EtherCAT Device Protocol

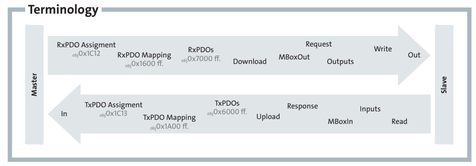
EtherCAT®

ESM

EtherCAT State Machine (ESM)

The EtherCAT State Machine defines a step-by-step set-up of each individual EtherCAT slave device and indicates available functionalities. A device can reject a state request from the master and signal an error with an error indication (error flag in AL Status register) and a related error code (AL Status Code register). The state request, state response and error response is exchanged via the ESC AL Control register ($_{reg}$0x0120), AL Status register ($_{reg}$0x0130) and AL Status Code register ($_{reg}$0x0134). The ESM specifies the slave behavior, while the master adopts it respectively. The ESM description below outlines the basic actions for each state transition: commands sent by the master and (local) behavior of the connected devices.

Terminology



INT ($_{reg}$0x0120/$_{reg}$0x0130 = 0x1): Only access to ESC registers

Master			Master		
Clear:	Configuration registers, e.g.:		Clear:	SM0 for Mailbox Out	($_{reg}$0x0800 – 0x0807)
	FMMUs	($_{reg}$0x0600 – 0x06FF)		SM1 for Mailbox In	($_{reg}$0x0808 – 0x080F)
	SyncManagers (SM)	($_{reg}$0x0800 – 0x087F)			
Set:	Fixed Physical Address	($_{reg}$0x0010)			
	SM0 for Mailbox Out	($_{reg}$0x0800 – 0x0807)			
	SM1 for Mailbox In	($_{reg}$0x0808 – 0x080F)			
If DC:	DC System Time setup:				
	Delay compensation	($_{reg}$0x0900, $_{reg}$0x0928)			
	Offset compensation	($_{reg}$0x0918, $_{reg}$0x0920)			
	Static drift compensation (~15.000 times)	($_{reg}$0x0910)			
Slave			**Slave**		
Verify:	Mailbox SyncManager settings		Stop:	Mailbox communication (STOP_MBX_HANDLER)	
Start:	Mailbox communication (START_MBX_HANDLER)				
Confirm:	State request to PRE-OPERATIONAL				

PRE-OPERATIONAL ($_{reg}$0x0120/$_{reg}$0x0130 = 0x2): Mailbox communication available — **BOOT** (0x3): optional

Master			Master		
Set:	Configuration objects via SDO, e.g.:		Clear:	SM2 for outputs	($_{reg}$0x0810 – 0x0817)
	RxPDO / TxPDO Assignment	($_{obj}$0x1C12 / $_{obj}$0x1C13)		SM3 for inputs	($_{reg}$0x0818 – 0x081F)
	RxPDO / TxPDO Mapping	($_{obj}$0x1A00 – 0x1BFF / $_{obj}$0x1600 – 0x17FF)		FMMU0 (maps outputs)	($_{reg}$0x0600 – 0x060F)
	SM2 for outputs	($_{reg}$0x0810 – 0x0817)		FMMU1 (maps inputs)	($_{reg}$0x0610 – 0x061F)
	SM3 for inputs	($_{reg}$0x0818 – 0x081F)	Disable:	Distributed Clocks	($_{reg}$0x0980)
	FMMU0 (maps outputs)	($_{reg}$0x0600 – 0x060F)			
	FMMU1 (maps inputs)	($_{reg}$0x0610 – 0x061F)			
If DC:	Configure SYNC/LATCH unit:				
	Set SYNC cycle time	($_{reg}$0x09A0 – 0x09A7)			
	Set DC start time	($_{reg}$0x0990 – 0x0997)			
	Set DC SYNC OUT unit	($_{reg}$0x0980 – 0x0981)			
	Set DC LATCH IN unit	($_{reg}$0x09A8 – 0x09A9)			
	Start continuous drift compensation	($_{reg}$0x0910 – 0x0917)			
Start:	Cyclic process data				
Slave			**Slave**		
Verify:	Process data SyncManager settings, PDO Mapping/Assignment		Stop:	Cyclic process data	
Start:	Input update (START_INPUT_HANDLER)				
Provide:	Valid Inputs				
Confirm:	State request to SAFE-OPERATIONAL				

SAFE-OPERATIONAL ($_{reg}$0x0120/$_{reg}$0x0130 = 0x4): Process data available, outputs still in safe state

Master			Master		
Provide:	Valid outputs				
Slave			**Slave**		
Verify:	Synchronization with DC, if required		Stop:	Output update (STOP_OUTPUT_HANDLER)	
Start:	Output update (START_OUTPUT_HANDLER)				
Confirm:	State request to OPERATIONAL				

OPERATIONAL ($_{reg}$0x0120/$_{reg}$0x0130 = 0x8): Input and output process data available

State transition/default timeout: PreopTimeout (3000ms) → SafeopOPTimeout (10000ms) → BackToSafeopTimeout (200ms) → BackToInitTimeout (5000ms)

References: ETG.1000.5 – AR (Application Relationship) | ETG.1000.4 – Attributes | ETG.1000.6 – AL state machine | ETG.2000 – InfoType

CoE

CoE Object Dictionary (OD)

The OD is based on CANopen® and provides a structure for any EtherCAT device. Each object is addressed by a 16-bit index and can have up to 255 object entries, addressed by an 8-bit sub-index (SI). The following Object Codes are distinguished:

- VARIABLE: SI0 only
- ARRAY*: all entries have the same data type and name except SI0
- RECORD*: entries may have different data types and names

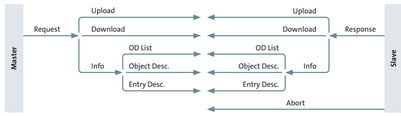
*SI0 defines the highest supported subindex. SI1 always has a 16-bit offset.

CoE base data types (excerpt)

Value	Data Type	Value	Data Type	Value	Data Type	Value	Data Type
0x0001	BOOL/BIT	0x0006	UINT	0x0008	ARRAY of UINT	0x001F	WORD
0x0002	SINT	0x0007	UDINT	0x0011	LREAL	0x0020	DWORD
0x0003	INT	0x0008	REAL	0x0015	LINT	0x0260	ARRAY of INT
0x0004	DINT	0x0009	STRING(n)	0x0018	ULINT	0x0261	ARRAY of SINT
0x0005	USINT	0x000A	ARRAY of BYTE	0x001E	BYTE	0x0262	ARRAY of DINT

Reference: ETG.1020 – Base Data Types

CoE SDO (Service Data Object) services



SDO services are used to read from and write to the online OD of the slave in a confirmed fashion. They are also used to read the OD structure. The master sends an SDO request, the slave sends either an SDO Response or an SDO Abort. The following SDO Request/Response services are defined:

- SDO Upload: read object/object entry from online OD
- SDO Download: write object/object entry from online OD
- Get OD List: returns all object indexes of the online OD
- Get Object Description: returns object name/code, data type and max. number of entries
- Get Entry Description: returns value info, data type, bit length, access rights of an entry

Reference: ETG.1000.5 – CoE service specification | ETG.1000.6 – CoE coding

SDO Command Specifier	SDO Services		
	0x02: SDO Request	0x03: SDO Response	0x08: SDO Info
0x00	Download Segmented	Upload Segmented	
0x01	Download	Download Segmented	Get OD List Req.
0x02	Upload	Upload	Get OD List Resp.
0x03	Upload Segmented	Download	Get Object Description Req.
0x04	Abort Transfer		Get Object Description Resp.
0x05			Get Entry Description Req.
0x06			Get Entry Description Resp.
0x07			SDO Info Error Req.

Modular Device Profile (MDP)

The MDP provides a basic structure for any EtherCAT slave to organize physical or logical modules within the device, based on the CoE OD. The slave's data is grouped based on its physical structure and/or logical/software structure. The MDP structure is based on so-called modules. A module has an assigned index range, typically:

- 1 RxPDO, 1 TxPDO (PdoIncrement = 1)
- 16 objects (with up to 255 entries per object) per functional index area (inputs, outputs, configuration, information, diagnosis) (IndexIncrement = 16).

Information which is not specific for a module is organized in the 0xFxxx Device index area.

CoE Object Dictionary structure, incl. MDP structure

General OD structure, MDP structure (0x6000 ff.) and attributes of the functional index areas:

MDP Device				
Object Dictionary	Module 0	Module 1	...	Module n
Communication area (0x1000 – 0x1FFF) e.g. object 0x1000, 0x1018, 0x10F3				
RxPDOs (0x1600 – 0x17FF)	0x1600	0x1601	...	0x16nn
TxPDOs (0x1A00 – 0x1BFF)	0x1A00	0x1A01	...	0x1Ann
Manufacturer specific area (0x2000 – 0x5FFF)				
Input area (0x6000 – 0x6FFF) Tx-mappable, read-only	0x6000 – 0x600F	0x6010 – 0x601F	...	0x6nn0 – 0x6nnF
Output area (0x7000 – 0x7FFF) Rx-mappable, read-writeable	0x7000 – 0x700F	0x7010 – 0x701F	...	0x7nn0 – 0x7nnF
Configuration area (0x8000 – 0x8FFF) read-writeable, usually not mappable	0x8000 – 0x800F	0x8010 – 0x801F	...	0x8nn0 – 0x8nnF
Information area (0x9000 – 0x9FFF) read-only, usually not mappable	0x9000 – 0x900F	0x9010 – 0x901F	...	0x9nn0 – 0x9nnF
Diagnosis area (0xA000 – 0xAFFF)	0xA000 – 0xA00F	0xA010 – 0xA01F	...	0xAnn0 – 0xAnnF
Device area (0xF000 – 0xFFFF) e.g. object 0xF000, 0xF010, 0xF030, 0xF050				

Reference: ETG.5001 – MDP Device model

Profiles

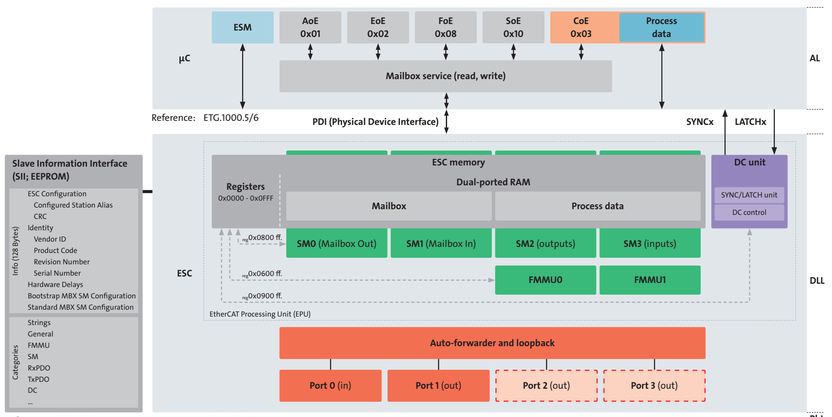
The major part of profiles is based on the CoE OD (incl. range 0x6000 ff.), while there are MDP-based profiles and the IEC61800 drive profiles (incl. "DS402"). The 32-bit profile number is provided by the slave via $_{obj}$0x1000, $_{obj}$0xF010 and via ESI element *Device:Profile* or *Module:Profile*. Bit 0-15 is the device profile number (e.g. 5003 for Semi Device Profile). Bit 16-31 is the module profile number (e.g. 2020 Mass Flow Controller). Important profiles are:

- ETG.5001.1 – General MDP Device Model Specification: Basic structure for any EtherCAT slave
- ETG.5001.3 – MDP Fieldbus Gateway Profile Specification: Incl. profiles for EtherCAT masters, Profibus DP, CAN, CANopen, DeviceNet
- ETG.5001.4 – MDP Safety Module Specification: Incl. profiles for FSoE Digital I/O connection, FSoE Safety Drive Profile, FSoE Master
- ETG.5003 – Semi Device Profile: Based on MDP structures, incl. profiles for mass flow controllers, temperature controllers, pressure gauges, valves, chillers, pumps, RF DC generators
- ETG.6010 – Implementation Directive for CiA402 Drive Profile (IEC61800-7-201)

Slave structure and EtherCAT Slave Controller (ESC)

The ESC processes the EtherCAT frames on the fly in hardware and implements the functionalities of the data link layer (DLL). Those include SyncManagers (SM), Fieldbus Memory Management Units (FMMU) and DC unit. Typically, EtherCAT slaves implement the application layer (AL) functionalities such as the ESM, parameter handling and process data handling on a µC – such slaves are called "complex device". Only for very simple I/O devices without parameters and without necessary AL error handling, the I/O hardware drivers are connected directly to the digital I/O interface of the ESC – such slaves are called "simple device".

The block diagram combines elements of the slave's hardware structure, functional entities of the ESC, software structure and protocol elements.



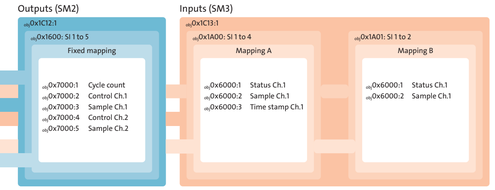
Process data

Process data configuration

The EtherCAT process data configuration allows very flexible PDO description. PDO configuration can be either fixed, selectable or configurable. When using MDP objects, inputs ($_{obj}$0x6000 – 0x6FFF) and outputs ($_{obj}$0x7000 – 0x7FFF) are mapped to PDO Mapping objects ($_{obj}$0x1600 – 0x16FF for RxPDO Mapping and $_{obj}$0x1A00 – 0x1BFF for TxPDO Mapping) and assigned to the respective SM via $_{obj}$0x1C12 (SM2) and $_{obj}$0x1C13 (SM3) for PDO Assignment. PDO Mapping and PDO Assignment objects are used by complex devices (with online and offline OD) as well as by simple devices (only in the EtherCAT Slave Information file).

Example: PDO Mapping and PDO Assignment

This example shows a fixed output mapping. The input mapping is selectable; either mapping A or B can be sassigned to SM3 via $_{obj}$0x1C13



OD Area	OD Index Range
Communication index area	0x1000 – 0x1FFF
RxPDO Mapping	0x1600 – 0x17FF
TxPDO Mapping	0x1A00 – 0x1BFF
PDO Assignment	0x1C12
TxPDO Assignment	0x1C13
Modules index area	0x6000 – 0xAFFF
Input area	0x6000 – 0x6FFF
Output area	0x7000 – 0x7FFF
Device index area	0xF000 – 0xFFFF

References: ETG.1000.5 – Process data interaction | ETG.1000.6 – Object Dictionary | ETG.5001.1 – PDO Mapping and PDO Assign

DC unit and synchronization

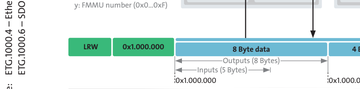
Distributed Clocks (DC) and synchronization

Synchronization of master and slave applications is based on a common time in the network (DC System Time). The synchronization modes define how this common time is used to synchronize the local applications. The SYNC/LATCH unit is used to generate SYNC/LATCH events based on the System Time.

DC System Time

The System Time is a 64-bit ns-based time starting 01.01.2000, 0:00h, or a 32-bit time respectively. After setting up the DC time, master and slaves share the same time base. The first DC slave behind the master is used as the reference clock. Each slave device has a local copy of the System Time stored in $_{reg}$0x0910.

DC System Time setup (1-3) and continuous drift compensation (4)



1. **Propagation Delay:** write to $_{reg}$0x0900 latches receive times on all ports; read latched times, calculate delays; write individual values to $_{reg}$0x0928
2. **Offset:** read individual local times; calculate offset to time reference; write individual offsets values to $_{reg}$0x0920
3. **Static Drift:** read System Time from reference clock and write to individual DC slaves via multiple (~15.000) xRMW datagrams
4. **Continuous Drift:** distribute System Time (xRMW) together with cyclic frames, e.g. every ms to keep deviation of distributed times small

Reference: ETG.1000.4 – Distributed clock

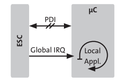
Reference: ETG.1020 – Synchronization

Synchronization modes

Applications may require different degrees of synchronization which is reflected by the different EtherCAT synchronization modes. The basic operation for DC modes is setup via $_{reg}$0x0980 – 0x0981. Additional information is provided by the SyncManager Parameter objects $_{obj}$0x1C32 for SM2 and $_{obj}$0x1C33 for SM3 (incl. minimum cycle time, calc and copy time, error counters).

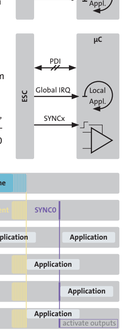
Free Run: Application is triggered by local clock and runs independently from EtherCAT cycle. ESI element *Device:Dc* is not available and $_{obj}$0x1C32/3 is optional if only Free Run is supported.

SM-Synchronous: Application is synchronized with the SM2 (SM3) event, which is generated when process data is written to SM2 (read from SM3). Events are mapped to global IRQ or polled from $_{reg}$0x0220. ESI element *Device:Dc* is not available if only SM-Synchronous is supported. If both, SM-Synchronous and DC-Synchronous are supported, then it is indicated in the ESI by *Dc:AssignActivate* = "#x0000"



DC-Synchronous: Application is synchronized using DC-based interrupt signals (SYNC0, SYNC1; ns-accuracy), generated by the SYNC/LATCH unit. Among many other DC modes, the following two show basic concepts:

- SYNC0: triggers the complete processing of the local cycle (see Minimum Cycle Time)
- SM2 and SYNC0 (even higher synchronization accuracy of the output event): SM2 event triggers reading of output data from SM2, processing, writing values to hardware drivers; then the SYNC0 event is used to activate output drivers. ESI element *Dc:AssignActivate* = "#x0300" for SYNC0 event generation



Reference: ETG.1020 – Synchronzation | ETG.2000 – DC

SM and FMMU

SyncManager (SM)

SMs coordinate access to the ESC memory from both sides, EtherCAT and PDI. This ensures data consistency. In case of mailbox communication it ensures that mailbox messages are not overwritten (1-buffer mode). In case of process data communication it ensures that process data can always be written to the memory by EtherCAT and can always be read by PDI side and vice versa (3-buffer mode). SyncManager 2/3 length is equal to the Rx/TxPDO length so that buffers internally are swapped once data was completely written/read.

Reference: ETG.1000.4 – Sync manager

Register			Mailbox		Process data	
Phys. start address	Length	Direction, Buffer No.	SM0	SM1	SM2*	SM3*
0x0800	0x0802	0x0804	Out, 1-buffer		Out, 3-buffer	
0x0808	0x080A	0x080C		In, 1-buffer		In, 3-buffer
0x0810	0x0812	0x0814				
0x0818	0x081A	0x081C				

*physical memory = 3 times Rx/TxPDO length

Fieldbus Memory Managment Unit (FMMU)

Typically, logical commands (LRD, LWR, LRW) are used for process data exchange: A single Lxx command addresses one or multiple slaves. The FMMUs of the individual slaves are configured during start-up to map the data from the EtherCAT command (logical address space) to the physical memory and vice versa. FMMUs are configured via registers starting at $_{reg}$0x0600, see also example 3.

Reference: ETG.1000.4 – Fieldbus memory management unit

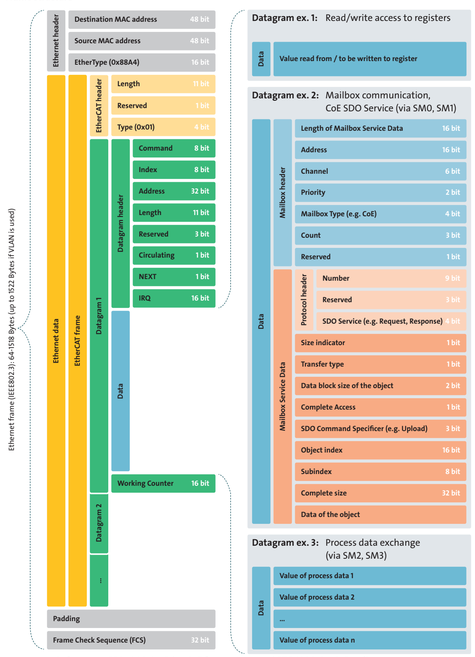
Frame processing and examples

Communication principle

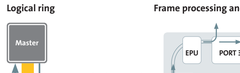
EtherCAT communication is always initiated by the master by sending frames via its Ethernet interface. Those are processed on the fly by the ESC. Processing within the ESC works in a "roundabout" fashion: Behind the EtherCAT Processing Unit (EPU) the frame is forwarded to the next port (and, if open, sent out to be processed by other slaves), while the returning frame is sent back to the master via port 0. Port 0 shall always be the IN port of the slave device. The topology always forms a logical ring, and neither frame collision nor congestion can occur by design. Throughput time can be calculated precisely, and errors can be detected easily via status and error counter registers ($_{reg}$0x0100, $_{reg}$0x0300 – 0x0313).

Reference: ETG.1000.4 – Frame processing principles

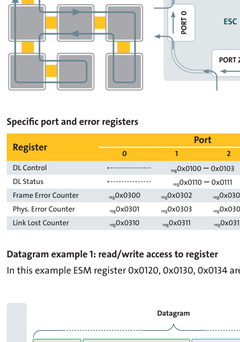
Frame structure



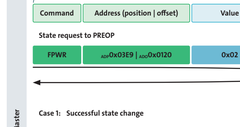
Datagram ex. 1: Read/write access to registers



Datagram ex. 2: Mailbox communication, CoE SDO Service (via SM0, SM1)



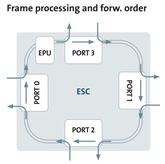
Datagram ex. 3: Process data exchange (via SM2, SM3)



References: ETG.1000.4 – EtherCAT frame structure | ETG.1000.6 – CoE coding

Logical ring

Frame processing and forw. order



Specific port and error registers

Register	Port			
	0	1	2	3
DL Control	$_{reg}$0x0100 — 0x0103			
DL Status	$_{reg}$0x0110 — 0x0111			
Frame Error Counter	$_{obj}$0x0300	$_{reg}$0x0302	$_{reg}$0x0304	$_{reg}$0x0306
Phys. Error Counter	$_{obj}$0x0301	$_{reg}$0x0303	$_{reg}$0x0305	$_{reg}$0x0307
Link Lost Counter	$_{obj}$0x0310	$_{reg}$0x0311	$_{reg}$0x0312	$_{reg}$0x0313

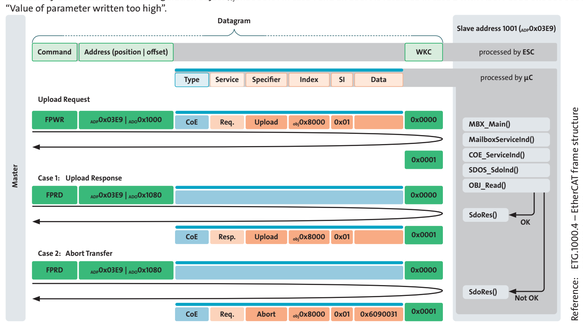
Datagram example 1: read/write access to register

In this example ESM register 0x0120, 0x0130, 0x0134 are written and read for state machine interactions.

Reference: ETG.1000.6 – Protocol State Machine

Datagram example 2: Mailbox communication, CoE SDO Service (via SM0, SM1)

In this example an SDO Download Request is written to SM0 Mailbox Out and the response/abort is read from SM1 Mailbox In: A value is successfully downloaded to the configuration object $_{obj}$0x8000:01 in case 1 and an abort is returned in case 2 with Abort Code 0x06090031 "Value of parameter written too high".



Reference: ETG.1000.4 – EtherCAT frame structure | ETG.1000.6 – SDO

Datagram example 3: Process data exchange (FMMU)

In this example process data is exchanged cyclically using a Logical Read Write command (LRW) and mapped by FMMUs to and from the slave's DPRAM (SM2/3).

Reference: ETG.1000.4 – Fieldbus memory management unit

Commands

EtherCAT commands (datagrams) address one or several slaves. Node addressing (APxx, FPxx) logical addressing (Lxx) and broadcast addressing (Bxx) is possible. With each successful read/write interaction every slave increments the Working Counter (WKC).

Specifier	Cmd	Description
0x00	NOP	No operation
0x01	APRD	Auto increment physical read
0x02	APWR	Auto increment physical write
0x03	APRW	Auto increment physical read write
0x04	FPRD	Configured address physical read
0x05	FPWR	Configured address physical write
0x06	FPRW	Configured address physical read write
0x07	BRD	Broadcast read
0x08	BWR	Broadcast write
0x09	BRW	Broadcast read write
0x0A	LRD	Logical memory read
0x0B	LWR	Logical memory write
0x0C	LRW	Logical memory read write
0x0D	ARMW	Auto increment physical read multiple write
0x0E	FRMW	Configured address physical read multiple write

Working Counter

Command	Action	Increment
xRD	Successful read	+1
xWR	Successful write	+1
xRW	Successful read	+1
	Successful write	+2

References: ETG.1000.4 – EtherCAT frame structure | ETG.1000.4 – Error detection overview