<b>Digital outputs DO0..8</b>			
24V DC output, high- side switch, transistor	$U_{OH}$ at $I_{OH} = 500\text{mA}$	$V_{IO-0,16V} < U_{OH} < V_{IO}$	
	$U_{OL}$ at $I_{OL} = 0\text{mA}$		0.5V
	Current limitation $I_{OH\_max}$	2,8A	
	Maximum current (Polyswitch protected)		4A (at 20°C)
	$I_{OL}(\text{off})$		10μA
	$t_{off}$ at $I_{OH} = 500\text{ mA}$	115μs	190μs
	$t_{on}$ at $I_{OH} = 500\text{ mA}$	75μs	125μs
<b>Digital inputs DI0 .. 15</b>			
24V DC inputs	$U_{IH}$	15V	30V
	$U_{IL}$	-3V	5V
	$I_{IH} = (U_{IH}-6,8)/8200$	1mA	2,8mA

Table 64: CANopen IO-X1 technical data part I/O

## Manufacturer specific functions

The CANopen IO-X1 supports the following device specific manufacturer extension:

- Disable digital input 8-Bit (Object 2010H)
- Enable pulsed digital output (Object 2011H)
- Enable retrigger pulsed digital output (Object 2012H)
- Enable active off pulsed digital output (Object 2013H)
- **Pulslength pulsed digital output** (Object 2014H)

The generic manufacturer specific extensions are described in *Section 8.4*.

## Error behavior

In addition to the error behavior described with *Section 9.4* the CANopen IO-X1 features a device specific error behavior for its digital outputs with the following parameters:

- Error Mode Output 8-Bit
- Error Value Output 8-Bit
- Filter Constant Output 8-Bit

## Object dictionary

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
2010H	Array	Disable digital input 8-Bit (see Section 8.4 on page 75)	Unsigned8	-	x	x
2011H	Array	Enable pulsed digital output	Unsigned8	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7	Unsigned8			
2012H	Array	Enable retrigger pulsed digital output	Unsigned8	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7	Unsigned8			
2013H	Array	Enable active off pulsed digital output	Unsigned8	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7	Unsigned8			
2014H	Array	Pulslength pulsed digital output	Unsigned8	-	x	x
	00H	Number of Input 8-Bit	Unsigned16			
	01H	DO0_Pulselength	Unsigned16			
	02H	DO1_Pulselength	Unsigned16			
	...					
	08H	DO7_Pulselength	Unsigned16			
6000H	Array	Read Digital Input 8-Bit	Unsigned8	x	-	-
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7	Unsigned8			
	02H	DI8_DI15	Unsigned8			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
<b>6003H</b>	<b>Array</b>	<b>Filter Constant Input 8-Bit</b>	<b>Unsigned8</b>	-	X	X
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_FilterConstant	Unsigned8			
	02H	DI8_DI15_FilterConstant	Unsigned8			
<b>6005H</b>	<b>Var</b>	<b>Global Interrupt Enable 8-Bit</b>	<b>Boolean</b>	-		
<b>6006H</b>	<b>Array</b>	<b>Interrupt Mask Any Change 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptAny Change	Unsigned8			
	02H	DI8_DI15_InterruptAny Change	Unsigned8			
<b>6007H</b>	<b>Array</b>	<b>Interrupt Mask Low to High 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptLowToHigh	Unsigned8			
	02H	DI8_DI15_InterruptLowToHigh	Unsigned8			
<b>6008H</b>	<b>Array</b>	<b>Interrupt Mask High to Low 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptHighToLow	Unsigned8			
	02H	DI8_DI15_InterruptHighToLow	Unsigned8			
<b>6200H</b>	<b>Array</b>	<b>Write Output 8-Bit</b>	<b>Unsigned8</b>	x	-	-
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7	Unsigned8			
<b>6206H</b>	<b>Array</b>	<b>Error Mode Output 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_ErrorMode	Unsigned8			



Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
6207H	Array	<b>Error Value Output 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_ErrorValue	Unsigned8			
6208H	Array	<b>Filter Constant Output 8-Bit</b>	<b>Unsigned8</b>	-	x	x
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_FilterConstant	Unsigned8			

Table 65: CANopen IO-X1 Object Dictionary (Device specific part)

### Parameter description

Parameter	Description
<b>Disable digital input 8-Bit</b>	Specifies a manufacturer specific filter for the digital inputs.  The filter disables or enables specific input lines. 0 = disable 1 = enable Default value: 00H
<b>Filter constant of digital inputs 8-Bit</b>	Specifies whether the manufacturer specific filter is used for an input. 0 = Filter for input disable 1 = Filter for input enable Default value: 00H
<b>Global interrupt enable 8-Bit</b>	This parameter enables/disables the interrupt of the inputs (generating of events) globally, without changing the interrupt masks in Object 6006H, 6007H and 6008H.  1 = enable 0 = disable Default value: 00H
<b>Interrupt mask any change 8-Bit</b>	Specifies the input lines that generate an event upon positive and/or negative edge detection. 0 = interrupt disable 1 = interrupt enable Default value: FFH

Parameter	Description
<b>Interrupt mask low to high 8-Bit</b>	<p>Specifies the input lines that generate an event upon positive edge detection.</p> <p>0 = interrupt disable 1 = interrupt enable</p> <p>Default value: 00H</p>
<b>Interrupt mask high to low 8-Bit</b>	<p>Specifies the input lines that generate an event upon negative edge detection.</p> <p>0 = interrupt disable 1 = interrupt enable</p> <p>Default value: 00H</p>
<b>Error mode output 8-Bit</b>	<p>Specifies whether an output is set to its pre-defined error value (<i>see Object 6207H</i>) in case of an error event (<i>see Section 9.4</i>).</p> <p>0 = output value not changed 1 = output value switch to the state specified in Object 6207H</p> <p>Default value: 00H</p>
<b>Error value output 8-Bit</b>	<p>This parameter specifies the error value for a digital output.</p> <p>0 = output shall be set to '0' 1 = output shall be set to '1'</p> <p>Default value: 00H</p>
<b>Filter Constant output 8-Bit</b>	<p>This parameter specifies an output filter mask for a group of 8 outputs.</p> <p>0     Updating of outputs disabled. The current value is kept, even on reception of a new output value.</p> <p>1     Updating of outputs enabled upon reception of new output data.</p> <p>Default value: FFH</p>
<b>Enable pulsed digital output</b>	<p>This parameter specifies the possibility to configure a digital output as a pulsed output.</p> <p>0 = pulsed output disable 1 = pulsed output enable</p> <p>Default value: 00H</p>
<b>Enable retrigger pulsed digital output</b>	<p>This parameter specifies the possibility to retrigger a digital pulsed output before the digital output is switch off automatically. The time of the pulse is new started.</p> <p>0 = retrigger disable 1 = retrigger possible</p> <p>Default value: 00H</p>

Parameter	Description
<b>Enable active off pulsed digital output</b>	This parameter specifies the possibility to switch off a digital pulsed output before the time, specified in 2014H, is over. 0 = active switch off disable 1 = switch off possible Default value: 00H
<b>Pulslength pulsed digital output</b>	This parameter specifies the pulslength of a digital pulsed output. The unit ist millisecond [ms] e.g.: 100 means 100ms switch on time Default value: 00H

Table 66: CANopen IO-X1 parameter description

### Default mapping of I/O

PDO	TPDO1	RPDO1
<b>COB-ID</b>	180H+node-ID	200H+node-ID
<b>Mapped objects</b>	2	1
<b>Mapped obj 1 (data byte 0)</b>	DI0_7 6000H/01H/08H <sup>1</sup>	DO0_7 6200H/01H/08H
<b>Mapped obj.2 (data byte 1)</b>	DI8_15 6000H/02H/08H	

Table 67: CANopen IO-X1 default mapping

<sup>1</sup> A mapping entry consists of: Object/Subindex/Datasize of mapped data

## Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

### *When using digital inputs*

- (1) Configure the digital input PDO transmission triggers (Object 6006H to 6008H).  
Note: Only one trigger type per channel is permitted.
- (2) Enable global interrupt generation for digital inputs (Object 6005H)
- (3) If required by the application, set the manufacturer specific filtering (Object 2010H) and enable these filters for the corresponding channels (Object 6003H)

### *When using digital outputs*

- (1) Enable updating of used channels (Object 6208H)

If the application requires pre-defined error values for the outputs:

- (2) Configure the error value of the outputs (Object 6207H)
- (3) Enable the error mode of the channels (Object 6206H)

### *When using digital pulsed outputs (Order number 3001010 only)*

- (4) Enable pulsed output of used channels (Object 2011H),  
e.g. 01H for channel AO0
- (5) Set the **pulslength of the pulsed digital output** of used channels (Object 2014H)  
e.g. set subindex 1 to 100<sub>dec</sub> for AO0, pulslength 100ms

If the application requires retrigger functionality:

- (6) Configure the retrigger value of the outputs (Object 2012H)  
e.g. 01H for AO0

If the application requires active switch off functionality:

- (7) Configure the active switch off value of the outputs (Object 2013H)  
e.g. 01H for AO0

**Accessory**

Order number	Part
171024 171054	3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171034	30-pin I/O connector plug
180134	Jumper for the CAN bus termination

Table 68: Accessory for CANopen IO-X1

**References**

CiA 303-1 V1.3

CiA 303-3 V1.2

CiA 301 V4.02

CiA 401 V2.1

# 11.2 CANopen IO-X2, digital input module 24DI DC 24V

## Order No. and options

3001001     CANopen IO-X2  
                 galvanic isolated CAN

## Properties

- 24 digital inputs 24VDC, galvanic isolated in groups of 4 inputs
- CANopen device according to CiA 401 V2.1
- 24 LEDs for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Jumper

## Module pinout

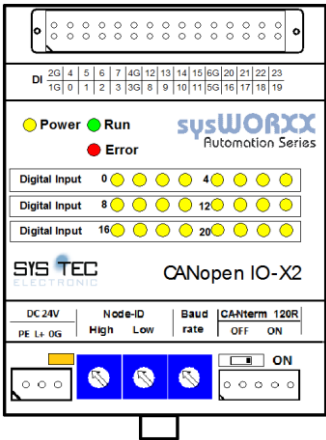


Figure 31: CANopen IO-X2 device schema

Pin	Name	Description
<b>Power supply connector</b>		
1	PE	
2	L+	+24VDC ±20%
3	OG	Ground 0 for device power supply

Pin	Name	Description
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+
<b>I/O connector</b>		
1*	1G	Ground 1 for digital inputs 0 to 3
2	2G	Ground 2 for digital inputs 4 to 7
3	0	digital input 0 24V to 1G
4	4	digital input 4 24V to 2G
5	1	digital input 1 24V to 1G
6	5	digital input 5 24V to 2G
7	2	digital input 2 24V to 1G
8	6	digital input 7 24V to 2G
9	3	digital input 3 24V to 1G
10	7	digital input 8 24V to 2G
11	3G	Ground 3 for digital inputs 8 to 11
13	4G	Ground 4 for digital inputs 12 to 15
15	8	digital input 8 24V to 3G
17	12	digital input 12 24V to 4G
19	9	digital input 9 24V to 3G
12	13	digital input 13 24V to 4G
14	10	digital input 10 24V to 3G
16	14	digital input 14 24V to 4G
18	11	digital input 11 24V to 3G
20	15	digital input 15 24V to 4G
21	5G	Ground 5 for digital inputs 16 to 19
23	6G	Ground 6 for digital inputs 20 to 23
25	16	digital input 16 24V to 5G
27	20	digital input 20 24V to 6G
29	17	digital input 17 24V to 5G
22	21	digital input 21 24V to 6G
24	18	digital input 18 24V to 5G
26	22	digital input 22 24V to 6G

Pin	Name	Description
28	19	digital input 19 24V to 5G
30	23	digital input 23 24V to 6G

Table 69: CANopen IO-X2 device pinout

## LED display

Digital input status LED field  
LED Off = 0 = Low  
LED On = 1 = High

Digital Input	0					4			
Digital Input	8					12			
Digital Input	13					20			

## Block diagram

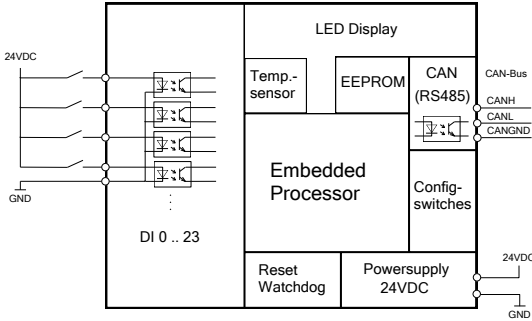


Figure 32: CANopen IO-X2 block diagram

## Technical data

Common		Typical	Maximum
Power supply	$V_{CPU}$	24V DC	±20%
Current consumption (I/Os inactive)	$I_{CPU}$	0,05A	
Temperature range	Storage		-20° ... +90°C
	Operation		-20° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	



Common		Typical	Maximum
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	
Connection scheme	Removable spring-type clamp connectors		

Table 70: CANopen IO-X2 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 71: CANopen IO-X2 technical data part communication

I/O		Minimum	Maximum
Digital inputs DI0 .. 23			
24V DC-inputs	$U_{InHigh}$	15V	30V
	$U_{InLow}$	-3V	5V
	$I_{IH} = (U_{IH}-6,8)/8200$	1mA	2,8mA
	Isolation voltage for galvanic isolation		1kV

Table 72: CANopen IO-X2 technical data part I/O

### Manufacturer specific functions

The CANopen IO-X2 supports the following device specific manufacturer extension:

- Disable digital input 8-Bit (Object 2010H)

The generic manufacturer specific extensions are described in *Section 8.4*.

### Error behavior

The CANopen IO-X2 has no device specific error behavior. Please refer to *Section 9.4* for configuration of error behavior on communication errors.

**Object dictionary**

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
2010H	Array	<b>Disable digital input 8-Bit</b> (see <i>Section 8.4 on page 75</i> )	Unsigned8	-	x	x
6000H	Array	<b>Read Digital Input 8-Bit</b>	Unsigned8	x	-	-
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7	Unsigned8			
	02H	DI8_DI15	Unsigned8			
6003H	Array	<b>Filter Constant Input 8-Bit</b>	Unsigned8	-	X	X
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_FilterConstant	Unsigned8			
	02H	DI8_DI15_FilterConstant	Unsigned8			
6005H	Var	<b>Global Interrupt Enable 8-Bit</b>	Boolean	-		
6006H	Array	<b>Interrupt Mask Any Change 8-Bit</b>	Unsigned8	-	x	x
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptAnyChange	Unsigned8			
	02H	DI8_DI15_InterruptAnyChange	Unsigned8			
6007H	Array	<b>Interrupt Mask Low to High 8-Bit</b>	Unsigned8	-	x	x
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptLowToHigh	Unsigned8			
	02H	DI8_DI15_InterruptLowToHigh	Unsigned8			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
<b>6008H</b>	<b>Array</b>	<b>Interrupt Mask High to Low 8-Bit</b>	<b>Unsigned8</b>	<b>-</b>	<b>x</b>	<b>x</b>
	00H	Number of Input 8-Bit	Unsigned8			
	01H	DI0_DI7_InterruptHighToLow	Unsigned8			
	02H	DI8_DI15_InterruptHighToLow	Unsigned8			

Table 73: CANopen IO-X2 Object Dictionary (Device specific part)

### Parameter description

Parameter	Description
<b>Disable digital input 8-Bit</b>	<p>This parameter specifies a manufacturer specific filter for the digital inputs.</p> <p>The filter disables or enables specific input lines.</p> <p>0 = disable 1 = enable</p> <p>Default value: 00H</p>
<b>Filter constant of digital inputs 8-Bit</b>	<p>Specifies whether the manufacturer specific filter is used for an input block.</p> <p>0 = Filter for input disable 1 = Filter for input enable</p> <p>Default value: 00H</p>
<b>Global interrupt enable 8-Bit</b>	<p>This parameter enables / disables the interrupt of the inputs (generating of events) globally without changing the interrupt masks in Object 6006H, 6007H and 6008H.</p> <p>1 = enable 0 = disable</p> <p>Default value: 00H</p>
<b>Interrupt mask any change 8-Bit</b>	<p>Specifies the input lines that generate an event upon positive and/or negative edge detection.</p> <p>0 = interrupt disable 1 = interrupt enable</p> <p>Default value: FFH</p>
<b>Interrupt mask low to high 8-Bit</b>	<p>Specifies the input lines that generate an event upon positive edge detection.</p> <p>0 = interrupt disable 1 = interrupt enable</p> <p>Default value: 00H</p>

Parameter	Description
<b>Interrupt mask high to low 8-Bit</b>	Specifies the input lines that generate an event upon negative edge detection. 0 = interrupt disable 1 = interrupt enable Default value: 00H

Table 74: CANopen IO-X2 parameter description

### Default mapping of I/O

PDO	TPDO1
<b>COB-ID</b>	180H+node-ID
<b>Mapped objects</b>	3
<b>Mapped obj 1 (data byte 0)</b>	DI0_7 6000H/01H/08H <sup>1</sup>
<b>Mapped obj.2 (data byte 1)</b>	DI8_15 6000H/02H/08H
<b>Mapped obj.3 (data byte 2)</b>	DI16_23 6000H/03H/08H

Table 75: CANopen IO-X2 default mapping

### Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Configure the digital input PDO transmission triggers (Object 6006H to 6008H).

<b>Note</b>
-------------

Only one trigger type per channel is permitted.
---

- (2) Enable Global interrupt for digital inputs (Object 6005H)

If the manufacturer-specific filters are required:

- (3) Set the manufacturer specific filtering (Object 2010H)
- (4) Enable these filters for the corresponding channels (Object 6003H)

---

<sup>1</sup> A mapping entry consists of: Object/Subindex/Datasize of mapped data

**Accessory**

Order number	Part
171024 171054	3-pin plug for the power supply
171023	5-pin plug with adapter cable to 9-pin D-Sub connector for CAN bus
171034	30-pin I/O connector plug
180134	1 jumper for the CAN bus termination

Table 76: Accessory for CANopen IO-X2

**References**

CiA 303-1 V1.3

CiA 303-3 V1.2

CiA 301 V4.02

CiA 401 V2.1

# 11.3 CANopen IO-X3, digital output module 24DO DC 24V

## Order No. and options

3001002     CANopen IO-X3  
                 galvanic isolated CAN

## Properties

- 24 digital outputs 24VDC/500mA, transistor, high side switch, short circuit protected
- CANopen device according to CiA 401 V2.1
- 24 LEDs for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Jumper
- Separated power supply pin for supply of digital output groups (see Section 2.3)

## Module pinout

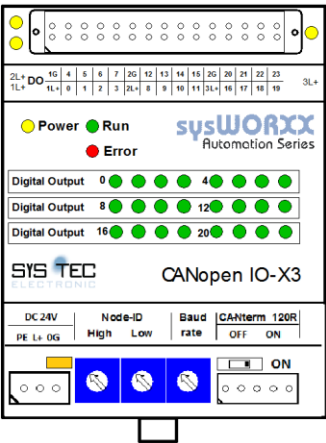


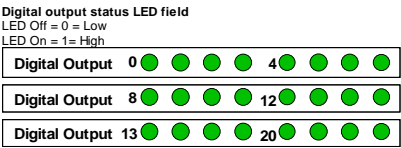
Figure 33: CANopen IO-X3 device schema

Pin	Name	Description
<b>Power supply connector</b>		
1	PE	
2	L+	+24VDC $\pm 20\%$
3	0G	Ground 0 for device power supply
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+
<b>I/O connector</b>		
1*	1L+	+24VDC for digital output 00 to 07 (optional connection to L+)
2	1G	Ground 1 for digital output 00 ... 07
3	0	digital output 0
4	4	digital output 4
5	1	digital output 1
6	5	digital output 5
7	2	digital output 2
8	6	digital output 6
9	3	digital output 3
10	7	digital output 7
11	2L+	+24VDC for digital output 8 to 15 ( )
12	2G	Ground 2 for digital output 8 to 15
13	8	digital output 8
14	12	digital output 12
15	9	digital output 9
16	13	digital output 13
17	10	digital output 10
18	14	digital output 14
19	11	digital output 11
20	15	digital output 15
21	3L+	+24VDC for digital output 16 to 23 ( )

Pin	Name	Description
22	3G	Ground 3 for digital output 16 to 23
23	16	digital output 16
24	20	digital output 20
25	17	digital output 17
26	21	digital output 21
27	18	digital output 18
28	22	digital output 22
28	19	digital output 19
30	23	digital output 23

Table 77: CANopen IO-X3 device pinout

LED display



Block diagram

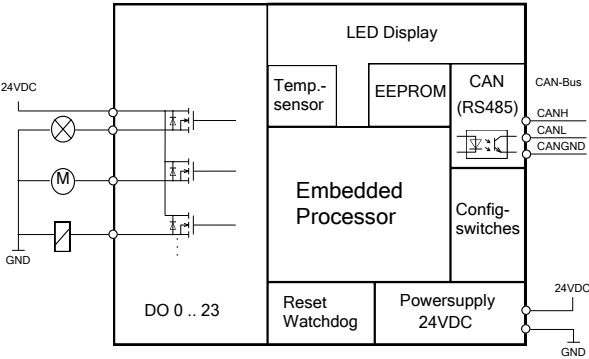


Figure 34: CANopen IO-X3 block diagram



**Technical data**

Common		Typical	Maximum
Power supply	V <sub>CPU</sub>	24V DC	±20%
	V <sub>IO</sub>	24V DC	±20%
Current consumption (I/Os inactive)	I <sub>CPU</sub>	0,05A	
	I <sub>IO</sub>	0,01A	
Temperature range	Storage		-20° ... +90°C
	Operation		-20° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	
Connection scheme	Removable spring-type clamp connectors		

Table 78: CANopen IO-X3 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 79: CANopen IO-X3 technical data part communication

I/O		Minimum	Maximum
<b>Digital outputs DO0..23</b>			
24V DC output, high-side switch	$U_{OH}$ at $I_{OH} = 500\text{mA}$	$V_{IO-0}, 16\text{V} < U_{OH} < V_{IO}$	
	$U_{OL}$ at $I_{OL} = 0\text{mA}$		0.5V
	Current limitation $I_{OH\_max}$	2,8A	
	Maximum current per group (Polyswitch protected)		4A (at 20°C)
	$I_{OL(off)}$		10μA
	$t_{off}$ at $I_{OH} = 500\text{ mA}$	115μs	190μs
	$t_{on}$ at $I_{OH} = 500\text{ mA}$	75μs	125μs

Table 80: CANopen IO-X3 technical data part I/O

### Manufacturer specific functions

The CANopen IO-X3 has no device specific manufacturer extensions.  
The generic manufacturer specific extensions are described in *Section 8.4*.

### Error behavior

In addition to the error behavior described with *Section 9.4* the CANopen IO-X3 features a device specific error behavior for its digital outputs with the following parameters:

- Error Mode Output 8-Bit
- Error Value Output 8-Bit
- Filter Constant Output 8-Bit

### Object dictionary

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
<b>6200H</b>	<b>Array</b>	<b>Write Output 8-Bit</b>	<b>Unsigned8</b>	<b>x</b>	<b>-</b>	<b>-</b>
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7	Unsigned8			
<b>6206H</b>	<b>Array</b>	<b>Error Mode Output 8-Bit</b>	<b>Unsigned8</b>	<b>-</b>	<b>x</b>	<b>X</b>
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_ErrorMode	Unsigned8			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restored
<b>6207H</b>	<b>Array</b>	<b>Error Value Output 8-Bit</b>	<b>Unsigned8</b>	<b>-</b>	<b>x</b>	<b>x</b>
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_ErrorValue	Unsigned8			
<b>6208H</b>	<b>Array</b>	<b>Filter Constant Output 8-Bit</b>	<b>Unsigned8</b>	<b>-</b>	<b>x</b>	<b>x</b>
	00H	Number of Output 8-Bit	Unsigned8			
	01H	DO0_DO7_FilterConstant	Unsigned8			

Table 81: CANopen IO-X3 Object Dictionary (Device specific part)

### Parameter description

Parameter	Description
<b>Error mode output 8-Bit</b>	<p>Specifies whether an output is set to its pre-defined error value (<i>see Object 6207H</i>) in case of an error event(<i>see Section 9.4</i>).</p> <p>0 = output value not changed  1 = output value switch to the state specified in Object 6207H</p> <p>Default value: 00H</p>
<b>Error value output 8-Bit</b>	<p>Specifies the error value for a group of 8 outputs.</p> <p>0 = output shall be set to '0' in case of error event  1 = output shall be set to '1' in case of error event</p> <p>Default value: 00H</p>
<b>Filter Constant output 8-Bit</b>	<p>Specifies an output filter mask for a group of 8 outputs.</p> <p>0     Updating of outputs disabled. The current value is not updated on reception of new output data.</p> <p>1     Updating of outputs enabled upon reception of new output data.</p> <p>Default value: FFH</p>

Table 82: CANopen IO-X3 parameter description

**Default mapping of I/O**

PDO	RPDO1
COB-ID	200H+node-ID
Mapped objects	3
Mapped obj 1 (data byte 0)	DO0_7 6200H/01H/08H <sup>1</sup>
Mapped obj.2 (data byte 1)	DO8_15 6200H/02H/08H
Mapped obj.3 (data byte 2)	DO16_23 6200H/03H/08H

Table 83: CANopen IO-X3 default mapping

**Device specific commissioning**

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Enable updating of used channels (Object 6208H)

If the application requires pre-defined error values for the outputs:

- (2) Configure the error value of the outputs (Object 6207H)
- (3) Enable the error mode of the channels (Object 6206H)

**Accessory**

Order number	Part
171024 171054	3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171034	30-pin I/O connector plug
180134	1 jumper for the CAN bus termination

Table 84: Accessory for CANopen IO-X3

---

<sup>1</sup> A mapping entry consists of: Object/Subindex/Datasize of mapped data

## References

CiA 303-1 V1.3

CiA 303-3 V1.2

CiA 301 V4.02

CiA 401 V2.1

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# 12 Analog I/O modules

## 12.1 CANopen IO-X4, analog input module 8AI U/I

### Order No. and options

3001003    CANopen IO-X4  
galvanic isolated CAN, 12-bit ADC

### Properties

- 8 analog input separately configurable for voltage or current measurement, differential measurement
- CANopen device according to CiA 404 V1.2
- LED for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Switch

### Module pinout

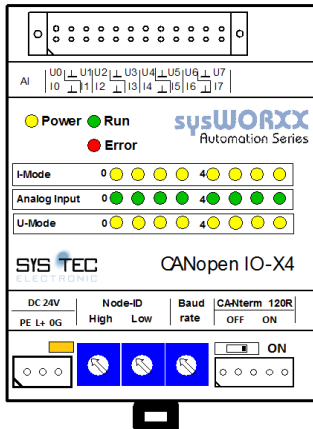


Figure 35: CANopen IO-X4 device schema

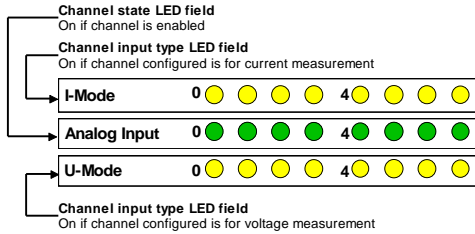
Pin	Name	Description
<b>Power supply connector</b>		
1	L+ PE	
2	0G L+	+24VDC ±20%

Pin	Name	Description
3	0G	Ground 0 for device power supply
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+
<b>I/O connector</b>		
1*	I0	Current input 0
2	U0	Voltage input 0
3	GND	GND channel 0
4	GND	GND channel 1
5	I1	Current input 1
6	U1	Voltage input 1
7	I2	Current input 2
8	U2	Voltage input 2
9	GND	GND channel 2
10	GND	GND channel 3
11	I3	Current input 3
12	U3	Voltage input 3
13	I4	Current input 4
14	U4	Voltage input 4
15	GND	GND channel 4
16	GND	GND channel 5
17	I5	Current input 5
18	U5	Voltage input 5
19	I6	Current input 6
20	U6	Voltage input 6
21	GND	GND channel 6
22	GND	GND channel 7
23	I7	Current input 7
24	U7	Voltage input 7

Table 85: CANopen IO-X4 device pinout



## LED display



## Block diagram

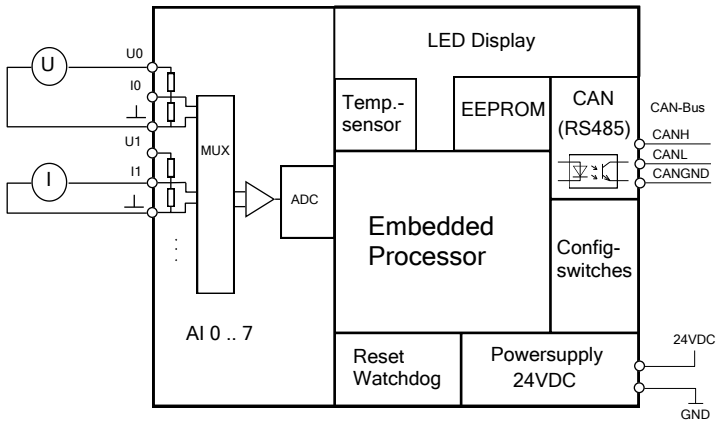


Figure 36: CANopen IO-X4 block diagram

## Technical data

Common		Typical	Maximum
Power supply	$V_{CPU}$	24V DC	$\pm 20\%$
Current consumption (I/Os inactive)	$I_{CPU}$	0,05A	
Temperature range	Storage		$-20^{\circ} \dots +90^{\circ}C$
	Operation		$-20^{\circ} \dots +70^{\circ}C$
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	

Common	Typical	Maximum
Connection scheme	Removable spring-type clamp connectors	

Table 86: CANopen IO-X4 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 87: CANopen IO-X4 technical data part communication

I/O		Minimum	Maximum
<b>Analog inputs AI0..7</b>			
U-Mode (voltage input)	Input range	-10V	+10V
	Input-Resistance		62kΩ
	Offset error		0,3%
I-Mode (current input)	Input range	0mA	20mA
	Input resistance		120Ω
	Offset error		0,3%
Common	Accuracy		0,5%
	ADC solution	16 Bit	
	Sampling rate <sup>1</sup>	12,5Hz (8ch)	100Hz (1ch)

Table 88: CANopen IO-X4 technical data part I/O

<sup>1</sup> The sampling rate decreases with the number of inputs enabled.

## Manufacturer specific functions

The CANopen IO-X4 supports the following device specific manufacturer extension:

- **for Production only** (Object 2500H)

The generic manufacturer specific extensions are described in *Section 8.4*.

## Error behavior

The CANopen IO-X4 has no device specific error behavior. Please refer to *Section 9.4* for configuration of error behavior on communication errors.

## Object dictionary

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
2500H	Array	for Production only		-		
	00H	Number Of Entries	Unsigned8			
	01H	reserved	Unsigned32			
	02H	manufacture date	Unsigned32			
	03H	calibration data	Unsigned32			
	04H	pAI_0_U_Gain	Real32			
	05H	pAI_0_U_Offset	Real32			
	06H	pAI_1_U_Gain	Real32			
	07H	pAI_1_U_Offset	Real32			
	...					
	12H	pAI_7_U_Gain	Real32			
	13H	pAI_7_U_Offset	Real32			
	14H	pAI_0_I_Gain	Real32			
	15H	pAI_0_I_Offset	Real32			
	...					
	22H	pAI_7_I_Gain	Real32			
	23H	pAI_7_I_Offset	Real32			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
	24H	reserved	Unsigned8			
	25H	reserved	Unsigned8			
	26H	reserved	Unsigned8			
<b>6110H</b>	<b>Array</b>	<b>AI Sensor Type</b>	<b>Unsigned16</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Sensor_Type	Unsigned16			
	...					
	07H	AI7_Sensor_Type	Unsigned16			
<b>6112H</b>	<b>Array</b>	<b>AI Operation mode</b>	<b>Unsigned8</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Operation_Mode	Unsigned8			
	...					
	07H	AI7_Operation_Mode	Unsigned8			
<b>6126H</b>	<b>Array</b>	<b>AI Scaling Factor</b>	<b>Unsigned8</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI Scaling Factor 0	Real32			
	...					
	07H	AI Scaling Factor 7	Real32			
<b>6127H</b>	<b>Array</b>	<b>AI Scaling Offset</b>	<b>Unsigned8</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI Scaling Offset 0	Real32			
	...					
	07H	AI Scaling Offset 7	Real32			
<b>6131H</b>	<b>Array</b>	<b>AI Physical Unit PV</b>	<b>Unsigned32</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Physical_Unit_PV	Unsigned32			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
	...					
	07H	AI7_Physical_Unit_PV	Unsigned32			
<b>6132H</b>	<b>Array</b>	<b>AI Decimal Digits PV</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Decimal_Digits_PV	Unsigned8			
	...					
	07H	AI7_Decimal_Digits_PV	Unsigned8			
<b>6150H</b>	<b>Array</b>	<b>AI Status</b>	<b>Unsigned8</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Status	Unsigned8			
	...					
	07H	AI7_Status	Unsigned8			
<b>7100H</b>	<b>Array</b>	<b>AI Input FV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_FV	Integer16			
	...					
	07H	AI7_Input_FV	Integer16			
<b>7130H</b>	<b>Array</b>	<b>AI Input PV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_PV	Integer16			
	...					
	07H	AI7_Input_PV	Integer16			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
7133H	Array	AI Interrupt delta Input PV	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Delta_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Delta_Input_PV	Integer16			

Table 89: CANopen IO-X4 Object Dictionary

### Parameter description

Parameter	Description
AI Sensor Type	<p>This parameter specifies the input type/range of the channel.</p> <p>41<sub>dec</sub> = input type <math>\pm 10V</math> (U-mode)  42<sub>dec</sub> = input type 0..10V (U-mode)  51<sub>dec</sub> = input type 4..20mA (I-mode)  52<sub>dec</sub> = input type 0..20mA (I-mode)</p> <p>Default value: 41<sub>dec</sub></p> <hr/> <p><b>Note</b></p> <p>Each channel has separated I/O points for connection of voltage input and current inputs.</p>
AI Operation mode	<p>Enables/disables an input channel.</p> <p>0 = Channel disabled  1 = Channel enabled (operating)</p> <p>Default value: 00H</p> <hr/> <p><b>Note</b></p> <p>Each operating channel (order not important) will reduce the maximum sampling rate by apx.1/8.</p>
AI Physical Unit PV	<p>This parameter assigns SI units and prefixes for the process values of each channel. The coding of the physical unit and prefixes is done according to the CiA 303-2. This value just provides additional information and has no influence on process value calculation.</p> <p>Possible values:</p> <p>00260000H = V</p>

Parameter	Description
	FD040000H = mA Default value: 00260000H
AI Decimal Digits PV	<p>This parameter specifies the number of decimal digits following the decimal point for interpretation of data type Integer16.</p> <p>Example :</p> <p>A process value of 1.234 V will be coded as 123 in Integer16 format if the number of decimal digits is set to 2.</p> <p>0 = no decimal digits 1 = one decimal digits 2 = two decimal digits 3 = three decimal digits</p> <p>Default value: 02H</p>
AI Status	<p>This read only parameter holds the status of the analog input channel.</p> <p>0 = no error 1 = measurement range underflow 2 = measurement range exceeded</p>
AI Interrupt delta input PV	<p>Specifies a "delta" value for triggering PDO transmission for an analog input channel.</p> <p>If the process value has changed for "delta" or more since the last transmission of the PDO, then the PDO is transmitted again.</p> <p>To disable this function set delta to 0.</p> <p>Default value: 00H (disabled)</p> <div> <p><b>Note</b></p> <p>The entered value must have the same physical unit and number of digits as configured for the respective channel.</p> </div>
AI Input FV	This object contains the field value (before scaling and calibration).
AI Input PV	This object contains the process value (after scaling).
manufacture date	<p>This object contains the manufacture date. The object is "read only"</p> <p>01112007H means 1<sup>st</sup> November 2007</p>
calibration date	<p>This object contains the date of the last calibration. The object is "read only".</p> <p>12112007H means 12<sup>th</sup> November 2007</p>

Parameter	Description
AI Scaling Factor	The Value "Factor" is multiply with the Processvalue.
AI Scaling Offset	The Value "Offset" is add to the Processvalue. see below

Table 90: CANopen IO-X4 parameter description

### Default mapping of I/O

PDO	TPDO1	TPDO2	TPDO3	TPDO4
COB-ID	180H+ node-ID	280H+ node-ID	380H+ node-ID	480H+ node-ID
<b>Mapped objects</b>	4	4	4	4
<b>Mapped object 1 (data byte 0+1)</b>	AI0 7130H /01H/10H <sup>1</sup>	AI2 7130H /03H/10H	AI4 7130H /05H/10H	AI6 7130H /07H/10H
<b>Mapped object 2 (data byte 2)</b>	AI0 State 6150H /01H/08H	AI2 State 6150H /03H/08H	AI4 State 6150H /05H/08H	AI6 State 6150H /07H/08H
<b>Mapped object 3 (data byte 3+4)</b>	AI1 7130H /02H/10H	AI3 7130H /04H/10H	AI5 7130H /06H/10H	AI7 7130H /08H/10H
<b>Mapped object 4 (data byte 5)</b>	AI1 State 6150H /02H/08H	AI3 State 6150H /04H/08H	AI5 State 6150H /06H/08H	AI7 State 6150H /08H/08H

Table 91: CANopen IO-X4 default mapping

### Relation between Fieldvalue (FV), Processvalue (PV) and Calibration

U-mode:

$$PV_{bc} = FV * 6,947 * 10^{-4}$$

$$PV = (PV_{bc} * pAI\_x\_U\_Gain + pAI\_x\_U\_Offset) * AI \text{ Scaling Factor}_x + AI \text{ Scaling Offset}_x$$

I-mode:

$$PV_{bc} = FV * 7,825 * 10^{-7}$$

$$PV = (PV_{bc} * pAI\_x\_I\_Gain + pAI\_x\_I\_Offset) * AI \text{ Scaling Factor}_x + AI \text{ Scaling Offset}_x$$

<sup>1</sup> A mapping entry consists of: Object/Subindex/Datasize of mapped data



“x” means number of AI channel

### Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, etc.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Configure the input type of each channel (Object 6110H).
- (2) Configure the number of digits used for calculation and presentation of the process value (Object 6132H) in Integer16.
- (3) Set the physical unit of each channel (Object 6131H).
- (4) If delta-triggered transmission of process values is needed configure the “delta” value of each channel (Object 7133).
- (5) Enable the channels in use (Object 6112H).

### Accessory

Order number	Part
171024 171054	2 3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171038	24-pin I/O connector plug
180134	Jumper for CAN-bus termination

Table 92: Accessory for CANopen IO-X4

### References

CiA 303-1 V1.3

CiA 303-3 V1.2

CiA 301 V4.02

CiA 404 V1.2

# 12.2 CANopen IO-X5, analog input module 8RTD

## Order No. and options

3001004     CANopen IO-X5  
                 galvanic isolated CAN, 12-bit ADC

## Properties

- 8 analog input suitable for resistor temperature devices (RTD) (e.g. PT100 or PT1000) in 2- or 3-wire connection scheme
- CANopen device according to CiA 404 V1.2
- LED for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Switch

## Module pinout

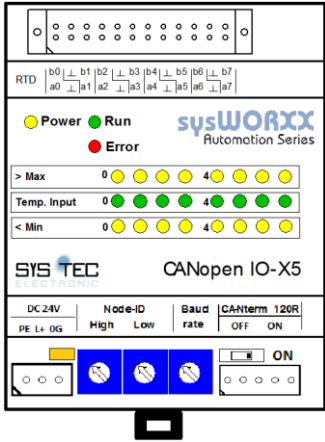


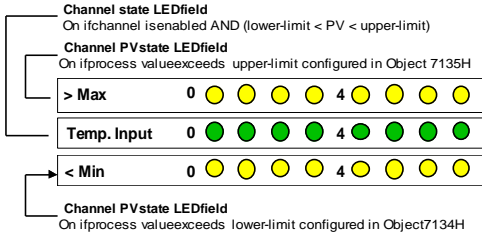
Figure 37: CANopen IO-X5 device schema

Pin	Name	Description
Power supply connector		
1	PE	
2	L+	+24VDC ±20%

Pin	Name	Description
	0G	Ground 0 for device power supply
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+
<b>I/O connector</b>		
1*	a0	RTD input a0
2	b0	RTD input b0
3	GND	GND RTD input 0
4	GND	GND RTD input 1
5	a1	RTD input a1
6	b1	RTD input b1
7	a2	RTD input a2
8	b2	RTD input b2
9	GND	GND RTD input 2
10	GND	GND RTD input 3
11	a3	RTD input a3
12	b3	RTD input b3
13	a4	RTD input a4
14	b4	RTD input b4
15	GND	GND RTD input 4
16	GND	GND RTD input 5
17	a5	RTD input a5
18	b5	RTD input b5
19	a6	RTD input a6
20	b6	RTD input b6
21	GND	GND RTD input 6
22	GND	GND RTD input 7
23	a7	RTD input a7
24	b7	RTD input b7

Table 93: CANopen IO-X5 device pinout

LED display



Condition	LED states	EMCY trigger
PV > Upper Limit PV	Yellow ">MAX" state LED (upper) on	no
Short Circuit (PV < Sensor Range Limit)	Yellow ">MAX" state LED (upper) blinking	yes
Channel enabled	Green <i>Temp. Input</i> LED on	No
PV < Lower Limit PV	Yellow "<MIN" state LED (lower) on	No
Sensor Fraction (PV > Sensor Range Limit)	Yellow "<MIN" state LED (lower) blinking	Yes

Table 94: Device specific LED states for CANopen IO-X5

## Block diagram

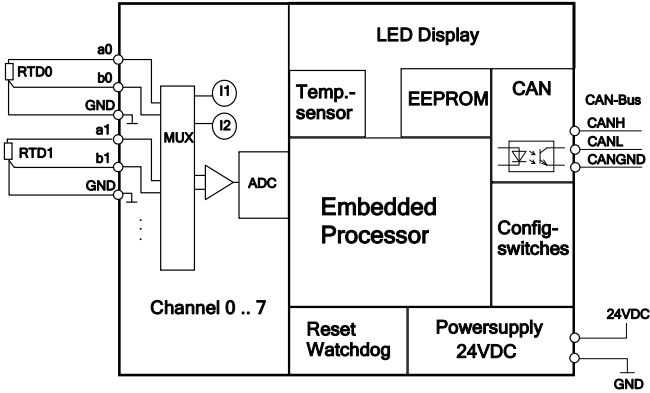


Figure 38: CANopen IO-X5 block diagram (3-wire connection)

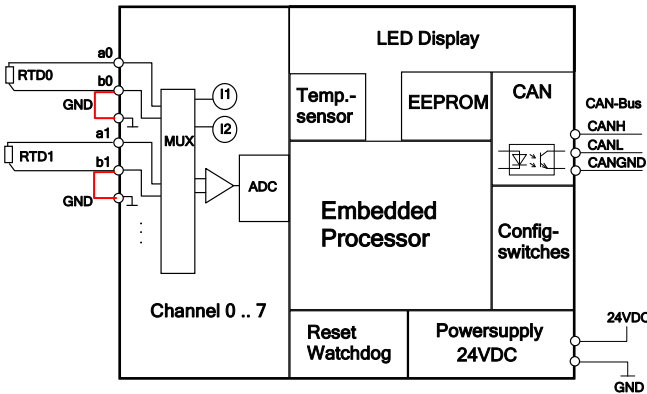


Figure 39: CANopen IO-X5 block diagram (2-wire connection)

## Technical data

Common		Typical	Maximum
Power supply	$V_{CPU}$	24V DC	$\pm 20\%$
Current consumption (I/Os inactive)	$I_{CPU}$	0,05A	
Temperature range	Storage		$-20^{\circ} \dots +90^{\circ}C$

Common		Typical	Maximum
	Operation		-20° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	
Connection scheme	Removable spring-type clamp connectors		

Table 95: CANopen IO-X5 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 96: CANopen IO-X5 technical data part communication

I/O	Minimum	Maximum
<b>RTD input Ch0..Ch7</b>		
Temperature range (sensor independent)	-200°C	+600°C
	73,2 K	873,2 K
	-328,0°F	1112,0°F
ADC solution	12-bit (optional 14-bit)	
Accuracy	0,5% PE (at 12-bit)	
Resolution PV		0,1K
Sampling rate <sup>1</sup>	12,5Hz (8ch)	100Hz (1ch)

Table 97: CANopen IO-X5 technical data part I/O

## Manufacturer specific functions

The CANopen IO-X5 supports the following device specific manufacturer extension:

<sup>1</sup> The sampling rate decreases with the number of inputs enabled.

- **for Production only** (Object 2500H)

The generic manufacturer specific extensions are described in *Section 8.4*.

### Error behavior

The CANopen IO-X5 has no device specific error behavior. Please refer to *Section 9.4* for configuration of error behavior on communication errors.

If an input channel is switched on without a sensor connected, the module will indicate this by setting the channel's AI Status in Object 6150H to value 01H.

### Object dictionary

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
2500H	Array	<b>for Production only</b>		-		
	00H	Number Of Entries	Unsigned8			
	01H	Reserved	Unsigned32			
	02H	manufacture date	Unsigned32			
	03H	calibration data	Unsigned32			
	04H	pGain_PT100_0	Real32			
	05H	pOffset_PT100_0	Real32			
	06H	pGain_PT100_1	Real32			
	07H	pOffset_PT100_1	Real32			
	...					
	12H	pGain_PT100_7	Real32			
	13H	pOffset_PT100_7	Real32			
	14H	pGain_PT1000_0	Real32			
	15H	pOffset_PT1000_0	Real32			
	...					
	22H	pGain_PT1000_7	Real32			
	23H	pOffset_PT1000_7	Real32			
	24H	Reserved	Unsigned8			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
	25H	Reserved	Unsigned8			
	26H	Reserved	Unsigned8			
<b>6110H</b>	<b>Array</b>	<b>AI Sensor Type</b>	<b>Unsigned16</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Sensor_Type	Unsigned16			
	...					
	07H	AI7_Sensor_Type	Unsigned16			
<b>6110H</b>	<b>Array</b>	<b>AI Sensor Type</b>	<b>Unsigned16</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Sensor_Type	Unsigned16			
	...					
	07H	AI7_Sensor_Type	Unsigned16			



Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
<b>6112H</b>	<b>Array</b>	<b>AI Operation mode</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Operation_Mode	Unsigned8			
	...					
	07H	AI7_Operation_Mode	Unsigned8			
<b>6126H</b>	<b>Array</b>	<b>AI Scaling Factor</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI Scaling Factor 0	Real32			
	...					
	07H	AI Scaling Factor 1	Real32			
<b>6127H</b>	<b>Array</b>	<b>AI Scaling Offset</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI Scaling Offset 0	Real32			
	...					
	07H	AI Scaling Offset 1	Real32			
<b>6131H</b>	<b>Array</b>	<b>AI Physical Unit PV</b>	<b>Unsigned32</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Physical_Unit_PV	Unsigned32			
	...					
	07H	AI7_Physical_Unit_PV	Unsigned32			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
<b>6132H</b>	<b>Array</b>	<b>AI Decimal Digits PV</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Decimal_Digits_PV	Unsigned8			
	...					
	07H	AI7_Decimal_Digits_PV	Unsigned8			
<b>6150H</b>	<b>Array</b>	<b>AI Status</b>	<b>Unsigned8</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Status	Unsigned8			
	...					
	07H	AI7_Status	Unsigned8			
<b>7100H</b>	<b>Array</b>	<b>AI Input FV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_FV	Integer16			
	...					
	07H	AI7_Input_FV	Integer16			
<b>7130H</b>	<b>Array</b>	<b>AI Input PV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_PV	Integer16			
	...					
	07H	AI7_Input_PV	Integer16			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
7133H	Array	<b>AI Interrupt delta Input PV</b>	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Delta_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Delta_Input_PV	Integer16			
7134H	Array	<b>AI Interrupt lower limit Input PV</b>	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Lower_Limit_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Lower_Limit_Input_PV	Integer16			
7135H	Array	<b>AI Interrupt upper limit Input PV</b>	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Upper_Limit_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Upper_Limit_Input_PV	Integer16			

Table 98: CANopen IO-X5 Object Dictionary

### Parameter description

Parameter	Description
AI Sensor Type	<p>This parameter specifies the type of sensor, which is connected to the analog input.</p> <p>30<sub>dec</sub> = PT100  33<sub>dec</sub> = PT1000  Default value: 30<sub>dec</sub></p>

Parameter	Description
AI Operation mode	<p>Enables/disables an input channel</p> <p>0 = Channel disabled 1 = Channel enabled (operating)</p> <p>Default value: 0H</p> <hr/> <p><b>Note</b></p> <p>Each active channel (the order is not important) will reduce the maximum sampling rate by apx.1/8.</p>
AI Physical Unit PV	<p>This parameter assigns SI units and prefixes for the process values of each channel. The coding of the physical unit and prefixes is done according to the CiA 303-2. This value just provides additional information and has no influence on process value calculation.</p> <p>Possible values:</p> <p>00050000H = K 002D0000H = °C 00AC0000H = °F</p> <p>Default value: 002D0000H (°C)</p>
AI Decimal Digits PV	<p>This parameter specifies the number of decimal digits following the decimal point for interpretation of data type Integer16.</p> <p>Example :</p> <p>A process value of 98.2°C will be coded as 982<sub>dec</sub> in Integer16 format if the number of decimal digits is set to 1 and 98<sub>dec</sub> if number of decimal digits is set to 0.</p> <p>0 = no decimal digits 1 = one decimal digits</p> <p>Default value: 1</p>
AI Status	<p>This read only parameter holds the status of the analog input channel.</p> <p>0 = no error 1 = input not valid (e.g. sensor break, short circuit, underflow)</p>

Parameter	Description								
AI Interrupt delta input PV	<p>Specifies a "delta" value for triggering PDO transmission for an analog input channel.</p> <p>If the process value has changed for "delta" or more since the last transmission of the PDO, then the PDO is transmitted again.</p> <p>To disable this function set delta to 0.</p> <p>Default value: 10<sub>dec</sub> (corresponds to 1,0°C under default settings)</p> <p><b>Note</b></p> <p>The entered value must have the same physical unit and number of digits as configured for the respective channel.</p>								
AI interrupt lower limit input PV	<p>This parameter sets the lower limit for triggering PDO transmission of an analog input channel. If the PV goes below this value, the corresponding LED on the LED display (&lt; MIN) is switched on. Is the process value between the minimal and maximal value, no PDO is transmitted.</p> <p>The Temperature range is defined as followed:</p> <table border="1"> <thead> <tr> <th>Minimum</th><th>Maximum</th></tr> </thead> <tbody> <tr> <td>-200,0°C</td><td>+600,0°C</td></tr> <tr> <td>73,2 K</td><td>873,2 K</td></tr> <tr> <td>-328,0°F</td><td>1112,0°F</td></tr> </tbody> </table> <p>Example : A value of 50,5°C will be coded as 505 in Integer16 format if the number of decimal digits is set to 1.</p> <p>Default value: -200°C</p>	Minimum	Maximum	-200,0°C	+600,0°C	73,2 K	873,2 K	-328,0°F	1112,0°F
Minimum	Maximum								
-200,0°C	+600,0°C								
73,2 K	873,2 K								
-328,0°F	1112,0°F								
AI interrupt upper limit input PV	<p>This parameter sets the upper limit for triggering PDO transmission of an analog input channel. If the PV exceeds this value, the corresponding LED on the LED display (&gt; MAX) is switched on. Is the process value between the minimal and maximal value, no PDO is transmitted.</p> <p>The Temperature range is defined as followed:</p> <table border="1"> <thead> <tr> <th>Minimum</th><th>Maximum</th></tr> </thead> <tbody> <tr> <td>-200,0°C</td><td>+600,0°C</td></tr> <tr> <td>73,2 K</td><td>873,2 K</td></tr> <tr> <td>-328,0°F</td><td>1112,0°F</td></tr> </tbody> </table> <p>Example : A value of 328,5°C will be coded as 3285 in Integer16 format if the number of decimal digits is</p>	Minimum	Maximum	-200,0°C	+600,0°C	73,2 K	873,2 K	-328,0°F	1112,0°F
Minimum	Maximum								
-200,0°C	+600,0°C								
73,2 K	873,2 K								
-328,0°F	1112,0°F								

Parameter	Description
	set to 1. Default value: -200°C
AI Input FV	This object contains the field value (before scaling and calibration).
AI Input PV	This object contains the process value (after scaling).
manufacture date	This object contains the manufacture date. The object is "read only" e.g.: 01112007H means 1 <sup>st</sup> November 2007
calibration date	This object contains the date of the last calibration. The object is "read only". e.g.: 12112007H means 12 <sup>th</sup> November 2007
AI Scaling Factor AI Scaling Offset	The Value "Factor" is multiply with the Processvalue. The Value "Offset" is add to the Processvalue. see below

Table 99: CANopen IO-X5 parameter description

## Default mapping of I/O

PDO	TPDO1	TPDO2	TPDO3	TPDO4
COB-ID	180H+ node-ID	280H+ node-ID	380H+ node-ID	480H+ node-ID
<b>Mapped objects</b>	4	4	4	4
<b>Mapped object 1 (data byte 0+1)</b>	AI0 7130H /01H/10H <sup>1</sup>	AI2 7130H /03H/10H	AI4 7130H /05H/10H	AI6 7130H /07H/10H
<b>Mapped object 2 (data byte 2)</b>	AI0 State 6150H /01H/08H	AI2 State 6150H /03H/08H	AI4 State 6150H /05H/08H	AI6 State 6150H /07H/08H
<b>Mapped object 3 (data byte 3+4)</b>	AI1 7130H /02H/10H	AI3 7130H /04H/10H	AI5 7130H /06H/10H	AI7 7130H /08H/10H
<b>Mapped object 4 (data byte 5)</b>	AI1 State 6150H /02H/08H	AI3 State 6150H /04H/08H	AI5 State 6150H /06H/08H	AI7 State 6150H /08H/08H

Table 100: CANopen IO-X5 default mapping

<sup>1</sup> A mapping entry consists of: Object/Subindex/Datasize of mapped data

## Relation between Fieldvalue (FV), Processvalue (PV) and Calibration

PT100:

$$R_{Tbc} = FV * 1,4532 * 10^{-2}$$

$$R = (R_{Tbc} * pGain\_PT1000\_x + pOffset\_PT1000\_x) \\ * AI \text{ Scaling Factor\_}x + AI \text{ Scaling Offset\_}x$$

PT1000:

$$R_{Tbc} = FV * 1,3796 * 10^{-1}$$

$$R = (R_{Tbc} * pGain\_PT100\_x + pOffset\_PT100\_x) \\ * AI \text{ Scaling Factor\_}x + AI \text{ Scaling Offset\_}x$$

“x” means number of AI channel

The calculation of PV is according to DIN IEC 60751.

## Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Configure the input/sensor type of each channel (Object 6110H).
- (2) Configure the number of digits used for the process value (Object 6132H).
- (3) Set the physical unit of each channel (Object 6131H).
- (4) Configure the “delta” value of each channel (Object 7133).
- (5) Configure the upper and lower limit of each channel (Object 7134H and 7135H)
- (6) Enable the channels in use (Object 6112H).

## Accessory

Order number	Part
171024 171054	3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171038	24-pin I/O connector plug
180134	Jumper for the CAN bus termination

Table 101: Accessory for CANopen IO-X5

## References

CiA 303-1 V1.3

CiA 303-3 V1.2

CiA 301 V4.02

CiA 404 V1.2



## 12.3 CANopen IO-X6, analog output module 8AO U/I

### Order No. and options

3001006    CANopen IO-X6  
galvanic isolated CAN, 10-bit DAC

### Properties

- 8 analog output, each configurable as current or voltage output
- CANopen device according to CiA 404 V1.2
- LED for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Jumper

### Module pinout

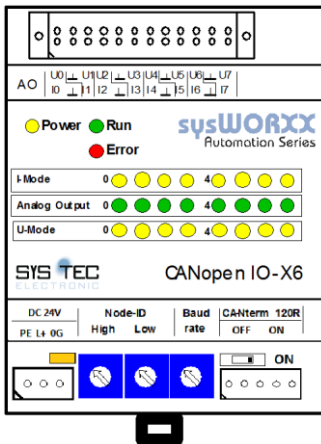


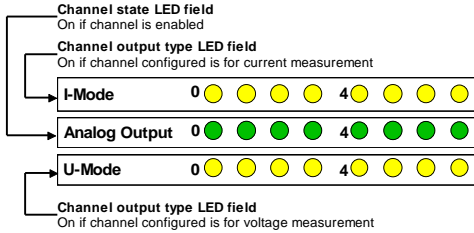
Figure 40: CANopen IO-X6 device schema

Pin	Name	Description
<b>Power supply connector</b>		
1	PE	
2	L+	+24VDC ±20%
3	0G	Ground 0 for device power supply

Pin	Name	Description
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+ (connected to L+ on modules without galvanic isolation, not used on modules with galvanic isolated CAN)
<b>I/O connector</b>		
1*	I0	Current output 0
2	U0	Voltage output 0
3	GND	GND channel 0
4	GND	GND channel 1
5	I1	Current output 1
6	U1	Voltage output 1
7	I2	Current output 2
8	U2	Voltage output 2
9	GND	GND channel 2
10	GND	GND channel 3
11	I3	Current output 3
12	U3	Voltage output 3
13	I4	Current output 4
14	U4	Voltage output 4
15	GND	GND channel 4
16	GND	GND channel 5
17	I5	Current output 5
18	U5	Voltage output 5
19	I6	Current output 6
20	U6	Voltage output 6
21	GND	GND channel 6
22	GND	GND channel 7
23	I7	Current output 7
24	U7	Voltage output 7

Table 102: CANopen IO-X6 device pinout

## LED display



## Block diagram

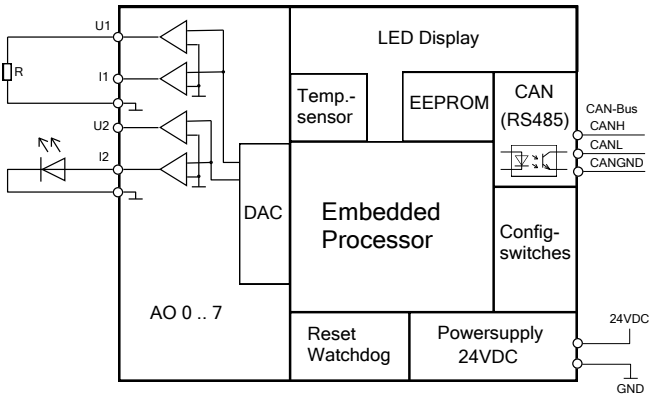


Figure 41: CANopen IO-X6 block diagram

## Technical data

Common		Typical	Maximum
Power supply	$V_{CPU}$	24V DC	±20%
Current consumption (I/Os inactive)	$I_{CPU}$	0,09A	
Temperature range	Storage		-20° ... +90°C
	Operation		-20° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	

Common	Typical	Maximum
Connection scheme	Removable spring-type clamp connectors	

Table 103: CANopen IO-X6 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 104: CANopen IO-X6 technical data part communication

I/O		Minimum	Maximum
<b>Analog outputs AO0 .. AO7</b>			
Voltage	Output range	0V	+10V
	Load Resistance	500Ω	
	DAC solution	10-bit (optional 12-bit)	
	Accuracy	0,5% (at 10-bit)	
	Zero-scale offset		120mV
	Settling time per channel		3μs
Current	Output range	0mA	+20mA
	Load Resistance	0Ω	500Ω
	DAC solution	10-bit (optional 12-bit)	
	Accuracy	0,5% (at 10-bit)	
	Zero-scale offset		0,3mA
	Settling time per channel		3μs

Table 105: CANopen IO-X6 technical data part I/O

## Manufacturer specific functions

The CANopen IO-X6 supports the following device specific manufacturer extension:

- **Channel Calibration** (Object 2400H)
- **for Production only** (Object 2500H)

The generic manufacturer specific extensions are described in *Section 8.4*.

### Error behavior

In addition to the error behavior described with *Section 9.4* the CANopen IO-X6 features a device specific error behavior for its analog outputs with the following parameters:

- AO Fault mode
- AO Fault FV

### Object dictionary

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
2400H	Array	<b>Channel Calibration</b>		-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Gain	Real32			
	02H	AO0_Offset	Real32			
	03H	AO1_Gain	Real32			
	04H	AO1_Offset	Real32			
	...					
	0FH	AO7_Gain	Real32			
2500H	Array	<b>for Production only</b>		-		
	00H	Number Of Entries	Unsigned8			
	01H	reserved	Unsigned32			
	02H	manufacture date	Unsigned32			
	03H	calibration data	Unsigned32			
	04H	pAO_0_U_Gain	Real32			
	05H	pAO_0_U_Offset	Real32			
	06H	pAO_1_U_Gain	Real32			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
	07H	pAO_1_U_Offset	Real32			
	...					
	12H	pAO_7_U_Gain	Real32			
	13H	pAO_7_U_Offset	Real32			
	14H	pAO_0_I_Gain	Real32			
	15H	pAO_0_I_Offset	Real32			
	...					
	22H	pAO_7_I_Gain	Real32			
	23H	pAO_7_I_Offset	Real32			
	24H	reserved	Unsigned8			
	25H	reserved	Unsigned8			
	26H	reserved	Unsigned8			
6301H	Array	AO Physical unit PV	Unsigned32	-	x	x
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Physical_Unit_PV	Unsigned32			
	...					
	07H	AO7_Physical_Unit_PV	Unsigned32			
6302H	Array	AO Decimal digits PV	Unsigned8	-	x	x
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Decimal_Digits_PV	Unsigned8			
	...					
	07H	AO7_Decimal_Digits_PV	Unsigned8			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
6310H	Array	AO Output Type	Unsigned16	-	x	x
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Output_Type	Unsigned16			
	...					
	07H	AO7_Output_Type	Unsigned16			
6340H	Array	AO Fault mode	Unsigned8	-	x	x
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Fault_Mode	Unsigned8			
	...					
	07H	AO7_Fault_Mode	Unsigned8			
7300H	Array	AO Output PV	Integer16	x	-	-
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Output_PV	Integer16			
	...					
	07H	AO7_Output_PV	Integer16			
7341H	Array	AO Fault FV	Integer16	-	x	x
	00H	Number Of Entries	Unsigned8			
	01H	AO0_Fault_Value	Integer16			
	...					
	07H	AO7_Fault_Value	Integer16			

Table 106: CANopen IO-X6 Object Dictionary

## Parameter description

Parameter	Description
AO Physical Unit PV	<p>This parameter assigns SI units and prefixes for the process values of each channel. The coding of the physical unit and prefixes is done according to the CiA 303-2. This value just provides additional information and has no influence on process value calculation.</p> <p>Possible values:</p> <p>00260000H = V FD040000H = mA</p> <p>Default value: 00260000H</p>
AO Decimal Digits PV	<p>Specifies the number of decimal digits following the decimal point for interpretation of data type Integer16.</p> <p>0 = no decimal digits 1 = one decimal digits 2 = two decimal digits 3 = three decimal digits (12-bit resolution only)</p> <p>Default value: 02H</p> <p>Example : A process value of 1.234 V will be coded as 123 in Integer16 format if the number of decimal digits is set to 2.</p>
AO Output type	<p>Specifies the analog output type.</p> <p>00<sub>dec</sub> = disabled 12<sub>dec</sub> = 0..10V 21<sub>dec</sub> = 4..20mA 23<sub>dec</sub> = 0..20mA</p> <p>Default value: 00<sub>dec</sub></p>
AO Fault mode	<p>Specifies whether an output is set to its pre-defined error value (see Object 6207H) in case of an error event (see Section 9.4).</p> <p>0 = output value reset 1 = output value shall take the pre-defined error value specified in Object 7341H</p>
AO Fault FV	<p>Specifies the value that an output channel shall be set to in case of an error event (see Section 9.4).</p> <p>You have to set as Fieldvalue: e.g. U-Mode, Faultvalue should set to 2VDC. <math>FV = 2V * 3048,09 = 6096</math> I-Mode, Faultvalue should set to 4mA. <math>FV = 4mA * 1310,68 = 5243</math></p>
AO Output PV	<p>This object holds the current process values.</p> <p>Values below or above limits according to the AO output</p>



Parameter	Description
	type are clipped to the limit value. e.g.: AO output mode 4...20mA, two decimal digits: an AO output PV of 200 results in an output value of 400
manufacture date	This object contains the manufacture date. The object is "read only" e.g.: 01112007H means 1 <sup>st</sup> November 2007
calibration date	This object contains the date of the last calibration. The object is "read only". e.g.: 12112007H means 12 <sup>th</sup> November 2007
Channel Calibration	Output Value ( $U_{out}$ or $I_{out}$ ) is the result of the following: The Value "Gain" is multiply with the Processvalue. The Value "Offset" is add to the Processvalue. see below

Table 107: CANopen IO-X6 parameter description

### Default mapping of I/O

PDO	RPDO1	RPDO1
COB-ID	200H+node-ID	300H+node-ID
<b>Mapped objects</b>	4	4
<b>Mapped object 1 (data byte 0+1)</b>	AO0_PV 7300H/01H/10H	AO4_PV 7300H/05H/10H
<b>Mapped object 2 (data byte 2+3)</b>	AO1_PV 7300H/02H/10H	AO5_PV 7300H/06H/10H
<b>Mapped object 3 (data byte 4+5)</b>	AO2_PV 7300H/03H/10H	AO6_PV 7300H/07H/10H
<b>Mapped object 4 (data byte 6+7)</b>	AO3_PV 7300H/04H/10H	AO7_PV 7300H/08H/10H

Table 108: CANopen IO-X6 default mapping

### Relation between Fieldvalue (FV), Processvalue (PV) and Calibration

U-mode:

$$FV_U = PV * 3048,09$$

$$U_{out} = (PV * pAO\_x\_U\_Gain + pAO\_x\_U\_Offset) * AOx\_Gain + AOx\_Offset$$

I-mode:

$$FV_I = PV * 1310,68$$

$$I_{out} = (PV * pAO\_x\_I\_Gain + pAO\_x\_I\_Offset) * AOx\_Gain + AOx\_Offset$$

“x” means number of AO channel

## Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Configure the output sensor type of each channel (Object 6310H).
- (2) Configure the number of digits used for the process value (Object 6302H).
- (3) Set the physical unit of each channel (Object 6301H).

If the application requires pre-defined error-values:

- (4) Configure the error value for each channel (Object 7341H).
- (5) Enable the fault mode for each channel that has an error value (Object 6340H)

## Accessory

Order number	Part
171024 171054	3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171038	24-pin I/O connector plug
180134	Jumper for the CAN bus termination

Table 109: Accessory for CANopen IO-X6

## References

CiA 303-1 V1.3  
 CiA 303-3 V1.2  
 CiA 301 V4.02  
 CiA 404 V1.2

## 12.4 CANopen IO-X7, analog input module 8TC

### Order No. and options

3001006	CANopen IO-X7 galvanic isolated CAN, 12-bit ADC
3001008	CANopen IO-X7 galvanic isolated CAN, 14-bit ADC

### Properties

- 8 analog input suitable for various types of thermocouple elements
- CANopen device according to CiA 404 V1.2
- LED for I/O state indication
- Galvanic isolated CAN-bus interface
- Non-volatile storage of configuration data
- Watchdog
- CAN bus termination (120Ω resistor) via Jumper

### Module pinout

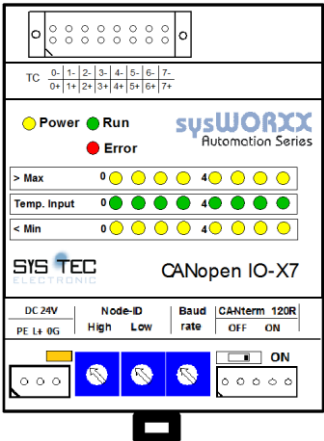


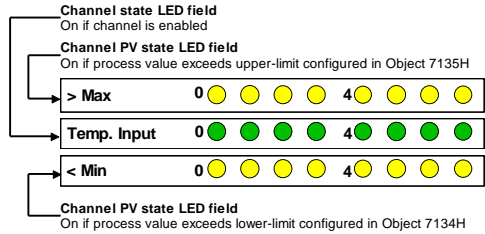
Figure 42: CANopen IO-X7 device schema

Pin	Name	Description
<b>Power supply connector</b>		
1*	PE	

Pin	Name	Description
2	L+	+24VDC $\pm 20\%$
3	0G	Ground 0 for device power supply
<b>CAN-bus interface connector</b>		
1*		CAN_GND
2		CAN_L
3		n.c.
4		CAN_H
5		CAN_V+ (connected to L+ on modules without galvanic isolation, not used on modules with galvanic isolated CAN)
<b>I/O connector</b>		
1*	0+	thermocouple input 0+
2	0-	thermocouple input 0-
3	1+	thermocouple input 1+
4	1-	thermocouple input 1-
5	2+	thermocouple input 2+
6	2-	thermocouple input 2-
7	3+	thermocouple input 3+
8	3-	thermocouple input 3-
9	4+	thermocouple input 4+
10	4-	thermocouple input 4-
11	5+	thermocouple input 5+
12	5-	thermocouple input 5-
13	6+	thermocouple input 6+
14	6-	thermocouple input 6-
15	7+	thermocouple input 7+
16	7-	thermocouple input 7-

Table 110: CANopen IO-X7 device pinout

LED display



Condition	LED states	EMCY trigger
PV > Upper Limit PV	Yellow ">MAX" state LED (upper) on	no
PV > Sensor Range Limit	Yellow ">MAX" state LED (upper) blinking	yes
Channel enabled	Green "Temp. Input" LED on	no
PV < Lower Limit PV	Yellow "<MIN" state LED (lower) on	no
Sensor Fraction (PV < own temperature)	Yellow "<MIN" state LED (lower) blinking	yes

Table 111: Device specific LED states for CANopen IO-X7

Block diagram

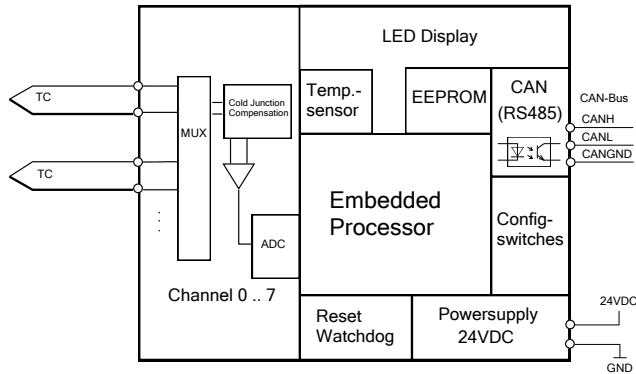


Figure 43: CANopen IO-X7 block diagram

**Technical data**

Common		Typical	Maximum
Power supply	V <sub>CPU</sub>	24V DC	±20%
Current consumption (I/Os inactive)	I <sub>CPU</sub>	0,07A	
Temperature range	Storage		-20° ... +90°C
	Operation		0° ... +70°C
Protection class	Enclosure	IP20	
Module weight		130g	
Dimensions	Width	71 mm	
	High	58 mm	
	Length	95 mm	
Connection scheme	Removable spring-type clamp connectors		

Table 112: CANopen IO-X7 technical data part common

Communication		Minimum	Maximum
CAN 2.0B (passive) compliant to CiA 120 and ISO 11898-2	bit rate	10kBit/s	1MBit/s
	number of nodes supported on same CAN-bus segment		110
	Isolation voltage <sup>1</sup>		1kV
	CAN_H and CAN_L, short-circuit proof towards 24V DC		
	High-speed CAN-bus transceiver compliant to ISO 11898		

Table 113: CANopen IO-X7 technical data part communication

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<sup>1</sup> Only on modules with galvanic isolated CAN-bus interface.

I/O		Minimum	Maximum
<b>Input Ch0 .. Ch7</b>			
Supported sensor types		J, K, L, R, S, T, E	
Input range for type E,J,K,L,T		0V	75mV
Input range for type R,S		0V	25mV
Temperature range for sensor type:	J	50°C	1200°C
	K	50°C	1372°C
	L	50°C	900°C
	R	50°C	1768°C
	S	50°C	1768°C
	T	50°C	400°C
	E	50°C	1000°C
Over voltage protection			5V
Sampling rate per channel		12,5Hz (8 channels)	100Hz (1 channel)
ADC solution		12-bit (optional 14-bit)	
Gain factor for type E,J,K,L,T		34,33	
Gain factor for type R,S		101	
Accuracy		≤ 0,5% (at 12-bit)	
Resolution PV			0,1K (at 12-bit)

Table 114: CANopen IO-X7 technical data part I/O

## Manufacturer specific functions

The CANopen IO-X7 supports the following device specific manufacturer extension:

- **for Production only** (Object 2500H)

The CANopen IO-X7 has no device specific manufacturer extensions. The generic manufacturer specific extensions are described in *Section 8.4*.

## Error behavior

The CANopen IO-X7 has no device specific error behavior. Please refer to *Section 9.4* for configuration of error behavior on communication errors.

If an input channel is switched on without a sensor connected (or sensor break), the module will indicate this by setting the corresponding Subindex of Object 6150H to value 01H.



## Object dictionary

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
<b>2500H</b>	<b>Array</b>	<b>for production only</b>		-	-	-
	00H	Number Of Entries	Unsigned8			
	01H	password	Unsigned32			
	02H	manufacture date	Unsigned32			
	03H	calibration date	Unsigned32			
	04H	AI_0_EJKLT_Gain	Real32			
	05H	AI_0_EJKLT_Offset	Real32			
	06H	AI_1_EJKLT_Gain	Real32			
	07H	AI_1_EJKLT_Offset	Real32			
	...					
	12H	AI_7_EJKLT_Gain	Real32			
	13H	AI_7_EJKLT_Offset	Real32			
	14H	AI_0_RS_Gain	Real32			
	15H	AI_0_RS_Offset	Real32			
	...					
	22H	AI_7_RS_Gain	Real32			
	23H	AI_7_RS_Offset	Real32			
	24H	reserved	Unsigned8			
	25H	reserved	Unsigned8			
	26H	reserved	Unsigned8			
<b>6110H</b>	<b>Array</b>	<b>AI Sensor Type</b>	<b>Unsigned16</b>	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Sensor_Type	Unsigned16			
	...					
	07H	AI7_Sensor_Type	Unsigned16			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
<b>6112H</b>	<b>Array</b>	<b>AI Operation mode</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Operation_Mode	Unsigned8			
	...					
	07H	AI7_Operation_Mode	Unsigned8			
<b>6126H</b>	<b>Array</b>	<b>AI Scaling Factor</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI_Scaling_Factor_0	Real32			
	...					
	07H	AI_Scaling_Factor_7	Real32			
<b>6127H</b>	<b>Array</b>	<b>AI Scaling Offset</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI_Scaling_Offset_0	Real32			
	...					
	07H	AI_Scaling_Offset_7	Real32			
<b>6131H</b>	<b>Array</b>	<b>AI Physical Unit PV</b>	<b>Unsigned32</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Physical_Unit_PV	Unsigned32			
	...					
	07H	AI7_Physical_Unit_PV	Unsigned32			

Object Index	Object type	Object name	Data type	Object mapable	Object stored	Object restore
<b>6132H</b>	<b>Array</b>	<b>AI Decimal Digits PV</b>	<b>Unsigned8</b>	<b>-</b>	<b>X</b>	<b>X</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Decimal_Digits_PV	Unsigned8			
	...					
	07H	AI7_Decimal_Digits_PV	Unsigned8			
<b>6150H</b>	<b>Array</b>	<b>AI Status</b>	<b>Unsigned8</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Status	Unsigned8			
	...					
	07H	AI7_Status	Unsigned8			
<b>7100H</b>	<b>Array</b>	<b>AI Input FV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_FV	Integer16			
	...					
	07H	AI7_Input_FV	Integer16			
<b>7130H</b>	<b>Array</b>	<b>AI Input PV</b>	<b>Integer16</b>	<b>X</b>	<b>-</b>	<b>-</b>
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Input_PV	Integer16			
	...					
	07H	AI7_Input_PV	Integer16			

Object Index	Object type	Object name	Data type	Object mappable	Object stored	Object restore
7133H	Array	AI Interrupt delta Input PV	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Delta_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Delta_Input_PV	Integer16			
7134H	Array	AI Interrupt lower limit Input PV	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Lower_Limit_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Lower_Limit_Input_PV	Integer16			
7135H	Array	AI Interrupt upper limit Input PV	Integer16	-	X	X
	00H	Number Of Entries	Unsigned8			
	01H	AI0_Interrupt_Upper_Limit_Input_PV	Integer16			
	...					
	07H	AI7_Interrupt_Upper_Limit_Input_PV	Integer16			

Table 115: CANopen IO-X7 Object Dictionary

## Parameter description

Parameter	Description
AI Sensor Type	<p>Specifies the type of sensor, which is connected to the input channel.</p> <p>0<sub>dec</sub> = no sensor is connected / disabled  1<sub>dec</sub> = thermocouple sensor type J  2<sub>dec</sub> = thermocouple sensor type K  3<sub>dec</sub> = thermocouple sensor type L  5<sub>dec</sub> = thermocouple sensor type R  6<sub>dec</sub> = thermocouple sensor type S</p>

Parameter	Description
	<p>7<sub>dec</sub> = thermocouple sensor type T  8<sub>dec</sub> = thermocouple sensor type E  Default value: 0<sub>dec</sub></p>
AI Operation mode	<p>Enables/disables an input channel  0 = Channel disabled  1 = Channel enabled (operating)  Default value: 00H</p>
AI Physical Unit PV	<p>This parameter assigns SI units and prefixes for the process values of each channel. The coding of the physical unit and prefixes is done according to the CiA 303-2. This value just provides additional information and has no influence on process value calculation.  Possible values:  00050000H = K  002D0000H = °C  00AC0000H = °F  Default value: 002D0000H (°C)</p>
AI Decimal Digits PV	<p>Specifies the number of decimal digits following the decimal point for interpretation of data type Integer16.  Example :  A process value of 98.2°C will be coded as 982<sub>dec</sub> in Integer16 format if the number of decimal digits is set to 1 and 98<sub>dec</sub> if number of decimal digits is set to 0.  0 = no decimal digits  1 = one decimal digits  Default value: 1</p>
AI Status	<p>This read only parameter holds the status of the analog input channel.  0 = no error  1 = sensor break  2 = measurement range exceeded</p>
AI Interrupt delta input PV	<p>Specifies a "delta" value for triggering PDO transmission for an analog input channel.  If the process value has changed for "delta" or more since the last transmission of the PDO, then the PDO is transmitted again.  To disable this function set delta to 0.  Default value: 10<sub>dec</sub>  (corresponds to 1.0°C under default settings)</p>
	<b>Note</b>

Parameter	Description
	The entered value must have the same physical unit and number of digits as configured for the respective channel.
AI interrupt lower limit input PV	<p>This parameter sets the lower limit for triggering PDO transmission of an analog input channel. If the PV goes below this value, the corresponding LED on the LED display (&lt; MIN) is switched on. Is the process value between the minimal and maximal value, no PDO is transmitted.</p> <p><b>Note</b></p> <p>The temperature range depends on the sensor type. There is no internal checking whether the configured range exceeds the selected sensor type or not!</p> <p>Example : A value of 50.5°C will be coded as 505<sub>dec</sub> in Integer16 format if the number of decimal digits is set to 1.</p>
AI interrupt upper limit input PV	<p>This parameter sets the upper limit for triggering PDO transmission of an analog input channel. If the PV exceeds this value, the corresponding LED on the LED display (&gt; MAX) is switched on. Is the process value between the minimal and maximal value, no PDO is transmitted.</p> <p><b>Note</b></p> <p>The temperature range depends on the sensor type. There is no internal checking whether the configured range exceeds the selected sensor type or not!</p> <p>Example : A value of 528,5°C will be coded as 5285<sub>dec</sub> in Integer16 format if the number of decimal digits is set to 1.</p>
AI Input FV	This object contains the field value (before scaling).
manufacture date	<p>This object contains the manufacture date. The object is "read only"</p> <p>e.g.: 01112007H means 1<sup>st</sup> November 2007</p>
calibration date	<p>This object contains the date of the last calibration. The object is "read only".</p> <p>e.g.: 12112007H means 12<sup>th</sup> November 2007</p>
Channel Calibration	<p>Output Value (PV) is the result of the following:</p> <p>The Value "Gain" is multiply with the Fieldvalue.</p> <p>The Value "Offset" is add to the Fieldvalue.</p>

Parameter	Description
	see below
AI Scaling Factor AI Scaling Offset	The Value "Factor" is multiply with the Fieldvalue. The Value "Offset" is add to the Fieldvalue. see below
AI Input PV	This object contains the process value (after scaling).

Table 116: CANopen IO-X7 parameter description

### Default mapping of I/O

PDO	TPDO1	TPDO2	TPDO3	TPDO4
COB-ID	180H+ node-ID	280H+ node-ID	380H+ node-ID	480H+ node-ID
<b>Mapped objects</b>	4	4	4	4
<b>Mapped object 1 (data byte 0+1)</b>	AI0 7130H /01H/10H	AI2 7130H /03H/10H	AI4 7130H /05H/10H	AI6 7130H /07H/10H
<b>Mapped object 2 (data byte 2)</b>	AI0 State 6150H /01H/08H	AI2 State 6150H /03H/08H	AI4 State 6150H /05H/08H	AI6 State 6150H /07H/08H
<b>Mapped object 3 (data byte 3+4)</b>	AI1 7130H /02H/10H	AI3 7130H /04H/10H	AI5 7130H /06H/10H	AI7 7130H /08H/10H
<b>Mapped object 4 (data byte 5)</b>	AI1 State 6150H /02H/08H	AI3 State 6150H /04H/08H	AI5 State 6150H /06H/08H	AI7 State 6150H /08H/08H

Table 117: CANopen IO-X7 default mapping

### Relation between Fieldvalue (FV), Processvalue (PV) and Calibration

Thermocouple sensor type E, J, K, L and T:

$$FV1 = (ADC_{value} * AI\_EJKLT\_Gain\_x + AI\_EJKLT\_Offset\_x) \\ * AI\_Scaling\_Factor\_x + AI\_Scaling\_Offset\_x$$

$$FV = FV1 * 2.222154[\mu V/Digit]$$

thermocouple sensor type R and S:

$$FV1 = (ADC_{value} * AI\_RS\_Gain\_x + AI\_RS\_Offset\_x) \\ * AI\_Scaling\_Factor\_x + AI\_Scaling\_Offset\_x$$

$$FV = FV1 * 0.755386[\mu V/Digit]$$

“x” means number of AI channel

The calculation of PV is according to IEC 584-1:1995.

### Device specific commissioning

The following steps list the device specific configuration, which are necessary to put the device into operation. Communication specific configuration (e.g. PDO Mapping and Linking, device guarding, ect.) is not considered here. Furthermore it is assumed that the basic commissioning (see *Section 6.1*) of the device has been finished.

- (1) Configure the sensor type of each channel (Object 6110H).
- (2) Configure the number of digits used for the process value (Object 6132H).
- (3) Set the physical unit of each channel (Object 6131H).
- (4) If required, configure the “delta” value of each channel (Object 7133).
- (5) If required, configure the upper and lower limit of each channel (Object 7134H and 7135H)
- (6) Enable the channels in use (Object 6112H).

### Accessory

Order number	Part
171024 171054	3 pole plug for the power supply
171023	5 pole plug with adapter cable to 9-pin D-Sub connector for CAN bus
171036	16-pin I/O connector plug
180134	Jumper for the CAN bus termination

Table 118: Accessory for CANopen IO-X7

### References

CiA 303-1 V1.3  
CiA 303-3 V1.2  
CiA 301 V4.02  
CiA 404 V1.2



# 13 Appendix

## 13.1 Conversation table of node-IDs

The following table shows a conversion of decimal node-IDs into hexadecimal format.

Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex
1	1	33	21	65	41	97	61
2	2	34	22	66	42	98	62
3	3	35	23	67	43	99	63
4	4	36	24	68	44	100	64
5	5	37	25	69	45	101	65
6	6	38	26	70	46	102	66
7	7	39	27	71	47	103	67
8	8	40	28	72	48	104	68
9	9	41	29	73	49	105	69
10	A	42	2A	74	4A	106	6A
11	B	43	2B	75	4B	107	6B
12	C	44	2C	76	4C	108	6C
13	D	45	2D	77	4D	109	6D
14	E	46	2E	78	4E	110	6E
15	F	47	2F	79	4F	111	6F
16	10	48	30	80	50	112	70
17	11	49	31	81	51	113	71
18	12	50	32	82	52	114	72
19	13	51	33	83	53	115	73
20	14	52	34	84	54	116	74
21	15	53	35	85	55	117	75
22	16	54	36	86	56	118	76
23	17	55	37	87	57	119	77
24	18	56	38	88	58	120	78
25	19	57	39	89	59	121	79
26	1A	58	3A	90	5A	122	7A
27	1B	59	3B	91	5B	123	7B
28	1C	60	3C	92	5C	124	7C
29	1D	61	3D	93	5D	125	7D
30	1E	62	3E	94	5E	126	7E
31	1F	63	3F	95	5F	127	7F

Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex	Node-ID decimal	Node-ID hex
32	20	64	40	96	60		

Table 119: Conversion table from decimal to hexadecimal Node-ID

## 13.2 Troubleshooting

### Warning limit/Bus off indicated on one or more modules

#### Error Frames

One sign of errors in the CAN wiring, the address assignment or the setting of the bit rate is an increased number of error frames: the diagnostic LED on the module then indicates Warning Limit exceeded or Bus-off state entered (see Section 9.1).

#### Note

Warning limit exceeded or bus-off state are indicated first of all at those nodes that have detected the most errors. These nodes, however, are not necessarily the cause for the occurrence of error frames!

If, for instance, one node causes unusual heavy bus traffic (e.g. analog inputs which trigger event-driven PDOs at a high rate), then the probability of its telegrams being damaged increases. Its error counter will be the first one, reaching a critical level.

#### node-ID and bit rate settings

Make sure that node-IDs were not assigned twice: to make sure there is only one producer for each CAN data telegram (when Pre-Defined Connection Set is used.).

#### Test 1

Check node-IDs. If the CAN communication works partially and all the devices support the boot up message, then the node-ID assignment can also be checked by recording the boot up messages after resetting the modules. However, this will not work on node-IDs that have been swapped.

Check that the same bit rate has been set on each node.

### Testing the CAN wiring

#### Warning

Proceed with the following test steps while the network is active - communication should not take place during the tests.

The following tests should be carried out in the stated sequence, because some of the tests assume that the previous test has been completed successfully. Not all the tests are generally necessary.

### *Network terminator and signal lines*

#### **Test 2**

For this test the nodes must be switched off or the CAN cable unplugged. Otherwise the measured results may be distorted by an active CAN transceiver.

Proceed with measuring the resistance between CAN\_High and CAN\_Low at each device, if necessary.

If the measured value is higher than  $65\Omega$ , it indicates the absence of a terminating resistor or a break in a signal lead. If the measured value is less than  $5\Omega$ , look for a short circuit between the CAN lines, more than the correct number of terminating resistors, or faulty transceivers.

#### **Test 3**

Check for a short circuit between the CAN ground and the signal lines, or between the screen (shield) and signal lines.

#### **Test 4**

Remove the earth connection from the CAN ground and screen. Check for a short circuit between the CAN ground and screen.

### *Topology*

The possible cable length in CAN networks depends heavily on the selected bit rate. CAN usually tolerates short drop lines. The maximum permitted length of drop lines should not be exceeded (see *Section 4.3*). The length of the cable installed on the field is often subject to estimating errors. The following test is therefore recommended to be performed!

#### **Test 5**

Measure the lengths of the drop lines and the total bus lengths (do not just make rough estimates!) and compare them with the topology rules for the relevant bit rate.

### *Screening and grounding*

#### **Test 6**

The power supply and the screen should be carefully earthed at the power supply unit, with a single joint only (star-shaped) and with low resistance. At all connecting points, branches and so forth the screen of the CAN cable (and possibly the CAN\_GND) must also be connected, as well as the signal lines.

#### Test 7

Use a DC ampere meter to measure the current between the power supply ground and the screen at the end of the network most remote from the power supply unit. An equalization current should be present. If there is no current, then either the screen is not connected all the way through, or the power supply unit is not properly earthed. If the power supply unit is somewhere in the middle of the network, the measurement should be performed at both ends. If necessary, this test can also be done at the ends of the drop lines.

#### Test 8

Interrupt the screen at a number of locations and measure the current to these connections. If there is a current present, the screen is earthed at more than one place, creating a ground loop.

#### *Potential differences*

The screen must be connected all the way through for this test, and must not have any current flow (*see Test 8*).

#### Test 9

Measure and record the voltage between the screen and the power supply ground at each node. The maximum potential difference between any two devices should be less than 5V.

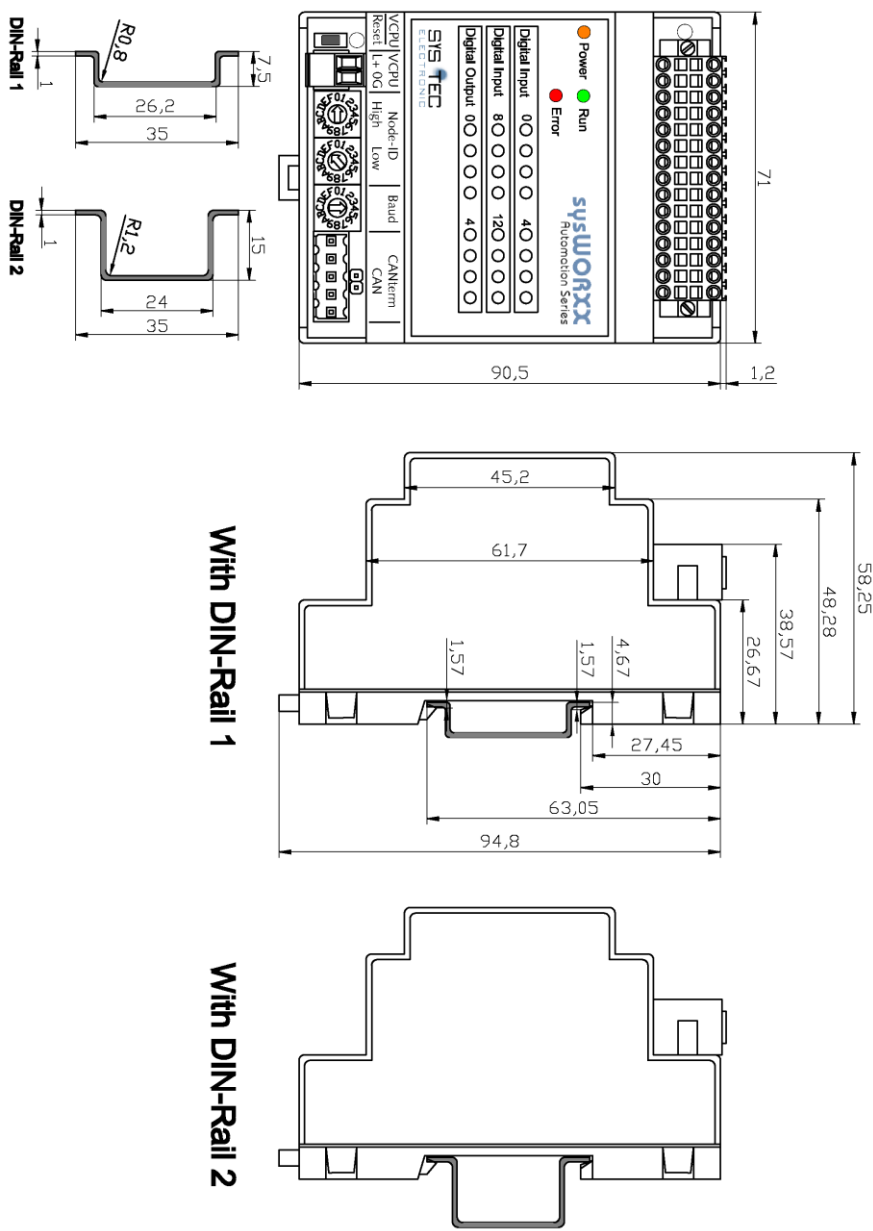
#### **Detect and localize the faults**

In a first approach "low-tech method" works best: disconnect parts of the network, and observe if the error disappears.

However, this does not work well for problems such as excessive potential differences, ground loops, EMC or signal distortion, since the reduction in the size of the network often solves the problem without the "missing" piece being the cause. The bus load also may change as the network is reduced in size, leading to a more harmonized traffic and therefore making localization of faults more difficult.

Diagnosis with an oscilloscope does not always work out successfully as it is hard to do low-level debugging on bit-layer. Especially on heavy traffic and/or disturbances. However, it might be possible to trigger on error frames using a oscilloscope - this type of diagnosis, however, is only recommended for experts.

13.3 Module Dimensions



### 13.4 Bus cable and termination resistors

The cables, connectors, and termination resistors used in CANopen networks shall meet the requirements defined in ISO 11898. In addition, this section gives some guidelines for selecting cables and connectors.

The table below shows some standard values for DC parameters for CANopen networks with less than 64 nodes:

Bus length [m]	Bus cable		Termination resistance [Ω]
	Length-related resistance [mΩ/m]	Diameter [mm <sup>2</sup> ]	
0 ... 40	70	0,25 ... 0,34	124
40 ... 300	<60	0,34 ... 0,6	150 ... 300
300 ... 600	<40	0,5 ... 0,6	150 ... 300
600 ... 1000	<26	0,75 ... 0,8	150 ... 300

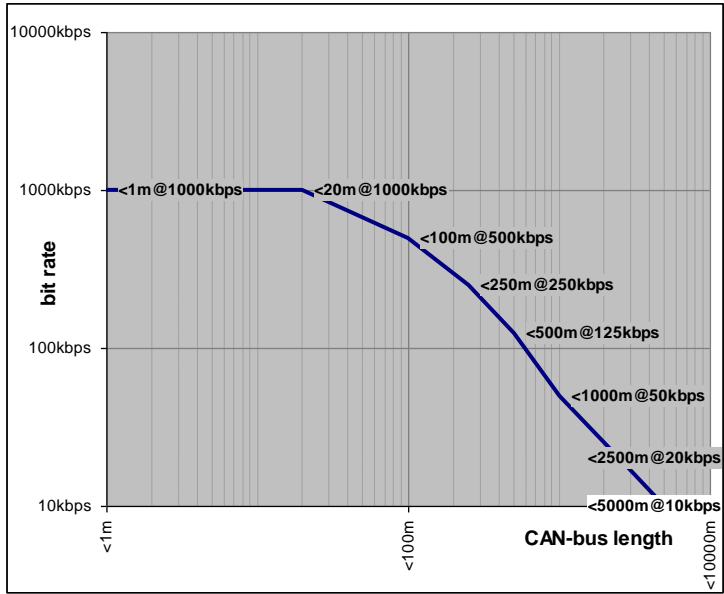


Table 120: CAN-bus length versus bit rate

A figure of 40m at 1 Mbit/s is often found in the CAN literature. This does not, however, apply for networks with optically isolated CAN controllers. The worst case calculation for opto-couplers results in a calculated bus length of 5 m at 1 Mbit/s - in practice, however, 20 m can be reached without difficulty. It may be necessary to use repeaters for bus lengths longer than 1000 m.

For drop cables a wire cross-section of 0.25 to 0.34 mm<sup>2</sup> is recommended.

When calculating the voltage drop, the real connector resistance should be considered too. The contact resistance of one connector can be assumed in a range of 2.5 to 10 mΩ.

With the assumed values for:

Minimum dominant value	$V_{\text{diff.out.min}} = 1.5 \text{ V}$
Minimum differential input resistance	$R_{\text{diff.min}} = 20 \text{ k}\Omega$
Requested differential input voltage	$V_{\text{th.max}} = 1.0 \text{ V}$
Minimum termination resistance	$R_{\text{T.min}} = 118 \Omega$

The following table shows the maximum length for different bus cables and different number of connected bus nodes.

Wire diameter [mm <sup>2</sup> ]	Maximum length [m] safety margin 0,2			Maximum length [m] safety margin 0,1		
	n=32	n=64	n=100	n=32	n=64	n=100
0,25	200	170	150	230	200	170
0,5	360	310	270	420	360	320
0,75	550	470	410	640	550	480

#### Note:

If driving more than 64 nodes and/or more than 250m bus length the accuracy of the  $V_{\text{cc}}$  supply voltage for the ISO 11898 transceiver is recommended to be 5% or lower. You also have to consider the minimum supply voltage of at least 4.75V when driving 50Ω load, i.e. 64 bus nodes, and at least 4.9V when driving 45Ω load, i.e. 100 bus nodes.

For more information please refer to standard CiA 303-1 and CiA 102.

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# Glossary

CAN:	<b>Controller Area Network</b> is an internationally standardized serial bus system.
COB:	<b>Communication Object</b> A unit of transportation in a CAN network. Data must be sent across a CAN Network inside a COB. There are 2048 different COBs in a CAN network. A COB can contain at most 8 bytes of data.
COB-ID:	Each COB is uniquely identified in a CAN network by a number called the <b>COB Identifier</b> (COB-ID). The COB-ID determines the priority of that COB for the MAC sub-layer.
Remote COB:	A COB whose transmission can be requested by another device.
CRC:	<b>Cyclic Redundancy Check.</b>
CSDO:	<b>Client SDO</b>
FV:	Field Value : the converted analog input value (raw value). This value is always left adjusted.
LED:	Light Emitting Diode
MAC:	<b>Medium Access Control</b> One of the sub-layers of the Data Link Layer in the CAN Reference Model that controls who gets access to the medium to send a message.
NMT:	<b>Network Management</b> One of the CANopen service elements of the application layer in the CAN OSI Reference Model. The NMT serves to configure, initialize, and handle errors in a CANopen network.
Node-ID:	The node-ID is the address of nodes in a CANopen network and therefore has to be assigned uniquely. It also determines the offset of the communication objects (COBs) and the priority of the node. The node-ID 0 is reserved. Possible values: 1 to 127
OSI:	<b>Open Systems Interconnection.</b>
PE:	upper range value
PDO:	<b>Process Data Object.</b>
PV:	Process Value: The field value is converted to the real physical dimension of the measured quality, and the result is called "process value".
RPDO:	<b>Receive PDO.</b>

Pre-defined Connection Set	The pre-defined connection set is a default assignment of CAN message identifiers (COB-IDs) to CANopen objects. This default assignment guarantees that the CAN message identifiers are uniquely assigned in the network, if the node-ID has been assigned uniquely.
SDO:	<b>Service Data Object.</b>
SI:	International system of units
SSDO:	<b>SDO Server.</b>
SYNC:	<b>Synchronization Object.</b>
TPDO:	<b>Transmit PDO.</b>
$U_{OH}$ :	Output voltage high
$U_{OL}$ :	Output voltage low
$U_{IH}$ :	Input voltage high
$U_{IL}$ :	Input voltage low
$I_{OH}$ :	Output current high
$I_{OL}$ :	Output current low
$I_{IH}$ :	Input current high
$t_{OFF}$ :	Output turn off time
$t_{ON}$ :	Output turn on time

# Index

Analog input module.....	139, 150, 176
Analog output module .....	165
Application planning .....	15
bit rate .....	42
CAN interfaces	
<i>CAN-Ethernet Gateway</i> .....	11
<i>USB-CANlog</i> .....	11
CAN interfaces	
<i>USB-CANmodul1</i> .....	10
<i>USB-CANmodul2</i> .....	10
CAN_GND .....	28
CAN_H.....	28
CAN_L .....	28
CAN_SHLD.....	28
CAN_V+.....	28
CANopen Configuration Suite .....	49
CANopen configuration tools .....	9
CANopen DeviceExplorer .....	49
CANopen introduction .....	3
CANopen IO-X1	
Error behaviour .....	114
CANopen IO-X1.....	109
Block diagram .....	112
LED display .....	111
Manufacturer specific functions ...	114
Module pinout.....	110
Properties.....	109
Technical data.....	112
CANopen IO-X1	
Object dictionary.....	115
CANopen IO-X1	
Parameter description .....	117
CANopen IO-X1	
Default mapping .....	119
CANopen IO-X1	
Commissioning.....	120
CANopen IO-X1	
Accessory .....	121
CANopen IO-X2	
Error behaviour .....	125
CANopen IO-X2 .....	122
Block diagram .....	124
Manufacturer specific functions ...	125
Module pinout.....	122
Properties.....	122
Technical data.....	124
CANopen IO-X2	
Object dictionary .....	126
CANopen IO-X2	
Parameter description .....	127
CANopen IO-X2	
Default mapping .....	128
CANopen IO-X2	
Commissioning.....	128
CANopen IO-X2	
Accessory .....	129
CANopen IO-X3	
Error behaviour .....	134
CANopen IO-X3 .....	130
Block diagram .....	132
Manufacturer specific functions ...	134
Module pinout.....	130
Properties.....	130
Technical data.....	133
CANopen IO-X3	
Object dictionary .....	134

<b>CANopen IO-X3</b>	
Parameter description.....	135
<b>CANopen IO-X3</b>	
Default mapping .....	136
<b>CANopen IO-X3</b>	
Commissioning .....	136
<b>CANopen IO-X3</b>	
Accessory .....	136
<b>CANopen IO-X4</b>	
Error behaviour.....	143
<b>CANopen IO-X4.....</b>	<b>139</b>
Block diagram.....	141
LED display .....	141
Manufacturer specific functions...	143
Module pinout.....	139
Properties .....	139
Technical data .....	141
<b>CANopen IO-X4</b>	
Object dictionary.....	143
<b>CANopen IO-X4</b>	
Parameter description.....	146
<b>CANopen IO-X4</b>	
Default mapping .....	148
<b>CANopen IO-X4</b>	
Commissioning .....	149
<b>CANopen IO-X4</b>	
Accessory.....	149
<b>CANopen IO-X5</b>	
Error behaviour.....	155
<b>CANopen IO-X5.....</b>	<b>150</b>
Block diagram.....	153
LED display .....	152
Manufacturer specific functions...	154
Module pinout.....	150
Properties .....	150
Technical data .....	153
<b>CANopen IO-X5</b>	
Object dictionary.....	155
<b>CANopen IO-X5</b>	
Parameter description .....	159
<b>CANopen IO-X5</b>	
Default mapping .....	162
<b>CANopen IO-X5</b>	
Commissioning.....	163
<b>CANopen IO-X5</b>	
Accessory.....	163
<b>CANopen IO-X6</b>	
Error behaviour.....	169
<b>CANopen IO-X6.....</b>	<b>165</b>
Block diagram.....	167
LED display .....	167
Manufacturer specific functions ...	168
Module pinout.....	165
Properties.....	165
Technical data .....	167
<b>CANopen IO-X6</b>	
Object dictionary.....	169
<b>CANopen IO-X6</b>	
Parameter description .....	172
<b>CANopen IO-X6</b>	
Default mapping .....	173
<b>CANopen IO-X6</b>	
Commissioning.....	175
<b>CANopen IO-X6</b>	
Accessory.....	175
<b>CANopen IO-X7</b>	
Error behaviour.....	180
<b>CANopen IO-X7.....</b>	<b>176</b>
Block diagram.....	178
LED display .....	178
Manufacturer specific functions ...	180
Module pinout.....	176
Properties.....	176
Technical data .....	179
<b>CANopen IO-X7</b>	
Object dictionary.....	181
<b>CANopen IO-X7</b>	
Parameter description .....	184

---

<b>CANopen IO-X7</b>	
Default mapping .....	187
<b>CANopen IO-X7</b>	
Commissioning .....	188
<b>CANopen IO-X7</b>	
Accessory .....	188
<b>CANopen PLC-C14eco</b> .....	8
<b>CDE</b> .....	<i>See CANopen Device Explorer</i>
<b>CiA 301</b> .....	4, 6
<b>CiA 302</b> .....	4, 10
<b>CiA 304</b> .....	4
<b>CiA 305</b> .....	33, 40, 42
<b>CiA 306</b> .....	5
<b>CiA 401</b> .....	4
<b>CiA 402</b> .....	4
<b>CiA 405</b> .....	4, 10
<b>CiA 406</b> .....	4
<b>Commissioning</b> .....	55
Startup of the sysWORXX I/O modules .....	56
<b>Communication method</b>	
Event driven .....	67
Individual polling .....	68
Synchronized .....	68
Timer driven .....	68
<b>Communication Parameter Set</b> .....	65
<b>Communication Services</b> .....	65
<b>Compact system</b> .....	15
<b>Components of the sysWORXX</b>	
CANopen I/O modules .....	12
<b>Configuring</b> .....	33
Basic device configuration .....	39
bit rate .....	40
CANopen networks .....	33
Defining the system .....	33
General rules .....	33
LSS .....	39, 40
node-ID .....	39
Resetting to factory settings .....	54
Store/Restore device configuration .....	51
Using Device Configuration Files .....	49
Using Layer Setting Services (LSS) .....	42
<b>Connecting</b> .....	23
CAN cable .....	27
CAN_GND .....	28
CAN_H .....	28
CAN_L .....	28
CAN_SHLD .....	28
CAN_V+ .....	28
CAN-bus .....	27
CAN-bus signals .....	28
grounded reference potential .....	25
Physical layout .....	29
Power supply .....	25
Wiring and cabling .....	27
<b>Contact information</b> .....	I
<b>DCF</b> .....	9, <i>See Device Configuration File</i>
<b>Device Configuration File</b> .....	5, 20, 49, 60
<b>Device identification data</b> .....	78
<b>Device monitoring</b> .....	73
<b>Diagnostic data</b> .....	90
<b>Diagnostics</b>	
Diagnostic data .....	90
Diagnostic messages .....	92
Evaluation of agnostic messages .....	92
Status LEDs .....	85
<b>Digital input and output module</b> .....	109
<b>Digital input module</b> .....	122
<b>Digital output module</b> .....	130
<b>Disclaimer</b> .....	I
<b>Distributed CANopen I/O modules</b> .....	11
<b>Distributed I/O systems</b> .....	1
<b>Drop lines</b> .....	29
<b>EDS</b> .....	9, <i>See Electronic Data Sheet</i>
<b>Electronic Data Sheet</b> .....	5, 42, 49
<b>Emergency messages</b> .....	73, 92
Emergency codes .....	93

Message structure .....	93	<b>Inhibit Timer</b> .....	<b>67</b>
<b>EN 50325-4</b> .....	<b>3</b>	<b>Installation</b> .....	<b>17</b>
<b>Error behavior</b> .....	<b>96</b>	Connectors.....	18
<b>Error behavior and system messages</b> .....	<b>85</b>	I/O modules.....	17
<b>Error conditions</b>		Setting the node-ID and termination .....	20
analog inputs .....	92	<b>Internal diagnostics and monitoring functions</b> .....	<b>73</b>
analog outputs .....	92	<b>ISO 11898-1</b> .....	<b>1</b>
digital outputs .....	92	<b>ISO 11898-2</b> .....	<b>1, 6</b>
integrated power supply and diagnostics .....	93	<b>Layer Setting Services</b> .....	<i>See LSS</i>
<b>Event driven</b> .....	<b>67</b>	<b>LED</b>	
<b>Extended temperature range</b> .....	<b>107</b>	Blinking cycles.....	86
<b>FullCAN</b> .....	<b>68</b>	Error .....	85
<b>Functions</b> .....	<b>61</b>	Error-LED double flashing .....	87, 89
Communication Services .....	65	Error-LED flickering .....	86, 88
Device identification data.....	78	Error-LED single flashing...87, 88, 89	
Internal diagnostics and monitoring	73	Error-LED tripple flashing .....	87
Manufacturer specific extensions..	75	Run .....	85
Object Dictionary .....	61	Run-LED blinking .....	86
Synchronized operations .....	80	Run-LED flickering.....	86
<b>General rules and regulations</b>		Run-LED single flashing .....	86
Operating the sysWORXX I/O modules.....	23	Run-LED tripple flashing.....	86, 89
<b>Guarding</b>		<b>Life Guard Time</b> .....	<b>101</b>
Heartbeat .....	102	<b>Life Guarding</b> .....	<b>101</b>
Life Guarding.....	101	<b>Life Time Factor</b> .....	<b>101</b>
Node Guarding .....	101	<b>LSS</b> .....	<b>33, 37, 39, 40, 42, 78</b>
Node Life Time .....	103	<b>LSS master</b> .....	<b>42, 43</b>
<b>Heartbeat</b> .....	<b>102</b>	<b>LSS slave</b> .....	<b>42</b>
Heartbeat Consumer .....	102	<b>Maintenance and service</b> .....	<b>59</b>
Heartbeat error .....	103	Removing and inserting I/O modules .....	59
Heartbeat Producer .....	102	<b>Manufacturer specific extensions</b> ..	<b>75</b>
<b>I/O filtering</b> .....	<b>75</b>	<b>Mapping Parameter Set</b> .....	<b>65</b>
<b>Identity Object</b> .....	<b>78</b>	<b>Mechanical and climatic ambient conditions</b> .....	<b>106</b>
<b>IEC 60364-4-41</b> .....	<b>25</b>	<b>Minimal NMT bootstrap master</b> .....	<b>75</b>
<b>IEC 61131-3 controls</b> .....	<b>8</b>	<b>Module/Network status and device guarding</b> .....	<b>99</b>
<b>IEC 61131-3 IDE</b> .....	<b>9</b>	<b>Mounting</b> .....	<b>17</b>
<b>Individual polled</b> .....	<b>68</b>		
<b>Inhibit Time</b> .....	<b>67</b>		

---

---

Requirements.....	17	100CH.....	101, 103
<b>Network Management .....</b>	<i>See NMT</i>	100DH.....	101, 103
<b>NMT.....</b>	<b>37, 57</b>	1010H.....	51
NMT state machine .....	99	1011H.....	51
state .....	85	1014H.....	95
<b>NMT command code</b>		1016H.....	103
01H.....	100	1017H.....	103
02H.....	100	1018H.....	78
80H.....	101	<b>1029H.....</b>	97
81H.....	101	2000H.....	75
82H.....	101	2001H.....	73, 74
<b>NMT master.....</b>	<b>99</b>	2010H.....	75, 115, 126
<b>NMT message</b>		<b>2500H.....</b>	181
Boot-up .....	57, 99	<b>6000H.....</b>	115, 126
Enter_PREOPERATIONAL_State		<b>6003H.....</b>	116, 126
.....	101	<b>6005H.....</b>	115, 116, 126
Reset_Communication .....	57, 73, 101	<b>6006H.....</b>	116, 126
Reset_Node .....	57, 73, 101	<b>6007H.....</b>	116, 126
Start_Remote_Node.....	57, 99, 100	<b>6008H.....</b>	116, 127
Stop_Remote_Node.....	100	<b>6110H.....</b>	143, 144, 155, 156, 169, 170, 181
<b>NMT messages .....</b>	<b>3</b>	<b>6112H.....</b>	144, 157, 182
<b>NMT slave .....</b>	<b>99</b>	<b>6126H.....</b>	182
<b>NMT state</b>		<b>6127H.....</b>	182
INITIALIZATION.....	56, 57, 99	<b>6131H.....</b>	144, 157, 182
OPERATIONAL.....	57, 100	<b>6132H.....</b>	145, 158, 183
PRE-OPERATIONAL .....	57, 99, 101	<b>6150H.....</b>	145, 158, 183
STOPPED.....	100	<b>6200H.....</b>	116, 134
<b>NMT STATE</b>		6206H.....	97, 116, 134
PRE-OPERATIONAL .....	98	6207H.....	97, 115, 117, 135
STOPPED.....	98	<b>6208H.....</b>	117, 135
<b>Node Guarding .....</b>	<b>101</b>	6301H.....	170
<b>Node Life Time .....</b>	<b>103</b>	6302H.....	170
<b>node-ID.....</b>	<b>6, 39, 42</b>	6310H.....	171
<b>Object</b>		6340H.....	97, 171
1001H.....	90	<b>7100H.....</b>	145, 158, 183
1003H.....	90	<b>7130H.....</b>	145, 158, 183
1005H.....	81	<b>7133H.....</b>	146, 159, 184
1006H.....	69	7300H.....	171
1007H.....	81		

---

7341H.....	97, 171
<b>Object Dictionary.....</b>	<b>4, 61</b>
<b>Parameter</b>	
AI Decimal Digits PV... 147, 160, 172, 185	
AI Interrupt delta input PV... 147, 161, 185	
AI interrupt lower limit input PV.. 161, 186	
AI interrupt upper limit input PV . 161, 186	
AI Operation mode .....	146, 160, 185
AI Physical Unit PV.....	146, 160, 172, 185
AI Sensor Type.....	146, 159, 184
AI Status.....	147, 160, 185
AO Fault FV.....	172
AO Fault mode .....	172
AO Output type.....	172
<b>COB-ID Emergency message....</b>	<b>96</b>
<b>COB-ID SYNC.....</b>	<b>82</b>
COB-ID used by PDO.....	63
<b>Communication Errors.....</b>	<b>98</b>
Communication parameter.....	63
<b>Consumer Heartbeat Time .....</b>	<b>104</b>
Device main voltage .....	74
Device temperature .....	74
<b>Disable digital input 8-Bit..</b>	<b>117, 127</b>
Dlx_Dlx_Disable.....	77
Error Count.....	91
<b>Error mode output 8-Bit ....</b>	<b>118, 135</b>
<b>Error Register .....</b>	<b>90</b>
<b>Error value output 8-Bit....</b>	<b>118, 119, 135</b>
Event timer .....	63
<b>Filter constant of digital inputs 8-Bit .....</b>	<b>117, 127</b>
<b>Filter Constant output 8-Bit ....</b>	<b>118, 135</b>
<b>Global interrupt enable 8-Bit... 117, 127</b>	

<b>Guard Time .....</b>	<b>103</b>
Inhibit Time.....	63
<b>Interrupt mask any change 8-Bit .....</b>	<b>117, 127</b>
<b>Interrupt mask high to low 8-Bit .....</b>	<b>118, 128</b>
<b>Interrupt mask low to high 8 Bit</b>	<b>118, 127</b>
<b>Life Time Factor.....</b>	<b>103</b>
Mapping parameter .....	63
NMT Boot enable .....	76
NMT Start Time .....	77
<b>Producer Heartbeat Time .....</b>	<b>104</b>
<b>Product Code.....</b>	<b>78</b>
<b>Revision Number .....</b>	<b>79</b>
<b>Serial Number .....</b>	<b>79</b>
Standard Error Field .....	91
<b>Synchronous Window Length ....</b>	<b>82</b>
Transmission Type .....	63
<b>Vendor ID .....</b>	<b>78</b>
<b>PDO .....</b>	<b>3, 65</b>
<b>PDO linking.....</b>	<b>65</b>
<b>PDO Linking.....</b>	<b>10</b>
<b>PDO mapping.....</b>	<b>70</b>
<b>PDO Mapping.....</b>	<b>10</b>
<b>PDO Transmission Type .....</b>	<b>67</b>
<b>PLCmodule-C14.....</b>	<b>8</b>
<b>Pre-defined Connection Set.....</b>	<b>65</b>
<b>Preface .....</b>	<b>3</b>
<b>Process Data Objects.....</b>	<b>65</b>
<b>Reading diagnostic data .....</b>	<b>90</b>
<b>Recycling and disposal.....</b>	<b>3</b>
<b>Remote Request .....</b>	<b>70</b>
<b>Removing and inserting I/O modules .....</b>	<b>59</b>
<b>Resetting to factory settings .....</b>	<b>54</b>
<b>RPDO.....</b>	<b>65</b>
<b>RTR frame.....</b>	<b>70</b>
<b>Safety Guidelines .....</b>	<b>I</b>
<b>SDO .....</b>	<b>3, 37, 72</b>

---



---

<b>Selection guide</b> .....	16	Electromagnetic compatibility .....	106
I/O modules.....	15	General technical data .....	105
Maximum configuration .....	16	Mechanical and climatic ambient conditions.....	106
<b>Serial number</b> .....	79	Shipping and storage conditions..	106
<b>Service Data Objects</b> .....	72	Standards and certifications .....	105
<b>Shipping and storage conditions</b> .	106	<b>Technical Support</b> .....	4
<b>Standards and certifications</b> .....	105	<b>Timer driven</b> .....	68
<b>Startup diagnostics</b> .....	73	<b>TN-S power supply</b> .....	25
<b>Startup of the sysWORXX I/O modules</b> .....	56	<b>TPDO</b> .....	65
<b>Status LEDs</b> .....	85	<b>Transmission type</b>	
<b>Store/Restore device configuration</b>	51	<b>0</b> .....	69
<b>SYNC</b> .....	3	<b>1...240</b> .....	69
<b>SYNC message</b> .....	80	<b>252/253</b> .....	70
<b>Synchronized</b> .....	68	<b>254/255</b> .....	70
<b>Synchronized operations</b> .....	80	Acyclic synchronous.....	69
<b>sysWORXX Automation Series</b> .....	8	Asynchronous .....	70
<b>Technical data</b> .....	105	Cyclic synchronous .....	69
CANopen IO-X1 .....	112	RTR only .....	70
CANopen IO-X2 .....	124	<b>Transmission type parameter</b> .....	69
CANopen IO-X3 .....	133	<b>Trunk lines</b> .....	29
CANopen IO-X4 .....	141	<b>VDE 0100</b> .....	25
CANopen IO-X5 .....	153	<b>VDE 0113</b> .....	25
CANopen IO-X6 .....	167	<b>Wiring schema</b> .....	29
CANopen IO-X7 .....	179		

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# Revision history

Date	Version	Editor	Comments
2005-Dez-14	L-1070e_01	C.Thomas	Beschreibung der Module und von CANopen Funktionalität eingepflegt
2006-Mar-19	L-1070e_01	A. von Collrepp	Complete revision. Missing sections added. Reformatting.
2006-Apr-03	L-1070e_01	A. von Collrepp	Finalizing. Pre-release.
2006-Jun-17	L-1070e_01	A. von Collrepp	Release version
2007-Nov-22	L-1070e_02	F. Jung-andreas	Completion pulsed DO for X1, Completion Calibration Entries for X4, X5, X6
2008-Mar-25	L-1070e_03	F. Jung-andreas	Completion Calibration Entries for X7
2008-Aug-07	L-1070e_04	F. Jung-andreas	Correction Status (0x6150) for X5 and physical unit (0x6131) for X5 and X7
2009-May-18	L-1070e_05	M. Berthel	Correction sampling rate for X7
2010-Mar-24	L-1070e_06	M. Berthel	new OD entries 1F51H and 2002H States of RUN- and ERROR-LED at Program Control Emergency Error Codes at Program Control all changes from firmware version 1.30
2010-Apr-26	L-1070e_07	M. Berthel	Change of LED display on modules X5 and X7 all changes from firmware version 1.31

## Revision history

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Date	Version	Editor	Comments
2014-Jun-26	L-1070e_09	F. Jung-andreas	change factor for calculation X5 PV with FV
2014-Dec-03	L-1070e_10	A.Süß	Change input current of DI of X1 and X2
2015-Sep-01	L-1070e_12	F.Reményi	Change of the description from the terminals, in consequence of the ESD-revision of the X-serie Change of the images of the modules with changed terminals Change of the parameters from the X4-Modul
2015-Sep-21	L-1070e_13	N. Hehlke	Adapt section 5.3 and 5.4.

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#### Widersprüche bei x1

-in der Beschreibung heist es, dass die Gerätespannungsversorgung und die der Spannungsversorgung der Ausgänge separate gespeist werden.

- in der Beschreibung der Anschlussbuchsen steht hingegen, dass diese intern verbunden sind

- man sollte so etwas separat anbieten

#### Widersprüche beim X3

-ähnlich wie beim X1

-allerdings wird hier in den Anschlussbuchsenbeschreibungen angegeben, dass alle drei Spannungsversorgungen der Ausgangsstufen mit dem Eingang verbunden sind, laut Schaltplan ist dies jedoch nur beim ersten Ausgang der Fall



# Suggestion for improvements

Document:	<b>sysWORXX CANopen I/O modules</b>
Document number:	<b>L-1070e_13</b>

How would you improve this manual?

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Did you find any mistakes in this manual?	page
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