



# MBs-CBCANH

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User Manual

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CANopen Master Communication Board

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Version	Date	Author	Description
V1.0	2016/12/26	Edison Lin	Draft
V1.1	2017/01/04	Edison Lin	Revised section 6.2.1.4 for Auto. Start Remote
V1.2	2017/3/24	Edison Lin	<ul style="list-style-type: none"> <li>- Revised manual design</li> <li>- Remove single status indicator</li> <li>- Revised ladder program example</li> </ul>
V1.3	2017/5/24	Curtis Li	Support importing EDS/DCF file
V1.4	2017/7/18	Curtis Li	Revised function block
V1.5	2017/7/19	Edison Lin	Fixed typo
V1.6	2017/8/4	Edison Lin	Modified block ladder-related information
V1.7	2017/12/11	Curtis Li	Add SDO task and NMT task, remove older info about SDO and NMT operation

## 1. Overview

The CBCANH board is a CANopen master communication board for MBs-series PLC and can be mounted on the extended board slot of the CPU module thus saves space. Any MBs PLC can effectively control or exchange data with slave devices on the CANopen network with it.

CANopen is a CAN-based industrial protocol and is widely used in field applications, such as automatic controls for industrial machinery, automobile control systems, factory automation, medical equipment control, building automation, remote data collection and control, environmental monitoring and others.

Both RPDO number and TPDO number supported on CBCANH board are 60, and the range of corresponding PLC registers is from R3200 to R3679. For better user experience, board provides multiple convenient functions including AutoSDO, Auto Start Remote, SDO task and NMT task. By AutoSDO, a set of pre-defined SDO operations are executed automatically once the board is turned on. This is used to configure the target devices; By Auto Start Remote, all slaves in the network are turned into Operational state once the board is turned on; SDO and NMT task makes it possible that SDO and NMT operations are done by accessing PLC registers, and makes PLC programming easier.

## 2. Specification

Item	Characteristics	
Compliance with	CAN 2.0A , DS301 V4.02	
PDO number	RPDO	Max. 60
	TPDO	Max. 60
SDO number	Server	1
	Client	1
AutoSDO	Max. 30 groups, each of which supports up to 12 SDO operations	
Application parameter object	Max. 1000	
Sync master	Configurable Sync time	
NMT master	Available through EasyCANHopenner and NMT task	
Time stamp	Consumer	
Error control	Heartbeat	
Baud	20K, 50K, 125K, 250K, 500K, 750K, and 1M	

Configuration	Remote	Supported
	PC utility	EasyCANHopener
Remote PLC programming	Supported	
Vendor ID	2EF(Hexadecimal)	
Signal terminal	3 Pin spring terminal	
Electric isolation	Yes	
Voltage/current	5V, 150mA	
Working temperature	0 ~ 60 °C	
Storage temperature	-20 ~ 80 °C	

Table 1 The specification of MBs-CBCANH

### 3. Installation and wiring

MBs PLC provides an extension slot on the left side of the CPU module for installing an additional communication board.



Figure 1 CBCANH top view

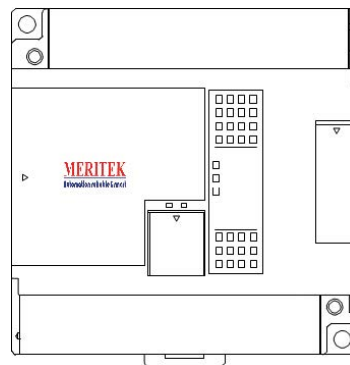


Figure 2 MBs PLC top view

The CBCANH connects to a CANopen network via a 3-pin spring style connector.

Pin	Signal	Description
1	CAN_H	CAN_H bus line (dominant high)
2	CAN_L	CAN_L bus line (dominant low)
3	CAN_GND	Ground / 0V / V-

Table 2 Definition of the pins

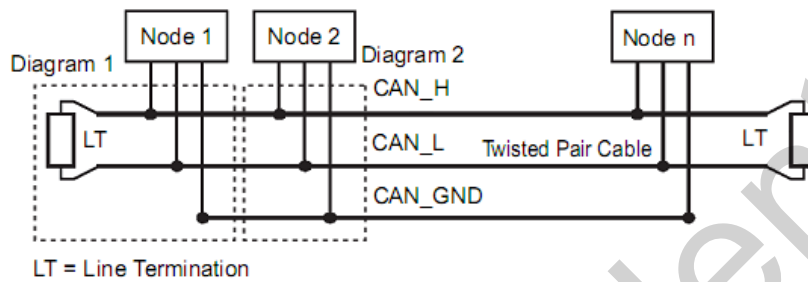


Figure 3 CANopen line termination

Normally for a node located at either left or right end of a network, a 120Ω 1/4W line termination resistor should be connected between CAN\_H and CAN\_L terminal pins as shown in above picture to ensure the signal quality, but for CBCANH, there's an easier way to implement the same function - short the jumper (JP4) labeled "Term" inside the CBCANH module. The following figure shows the location of the jumper.

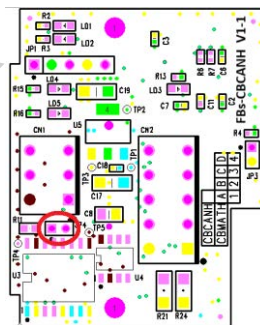


Figure 4 Term jumper location

#### 4. PLC application interface

The CPU module communicates with the CBCANH board via its internal registers. These registers basically fall into the following areas:

##### 4.1 Communication interface area

In this area, there are 70 reserved registers, ranging from R3700 to R3769.

These registers shall be reserved for internal system operation and CAN NOT be used for user's applications since the configuration tool, EasyCANHopper, communicates with the CBCANH through this area.

#### 4.2 Parameter data area

The size of this area is configurable up to 1000 registers. From the point of view of the network, these registers in this area act as objects for access. These registers can be addressed by their indexes and sub-indexes, thus they can be accessed by SDO services. With this function, users can change or adjust parameters of users' applications over network easily during system installation in the field.

#### 4.3 Process data area

There are 80 registers in this area, ranging from R3200 to R3679. The real-time data(PDO) of the PLC is exchanged with other nodes on the network via this area.

Sequence	Item	Function	Register
1	RPDO1	Word #1	R3200
2		Word #2	R3201
3		Word #3	R3202
4		Word #4	R3203
5 ~ 240	RPDO2 ~ RPDO60		R3204 ~ R3439
241	TPDO1	Word #1	R3440
242		Word #2	R3441
243		Word #3	R3442
244		Word #4	R3443
245 ~ 480	TPDO2 ~ TPDO60		R3444 ~ R3679

Table 3 Process data area

The data length (0-4, with one register size per unit) of each PDO (Process Data Object) is configurable. When the data length is smaller than 4, preceding registers will be used first. For example, if the length of RPDO1 is 2, only the first two registers R3200 and R3201 will be used. The starting register number of each PDO is fixed and will not be changed even if a preceding PDO does not use up all of its usable registers. Any unoccupied registers in this range can be free to use by applications.

#### 4.4 Module status area

Sequence	Register	Function	
1	R3680	Module Status	Low Byte: Bit 0 : =0, Normal =1, Stopped when excessive RX error occur while startup. Bit 1: AutoSDO execution status Bit 2: Reserved Bit 3: =1, CAN Rx error Bit 4: =1, CAN Tx error High Byte: Bit[15:8] CBCANH state. =0, init. =5, OPERATIONAL. =4, STOPPED. =127 PRE-OPERATIONAL
2	R3681 ~ R3684	TPDO Status	Each bit represents the receiving status of each TPDO. When a bit =1, it means data update is normal.
3	R3685	Heart beat status	Nodes 1-15 When Bit[1]=1, it means the heartbeat in Node 1 is detected. The detection cycle is determined by Heartbeat guard Time. When Heartbeat guard time = 0, this register is not valid since CBCAN will not monitor heartbeat signals
4	R3686		Node 16-31
5	R3687		Node 32-47
6	R3688		Node 48-63
7	R3689		Node 64-79
8	R3690		Node 80-95
9	R3691		Node 96-101
10	R3692		Node 102-127
11	R3693	Time Stamp	Second (0-59)
12	R3694		Minute (0-59)
13	R3695		Hour (0-23)
14	R3696		Day (1-31)
15	R3697		Month (1-12)
16	R3698		Year (2000-2099)



17	R3699	Time Stamp receiving indication	The value of this register increment by one when a new Time Stamp packet is received and rollover at 65535.
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Table 4 Module status area

#### 4.5 Reserved PLC registers for block ladders

Register	Description	
R3100 - R3199	R3116	CMR parameter: The number of register to send
	R3106	CMR parameter: The base register to send
	others	Internal use
M1000, M1962	Internal use	

Table 5 Reserved PLC registers

### 5. LED Indicators

Indicator State	Node Operation State
Single flash	PRE-OPERATIONAL
on and off every 2 secs	STOPPED
Blinking	OPERATIONAL

Table 6 RUN LED(green)

Indicator State	Error State
Off	No error
Single flash	Warning limit reach
Triple flash	Rcv. SYNC signal is time-out
Quadruple flash	Any one of expected TXPDOs is time-out
On	Bus off

Table 7 ERR LED(red)

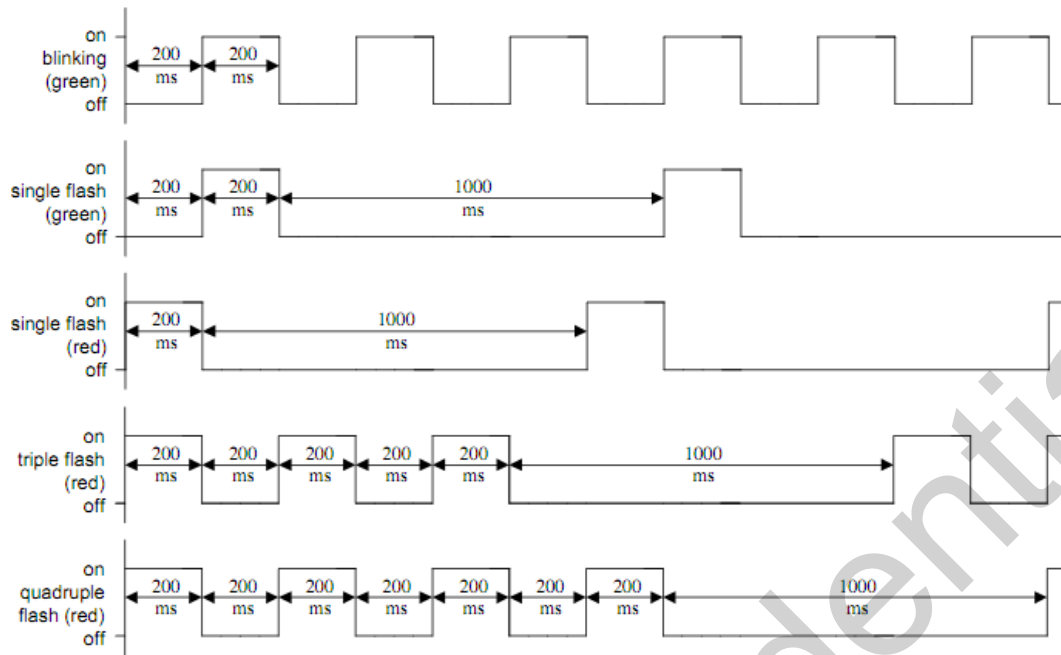


Figure 5 Indicator status and flash rate

## 6. EasyCANHopener

Major functions of the software:

- Configuration of the CBCANH board, including RPDO and TPDO mapping, AutoSDO, SDO task, NMT task, Auto Start Remote, and other settings. Configuration can be exported as a chcfg file for duplication, storage, and modification offline.
- SDO Service: Users can either access a single controller object directly, or access multiple objects using batch operation. The batch contents can also be saved in files to be reused in the future.
- PLC remote access bridge: The MBs PLC is usually connected to the Winproladder via local serial port. When this function is enabled, the CBCANH can work as a remote programming gateway, and the Winproladder can connect to another MBs PLC equipped with CBCAN board at remote site through the CBCANH.
- NMT service: with a single operation, users can send "Start Remote", "Enter PRE-OPERATIONAL", "Reset Node", "Reset Communication" or "Stop" commands to a specific node or all nodes on the network.
- CBCANH firmware update: Users can update the firmware of the CBCANH board on the PLC via the serial port.

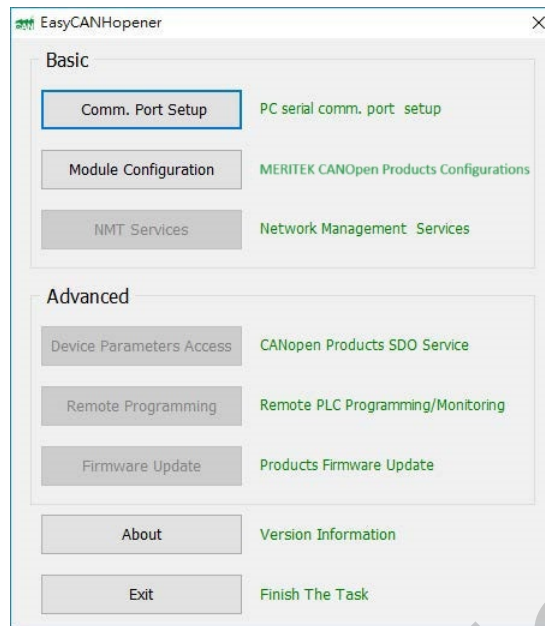


Figure 6 Main menu

### 6.1 PLC connection

All operations requiring a PLC connection will not be enabled before a successful serial communication with the PLC, so one has to use Comm. Port Setup to establish the connection beforehand, as shown in the Figure 7.

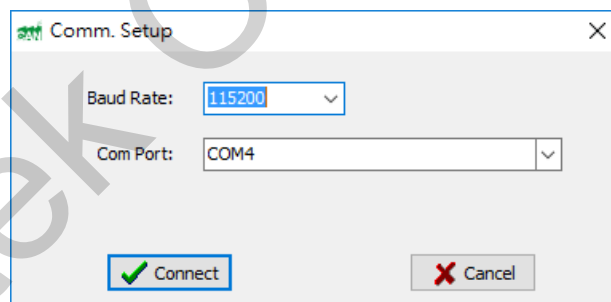


Figure 7 Baud setup

A full functioning main menu can be referred to in the Figure 8.

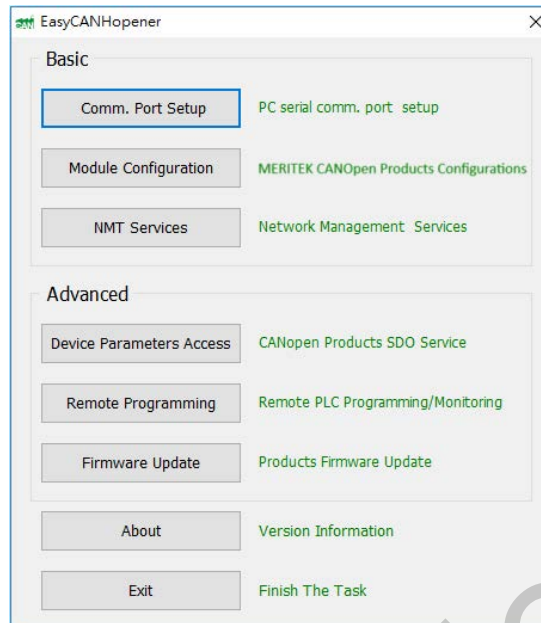


Figure 8 Main menu with full functions

## 6.2 Configuration setup

Click the “Module Configuration” button on the main page to enter the Configuration Setup screen as shown below.

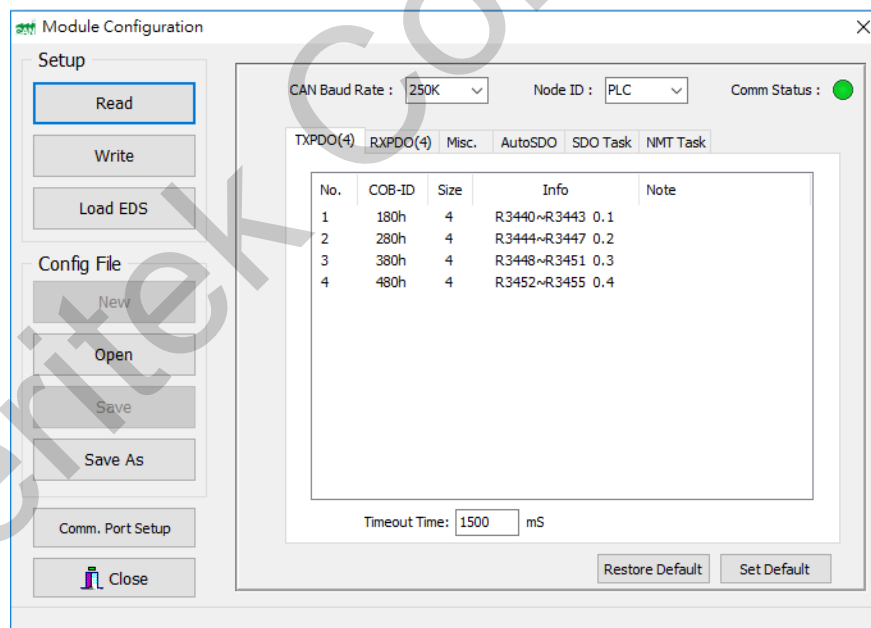


Figure 9 Configuration setup

### 6.2.1 Create new configuration

When entering the Configuration Setup screen, a new configuration file will be generated automatically and all parameters are in their

default values. Users should be aware that node ID in PDO default configuration is empty.

#### 6.2.1.1 Basic setup

**CAN Baud Rate:** This is the network operating speed. The default value is 250K bps. The range is 20K-1M bps. The same baud rate must be set for all node devices on the network; otherwise, they will not operate properly.

**Node ID:** This ID is set to indicate the node id of the CBCANH on the CANopen network and can be configured as 1-127 or "PLC". When it is set to "PLC", the node ID will be configured with the station number of the PLC CPU module for quick integration into the system without additional efforts. The default value for this setting is "PLC".

**Comm Status:** An indicator shows the connection status with the PLC. Normally a green light should be observed.

#### 6.2.1.2 TPDO setup

Click the TPDO tab to enter the receive process data object (TPDO) setup page as shown in the figure below. It is used to receive real-time data from slaves.

The screenshot shows the 'TXPDO(4)' tab selected. Below the tabs is a table with the following data:

No.	COB-ID	Size	Info	Note
1	180h	4	R3440~R3443 0.1	
2	280h	4	R3444~R3447 0.2	
3	380h	4	R3448~R3451 0.3	
4	480h	4	R3452~R3455 0.4	

At the bottom, there is a 'Timeout Time' field set to '1500' with 'mS' as the unit.

Figure 10 TPDO setup

The number in the parentheses of the tab name represents the

quantity of PDOs that has been defined.

As shown in the Figure 10, four TXPDOs have been defined. The TPDO can be configured by the pop-up menu as shown in the figure below.

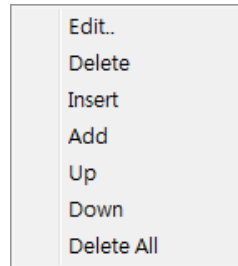


Figure 11 TPDO pop-up menu

The functions in this popup menu are described as below:

- Edit: Right-click on the PDO you want to edit to start the pop menu, and select Edit... from the menu. Or, simply double-click the PDO you want to edit to start the following screen.

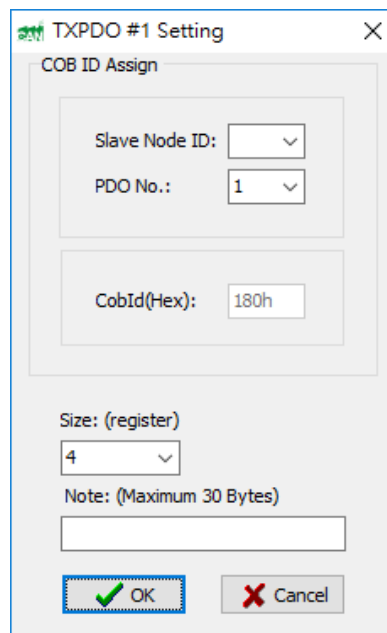


Figure 12 Edit TXPDO

From this screen, users can configure the communication object ID (COB-ID) and data length:

- COB-ID : Each node on the CANopen network has a unique set of COB-IDs for PDO mapping, and CBCANH

as a master needs to know what the mapping is like on the network in order to control or receive data as expected. Also each node can own up to 4 TXPDO COB-ID and 4 RXPDO COB-IDs for data exchange. Figure 12 shows a default TXPDO setting with empty node ID. Be sure to fill in a valid ID while configuring.

- Size Setup: The valid size of the TXPDO can be from one to four 16-bit words.
- Note: Comment of a TPDO
- Delete: Right-click the PDO you want to delete and select “Delete” from the pop menu to delete the PDO.
- Insert: Right-click any location where a PDO to be inserted and select “Insert” from the pop menu to start the PDO Edit screen. After the configuration on the popup menu is done, a new PDO will be inserted at the location addressed.
- Add: Right-click the screen to start the popup menu. Select “Add” to start the PDO Edit screen. After the configuration on the popup menu is done, a new PDO will be added at the end of the list.
- Up: Right-click the PDO to be moved up. Select “Up” on the popup menu to move the PDO to one position upward.
- Down: Right-click the PDO to be moved down. Select “Down” on the popup menu to move the PDO to one position downward.
- Delete All: Right-click on the screen to start the pop menu. Select “Delete All” to delete all PDOs in the list.

There is an additional item “Timeout Time” at the bottom of the TPDO setup page as shown in Figure 10:

***Timeout Time:***

This setting is used to indicate the deadline after the reception of a TPDO message. If TPDO messages are received properly within

this interval, the corresponding bit of PLC internal register R3681 “TPDO status” will be set to 1. If not, the bit will be set to 0 to indicate the TPDO timeout event. The default value for this setting is 1.5 seconds.

### 6.2.1.3 RPDO setup

The RPDO setup is similar to the TPDO's; this section only described the difference between TPDO and RPDO setup. Please refer to the section 6.2.1.2 for those similar settings.

There is one additional item “Transmission Type” added to the RXPDO Edit page:

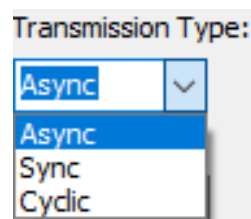


Figure 13 Transmission type

#### Transmission Type

- Async (asynchronous transmission): A RPDO is transmitted when the RPDO data is changed or event time is elapsed. After RPDO messages are transmitted, the end of the Inhibit Time must be reached before sending next RPDO message. With this function, users can prevent the communication bandwidth from being consumed by unexpected high frequency of input signals.
- Sync. (synchronous transmission): Whenever the status changes, the RPDO message will be transmitted immediately after the next SYNC message is received.
- Cyclic: RPDO messages are transmitted periodically in time with the cyclic time setting.



TXPDO(4)		RXPDO(4)		Misc.	AutoSDO	SDO Task	NMT Task
No.	COB-ID	Size	Info	Note			
1	200h	4	R3200~R3203 0.1				
2	300h	4	R3204~R3207 0.2				
3	400h	4	R3208~R3211 0.3				
4	500h	4	R3212~R3215 0.4				

Inhibit Time:  mS    Event Time:  mS    Cyclic Time:  mS

Figure 14 RXPDO setup

**Inhibit Time** The minimum transmission time interval when RXPDO are transmitted in Async. mode. After the transmitting of RXPDO messages, the next RXPDO message will not be sent until the end of inhibit time even if the status is changed during the inhibit time period. The default value is 10ms and cannot be changed.

**Event Time** The maximum transmission time interval when RXPDO are transmitted in Async. mode. After the transmitting of RXPDO messages, the next RXPDO message will be sent immediately after the end of event time even if the status is not changed during the event time period. The default value is 1 second.

**Cycle Time** The transmission time interval used in the Cyclic mode. The default value is 2 seconds.

#### 6.2.1.4 Miscellaneous

Click the “Misc.” tab to edit miscellaneous setup as shown in the Figure 15 below.

The screenshot shows the 'Misc.' configuration tab. Under 'HeartBeat', 'Cycle Time' is 1000 mS and 'Guard Time' is 1050 mS. Under 'Parameter Zone', 'Size' is 0 and 'Start Address' is R 0. The 'Sync. Master' checkbox is checked, with a 'Sync. Time' of 100 ms. The 'Auto. Start Remote' checkbox is also checked.

Figure 15 Misc. setup

**Heartbeat** This informs the existence of a node within a specific time interval. In normal circumstances, a node will send a heartbeat signal at a regular interval. Other nodes determine if this node is operating normally based on this signal.

- **Cycle Time:** This represents the regular interval the node sends the heartbeat signal. If the value is “0”, this means the heartbeat function is disabled.
- **Guard Time:** This represents the time criteria for a node to detect if the heartbeat of other nodes is normal. In general, individual nodes have individual cycle times, thus users should set different cycle times for different nodes. However, this system assumes that the cyclic time of all nodes are the same in order to simplify the configuration process. In this case, the value must be greater than the default value.

**Parameter data** In general, there are usually some parameters that do not change frequently. These parameters can be mapped to the CANOpen objects through the SDO (Service Data Object) service for remote access over the network.

- **Size:** This setting is to indicate the quantity of the mapped registers. The maximum value is 1000.

- **Start Address:** This represents the start address of the mapped register. Only R-registers can be mapped as parameter registers.

**Sync. Master** When this option is enabled (checked), the CBCANH will operate as a sync. master node which transmits synchronous messages.

**Sync. Time** When Sync master option is enabled, this value represents the interval of synchronous messages transmission.

**Auto Start Remote** When enabled, the CBCANH will put all the slaves on the network in OPERATIONAL mode using NMT after boot up and the execution of AutoSDO if any.

#### 6.2.1.5 AutoSDO

Maximum 30 groups are supported and each of which can be configured up to 12 SDO operations. Each group can have unique node ID or share the same node ID if more operations are needed. AutoSDO will be executed sequentially during power on or through a ladder program and the result can be checked through the configuration tool. It could be used to configure slaves automatically before the execution of a ladder program.

**WR** A SDO operation which writes data into a slave device, e.g. PDO mapping and any preset value.

The screenshot shows the 'ASCmdEdit' dialog box with the following fields and values:

Field	Value
Operation	Write
Object Index (Hex)	6040
Sub Index (Hex)	0000
Data Size (Bits)	16
Data (Hex)	047E
Status Code (Hex)	00000000

At the bottom, there are 'OK' and 'Cancel' buttons.

Figure 16 AutoSDO write operation

**MR** A SDO operation which reads data from a slave device and compares it with preset data. A mask will be used to logical AND with data read, which makes a BIT comparison possible. Status Code shows the result of monitoring.

The screenshot shows a dialog box titled "ASCmdEdit" with a "Command" section. The "Operation" dropdown is set to "Monitor". The "Object Index (Hex)" is 6041, "Sub Index (Hex)" is 0000, and "Data Size (Bits)" is 16. The "Data (Hex)" field contains 1231, and the "Mask (Hex)" field contains FFFF. The "Status Code (Hex)" field is empty. At the bottom, there are "OK" and "Cancel" buttons.

Field	Value
Operation	Monitor
Object Index (Hex)	6041
Sub Index (Hex)	0000
Data Size (Bits)	16
Data (Hex)	1231
Mask (Hex)	FFFF
Status Code (Hex)	

Figure 17 AutoSDO monitor

### 6.2.2 SDO Task

SDO task makes it possible that SDO operations can be done by accessing registers of PLC. Adding a new SDO task is as simple as configuring it with index and sub-index of a specific node, operation mode, type and start address of corresponding PLC registers in SDO task page. After the setup is finished, accessing the corresponding PLC registers is the same as accessing SDO data. Maximum 32 operations are supported.

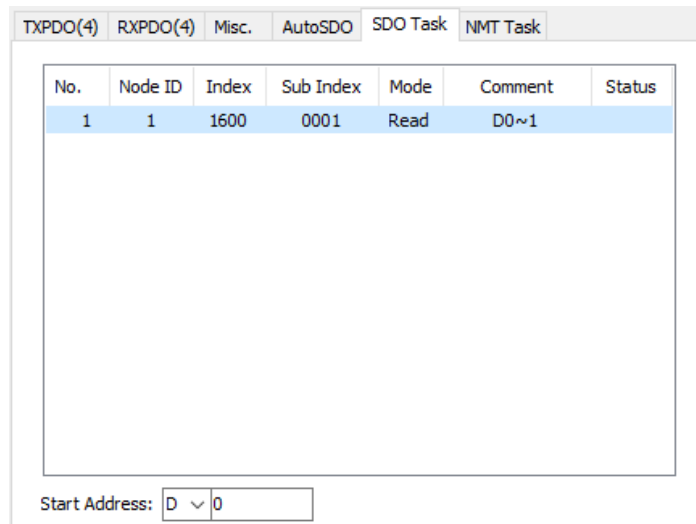


Figure 18 SDO task setup

As shown in Figure 18, SDO task supports two modes, including read and write. Both of them support data access in three variant data length (8/16/32 bits). Status code shows the result of execution, either success or error code is returned.

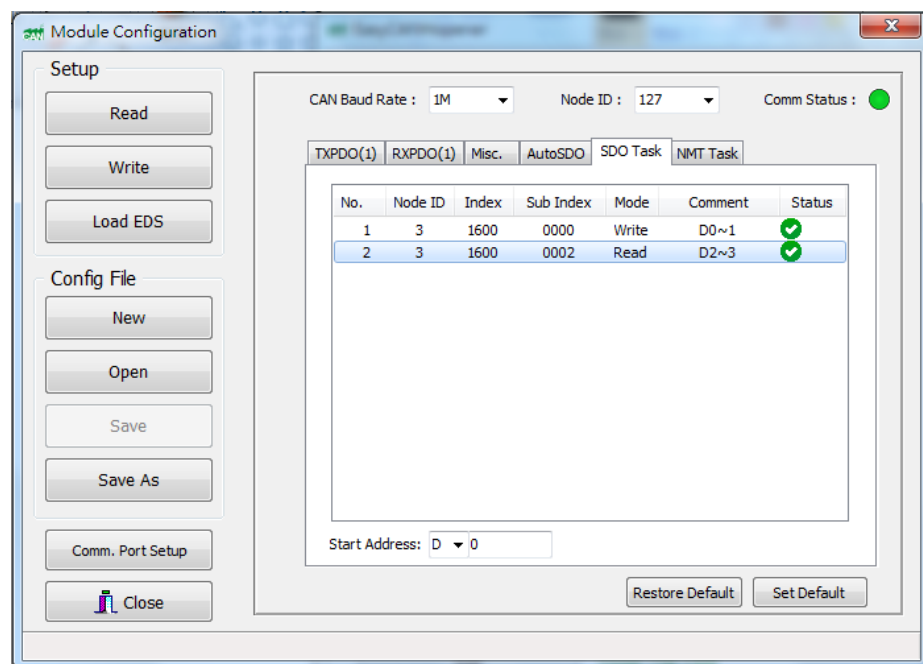


Figure 19 SDO task page

If the operation mode is read, the data accessed from slaves is put into the corresponding PLC registers. If the operation mode is write, the data which is about to be transmitted is put into the

corresponding PLC registers. As shown in Figure 19, each SDO task occupies two PLC registers regardless of the data size.

### 6.2.3 NMT Task

NMT task makes it possible that NMT commands can be done by accessing registers of PLC. Adding a new NMT task is as simple as configuring it with target node, NMT command, type and start address of corresponding PLC registers in NMT task page. After the setup is finished, accessing the corresponding PLC registers is the same as executing NMT command. Maximum 32 operations are supported.

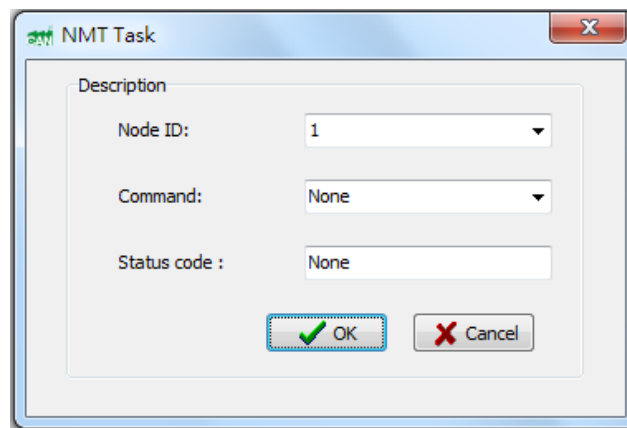


Figure 20 NMT task setup

The NMT task setup page is shown in Figure 20. Besides the same NMT commands that NMT Services has, NMT task has one additional command named "none". NMT command "none" has no default command and used in the situation when the operation is decided sometime later. Status code shows the result of execution, either success or error code is returned.

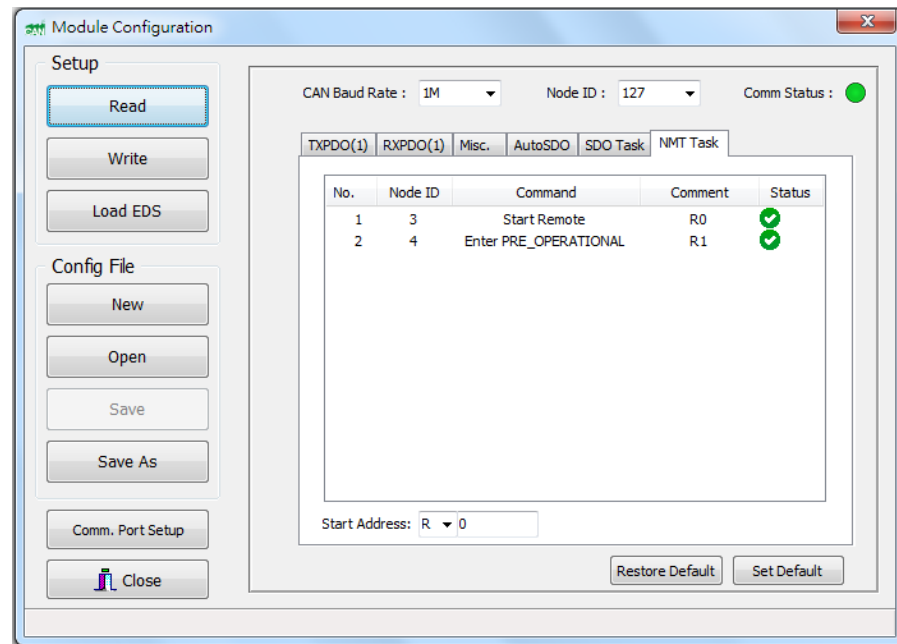


Figure 21 NMT task page

As shown in Figure 10, each NMT task occupies one PLC register. The Most Significant Byte(MSB) of corresponding PLC register stores NMT command, while the Least Significant Byte(LSB) of corresponding PLC register is used to trigger command and store the result of execution. The corresponding value of NMT command, as shown in Table 1, is filled into MSB. The value filled into LSB to trigger command is shown in Table 2.

NMT Command	Value
None	0
Start Remote	1
Enter Pre-Operational	2
Reset Node	3
Reset Communication	4
Stop	5

Table 8 Corresponding values of NMT commands

Status Code	Description
0001h	Successful
0002h	Failed
Other Values	Trigger Command

Table 9 Corresponding values of status codes

For example, to execute NMT command “Start Remote” through NMT task, one should set the content of corresponding PLC register as value shown below:

**0103H**


After execution, status code returns the result. If it works successfully, the content of corresponding PLC register should be the same as value shown below:

**0101H**

#### 6.2.4 Save configurations to files

Click the “Save...” or “Save As” button. The save configuration window will pop up. Input the name of the file to be saved and click the “Save” button to save the configurations.

#### 6.2.5 Open old configuration files

Click the “Open...” button. The open configuration file window will pop up. Click the  button and select the configuration files that have been saved. Click the OK button to open the selected configuration file.

#### 6.2.6 Read CBCANH configurations

Click the “Read” button to retrieve current configuration in the module.

#### 6.2.7 Write configurations to CBCANH Board

Click the “Write” button to write configuration into the module.

#### 6.2.8 Load EDS



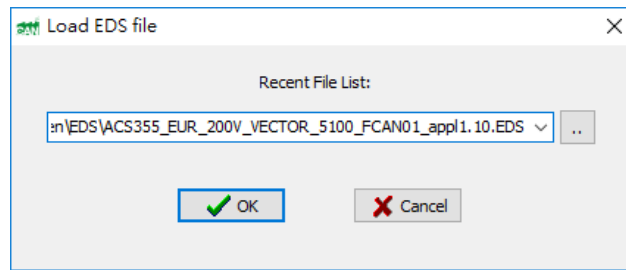


Figure 22 Load EDS file

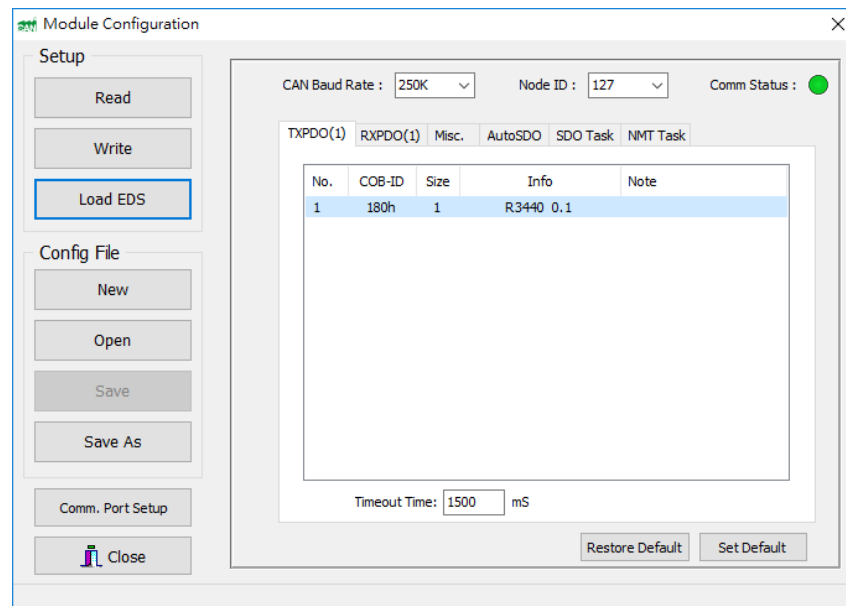


Figure 23 After loading a EDS file

### 6.2.9 End configuration setup

Click the “Close” button to exit the relevant configuration setup functions.

## 6.3 SDO Service

Click the “Device Parameter Access” button on the main page to enter the SDO Service screen as shown below. The setup items are described below.

**Node ID:** ID of one of the nodes on the network.

**Index:** Object index

**Sub-Index:** Object sub-index

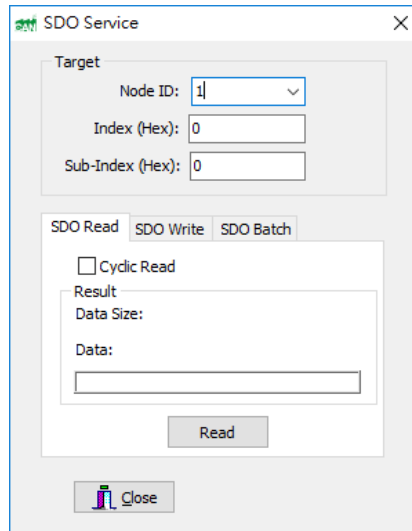


Figure 24 SDO service page

### 6.3.1 SDO Read

Click the SDO Read tab to enter the SDO Service screen as shown in Figure 25.

**Cyclic Read** Select (check) this option to read SDO data repeatedly. This function is useful for observing the dynamic change of objects.

**Read** Click the button to start reading SDO data. The results will be displayed in the window as shown below.

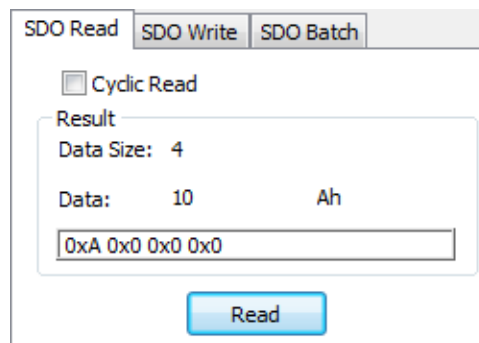


Figure 25 SDO read page

The value “4” in the Data Size item means that the size of the data is 4 bytes. The data content are given in decimal (10), hexadecimal (AH) and string type (0xA 0x0 0x0 0x0).

### 6.3.2 SDO write

Click the SDO Write tab to enter the SDO Write service screen as shown in Figure 26.

Figure 26 SDO write page

**Data Type** Type of object data. Only Byte, Word and Dword data are supported.

**Data** The value to set. Users can select data format from the pull-down list next to the box: Hex (hexadecimal) or Decimal.

**Write** Click the button and start to write. An error window will pop up if there is any error.

### 6.3.3 SDO batch

By using SDO batch, a list of pre-defined multiple SDO commands can be sent out sequentially. It is very useful when multiple CBCANH modules need to be set up with similar configuration, thus users don't need to configure all functions one by one.

First, click the SDO Batch tab to enter the SDO batch screen as shown in Figure 27.

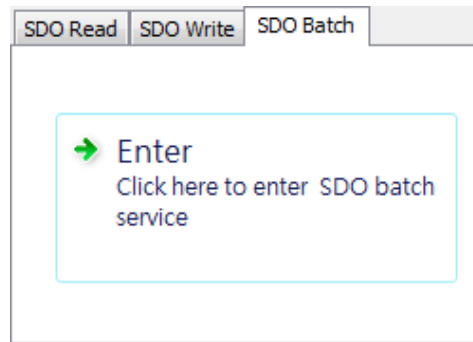


Figure 27 SDO batch

Click on the SDO batch window in Figure 27 to start SDO batch editing as shown in Figure 28.

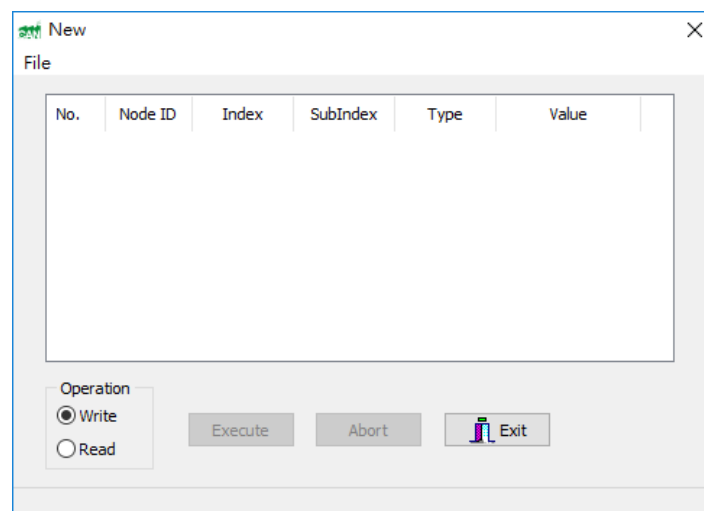


Figure 28 SDO batch setup page

#### 6.3.3.1 Create batch contents

After entering the SDO batch service screen, there should be no batch contents. Then, users can create the batch content. The menu pops up as shown below.

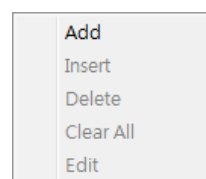


Figure 29 pop-up menu for creating batch

**Add:** Right-click the batch content window and select “Add” from the pop menu to start the following window.

Figure 30 Add a SDO command

**Node ID** Select the ID of the node you want to write SDO data to.

**Index** Input the index value.

**Sub-Index** Input the sub-index value.

**Data Type** Select SDO data type: Byte, Word or Dword.

**Value** Input a value.

Click the OK button to complete the creation of the new batch content.

**Insert:** Right-click the location where the batch command to be inserted and select “Insert” from the pop-up menu. Click the “OK” button to insert a new batch command in the specified location.

**Delete:** Right-click the batch item you want to delete and select “Delete” from the pop-up menu to delete the SDO command.

**Delete All:** Right-click the batch content window and select “Delete All” from the pop-up menu to delete all batch commands.

**Edit:** Right-click the batch item you want to edit and select “Edit” from the pop-up menu or double-click the command item to edit its content. Then, click the “OK” button to complete modifying the content.

### 6.3.3.2 Save batch contents

Click “File” from the main menu at the top of the window and click “Save” or “Save As” from the pull-down to save the current batch contents in a file.

### 6.3.3.3 Read this batch file

Click “File” from the main menu at the top of the window and click “Open” from the pull-down list to read the contents of the batch file.

### 6.3.3.4 Execute batch write

First, select the “Write” option in the operation group. Then, click the “Execute” button to start batch write. SDO write commands will be sent out according to the contents in the batch window.

### 6.3.3.5 Execute batch read

First, select the “Read” option in the operation group. Then, click the “Execute” button to start batch read. SDO read commands will be sent out according to the contents in the batch window. It differs from “batch write” in the read-back values will overwrite the original ones.

## 6.4 PLC remote monitoring service

With this service, the ladder programming software, Winproladder, connects to the remote PLC equipped with the CBCANH board via the PC serial port. The ladder programs on the remote PLC therefore can be modified using CANopen network.

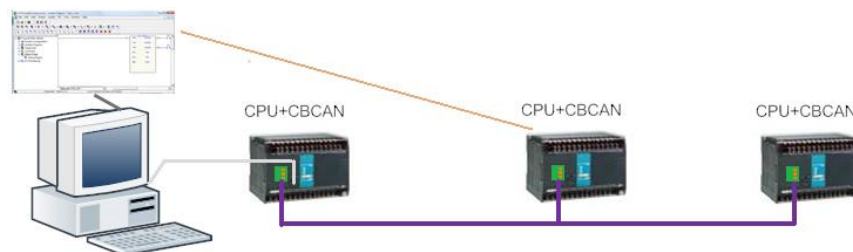


Figure 31 PLC remote monitoring service

### 6.4.1 Open service

Click the “Remote Programming” button on the main page to enter the remote monitoring service screen as shown in Figure 32.

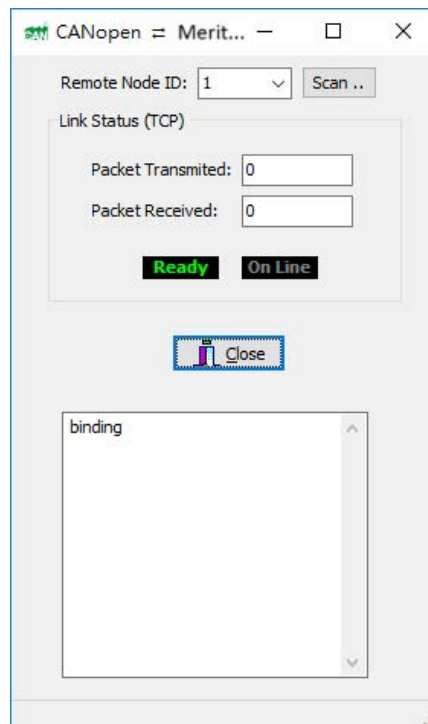


Figure 32 Gateway status window

Items in the screen are described as follows:

**Remote Node ID:** Input the ID of the node which you want to connect.

**Link Status:** Auxiliary status.

**Packet Transmitted:** The quantity of data packets transmitted to the remote PLC.

**Packet Received:** The quantity of data packets received from the remote PLC.

This service is completed through the local CBCAN module which operates as a gateway between the remote PLC and local Winproladder software. It is based on the TCP communication at port 500.

**Ready:** When the system is ready for the service, the button is green.

**On Line:** When the TCP network and application are linked, the button is green.

#### 6.4.2 Run service

Users must connect to local machine IP 127.0.0.1 at port #500 via TCP connection to subscribe the service. Therefore, an example of Winproladder settings is shown in Figure 33:

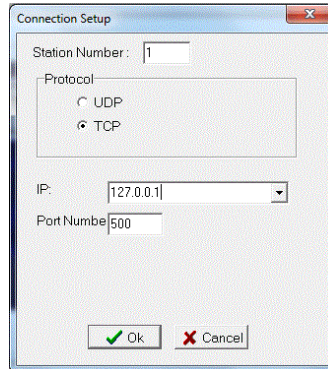


Figure 33 WinProladder connection setup page

As it is connected via the TCP communication, users can link up with the CANopen network with Ethernet from a remote site.

#### 6.5 NMT Services

Click the “NMT Service” button on the main page to enter the NMT Services screen as shown in Figure 34.

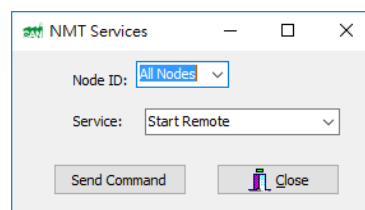


Figure 34 NMT service

**Node ID:** Input the ID of the NMT slave node to be managed. Users can select either a single node (1-127) or all nodes.

**Service:** The service includes “Start Remote”, “Enter PRE\_OPERATIONAL”, “Reset Node”, “Reset Communication”, and “Stop”



After the configuration is done, click the “Send Command” button to start NMT service.

## 6.6 CBCANH Firmware Update

Click the “Firmware Update” button on the main page to enter the Firmware Update screen as shown in Figure 35.

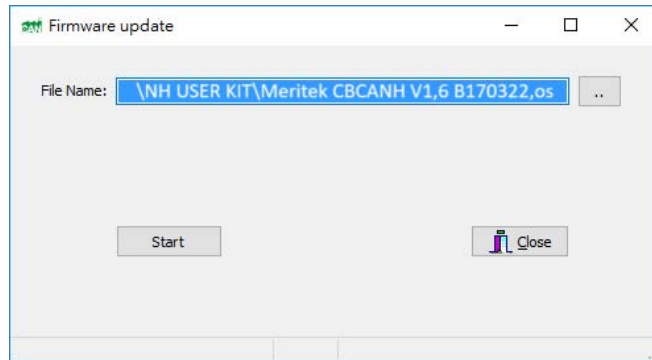



Figure 35 Firmware update

### 6.6.1 Select firmware files

Click the  button to open the file selection window. After selecting the firmware file, press the “OK” button, the following confirmation dialog box will pop up with the corresponding firmware information.

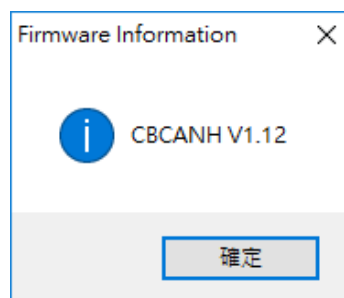


Figure 36 Firmware information

### 6.6.2 Start firmware update

Click the “Start” button to start the firmware update.

## 6.7 End operations

Click the “Exit” button on the main page to close EasyCANHOpener utility.

## 7. Block ladders for CBCANH control

### - CMR

As shown in Figure 37, it is a calling block used to update a certain set of PLC registers which maps to configured RPDOs to the CBCANH. Place only one of it in the bottom of the main ladder program and make sure the corresponding reserved registers have been set as intended. Refer to section 4.5 and the appendix A for more information.

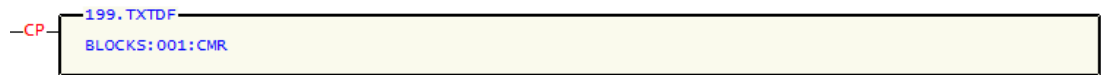


Figure 37 CBCANH-specific block ladder - CMR

### - AUTOSDO\_CTRL

As shown in Figure 38, it is a calling block which provides an alternative way to execute AutoSDO groups in the ladder program. Users should call the block ladder from a sub-function in case of triggering, as shown in Figure 39.

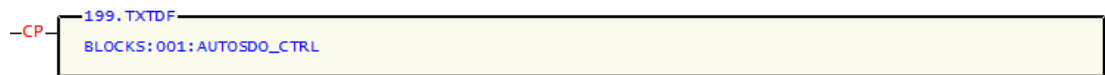


Figure 38 CBCANH-specific block ladder - AUTOSDO\_CTRL

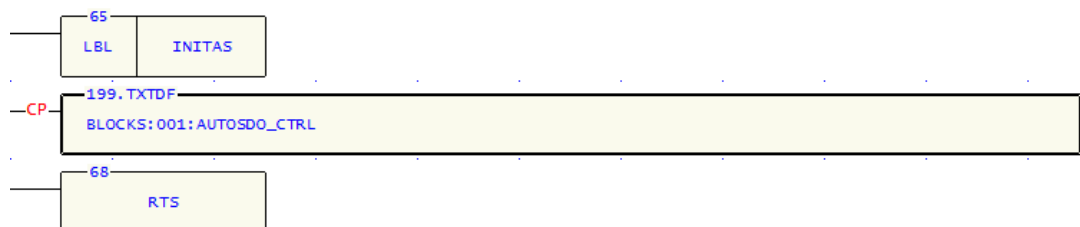


Figure 39 Calling AUTOSDO\_CTRL from a sub-function

## Appendix A

### 1.1 Application Notes

CBCANH is a CANopen master communication module which provides the MBs series PLC with the ability to exchange data with or control slave devices. Most of the CANopen objects in the CBCANH are configurable via EasyCANHopenner utility and shall be configured properly according to field network requirements. The purpose of this section is to provide a quick configuration reference to assist users to embrace the world of CANopen control.

#### 1.1.1 Example: Homing control of a Estun servo drive

The environment setup is a CANopen network with CBCANH as a master device and Estun servo drive as a slave device. The ladder program example uses a timer to activate or deactivate the homing operation.

The CBCANH as a master uses the configuration in the following table to connect to the CANopen network.

items	Values
Node ID	8
Slave Node ID	1
Baud	1M bps
Sync. master	Disabled
Error control	Heartbeat producer (1000 ms) Heartbeat consumer (1050 ms)
Number of AutoSDO group	2
Number of RPDO	1 (1 Word) Transmission type: Async. Mode
Number of TPDO	N/A

Table 10 network configuration

All settings can be configured via EasyCANHopenner to properly prepare the CBCANH for the example. The node ID and baud are usually first things to configure in terms of master settings. To start configuration, click the “Module Configuration” button on the main page of EasyCANHopenner.

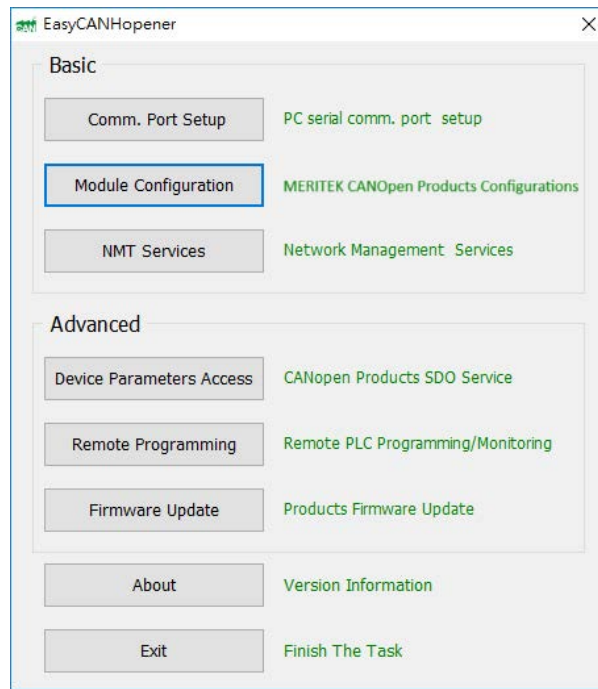


Figure 40 Main menu

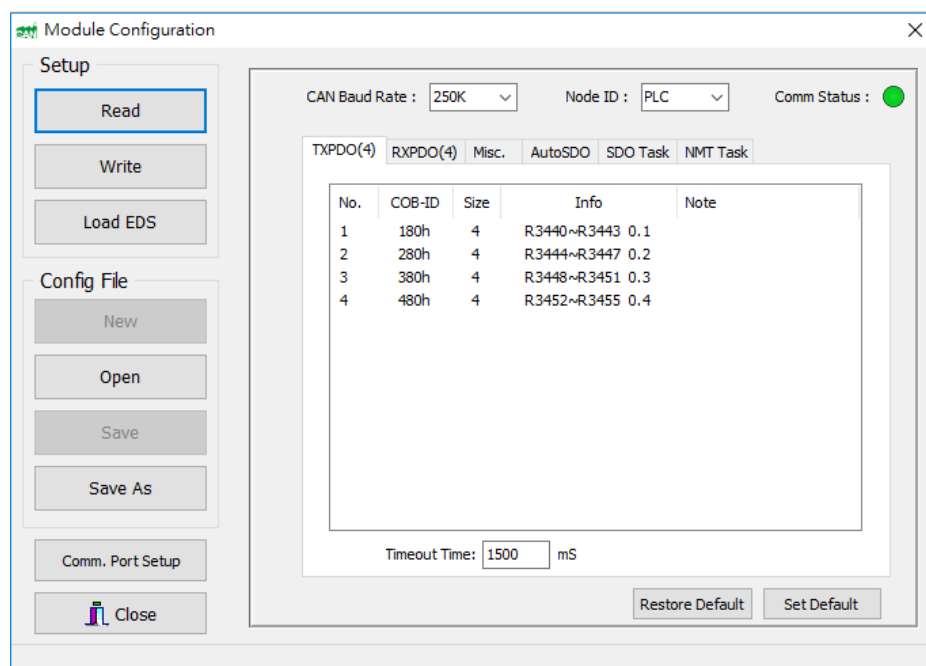


Figure 41 Module configuration

The node ID of the Estun servo drive is 1, thus any other ID except 1 in the range of 1 and 127 can be assigned to CBCANH. Assuming that the MBs PLC uses 8 as the station number, the node ID for the CBCANH can be configured as "PLC" to use the same.

CAN Baud Rate : 1M Node ID : PLC

Figure 42 Baud and node ID configuration

### AutoSDO setting

Configure as shown in the Figure 43

TXPDO(0) RXPDO(1) Misc. AutoSDO SDO Task NMT Task

No.	Node ID	Status	Count
1	1	ON	12
2	1	ON	2

AutoSDO Node 0

☒ Enabled

Node ID: 1

No.	Mode	Index	Sub Index	Data	Mask	Status
1	WR	6040	0000	0000	-	
2	WR	6040	0000	0080	-	
3	WR	1600	0000	00	-	
4	WR	1600	0001	60400010	-	
5	WR	1600	0000	01	-	
6	WR	6060	0000	06	-	
7	WR	6098	0000	04	-	
8	WR	6099	0002	00000064	-	
9	MR	6041	0000	0000	000F	
10	WR	6040	0000	0006	-	
11	MR	6041	0000	0001	000F	
12	WR	6040	0000	0007	-	

OK Cancel

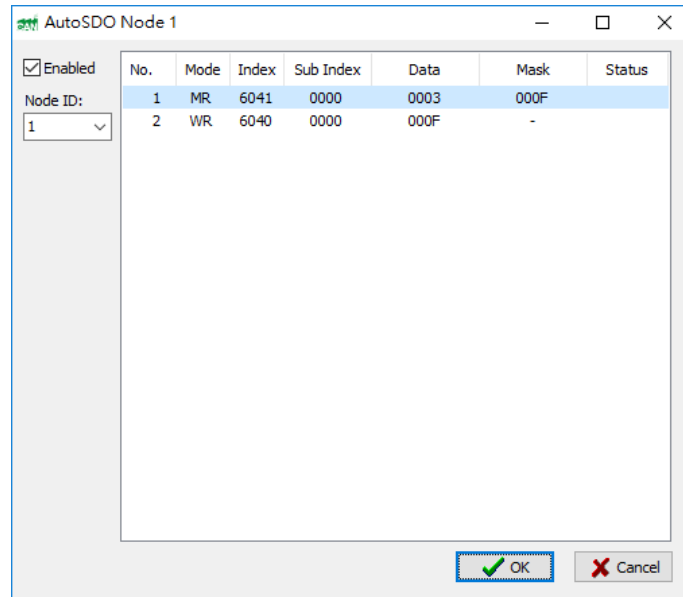


Figure 43 AutoSDO setup

Two AutoSDO groups with 14 SDO operations are created for the Estun servo drive following the homing example given in the CANopen operation manual of Estun servo drive. The node IDs of the groups should be 1.

AutoSDO write operation is as shown in the Figure 44

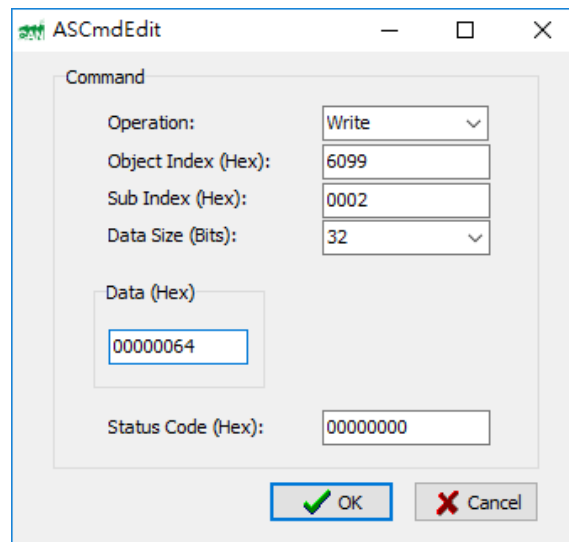


Figure 44 AutoSDO write

WR is a SDO download operation , which writes a given length of data(8/16/32 bits) into a target object dictionary index.

AutoSDO monitor operation is as shown in the Figure 45

The screenshot shows a dialog box titled "ASCmdEdit" with a "Command" section. The "Operation" is set to "Monitor". The "Object Index (Hex)" is "6041", the "Sub Index (Hex)" is "0000", and the "Data Size (Bits)" is "16". The "Data (Hex)" field contains "0003" and the "Mask (Hex)" field contains "000F". The "Status Code (Hex)" field is empty. At the bottom, there are "OK" and "Cancel" buttons.

Field	Value
Operation	Monitor
Object Index (Hex)	6041
Sub Index (Hex)	0000
Data Size (Bits)	16
Data (Hex)	0003
Mask (Hex)	000F
Status Code (Hex)	

Figure 45 AutoSDO MR

MR is a SDO operation which monitors the value of a specific object dictionary index. MR shows success only if the following equation for a monitoring operation satisfies :

$$\text{Data} == \text{AND}(\text{SDO Upload Data}, \text{Mask})$$

#### RPDO setting

As shown in the Figure 46, only one RXPDO is required for configuration in the example.

TXPDO(0)		RXPDO(1)		Misc.		AutoSDO		SDO Task		NMT Task	
No.	COB-ID	Size	Info		Note						
1	201h	1	R3200 1.1								

Inhibit Time: 10 mS      Event Time: 1000 mS      Cyclic Time: 2000 mS

**RXPDO #1 Setting**

COB ID Assign

Slave Node ID: 1

PDO No.: 1

CobId(Hex): 201h

Size: (register) 1      Transmission Type: Async

Note: (Maximum 30 Bytes)

OK      Cancel

Figure 46 RXPDO configuration

Three additional settings are related to the transmission type and are located at the bottom of RXPDOs list page. “Cyclic Time” is only valid when “Cyclic” transmission type is used. “Inhibit Time” and “Event Time” are two transmission parameters for “Async” type. In this application, there is no requirement specified for these two parameters. “Event Time” may use the default settings 1000ms, while “Inhibit Time” is fixed to 10ms and it cannot be changed. The “Event Time” 1000ms which means the consecutive RXPDO messages shall be transmitted within 1000ms even if no event occurs. The setting 10ms for “Inhibit Time” means the consecutive RXPDO messages will



not be transmitted within 10 ms even if events are triggered during that period.

Inhibit Time:  mS      Event Time:  mS      Cyclic Time:  mS

Figure 47 Transmission parameter setting

### Misc. Setting

On Misc. setting page, there are three main functions “HeartBeat”, “Parameter Zone”, and “Sync. Master”. The “Parameter Zone” configuration is not related to the CANopen network communication and can be disabled (set to 0 to disable) for this application. “Sync Master” can be disabled for it is not used in the example. The “Guard Time” should use a higher value than the cycle time defined in the slave devices. In this example, “Guard Time” is set to the value 1050 ms for monitoring the heartbeat messages on the network.

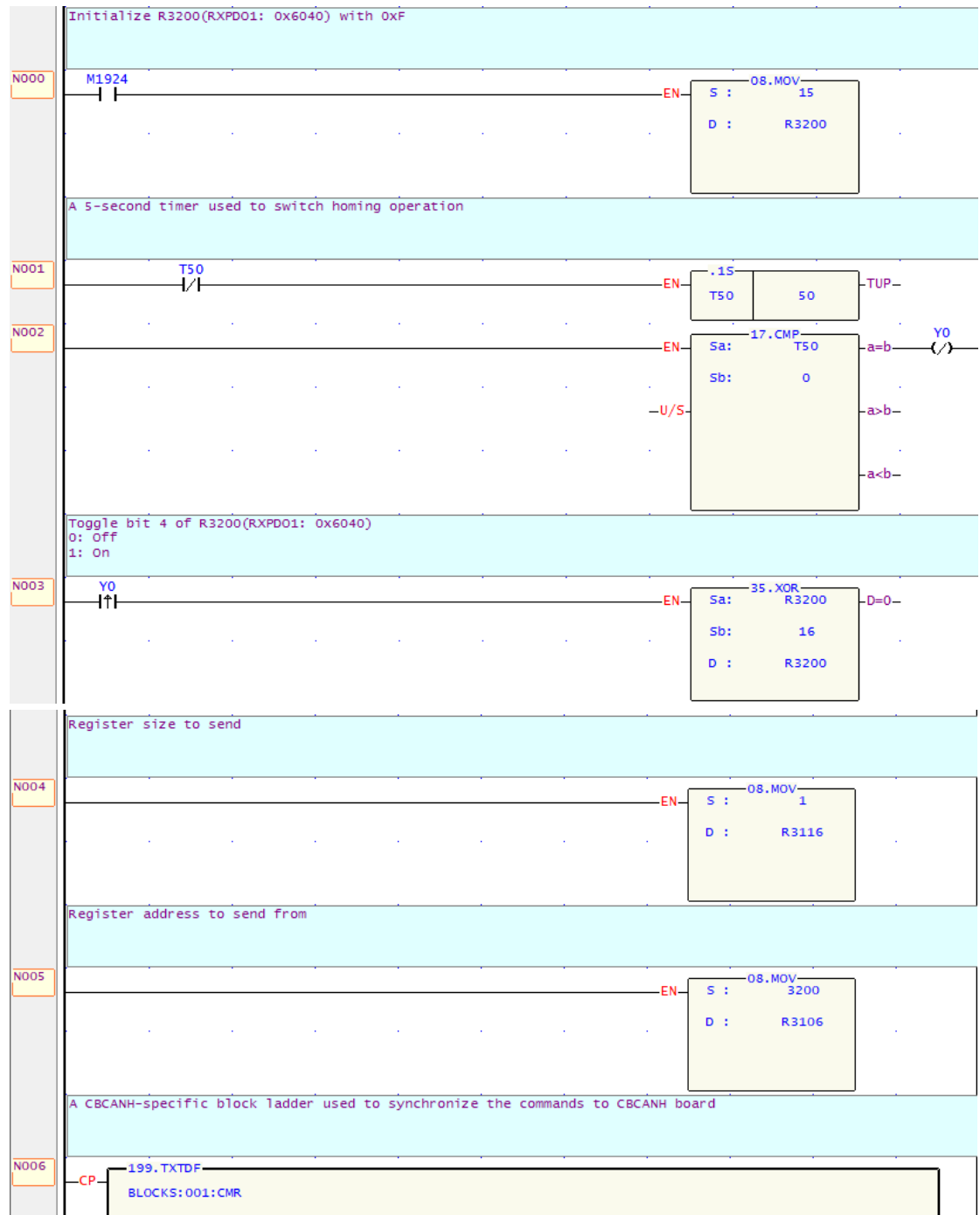
### Write Configuration to CBCANH

After above settings are done, the configuration then can be downloaded to CBCANH. Click “Write” button to start the procedure.

### PDO <-> PLC register mapping

After downloading the new configuration to the CBCANH, the CBCANH should be able to communicate with the slaves. The CBCANH supports maximum 60 RXPDOs and 60 TXPDOs, or 15 drive devices. Each PDO supports maximum 8 bytes of data, and mapped to the MBs PLC internal registers. The CBCANH maps the received data of TXPDOs to the internal registers R3440~R3679, and the internal registers R3200~R3439 are mapped to the RXPDOs by using the block ladder CMR. In the example, RXPDO1 is read from R3200.

### Example program



**Appendix B****The object dictionary of CBCANH****. Communication Object**

Index	SubIndex	Name	Data Type	Access	Default
1000H	0	Equipment Type	I32U	R	0
1001H	0	Error Register	I8U	R	0
1005H	0	COB-ID of SYNC	I32U	R	80H
100CH	0	Guard Time	I16U	R	0
100DH	0	Life Time Factor	I8U	R	0
1016H	Consumer Heartbeat Time				
	0	Item Count	I8U	R	1
	1	Consumer Heartbeat Time	I32U	R	1020
1017H	0	Producer Heartbeat Time	I32U	R	1000
1018H	Identity Object				
	0	Item Count	I8U	R	4
	1	Vendor code	I32U	R	2EFH
	2	Product Code	I32U	R	0
	3	Revision No.	I32U	R	0
	4	Serial No.	I32U	R	0
1400H	RXPDO1 Communication Parameters				
	0	Item Count	I8U	R	2
	1	RXPDO1 COB-ID	I32U	R	CFG
	2	Transmission type	I8U	R	0xff
1401H~ 143BH	RXPDO2~RXPDO60 Communication Parameters				
1600H	RXPDO1 Mapped Objects				
	0	Item Count	I8U	R	4
	1	RXPDO1 Mapped Object #1	I32U	R	CFG
	2	RXPDO1 Mapped Object #2	I32U	R	CFG
	3	RXPDO1 Mapped Object #3	I32U	R	CFG
	4	RXPDO1 Mapped Object #4	I32U	R	CFG
1601H~ 163BH	RXPDO2 ~ RXPDO60 Mapped Objects				

## Communication Object (Cont.)

Index	SubIndex	Name	Data type	Access	Default
1800H	TXPDO1 Communication Parameters				
	0	Item Count	I8U	R	5
	1	TXPDO1 COB-ID	I32U	R	CFG
	2	TXPDO1 Transmission Type	I32U	R	0xff
	3	TXPDO1 Inhibit Time	I32U	R	CFG
	4	Reserved	-	-	-
	5	Event Time	I16U	R	CFG
1801H ~ 183BH	TXPDO2 ~ TXPDO60 Communication Parameters				
1A00H	TXPDO1 Mapped Objects				
	0	Item Count	I8U	R	4
	1	TXPDO1 Mapped Object #1	I32U	R	CFG
	2	TXPDO1 Mapped Object #2	I32U	R	CFG
	3	TXPDO1 Mapped Object #3	I32U	R	CFG
	4	TXPDO1 Mapped Object #4	I32U	R	CFG
1A01H ~ 1A3BH	TXPDO2 ~ TXPDO60 Mapped Objects				

## . PLC Parameter Zone Objects (Max. 1000 R register)

Index	SubIndex	Name	Data type	Access	Default
2000H	1	P Zone+0	WORD	RW	
2000H	2	P Zone+1	WORD	RW	
2000H	n	P Zone+n-1	.		
2000H	100	P Zone+99	WORD	RW	
2001H	1	P Zone+100	WORD	RW	
2001H	2	P Zone+101	WORD	RW	
~	~	~	WORD	RW	
2009H	100	P Zone+999	WORD	RW	

## . PLC Process Data Objects

Index	SubIndex	Name	Data type	Access	Map
TXPDO process data					
2010H	1	R3200	I16U	R	Yes
	2	R3201		R	
	3	R3202		R	
	4	R3203		R	

2011H ~ 204BH	R3204~R3439				
RXPDO process data					
204CH	1	R3440	116U	R	Yes
	2	R3441		R	
	3	R3442		R	
	4	R3443		R	
204DH ~ 2087H	R3444~R3679				

## .Program Version Objects

Index	SubIndex	Name	Data type	Access	Default
4000H	0	Item Count	I8U	R	2
	1	CBCANH Firmware version	I32U	R	
	2	Ladder software version	I32U	R	

Ladder software version 由 PLC 的 R3697 決定

## . Electron board Version Objects

Index	SubIndex	Name	Data type	Access	Default
4001H	0	Item Count	I8U	R	1
	1	Electron board version	I32U	R	

**SDO ERROR CODE**

Error Code Name	Error Value	Description
ABORT_TIME_OUT	0x05040000L	SDO service Time out
ABORT_NO_OBJ	0x06020000L	No such object
ABORT_RO	0x06010002L	Attempt to write a read-only object
ABORT_SYS_LENGTH	0x06040047L	Data length exceed system allow
ABORT_NO_SEGEMNT	0x06010000L	Not support segment transfer
ABORT_OBJ_LENGTH	0x06070010L	Not match object length
ABORT_SYNC	0x05040001L	Command specifier not valid
ABORT_TOGGLE_BIT	0x05030000L	Toggle bit not alternated
ABORT_PARM_LENGTH	0x06070012L	Length of service parameter too high
ABORT_WO	0x06010001L	Attempt to read a write-only object
ABORT_READ_LENGTH	0x05040005L	Object length too big to read