

MiSUMi

Motorized Drum Driver Controller

with Magnetic Encoder (N4 Type, 1:4, EtherCAT Communication)

Quick Start Guide

Ver1.0

Revision History

Version	Time	Description
V1.0	2025/06/06	First Edition

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1. Technical Terms

1. Brushless DC Motor: A brushless DC motor consists of a permanent magnet rotor and a stator with windings. This type of motor offers advantages such as simple structure, high reliability, good stability, high efficiency, and strong adaptability, leading to its widespread application.
2. Magnetic Encoder Sensor: A device installed inside the motor to provide rotor position feedback.
3. PNP: Active high, general power supply range: 15~30V
4. NPN: Active low, general power supply range: 0~0.8V
5. Braking Resistor: A component used to dissipate regenerative energy during motor braking, converting the back electromotive force (regenerative energy) generated when the motor stops into heat energy to prevent potential damage.
6. LED: Light Emitting Diode, used to indicate the status of the drive system.
7. EtherCAT: Ethernet for Control Automation Technology, based on the standard Ethernet physical layer and TCP/IP protocol framework, breaks through the real-time bottleneck of traditional Ethernet through innovative "processing methods," becoming one of the mainstream technologies in the field of industrial automation.
8. ZPA: Zero-pressure accumulation.
9. Zone: A basic conveying zone consisting of one photoelectric sensor and at least one motorized roller.

2. Basic Features

- Supports plug-and-play replacement without addressing or additional configuration
- All functions and I/O terminals have LED status indicators
- Integrated logic for zero-pressure accumulation conveyor applications (including initialization)
- Configurable via PLC and PC tools (based on the current motorized roller platform)
- Built-in 100 Mbps Ethernet switch

- Voltage limiting via the braking chopper
- Functional grounding connection for the communication cable shield
- Reverse polarity protection for input and output voltage supply
- Closed-loop speed control
- Dual LED status display
- Fault output function
- Built-in braking resistor
- Switchable PNP/NPN I/O input control
- Fast switching between 24 V and 48 V

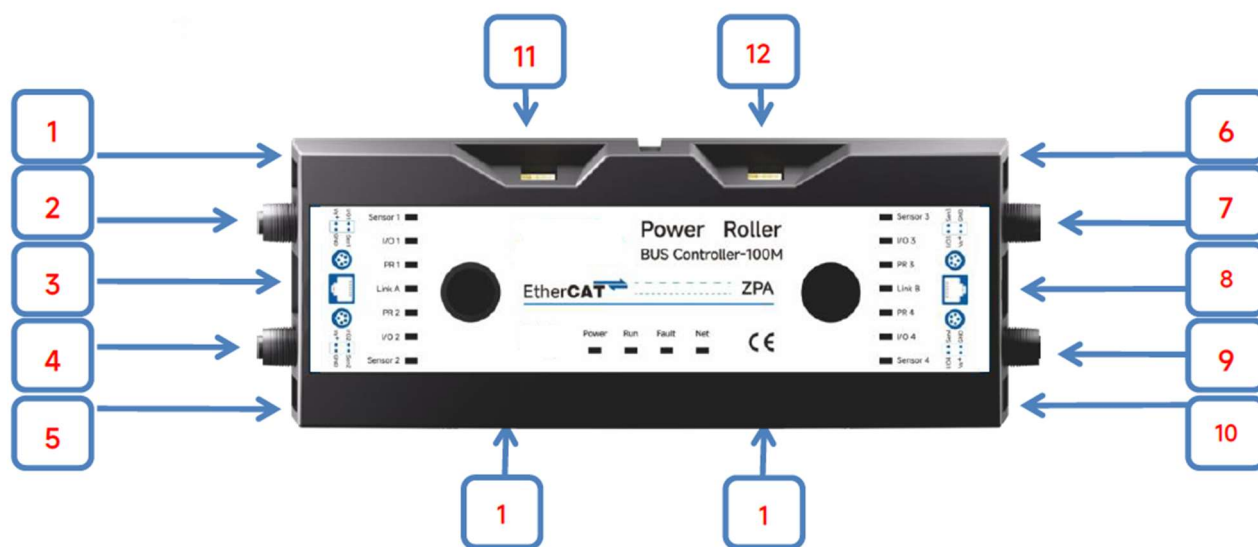
3. Compatible Motorized Roller Specifications

Rated voltage of the drum	Voltage Range (V)	Rated Power (W)	Rated Current (A)	Starting Current (A)
DC 24V	20~26	35	2.5±0.5	6.25±0.5
		50	3.2±0.5	8±0.5
		80	4.5±0.5	11.25±0.5
DC 48V	40~52	35	1.3±0.5	3.25±0.5
		50	1.6±0.5	4±0.5
		80	2.3±0.5	5.75±0.5

4. Power Supply Requirements

drum power	Switching power supply power	Suggested wire diameter	Suggested wire length
35W	≥80W	0.75mm ² (4A)	≤12 meters
50W	≥120W	0.75mm ² (4A)	≤9 meters
80W	≥200W	1mm ² (6A)	≤9 meters
*Note: When using multiple rollers in practice, it is recommended to use a high-power power supply and avoid single power supply, for example: Using a 35W electric drum, a 450W power supply can connect 9 to 11 electric drums for use (with step-by-step start of the drums), which can be calculated as 1.2 to 1.5 times the power rating of the electric drums.			

5. Controller Board Layout

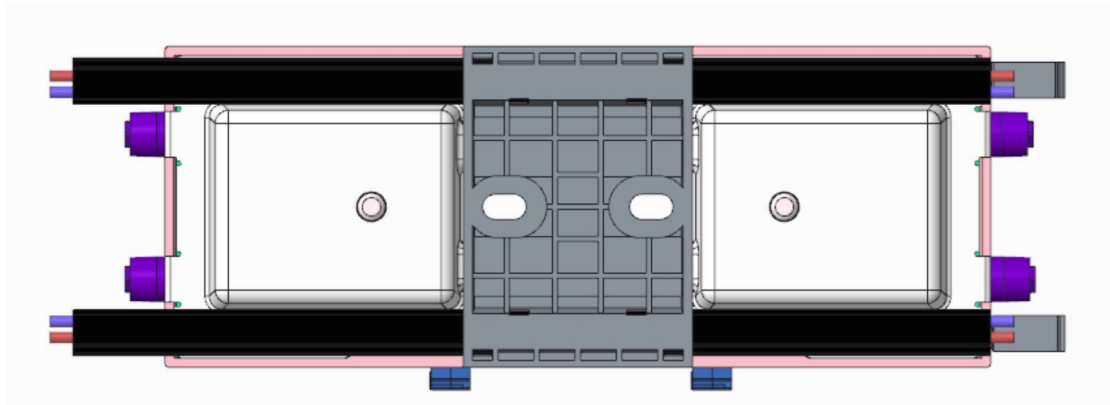


Sequence Position	Function	Description
1	Sensor1	Sensor 1 and IO1 interface
2	Roller 1 terminal	5-pin drum terminal
3	RJ45-A	Slave Interface - LINK A (IN Port)
4	Roller 2 terminal	5-pin drum terminal
5	Sensor2	Sensor 2 and IO2 interface
6	Sensor3	Sensor 3 and IO3 interface
7	Roller 3 terminals	5-pin drum terminal
8	RJ45-B	Slave Interface - LINK B (OUT Port)
9	Roller 4 terminals	5-pin drum terminal
10	Sensor4	Sensor 4 and IO4 interface
11	Logic circuit 1	Logic circuit power supply: The control logic power can use cables with a wire diameter of 1.5mm ² , and the logic power is 24V.
12	Logic Circuit 2	Logic circuit power supply: The control logic power can use cables with a wire diameter of 1.5mm ² , and the logic power is 24V.
13	Power circuit 1	The motor circuit is powered on. For the power supply, it is recommended to use cables with a wire diameter of 2.5mm ² . The power supply voltage should be 48V or 24V.
14	Power circuit 2	The motor circuit is powered on. For the power supply, it is recommended to use cables with a wire diameter of 2.5mm ² . The power supply voltage should be 48V or 24V.

5.1 Power Interface

The bus card has two power interfaces. The upper interface on the controller is the control logic power input, which supplies the control logic section, while the lower interface is the drive power input used to power the motor. Both interfaces use ASI flat cables connected through insulation-piercing connectors and secured with cable covers.

For the power supply, it is recommended to use cables with a wire diameter of 2.5mm^2 , while for the control logic power supply, cables with a wire diameter of 1.5mm^2 can be used.



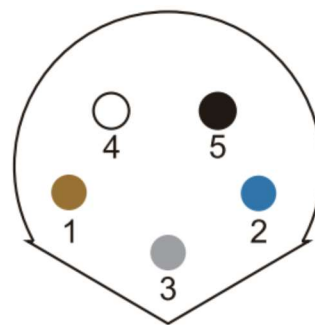
For both power supplies, the positive terminal (brown) faces downward and the negative terminal (blue) faces upward. Do not interchange the drive power supply and the logic power supply. Also ensure the voltage is correct to avoid misconnection (foolproof mechanical design).

 The power supply for the bus control card's drive and logic circuits is 24V. Since the controller can drive four motor channels simultaneously, significant power fluctuations may occur during operation. Please use independent power supplies to connect the drive and logic power circuits separately.

5.2 Motor Interface

There are four motor interfaces, which can simultaneously drive four electric rollers. The motor interfaces are dedicated to Misumi electric rollers.

线脚	颜色	功能
1	棕色	电源输入正极
2	蓝色	电源输入负极
3	灰色	调速信号输入
4	白色	转向信号输入
5	黑色	错误反馈输出



5.3 Sensor Interface

The bus card has four sensor interfaces, each with four pins for connecting to the positive power supply, negative power supply, sensor signal, and auxiliary digital input/output signal.

The sensor interface uses KF2EDGKS-3.5-2-2P. The table below defines the sensor interface:

pin	signal	Description
1	24V+	The controller outputs a positive 24V power supply externally.
2	GND	Negative terminal of 24V power supply
3	SENSOR	Sensor signal input
4	I/O	Auxiliary Digital Input/Output

 Pins 1 and 2 serve as the positive and negative power terminals, respectively. Short-circuiting or reversing their polarity may damage the sensor interface and peripherals; please exercise caution during use.

 When using the ZPA function, the sensor signal must be connected to pin 3. If connected to pin 4, the program will fail to correctly identify the presence of goods and control the conveyor operation.

5.4 Ethernet Port

An RJ45 Ethernet port is provided on each side of the controller for communication with the PLC and other controllers.

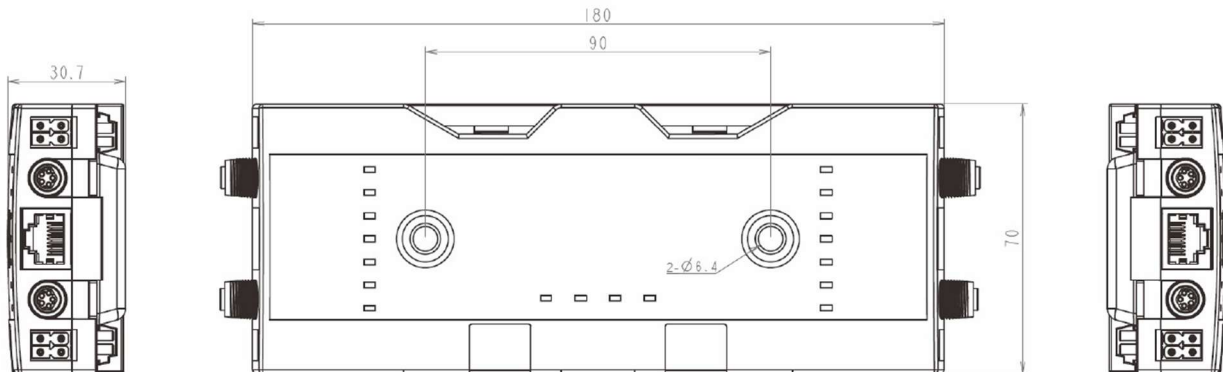
 In environments with electromagnetic noise, it is recommended to use shielded Ethernet cables to prevent data loss or other unexpected results during communication.

5.5 Indicator Lights

LED Name	Color	Status	"Meaning"
Power	green	On/Off	Solid: Voltage normal; Off: Voltage abnormal
Run	green	On/Off	Constant: The control card is ready and can drive normally. Extinguished: The control card needs to be configured
Fault	Red	On/Off/Blink	Constant on: Control card fault Extinguished: Control card is normal Blinking: Blinks 6 times and then turns off during emergency brake stop.
Net Run	green	On/Off	Solid: Networking mode; Off: Standalone mode
Sensor 1	green	On/Off	Solid: Signal input present; Off: No signal input
I/O 1	green	On/Off	Solid: Signal input present; Off: No signal input
RD 1	yellow	On/Off	Solid: Drum connected; Off: Abnormal or no connection
Sensor 2	green	On/Off	Solid: Signal input present; Off: No signal input
I/O 2	green	On/Off	Solid: Signal input present; Off: No signal input
RD 2	yellow	On/Off	Solid: Drum connected; Off: Abnormal or no connection
Sensor 3	green	On/Off	Solid: Signal input present; Off: No signal input
I/O 3	green	On/Off	Solid: Signal input present; Off: No signal input
RD 3	Yellow	On/Off	Solid: Drum connected; Off: Abnormal or no connection
Sensor 4	green	On/Off	Solid: Signal input present; Off: No signal input
I/O 4	green	On/Off	Solid: Signal input present; Off: No signal input
RD 4	Yellow	On/Off	Solid: Drum connected; Off: Abnormal or no connection
Link/ActA	green	On/Off	Solid: Normal communication connection; Off: Abnormal or no connection
Link/ActB	green	On/Off	Solid: Normal communication connection; Off: Abnormal or no connection

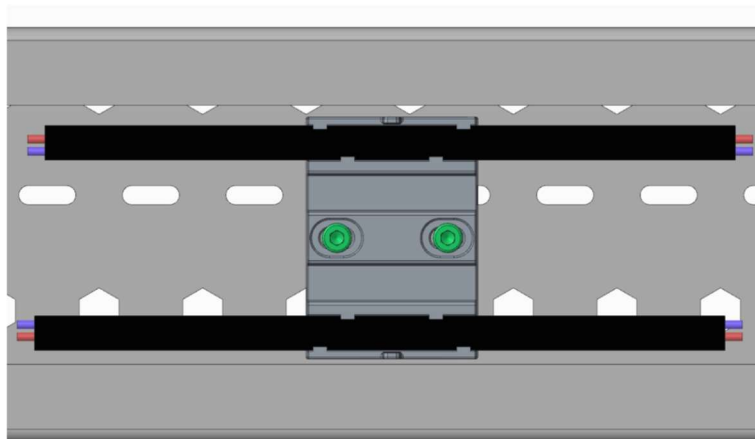
6. Dimensional Installation

6.1 Installation Dimensions

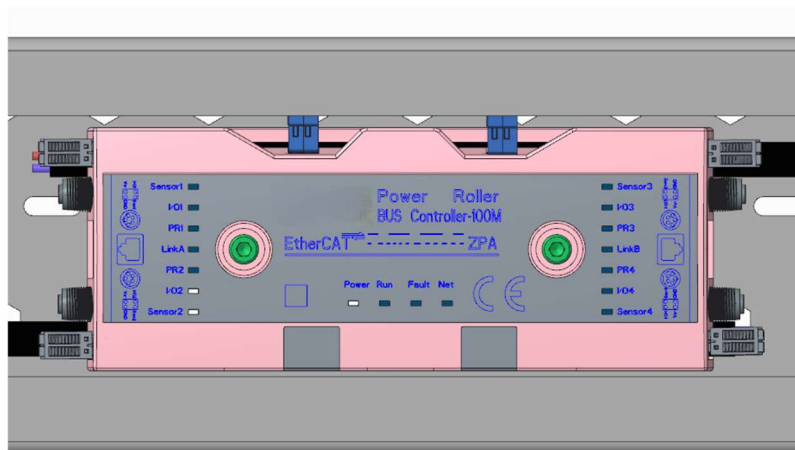


6.2 Installation Steps

Step 1: Install the flat cable onto the plastic bracket, and secure the plastic bracket to the profile frame using two M5 bolts.



Step 2: Fix the control card to the plastic bracket, and fix the control card to the profile frame through the two M6 bolts in the middle.



7. Application Environment

Category	DC 48V motor configuration	DC 24V motor configuration
Rated voltage of power supply	48V DC	24V DC
Power supply voltage range	42 to 52V DC	20 to 26V DC
Rated voltage of logical power supply	24V DC	
Logic power supply voltage range	18 to 26V DC	
Logic control current	The controller's maximum current is 0.2A, plus the connected sensors/actuators totaling 1.6A.	
Motor temperature protection	105°C	
Controller temperature protection	85°C	
Current protection	fuse	
Protection Level	IP20	
Operating environment temperature	0 to 40°C	
Storage ambient temperature	-40 to 85°C	
Operating environment humidity	5% to 95% RH (non-condensing)	
working environment air	Non-corrosive gas	
Working vibration intensity	0.5G	
Installation Location	indoor	

 Ensure the controller is assembled correctly to avoid damage or malfunction.

 The controller should be installed on a flat bracket to ensure that it does not twist or deform due to external forces during and after installation.

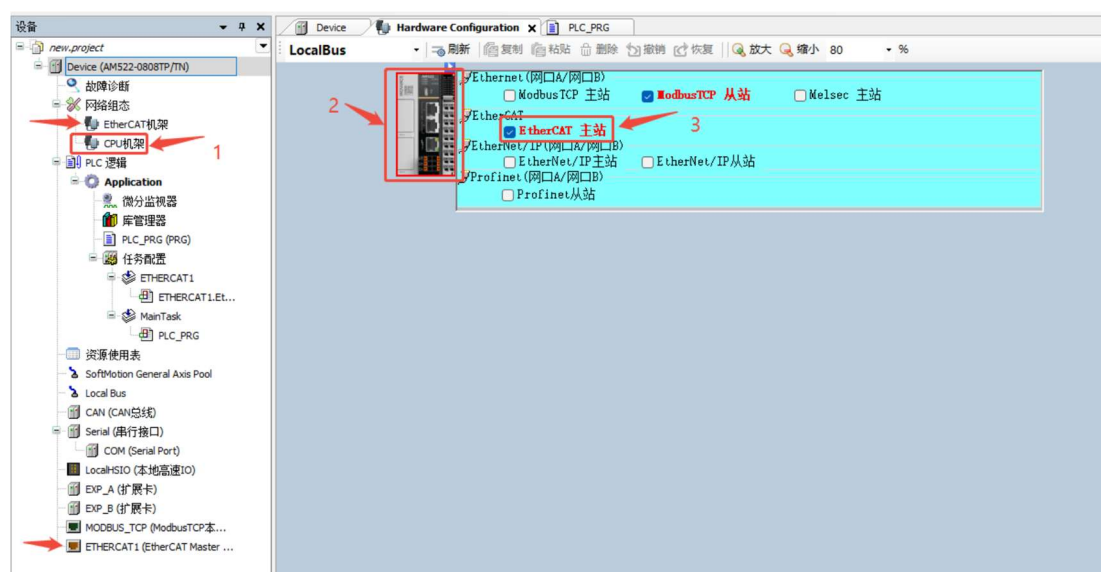
 The nuts of the fixing screws should not be left too high, as this may affect the connection of the network cables.

 The controller must not be installed in an environment completely sealed by metal, as this will block wireless signals and cause Bluetooth functionality to malfunction. After installing the controller, avoid drilling holes in metal brackets near the controller to prevent metal shavings from falling into the controller, which could cause a short circuit and damage the device.

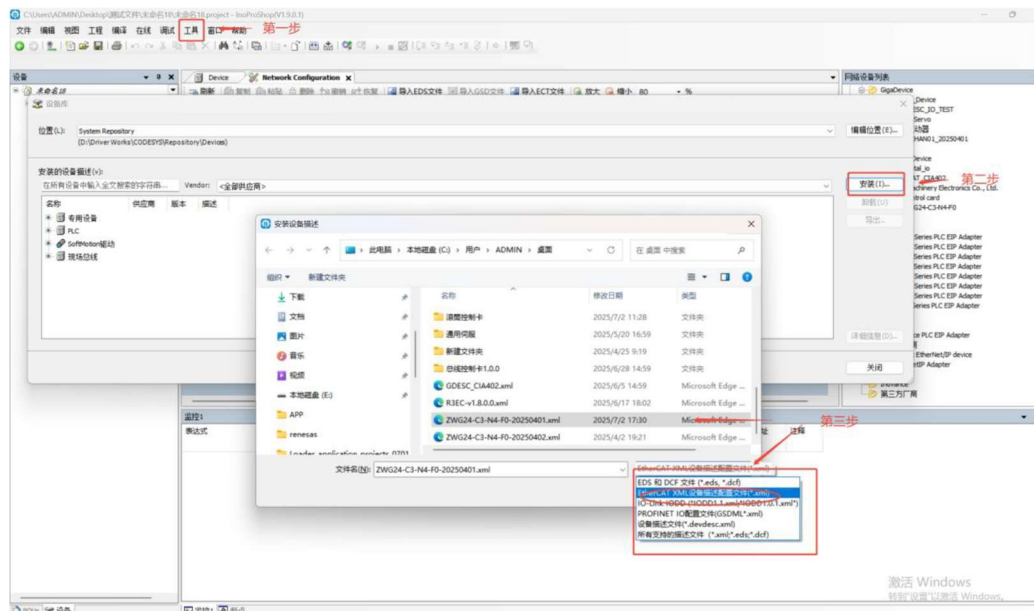
8. Operating Example

8.1 Import Device Description XML File

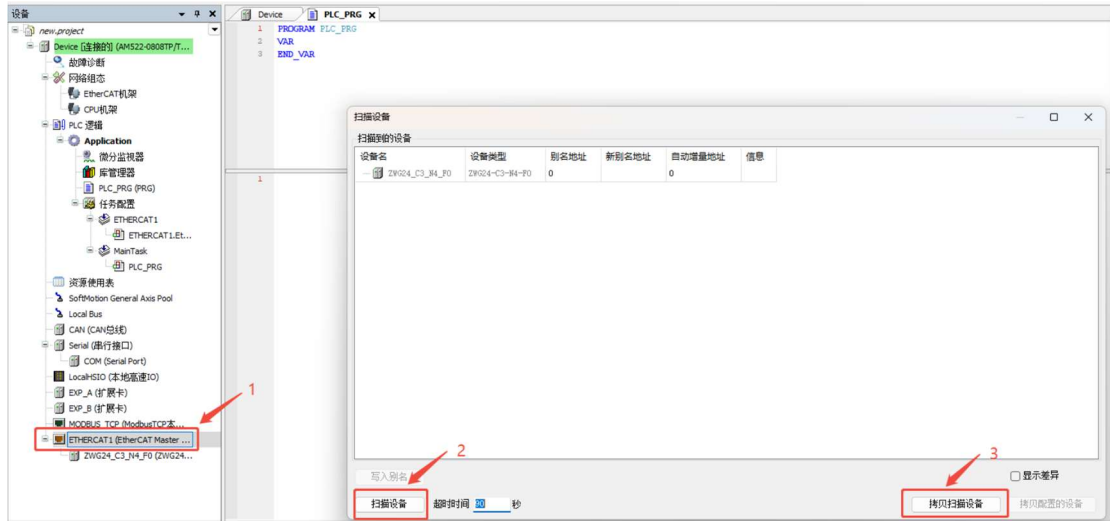
The following example uses Inovance inoProShop software and an AM522 PLC:
First, locate the CPU rack on the left, double-click the PLC, and check the EtherCAT master station. The EtherCAT rack and ETHERCAT1 will then appear.



On the software's top navigation bar, select Tools -> Device Library. In the Device Library window, click Install to open the local file browser. In the file type dropdown list, select the EtherCAT XML device description file option, then locate and open the file "EA-MRD24-C3-N4-F0-20250401.XML", as shown below.

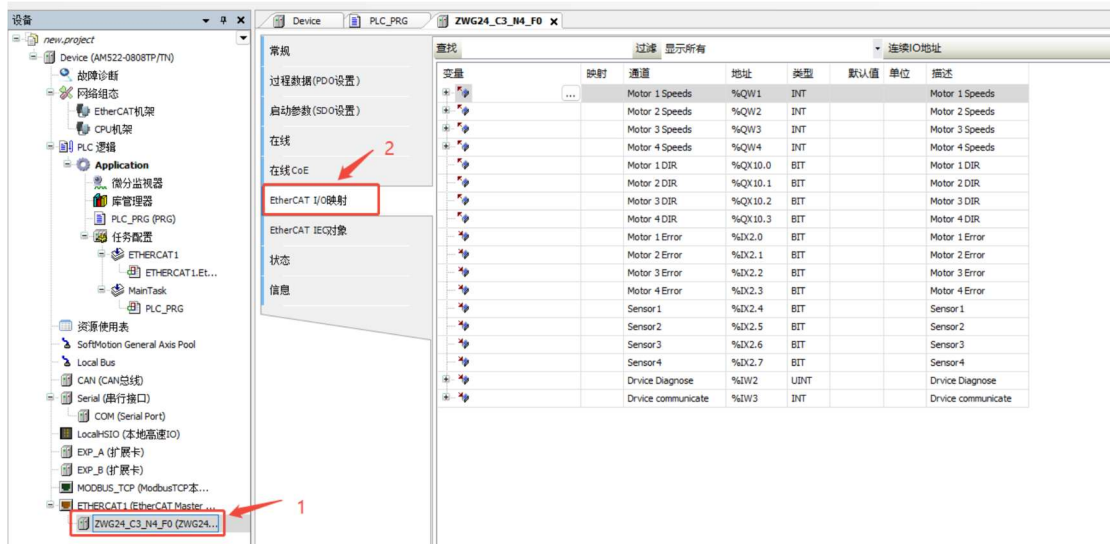


After importing the device description XML file, right-click ETHERCAT1 to select Scan Devices. In the pop-up window, click Scan Devices. Once scanned, click Copy Scanned Device. (If devices cannot be scanned, check whether the IN and OUT ports are distinguished.)

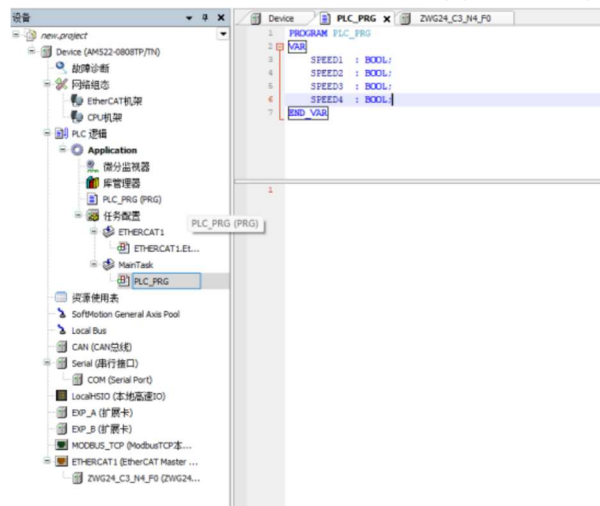


8.2 Parameter Configuration

Double-click the roller bus card (EA-MRD24-C3-N4-F0) to open the EtherCAT I/O mapping. Multiple variable channels used to control roller operation are displayed here. To use them in the program, create the corresponding variables and map them accordingly, as shown below.



First, create the relevant variables in the program and then associate them. Double-click the empty cell in the EtherCAT I/O mapping that you want to associate with, click the ellipsis button behind it, and select the corresponding variable to associate. By obtaining the value of the variable, the input/output values of the bus card are read and written, thereby connecting the status of each channel of the bus card with the actual application program. As shown in the figure.



常规

过程数据(PDO设置)

启动参数(SDO设置)

在线

在线CoE

EtherCAT I/O映射

EtherCAT IEC对象

状态

信息

查找

过滤 显示所有

连续IO地址

变量	通道	地址	类型	默认值	单位	描述
Motor 1 Speeds	%QW1	INT			Motor 1 Speeds	
Motor 2 Speeds	%QW2	INT			Motor 2 Speeds	
Motor 3 Speeds	%QW3	INT			Motor 3 Speeds	
Motor 4 Speeds	%QW4	INT			Motor 4 Speeds	
Motor 1 DIR	%QX10.0	BIT			Motor 1 DIR	
Motor 2 DIR	%QX10.1	BIT			Motor 2 DIR	
Motor 3 DIR	%QX10.2	BIT			Motor 3 DIR	
Motor 4 DIR	%QX10.3	BIT			Motor 4 DIR	
Motor 1 Error	%IX2.0	BIT			Motor 1 Error	
Motor 2 Error	%IX2.1	BIT			Motor 2 Error	
Motor 3 Error	%IX2.2	BIT			Motor 3 Error	
Motor 4 Error	%IX2.3	BIT			Motor 4 Error	
Sensor1	%IX2.4	BIT			Sensor1	
Sensor2	%IX2.5	BIT			Sensor2	
Sensor3	%IX2.6	BIT			Sensor3	
Sensor4	%IX2.7	BIT			Sensor4	
Drive Diagnose	%IW2	UINT			Drive Diagnose	
Drive communicate	%IW3	INT			Drive communicate	

双击就会出现

输入助手

文本搜索 类别

变量

找到对应位置的变量

名称	类型	地址
Application	应用	
PLC_PRG	PROGRAM	
SPEED1	BOOL	
SPEED2	BOOL	
SPEED3	BOOL	
SPEED4	BOOL	
IoConfig_Globals	VAR_GLOBAL	
SM3_Basic	库	SM3_Basic, 4.10.9.0 (3S - S
SM3_Math	库	SM3_Math, 4.10.0.0 (3S - S
SM3_CNC	库	SM3_CNC, 4.2.1.1 (3S - S
IoDrvEthercatLib	库	IoDrvEtherCAT, 3.5.11.50 (3S

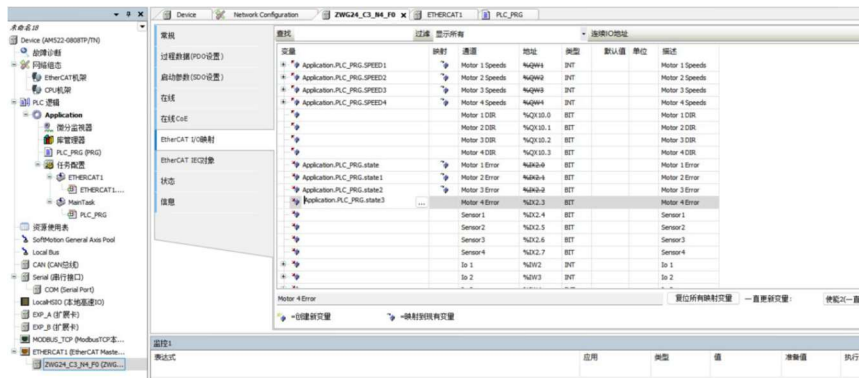
☒ 结构化显示(S) 过滤器(F) 无

☒ 插入时格式化参数(w) ☐ 插入时添加命名空间(n)

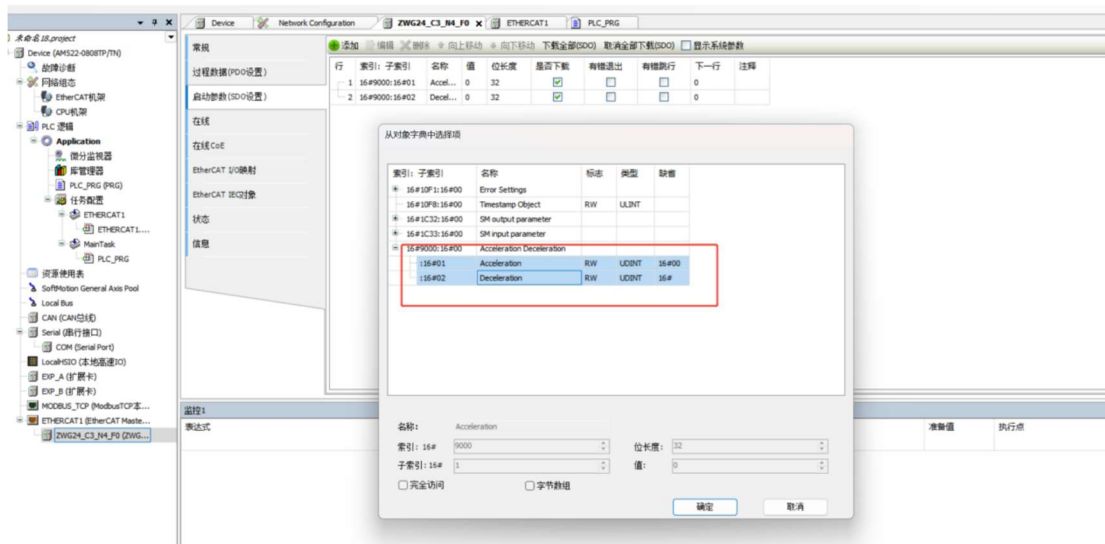
文档(D)

```
PROGRAM PLC_PRG
```

确定 取消



SDO Configuration: Double-click the roller bus card to select "Startup Parameter SDO". The startup parameters of the roller bus card include acceleration ACC and deceleration DEC. Select "Add" at the top, locate index 16#9000 in the object dictionary, and add its sub-indices 16#01 and 16#02. After configuration, download the program to the PLC for debugging.



8.3 Object Dictionary Access Methods

Understanding the Object Dictionary: The function blocks for reading the EtherCAT slave object dictionary are ETC_CO_SdoRead, ETC_CO_SdoRead4, ETC_CO_SdoReadDWord, and ETC_CO_SdoRead_Access.

There are also four function blocks for writing to the object dictionary, including ETC_CO_SdoWrite, ETC_CO_SdoWrite4, ETC_CO_SdoWriteDWord, and ETC_CO_SdoWrite_Access.

The differences in reading the object dictionary are as follows, and writing to the object dictionary is similar.

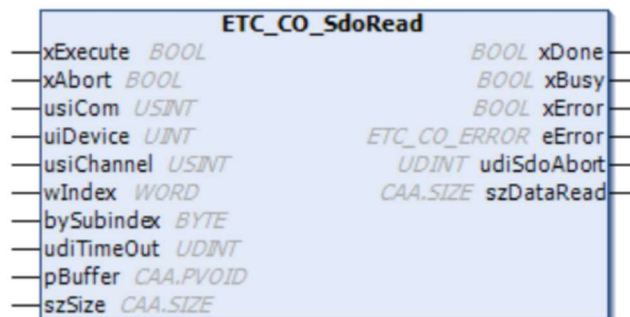
ETC_CO_SdoRead can read the value of an object dictionary by byte count and supports reading object dictionaries larger than 4 bytes;

ETC_CO_SdoRead4 can only read object dictionary entries of 4 bytes or less;
The object dictionary value read by ETC_CO_SdoReadDWord is converted to the
DWORD data type;
ETC_CO_SdoRead_Access can read the values of all sub-indexes of an object
dictionary index at once.

8.4 Introduction to Reading and Writing the Object Dictionary

This document mainly introduces the following two function blocks, which can meet the usage requirements.

① ETC_CO_SdoRead:



Key Parameter Description

"Input"	xExecute	Execute on rising edge
	xAbsort	If this parameter is set to 'TRUE', the current read process will be terminated.
	usiCom	Number of EtherCAT masters: If only one EtherCAT master is used, usiCom is '1'. When using multiple masters, the first master is '1', the second is '2', and so on.
	uiDevice	The physical address of the slave station.
	usiChannel	Reserved for future expansion, currently unused.
	wIndex	The parameter index in the object dictionary.
	bySubIndex	Sub-indexes of parameters in the object dictionary.
	udiTimeout	Timeout (in milliseconds). If the parameter is not read within this time, an error message will be displayed.
	pBuffer	Pointer to the data buffer, which is the storage area for data after the parameter is successfully passed.
	szSize	The size of the data buffer (see above: pBuffer), in bytes.
"Output"	xDone	Parameter read success flag
	xBusy	Parameter reading flag
	xError	Read error flag
	udiSdoAbort	When the device check fails
	szDataRead	The number of bytes to read; the maximum szSize (see input parameters).

② ETC_CO_SdoWriteD: Keyword description is similar to reading

ETC_CO_SdoWriteDWord		
xExecute	BOOL	BOOL xDone
xAbort	BOOL	BOOL xBusy
usiCom	USINT	BOOL xError
uiDevice	UINT	ETC_CO_ERROR eError
usiChannel	USINT	UDINT udiSdoAbort
wIndex	WORD	
bySubindex	BYTE	
udiTimeOut	UDINT	
dwData	DWORD	
usiDataLength	USINT	

8.5 Reading and Writing the Object Dictionary

① Define storage area

```

1 PROGRAM PLC_PRG
2   VAR
3
4     Sdo_ACC          : ARRAY[1..4] OF BYTE;
5     Sdo_DEC          : ARRAY[1..4] OF BYTE;
6     ETC_CO_SdoRead4_0 : ETC_CO_SdoRead4;
7     ETC_CO_SdoRead_0  : ETC_CO_SdoRead;
8     ETC_CO_SdoWriteD  : ETC_CO_SdoWriteDWord;
9     SW0: BOOL;
10    SW1: BOOL;
11  ;
12 END_VAR

```

定义储存区域

② Write function block program

This example demonstrates how to read the acceleration and deceleration values from the SDO of a bus card. Double-click the drum bus card, and locate the slave address under "General":



常规 地址 额外的

过程数据(PDO设置)

启动参数(SDO设置)

在线

在线 CoE

EtherCAT I/O映射

EtherCAT IEC对象

状态

信息

自动增量地址 0

从站地址 1001

使能专家设置

选项

可在主站“总览”界面设置使能

分布式时钟

从站别名 (可以通过主站“总览”界面设置别名)

禁止

配置站点别名 (ADO 0x0012) 1001

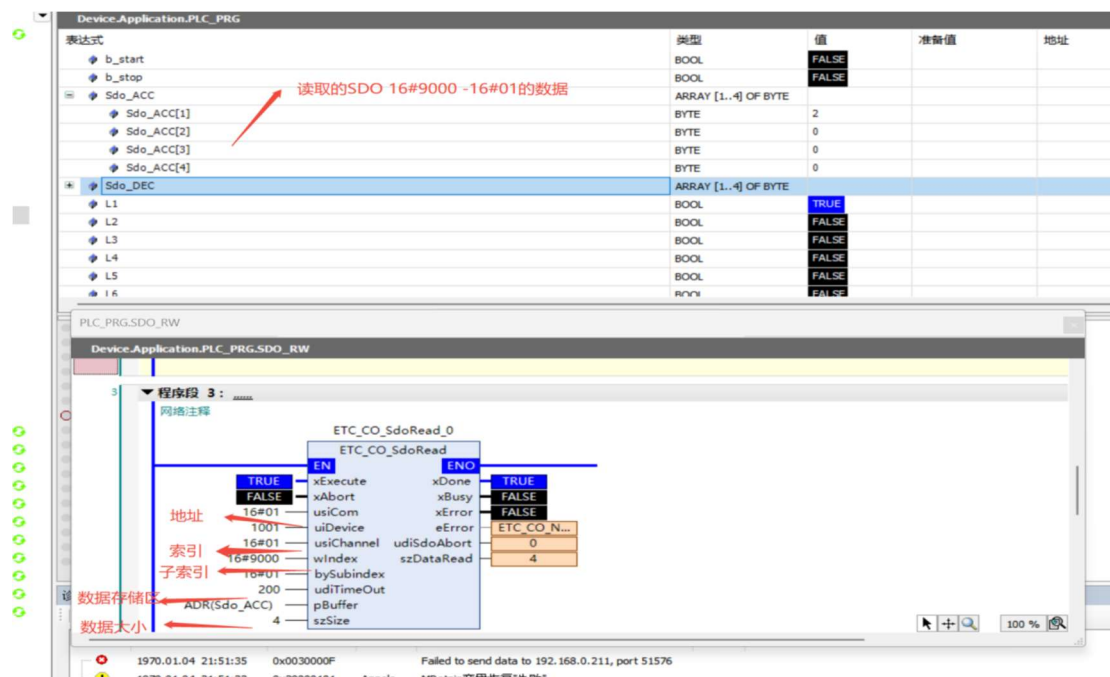
显示设备标识 (ADO 0x0134)

数据字 (2 字节) ADO (hex) 0

Set the Acceleration of subindex 16#01 to 2 as follows during initialization:

行	索引: 子索引	名称	值	位长度	是否下载	有错误退出	有错误跳行	下一行	注释
1	16#9000:16#01	Acceleration	2	32	☒	☐	☐	0	
2	16#9000:16#02	Deceleration	2	32	☒	☐	☐	0	

Subsequently, the data is read via function blocks.



The screenshot shows the GX Developer interface. The top window displays variable declarations for the PLC_PRG project. The bottom window shows a function block call for ETC_CO_SdoRead_0.

Variable Declaration (Device.Application.PLC_PRG):

表达式	类型	值	注释
b_start	BOOL	FALSE	
b_stop	BOOL	FALSE	
Sdo_ACC	ARRAY [1..4] OF BYTE		
Sdo_ACC[1]	BYTE	2	
Sdo_ACC[2]	BYTE	0	
Sdo_ACC[3]	BYTE	0	
Sdo_ACC[4]	BYTE	0	
Sdo_DEC	ARRAY [1..4] OF BYTE		
L1	BOOL	TRUE	
L2	BOOL	FALSE	
L3	BOOL	FALSE	
L4	BOOL	FALSE	
L5	BOOL	FALSE	
L6	BOOL	FALSE	

Function Block Call (Device.Application.PLC_PRG.SDO_RW):

程序段 3: ETC_CO_SdoRead_0

网络注释: 读取的SDO 16#9000-16#01的数据

地址: 16#01

索引: 16#01

子索引: 16#01

数据存储器: ADR(Sdo_ACC)

数据大小: 4

ETC_CO_SdoRead_0 参数:

- EN: TRUE
- xDone: TRUE
- xEAbort: FALSE
- xBusy: FALSE
- uiDevice: 16#01
- uiChannel: 16#01
- winIndex: 16#01
- bySubindex: 16#01
- udiTimeOut: 200
- pBuffer: ADR(Sdo_ACC)
- szSize: 4
- szDataRead: 4
- ETC_CO_N...: 0

Write SDO data: Online write SDO acceleration to 5, then read it out

程序段 4:

网络注释

ETC_CO_SdoWriteD

ETC_CO_SdoWriteDWord

EN

FALSE

xExecute

FALSE

xAbort

16#01

usiCom

1001

uiDevice

16#01

usiChannel

16#9000

wIndex

16#01

bySubindex

200

udiTimeOut

5

dwData

1

usiDataLength

ENO

FALSE

xDone

FALSE

xBusy

FALSE

xError

ETC_CO_N...

0

udiSdoAbort

地址

索引

子索引

写入SDO数据, 这里举例写入SDO 索引16#9000, 16#1中加速度5

数据大小

程序段 5:

Sdo_ACC

Sdo_ACC[1]

BYTE

5

Sdo_ACC[2]

BYTE

0

Sdo_ACC[3]

BYTE

0

Sdo_ACC[4]

BYTE

0

Sdo_DEC

ARRAY [1..4] OF BYTE

1

读到数据

PLC_PRG.SDO_RW

Device:Application.PLC_PRG.SDO_RW

Dec_Set

1

200

udiTimeOut

dwData

1

usiDataLength

程序段 3:

网络注释

ETC_CO_SdoRead_0

ETC_CO_SdoRead

EN

TRUE

xExecute

FALSE

xAbort

16#01

usiCom

1001

uiDevice

16#01

usiChannel

16#9000

wIndex

16#01

bySubindex

ENO

TRUE

xDone

FALSE

xBusy

FALSE

xError

ETC_CO_N...

0

udiSdoAbort

szDataRead

4

mSpeed3

0

:=Speed_3

0

mSpeed4

0

:=Speed_4

0

9. Object Dictionary

9.1 Service Data Object (SDO)

Index	Sub-index	Name	Data Type	Valid Data Range	Access Attributes	Description
9000H	01H	Acceleration	Unsigned16	0-255	R/w	8-speed acceleration: 1:100ms 2: 250ms 3: 500ms 4: 660ms 5: 1s 6: 1s250ms 7: 1s450ms 8: 2s Default: 500ms
9000H	02H	Deceleration	Unsigned16	0-255	R/w	8-speed acceleration: 1:100ms 2: 250ms 3: 500ms 4: 660ms 5: 1s 6: 1s250ms 7: 1s450ms 8: 2s Default: 500ms

9.2 Process Data Objects TXPDO

Index	Sub-index	Name	Data Type	Valid Data Range	Access Attribute	Description
1601H	01H	Motor1 Speed	Int	0-32767	R/w	Speed range (8500-32767)
	02H	Motor2 Speed	Int	0-32767	R/w	Speed range (8500-32767)
	03H	Motor3 Speed	Int	0-32767	R/w	Speed range (8500-32767)
	04H	Motor4 Speed	Int	0-32767	R/w	Speed range (8500-32767)
1602H	01H	Motor1 Dir	Bit	0-1	R/w	Direction setting value
	02H	Motor2 Dir	Bit	0-1	R/w	Direction setting value
	03H	Motor3 Dir	Bit	0-1	R/w	Direction setting value
	04H	Motor4 Dir	Bit	0-1	R/w	Direction setting value
1A00H	01H	Motor1 Error	Bit	0-1	Ro	Read motor error status
	02H	Motor2 Error	Bit	0-1	Ro	Read motor error status
	03H	Motor3 Error	Bit	0-1	Ro	Read motor error status
	04H	Motor4 Error	Bit	0-1	Ro	Read motor error status
1A01H	01H	Sensor1	Bit	0-1	Ro	Sensor Status Read
	02H	Sensor2	Bit	0-1	Ro	Sensor Status Read
	03H	Sensor3	Bit	0-1	Ro	Sensor Status Read
	04H	Sensor4	Bit	0-1	Ro	Sensor Status Read
1A01H	01H	IO 1	Int	0-32767	Ro	Analog input value reading
	02H	IO 2	Int	0-32767	Ro	Analog input value reading
	03H	IO 3	Int	0-32767	Ro	Analog input value reading
	04H	IO 4	Int	0-32767	Ro	Analog input value reading

1A03H	01H	Drvice Diagnose	Uint	0-32767	Ro	Control card status read: 1000: Motor control undervoltage 1010: Motor control overvoltage 1020: Control card undervoltage 1030: Overvoltage of control card
1A04H	01H	Drvice Communicate	int	0-32767	Ro	ETHERCAT status read: 00: ETHERCAT communication error or not connected 01: ETHERCAT Communication Preprocessing Status 10: ETHERCAT communication normal status

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