

X20DS1828

Data sheet
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1 General information

1.1 Other applicable documents

For additional and supplementary information, see the following documents.

Other applicable documents

Document name	Title
MAX20	X20 System user's manual

1.2 Order data


Order number	Short description	Figure
	Digital signal processing and preparation	
X20DS1828	X20 digital signal module, 1 HIPERFACE interface, NetTime function	
	Required accessories	
	Bus modules	
X20BM11	X20 bus module, 24 VDC keyed, internal I/O power supply connected through	
X20BM15	X20 bus module, with node number switch, 24 VDC keyed, internal I/O power supply connected through	
	Terminal blocks	
X20TB12	X20 terminal block, 12-pin, 24 VDC keyed	

Table 1: X20DS1828 - Order data

1.3 Module description

This module is equipped with 1 HIPERFACE encoder interface. This module can be used to evaluate encoders installed in third-party motors as well as encoders for external axes (encoders that scan any machine movement).

Functions:

- [HIPERFACE](#)
- [SinCos encoders](#)
- [Diagnostic functions](#)
- [NetTime Technology](#)
- [Flatstream communication](#)

HIPERFACE

HIPERFACE is a standard that, like EnDat, combines the advantages of absolute and incremental position measurement and provides read/write parameter memory in the encoder. Due to the absolute position measurement (absolute position is read in serially), the homing procedure is usually omitted.

SinCos encoders

SinCos encoders with 1 V_{ss} are particularly common in linear drives and systems with high-resolution optical or magnetic position measuring systems. The module can process input signals with a frequency of up to 400 kHz.

Diagnostic functions

The input signals are monitored. This makes it possible to detect open circuits, conductor faults and failures in the encoder power supply.

NetTime timestamp for the position

It is not just the position value that is important for highly dynamic positioning tasks, but also the exact time the position is measured. The module is equipped with a NetTime function for this that supplies a timestamp for the recorded position with microsecond accuracy.

Flatstream communication

"Flatstream" was designed for X2X and POWERLINK networks and allows data transfer to be adapted to individual demands. This allows data to be transferred more efficiently than with standard cyclic polling.

2 Technical description

2.1 Technical data

Order number	X20DS1828
Short description	
I/O module	1x HIPERFACE interface
General information	
B&R ID code	0xAEC7
Status indicators	Counting direction, operating state, module status
Diagnostics	
Module run/error	Yes, using LED status indicator and software
Counting direction	Yes, using LED status indicator
Power consumption	
Bus	0.01 W
Internal I/O	1.3 W
Additional power dissipation caused by actuators (resistive) [W]	-
Type of signal lines	Shielded lines must be used for all signal lines.
Certifications	
CE	Yes
UKCA	Yes
ATEX	Zone 2, II 3G Ex nA nC IIA T5 Gc IP20, Ta (see X20 user's manual) FTZÜ 09 ATEX 0083X
UL	cULus E115267 Industrial control equipment
HazLoc	cCSAus 244665 Process control equipment for hazardous locations Class I, Division 2, Groups ABCD, T5
KC	Yes
Encoder inputs	
Angular position resolution	13-bit, with a signal of 1 V _{SS}
Encoder monitoring	Yes
Max. encoder cable length	10 m
Sine/Cosine inputs	
Signal transmission	Differential signals, symmetrical
Signal frequency	DC up to 200 kHz
Differential voltage	1 V _{SS}
Common-mode voltage	Max. ±10 V
Terminating resistor	120 Ω
Encoder power supply	
Output voltage	11 V
Load capacity	150 mA
Protective measures	
Overload-proof	Yes
Short-circuit proof	Yes
Parameter channel (RS485)	
Signal transmission	5 VDC differential signal, EiA RS485 standard
Transmission status	See the HIPERFACE specification.
Electrical properties	
Electrical isolation	Channel isolated from bus Channel not isolated from channel
Operating conditions	
Mounting orientation	
Horizontal	Yes
Vertical	Yes
Installation elevation above sea level	
0 to 2000 m	No limitation
>2000 m	Reduction of ambient temperature by 0.5°C per 100 m
Degree of protection per EN 60529	IP20

Table 2: X20DS1828 - Technical data


Technical description

Order number	X20DS1828
Ambient conditions	
Temperature	
Operation	
Horizontal mounting orientation	-25 to 60°C
Vertical mounting orientation	-25 to 50°C
Derating	See section "Derating".
Storage	-40 to 85°C
Transport	-40 to 85°C
Relative humidity	
Operation	5 to 95%, non-condensing
Storage	5 to 95%, non-condensing
Transport	5 to 95%, non-condensing
Mechanical properties	
Note	Order 1x terminal block X20TB12 separately. Order 1x bus module X20BM11 separately.
Pitch	12.5 ^{+0.2} mm

Table 2: X20DS1828 - Technical data

2.2 LED status indicators

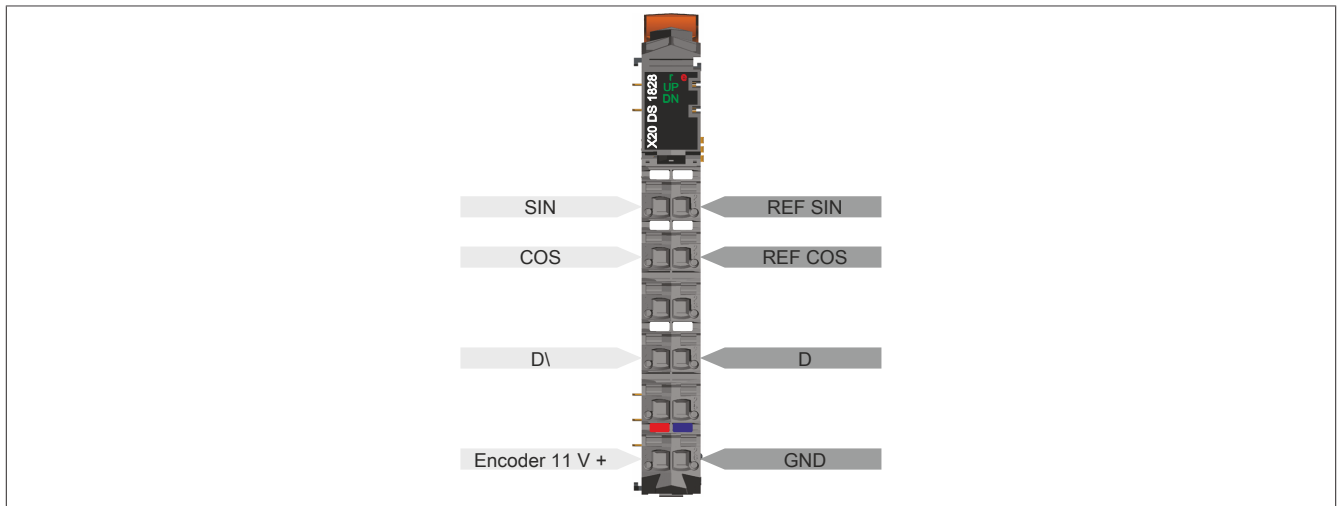
For a description of the various operating modes, see section "Additional information - Diagnostic LEDs" in the X20 system user's manual.

Figure	LED	Color	Status	Description
	r	Green	Off	No power to module
			Single flash	RESET mode
			Double flash	BOOT mode (during firmware update) ¹⁾
			Blinking	PREOPERATIONAL mode
			On	RUN mode
	e	Red	Off	No power to module or everything OK
			On	Error or reset state. Possible cause: • Encoder supply error
			Single flash	I/O error - Possible causes: • Sine/Cosine relative position error (open line) • Sine/Cosine absolute position error (reference)
			Double flash	System error. Possible causes: • HIPERFACE communication error
			Triple flash	I/O error and system error
			Single flash, inverted	Error or reset state and I/O error
			Double flash, inverted	Error or reset state and system error
			Triple flash, inverted	Error or reset state, I/O error and system error
	UP	Green	On	The "UP/DN" LEDs are lit depending on the rotational direction and the speed of the connected encoder. The "UP" LED indicates when the encoder position changes in the positive direction.
	DN	Green	On	The "DN" LED indicates when the encoder position changes in the negative direction.

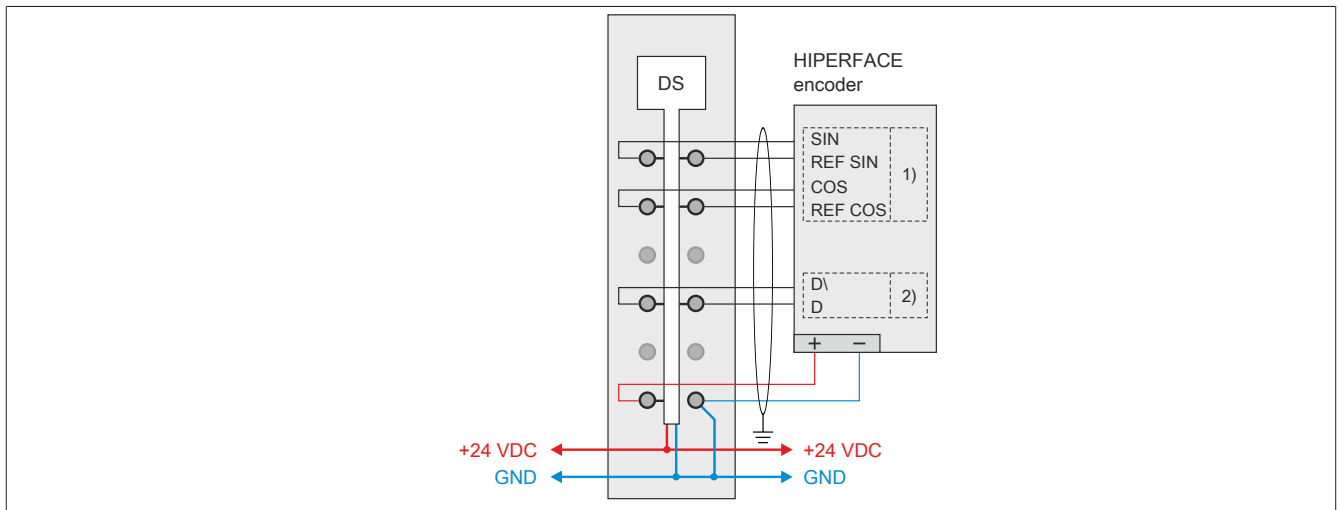
1) Depending on the configuration, a firmware update can take up to several minutes.

2.3 Pinout

Shielded cables must be used for all signal lines.



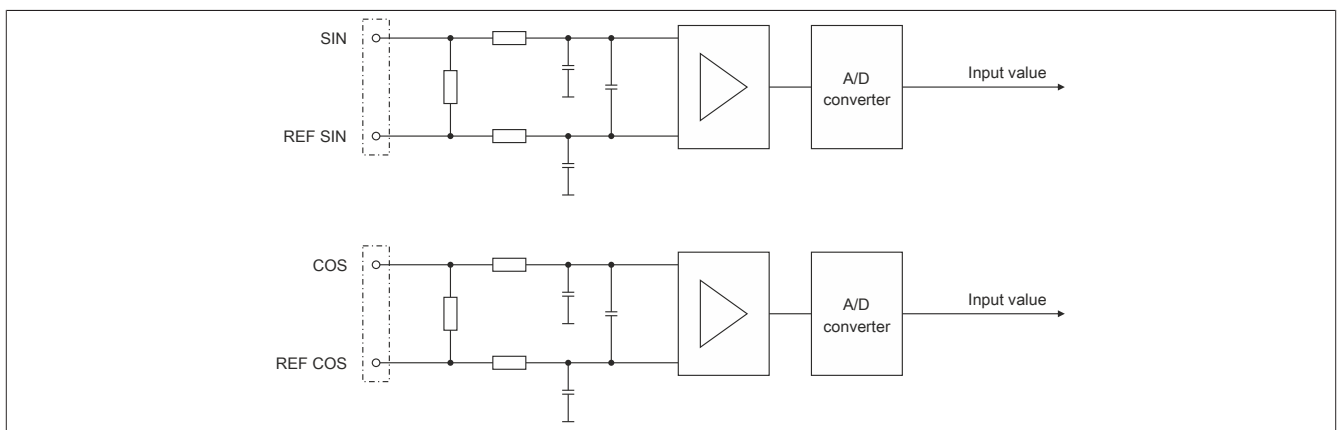
2.4 Connection example



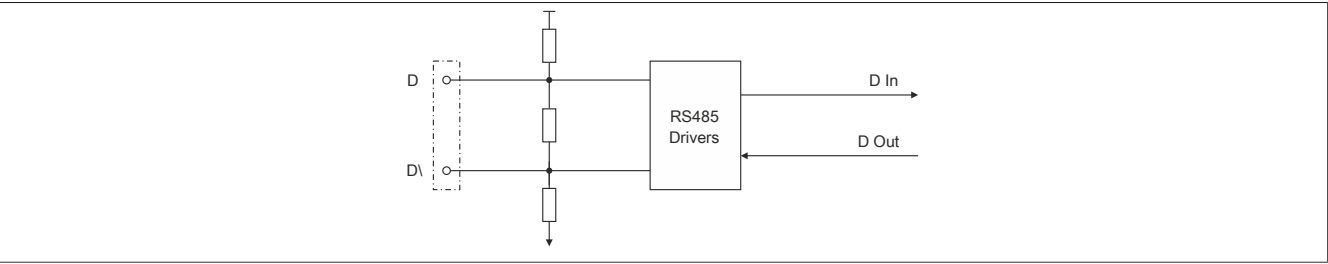
- 1) Process data channel
- 2) Parameter channel

2.5 Input circuit diagram

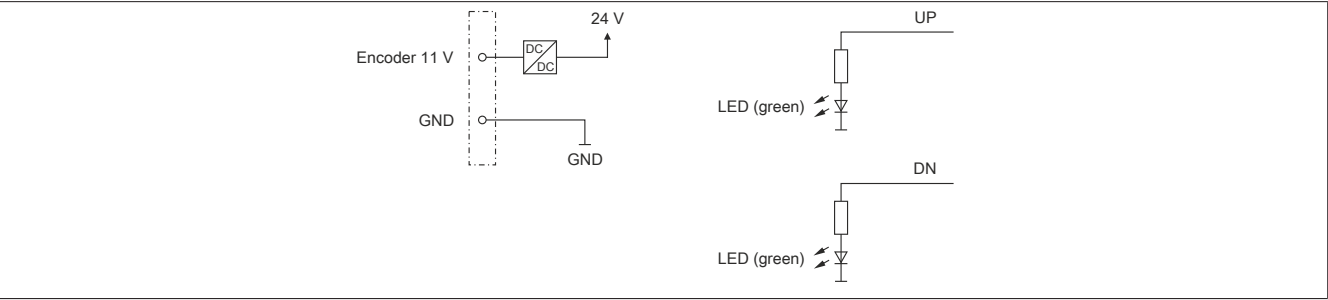
2.5.1 Diagram for the process data channel (sine-cosine track)



2.5.2 Circuit diagram for the parameter channel (RS485 interface)



2.5.3 Circuit diagram for the encoder supply and LEDs



2.6 Derating

There is no derating when operated below 55°C.

When operated above 55°C, the modules to the left and right of this module are permitted to have a maximum power dissipation of 1.15 W!

For an example of calculating the power dissipation of I/O modules, see section "Mechanical and electrical configuration - Power dissipation of I/O modules" in the X20 user's manual.

	X20 module		This module		X20 module	
	Power dissipation >1.15 W				Power dissipation >1.15 W	
	Neighboring X20 module				Neighboring X20 module	
	Power dissipation ≤1.15 W				Power dissipation ≤1.15 W	

2.7 Usage after the X20IF1091-1

If this module is operated after X2X Link module X20IF1091-1, delays may occur during the Flatstream transfer. For detailed information, see section "Data transfer on the Flatstream" in X20IF1091-1.

3 Function description

3.1 HIPERFACE

HIPERFACE is a standard developed by Max Stegmann GmbH (www.stegmann.de) that, like EnDat, combines the advantages of absolute and incremental position measurement and provides read/write parameter memory in the encoder. Due to the absolute position measurement (absolute position is read in serially), the homing procedure is usually omitted. If necessary, a multi-turn encoder should be used. To save costs, however, a single-turn encoder can also be used together with a reference switch. In this case, however, a homing procedure must be performed.

The incremental method enables the short delay times required for highly dynamic drives during position measurement. Thanks to the sinusoidal incremental signals and fine resolution in the HIPERFACE module, a very high position resolution is achieved despite moderate signal frequencies.

3.1.1 Configuring the digital interface

HIPERFACE is based on RS485 physics (EIA-485) and allows communication with up to 32 HIPERFACE slaves.

There are 2 different methods available for using the slave data in the control program. The essential slave values can be temporarily stored in the module and are then available to the controller. The module also provides Flatstream mode, which supports the entire range of commands per the HIPERFACE specification.

For detailed information about the HIPERFACE specification, see "Description of HIPERFACE".

Configuration

- Determining the position

The information from the digital and analog interfaces is required for high-resolution position detection. The HIPERFACE address of the station whose sine/cosine track is read into the module must be entered. If only one slave is connected, the broadcast address (255) can also be used.

- Capture position width

The number of bits for the absolute capture position width must be taken from the encoder manufacturer's data and usually consists of 3 values:

- 5 bits: Resolution of the digital absolute position
- 2^y bits: Number of sine/cosine periods per revolution
- x bits: HIPERFACE data format number of bits per revolution

The sum of the calculated values results in HfRefWidth ($5+x+y$).

Example:

When using motor 80MPH4.600S111-02, the position width of the reference station must have value 21 since the HIPERFACE encoder used measures the absolute position with a data width of 21 bits (the x = 12 most significant bits encode the multi-turn information, the next y = 4 bits count the sin/cos periods within a mechanical revolution and the z = 5 least significant bits encode the absolute position within a sin/cos period). If a value > 21 is set (e.g. 32), the module firmware detects a jump in the absolute position with every 0-crossing of the absolute position (overflow of the 21-bit position value from 0x00000000 to 0x0001FFFF or vice versa).



Information:

The registers are described in "[HIPERFACE - Configuring the digital interface](#)" on page 58.

3.1.2 Reading the identification

The digital interface makes it possible to precisely identify the HIPERFACE slave used. The parameter data can e.g. be queried when the controller is started up. If deviations from the previous hardware configuration occur, the program can react accordingly.

Configuration

The parameter to be read out is specified using 2 registers. One contains the address of the desired HIPERFACE slave and the other a code for the value to be read out.

Retrieval

After correct configuration, the selected parameter is cyclically transferred to the module. There are 8 registers available as buffer memory. The module confirms successful receipt by setting HfIdentOkByte.



Information:

The registers are described in "[HIPERFACE - Read ID](#)" on page 59.

3.1.3 Reading the additional encoder position

The module is able to read in up to 2 additional position values via the HIPERFACE interface and make them available to the controller. In addition to the position value, the corresponding timestamp is also processed.

Configuration

To read out the position value of the respective HIPERFACE slave, the address must be specified. 1 register per position value is provided for this purpose.

Retrieval

After correct configuration, the position value is cyclically transferred to the module. There are 5 registers per slave available as buffer memory. The module automatically generates the timestamp and confirms successful receipt by setting the corresponding AddPosOk0x bit. The HIPERFACE specification does not specify the format of the received parameter. The module therefore provides the position value and time in 2 variants. Which position register must be used for further processing depends on the HIPERFACE slave. The format of the timestamp can be freely selected by the user.



Information:

The registers are described in "[HIPERFACE - Reading additional encoder positions](#)" on page 61.

3.1.4 Reading additional analog values

The module is able to read in up to 4 analog values (16-bit) via the HIPERFACE interface and make them available to the controller. In addition to the buffered analog value, the corresponding timestamp is also processed.

Configuration

The analog value to read out is specified using 2 registers. One contains the address of the desired station and the other the channel for the parameter to read out. An overview with readable analog values is described in the data sheet of the respective slave.

Retrieval

After correct configuration, the analog value is cyclically transferred to the module. There are 5 registers available as buffer memory. The module automatically generates the timestamp and confirms successful receipt by setting the corresponding AnalogChOk0x bit. The HIPERFACE specification does not specify the format of the received parameter. The module therefore provides the value and time in 2 variants. The value register that must be used for further processing depends on the periphery. The format of the timestamp can be freely selected by the user.



Information:

The registers are described in "[HIPERFACE - Reading additional analog values](#)" on page 62.

Function description

3.1.5 HIPERFACE with FlatStream

HIPERFACE is an asynchronous interface capable of half-duplex communication. Various features have been included to ensure that signals are transmitted without errors.

- The user can choose to have a parity bit added when transmitting a data block.
- A checksum is sent together with a signal and evaluated by the receiver.
- The command to which the encoder is responding is repeated at the start of a response.

In Flatstream mode, the module works as a bridge between the controller and the HIPERFACE slave. HIPERFACE-specific algorithms have been implemented to monitor timeouts and handle checksums. These details are not accessible to the user during normal operation.

Additional information is provided in the "Description of HIPERFACE" document.

3.1.5.1 Overview of conventional HIPERFACE commands for FlatStream mode

Command byte [hex]	Command	Code0
0x42	Read position	
0x43	Set position	•
0x44	Read analog value	
0x46	Read counter	
0x47	Increment counter	
0x49	Delete counter	•
0x4A	Read data	
0x4B	Save data	
0x4C	Read status of a data field	
0x4D	Create data field	
0x4E	Read available memory area	
0x4F	Change access key	
0x50	Read encoder status	
0x52	Read nameplate	
0x53	Reset encoder	
0x55	Allocate encoder address	•
0x56	Read serial number and program version	
0x57	Configure serial interface	•

Code0 is a byte that was added to the transfer protocol for safety reasons. It protects important system parameters from being overwritten by mistake (default: Code0 = 0x55).

3.1.5.2 Read position (0x42)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x42	Command byte (read position)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x42	
3	Pos_HH	Response (data bytes)
4	Pos_HL	
5	Pos_LH	
6	Pos_LL	
Master		

3.1.5.3 Set position (0x43)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x43	Command byte (set position)
3	Pos_HH	New position (data bytes)
4	Pos_HL	
5	Pos_LH	
6	Pos_LL	
7	Code0	Safety byte in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x43	
Master		

3.1.5.4 Read analog value (0x44)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x44	Command byte (read analog value)
3	channel	Channel byte (selects desired analog value)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and channel byte (safety)
2	0x44	
3	channel	
4	Value_H	Value read
5	Value_L	
Master		

3.1.5.5 Read counter (0x46)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x46	Command byte (read counter)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x46	
3	Ctr_H	Counter value
4	Ctr_M	
5	Ctr_L	
Master		

Function description

3.1.5.6 Increment counter (0x47)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x47	Command byte (increment counter)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x47	
Master		

3.1.5.7 Clear counter (0x49)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x49	Command byte (clear counter)
3	Code0	Safety byte in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x49	
Master		

3.1.5.8 Read data (0x4A)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4A	Command byte (read data)
3	Data field	ID of data to be read:
4	Byte address	Number of the data field, start byte within the data field and number of bytes to be read
5	Count	
6	Access code	Access code in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and ID of data to be read (safety)
2	0x4A	
3	Data field	
4	Byte address	
5	Count	
6...n	Data1...n	Data to be read
Master		

3.1.5.9 Save data (0x4B)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4B	Command byte (save data)
3	Data field	ID of data to be saved:
4	Byte address	Number of the data field, start byte within the data field and number of bytes to be read
5	Count	
6	Access code	Access code in accordance with the HIPERFACE specification
7...x	Data1...n	Data to be saved
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and ID of data to be saved (safety)
2	0x4B	
3	Data field	
4	Byte address	
5	Count	
Master		

3.1.5.10 Read status of a data field (0x4C)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4C	Command byte (determine status of a data field)
3	Data field	Number of the data field
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and number of the data field (safety)
2	0x4C	
3	Data field	
4	Status	Access mode for queried data field
Master		

Function description

3.1.5.11 Create data field (0x4D)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4D	Command byte (create data field)
3	Data field	Number of the data field
4	Status	Access mode for the data field
5	Access code	Access code in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte, number of the data field and access mode of the data field (safety)
2	0x4D	
3	Data field	
4	Status	
Master		

3.1.5.12 Read available memory area (0x4E)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4E	Command byte (read available memory area)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x4E	
3	Free memory	Number of available 16-byte blocks
4	Number of data fields	Number of data fields
Master		

3.1.5.13 Change access key (0x4F)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x4F	Command byte (change access key)
3	Code number	Safety code from the slave manufacturer
4	Old code	
5	New code	
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and code number (safety)
2	0x4F	
3	Code number	
Master		

3.1.5.14 Read encoder status (0x50)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x50	Command byte (read encoder status)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x50	
3	Encoder status	Status byte as specified by the slave manufacturer
Master		

3.1.5.15 Read nameplate (0x52)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x52	Command byte (read nameplate)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x52	
3	RS485 settings	Nameplate in accordance with HIPERFACE specification: HIPERFACE configuration, type of encoder, size of memory and other options
4	Encoder type	
5	Size of EEPROM	
6	Options	
Master		

3.1.5.16 Encoder reset (0x53)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x53	Command byte (encoder reset)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
-	-	No response
Master		

Function description

3.1.5.17 Allocate encoder address (0x55)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x55	Command byte (allocate encoder address)
3	New address	New HIPERFACE address
4	Code0	Safety byte in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x55	
Master		

3.1.5.18 Read serial number and program version (0x56)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x56	Command byte (read serial number and program version)
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address and command byte (safety)
2	0x56	
3...11	Serial number	9 characters
12...n	Firmware version	Max. 20 characters
...n+8	Firmware date	8 characters (format: DD.MM.YY)
Master		

3.1.5.19 Configure serial interface (0x57)

Master command

Protocol bytes		Information
No.	Name	
Master		
1	Address	Address of the HIPERFACE slave
2	0x57	Command byte (configure serial interface)
3	RS485 settings	New baud rate in accordance with the HIPERFACE specification
4	Code0	Safety byte in accordance with the HIPERFACE specification
Slave		

Slave response

Protocol bytes		Information
No.	Name	
Slave		
1	Address	Repeated address, command byte and new baud rate (safety)
2	0x57	
3	RS485 settings	
Master		

3.2 SinCos encoders

The module has an analog interface for recording a differential sine, cosine and reference signal. This allows the position of a motor shaft to be read in combination with a sin/cos encoder. The position data received is processed in 2 different formats and provided with a timestamp.



Information:

The registers are described in "[Sin/Cos - Analog interface configuration](#)" on page 57.

3.2.1 Format of the SinCos signal

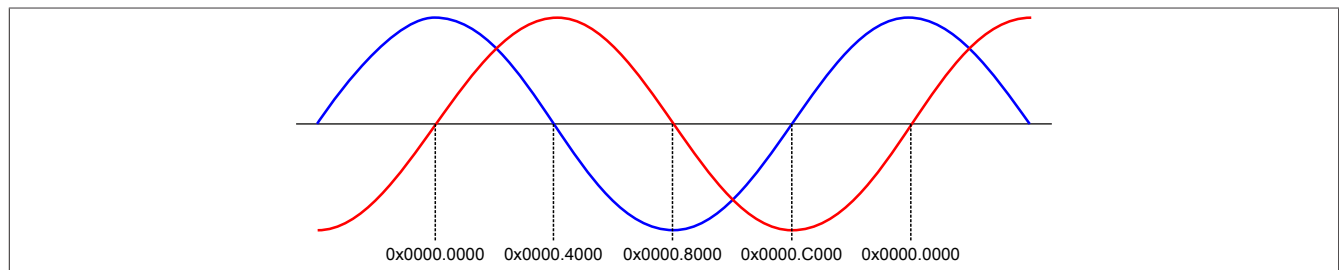
The absolute position of the encoder is resolved with 64-bit. The position value is stored in registers PositionHW and PositionLW. The upper 32 bits are in register PositionHW and the lower 32 bits in register PositionLW.

The low word of the position can be addressed separately as needed. However, this value can also be used as the default position value.

- PositionLW and Position are identical in function.
- PositionHW extends the integer range of PositionLW with additional multi-turn functionality.

64-bit register	PositionHW (unsigned)	PositionLW (unsigned)																
32-bit register	-	Position (signed)																
Format	Integer extension (to 48-bit)	Integer (16-bit)	Decimal places (with 13-bit resolution)															
Information		A full sine wave corresponds to one increment of the integer.	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
			x	x	x	x	x	x	x	x	x	x	x	x	x	x	0	0
			Attention: The lower 3 bits always contain the value 0.															
Word/DWord	DWord	Word 1	Word 0															

Relationship between sine curve (red) and decimal places:



3.3 Diagnostic functions

The module is able to diagnose error states. With this module, error diagnostics are performed in 2 ways:

- [Typical module diagnostics](#)
- [Typical HIPERFACE diagnostics](#)

Typical module diagnostics

The module can detect errors independently. It diagnoses 5 different errors or warnings. The error bits can be retrieved both individually and in packets.

- **Encoder power supply**
Power supply of the encoder impermissibly low.
- **Vss Sin/Cos**
The voltage value for the Sin/Cos track violates the configured limit values → See register "[SinCosVss-Min](#)" on page 57 or "[SinCosVssMax](#)" on page 57.
If an error is detected on the analog interface, the last correctly determined values remain valid. A time period can be set during which the module receives correct values again after the error state without further processing them internally. Only then will newly read-in correct analog values be recognized as valid.
- **Position error**
The determined position value violates internal requirements.
- **HIPERFACE - Communication**
Faulty communication of the HIPERFACE interface (RS485).
- **HIPERFACE - Reference warning**
The digital interface provides an absolute position value that can be used to precisely describe the position of the axis. At the start of a measurement, the position value is therefore referenced to this absolute value. Very fast incremental changes can be recorded via the analog interface. This way, the module can count the position value with high resolution. Both the analog and the digital signal are read in cyclically. If the incrementally determined value diverges from the absolute value during operation, the position must be referenced again and the warning is triggered and displayed.

Typical HIPERFACE diagnostics

The HIPERFACE standard already provides memory areas for error diagnostics. Error management has been adjusted in order to use error detection per the HIPERFACE standard. An additional register has been implemented in the module that processes this section of the encoder memory. The error memory is mirrored to the register in the module and can be interpreted by the user.

Error ID

The error ID specifies an error that has occurred. The error ID is not explicitly standardized, however, and must be looked up separately in the HIPERFACE slave manual. The module also diagnoses a timeout of the HIPERFACE interface. Error ID 255 is generated for this.



Information:

The registers are described in "[Error management](#)" on page 55.

3.4 NetTime Technology

NetTime refers to the ability to precisely synchronize and transfer system times between individual components of the controller or network (controller, I/O modules, X2X Link, POWERLINK, etc.).

This allows the moment that events occur to be determined system-wide with microsecond precision. Upcoming events can also be executed precisely at a specified moment.



3.4.1 Time information

Various time information is available in the controller or on the network:

- System time (on the PLC, Automation PC, etc.)
- X2X Link time (for each X2X Link network)
- POWERLINK time (for each POWERLINK network)
- Time data points of I/O modules

The NetTime is based on 32-bit counters, which are increased with microsecond resolution. The sign of the time information changes after 35 min, 47 s, 483 ms and 648 μ s; an overflow occurs after 71 min, 34 s, 967 ms and 296 μ s.

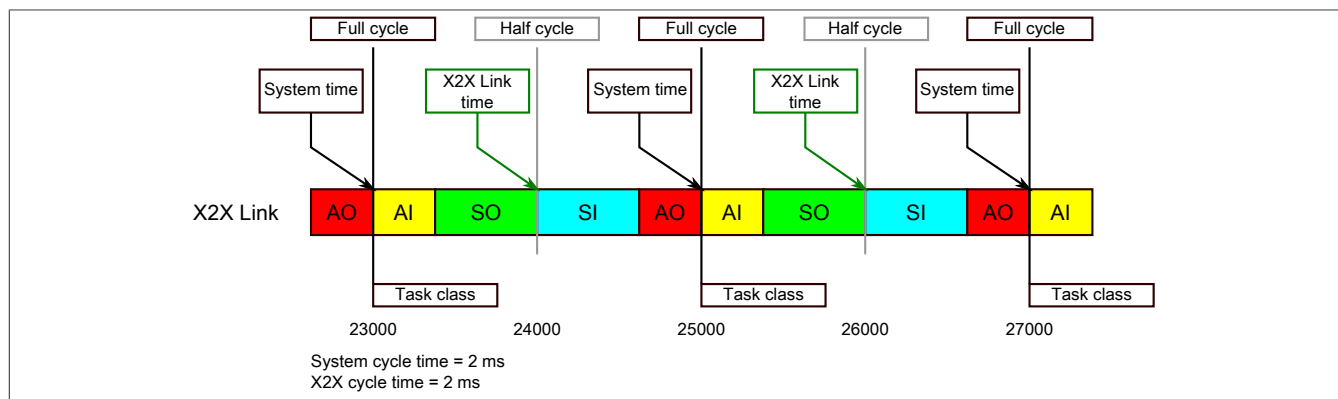
The initialization of the times is based on the system time during the startup of the X2X Link, the I/O modules or the POWERLINK interface.

Current time information in the application can also be determined via library AsIOTime.

3.4.1.1 Controller data points

The NetTime I/O data points of the controller are latched to each system clock and made available.

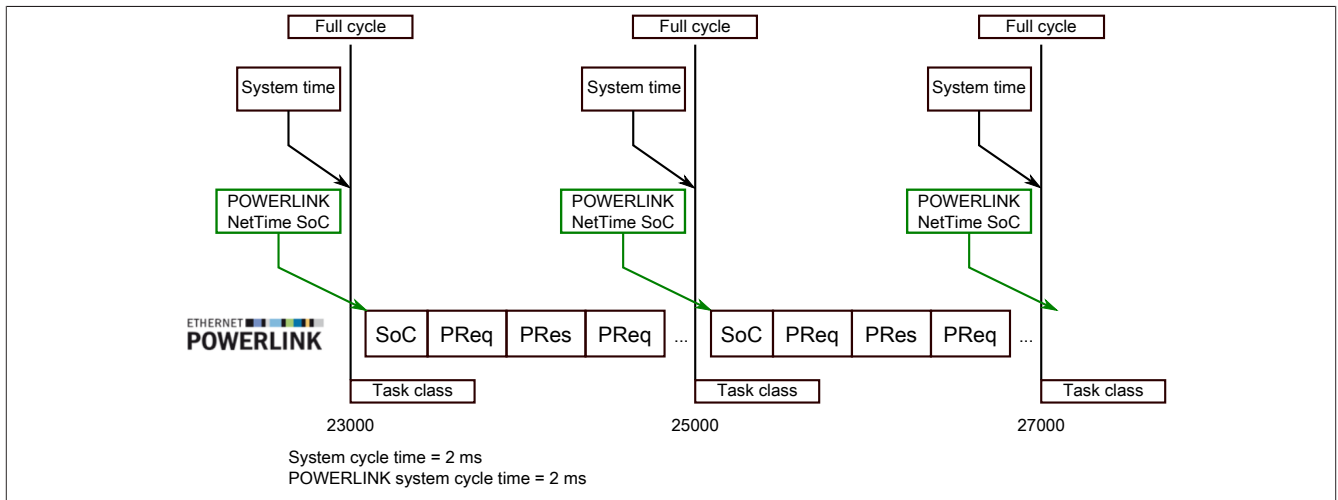
3.4.1.2 X2X Link - Reference time point



The reference time point on the X2X Link network is always calculated at the half cycle of the X2X Link cycle. This results in a difference between the system time and the X2X Link reference time point when the reference time is read out.

In the example above, this results in a difference of 1 ms, i.e. if the system time and X2X Link reference time are compared at time 25000 in the task, then the system time returns the value 25000 and the X2X Link reference time returns the value 24000.

3.4.1.3 POWERLINK - Reference time point

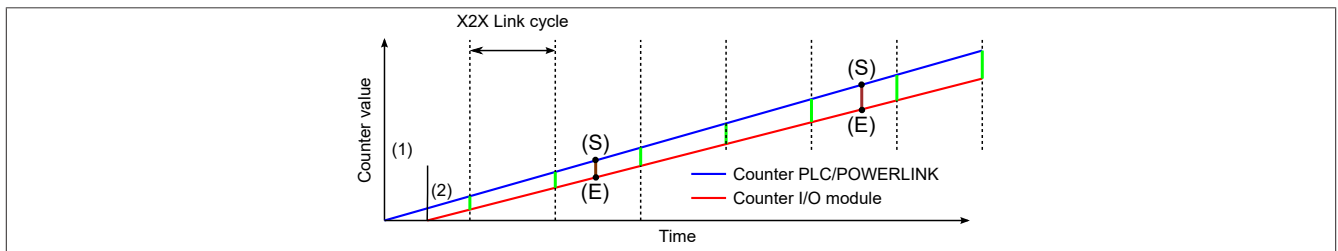


The POWERLINK reference time point is always calculated at the start of cycle (SoC) of the POWERLINK network. The SoC starts 20 µs after the system clock due to the system. This results in the following difference between the system time and the POWERLINK reference time:

POWERLINK reference time = System time - POWERLINK cycle time + 20 µs

In the example above, this means a difference of 1980 µs, i.e. if the system time and POWERLINK reference time are compared at time 25000 in the task, then the system time returns the value 25000 and the POWERLINK reference time returns the value 23020.

3.4.1.4 Synchronization of system time/POWERLINK time and I/O module



At startup, the internal counters for the controller/POWERLINK (1) and the I/O module (2) start at different times and increase the values with microsecond resolution.

At the beginning of each X2X Link cycle, the controller or POWERLINK network sends time information to the I/O module. The I/O module compares this time information with the module's internal time and forms a difference (green line) between the two times and stores it.

When a NetTime event (E) occurs, the internal module time is read out and corrected with the stored difference value (brown line). This means that the exact system moment (S) of an event can always be determined, even if the counters are not absolutely synchronous.

Note

The deviation from the clock signal is strongly exaggerated in the picture as a red line.

3.4.2 Timestamp functions

NetTime-capable modules provide various timestamp functions depending on the scope of functions. If a timestamp event occurs, the module immediately saves the current NetTime. After the respective data is transferred to the controller, including this precise moment, the controller can then evaluate the data using its own NetTime (or system time), if necessary.

For details, see the respective module documentation.

3.4.2.1 Time-based inputs

NetTime Technology can be used to determine the exact moment of a rising edge at an input. The rising and falling edges can also be detected and the duration between 2 events can be determined.

**Information:**

The determined moment always lies in the past.

3.4.2.2 Time-based outputs

NetTime Technology can be used to specify the exact moment of a rising edge on an output. The rising and falling edges can also be specified and a pulse pattern generated from them.

**Information:**

The specified time must always be in the future, and the set X2X Link cycle time must be taken into account for the definition of the moment.

3.4.2.3 Time-based measurements

NetTime Technology can be used to determine the exact moment of a measurement that has taken place. Both the starting and end moment of the measurement can be transmitted.

3.5 Flatstream communication

3.5.1 Introduction

B&R offers an additional communication method for some modules. "Flatstream" was designed for X2X and POWERLINK networks and allows data transfer to be adapted to individual demands. Although this method is not 100% real-time capable, it still allows data transfer to be handled more efficiently than with standard cyclic polling.

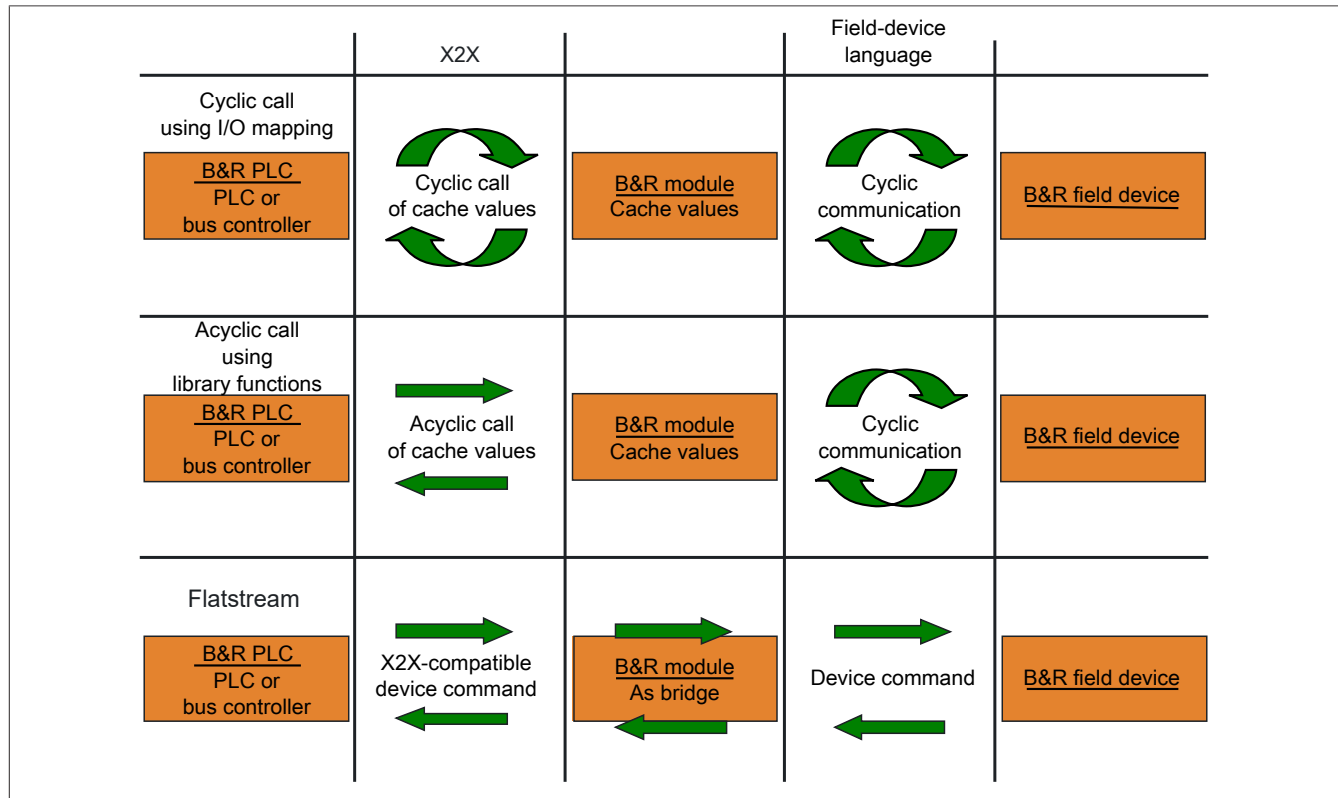


Figure 1: 3 types of communication

Flatstream extends cyclic and acyclic data queries. With Flatstream communication, the module acts as a bridge. The module is used to pass controller requests directly on to the field device.

3.5.2 Message, segment, sequence, MTU

The physical properties of the bus system limit the amount of data that can be transmitted during one bus cycle. With Flatstream communication, all messages are viewed as part of a continuous data stream. Long data streams must be broken down into several fragments that are sent one after the other. To understand how the receiver puts these fragments back together to get the original information, it is important to understand the difference between a message, a segment, a sequence and an MTU.

Message

A message refers to information exchanged between 2 communicating partner stations. The length of a message is not restricted by the Flatstream communication method. Nevertheless, module-specific limitations must be considered.

Segment (logical division of a message):

A segment has a finite size and can be understood as a section of a message. The number of segments per message is arbitrary. So that the recipient can correctly reassemble the transferred segments, each segment is preceded by a byte with additional information. This control byte contains information such as the length of a segment and whether the approaching segment completes the message. This makes it possible for the receiving station to interpret the incoming data stream correctly.

Sequence (how a segment must be arranged physically):

The maximum size of a sequence corresponds to the number of enabled Rx or Tx bytes (later: "MTU"). The transmitting station splits the transmit array into valid sequences. These sequences are then written successively to the MTU and transferred to the receiving station where they are lined up together again. The receiver stores the incoming sequences in a receive array, obtaining an image of the data stream in the process.

With Flatstream communication, the number of sequences sent are counted. Successfully transferred sequences must be acknowledged by the receiving station to ensure the integrity of the transfer.

MTU (Maximum Transmission Unit) - Physical transport:

MTU refers to the enabled USINT registers used with Flatstream. These registers can accept at least one sequence and transfer it to the receiving station. A separate MTU is defined for each direction of communication. OutputMTU defines the number of Flatstream Tx bytes, and InputMTU specifies the number of Flatstream Rx bytes. The MTUs are transported cyclically via the X2X Link network, increasing the load with each additional enabled USINT register.

Properties

Flatstream messages are not transferred cyclically or in 100% real time. Many bus cycles may be needed to transfer a particular message. Although the Rx and Tx registers are exchanged between the transmitter and the receiver cyclically, they are only processed further if explicitly accepted by register "InputSequence" or "OutputSequence".

Behavior in the event of an error (brief summary)

The protocol for X2X and POWERLINK networks specifies that the last valid values should be retained when disturbances occur. With conventional communication (cyclic/acyclic data queries), this type of error can generally be ignored.

In order for communication to also take place without errors using Flatstream, all of the sequences issued by the receiver must be acknowledged. If Forward functionality is not used, then subsequent communication is delayed for the length of the disturbance.

If Forward functionality is being used, the receiving station receives a transmission counter that is incremented twice. The receiver stops, i.e. it no longer returns any acknowledgments. The transmitting station uses SequenceAck to determine that the transfer was faulty and that all affected sequences must be repeated.

3.5.3 The Flatstream principle

Requirements

Before Flatstream can be used, the respective communication direction must be synchronized, i.e. both communication partners cyclically query the sequence counter on the remote station. This checks to see if there is new data that should be accepted.

Communication

If a communication partner wants to transmit a message to its remote station, it should first create a transmit array that corresponds to Flatstream conventions. This allows the Flatstream data to be organized very efficiently without having to block other important resources.

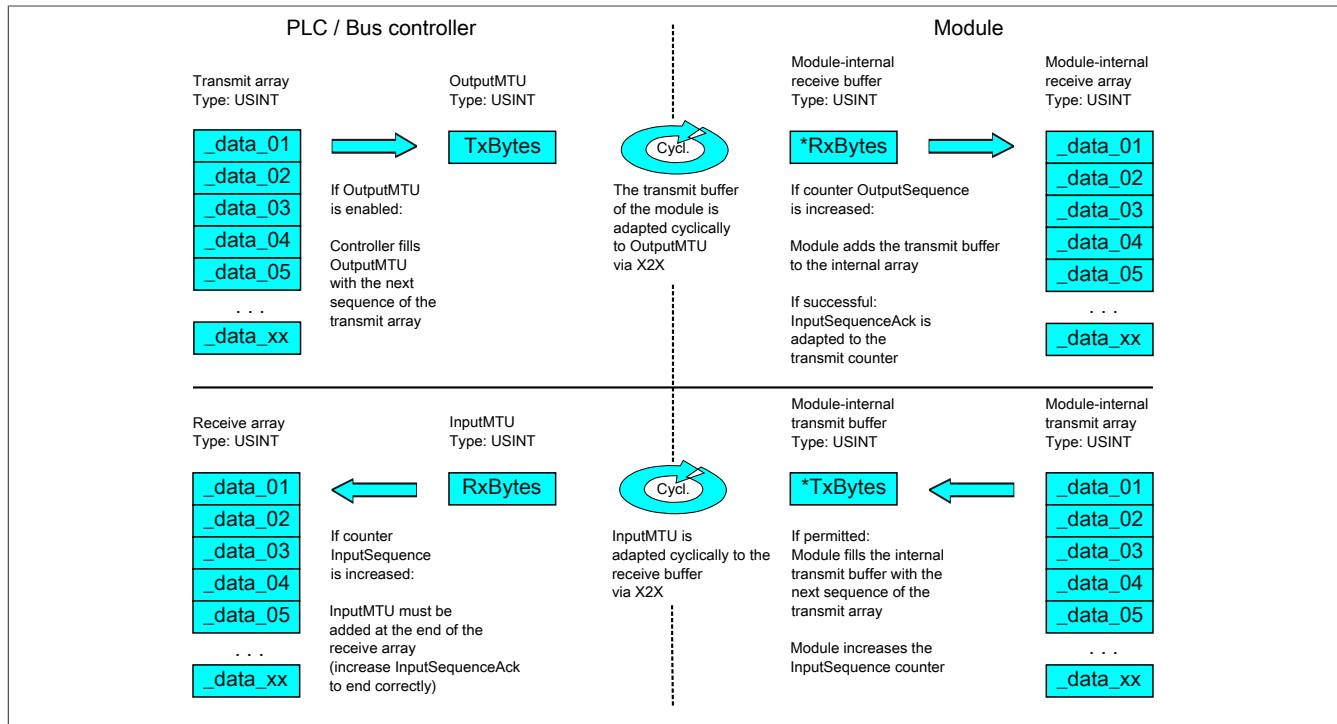


Figure 2: Flatstream communication

Procedure

The first thing that happens is that the message is broken into valid segments of up to 63 bytes, and the corresponding control bytes are created. The data is formed into a data stream made up of one control bytes per associated segment. This data stream can be written to the transmit array. The maximum size of each array element matches that of the enabled MTU so that one element corresponds to one sequence. If the array has been completely created, the transmitter checks whether the MTU is permitted to be re-filled. It then copies the first element of the array or the first sequence to the Tx byte registers. The MTU is transported to the receiver station via X2X Link and stored in the corresponding Rx byte registers. To signal that the data should be accepted by the receiver, the transmitter increases its SequenceCounter. If the communication direction is synchronized, the remote station detects the incremented SequenceCounter. The current sequence is appended to the receive array and acknowledged by SequenceAck. This acknowledgment signals to the transmitter that the MTU can now be refilled.

If the transfer is successful, the data in the receive array will correspond 100% to the data in the transmit array. During the transfer, the receiving station must detect and evaluate the incoming control bytes. A separate receive array should be created for each message. This allows the receiver to immediately begin further processing of messages that are completely transferred.

3.5.4 Registers for Flatstream mode

5 registers are available for configuring Flatstream. The default configuration can be used to transmit small amounts of data relatively easily.



Information:

The controller communicates directly with the field device via registers "OutputSequence" and "InputSequence" as well as the enabled Tx and RxBytes bytes. For this reason, the user must have sufficient knowledge of the communication protocol being used on the field device.

3.5.4.1 Flatstream configuration

To use Flatstream, the program sequence must first be expanded. The cycle time of the Flatstream routines must be set to a multiple of the bus cycle. Other program routines should be implemented in Cyclic #1 to ensure data consistency.

At the absolute minimum, registers "InputMTU" and "OutputMTU" must be set. All other registers are filled in with default values at the beginning and can be used immediately. These registers are used for additional options, e.g. to transfer data in a more compact way or to increase the efficiency of the general procedure.

The Forward registers extend the functionality of the Flatstream protocol. This functionality is useful for substantially increasing the Flatstream data rate, but it also requires quite a bit of extra work when creating the program sequence.



Information:

In the rest of this description, the names "OutputMTU" and "InputMTU" do not refer to the registers names. Instead, they are used as synonyms for the currently enabled Tx or Rx bytes.



Information:

The registers are described in ["Flatstream registers" on page 63](#).

Registers are described in section "Flatstream communication" in the respective data sheets.

3.5.4.2 Flatstream operation

When using Flatstream, the communication direction is very important. For transmitting data to a module (output direction), Tx bytes are used. For receiving data from a module (input direction), Rx bytes are used. Registers "OutputSequence" and "InputSequence" are used to control or secure communication, i.e. the transmitter uses them to give instructions to apply data and the receiver confirms a successfully transferred sequence.



Information:

The registers are described in ["Flatstream registers" on page 63](#).

Registers are described in section "Flatstream communication" in the respective data sheets.

3.5.4.2.1 Format of input and output bytes

Name:

"Format of Flatstream" in Automation Studio

On some modules, this function can be used to set how the Flatstream input and output bytes (Tx or Rx bytes) are transferred.

- **Packed:** Data is transferred as an array.
- **Byte-by-byte:** Data is transferred as individual bytes.

3.5.4.2.2 Transporting payload data and control bytes

The Tx and Rx bytes are cyclic registers used to transport the payload data and the necessary control bytes. The number of active Tx and Rx bytes is taken from the configuration of registers "OutputMTU" and "InputMTU", respectively.

In the user program, only the Tx and Rx bytes from the controller can be used. The corresponding counterparts are located in the module and are not accessible to the user. For this reason, the names were chosen from the point of view of the controller.

- "T" - "Transmit" → Controller transmits data to the module.
- "R" - "Receive" → Controller receives data from the module.

3.5.4.2.2.1 Control bytes

In addition to the payload data, the Tx and Rx bytes also transfer the necessary control bytes. These control bytes contain additional information about the data stream so that the receiver can reconstruct the original message from the transferred segments.

Bit structure of a control byte

Bit	Name	Value	Information
0 - 5	SegmentLength	0 - 63	Size of the subsequent segment in bytes (default: Max. MTU size - 1)
6	nextCBPos	0	Next control byte at the beginning of the next MTU
		1	Next control byte directly after the end of the current segment
7	MessageEndBit	0	Message continues after the subsequent segment
		1	Message ended by the subsequent segment

SegmentLength

The segment length lets the receiver know the length of the coming segment. If the set segment length is insufficient for a message, then the information must be distributed over several segments. In these cases, the actual end of the message is detected using bit 7 (control byte).



Information:

The control byte is not included in the calculation to determine the segment length. The segment length is only derived from the bytes of payload data.

nextCBPos

This bit indicates the position where the next control byte is expected. This information is especially important when using option "MultiSegmentMTU".

When using Flatstream communication with MultiSegmentMTUs, the next control byte is no longer expected in the first Rx byte of the subsequent MTU, but transferred directly after the current segment.

MessageEndBit

"MessageEndBit" is set if the subsequent segment completes a message. The message has then been completely transferred and is ready for further processing.



Information:

In the output direction, this bit must also be set if one individual segment is enough to hold the entire message. The module will only process a message internally if this identifier is detected.

The size of the message being transferred can be calculated by adding all of the message's segment lengths together.

Flatstream formula for calculating message length:

Message [bytes] = Segment lengths (all CBs without ME) + Segment length (of the first CB with ME)	CB	Control byte
	ME	MessageEndBit

3.5.4.2.3 Communication status

The communication status is determined via registers "OutputSequence" and "InputSequence".

- OutputSequence contains information about the communication status of the controller. It is written by the controller and read by the module.
- InputSequence contains information about the communication status of the module. It is written by the module and should only be read by the controller.

3.5.4.2.3.1 Relationship between OutputSequence and InputSequence

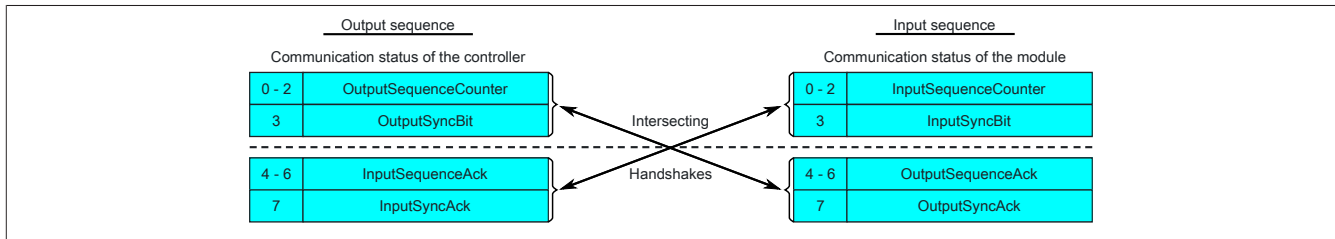


Figure 3: Relationship between OutputSequence and InputSequence

Registers OutputSequence and InputSequence are logically composed of 2 half-bytes. The low part indicates to the remote station whether a channel should be opened or whether data should be accepted. The high part is to acknowledge that the requested action was carried out.

SyncBit and SyncAck

If SyncBit and SyncAck are set in one communication direction, then the channel is considered "synchronized", i.e. it is possible to send messages in this direction. The status bit of the remote station must be checked cyclically. If SyncAck has been reset, then SyncBit on that station must be adjusted. Before new data can be transferred, the channel must be resynchronized.

SequenceCounter and SequenceAck

The communication partners cyclically check whether the low nibble on the remote station changes. When one of the communication partners finishes writing a new sequence to the MTU, it increments its SequenceCounter. The current sequence is then transmitted to the receiver, which acknowledges its receipt with SequenceAck. In this way, a "handshake" is initiated.



Information:

If communication is interrupted, segments from the unfinished message are discarded. All messages that were transferred completely are processed.

Function description

3.5.4.3 Synchronization

During synchronization, a communication channel is opened. It is important to make sure that a module is present and that the current value of SequenceCounter is stored on the station receiving the message. Flatstream can handle full-duplex communication. This means that both channels / communication directions can be handled separately. They must be synchronized independently so that simplex communication can theoretically be carried out as well.

Synchronization in the output direction (controller as the transmitter):

The corresponding synchronization bits (OutputSyncBit and OutputSyncAck) are reset. Because of this, Flatstream cannot be used at this point in time to transfer messages from the controller to the module.

Algorithm

1) The controller must write 000 to OutputSequenceCounter and reset OutputSyncBit. The controller must cyclically query the high nibble of register "InputSequence" (checks for 000 in OutputSequenceAck and 0 in OutputSyncAck). The module does not accept the current contents of InputMTU since the channel is not yet synchronized. The module matches OutputSequenceAck and OutputSyncAck to the values of OutputSequenceCounter and OutputSyncBit.
2) If the controller registers the expected values in OutputSequenceAck and OutputSyncAck, it is permitted to increment OutputSequenceCounter. The controller continues cyclically querying the high nibble of register "OutputSequence" (checks for 001 in OutputSequenceAck and 0 in InputSyncAck). The module does not accept the current contents of InputMTU since the channel is not yet synchronized. The module matches OutputSequenceAck and OutputSyncAck to the values of OutputSequenceCounter and OutputSyncBit.
3) If the controller registers the expected values in OutputSequenceAck and OutputSyncAck, it is permitted to increment OutputSequenceCounter. The controller continues cyclically querying the high nibble of register "OutputSequence" (checks for 001 in OutputSequenceAck and 1 in InputSyncAck). Note: Theoretically, data can be transferred from this point forward. However, it is still recommended to wait until the output direction is completely synchronized before transferring data. The module sets OutputSyncAck. The output direction is synchronized, and the controller can transmit data to the module.

Synchronization in the input direction (controller as the receiver):

The corresponding synchronization bits (InputSyncBit and InputSyncAck) are reset. Because of this, Flatstream cannot be used at this point in time to transfer messages from the module to the controller.

Algorithm

The module writes 000 to InputSequenceCounter and resets InputSyncBit. The module monitors the high nibble of register "OutputSequence" and expects 000 in InputSequenceAck and 0 in InputSyncAck.
1) The controller is not permitted to accept the current contents of InputMTU since the channel is not yet synchronized. The controller must match InputSequenceAck and InputSyncAck to the values of InputSequenceCounter and InputSyncBit. If the module registers the expected values in InputSequenceAck and InputSyncAck, it increments InputSequenceCounter. The module monitors the high nibble of register "OutputSequence" and expects 001 in InputSequenceAck and 0 in InputSyncAck.
2) The controller is not permitted to accept the current contents of InputMTU since the channel is not yet synchronized. The controller must match InputSequenceAck and InputSyncAck to the values of InputSequenceCounter and InputSyncBit. If the module registers the expected values in InputSequenceAck and InputSyncAck, it sets InputSyncBit. The module monitors the high nibble of register "OutputSequence" and expects 1 in InputSyncAck.
3) The controller is permitted to set InputSyncAck. Note: Theoretically, data could already be transferred in this cycle. If InputSyncBit is set and InputSequenceCounter has been increased by 1, the values in the enabled Rx bytes must be accepted and acknowledged (see also "Communication in the input direction"). The input direction is synchronized, and the module can transmit data to the controller.

3.5.4.4 Transmitting and receiving

If a channel is synchronized, then the remote station is ready to receive messages from the transmitter. Before the transmitter can send data, it must first create a transmit array in order to meet Flatstream requirements.

The transmitting station must also generate a control byte for each segment created. This control byte contains information about how the subsequent part of the data being transferred should be processed. The position of the next control byte in the data stream can vary. For this reason, it must be clearly defined at all times when a new control byte is being transmitted. The first control byte is always in the first byte of the first sequence. All subsequent positions are determined recursively.

Flatstream formula for calculating the position of the next control byte:

$$\text{Position (of the next control byte)} = \text{Current position} + 1 + \text{Segment length}$$

Example

3 autonomous messages (7 bytes, 2 bytes and 9 bytes) are being transmitted using an MTU with a width of 7 bytes. The rest of the configuration corresponds to the default settings.

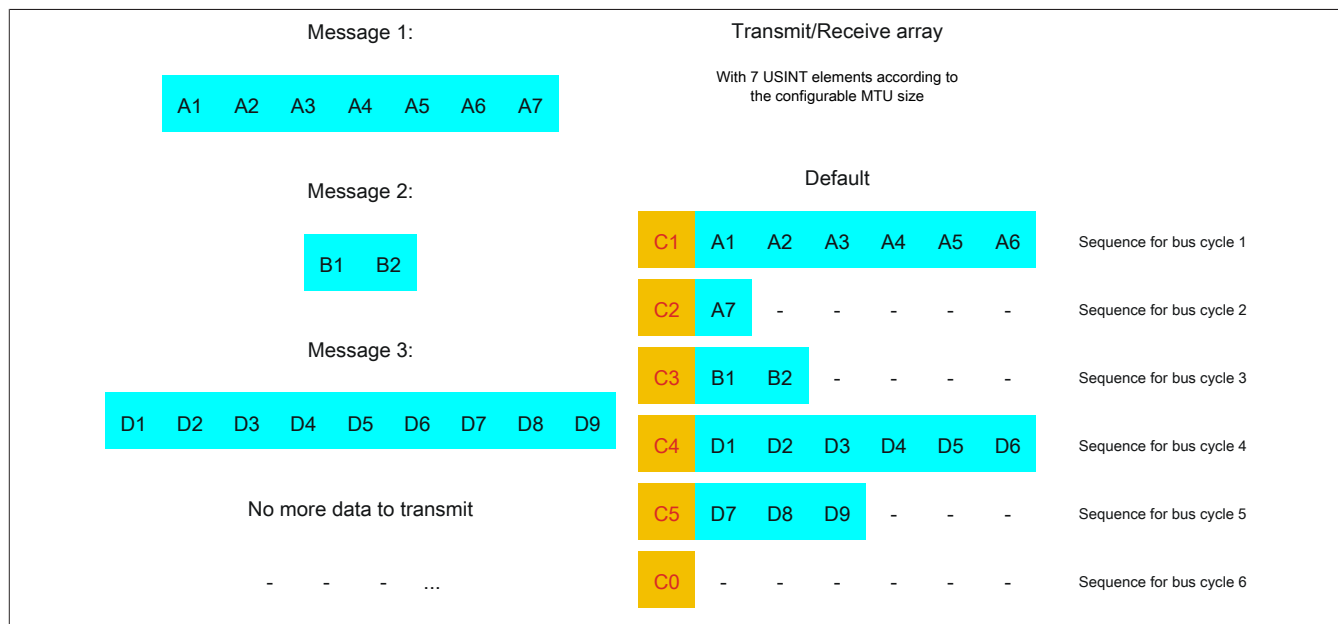


Figure 4: Transmit/Receive array (default)

Function description

The messages must first be split into segments. In the default configuration, it is important to ensure that each sequence can hold an entire segment, including the associated control byte. The sequence is limited to the size of the enable MTU. In other words, a segment must be at least 1 byte smaller than the MTU.

MTU = 7 bytes → Max. segment length = 6 bytes

- Message 1 (7 bytes)
 - ⇒ First segment = Control byte + 6 bytes of data
 - ⇒ Second segment = Control byte + 1 data byte
- Message 2 (2 bytes)
 - ⇒ First segment = Control byte + 2 bytes of data
- Message 3 (9 bytes)
 - ⇒ First segment = Control byte + 6 bytes of data
 - ⇒ Second segment = Control byte + 3 data bytes
- No more messages
 - ⇒ C0 control byte

A unique control byte must be generated for each segment. In addition, the C0 control byte is generated to keep communication on standby.

C0 (control byte 0)			C1 (control byte 1)			C2 (control byte 2)		
- SegmentLength (0)	=	0	- SegmentLength (6)	=	6	- SegmentLength (1)	=	1
- nextCBPos (0)	=	0	- nextCBPos (0)	=	0	- nextCBPos (0)	=	0
- MessageEndBit (0)	=	0	- MessageEndBit (0)	=	0	- MessageEndBit (1)	=	128
Control byte	Σ	0	Control byte	Σ	6	Control byte	Σ	129

Table 3: Flatstream determination of the control bytes for the default configuration example (part 1)

C3 (control byte 3)			C4 (control byte 4)			C5 (control byte 5)		
- SegmentLength (2)	=	2	- SegmentLength (6)	=	6	- SegmentLength (3)	=	3
- nextCBPos (0)	=	0	- nextCBPos (0)	=	0	- nextCBPos (0)	=	0
- MessageEndBit (1)	=	128	- MessageEndBit (0)	=	0	- MessageEndBit (1)	=	128
Control byte	Σ	130	Control byte	Σ	6	Control byte	Σ	131

Table 4: Flatstream determination of the control bytes for the default configuration example (part 2)

3.5.4.4.1 Transmitting data to a module (output)

When transmitting data, the transmit array must be generated in the application program. Sequences are then transferred one by one using Flatstream and received by the module.



Information:

Although all B&R modules with Flatstream communication always support the most compact transfers in the output direction, it is recommended to use the same design for the transfer arrays in both communication directions.

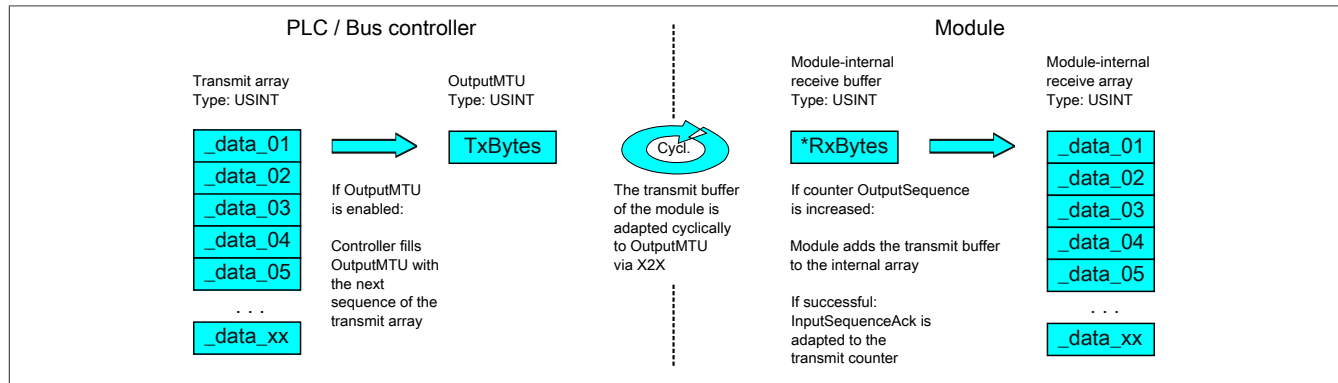


Figure 5: Flatstream communication (output)

Message smaller than OutputMTU

The length of the message is initially smaller than OutputMTU. In this case, one sequence would be sufficient to transfer the entire message and the necessary control byte.

Algorithm

Cyclic status query: - The module monitors OutputSequenceCounter.
0) Cyclic checks: - The controller must check OutputSyncAck. → If OutputSyncAck = 0: Reset OutputSyncBit and resynchronize the channel. - The controller must check whether OutputMTU is enabled. → If OutputSequenceCounter > InputSequenceAck: MTU is not enabled because the last sequence has not yet been acknowledged.
1) Preparation (create transmit array): - The controller must split up the message into valid segments and create the necessary control bytes. - The controller must add the segments and control bytes to the transmit array.
2) Transmit: - The controller transfers the current element of the transmit array to OutputMTU. → OutputMTU is transferred cyclically to the module's transmit buffer but not processed further. - The controller must increase OutputSequenceCounter.
Reaction: - The module accepts the bytes from the internal receive buffer and adds them to the internal receive array. - The module transmits acknowledgment and writes the value of OutputSequenceCounter to OutputSequenceAck.
3) Completion: - The controller must monitor OutputSequenceAck. → A sequence is only considered to have been transferred successfully if it has been acknowledged via OutputSequenceAck. In order to detect potential transfer errors in the last sequence as well, it is important to make sure that the length of the Completion phase is run through long enough.
Note: To monitor communication times exactly, the task cycles that have passed since the last increase of OutputSequenceCounter should be counted. In this way, the number of previous bus cycles necessary for the transfer can be measured. If the monitoring counter exceeds a predefined threshold, then the sequence can be considered lost. (The relationship of bus to task cycle can be influenced by the user so that the threshold value must be determined individually.) - Subsequent sequences are only permitted to be transmitted in the next bus cycle after the completion check has been carried out successfully.

Function description

Message larger than OutputMTU

The transmit array, which must be created in the program sequence, consists of several elements. The user must arrange the control and data bytes correctly and transfer the array elements one after the other. The transfer algorithm remains the same and is repeated starting at the point *Cyclic checks*.

General flowchart

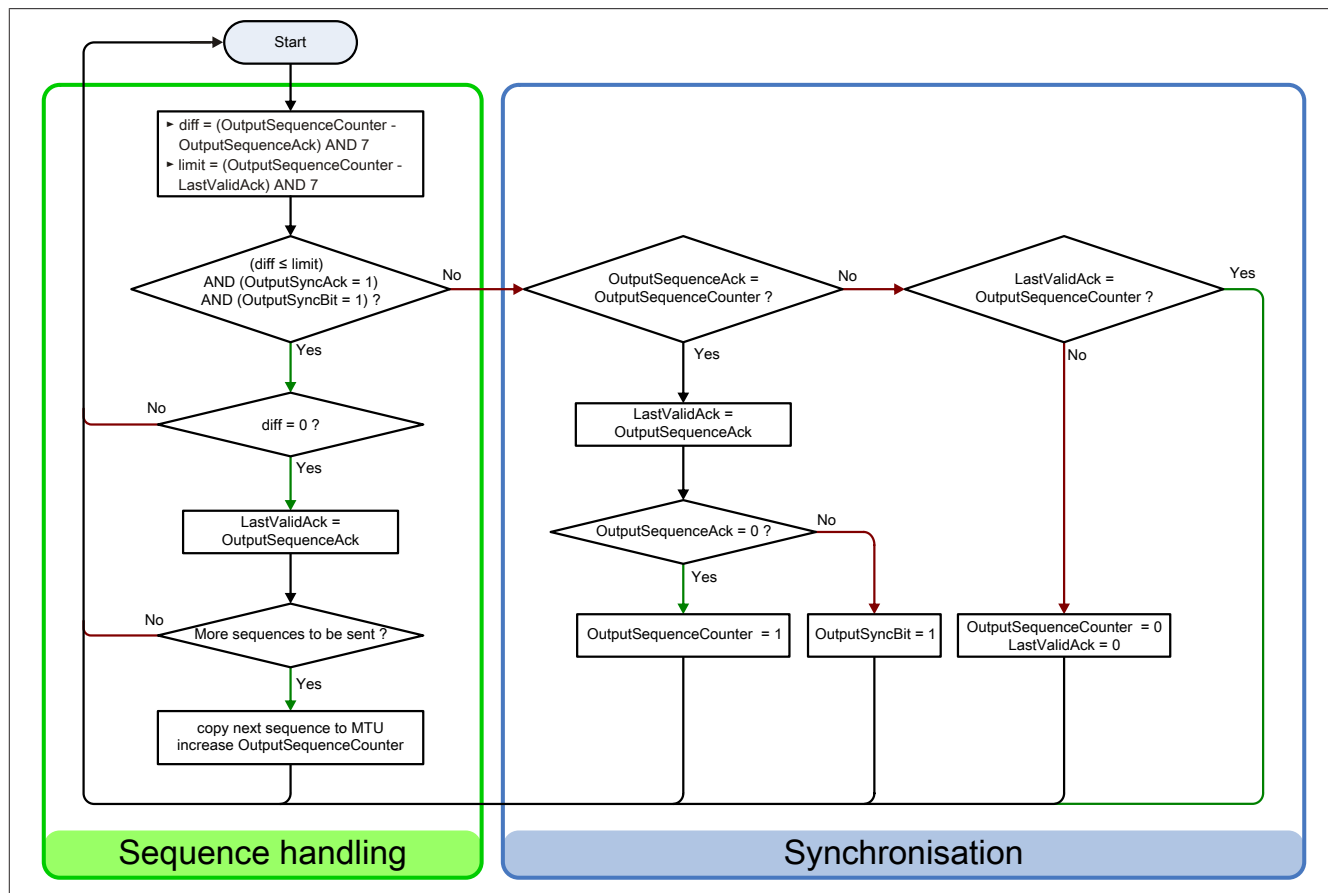


Figure 6: Flowchart for the output direction

3.5.4.4.2 Receiving data from a module (input)

When receiving data, the transmit array is generated by the module, transferred via Flatstream and must then be reproduced in the receive array. The structure of the incoming data stream can be set with the mode register. The algorithm for receiving the data remains unchanged in this regard.

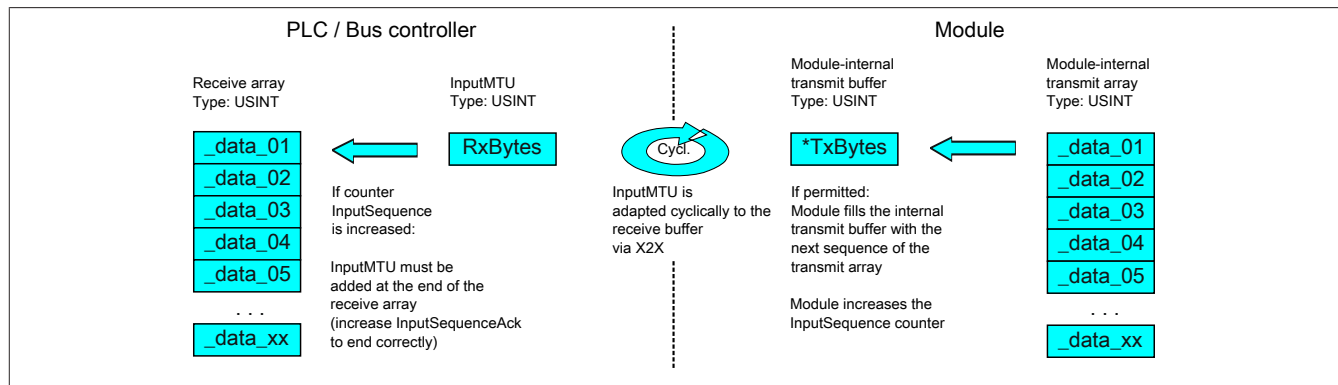


Figure 7: Flatstream communication (input)

Algorithm

0) Cyclic status query: - The controller must monitor InputSequenceCounter.
Cyclic checks: - The module checks InputSyncAck. - The module checks InputSequenceAck.
Preparation: - The module forms the segments and control bytes and creates the transmit array.
Action: - The module transfers the current element of the internal transmit array to the internal transmit buffer. - The module increases InputSequenceCounter.
1) Receiving (as soon as InputSequenceCounter is increased): - The controller must apply data from InputMTU and append it to the end of the receive array. - The controller must match InputSequenceAck to InputSequenceCounter of the sequence currently being processed.
Completion: - The module monitors InputSequenceAck. → A sequence is only considered to have been transferred successfully if it has been acknowledged via InputSequenceAck. - Subsequent sequences are only transmitted in the next bus cycle after the completion check has been carried out successfully.

General flowchart

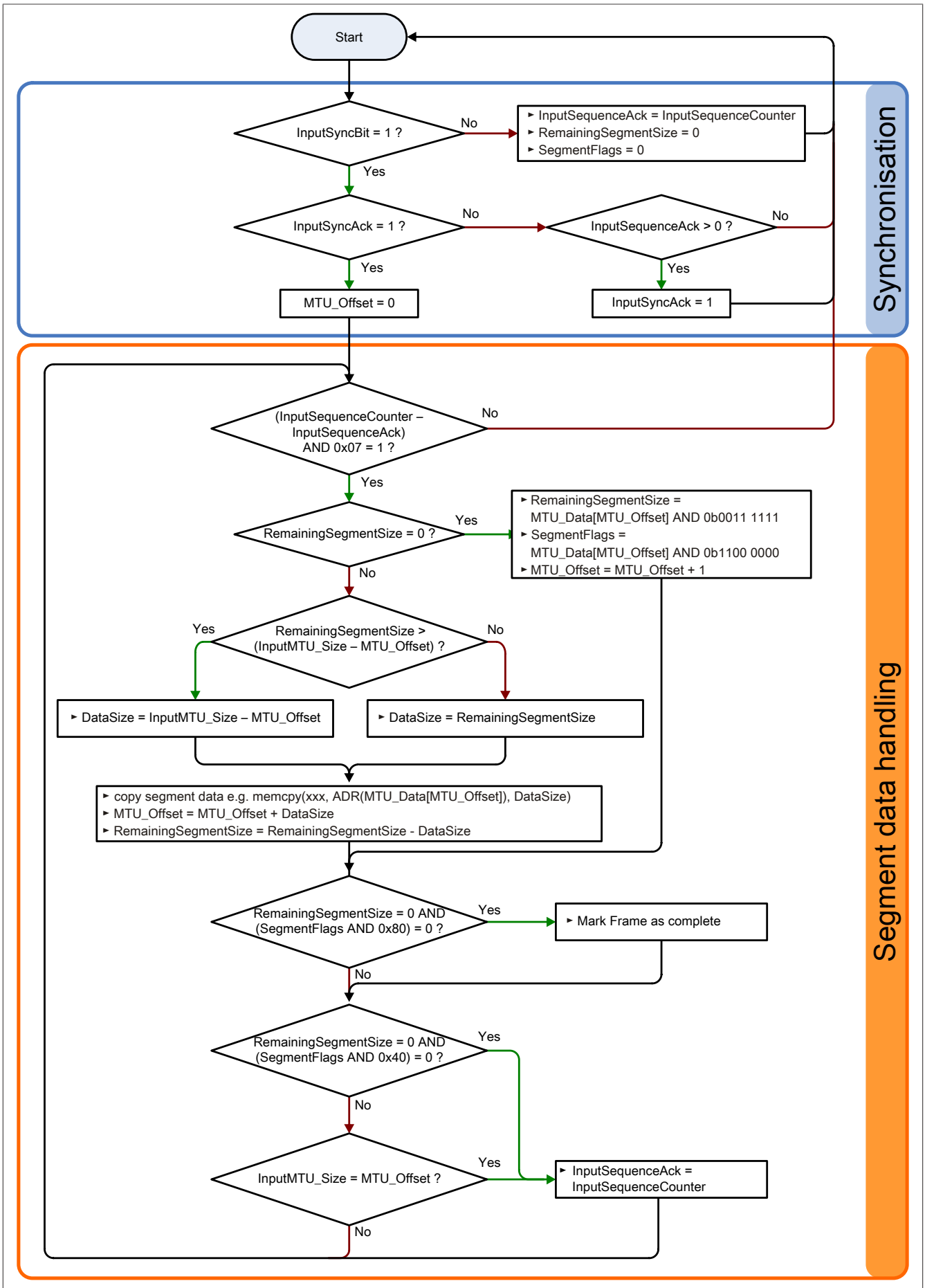


Figure 8: Flowchart for the input direction

3.5.4.4.3 Details

It is recommended to store transferred messages in separate receive arrays.

After a set MessageEndBit is transmitted, the subsequent segment should be added to the receive array. The message is then complete and can be passed on internally for further processing. A new/separate array should be created for the next message.



Information:

When transferring with MultiSegmentMTUs, it is possible for several small messages to be part of one sequence. In the program, it is important to make sure that a sufficient number of receive arrays can be managed. The acknowledge register is only permitted to be adjusted after the entire sequence has been applied.

If SequenceCounter is incremented by more than one counter, an error is present.

In this case, the receiver stops. All additional incoming sequences are ignored until the transmission with the correct SequenceCounter is retried. This response prevents the transmitter from receiving any more acknowledgments for transmitted sequences. The transmitter can identify the last successfully transferred sequence from the remote station's SequenceAck and continue the transfer from this point.



Information:

This situation is very unlikely when operating without "Forward" functionality.

Acknowledgments must be checked for validity.

If the receiver has successfully accepted a sequence, it must be acknowledged. The receiver takes on the value of SequenceCounter sent along with the transmission and matches SequenceAck to it. The transmitter reads SequenceAck and registers the successful transmission. If the transmitter acknowledges a sequence that has not yet been dispatched, then the transfer must be interrupted and the channel resynchronized. The synchronization bits are reset and the current/incomplete message is discarded. It must be sent again after the channel has been resynchronized.

3.5.4.5 Flatstream mode

In the input direction, the transmit array is generated automatically. Flatstream mode offers several options to the user that allow an incoming data stream to have a more compact arrangement. These include:

- [Standard](#)
- [MultiSegmentMTU allowed](#)
- [Large segments allowed:](#)

Once enabled, the program code for evaluation must be adapted accordingly.



Information:

All B&R modules that offer Flatstream mode support options "Large segments" and "MultiSegmentMTU" in the output direction. Compact transfer must be explicitly allowed only in the input direction.

Standard

By default, both options relating to compact transfer in the input direction are disabled.

1. The module only forms segments that are at least one byte smaller than the enabled MTU. Each sequence begins with a control byte so that the data stream is clearly structured and relatively easy to evaluate.
2. Since a Flatstream message is permitted to be any length, the last segment of the message frequently does not fill up all of the MTU's space. By default, the remaining bytes during this type of transfer cycle are not used.

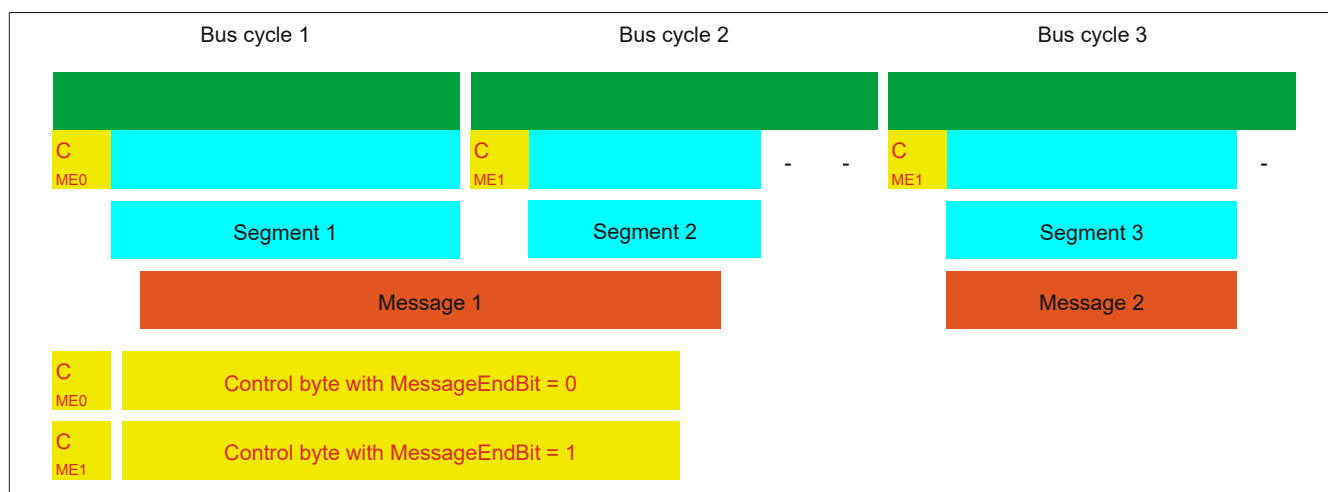


Figure 9: Message arrangement in the MTU (default)

MultiSegmentMTU allowed

With this option, InputMTU is completely filled (if enough data is pending). The previously unfilled Rx bytes transfer the next control bytes and their segments. This allows the enabled Rx bytes to be used more efficiently.

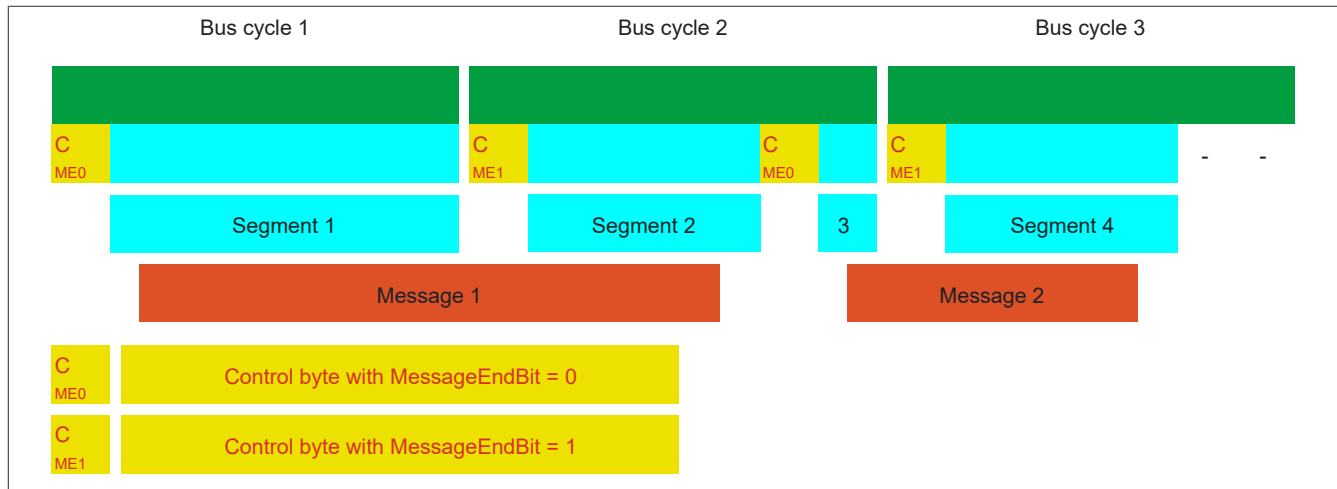


Figure 10: Arrangement of messages in the MTU (MultiSegmentMTU)

Large segments allowed:

When transferring very long messages or when enabling only very few Rx bytes, then a great many segments must be created by default. The bus system is more stressed than necessary since an additional control byte must be created and transferred for each segment. With option "Large segments", the segment length is limited to 63 bytes independently of InputMTU. One segment is permitted to stretch across several sequences, i.e. it is possible for "pure" sequences to occur without a control byte.



Information:

It is still possible to split up a message into several segments, however. If this option is used and messages with more than 63 bytes occur, for example, then messages can still be split up among several segments.

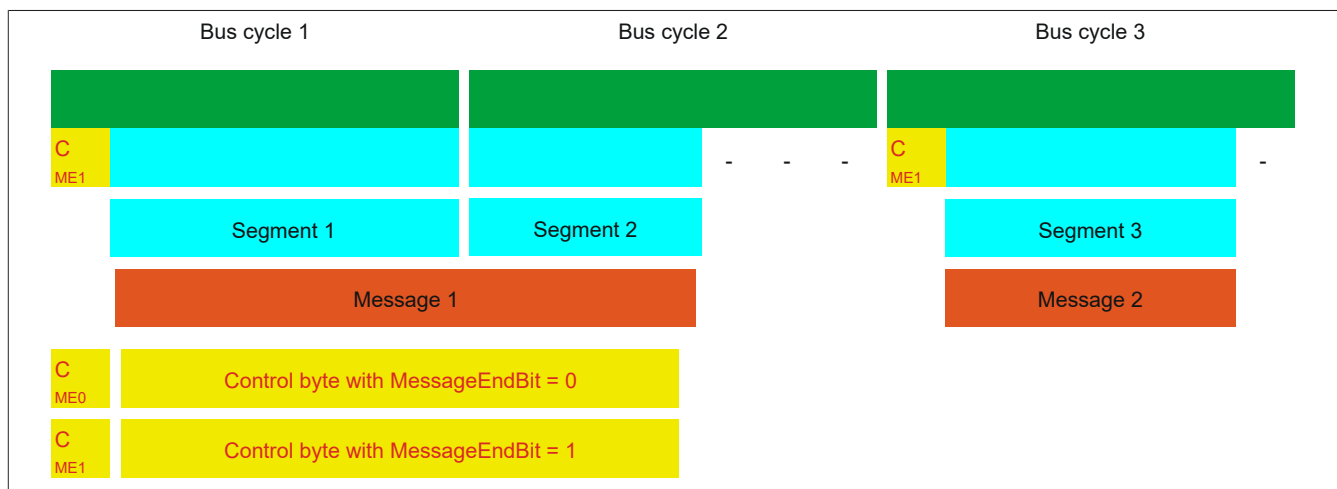


Figure 11: Arrangement of messages in the MTU (large segments)

Function description

Using both options

Using both options at the same time is also permitted.

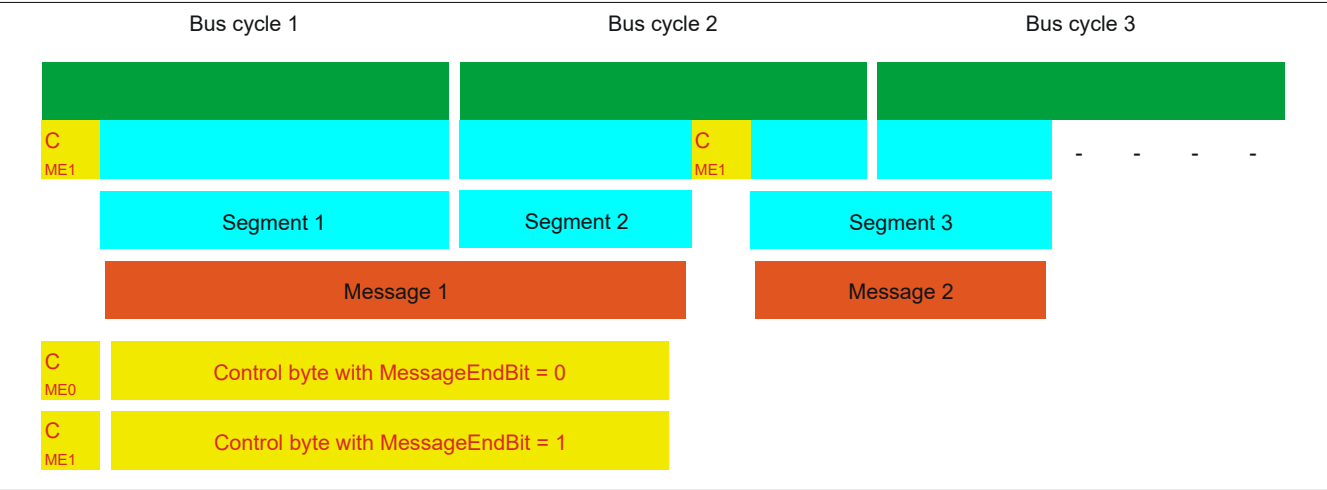


Figure 12: Arrangement of messages in the MTU (large segments and MultiSegmentMTU)

3.5.4.6 Adjusting the Flatstream

If the way messages are structured is changed, then the way data in the transmit/receive array is arranged is also different. The following changes apply to the example given earlier.

MultiSegmentMTU

If MultiSegmentMTUs are allowed, then "open positions" in an MTU can be used. These "open positions" occur if the last segment in a message does not fully use the entire MTU. MultiSegmentMTUs allow these bits to be used to transfer the subsequent control bytes and segments. In the program sequence, the "nextCB-Pos" bit in the control byte is set so that the receiver can correctly identify the next control byte.

Example

3 autonomous messages (7 bytes, 2 bytes and 9 bytes) are being transmitted using an MTU with a width of 7 bytes. The configuration allows the transfer of MultiSegmentMTUs.

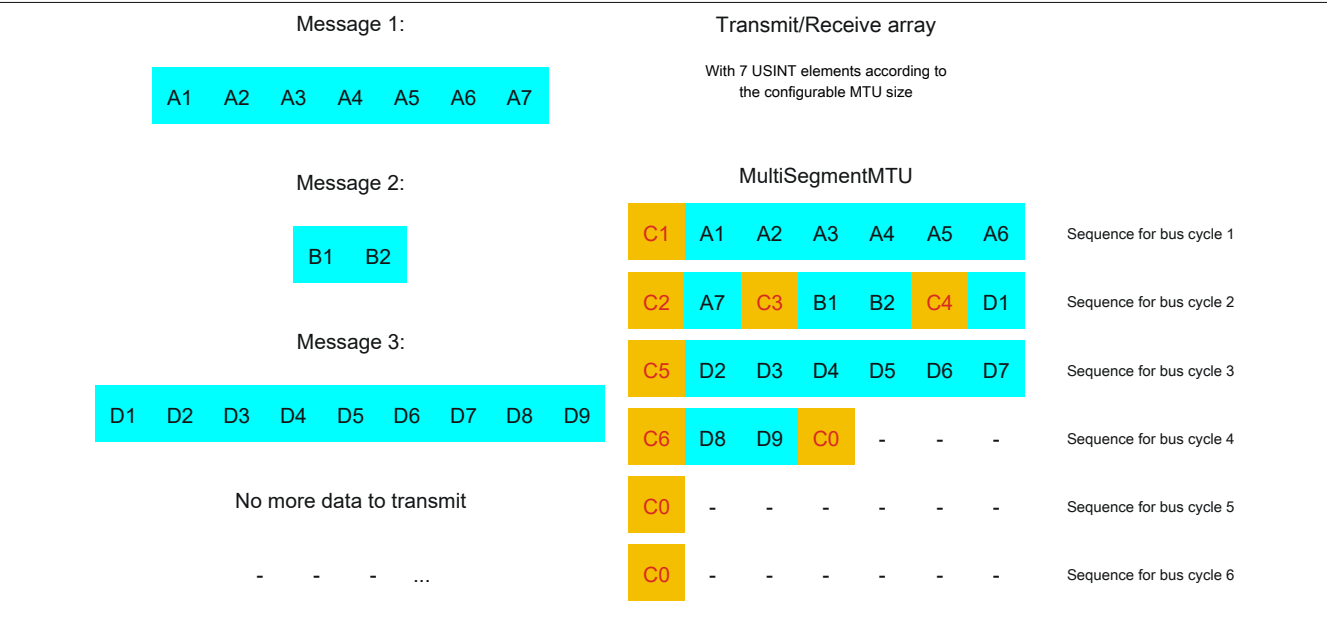


Figure 13: Transmit/Receive array (MultiSegmentMTU)

The messages must first be split into segments. As in the default configuration, it is important for each sequence to begin with a control byte. The free bits in the MTU at the end of a message are filled with data from the following message, however. With this option, the "nextCBPos" bit is always set if payload data is transferred after the control byte.

MTU = 7 bytes → Max. segment length = 6 bytes

- Message 1 (7 bytes)
 - ⇒ First segment = Control byte + 6 bytes of data (MTU full)
 - ⇒ Second segment = Control byte + 1 byte of data (MTU still has 5 open bytes)
- Message 2 (2 bytes)
 - ⇒ First segment = Control byte + 2 bytes of data (MTU still has 2 open bytes)
- Message 3 (9 bytes)
 - ⇒ First segment = Control byte + 1 byte of data (MTU full)
 - ⇒ Second segment = Control byte + 6 bytes of data (MTU full)
 - ⇒ Third segment = Control byte + 2 bytes of data (MTU still has 4 open bytes)
- No more messages
 - ⇒ C0 control byte

A unique control byte must be generated for each segment. In addition, the C0 control byte is generated to keep communication on standby.

C1 (control byte 1)			C2 (control byte 2)			C3 (control byte 3)		
- SegmentLength (6)	=	6	- SegmentLength (1)	=	1	- SegmentLength (2)	=	2
- nextCBPos (1)	=	64	- nextCBPos (1)	=	64	- nextCBPos (1)	=	64
- MessageEndBit (0)	=	0	- MessageEndBit (1)	=	128	- MessageEndBit (1)	=	128
Control byte	Σ	70	Control byte	Σ	193	Control byte	Σ	194

Table 5: Flatstream determination of the control bytes for the MultiSegmentMTU example (part 1)



Warning!

The second sequence is only permitted to be acknowledged via SequenceAck if it has been completely processed. In this example, there are 3 different segments within the second sequence, i.e. the program must include enough receive arrays to handle this situation.



Mise en garde !

La deuxième séquence ne peut être acquittée via SequenceAck que si elle a été entièrement traitée. Dans cet exemple, il y a 3 segments différents dans la deuxième séquence, c'est-à-dire que le programme doit inclure suffisamment de tableaux de réception pour gérer cette situation.

C4 (control byte 4)			C5 (control byte 5)			C6 (control byte 6)		
- SegmentLength (1)	=	1	- SegmentLength (6)	=	6	- SegmentLength (2)	=	2
- nextCBPos (6)	=	6	- nextCBPos (1)	=	64	- nextCBPos (1)	=	64
- MessageEndBit (0)	=	0	- MessageEndBit (1)	=	0	- MessageEndBit (1)	=	128
Control byte	Σ	7	Control byte	Σ	70	Control byte	Σ	194

Table 6: Flatstream determination of the control bytes for the MultiSegmentMTU example (part 2)

Function description

Large segments

Segments are limited to a maximum of 63 bytes. This means they can be larger than the active MTU. These large segments are divided among several sequences when transferred. It is possible for sequences to be completely filled with payload data and not have a control byte.



Information:

It is still possible to subdivide a message into several segments so that the size of a data packet does not also have to be limited to 63 bytes.

Example

3 autonomous messages (7 bytes, 2 bytes and 9 bytes) are being transmitted using an MTU with a width of 7 bytes. The configuration allows the transfer of large segments.

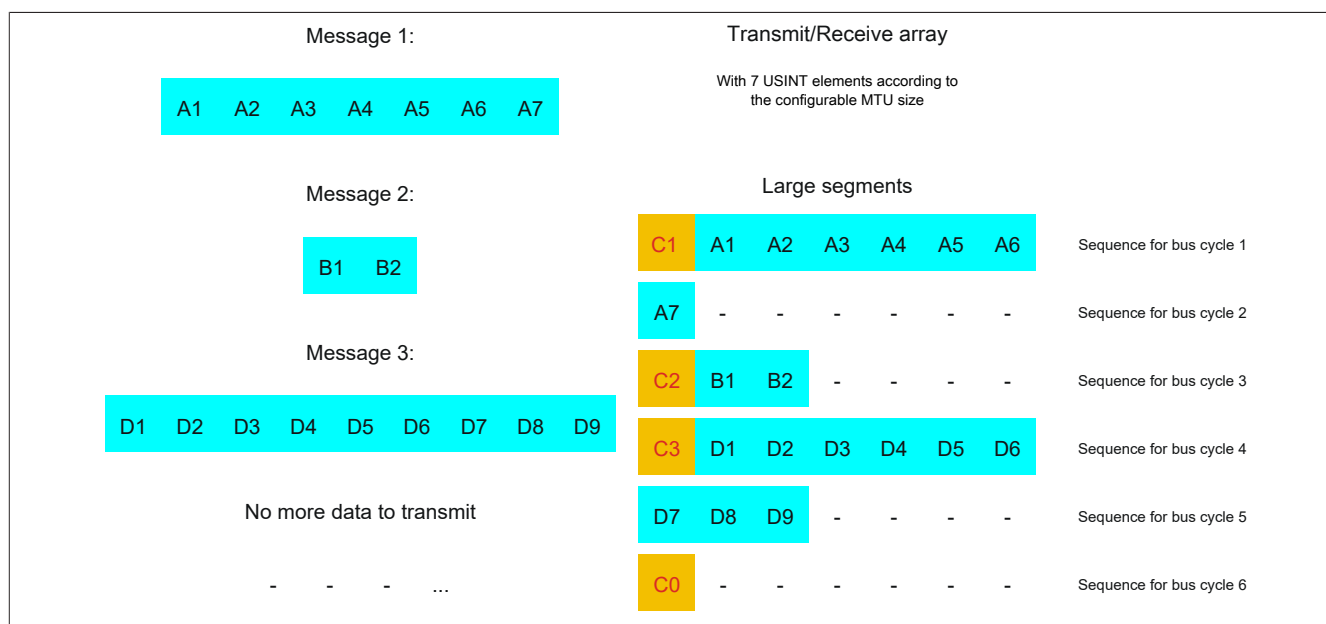


Figure 14: Transmit/receive array (large segments)

The messages must first be split into segments. The ability to form large segments means that messages are split up less frequently, which results in fewer control bytes generated.

Large segments allowed → Max. segment length = 63 bytes

- Message 1 (7 bytes)
 - ⇒ First segment = Control byte + 7 bytes of data
- Message 2 (2 bytes)
 - ⇒ First segment = Control byte + 2 bytes of data
- Message 3 (9 bytes)
 - ⇒ First segment = Control byte + 9 bytes of data
- No more messages
 - ⇒ C0 control byte

A unique control byte must be generated for each segment. In addition, the C0 control byte is generated to keep communication on standby.

C1 (control byte 1)			C2 (control byte 2)			C3 (control byte 3)		
- SegmentLength (7)	=	7	- SegmentLength (2)	=	2	- SegmentLength (9)	=	9
- nextCBPos (0)	=	0	- nextCBPos (0)	=	0	- nextCBPos (0)	=	0
- MessageEndBit (1)	=	128	- MessageEndBit (1)	=	128	- MessageEndBit (1)	=	128
Control byte	Σ	135	Control byte	Σ	130	Control byte	Σ	137

Table 7: Flatstream determination of the control bytes for the large segment example

Large segments and MultiSegmentMTU

Example

3 autonomous messages (7 bytes, 2 bytes and 9 bytes) are being transmitted using an MTU with a width of 7 bytes. The configuration allows transfer of large segments as well as MultiSegmentMTUs.

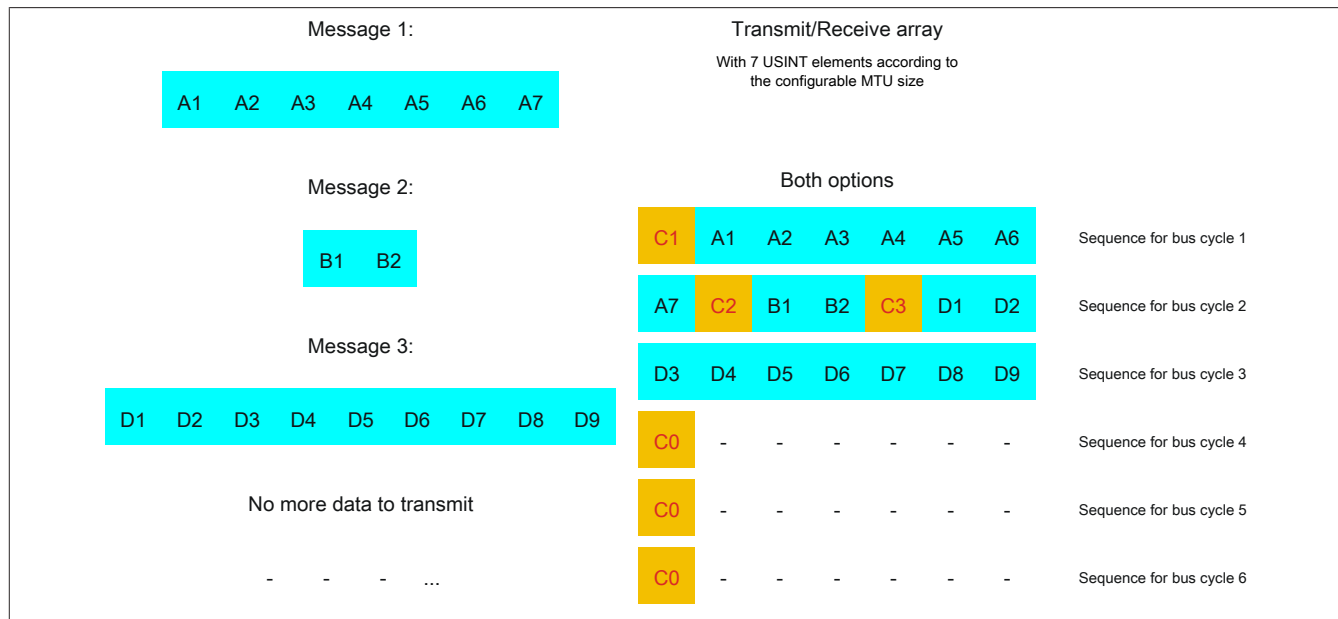


Figure 15: Transmit/Receive array (large segments and MultiSegmentMTU)

The messages must first be split into segments. If the last segment of a message does not completely fill the MTU, it is permitted to be used for other data in the data stream. Bit "nextCBPos" must always be set if the control byte belongs to a segment with payload data.

The ability to form large segments means that messages are split up less frequently, which results in fewer control bytes generated. Control bytes are generated in the same way as with option "Large segments".

Large segments allowed → Max. segment length = 63 bytes

- Message 1 (7 bytes)
 - ⇒ First segment = Control byte + 7 bytes of data
- Message 2 (2 bytes)
 - ⇒ First segment = Control byte + 2 bytes of data
- Message 3 (9 bytes)
 - ⇒ First segment = Control byte + 9 bytes of data
- No more messages
 - ⇒ C0 control byte

A unique control byte must be generated for each segment. In addition, the C0 control byte is generated to keep communication on standby.

C1 (control byte 1)			C2 (control byte 2)			C3 (control byte 3)		
- SegmentLength (7)	=	7	- SegmentLength (2)	=	2	- SegmentLength (9)	=	9
- nextCBPos (0)	=	0	- nextCBPos (0)	=	0	- nextCBPos (0)	=	0
- MessageEndBit (1)	=	128	- MessageEndBit (1)	=	128	- MessageEndBit (1)	=	128
Control byte	Σ	135	Control byte	Σ	130	Control byte	Σ	137

Table 8: Flatstream determination of the control bytes for the large segment and MultiSegmentMTU example

3.5.5 Example of function "Forward" with X2X Link

Function "Forward" is a method that can be used to substantially increase the Flatstream data rate. The basic principle is also used in other technical areas such as "pipelining" for microprocessors.

3.5.5.1 Function principle

X2X Link communication cycles through 5 different steps to transfer a Flatstream sequence. At least 5 bus cycles are therefore required to successfully transfer the sequence.

	Step I	Step II	Step III	Step IV	Step V
Actions	Transfer sequence from transmit array, increase Sequence-Counter	Cyclic synchronization of MTU and module buffer	Append sequence to receive array, adjust SequenceAck	Cyclic synchronization MTU and module buffer	Check SequenceAck
Resource	Transmitter (task to transmit)	Bus system (direction 1)	Recipients (task to receive)	Bus system (direction 2)	Transmitter (task for Ack checking)

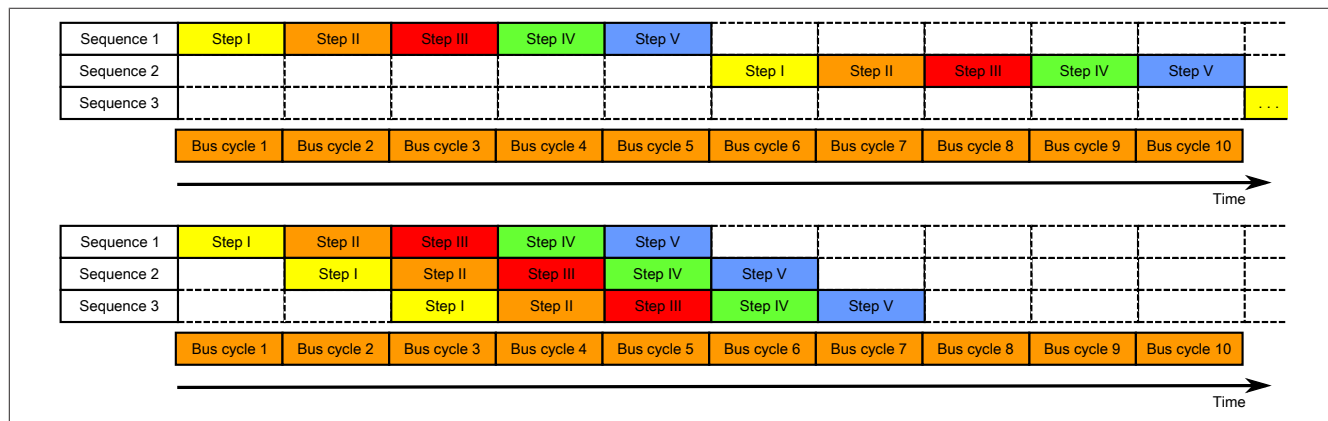


Figure 16: Comparison of transfer without/with Forward

Each of the 5 steps (tasks) requires different resources. If Forward functionality is not used, the sequences are executed one after the other. Each resource is then only active if it is needed for the current sub-action. With Forward, a resource that has executed its task can already be used for the next message. The condition for enabling the MTU is changed to allow for this. Sequences are then passed to the MTU according to the timing. The transmitting station no longer waits for an acknowledgment from SequenceAck, which means that the available bandwidth can be used much more efficiently.

In the most ideal situation, all resources are working during each bus cycle. The receiver must still acknowledge every sequence received. Only when SequenceAck has been changed and checked by the transmitter is the sequence considered as having been transferred successfully.

3.5.5.2 Configuration

The Forward function must only be enabled for the input direction. Flatstream modules have been optimized in such a way that they support this function. In the output direction, the Forward function can be used as soon as the size of OutputMTU is specified.



Information:

The registers are described in ["Flatstream registers" on page 63](#).

Registers are described in section ["Flatstream communication"](#) in the respective data sheets.

3.5.5.2.1 Delay time

The delay time is specified in microseconds. This is the amount of time the module must wait after sending a sequence until it is permitted to write new data to the MTU in the following bus cycle. The program routine for receiving sequences from a module can therefore be run in a task class whose cycle time is slower than the bus cycle.

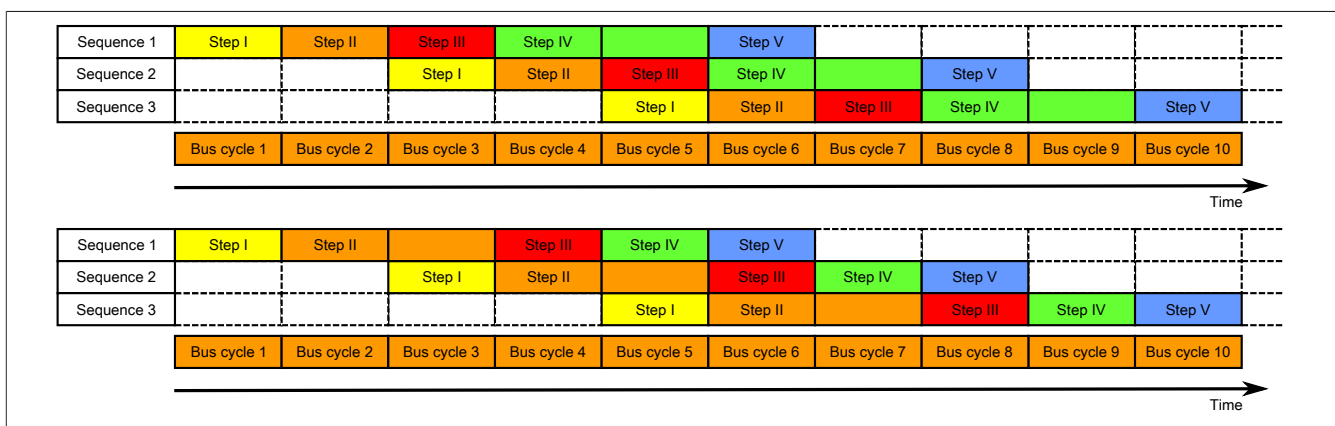


Figure 17: Effect of ForwardDelay when using Flatstream communication with the Forward function

In the program, it is important to make sure that the controller is processing all of the incoming InputSequences and InputMTUs. The ForwardDelay value causes delayed acknowledgment in the output direction and delayed reception in the input direction. In this way, the controller has more time to process the incoming InputSequence or InputMTU.

Function description

3.5.5.3 Transmitting and receiving with Forward

The basic algorithm for transmitting and receiving data remains the same. With the Forward function, up to 7 unacknowledged sequences can be transmitted. Sequences can be transmitted without having to wait for the previous message to be acknowledged. Since the delay between writing and response is eliminated, a considerable amount of additional data can be transferred in the same time window.

Algorithm for transmitting

Cyclic status query: - The module monitors OutputSequenceCounter.
0) Cyclic checks: - The controller must check OutputSyncAck. → If OutputSyncAck = 0: Reset OutputSyncBit and resynchronize the channel. - The controller must check whether OutputMTU is enabled. → If OutputSequenceCounter > OutputSequenceAck + 7, then it is not enabled because the last sequence has not yet been acknowledged.
1) Preparation (create transmit array): - The controller must split up the message into valid segments and create the necessary control bytes. - The controller must add the segments and control bytes to the transmit array.
2) Transmit: - The controller must transfer the current part of the transmit array to OutputMTU. - The controller must increase OutputSequenceCounter for the sequence to be accepted by the module. - The controller is then permitted to transmit in the next bus cycle if the MTU has been enabled.
The module responds since OutputSequenceCounter > OutputSequenceAck: - The module accepts data from the internal receive buffer and appends it to the end of the internal receive array. - The module is acknowledged and the currently received value of OutputSequenceCounter is transferred to OutputSequenceAck. - The module queries the status cyclically again.
3) Completion (acknowledgment): - The controller must check OutputSequenceAck cyclically. → A sequence is only considered to have been transferred successfully if it has been acknowledged via OutputSequenceAck. In order to detect potential transfer errors in the last sequence as well, it is important to make sure that the algorithm is run through long enough. Note: To monitor communication times exactly, the task cycles that have passed since the last increase of OutputSequenceCounter should be counted. In this way, the number of previous bus cycles necessary for the transfer can be measured. If the monitoring counter exceeds a predefined threshold, then the sequence can be considered lost (the relationship of bus to task cycle can be influenced by the user so that the threshold value must be determined individually).

Algorithm for receiving

0) Cyclic status query: - The controller must monitor InputSequenceCounter.
Cyclic checks: - The module checks InputSyncAck. - The module checks if InputMTU for enabling. → Enabling criteria: InputSequenceCounter > InputSequenceAck + Forward
Preparation: - The module forms the control bytes / segments and creates the transmit array.
Action: - The module transfers the current part of the transmit array to the receive buffer. - The module increases InputSequenceCounter. - The module waits for a new bus cycle after time from ForwardDelay has expired. - The module repeats the action if InputMTU is enabled.
1) Receiving (InputSequenceCounter > InputSequenceAck): - The controller must apply data from InputMTU and append it to the end of the receive array. - The controller must match InputSequenceAck to InputSequenceCounter of the sequence currently being processed.
Completion: - The module monitors InputSequenceAck. → A sequence is only considered to have been transferred successfully if it has been acknowledged via InputSequenceAck.

Details/Background

1. Illegal SequenceCounter size (counter offset)

Error situation: MTU not enabled

If the difference between SequenceCounter and SequenceAck during transmission is larger than permitted, a transfer error occurs. In this case, all unacknowledged sequences must be repeated with the old SequenceCounter value.

2. Checking an acknowledgment

After an acknowledgment has been received, a check must verify whether the acknowledged sequence has been transmitted and had not yet been unacknowledged. If a sequence is acknowledged multiple times, a severe error occurs. The channel must be closed and resynchronized (same behavior as when not using Forward).



Information:

In exceptional cases, the module can increment OutputSequenceAck by more than 1 when using Forward.

An error does not occur in this case. The controller is permitted to consider all sequences up to the one being acknowledged as having been transferred successfully.

3. Transmit and receive arrays

The Forward function has no effect on the structure of the transmit and receive arrays. They are created and must be evaluated in the same way.

3.5.5.4 Errors when using Forward

In industrial environments, it is often the case that many different devices from various manufacturers are being used side by side. The electrical and/or electromagnetic properties of these technical devices can sometimes cause them to interfere with one another. These kinds of situations can be reproduced and protected against in laboratory conditions only to a certain point.

Precautions have been taken for transfer via X2X Link in case such interference should occur. For example, if an invalid checksum occurs, the I/O system will ignore the data from this bus cycle and the receiver receives the last valid data once more. With conventional (cyclic) data points, this error can often be ignored. In the following cycle, the same data point is again retrieved, adjusted and transferred.

Using Forward functionality with Flatstream communication makes this situation more complex. The receiver receives the old data again in this situation as well, i.e. the previous values for SequenceAck/SequenceCounter and the old MTU.

Loss of acknowledgment (SequenceAck)

If a SequenceAck value is lost, then the MTU was already transferred properly. For this reason, the receiver is permitted to continue processing with the next sequence. The SequenceAck is aligned with the associated SequenceCounter and sent back to the transmitter. Checking the incoming acknowledgments shows that all sequences up to the last one acknowledged have been transferred successfully (see sequences 1 and 2 in the image).

Function description

Loss of transmission (SequenceCounter, MTU):

If a bus cycle drops out and causes the value of SequenceCounter and/or the filled MTU to be lost, then no data reaches the receiver. At this point, the transmission routine is not yet affected by the error. The time-controlled MTU is released again and can be rewritten to. The receiver receives SequenceCounter values that have been incremented several times. For the receive array to be put together correctly, the receiver is only permitted to process transmissions whose SequenceCounter has been increased by one. The incoming sequences must be ignored, i.e. the receiver stops and no longer transmits back any acknowledgments. If the maximum number of unacknowledged sequences has been sent and no acknowledgments are returned, the transmitter must repeat the affected SequenceCounter and associated MTUs (see sequence 3 and 4 in the image).

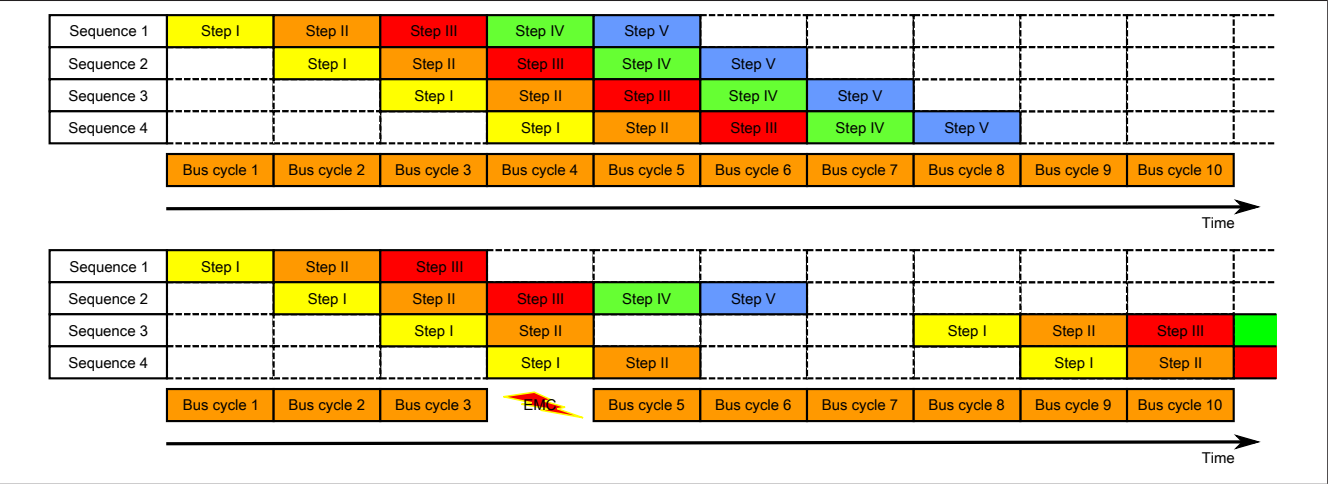


Figure 18: Effect of a lost bus cycle

Loss of acknowledgment

In sequence 1, the acknowledgment is lost due to disturbance. Sequences 1 and 2 are therefore acknowledged in Step V of sequence 2.

Loss of transmission

In sequence 3, the entire transmission is lost due to disturbance. The receiver stops and no longer sends back any acknowledgments. The transmitting station continues transmitting until it has issued the maximum permissible number of unacknowledged transmissions. 5 bus cycles later at the earliest (depending on the configuration), it begins resending the unsuccessfully sent transmissions.

4 Commissioning

4.1 Using the module on the bus controller

Function model 254 "Bus controller" is used by default only by non-configurable bus controllers. All other bus controllers can use other registers and functions depending on the fieldbus used.

For detailed information, see section "Additional information - Using I/O modules on the bus controller" in the X20 user's manual (version 3.50 or later).

4.1.1 CAN I/O bus controller

The module occupies 2 analog logical slots on CAN I/O.

5 Register description

5.1 General data points

In addition to the registers described in the register description, the module has additional general data points. These are not module-specific but contain general information such as serial number and hardware variant.

General data points are described in section "Additional information - General data points" in the X20 System user's manual.

5.2 Register overview - Function model 0 (standard)

Register	Name	Data type	Read		Write	
			Cyclic	Acyclic	Cyclic	Acyclic
Module configuration						
513	CfO_SlframeGenID	USINT				•
Basic functions						
683	SDCLifeCount	SINT	•			
1236	PositionHW	UDINT	•			
1244	PositionLW	UDINT	•			
	Position	DINT				
1228	PosTime (32-bit)	DINT	•			
1230	PosTime (16-bit)	INT	•			
1219	PosCycle	SINT	•			
Error management						
387	ErrorEnableID_0F08	USINT	•			•
259	ErrorInfo	USINT				
	EncoderSupplyError	Bit 0				
	VssCheckError	Bit 2				
	PositionError	Bit 3				
	HfComError	Bit 4				
	HfRefWarning	Bit 5				
323	AckErrorInfo	USINT			•	
	AckEncoderSupplyError	Bit 0				
	AckVssCheckError	Bit 2				
	AckPositionError	Bit 3				
	AckHfComError	Bit 4				
	AckHfRefWarning	Bit 5				
2116	HfErrorCode	UDINT	•			
Sin/Cos - Configuration						
1025	SinCosEnable	USINT				•
1027	SinCosRefSource	USINT				•
1034	SinCosVssMin	UINT				•
1038	SinCosVssMax	UINT				•
1044	SinCosQuitTime	UDINT				•
HIPERFACE - Configuration						
2049	HfMode	USINT				•
2053	HfParity	USINT				•
2055	HfCharTimeout	USINT				•
2060	HfBaud	UDINT				•
2068	HfRepressErrTime	UDINT				•
2073	HfRefAdr	USINT				•
2075	HfRefWidth	USINT				•
HIPERFACE - Identification						
2561	HfAdrIdent	USINT				•
2563	HfSelectionIdent	USINT				•
2631	HfIdentOk	USINT		•		
2688	HfRs485Settings	USINT		•		
2689	HfEncoderType	USINT		•		
2690	HfEepromSize	USINT		•		
2691	HfOptionFlags	USINT		•		
2692	HfFreeMemory	USINT		•		
2693	HfDataFields	USINT		•		
2693 + N	HfExtByte0N (index N = 1 to 10)	USINT		•		
HIPERFACE - Additional positions						
2817	AddPosAdr01	USINT				•

Register	Name	Data type	Read		Write	
			Cyclic	Acyclic	Cyclic	Acyclic
2887	AddPosOk (byte)	USINT	•			
	AddPosOk01	Bit 0				
	AddPosOk02	Bit 1				
2956	AddPosition01	DINT	•			
2958	AddPosition01	INT	•			
2948	AddPosTime01	DINT	•			
2950	AddPosTime01	INT	•			
2825	AddPosAdr02	USINT				•
2972	AddPosition02	DINT	•			
2974	AddPosition02	INT	•			
2964	AddPosTime02	DINT	•			
2966	AddPosTime02	INT	•			
HIPERFACE - Additional analog values						
3065 + N * 8	AnalogAdrCh0N (index N = 1 to 4)	USINT				•
3067 + N * 8	AnalogCh0N (index N = 1 to 4)	USINT				•
3143	AnalogChOk (byte)	USINT	•			
	AnalogChOk01	Bit 0				
				
	AnalogChOk04	Bit 3				
3194 + N * 16	AnalogChValue0N (index N = 1 to 4)	(U)INT	•			
3188 + N * 16	AnalogChTime0N (index N = 1 to 4) (32-bit)	DINT	•			
3190 + N * 16	AnalogChTime0N (index N = 1 to 4) (16-bit)	INT	•			
Flatstream mode						
2305	OutputMTU	USINT				•
2307	InputMTU	USINT				•
2309	FlatStreamMode	USINT				•
2311	Forward	USINT				•
2316	ForwardDelay	UINT				•
2368	InputSequence	USINT	•			
2368 + N	RxByteN (index N = 1 to 15)	USINT	•			
2400	OutputSequence	USINT			•	
2400 + N	TxByteN (index N = 1 to 15)	USINT			•	

5.3 Register overview - Function model 254 (bus controller)

Register	Offset ¹⁾	Name	Data type	Read		Write	
				Cyclic	Acyclic	Cyclic	Acyclic
Module configuration							
513	-	CfO_SlframeGenID	USINT				•
Basic functions							
1236	0	PositionHW	UDINT	•			
1244	4	PositionLW	UDINT	•			
1219	15	PosCycle	SINT	•			
Error management							
387	-	ErrorEnableID_0F08	USINT				•
259	14	ErrorInfo	USINT	•			
		EncoderSupplyError	Bit 0				
		VssCheckError	Bit 2				
		PositionError	Bit 3				
		HfComError	Bit 4				
		HfRefWarning	Bit 5				
323	6	AckErrorInfo	USINT			•	
		AckEncoderSupplyError	Bit 0				
		AckVssCheckError	Bit 2				
		AckPositionError	Bit 3				
		AckHfComError	Bit 4				
		AckHfRefWarning	Bit 5				
2116	-	HfErrorCode	UDINT	•			
Sin/Cos - Configuration							
1025	-	SinCosEnable	USINT				•
1027	-	SinCosRefSource	USINT				•
1034	-	SinCosVssMin	UINT				•
1038	-	SinCosVssMax	UINT				•
1044	-	SinCosQuitTime	UDINT				•
HIPERFACE - Configuration							
2049	-	HfMode	USINT				•
2053	-	HfParity	USINT				•
2055	-	HfCharTimeout	USINT				•
2060	-	HfBaud	UDINT				•
2068	-	HfRepressErrTime	UDINT				•
2073	-	HfRefAdr	USINT				•
2075	-	HfRefWidth	USINT				•
HIPERFACE - Identification							
2561	-	HfAdrIdent	USINT				•
2563	-	HfSelectionIdent	USINT				•
2631	-	HfIdentOk	USINT		•		
2688	-	HfRs485Settings	USINT		•		
2689	-	HfEncoderType	USINT		•		
2690	-	HfEepromSize	USINT		•		
2691	-	HfOptionFlags	USINT		•		
2692	-	HfFreeMemory	USINT		•		
2693	-	HfDataFields	USINT		•		
2693 + N	-	HfExtByte0N (index N = 1 to 10)	USINT		•		
HIPERFACE - Additional positions							
2817	-	AddPosAdr01	USINT				•
2887	-	AddPosOk (byte)	USINT	•			
		AddPosOk01	Bit 0				
		AddPosOk02	Bit 1				
2956	-	AddPosition01	DINT	•			
2958	-	AddPosition01	INT	•			
2825	-	AddPosAdr02	USINT				•
2972	-	AddPosition02	DINT	•			
2974	-	AddPosition02	INT	•			
HIPERFACE - Additional analog values							
3065 + N * 8	-	AnalogAdrCh0N (index N = 1 to 4)	USINT				•
3067 + N * 8	-	AnalogCh0N (index N = 1 to 4)	USINT				•
3143	-	AnalogChOk (byte)	USINT	•			
		AnalogChOk01	Bit 0				
					
		AnalogChOk04	Bit 3				
3194 + N * 16	-	AnalogChValue0N (index N = 1 to 4)	(U)INT	•			
Flatstream mode							
2305	-	OutputMTU	USINT				•
2307	-	InputMTU	USINT				•
2309	-	FlatStreamMode	USINT				•
2311	-	Forward	USINT				•
2316	-	ForwardDelay	UINT				•

Register	Offset ¹⁾	Name	Data type	Read		Write	
				Cyclic	Acyclic	Cyclic	Acyclic
2368	8	InputSequence	USINT	•			
2368 + N	9 to 13	RxByteN (index N = 1 to 5)	USINT	•			
2400	0	OutputSequence	USINT			•	
2400 + N	1 to 5	TxByteN (index N = 1 to 5)	USINT			•	

1) The offset specifies the position of the register within the CAN object.

5.4 Module configuration

The user can use the following configuration register to define various module settings. In this way, e.g. the behavior on the X2X Link is influenced.

5.4.1 Data query

Name:

CfO_SlframeGenID

This register can be used to define when the synchronous/cyclic input data is generated. "X2X cycle optimized" should be set for jitter-free data acquisition. "Fast reaction" can be set for the best performance.

Data type	Value	Information
USINT	9	Fast reaction
	14	X2X cycle optimized; Bus controller default

5.5 Basic functions

The module can read in a position in conjunction with a HIPERFACE encoder. There are 5 registers available for further processing. In this way, the user can freely choose the format best suited to their individual application.

5.5.1 SDC counter register

Name:

SDCLifeCount

The 8-bit counter register is needed for the SDC software package. It is incremented with the system clock to allow the SDC to check the validity of the data frame.

Data type	Values
SINT	-128 to 127

5.5.2 Absolute position values

Name:

PositionHW

PositionLW

The absolute position of the encoder is defined using 64-bit resolution. The position value is stored in the PositionHW and PositionLW registers. The upper 32 bits are stored in the PositionHW register, while the lower 32 bits are stored in the PositionLW register.

For SinCos signal evaluation, see "[Format of the SinCos signal](#)" on page 19 for information about the data format.

Data type	Value
2x UDINT	0 to 4,294,967,295

5.5.3 SDC position value

Name:

Position

The SDC library requires the position as a signed 32-bit value. The low word of the position can be addressed separately for this purpose. However, the value can also be used as a standard position value.

Data type	Value
DINT	-2,147,483,648 to 2,147,483,647

5.5.4 NetTime of the position values

Name:

PosTime

The current NetTime value is assigned to each determined position in this register. The NetTime is recorded with microsecond precision.

The use of the SDC library requires a 16-bit value. The NetTime value is therefore also processed in this format.

For additional information about NetTime and timestamps, see "[NetTime Technology](#)" on page 21.

Data type	Value	Information
DINT	-2,147,483,648 to 2,147,483,647	NetTime in μ s
INT	-32,768 to 32,767	

5.5.5 Counter for position values

Name:

PosCycle

PosCycle is an integer counter that is incremented as soon as the module has saved a new valid position value.

Data type	Value
SINT	-128 to 127

5.6 Error management

This module can be used to diagnose error states. There are 2 ways this module performs error diagnostics:

- ["Module-based diagnostics" on page 55](#)
- ["HIPERFACE-based diagnostics" on page 56](#)

5.6.1 Module-based diagnostics

The module recognizes errors independently. The error bits can be retrieved both individually and in packets.

5.6.1.1 Enabling/disabling error messages

Name:

ErrorEnableID_0F08

The implemented diagnostic algorithms can be enabled or disabled in this register.

Data type	Value	Bus controller default
USINT	See bit structure.	255

Bit structure:

Bit	Name ¹⁾	Value	Information
0	Encoder power supply	0	Error detection disabled
		1	Error detection enabled (bus controller default setting)
1	Reserved	-	
2	Vss Sin/Cos	0	Error detection disabled
		1	Error detection enabled (bus controller default setting)
3	Position error	0	Error detection disabled
		1	Error detection enabled (bus controller default setting)
4	HIPERFACE - Communication	0	Error detection disabled
		1	Error detection enabled (bus controller default setting)
5	HIPERFACE - Reference warning	0	Warning disabled
		1	Warning enabled (bus controller default setting)
6 - 7	Reserved	-	

1) For a description of the individual errors, see ["Diagnostic functions" on page 20](#).

5.6.1.2 Show error messages

Name:

ErrorInfo

EncoderSupplyError

VssCheckError

PositionError

HfComError

HfRefWarning

This register indicates any errors or warnings that have not yet been acknowledged. For the meaning of individual error messages, see register ["Enabling/disabling error messages" on page 55](#).

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Name	Value	Information
0	EncoderSupplyError	0	No error
		1	Encoder supply error
1	Reserved	-	
2	VssCheckError	0	No error
		1	Vss error on the Sin/Cos track
3	PositionError	0	No error
		1	Position error
4	HfComError	0	No error
		1	HIPERFACE communication error
5	HfRefWarning	0	No warning
		1	HIPERFACE reference warning
6 - 7	Reserved	-	

Register description

5.6.1.3 Acknowledge error messages

Name:

AckErrorInfo

AckEncoderSupplyError

AckVssCheckError

AckPositionError

AckHfComError

AckHfRefWarning

This register is used to acknowledge an error or warning message that occurred in the ["Show error messages" on page 55](#) register. For the meaning of individual error messages, see register ["Enabling/disabling error messages" on page 55](#).

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Name	Value	Information
0	AckEncoderSupplyError	0	No error acknowledgment
		1	Error acknowledgment
1	Reserved	-	
2	AckVssCheckError	0	No error acknowledgment
		1	Error acknowledgment
3	AckPositionError	0	No error acknowledgment
		1	Error acknowledgment
4	AckHfComError	0	No error acknowledgment
		1	Error acknowledgment
5	AckHfRefWarning	0	No acknowledgment
		1	Acknowledgment
6 - 7	Reserved	-	

5.6.2 HIPERFACE-based diagnostics

The HIPERFACE standard already provides memory areas for error diagnostics. Precise information about which errors are detected in this way must be looked up in the encoder manual.

5.6.2.1 HfErrorCode

Name:

HfErrorCode

This register is used to store the error code that identifies the current problem with the HIPERFACE interface.

Data type	Value
UDINT	See bit structure.

Internally, the register consists of 4 pieces of information.

Bit structure:

Bit	Name	Information
00 - 07	Error ID	See "Typical HIPERFACE diagnostics" on page 20 .
08 - 15	Last command	Command that caused the error on the slave
16 - 23	Station address	Address of the faulty HIPERFACE slave
24 - 31	Error counter	Counts the number of errors that have occurred

5.7 Sin/Cos - Analog interface configuration

In addition to the digital HIPERFACE, the module also has an analog interface for recording a differential sine/cosine signal.

5.7.1 Enabling SinCos

Name:

SinCosEnable

This register must always have the value 1 for configuration reasons.

Data type	Value	Information
USINT	1	Bus controller default: 1

5.7.2 SinCosRefSource

Name:

SinCosRefSource

This register must always have the value 3 for configuration reasons.

Data type	Value	Information
USINT	3	Bus controller default: 3

5.7.3 Configuring the lower Vss value

Name:

SinCosVssMin

This register specifies the lower limit value for the peak-to-peak voltage of the sine/cosine track. The incoming signal is monitored in this way. If the incoming value falls below this specified limit, then the module reports the corresponding error.

Data type	Value	Information
UINT	0 to 1500	Values in mV Bus controller default: 800

5.7.4 Configuring the upper Vss value

Name:

SinCosVssMax

This register specifies the upper limit value for the peak-to-peak voltage of the sine/cosine track. The incoming signal is monitored in this way. If the incoming value exceeds this specified limit, then the module reports the corresponding error.

Data type	Value	Information
UINT	0 to 1500	Values in mV Bus controller default: 1200

5.7.5 Configuring the delay time after errors

Name:

SinCosQuitTime

In this register, a time period can be set during which the module receives correct values again after the error state without further processing them internally.

Data type	Value	Information
UDINT	0 to 20000000	Values in μ s Bus controller default: 100000

5.8 HIPERFACE

5.8.1 HIPERFACE - Configuring the digital interface

HIPERFACE builds upon the RS-485 (EIA-485) specification and permits communication with multiple HIPERFACE slaves.

5.8.1.1 HfMode

Name:
HfMode

This register is used to enable the HIPERFACE interface and must always be set to the value 1 for configuration reasons.

Data type	Value	Information
USINT	1	Bus controller default: 1

5.8.1.2 HfParity

Name:
HfParity

This register configures the parity bit for the interface.

Data type	Values	Information
USINT	69	E → even parity bit Bus controller default setting
	78	N → no parity bit
	79	O → odd parity bit

5.8.1.3 HfCharTimeout

Name:
HfCharTimeout

This register configures the time that the module waits after receiving the last data block to add additional data to the current data packet (frame). When this time expires, the data received thus far is saved in a frame. The transfer is complete and the data can be evaluated.



Information:

Time is specified as a char value in order to ensure identical behavior regardless of the baud rate setting.

Data type	Values	Information
USINT	1 to 255	Char Bus controller default setting: 55

5.8.1.4 HfBaud

Name:
HfBaud

This register configures the baud rate (transfer rate) of the interface.
The module does not allow a transfer rate of 600 baud.

Data type	Values	Information
UDINT	1200, 2400, 4800, 9600, 19200, 38400	Baud Bus controller default setting: 9600

5.8.1.5 HfRepressErrTime

Name:
HfRepressErrTime

This register configures the minimum time period for which an error code remains entered in register "HfErrorCode". This ensures that the controller registers every error that occurs.

Data type	Value	Information
UDINT	1 to 20000000	Time in µs; Bus controller default: 100000

5.8.1.6 HfRefAdr

Name:
HfRefAdr

The module can manage up to 32 HIPERFACE slaves via the digital interface. The HIPERFACE address of the station whose sine/cosine track is read into the module is entered in this register. For additional details, see ["Configuring the digital interface" on page 9](#).

Data type	Values	Information
USINT	0	Operation without sine/cosine track
	64 to 95	Open address range for max. 32 HIPERFACE slaves. Bus controller default setting: 64
	255	Broadcast address

5.8.1.7 HfRefWidth

Name:
HfRefWidth

This register is used to configure the absolute detection position. The number of bits must be taken from the encoder manufacturer's data. For details, see ["Configuring the digital interface" on page 9](#).

Data type	Values	Information
USINT	8 to 32	Bus controller default setting: 32

5.8.2 HIPERFACE - Read ID

The digital interface makes it possible to precisely identify the HIPERFACE slave used.

5.8.2.1 HfAdrIdent

Name:
HfAdrIdent

This register is used to set the HIPERFACE address of the slave with parameters that are to be processed in the module.

Data type	Values	Information
USINT	0	Identification deactivated Bus controller default setting
	64 to 95	Open address range for max. 32 HIPERFACE slaves
	255	Broadcast address (when operating with one slave)

5.8.2.2 HfSelectionIdent

Name:
HfSelectionIdent

This register defines the parameters that should be provided in the slave response and buffered in the module's ["HfExtByte" on page 61](#) register.

Data type	Values	Values
USINT	0	Serial number Bus controller default setting
	1	Firmware date
	2	High part of firmware version
	3	Low part of firmware version

5.8.2.3 HfIdentOk

Name:
HfIdentOk

This register's bits provide information about the validity of the latest ID values in temporary storage.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Description	Value	Information
0	HfIdentOk01	0	Parameter 01 invalid
		1	Parameter 01 valid
1 - 7	Reserved	-	

Register description

5.8.2.4 HfRs485Settings

Name:
HfRs485Settings

This register is used to temporarily store the current network configuration expected by the slave. The register value is specifically structured for HIPERFACE.

Data type	Value
USINT	See bit structure.

Bit structure:

Bit	Name	Value	Information
0 - 2	Speed code	001	1200 baud
		010	2400 baud
		011	4800 baud
		100	9600 baud
		101	19200 baud
		110	38400 baud
3	Reserved	-	
4	Number of parity bits	0	No parity bit
		1	1 parity bit
5	Type of parity bit	0	Even
		1	Odd
6	Behavior if a timeout occurs	0	Timeout 11/baudrate
		1	Timeout 4*11/baud rate
7	Network behavior	0	Bus
		1	Direct connection

5.8.2.5 HfEncoderType

Name:
HfEncoderType

This register is used to temporarily store the ID of the current encoder. The register value is structured specifically for each slave and must be looked up in the encoder's data sheet.

Data type	Values
USINT	0 to 255

5.8.2.6 HfEepromSize

Name:
HfEepromSize

This register is used to store the size of the EEPROM being used. The number of 16-byte blocks is specified.

Data type	Values	Values
USINT	0 to 255	16-byte blocks

5.8.2.7 HfOptionFlags

Name:
HfOptionFlags

This register is used to store slave-specific hardware and software settings.

Data type	Values
USINT	0 to 255

5.8.2.8 HfFreeMemory

Name:
HfFreeMemory

This register is used to indicate the number of free 16-byte blocks remaining on the HIPERFACE slave.

Data type	Values	Information
USINT	0 to 255	16-byte blocks

5.8.2.9 HfDataFields

Name:
HfDataFields

This register is used to indicate the number of data fields that have been written thus far.

Data type	Values
USINT	0 to 255

5.8.2.10 HfExtByte

Name:
HfExtByte01 to HfExtByte10

These registers provide the respective parameters according to how the "HfSelectionIdent" on page 59 register is configured.

Data type	Values
USINT	0 to 255

5.8.3 HIPERFACE - Reading additional encoder positions

The module is able to read in up to 2 additional position values via the HIPERFACE interface and make them available to the controller. In addition to the position value, the corresponding [timestamp](#) is also processed.

5.8.3.1 AddPosAdr

Name:
AddPosAdr01 to AddPosAdr02

The HIPERFACE addresses of the slaves whose position values should also be processed in the module are set in these registers.

Data type	Values	Information
USINT	0	Additional encoder position disabled Bus controller default setting
	64 to 95	Open address range for max. 32 HIPERFACE slaves
	255	Broadcast address (when operating with one slave)

5.8.3.2 AddPosOk (byte)

Name:
AddPosOk01 to AddPosOk02

This register's bits provide information about the validity of the last position values in temporary storage.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Description	Value	Information
0	AddPosOk01	0	Position value 01 invalid
		1	Position value 01 valid
1	AddPosOk02	0	Position value 02 invalid
		1	Position value 02 valid
2 - 7	Reserved	-	

5.8.3.3 AddPosition

Name:
AddPosition01 to AddPosition02

These registers provide the current position values, depending on the register address, as signed 2-byte or 4-byte values.

Data type	Values
DINT	-2,147,483,648 to 2,147,483,647
INT	-32768 to 32767

Register description

5.8.3.4 AddPosTime

Name:

AddPosTime01 to AddPosTime02

These registers provide the timestamp of the most recently received position values, depending on the register address, as signed 2-byte or 4-byte values.

For additional information about NetTime and timestamps, see "[NetTime Technology](#)" on page 21.

Data type	Values	Information
DINT	-2,147,483,648 to 2,147,483,647	NetTime in μ s
INT	-32768 to 32767	

5.8.4 HIPERFACE - Reading additional analog values

The module is able to read in up to 4 analog values (16-bit) via the HIPERFACE interface and make them available to the controller. In addition to the buffered analog value, the corresponding **timestamp** is also processed.

5.8.4.1 AnalogAdrCh

Name:

AnalogAdrCh01 to AnalogAdrCh04

These registers are used to set the addresses of the HIPERFACE slaves with analog values that should be processed in the module. To query multiple values from one HIPERFACE slave, it may make sense to write the same address to different AnalogAdrCh registers.

Data type	Values	Information
USINT	0	Additional analog values disabled Bus controller default setting
	64 to 95	Open address range for max. 32 HIPERFACE slaves
	255	Broadcast address (when operating with one slave)

5.8.4.2 AnalogCh

Name:

AnalogCh01 to AnalogCh04

These registers define the channel to be read that is written by the bus station to the module's temporary storage.

Data type	Values	Information
USINT	See encoder data sheet	Bus controller default setting: 0

5.8.4.3 AnalogChOk (byte)

Name:

AnalogChOk01 to AnalogChOk04

This register's bits provide information about the validity of the values in temporary storage.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Description	Value	Information
0	AnalogChOk01	0	Analog value 01 invalid
		1	Analog value 01 valid
...
3	AnalogChOk04	0	Analog value 04 invalid
		1	Analog value 04 valid
4 - 7	Reserved	-	

5.8.4.4 AnalogChValue

Name:

AnalogChValue01 to AnalogChValue04

These registers provide the current analog values, depending on the register address, as signed or unsigned 2-byte values.

Data type	Values
UINT	0 to 65535
INT	-32768 to 32767

5.8.4.5 AnalogChTime

Name:

AnalogChTime01 to AnalogChTime04

These registers provide the timestamp of the most recently received analog values, depending on the register address, as signed 2-byte or 4-byte values.

For additional information about NetTime and timestamps, see ["NetTime Technology" on page 21](#).

Data type	Values	Information
DINT	-2,147,483,648 to 2,147,483,647	NetTime in μ s
INT	-32768 to 32767	

5.9 Flatstream registers

At the absolute minimum, registers "InputMTU" and "OutputMTU" must be set. All other registers are filled in with default values at the beginning and can be used immediately. These registers are used for additional options, e.g. to transfer data in a more compact way or to increase the efficiency of the general procedure.



Information:

For detailed information about Flatstream, see [Flatstream communication](#).

5.9.1 Number of enabled Tx and Rx bytes

Name:

OutputMTU

InputMTU

These registers define the number of enabled Tx or Rx bytes and thus also the maximum size of a sequence. The user must consider that the more bytes made available also means a higher load on the bus system.

Data type	Values
USINT	See the register overview.

5.9.2 Transporting payload data and control bytes

Name:

TxByte1 to TxByteN

RxByte1 to RxByteN

(The value the number N is different depending on the bus controller model used.)

The Tx and Rx bytes are cyclic registers used to transport the payload data and the necessary control bytes. The number of active Tx and Rx bytes is taken from the configuration of registers "OutputMTU" and "InputMTU", respectively.

- "T" - "Transmit" → Controller transmits data to the module.
- "R" - "Receive" → Controller receives data from the module.

Data type	Values
USINT	0 to 255

5.9.3 Communication status of the controller

Name:

OutputSequence

This register contains information about the communication status of the controller. It is written by the controller and read by the module.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Name	Value	Information
0 - 2	OutputSequenceCounter	0 - 7	Counter for the sequences issued in the output direction
3	OutputSyncBit	0	Output direction (disable)
		1	Output direction (enable)
4 - 6	InputSequenceAck	0 - 7	Mirrors InputSequenceCounter
7	InputSyncAck	0	Input direction not ready (disabled)
		1	Input direction ready (enabled)

OutputSequenceCounter

The OutputSequenceCounter is a continuous counter of sequences that have been issued by the controller. The controller uses OutputSequenceCounter to direct the module to accept a sequence (the output direction must be synchronized when this happens).

OutputSyncBit

The controller uses OutputSyncBit to attempt to synchronize the output channel.

InputSequenceAck

InputSequenceAck is used for acknowledgment. The value of InputSequenceCounter is mirrored if the controller has received a sequence successfully.

InputSyncAck

The InputSyncAck bit acknowledges the synchronization of the input channel for the module. This indicates that the controller is ready to receive data.

5.9.4 Communication status of the module

Name:

InputSequence

This register contains information about the communication status of the module. It is written by the module and should only be read by the controller.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Name	Value	Information
0 - 2	InputSequenceCounter	0 - 7	Counter for sequences issued in the input direction
3	InputSyncBit	0	Not ready (disabled)
		1	Ready (enabled)
4 - 6	OutputSequenceAck	0 - 7	Mirrors OutputSequenceCounter
7	OutputSyncAck	0	Not ready (disabled)
		1	Ready (enabled)

InputSequenceCounter

The InputSequenceCounter is a continuous counter of sequences that have been issued by the module. The module uses InputSequenceCounter to direct the controller to accept a sequence (the input direction must be synchronized when this happens).

InputSyncBit

The module uses InputSyncBit to attempt to synchronize the input channel.

OutputSequenceAck

OutputSequenceAck is used for acknowledgment. The value of OutputSequenceCounter is mirrored if the module has received a sequence successfully.

OutputSyncAck

The OutputSyncAck bit acknowledges the synchronization of the output channel for the controller. This indicates that the module is ready to receive data.

5.9.5 Flatstream mode

Name:

FlatstreamMode

A more compact arrangement can be achieved with the incoming data stream using this register.

Data type	Values
USINT	See the bit structure.

Bit structure:

Bit	Name	Value	Information
0	MultiSegmentMTU	0	Not allowed (default)
		1	Permitted
1	Large segments	0	Not allowed (default)
		1	Permitted
2 - 7	Reserved		

5.9.6 Number of unacknowledged sequences

Name:

Forward

With register "Forward", the user specifies how many unacknowledged sequences the module is permitted to transmit.

Recommendation:

X2X Link: Max. 5

POWERLINK: Max. 7

Data type	Values
USINT	1 to 7 Default: 1

5.9.7 Delay time

Name:

ForwardDelay

This register is used to specify the delay time in microseconds.

Data type	Values
UINT	0 to 65535 [μ s] Default: 0

5.10 Minimum I/O update time

The minimum I/O update time specifies how far the bus cycle can be reduced so that an I/O update is performed in each cycle.

Minimum I/O update time
100 μ s

5.11 Minimum cycle time

The minimum cycle time specifies how far the bus cycle can be reduced without communication errors occurring. It is important to note that very fast cycles reduce the idle time available for handling monitoring, diagnostics and acyclic commands.

Minimum cycle time
100 μ s