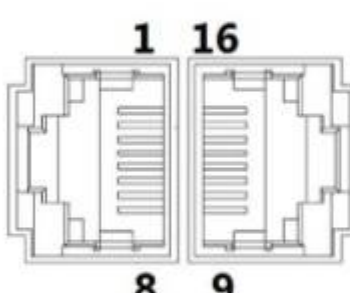


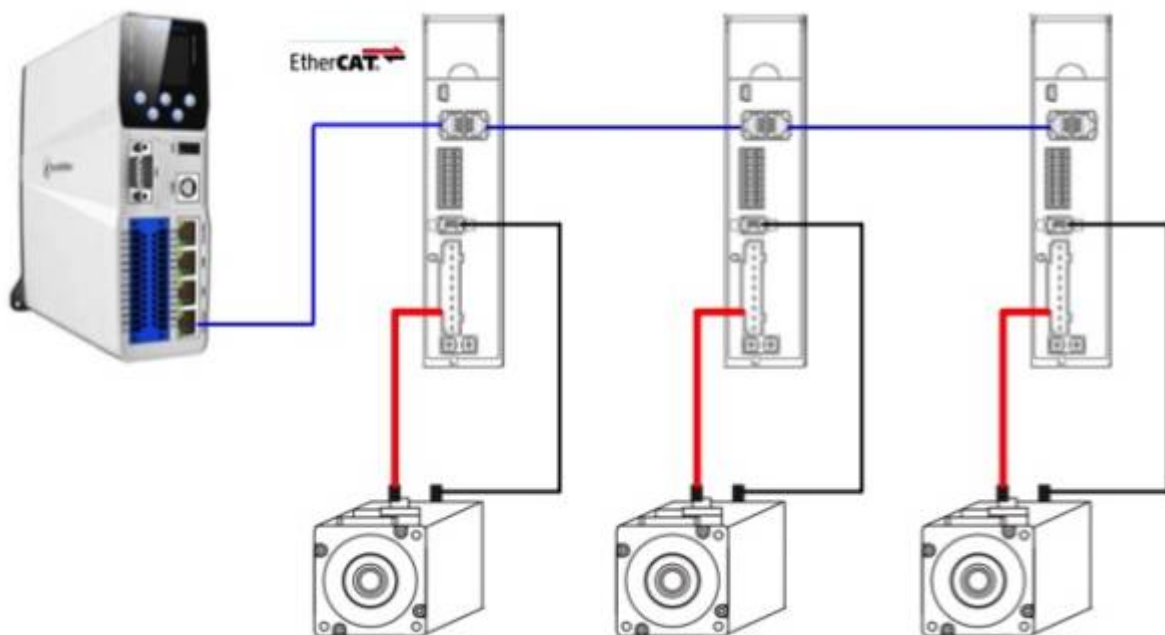
# EtherCAT

## Port pinout

CN3 and CN4 are communication ports for EtherCAT protocol. LAN cable from master device will be connected to CN3 (IN) and CN4 (OUT) will be connected to the next slave device.

Port	Pin	Signal	Description
	1, 9	E_TX+	EtherCAT Data sending positive terminal
	2, 10	E_TX-	EtherCAT Data sending negative terminal
	3, 11	E_RX+	EtherCAT Data receiving positive terminal
	4, 12	--	--
	5, 13	--	--
	6, 14	E_RX-	EtherCAT Data receiving negative terminal
	7, 15	--	--
	8, 16	--	--
	Frame	PE	Shielded ground

Example of EtherCAT communication cable connections between master and slave devices



## Configuration File

XML File: [:nl7\\_servo:nl7\\_xml\\_file.zip](#)

4 Receive PDOs and 1 Transmitt PDO are available as standard configuration.

Generale	Seleziona uscite	Seleziona ingressi																																																																																																			
Dati di processo modalità esperta	<table border="1"><thead><tr><th>Nome</th><th>Tipo</th><th>Indice</th></tr></thead><tbody><tr><td><input checked="" type="checkbox"/> <b>16#1600 Receive PDO 1</b></td><td></td><td></td></tr><tr><td>Control word</td><td>UINT</td><td>16#6040:16#00</td></tr><tr><td>Profile target position</td><td>DINT</td><td>16#607A:16#00</td></tr><tr><td>Touch Probe Function</td><td>UINT</td><td>16#60B8:16#00</td></tr><tr><td><input type="checkbox"/> <b>16#1601 Receive PDO 2</b></td><td></td><td></td></tr><tr><td>Control word</td><td>UINT</td><td>16#6040:16#00</td></tr><tr><td>Target velocity</td><td>DINT</td><td>16#60FF:16#00</td></tr><tr><td>Torque offset</td><td>INT</td><td>16#60B2:16#00</td></tr><tr><td>Modes of operation</td><td>USINT</td><td>16#6060:16#00</td></tr><tr><td><input type="checkbox"/> <b>16#1602 Receive PDO 3</b></td><td></td><td></td></tr><tr><td>Control word</td><td>UINT</td><td>16#6040:16#00</td></tr><tr><td>Target Torque</td><td>INT</td><td>16#6071:16#00</td></tr><tr><td>Torque slope</td><td>UDINT</td><td>16#6087:16#00</td></tr><tr><td>Modes of operation</td><td>USINT</td><td>16#6060:16#00</td></tr><tr><td><input type="checkbox"/> <b>16#1603 Receive PDO 4</b></td><td></td><td></td></tr><tr><td>Control word</td><td>UINT</td><td>16#6040:16#00</td></tr><tr><td>Homing method</td><td>SINT</td><td>16#6098:16#00</td></tr><tr><td>Homing velocity (fast)</td><td>UDINT</td><td>16#6099:16#01</td></tr><tr><td>Homing velocity (slow)</td><td>UDINT</td><td>16#6099:16#02</td></tr><tr><td>Homing acceleration</td><td>UDINT</td><td>16#609A:16#00</td></tr><tr><td>Homing offset</td><td>DINT</td><td>16#607C:16#00</td></tr><tr><td>Modes of operation</td><td>USINT</td><td>16#6060:16#00</td></tr></tbody></table>	Nome	Tipo	Indice	<input checked="" type="checkbox"/> <b>16#1600 Receive PDO 1</b>			Control word	UINT	16#6040:16#00	Profile target position	DINT	16#607A:16#00	Touch Probe Function	UINT	16#60B8:16#00	<input type="checkbox"/> <b>16#1601 Receive PDO 2</b>			Control word	UINT	16#6040:16#00	Target velocity	DINT	16#60FF:16#00	Torque offset	INT	16#60B2:16#00	Modes of operation	USINT	16#6060:16#00	<input type="checkbox"/> <b>16#1602 Receive PDO 3</b>			Control word	UINT	16#6040:16#00	Target Torque	INT	16#6071:16#00	Torque slope	UDINT	16#6087:16#00	Modes of operation	USINT	16#6060:16#00	<input type="checkbox"/> <b>16#1603 Receive PDO 4</b>			Control word	UINT	16#6040:16#00	Homing method	SINT	16#6098:16#00	Homing velocity (fast)	UDINT	16#6099:16#01	Homing velocity (slow)	UDINT	16#6099:16#02	Homing acceleration	UDINT	16#609A:16#00	Homing offset	DINT	16#607C:16#00	Modes of operation	USINT	16#6060:16#00	<table border="1"><thead><tr><th>Nome</th><th>Tipo</th><th>Indice</th></tr></thead><tbody><tr><td><input checked="" type="checkbox"/> <b>16#1A00 Transmit PDO 1</b></td><td></td><td></td></tr><tr><td>Last error code</td><td>UINT</td><td>16#603F:16#00</td></tr><tr><td>Status word</td><td>UINT</td><td>16#6041:16#00</td></tr><tr><td>Modes of operation display</td><td>SINT</td><td>16#6061:16#00</td></tr><tr><td>Actual motor position</td><td>DINT</td><td>16#6064:16#00</td></tr><tr><td>Touch Probe Status</td><td>UINT</td><td>16#60B9:16#00</td></tr><tr><td>Touch probe pos1 pos value</td><td>DINT</td><td>16#60BA:16#00</td></tr><tr><td>Digital inputs</td><td>UDINT</td><td>16#60FD:16#00</td></tr><tr><td><input type="checkbox"/> <b>16#1A01 Transmit PDO 2</b></td><td></td><td></td></tr></tbody></table>	Nome	Tipo	Indice	<input checked="" type="checkbox"/> <b>16#1A00 Transmit PDO 1</b>			Last error code	UINT	16#603F:16#00	Status word	UINT	16#6041:16#00	Modes of operation display	SINT	16#6061:16#00	Actual motor position	DINT	16#6064:16#00	Touch Probe Status	UINT	16#60B9:16#00	Touch probe pos1 pos value	DINT	16#60BA:16#00	Digital inputs	UDINT	16#60FD:16#00	<input type="checkbox"/> <b>16#1A01 Transmit PDO 2</b>		
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