Smart encoders & actuators

User's guide

IF55 ROT EP
IF55 LIN EP

EtherNet/IP™

- SSI to EtherNet/IP converter
- Suitable for SSI rotary and linear encoders
- Accepts MSB & LSB Aligned protocols up to 30 bits
- M12 connectors
- Class 1 Real Time Ethernet (RTE) according to IEC 61 784-2

Suitable for the following models:

- IF55 ROT EP (for rotary encoders)
- IF55 LIN EP (for linear encoders)

General Contents

General contents

Subject index

Typographic and iconographic conventions

In this guide, to make it easier to understand and read the text the following typographic and iconographic conventions are used:

- parameters and objects both of the device and the interface are colored in **GREEN**;
- alarms are colored in **RED**;
- states are colored in **FUCSIA**.

When scrolling through the text some icons can be found on the side of the page: they are expressly designed to highlight the parts of the text which are of great interest and significance for the user. Sometimes they are used to warn against dangers or potential sources of danger arising from the use of the device. You are advised to follow strictly the instructions given in this guide in order to guarantee the safety of the user and ensure the performance of the device. In this guide the following symbols are used:

	This icon, followed by the word WARNING, is meant to highlight the parts of the text where information of great significance for the user can be found: user must pay the greatest attention to them! Instructions must be followed strictly in order to guarantee the safety of the user and a correct use of the device. Failure to heed a warning or comply with instructions could lead to personal injury and/or damage to the unit or other equipment.
	This icon, followed by the word NOTE, is meant to highlight the parts of the text where important notes needful for a correct and reliable use of the device can be found. User must pay attention to them! Failure to comply with instructions could cause the equipment to be set wrongly: hence a faulty and improper working of the device could be the consequence.
	This icon is meant to highlight the parts of the text where suggestions useful for making it easier to set the device and optimize performance and reliability can be found. Sometimes this symbol is followed by the word EXAMPLE when instructions for setting parameters are accompanied by examples to clarify the explanation.

Preliminary information

This guide is designed to provide the most complete and exhaustive information the operator needs to correctly and safely install and operate the **SSI to EtherNet/IP gateways of the IF55 series**.

IF55 series gateways allow the **integration of SSI encoders**, both rotary and linear, **into conventional fieldbuses or industrial Ethernet networks**.
The present manual is specifically designed to describe the SSI to EtherNet/IP IF55 model for both rotary and linear encoders (order code IF55 ROT EP and IF55 LIN EP).
For information on the gateways designed for the integration of other fieldbus encoders (for example SSI to Profinet: order codes IF55 ROT PT and IF55 LIN PT; SSI to EtherCAT: order codes IF55 ROT EC and IF55 LIN EC; SSI to Profibus: order codes IF55 ROT PB and IF55 LIN PB; and SSI to CANopen: order codes IF55 ROT CB and IF55 LIN CB), refer to the specific documentation.

Please note that the present manual does not prescind from the user's guide of the SSI encoder the gateway has to be connected to. Please read carefully the encoder's documentation before installing, connecting and operating the measuring system.
For detailed technical specifications please refer also to the product datasheet.

To make it easier to read the text, this guide can be divided into some main sections.

In the first section (from chapter 1 to chapter 4) general information concerning the safety, the mechanical installation and the electrical connection.

In the second section (chapter 5) information on how to install and configure the converter under the Studio 5000 development environment as well as tips for setting up and running properly and efficiently the unit are provided.

In the third section (chapter 6) both general and specific information is given on the EtherNet/IP interface. In this section the interface features and the parameters implemented in the unit are fully described.

In the fourth section (chapter 7) the Integrated Web Server is described.

NOTE
In the following pages the attributes and parameters that are specific to converters for rotary encoders are marked with an R letter in brackets, for example **64-01-10 Measuring Units per Span (R)**; the attributes and parameters that are specific to converters for linear encoders are marked with an L letter in brackets, for example **64-01-10 Position Step Setting (L)**.

Glossary of EtherNet/IP terms

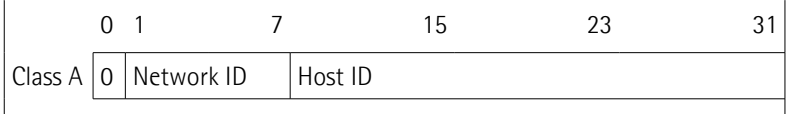
Adapter	Devices such as drives, controllers, and computers usually require an adapter to provide a communication interface between them and a network such as EtherNet/IP. An adapter reads data on the network and transmits it to the connected device. It also reads data in the device and transmits it to the network.
Adapter Class Device	An Adapter Class product emulates functions provided by traditional rack-adapter products. This type of node exchanges real-time I/O data with a Scanner Class product. It does not initiate connections on its own (see I/O Adapter).
Application I/O Trigger	The Application Trigger is one of three types of I/O triggers supported by CIP for the exchange of data on I/O connections. It is very similar to the CoS trigger and not common.
Application Objects	A reference to multiple Object Classes that implement product-specific features.
Attribute	Attributes are characteristics of an Object and/or an Object Class. They provide a description of an externally visible characteristic or feature of an object. Typically, Attributes provide status information or govern the operation of an Object. For example: the ASCII name of an object; and the repetition rate of a cyclic object. The Attribute part of an object specification is divided into two sections: • Class attributes; • Instance attributes.
Behavior	The relationship between attribute values and services, i.e. a specification of how an object acts. Actions results from different events the object detects, such as receiving service request, detecting internal faults or elapsing timers. The Behavior of an Object indicates how it responds to particular events. For example, a person can be abstractly viewed as an Instance within the Class Human. Generally speaking, all humans have the same set of attributes: age, gender, etc., yet, because the values of each attribute vary, each of us looks/behaves in a distinct fashion.
BOOTP (Bootstrap Protocol)	BOOTP lets the device configure itself dynamically at boot time if the network has a BOOTP server. The BOOTP server assigns the device a pre-configured IP address, a subnet mask, and a gateway address; therefore, you do not have to configure these using the parameters in the device. BOOTP can make it easier to administer an EtherNet/IP network.
Bridge	A bridge refers to a network device that can route messages from one Ethernet network to another.

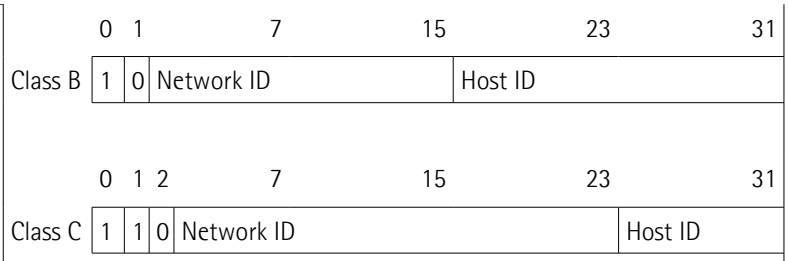
Broadcast	A broadcast transmission is a packet that all nodes on the network receive.
Change of State I/O Trigger	Change of State (CoS) is one of three types of I/O triggers supported by CIP for the exchange of data on Class 0 or 1 I/O connections. CoS endpoints send their messages when a change occurs. The data is also send at a background cyclic interval if no change occurs to keep the connection from timing out.
CIP (Common Industrial Protocol)	CIP is the transport and application layer protocol used for messaging over EtherNet/IP, ControlNet, and DeviceNet networks. The protocol is used for implicit messaging (real time I/O) and explicit messaging (configuration, data collection, and diagnostics).
Class	A class (of objects) is a set of objects that all represent the same kind of system component. A class is a generalization of an object. All objects in a class are identical in form and behavior, but may contain different attribute values. A class contains the objects that relate to a device, they are organized in instances. Ethernet/IP encoders from Lika supports the following classes: • Identity Object (Class Code 01h); • Message Router Object (Class Code 02h); • Assembly Object (Class Code 04h); • Connection Manager Object (Class Code 06h); • Position Sensor Object (Class Code 23h); • TCP/IP Interface Object (Class Code F5h); • EtherNet Link Object (Class Code F6h); • Device Level Ring (DLR) Object (Class Code 47h); • Quality of Service (QoS) Object (Class Code 48h).
Class Attribute	A Class Attribute is an attribute whose scope is that of the class as a whole, rather than any one particular instance. Therefore, the list of Class Attributes is different than the list of Instance Attributes. CIP defines the Instance ID value zero (0) to designate the Class level versus a specific Instance within the Class.
Class code	A hexadecimal identifier assigned to each CIP object.
Connected Messaging	A CIP connection is a relationship between two or more application objects on different nodes. The connection establishes a virtual circuit between end points for transfer of data. Node resources are reserved in advance of data transfer and are dedicated and always available. Connected messaging reduces data handling of messages in the node. Connected messages can be Implicit (I/O) or Explicit.
Connection Establishment/Close	Connections are established Connection Originators using the ForwardOpen service and closed by using the ForwardClose service. Connection clean-up takes place when either connection end point times out.

Connection Originator	The source node that makes a request to a Connection Target for a connection. It can initiate either an I/O connection or explicit message connection using the ForwardOpen service.
Connection Target	Destination for I/O or explicit message connection requests. Responds to a connection request with a ForwardOpen service response.
Client	Within a client/server model, the client is the device that sends a request to a server. The client expects a response from the server.
Communication Objects	A reference to the Object Classes that manage and provide the run-time exchange of implicit (I/O) and explicit messages.
Consumer	Within the producer/consumer model, the consumer is one of potentially several consuming devices that picks up a message placed on the network by a producing device.
Controller	A controller, also called programmable logic controller, is a solid-state control system that has a user-programmable memory for storage of instructions to implement specific functions such as I/O control, logic, timing, counting, report generation, communication, arithmetic, and data file manipulation. A controller consists of a central processor, input/output interface, and memory.
Cyclic I/O Trigger	Cyclic is one of three types of I/O triggers supported by CIP for the exchange of data on Class 0 or 1 I/O connections. Endpoints send their messages at pre-determined cyclic time intervals.
Data Rate	The data rate is the speed at which data is transferred on the EtherNet/IP network. You can set the device to a data rate of 10 Mbps Full-Duplex, 10 Mbps Half-Duplex, 100 Mbps Full-Duplex, or 100 Mbps Half-Duplex. If another device on the network sets or auto-negotiates the data rate, you can set the device to automatically detect the data rate.
DSI (Drive Serial Interface)	DSI stands for Drive Serial Interface, it is based on the ModBus RTU serial communication protocol.
DSI Peripheral	A device that provides an interface between DSI and a network or user.
DSI Product	A device that uses the DSI communications interface to communicate with one or more peripheral devices. For example, a motor drive is a DSI product.
Duplex	Duplex describes the mode of communication. Full-duplex communications let a device exchange data in both directions at the same time. Half-duplex communications let a device exchange data only in one direction at a time. The duplex used by the adapter depends on the type of duplex that other network devices, such as switches, support.
EDS (Electronic Data Sheet) Files	EDS files are simple text files that are used by network configuration tools for EtherNet/IP to describe products so

	that you can easily commission them on a network. EDS files describe a product device type, revision, and configurable parameters. EDS files can be downloaded from Lika web site.
EDS File	An Electronic Data Sheet (EDS) is an ASCII text file that describes the features of an EtherNet/IP device and is used by software tools for device and network connection configuration.
EEPROM	EEPROM is the permanent memory of a device. Devices such as the encoder store parameters and other information in EEPROM so that they are not lost when the device loses power. EEPROM is sometimes called "NVS (Non-Volatile Storage)".
Encapsulation Protocol	Defines the communication relationship between two nodes known as an Encapsulation Session. The Encapsulation Protocol uses TCP/UDP Port 44818 for several Encapsulation Commands and for CIP Explicit Messaging. An example encapsulation command is the List_Identity Command that performs a "network who". An Encapsulation Session must be established before any CIP communications can take place. Data format for the Encapsulation Protocol is Little-Endian.
EtherNet/IP Network	Ethernet/IP (Industrial Protocol) is an open producer-consumer communication network based on the Ethernet standard (IEEE 802.3), TCP/IP, UDP/IP, and CIP. Designed for industrial communications, both I/O and explicit messages can be transmitted over the network. Each device is assigned a unique IP address and transmits data on the network. The number of devices that an EtherNet/IP network can support depends on the class of IP address. For example, a network with a Class C IP address can have 254 nodes. General information about EtherNet/IP and the EtherNet/IP specification are maintained by the Open DeviceNet Vendor's Association (ODVA). ODVA is online at http://www.odva.org.
Exclusive Owner Connection	This is one of three types of Implicit (I/O) Connections. It is a Class 0 or 1 bidirectional connection to an Output connection point (typically an Assembly Object), where the data of this assembly can only be controlled by one Scanner. There may be a connection to an input assembly; this data is being sent to the scanner. If the input data length is zero, then this direction becomes a Heartbeat connection.
Explicit Message Client	An explicit message client initiates request/response oriented communications with other devices. Examples of explicit message clients are HMI devices, programming tools, or PC or Linux based applications that gather data from control devices.
Explicit Message Server	An explicit message server responds to request/response oriented communications initiated by explicit message clients. An example of an explicit message server is a bar code reader.
Explicit Messaging	Explicit Messages are used to transfer data that does not

	require continuous updates. They are typically used to configure, monitor, and diagnose a device over the network. Explicit Messages can be sent as a connected or unconnected message. CIP defines an Explicit Messaging protocol that states the meaning of the message. This messaging protocol is contained in the message data. Explicit Messaging provide the means by which typical request/response oriented functions are performed (e.g., module configuration). These messages are typically point-to-point. Message rates and latency requirements are typically not as demanding as I/O messaging.
ForwardOpen Service Request	The ForwardOpen Service Request is sent by the Connection Originator and received by the Connection Target to open and establish explicit and I/O connections. The ForwardOpen Service request and associated response contains all of the connection parameters, including transport class, production trigger, timing information, electronic key and connection IDs.
Gateway	A gateway is a device on a network that connects an individual network to a system of networks. When a node needs to communicate with a node on another network, a gateway transfers the data between the two networks.
Hardware Address	Each Ethernet device has a unique hardware address (sometimes called a MAC address) that is 48 bits. The address appears as six digits separated by colons (for example, xx:xx:xx:xx:xx:xx). Each digit has a value between 0 and 255 (0x00 and 0xFF). This address is assigned in the hardware and cannot be changed. It is required to identify the device if you are using a BOOTP utility.
I/O Adapter	An I/O Adapter receives implicit communications requests from an I/O Scanner then produces and consumes its I/O data, typically at the requested cyclic rate. An I/O Adapter can be a simple digital input device, or something more complex such as a modular pneumatic valve system.
I/O Client	Function that uses the I/O messaging services of another (I/O Server) device to perform a task. Initiates a request for an I/O message to the server module. The I/O Client is a Connection Originator of Implicit Message connections
I/O Data	I/O data, sometimes called "implicit messages" or "input/output," transmit time-critical data. The terms "input" and "output" are defined from the controller's point of view. Output is transmitted by the controller and consumed by the device. Input is transmitted by the device and consumed by the controller.
I/O Messaging	Used interchangeably with the term Implicit Messaging.
I/O Scanner	An I/O scanner initiates implicit connections with I/O adapter devices, i.e., it is an I/O Client. A scanner is typically the most complex type of EtherNet/IP device, as it must deal with issues such as configuration of which connections to make, and how to configure the adapter device. Scanners also typically

	support initiating explicit messages, i.e., it is also an Explicit Message Client. A programmable controller is an example of an I/O scanner (used interchangeably with Scanner Class).
I/O Server	Function that provides I/O messaging services to another (I/O Client) device. Responds to a request from the I/O Client for an I/O connection. An I/O Server is the target of the implicit message connection request.
Implicit Messaging	Implicit Messages are exchanged across I/O Connections with an associated Connection ID. The Connection ID defines the meaning of the data and establishes the regular/repeated transport rate and the transport class. No messaging protocol is contained within the message data as with Explicit Messaging. Implicit Messages can be point to point (unicast) or multicast and are used to transmit application specific I/O data. This term is used interchangeably with the term I/O Messaging. Implicit Messaging on EtherNet/IP uses UDP/IP frames on port 2222. They are typically Class 0 or 1 and of the type Exclusive Owner, Input Only and Listen Only.
Input Only Connection	This is one of three types of Implicit (I/O) Connections. It is a Class 0 or 1 Connection to an Input connection point (typically an assembly object). The scanner receives input data from the target device and produces a Heartbeat to the target device. There is no Output data.
Instance	An object instance is the actual representation of a particular object within a class, i.e. it is a specific and real (physical) occurrence of an object. For example: New Zealand is an instance of the object class Country. Each instance of a class has the same attributes, but also has its own particular set of attribute values. The terms Object, Instance, and Object Instance all refer to a specific Instance.
Instance Attribute	An Instance Attribute is an attribute whose value is unique to an object instance and whose definition is shared by all instances of an object. Each instance need only support the optional attributes that apply to it. If an instance does not support an optional attribute, the Attribute Not Supported (General Status code 0x14) error shall be returned for services targeting that attribute.
IP Address	A unique IP address identifies each node on an EtherNet/IP network. An IP address consists of 32 bits that are divided into four segments of one byte each. It appears as four decimal integers separated by periods (xxx.xxx.xxx.xxx). Each "xxx" can have a decimal value from 0 to 255. For example, an IP address could be 192.168.0.1. An IP address has two parts: a network ID and a host ID. The class of network determines the format of the address. 

	 The number of devices on your EtherNet/IP network will vary depending on the number of bytes that are used for the network address. In many cases you are given a network with a Class C address, in which the first three bytes contain the network address (subnet mask = 255.255.255.0). This leaves 8 bits or 256 addresses on your network. Because two addresses are reserved for special uses (0 is an address for the network usually used by the router, and 255 is an address for broadcast messages to all network devices), you have 254 addresses to use on a Class C address block. You must ensure that each device on the Internet has a unique address. You can then set the unique IP address for the device by using a BOOTP server or by manually configuring parameters in the device. The device reads the values of these parameters only at power-up.
Listen Only Connection	This is one of three types of Implicit Connections. It is a Class 0 or 1 Connection to an Input connection point (typically an assembly object). The scanner receives input data from the target device and produces a Heartbeat to the target device. There is no Output data. A Listen Only Connection can only be attached to an existing Exclusive Owner or Input Only Connection. If this underlying connection closes, then the Listen Only connection will also be closed or timed out.
Master	EtherNet/IP does not use Master/SIave technology or terminology.
Message Client	Function that uses the Explicit messaging services of another (Message Server) device to perform a task. Initiates an Explicit Message request to the server device.
Message Server	Function that provides Explicit Messaging services to another (Message Client) device. Responds to an Explicit Message request from the Message Client.
Multicast	Multicast is the single transmission of an I/O data packet that may be consumed by multiple devices using multicast IP and Ethernet destination addresses. See Producer/Consumer Communications Model.
Object	A CIP node is modeled as a collection of Objects. An Object provides an abstract representation of a particular component within a product. The realization of this abstract object model within a product is implementation dependent. In other words, a product internally maps this object model in a fashion specific to its implementation.
Ping	A ping is a message that is sent by a DSI product to its peripheral devices. They use the ping to gather data about the

	product, including whether it can receive messages and whether they can log in for control.
Point to Point (Unicast)	Point to Point or Unicast is the transmission of data to a single device.
Producer	Within the producer/consumer model, the producing device places a message on the network for consumption by one or several consumers. Generally, the produced message is not directed to a specific consumer.
Producer/Consumer Communications Model	For I/O Connections, CIP supports object-oriented Producer/Consumer communication. Connection identifiers embedded into each message are used by devices to determine which messages they should "consume" from other devices that "produce" messages. This enables efficient use of network bandwidth by transmitting information only once. Less bandwidth equates to greater efficiency and overall speed. EtherNet/IP uses IP multicast and Ethernet multicast destination addressing to implement this capability.
Requested Packet Interval (RPI)	EtherNet/IP devices typically produce or consume data based upon a Requested Packet Interval (RPI) value. Producer devices send data packets at a predetermined time interval based on the RPI, whereas consumer devices will listen for a packet of data at a given RPI.
Scanner Class	A Scanner Class product exchanges real-time I/O data with Adapter Class and Scanner Class products. This type of node can respond to connection requests and can also initiate connections to target devices (see I/O Scanner).
Server	Within a client/server model, the server is the device that receives a request from a client. The server is expected to give a response to the client.
Service (common service)	A list of the common services defined for the object. A function supported by an object and/or object class.
Service (object-specific service)	The full specifications of any services unique to the object.
Service code	Service codes are used to define the action that is requested to take place when an object or parts of an object are addressed through explicit messages. They are used to access classes or the attributes of a class or to generate specific events.
Slave	EtherNet/IP does not use Master/SIave technology or terminology.
Subnet Mask	A subnet mask is an extension to the IP addressing scheme that lets you use a single network ID for multiple physical networks. A bit mask identifies the part of the address that specifies the network and the part of the address that specifies the unique node on the network. A "1" in the subnet mask indicates the bit is used to specify the network. A "0" in

	the subnet mask indicates that the bit is used to specify the node. For example, a subnet mask on a Class C address may appear as follows: 11111111 11111111 11111111 11000000 (255.255.255.192). This mask indicates that 26 bits are used to identify the network and 6 bits are used to identify devices on each network. Instead of a single physical Class C network with 254 devices, this subnet mask divides it into four networks with up to 62 devices each.
Switches	Switches are network devices that provide virtual connections that help to control collisions and reduce traffic on the network. They are able to reduce network congestion by transmitting packets to an individual port only if they are destined for the connected device. In a control application, in which real time data access is critical, network switches may be required in place of hubs.
TCP (Transmission Control Protocol)	EtherNet/IP uses this protocol to transfer Explicit Messaging packets using IP. TCP guarantees delivery of data through the use of retries.
Transport Classes	CIP defines several Transport Classes for messaging connections. Within EtherNet/IP, I/O data sent on Class 1 connections is pre-pended with a 16-bit sequence count, while data on Class 0 connections is not. Class 3 connections are used for Explicit Messaging Connections.
UDP (User Datagram Protocol)	EtherNet/IP uses this protocol to transfer I/O packets using IP. UDP provides a simple, but fast capability to send I/O messaging packets between devices. This protocol ensures that devices transmit the most recent data because it does not use acknowledgments or retries.
Unconnected Messaging	Provides a means for a node to send message requests without establishing a CIP connection prior to data transfer. More overhead is contained within each message and the message is not guaranteed destination node resources. Unconnected Messaging is used for non-periodic requests (e.g., network "Who" function). Applies to explicit messages only.
Unicast (Point to Point)	Unicast or Point to Point is a connection for the transmission of data to a single device.

List of abbreviations

API	Actual Packet Interval
ASCII	American Standard Code for Information Interchange
ASN.1	Abstract Syntax Notation
CIP	The Common Industrial Protocol defined in this volume of the CIP Networks Library. CIP includes both connected and unconnected messaging.
CID	Connection Identifier
DLL	Data Link Layer
EPR	Expected Packet Rate
ISO	International Standards Organization
MAC ID	Media Access Control Identifier
PDU	Protocol Data Unit
ODVA	ODVA, Inc.
O ➡ T	Originator to Target (used to describe packets that are sent from the originator to the target)
OSI	Open Systems Interconnection (see ISO 7498)
RPI	Requested Packet Interval
SDU	Service Data Unit
SEM	State Event Matrix
SEMI	Semiconductor Equipment Materials International
STD	State Transition Diagram, used to describe object behaviour
T ➡ O	Target to Originator (used to describe packets that are sent from the target to the originator)
UCMM	Unconnected Message Manager

References

[1] THE CIP NETWORKS LIBRARY, Volume 1, Common Industrial Protocol (CIP™), Edition 3.22, April 2017

[2] THE CIP NETWORKS LIBRARY, Volume 2, EtherNet/IP Adaptation of CIP, Edition 1.23, April 2017

1 - Safety summary

1.1 Safety

- Always adhere to the professional safety and accident prevention regulations applicable to your country during device installation and operation;
- installation and maintenance operations have to be carried out by qualified personnel only, with power supply disconnected and stationary mechanical parts;
- device must be used only for the purpose appropriate to its design: use for purposes other than those for which it has been designed could result in serious personal and/or the environment damage;
- high current, voltage and moving mechanical parts can cause serious or fatal injury;
- warning! Do not use in explosive or flammable areas;
- failure to comply with these precautions or with specific warnings elsewhere in this manual violates safety standards of design, manufacture, and intended use of the equipment;
- Lika Electronic assumes no liability for the customer's failure to comply with these requirements.

1.2 Electrical safety

- Turn off power supply before connecting the device;
- connect according to explanation in the "4 - Electrical connections" section on page 29;
- in compliance with the 2014/30/EU norm on electromagnetic compatibility, following precautions must be taken:
  - before handling and installing, discharge electrical charge from your body and tools which may come in touch with the device;
  - power supply must be stabilized without noise, install EMC filters on device power supply if needed;
  - always use shielded cables (twisted pair cables whenever possible);
  - avoid cables runs longer than necessary;
  - avoid running the signal cable near high voltage power cables;
  - mount the device as far as possible from any capacitive or inductive noise source, shield the device from noise source if needed;
  - to guarantee a correct working of the device, avoid using strong magnets on or near by the unit;
  - minimize noise by connecting the shield and/or the connector housing and/or the frame to ground. Make sure that ground is not affected by noise. The connection point to ground can be situated both on the device side and on user's side. The best solution to minimize the interference must be carried out by the user. Provide the ground connection as close as possible to the converter. We suggest using the ground point provided in the cap, use one TCEI M3 x 6 cylindrical head screw with two tooth lock washers.

1.3 Mechanical safety

- Install the device following strictly the information in the "3 - Mounting instructions" section on page 27;
- mechanical installation has to be carried out with stationary mechanical parts;
- do not disassemble the converter, unless otherwise indicated;
- do not tool the converter or its shaft;
- delicate electronic equipment: handle with care; do not subject the device and the shaft to knocks or shocks;
- respect the environmental characteristics declared by manufacturer.

2 - Identification

Device can be identified through the **order code**, the **serial number** and the **MAC address** printed on the label applied to its body. Information is listed in the delivery document too. Please always quote the order code, the serial number and the MAC address when reaching Lika Electronic for purchasing spare parts or needing assistance. For any information on the technical characteristics of the product refer to the technical catalog.

Warning: devices having order code ending with "/Sxxx" may have mechanical and electrical characteristics different from standard and be supplied with additional documentation for special connections (Technical info).

3 - Mounting instructions

WARNING
Installation and maintenance operations must be carried out by qualified personnel only, with power supply disconnected and mechanical parts absolutely in stop.

3.1 Overall dimensions

(values are expressed in mm)

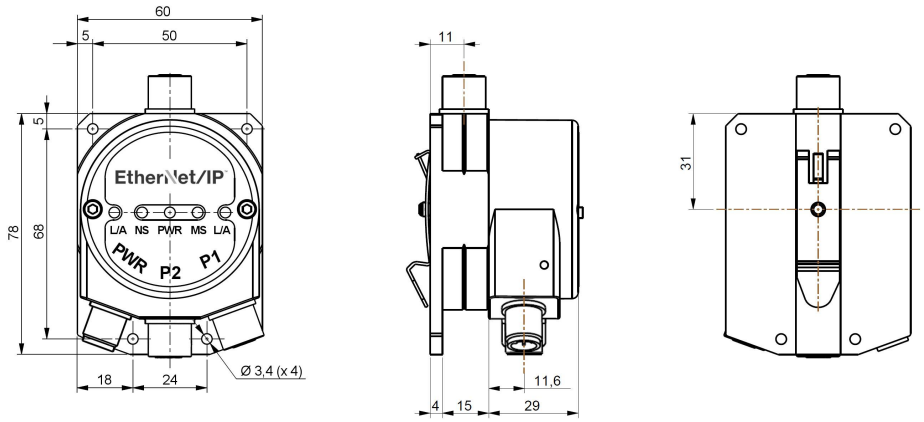


Figure 1 - Overall dimensions

3.2 Installation on panel (Figure 1)

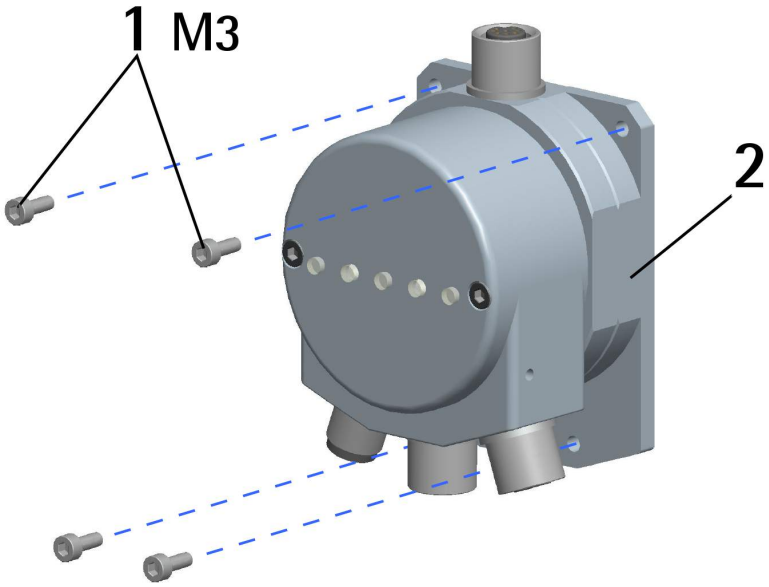


Figure 2 - Installation on panel

The unit is designed for installation on the even surface of a panel.
The back flange **2** is fitted with four holes for inserting the fixing screws **1**. Tighten the four fixing screws **1** until the unit is properly fastened to the support. Use **four M3 8 mm min. long cylinder head screws**. The recommended tightening torque is **1.1 Nm**.

3.3 Installation with DIN rail clip (Figure 2)

The unit can be installed on DIN profiles inside a rack. A clip **3** for direct fitting on DIN TS35 rails is supplied for free. It has to be fixed on the back of the flange **2** by means of the provided screw **4**.

WARNING
To mount the clip **3** you need to remove the cap **5** and drill a hole **A** in the back flange **2**. Delicate electronic circuits and wirings are located inside the cap **5**. Thus this operation has to be accomplished by skilled personnel only. Please pay careful attention and observe great precaution when carrying out this operation.

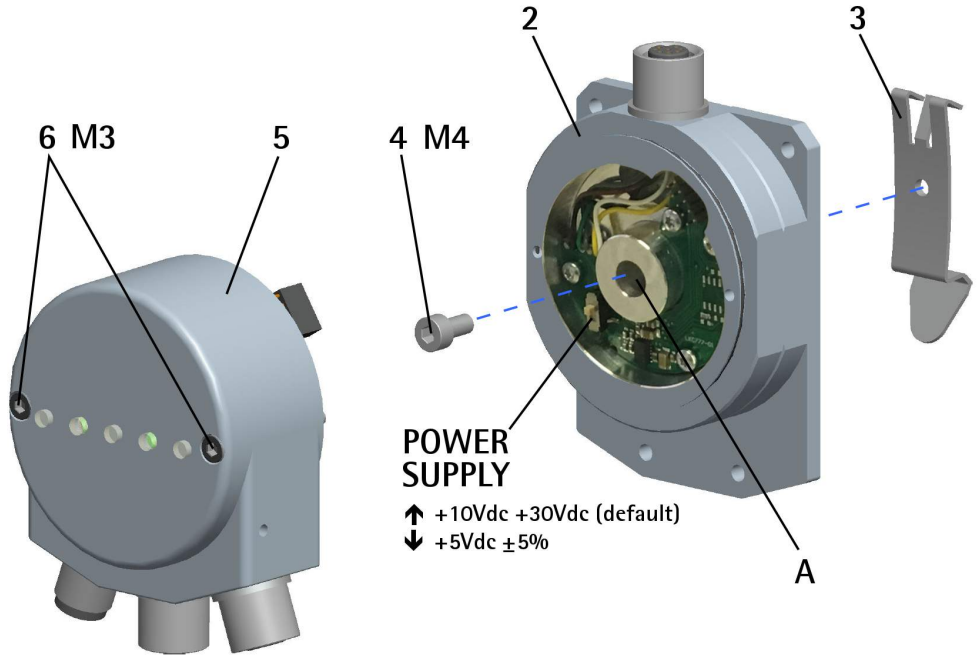


Figure 3 - Installation with DIN rail clip

- Loosen the two screws **6** that fasten the cap **5** to the back flange **2**;
- open the cap **5** and separate it from the flange **2**; please pay attention to the internal wirings and connectors;
- drill a 4.5 mm diameter hole **A** in the flange **2**; use the notch in the inside of the flange **2** to guide the drill bit;

WARNING
Carefully remove the scrap material after drilling.

- mount the clip **3** on the back of the flange **2** and fix it by means of the provided M4 x 8 screw **4**; it has to be screwed on the inner side of the flange **2**;
- replace the cap **5** and fix it by means of the screws **6**.

4 - Electrical connections

WARNING
Installation, electrical connection and maintenance operations must be carried out by qualified personnel only, with power supply disconnected. Mechanical components must be in stop.

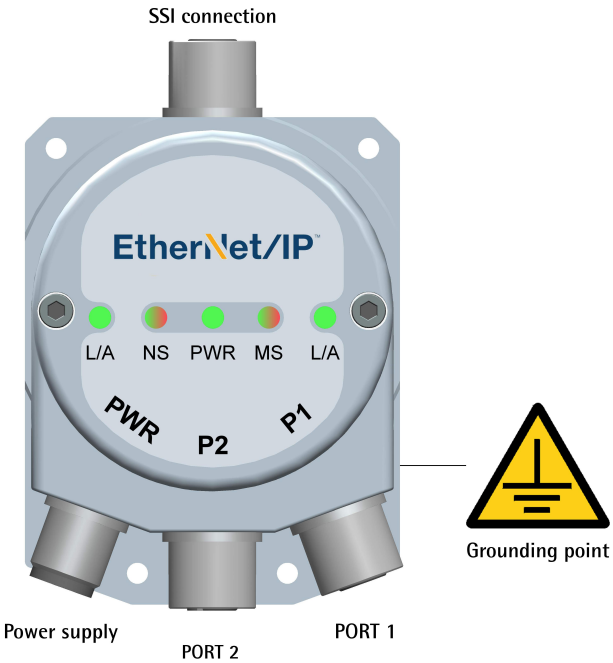


Figure 4 - IF55 EP

4.1 Connection cap of the converter

WARNING
Do not remove or mount the connection cap with power supply switched ON. Damage may be caused to internal components.

The DIP switches meant to set *via hardware* the node ID of the converter and the voltage level of the power supply to be provided to the connected encoder are located inside the connection cap. Thus you must remove the connection cap to access them.

NOTE
Be careful not to damage the internal components when you perform this operation.

To remove the connection cap loosen the two screws **1**. Please be careful with the internal connector.
Always replace the connection cap at the end of the operation. Take care in re-connecting the internal connector. Tighten the screws **1** using a tightening torque of approx. 2.5 Nm.

WARNING
You are required to check that the converter back flange and the connection cap are at the same potential before replacing the connection cap!

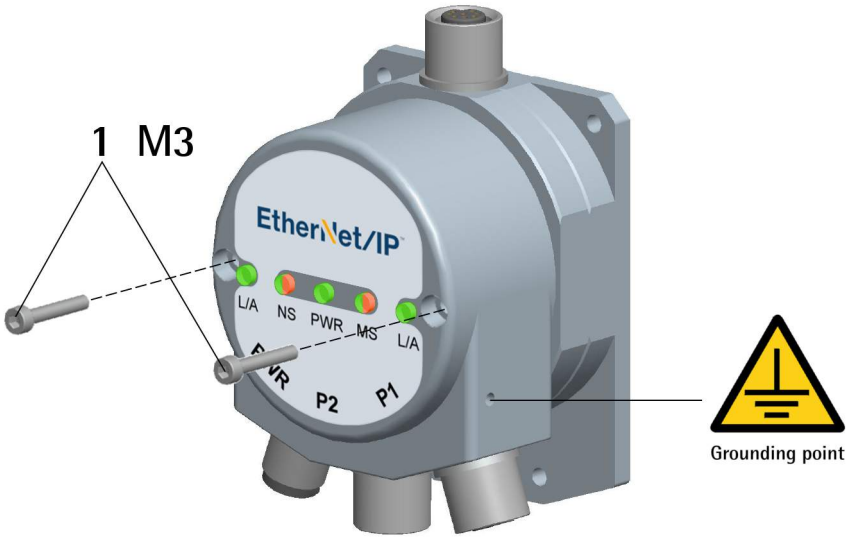
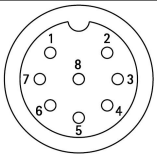


Figure 5 - Removing the connection cap

4.2 SSI connection (Figure 4)

The connection cap is fitted with one M12 8-pin female connector to network the IF55 gateway and the SSI encoder.

M12 8-pin	SSI connection
(frontal side)	 A coding female

Pin	Description
1	0Vdc power supply
2	+Vdc power supply *
3	Clock OUT +
4	Clock OUT -
5	Data IN +
6	Data IN -
7 and 8	not connected

* The power supply voltage level must be set through the POWER SUPPLY DIP switch located inside the enclosure of the converter, see the "4.7 POWER SUPPLY DIP switch (Figure 6)" section on page 33.

WARNING

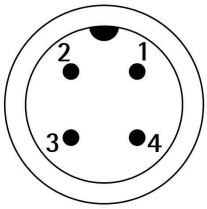
The max. length of the SSI cable must not exceed 30 m / 98.425 ft.

4.3 Power supply and EtherNet/IP interface connectors (Figure 4)

The connection cap is fitted with three M12 4-pin connectors with pin-out in compliance with the Ethernet standard. Therefore you can use standard Ethernet cables commercially available, for more information see later.

4.3.1 PWR Power supply connector (Figure 4)

M12 4-pin male connector with A coding is used for power supply.

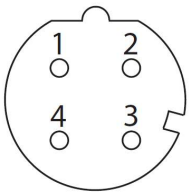


Description	Pin
+10Vdc +30Vdc	1
n.c.	2
0Vdc	3
n.c.	4

n.c. = not connected

4.3.2 P1 Port 1 and P2 Port 2 connectors (Figure 4)

Two M12 4-pin female connectors with D coding are used for Ethernet connection through port 1 and port 2.



Description	Pin
Tx Data +	1
Rx Data +	2
Tx Data -	3
Rx Data -	4

The Ethernet interface supports 100 Mbit/s, half-duplex/full-duplex operation.
P1 PORT 1 and P2 PORT 2 M12 connectors have pin-out in compliance with the Ethernet standard. Therefore you can use standard Ethernet cables commercially available, for more information see later.
P1 PORT 1 and P2 PORT 2 connectors are interchangeable.

4.4 Network configuration: cables, hubs, switches - Recommendations

Cables and connectors comply with the Ethernet specifications.
Standard Ethernet cables type CAT-5, CAT-5e and CAT-6 commercially available can be used.
The minimum cabling performance that will support EtherNet/IP is Category 5 as defined by ANSI/TIA/EIA-568-B.2 Annex N. There are reasons to select one category of cabling over another. In general, the higher the category, the better the cabling performance. Another consideration is balance. Category 5e, 6 and the newest proposed category, known as augmented 6 or Category 6a, will support current applications such as 1Gb/s and 10 Gb/s. Generally speaking, the greater the cabling category, the less EMC protection that is needed. Consult your cable supplier for guidance on EMC protection for the specific cable being used.
For complete information please refer to IEC 61918, IEC 61784-5-13 and IEC 61076-2-101.

The maximum cable length (100 meters) predefined by Ethernet 100Base-TX must be compulsorily fulfilled.
Regarding wiring and EMC measures, the IEC 61918 and IEC 61784-5-13 must be considered.
Compliance with IEEE Ethernet standards provides users with a choice of network interface speeds – e.g., 10, 100 Mbps, 1 Gbps and beyond – and a flexible network architecture compatible with commercially available Ethernet installation options including copper, fiber, fiber ring and wireless, and topologies including star, linear and ring.
A hub is an inexpensive connectivity method that provides an easy method of connecting devices on information networks (shared Ethernet). A switch reduces collisions and is recommended for real-time control installations (switched Ethernet). Routers are used to isolate control data traffic from other types of office data traffic, to isolate information traffic on the plant floor from control traffic on the plant floor, and for security purposes, i.e., firewalls. Repeaters

extend the overall network cable length. They can also connect networks with different media types.

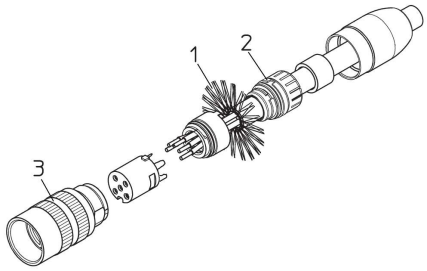
For a complete list of the available cordsets, patchcords and connection kits please refer to the product datasheet ("Accessories" list).

4.5 Ground connection

To minimize noise connect properly the shield and/or the connector housing and/or the frame to ground. Connect properly the cable shield to ground on user's side. Lika's EC- pre-assembled cables are fitted with shield connection to the connector ring nut in order to allow grounding through the body of the device. Lika's E- connectors have a plastic gland, thus grounding is not possible. If metal connectors are used, connect the cable shield properly as recommended by the manufacturer. Anyway make sure that ground is not affected by noise. It is recommended to provide the ground connection as close as possible to the device. We suggest using the ground point provided in the cap (see Figure 5, use 1 TCEI M3 x 6 cylindrical head screw with 2 tooth lock washers).

4.6 Connection of the shield

Disentangle and shorten the shielding **1** and then bend it over the part **2**; finally place the ring nut **3** of the connector. Be sure that the shielding **1** is in tight contact with the ring nut **3**.



4.7 POWER SUPPLY DIP switch (Figure 6)

WARNING
Power supply must be turned off before performing this operation!

The power supply voltage level to be provided to the connected encoder must be set through the POWER SUPPLY DIP switch located inside the enclosure of the converter. It must be according to the power supply voltage level required by the connected SSI encoder. To access the POWER SUPPLY DIP switch refer to the "4.1 Connection cap of the converter" section on page 30.

Set the POWER SUPPLY DIP switch to UP position to provide +10Vdc +30Vdc power supply voltage level to the encoder (default setting); set the POWER

SUPPLY DIP switch to DOWN position to provide +5Vdc ±5% power supply voltage level to the encoder.

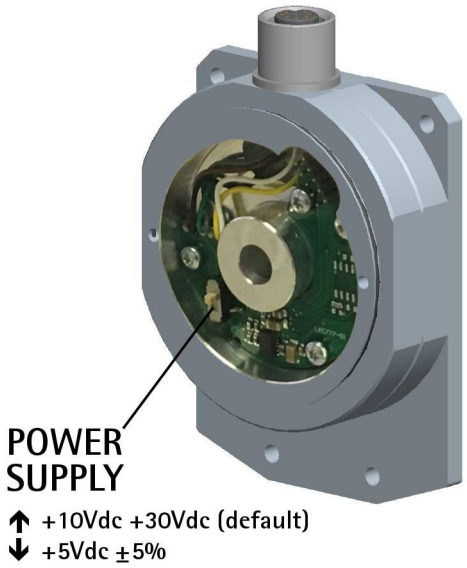


Figure 6

4.8 MAC address and IP address

The unit can be identified in the network through the **MAC address** and the **IP address**.

The MAC address has to be intended as a permanent and globally unique identifier assigned to the unit for communication on the physical layer; while the IP address is the name of the unit in a network using the Internet protocol. MAC address is 6-byte long and cannot be modified. It consists of two parts, numbers are expressed in hexadecimal notation: the first three bytes are used to identify the manufacturer (OUI, namely Organizationally Unique Identifier), while the last three bytes are the specific identifier of the unit. The MAC address can be found on the label applied to the converter.

The IP address must be assigned by the user to each interface of the unit to be connected in the network as well as the subnet mask.

For additional information on the MAC address refer to the "5.4 MAC address" section on page 51.

For additional information on the IP address refer to the "4.9 EtherNet/IP Node ID" section below.

4.9 EtherNet/IP Node ID

By default, the converter is configured so that it uses the IP address, Subnet mask, and Gateway address that are saved internally. The use of a DHCP Server to allocate the IP address is disabled.

The IP address, the Subnet mask and the Gateway address are set next to the **IP Address**, **Network Mask** and **Gateway Address** parameters in the **F5-01-05**

Interface Configuration attribute, see the "6.12.6 Class F5h: TCP/IP Interface Object" section on page 137. For more information on setting the node ID *via software* refer to the "4.9.1 Setting the node ID via software" section hereafter.
The following table summarizes the default software IP parameters.

IP Parameter	IP address
IP address	192.168.1.10
Subnet mask	255.255.255.0
Gateway address	0.0.0.0
DHCP	Disabled

As an alternative, the node address can be set *via hardware* by using the DIP switch located inside the enclosure. For more information on setting the node ID via hardware refer to the "4.9.2 Setting the node ID via hardware (DIP A dip switch)" section below.

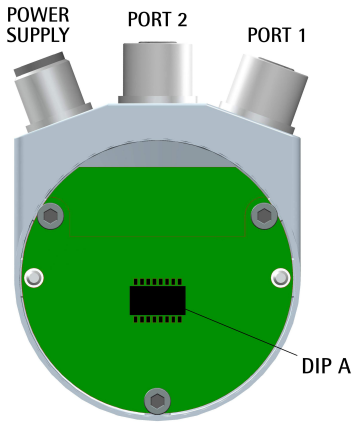
4.9.1 Setting the node ID via software

As stated, by default, the converter is configured so that it uses the IP address saved internally. The sliding levers in the DIP A DIP switch located inside the enclosure are all set to OFF (value 0_{10}, 00000000_2) so meaning that the software values saved internally are used, see the next section.
The software values can be changed by using a software tool such as Studio 5000 or by means of the integrated web server (see the "7.8 Network configuration" section on page 172) or by enabling a DHCP server (see the "4.9.2 Setting the node ID via hardware (DIP A dip switch)" section hereafter).
Any Net ID value and Host ID value can be set via software.

4.9.2 Setting the node ID via hardware (DIP A dip switch)

WARNING
Power supply must be turned off before setting the DIP switch!

The EtherNet/IP node ID can be set *via hardware* using the DIP A DIP switch located inside the enclosure. To access the DIP A dip switch please refer to the "4.1 Connection cap of the converter" section on page 30.

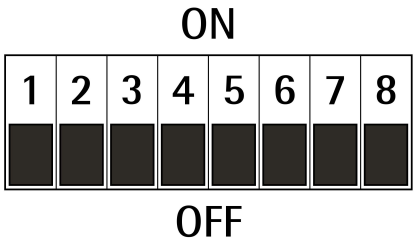


The DIP A DIP switch allows to set the Host ID; the Net ID is fixed, as defined in the following table:

192.168.1.	EtherNet/IP Node
Net ID	Host ID

Allowed node addresses range between 1_{10} (00000001_2) and 254_{10} (11111110_2). The subnet mask is 255.255.255.0.
Value 0_{10} (00000000_2) means that the system uses the software IP address, Subnet mask, and Gateway address that are saved internally (default value, see the "4.9.1 Setting the node ID via software" section on page 35).
Value 255_{10} (11111111_2) enables the use of a DHCP Server. The IP address and the Subnet mask are assigned by a DHCP Server.
The dip switches are evaluated only during switching the operating voltage on or when resetting the converter.
Changes in the position of the switches when the converter is switched on are taken into consideration only after switching the converter off and then on again.

DIP A:

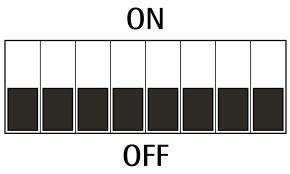


Set the EtherNet/IP node ID in binary value: ON = 1, OFF = 0

bit	1 LSB	2	3	4	5	6	7	8 MSB
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	2^7

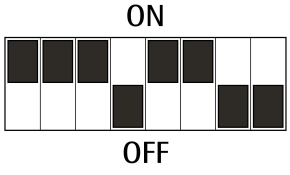
EXAMPLE
Enabling the software node ID = 0:
0_{10} = 0000 0000$_2$ (binary value)

bit	1	2	3	4	5	6	7	8
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	2^7
	OFF	OFF	OFF	OFF	OFF	OFF	OFF	OFF



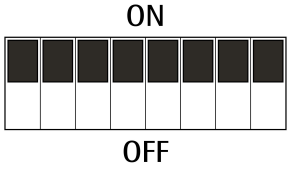
Setting the node ID = 55:
55_{10} = 0011 0111$_2$ (binary value)

bit	1	2	3	4	5	6	7	8
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	2^7
	ON	ON	ON	OFF	ON	ON	OFF	OFF



Enabling the DHCP server = 255:
255_{10} = 1111 1111$_2$ (binary value)

bit	1	2	3	4	5	6	7	8
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	2^7
	ON	ON	ON	ON	ON	ON	ON	ON



4.10 Diagnostic LEDs (Figure 4)

Five LEDs located in the cap of the converter (see Figure 4) are meant to show visually the operating or fault status of the converter and the EtherNet/IP interface. The meaning of each LED is explained in the following tables.

LED	Description
L/A Link/Activity LED for port 2 P2 (green)	It shows the state and the activity of the physical link (port 2 P2).
OFF	Link not active, no activity on port 2 P2.
ON	Port 2 P2 link active, no activity.
FLASHING	Activity on port 2 P2.

LED	Description
NS Network Status LED (green / red)	It shows the current state of the network.
OFF	• The device is switched OFF. • No IP address has been set.
ON green	The device is online, one or more CIP connections have been established (Class 1 or Class 3 communications).
FLASHING green	The device is online, but no CIP connection has been established; one or more CIP connections have been expired (Class 1 or Class 3 communications).
ON red	• Duplicate IP address conflict has occurred, two devices on the network have been assigned the same IP address. • A fatal error has occurred.

LED	Description
PWR Power LED (green)	It shows the power supply state.
OFF	The converter power supply is switched OFF.
ON	The converter power supply is switched ON.

LED	Description
MS Module Status LED (green / red)	It shows the state of the EtherNet/IP device.
OFF	The power supply is switched OFF.
ON green	The device is controlled by a Scanner in Run state.
FLASHING green	• The device is not configured. • The Scanner is in Idle state.
ON red	A major fault, i.e. an unexpected error has occurred (EXCEPTION state, FATAL error, etc.). See the **01-01-05 Status** attribute on page 89.
FLASHING red	One or more recoverable faults have occurred. The module is configured, but stored parameters differ from currently used parameters. See the **01-01-05 Status** attribute on page 89.

LED	Description
L/A Link/Activity LED for port 1 P1 (green)	It shows the state and the activity of the physical link (port 1 P1).
OFF	Link not active, no activity on port 1 P1.
ON	Port 1 P1 link active, no activity.
BLINKING	Activity on port 1 P1.

While the converter is performing its power up testing, the NS network status indicator and the MS module status indicator shall perform a test sequence.

5 - Quick reference

5.1 Quick setting and main functions

The following instructions allow the operator to quickly and safely set up the converter in a standard operational mode and to execute its main functions.
Sometimes a function or a procedure can be accomplished by using alternative ways:

- by means of a software tool such as Studio 5000 from Rockwell Automation (see the "5.5 Installing the converter under Studio 5000 design environment" section on page 52 ff);
- by means of the Integrated Web Server (see the "7 - Integrated Web Server" section on page 153);
- or via hardware by means of the internal Dip switches (see the "4.9.2 Setting the node ID via hardware (DIP A dip switch)" section on page 35).

They are all mentioned whenever available.
For complete and detailed information please read the mentioned pages thoroughly.

5.1.1 If you connect a rotary encoder

- Mechanically install the device, see on page 27 ff;
- execute the electrical and network connections, see on page 29 ff;
- switch on the +10Vdc +30Vdc power supply;
- in the software tool install the EDS file, see on page 59 ff;
- in the software tool insert the Lika module and select the converter type, see on page 62 ff;
- in the software tool set the device name, see on page 62 ff;
- if required, set the IP address and the subnet mask to the node, see here later for alternatives; the default address (software address) set by Lika is **192.168.1.10**;
- set the characteristics of the connected SSI encoder:
  - set the number of SSI clocks next to the **No of SSI clocks (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute;
  - set the output code used by the SSI encoder to arrange the output information next to the **SSI output code (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute;
  - set the protocol used by the SSI encoder to arrange the absolute information next to the **SSI protocol (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute;
  - set the physical singleturn resolution of the SSI encoder next to the **Singleturn resolution (bits)** parameter in the **64-01-51 Encoder Resolution (R)** attribute; the **64-01-2A Physical Resolution Span (R)** attribute is automatically set accordingly;

  - set the physical multiturn resolution of the SSI encoder next to the **Multiturn resolution (bits)** parameter in the **64-01-51 Encoder Resolution (R)** attribute; the **64-01-2B Number of Spans (R)** attribute is automatically set accordingly;
- the attributes used to specifically configure the converter are grouped in the Communications Adapter Device Object, see the "6.12.5 Class 64h: Application Object" section on page 97; they allow, for example, to set the singleturn resolution or the total resolution, to enable the scaling function or to change the counting direction; the complete list of the default parameters is available on page 176;
- if you want to use the physical resolution (see the **64-01-2A Physical Resolution Span (R)** attribute and the **64-01-2B Number of Spans (R)** attribute), please check that the **64-01-0E Scaling Function Control (R)** attribute is disabled (= 00h; see on page 101);
- otherwise, if you need a custom resolution, enable the scaling function in the **64-01-0E Scaling Function Control (R)** attribute (= 01h; see on page 101) and then set the resolution you need for your application next to the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes (see on page 104 ff);
- if you need you can enter the Preset value next to the **64-01-13 Preset Value** attribute and then set it in the desired position; see on page 113;
- save the new setting values (use the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute; see on page 135).

5.1.2 If you connect a linear encoder

- Mechanically install the device, see on page 27 ff;
- execute the electrical and network connections, see on page 29 ff;
- switch on the +10Vdc +30Vdc power supply;
- in the software tool install the EDS file, see on page 59 ff;
- in the software tool insert the Lika module and select the converter type, see on page 62 ff;
- in the software tool set the device name, see on page 62 ff;
- if required, set the IP address and the subnet mask to the node, see here later for alternatives; the default address (software address) set by Lika is **192.168.1.10**;
- set the characteristics of the connected SSI encoder:
  - set the number of SSI clocks next to the **No of SSI clocks (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute;
  - set the output code used by the SSI encoder to arrange the output information next to the **SSI output code (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute;
  - set the protocol used by the SSI encoder to arrange the absolute information next to the **SSI protocol (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute;

  - set the physical resolution of the SSI encoder expressed in nanometres next to the **64-01-51 Encoder Resolution (L)** attribute; the **64-01-2A Physical Measuring Step (L)** attribute is automatically set accordingly;
  - set the max. number of information the SSI encoder is able to provide for the max. measuring length next to the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute;
- the attributes used to specifically configure the converter are grouped in the Communications Adapter Device Object, see the "6.12.5 Class 64h: Application Object" section on page 97; they allow, for example, to set the singleturn resolution or the total resolution, to enable the scaling function or to change the counting direction; the complete list of the default parameters is available on page 176;
- if you want to use the physical resolution (see the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute), please check that the **64-01-0E Scaling Function Control (L)** attribute is disabled (= 00h; see on page 102);
- otherwise, if you need a custom resolution, enable the scaling function in the **64-01-0E Scaling Function Control (L)** attribute (= 01h; see on page 102) and then set the resolution you need for your application next to the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes (see on page 105 ff);
- if you need you can enter the Preset value next to the **64-01-13 Preset Value** attribute and then set it in the desired position; see on page 113;
- save the new setting values (use the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute; see on page 135).

5.1.3 Setting the node address

The node address and the network-related parameters can be set either via software or via hardware.
Software configuration:

- set the **IP Address**, **Network Mask** and **Gateway Address** parameters in the **F5-01-05 Interface Configuration** attribute, see the "6.12.6 Class F5h: TCP/IP Interface Object" section on page 137; the sliding levers in the DIP A DIP switch are all set to OFF (value 0_{10}, 00000000_2), see the "4.9 EtherNet/IP Node ID" section on page 34);
- set the parameters in the Integrated Web Server, see the "7.8 Network configuration" section on page 172; the sliding levers in the DIP A DIP switch are all set to OFF (value 0_{10}, 00000000_2), see the "4.9 EtherNet/IP Node ID" section on page 34);
- enable a DHCP Server as follows (the sliding levers in the DIP A DIP switch are all set to OFF -value 0_{10}, 00000000_2-; or all set to ON -value 255_{10}, 11111111_2-):
  - see the **F5-01-03 Configuration Control** attribute, see the "6.12.6 Class F5h: TCP/IP Interface Object" section on page 137;

- enable the DHCP Server in the Integrated Web Server, see the "7.8 Network configuration" section on page 172.

Hardware configuration:

- set the sliding levers in the DIP A DIP switch to value 0_{10} (00000000_2) to enable the software IP address, Subnet mask, and Gateway address that are saved internally, see software configuration above;
- set the sliding levers in the DIP A DIP switch to any value in the range between 1_{10} (00000001_2) and 254_{10} (11111110_2). The Subnet mask is 255.255.255.0;
- set the sliding levers in the DIP A DIP switch to value 255_{10} (11111111_2) to enable the use of a DHCP Server.

5.1.4 Setting scaling function and custom resolution

- If you want to use the physical resolution of the encoder, please check that the **64-01-0E Scaling Function Control (R)** / **64-01-0E Scaling Function Control (L)** attribute is disabled (="0"), see on page 101 / 102; in this case, the device uses the physical resolution (see the **64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)** attributes, if the encoder is rotary; see the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute, if the encoder is linear) to arrange the absolute position value.
  You can also use the Integrated Web Server, see the "7.6 Setting the attributes" section on page 161; or a software tool, see the "5.5.11 Configuring the converter" section on page 65;
- on the contrary, if you need a custom resolution, you must enable the scaling function by setting the **64-01-0E Scaling Function Control (R)** / **64-01-0E Scaling Function Control (L)** attribute to ="1" first and then set the required resolution parameters:
  if the encoder is rotary:
  - set the singleturn resolution next to the **64-01-10 Measuring Units per Span (R)** attribute, see on page 104;
  - set the total resolution next to the **64-01-11 Total Measuring Range (R)** parameter, see on page 108.

  If the encoder is linear:
  - set the custom resolution next to the **64-01-10 Position Step Setting (L)** attribute, see on page 105;
  - set the total measuring range next to the **64-01-11 Total Measuring Range (L)** parameter, see on page 110.

  You can also use the Integrated Web Server, see the "7.6 Setting the attributes" section on page 161; or a software tool, see the "5.5.11 Configuring the converter" section on page 65.

NOTE

Please consider that if the **Bypass mode** parameter in the **64-01-50 Encoder Settings (R)** (see on page 123) / **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1" = enabled, the scaling function -even if enabled- is ignored.

5.1.5 Reading the absolute position

To read the position value you can choose among the following methods.

- To read the absolute position of the encoder see the **64-01-03 Position value (R)** attribute on page 98 for rotary encoders; / see the **64-01-03 Position value (L)** attribute on page 98 for linear encoders;
- open the Integrated Web Server, see the "7.3 Encoder position and speed" section on page 155; see the "7.4 Converter information (EtherNet/IP attributes)" section on page 157;
- open the **Monitor Tags** tabbed page in your project, see the "5.5.9 Checking the communication" section on page 64.

NOTE

Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) / **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "0" = disabled, the position value read by the encoder can be processed according to needs, so the user can scale the value, set a preset and change the counting direction. On the contrary, if the **Bypass mode (R)** / **Bypass mode (L)** parameter is set to "1" = enabled, the information from the encoder is transmitted "as it is" and not processed in any way. The preset, scaling, and counting direction functions -even if set and enabled- are ignored and the **64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)** attributes (rotary encoder) / **64-01-2A Physical Measuring Step (L)** attribute and **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (linear encoder) are used to calculate the position information. If, for example, the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated. As soon as the "Bypass mode" is disabled, the preset, scaling, and counting direction functions -if set and enabled- become active and the **64-01-03 Position value (R)** / **64-01-03 Position value (L)** will be accordingly.

5.1.6 Reading the velocity value

To read the velocity value you can choose among the following methods.

- To read the velocity value of the encoder see the **64-01-18 Velocity Value** attribute on page 115;
- open the Integrated Web Server, see the "7.3 Encoder position and speed" section on page 155; see the "7.4 Converter information (EtherNet/IP attributes)" section on page 157;
- open the **Monitor Tags** tabbed page in your project, see the "5.5.9 Checking the communication" section on page 64.

5.1.7 Setting and executing the preset

To set and execute the preset you can choose among the following methods.

- Enter a suitable value next to the **64-01-13 Preset Value** attribute, see on page 113; the preset value is activated as soon as the value is confirmed.
- If you need to activate the value that has been already set next to the **64-01-13 Preset Value** attribute in a different physical position of the encoder shaft, you can use the bit 0 **Activate Preset** in the **64-01-68 Command Register** attribute, see on page 134.
- Open the **Set IF55-ROT-EP Preset** page in the Integrated Web Server, see the "7.5 Setting the Preset value" section on page 159.
- Use the Test_IF55_ROT_Lika.acd sample program, you can find it in the **SW_IF55_ROT_EP_Example.zip** compressed file. Refer also to the "5.5.12 How to create a sample program and send parameters" section on page 65.

NOTE

Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) / **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1" = enabled, the preset function -even if set and activated- is ignored. If the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated.

5.1.8 Saving data

To save the parameters permanently you can choose among the following methods.

- Use the Class Service 16h available for the Application Object, see on page 97.
- Set the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1 and then back to 0, see on page 135.
- Use the **Save Parameters** function in the **Set IF55-ROT-EP Registers** page of the Integrated Web Server, see the "7.6 Setting the attributes" section on page 161.

5.1.9 Restoring defaults

To restore the default parameters you can choose among the following methods.

- Use the Class Service 15h available for the Application Object, see on page 97.
- Set the bit 7 **Restore Parameters to Defaults** in the **64-01-68 Command Register** attribute to 1 and then back to 0, see on page 135.
- Use the **Load Default Param.** function in the **Set IF55-ROT-EP Registers** page of the Integrated Web Server, see the "7.6 Setting the attributes" section on page 161.

5.1.10 Examples for rotary encoders

EXAMPLE 1
We need to connect an **MM36 12/8192 BB** rotary encoder.

The main features of the rotary encoder are:
Singleturn resolution: **12 bits = 4,096 cpr** ("12", see the order code in the product datasheet).
Multiturn resolution: **13 bits = 8,192 rev.** ("8192", see the order code in the product datasheet).
Total resolution = **25 bits** = 4,096 x 8,192 = 33 554 432
Output code: **Binary code** ("BB", see the order code in the product datasheet).
SSI protocol: **25-bit "LSB Right Aligned" protocol** (see the User's manual).

64-01-50 Encoder Settings (R) = 1900h
No of SSI clocks (R) = 19h (= 25 dec)
SSI output code (R) = 0h (= Binary code)
SSI protocol (R) = 0h (= 25-bit "LSB Right Aligned" protocol)
64-01-51 Encoder Resolution (R) = 0D0Ch
Singleturn resolution (bits) = 0Ch (=12 bits = 4,096 cpr)
Multiturn resolution (bits) = 0Dh (= 13 bits = 8,192 rev.)

64-01-2A Physical Resolution Span (R) and **64-01-2B Number of Spans (R)** attributes are automatically set accordingly and used to arrange the position information.
Total Physical Resolution = **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**
If you want to use the physical resolution:
64-01-0E Scaling Function Control (R) attribute = 00h

If you need a custom resolution:
64-01-0E Scaling Function Control (R) attribute = 01h
Now set the resolution you need for your application next to the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes

EXAMPLE 2
We need to connect an **AM58 13/4096 G** rotary encoder.

The main features of the rotary encoder are:
Singleturn resolution: **13 bits = 8,192 cpr** ("13", see the order code in the product datasheet).
Multiturn resolution: **12 bits = 4,096 rev.** ("4096", see the order code in the product datasheet).
Total resolution = **25 bits** = 8,192 x 4,096 = 33 554 432
Output code: **Gray code** ("G", see the order code in the product datasheet).

SSI protocol: **25-bit "LSB Right Aligned" protocol** (see the User's manual).

64-01-50 Encoder Settings (R) = 1910h
No of SSI clocks (R) = 19h (= 25 dec)
SSI output code (R) = 1h (= Gray code)
SSI protocol (R) = 0h (= 25-bit "LSB Right Aligned" protocol)
64-01-51 Encoder Resolution (R) = 0C0Dh
Singleturn resolution (bits) = 0Dh (=13 bits = 8,192 cpr)
Multiturn resolution (bits) = 0Ch (= 12 bits = 4,096 rev.)

64-01-2A Physical Resolution Span (R) and **64-01-2B Number of Spans (R)** attributes are automatically set accordingly and used to arrange the position information.
Total Physical Resolution = **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**

If you want to use the physical resolution:
64-01-0E Scaling Function Control (R) attribute = 00h

If you need a custom resolution:
64-01-0E Scaling Function Control (R) attribute = 01h
Now set the resolution you need for your application next to the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes

EXAMPLE 3
We need to connect an **HM58 16/16384 GA** rotary encoder.

The main features of the rotary encoder are:
Singleturn resolution: **16 bits = 65,536 cpr** ("16", see the order code in the product datasheet).
Multiturn resolution: **14 bits = 16,384 rev.** ("16384", see the order code in the product datasheet).
Total resolution = **30 bits** = 65,536 x 16,384 = 1 073 741 824
Output code: **Gray code** ("GA", see the order code in the product datasheet).
SSI protocol: **"LSB Right Aligned" protocol** (see the User's manual).

64-01-50 Encoder Settings (R) = 1E10h
No of SSI clocks (R) = 1Eh (= 30 dec)
SSI output code (R) = 1h (= Gray code)
SSI protocol (R) = 0h (= "LSB Right Aligned" protocol)
64-01-51 Encoder Resolution (R) = 0E10h
Singleturn resolution (bits) = 10h (=16 bits = 65,536 cpr)
Multiturn resolution (bits) = 0Eh (= 14 bits = 16,384 rev.)

64-01-2A Physical Resolution Span (R) and **64-01-2B Number of Spans (R)** attributes are automatically set accordingly and used to arrange the position information.
Total Physical Resolution = **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**
If you want to use the physical resolution:
64-01-0E Scaling Function Control (R) attribute = 00h

If you need a custom resolution:
64-01-0E Scaling Function Control (R) attribute = 01h
Now set the resolution you need for your application next to the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes

5.1.11 Examples for linear encoders

EXAMPLE 1
We need to connect a **SMA5-GA-50** linear encoder.

The main features of the linear encoder are:
Resolution: **0.05 mm** (-50-, see the order code in the product datasheet).
Max. measuring length: **5,050 mm** (see the "Mechanical Specifications" in the product datasheet).
Output code: **Gray code** (-GA-, see the order code in the product datasheet).
SSI protocol: **25-bit "LSB Right Aligned" protocol** (see the User's manual).

64-01-50 Encoder Settings (L)
No of SSI clocks (L) = 19h (= 25 dec)
SSI output code (L) = 01h (= Gray code)
SSI protocol (L) = 00h (= 25-bit "LSB Right Aligned" protocol)
Physical Total Resolution (L) = 11h (= Max. measuring length/Resolution = 5,050/0.05 = 101,000 ≈ 2^{17} = 17 bits)
64-01-51 Encoder Resolution (L) = C350h (0.05 mm resolution = 50,000 nm resolution)
64-01-11 Total Measuring Range (L) = 0002 0000h (= 5,050/0.05 = 101,000 information; default and max. value 2^{17} = 131,072 dec = 0002 0000h) as a default; the user can set a custom measuring range

If you want to use the physical resolution:
64-01-0E Scaling Function Control (L) attribute = 00h

If you need a custom resolution:
64-01-0E Scaling Function Control (L) attribute = 01h
64-01-10 Position Step Setting (L) ≥ **64-01-2A Physical Measuring Step (L)**

If you set a 0 preset along the path, when the encoder moves back and cross the zero, the value immediately after 0 will be $2^{\text{Physical Total Resolution (L)}}$ - 1, i.e. 131,071 (assuming that **64-01-11 Total Measuring Range (L)** = 131,072).

...	131069	131070	131071	0	1	2	...

EXAMPLE 2
We need to connect a **SMAX-BG-100** linear encoder.

The main features of the linear encoder are:
Resolution: **0.1 mm** (-100-, see the order code in the product datasheet).
Max. measuring length: **600 mm** (see the "Mechanical Specifications" in the product datasheet).
Output code: **Binary code** (-BG-, see the order code in the product datasheet).
SSI protocol: **"MSB Left Aligned" protocol** (see the User's manual).

64-01-50 Encoder Settings (L)
No of SSI clocks (L) = 0Dh (= 13 dec), according to **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute
SSI output code (L) = 00h (= Binary code)
SSI protocol (L) = 01h (= "MSB Left Aligned" protocol)
Physical Total Resolution (L) = 0Dh (= Max. measuring length/Resolution = 600/0.1 = 6,000 ≈ 2^{13} = 13 bits)
64-01-51 Encoder Resolution (L) = 0001 86A0h (0.1 mm resolution = 100,000 nm resolution)
64-01-11 Total Measuring Range (L) = 0000 2000h (= 600/0.1 = 6,000 information; default and max. value 2^{13} = 8,192 dec = 0000 2000h) as a default; the user can set a custom measuring range

If you want to use the physical resolution:
64-01-0E Scaling Function Control (L) attribute = 00h

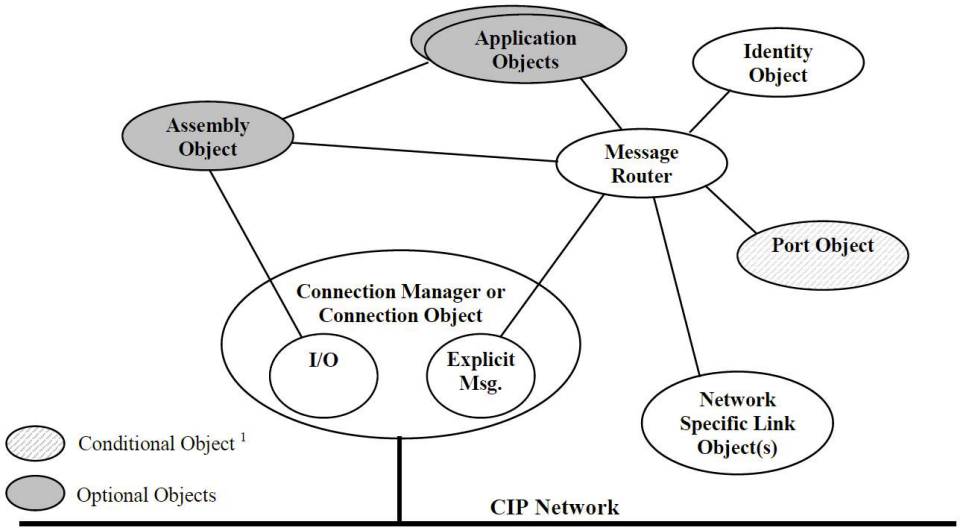
If you need a custom resolution:
64-01-0E Scaling Function Control (L) attribute = 01h
64-01-10 Position Step Setting (L) ≥ **64-01-2A Physical Measuring Step (L)**

If you set a 0 preset along the path, when the encoder moves back and cross the zero, the value immediately after 0 will be $2^{\text{Physical Total Resolution (L)}}$ -1, i.e. 8,191 (assuming that **64-01-11 Total Measuring Range (L)** = 8,192).

...	8189	8190	8191	0	1	2	...

5.2 About Lika converters

Lika converters are **0C hex type devices** and comply with the specifications reported in the Chapter 6 "Device Profiles, Communications Adapter Device Type 0C hex" of the publication "THE CIP NETWORKS LIBRARY, Volume 1, Common Industrial Protocol (CIP™)".
The Object Model of a communications adapter device is represented in the following picture:



1 – Required if the device routes between two or more CIP subnets, optional otherwise

Figure 7 - Object model

The Parameter Object data mapping complies with information in the "Mapping Parameter Object Data" section.
The attributes that are used to specifically configure the converter and make it operational in order to provide connection and communication are all grouped in the Application Object, refer to the "6.12.5 Class 64h: Application Object" section on page 97.

5.2.1 Network identity

Lika EtherNet/IP converters use the following identity settings available in the Identity Object, see the "6.12.1 Class 01h: Identity Object" section on page 87:

Identity Name: **Vendor ID**
Attribute: **01-01-01 Vendor ID**
Setting: **0299h = 665dec = Lika Electronic Srl**

Identity Name: **Device Type**
Attribute: **01-01-02 Device type**
Setting: **000Ch: Communications Adapter Device Profile**

Identity Name: **Product Code**
Attribute: **01-01-03 Product code**
Setting: **0020h = 32dec = IF55-ROT series converter** = converter for rotary encoders
Setting: **0021h = 33dec = IF55-LIN series converter** = converter for linear encoders

Identity Name: **Revision**
Attribute: **01-01-04 Revision**
Setting: **device dependent**

Identity Name: **Serial Number**
Attribute: **01-01-06 Serial number**
Setting: **device dependent**

Identity Name: **Product Name**
Attribute: **01-01-07 Product name**
Setting: **IF55-ROT Posicontrol Device** **converter for rotary encoders**
IF55-LIN Posicontrol Device **converter for linear encoders**

5.2.2 Network and communication settings

The **MAC address** of the device is always reported in the label applied to the converter enclosure. See on page 34.
The **EtherNet/IP Node ID** can be set both via software and via hardware using the DIP A DIP switch located inside the converter enclosure. By default it is set via software and its value is 192.168.1.10. See on page 34.

5.3 Configuring the converter with Studio 5000 V30.00 from Rockwell Automation

In this manual some screenshots are shown to explain how to install and configure the converter in a supervisor. In the specific example the development environment is Studio 5000 V30.00 from Rockwell Automation; it is used in combination with CompactLogix 5370 L1 Controller "1769-L16ER-BB1B/B" series from Allen Bradley. Therefore, the information on the installation of the EDS file, the assignment of the IP address and the device name, the configuration of the converter in the network, topology, diagnostics, etc. will always refer to the aforementioned design environment. If you need to install the converter using a different configuration tool, please read and follow

carefully the instructions given in the documentation provided by the manufacturer.
In the following pages the Controller is assumed to have 192.168.1.20 IP address and 255.255.255.0 Subnet mask.

Lika Electronic EtherNet/IP converter documentation can be provided with a **sample project** supplied free of charge. This program is designed to make your own project planning, programming, communication and diagnostics with Studio 5000 V30.00 design environment user-friendly and reliable. For instance it allows to set the Preset value and execute it. See for example the **SW_IF55_ROT_EP_Example.zip** compressed file.

5.4 MAC address

The MAC address is an identifier unique worldwide.
The MAC-ID consists of two parts: the first three bytes are the manufacturer ID and are provided by IEE standard authority; the last three bytes represent a consecutive number of the manufacturer.

NOTE
The MAC address is always printed on the converter label for commissioning purposes.

The MAC address has the following structure:

Bit value 47 ... 24			**Bit value 23 ... 0**		
10	B9	FE	X	X	X
Company code (OUI)			**Consecutive number**		

The MAC address can also be read next to the **F6-01-03 Physical Address** attribute. Refer to the "6.12.7 Class F6h: Ethernet Link Object" section on page 142.
It is further shown in the **IF55-xxx-EP Information** page of the web server under the title of the page. Refer to the "7.4 Converter information (EtherNet/IP attributes)" section on page 157.

5.5 Installing the converter under Studio 5000 design environment

5.5.1 Description of the EDS file

The functionality of an EtherNet/IP device is always described in an EDS file (Electronic Data Sheet file). The Electronic Data Sheet file provides information about the device basic communication and functional properties. It must be installed in the Controller.

Lika Electronic's EtherNet/IP converters for SSI rotary and linear encoders are supplied with their own EDS file. Please note that the rotary encoder converters and the linear encoder converters have different EDS files. Files for rotary encoders are marked with ROT- in the file name; while files for linear encoders are marked with LIN- in the file name.

The names of the files are:

- **IF55_ROT_EP_Hx_Sx.eds** converters for rotary encoders
- **IF55_LIN_EP_Hx_Sx.eds** converters for linear encoders

where:

- "IF55" is the converter series;
- "ROT" indicates that it is designed to interface SSI rotary encoders (while "LIN" type converters are designed to interface SSI linear encoders);
- "EP" is the Lika code that identifies the EtherNet/IP protocol;
- "Hx" is the hardware version of the converter;
- "Sx" is the software version of the converter.

The version of the EDS file is reported under the Version item inside the file.
EDS files can be paired with the **IF55_EP.ico** picture file available inside the file folder (the picture is also integrated into the EDS file).

Follow the path **www.lika.biz > DISPLAYS & INTERFACES > SIGNAL CONVERTERS & INTERFACES (POSICONTROL) > IF55** to download the EDS files from Lika's corporate web site.

5.5.2 Configuring the network interface controller (NIC) of the computer

To set the computer's IP address in Windows, type *network and sharing* into the **Search** box in the **Start** menu and select **Network and Sharing Center** when the **Control Panel** comes up.

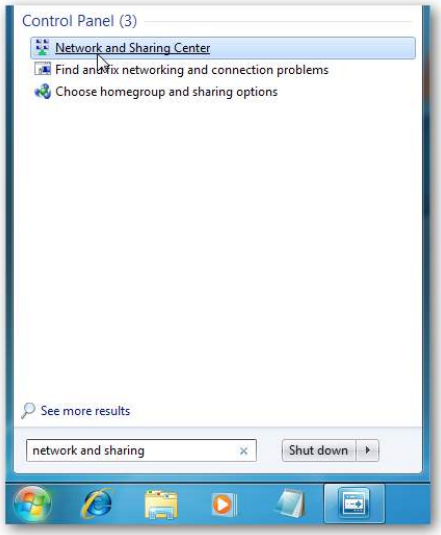


Figure 8 - Network and Sharing Center

Then when the **Network and Sharing Center** opens, click on **Change adapter settings**.

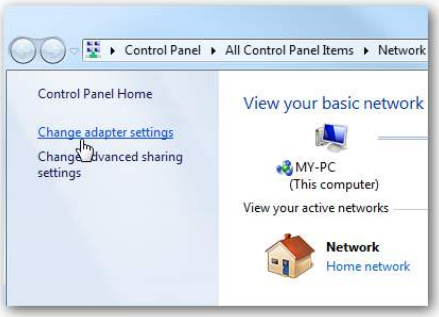


Figure 9 - Change adapter settings

Right-click on your local adapter and select **Properties**.

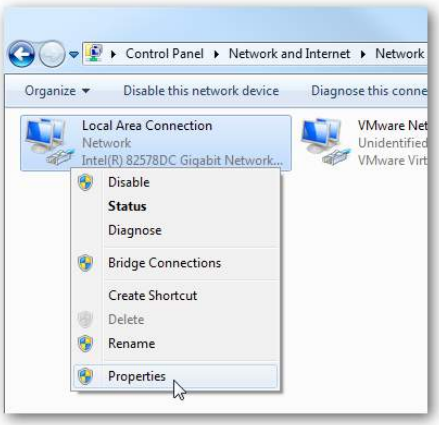


Figure 10 - Local Area Connection properties

In the **Local Area Connection Properties** window highlight *Internet Protocol Version 4 (TCP/IPv4)*, then click the **Properties** button.

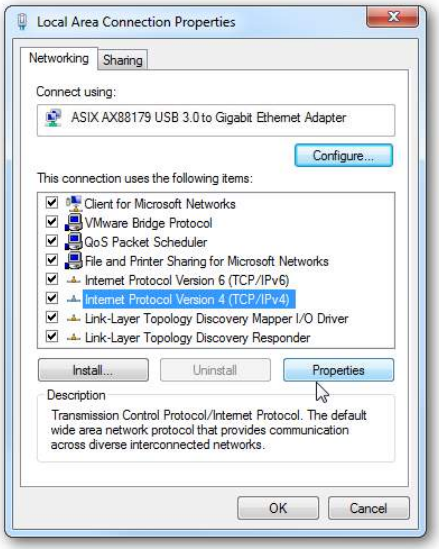


Figure 11 - Internet Protocol Version 4 properties

Now select the **Use the following IP address** radio button and enter the correct IP, Subnet mask, and Default gateway that corresponds with your network setup. Then, if required, enter your Preferred and Alternate DNS Server addresses. We suggest setting a simple Class C network configuration such as 192.168.1.xx as the default software IP address of the converter has this NET ID. Check **Validate settings upon exit** so Windows can find any problems with the addresses you entered. When you are finished click **OK**.

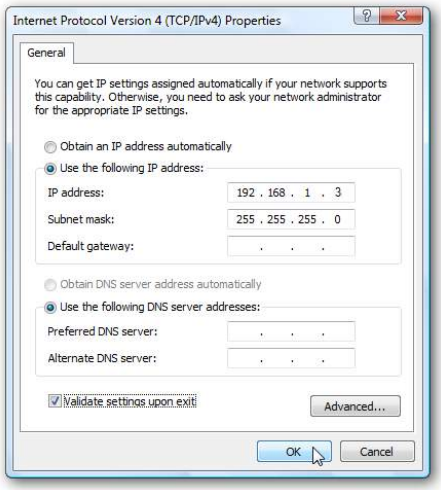


Figure 12 - Setting the IP Address

5.5.3 Networking the PC and the Controller

Use a Category 5 minimum cable to network the Ethernet port of the PC to the Ethernet port of the Controller.

5.5.4 Configuring the driver

Launch the **RSLinx Classic** communication software and then open **RSWho** by pressing **Communication** and then the **RSWho** command.
Again in the menu bar of the main page press **Communication** and then the **Configure Drivers** command.
The **Configure Drivers** dialog box will appear.

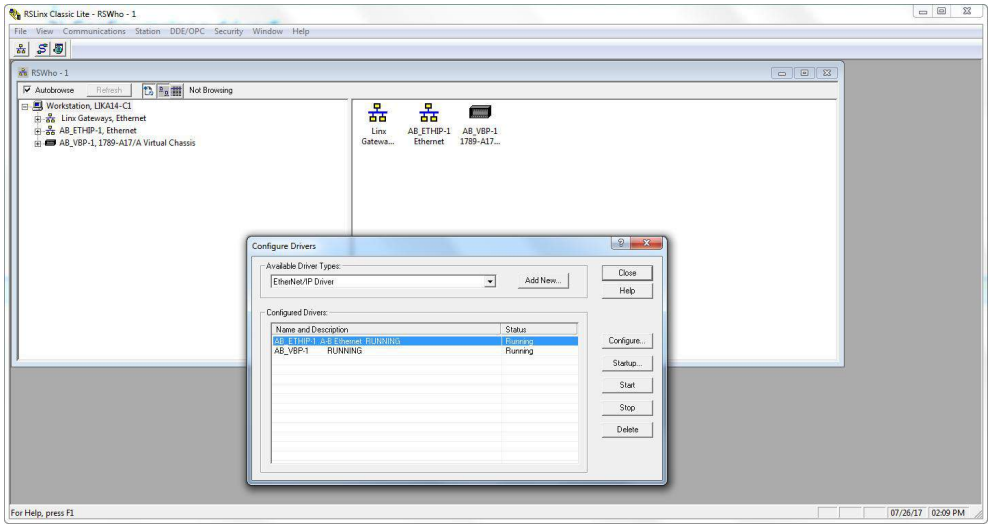


Figure 13 - Configure Drivers

From the **Configure Drivers** dialog box, select the desired driver from the **Available Driver Types** list.
Click **Add New**. The **Add New RSLinx Classic Driver** dialog box opens.
Enter a name for the selected driver (15 characters at maximum), and click **OK**.
The **Configuration** dialog box for that driver shows.
In the **Configuration** dialog box, enter the appropriate parameters for the desired driver.
Click **OK** to close the **Configuration** dialog box. The new driver now appears in the **Configured Drivers** list.
Press **Close** to close the dialog box.

Now right-click the driver you have just installed and press **Configure Driver**.

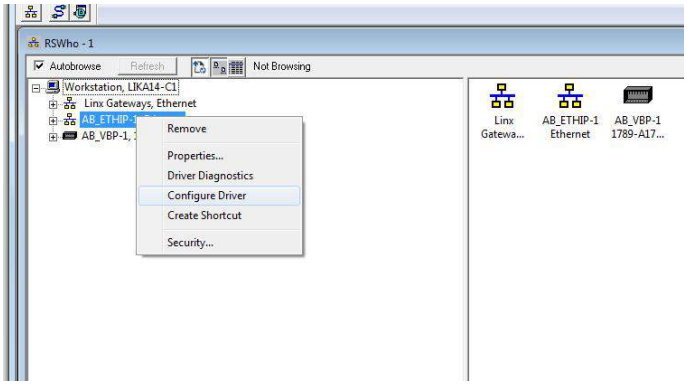


Figure 14 - Configure Driver

In the **Configure Driver** dialog box, select the network interface controller you configured and connected to the PLC; finally press **OK** to confirm.

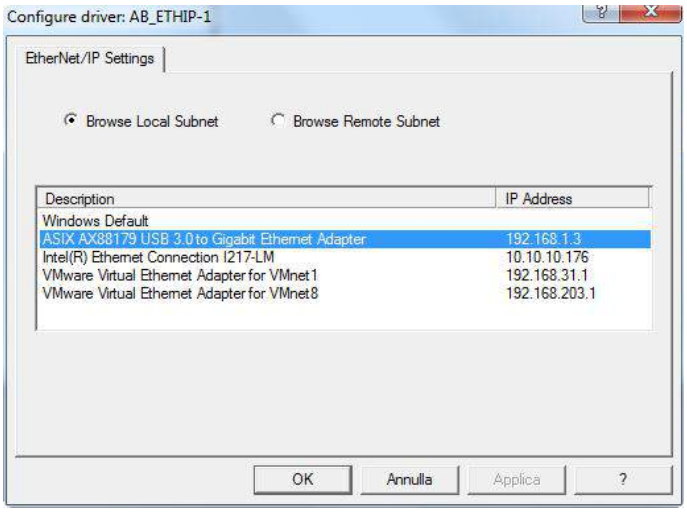


Figure 15 - Browse Local Subnet

5.5.5 Starting a new project

Double-click on the **Studio 5000** icon on your Desktop to launch Studio 5000 software. The Studio 5000 Splash Screen appears.
Select **New Project** under the **Create** section.

Figure 16 - Studio 5000 New Project

When the **New Project** pop-up is displayed, select **Logix** and the type of controller (such as "1769-L16ER-BB1B", in the example). Enter the name of the project and the path where the file has to be saved.

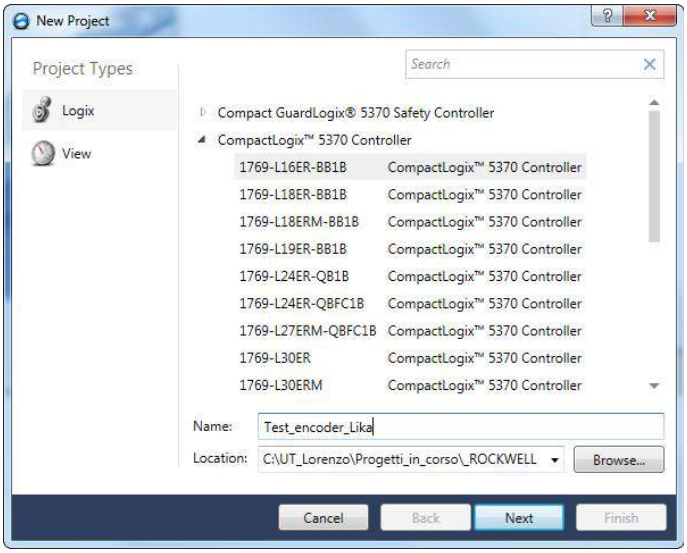


Figure 17 - New Project

Press the **Next** button and then set the **Revision** and the **Expansion I/O** settings. Finalize by pressing the **Finish** button.

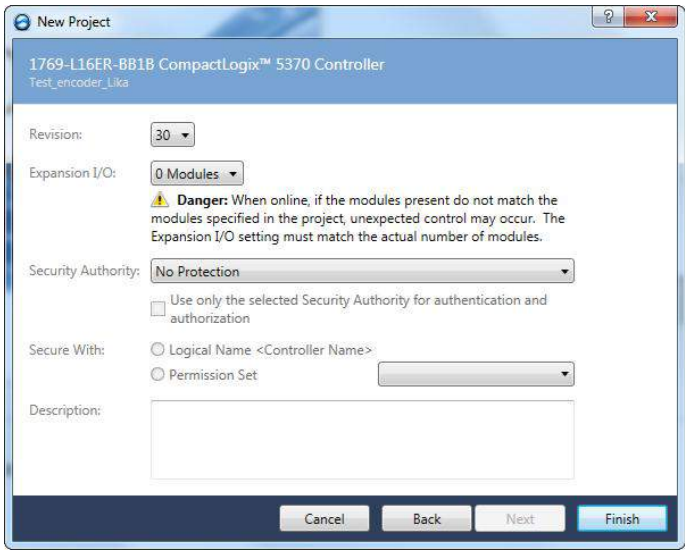


Figure 18 - Controller's settings

5.5.6 Installing the EDS file

To manually register the EDS files of the converter in the **EDS Hardware Installation Tool**, perform the following steps.

Launch the **EDS Hardware Installation Tool** by pressing **Tools** and then the **EDS Hardware Installation Tool** command.
The **Rockwell Automation's EDS Wizard** dialog box opens.
On the **Options** screen select **Register an EDS file(s)**, then press **Next**.

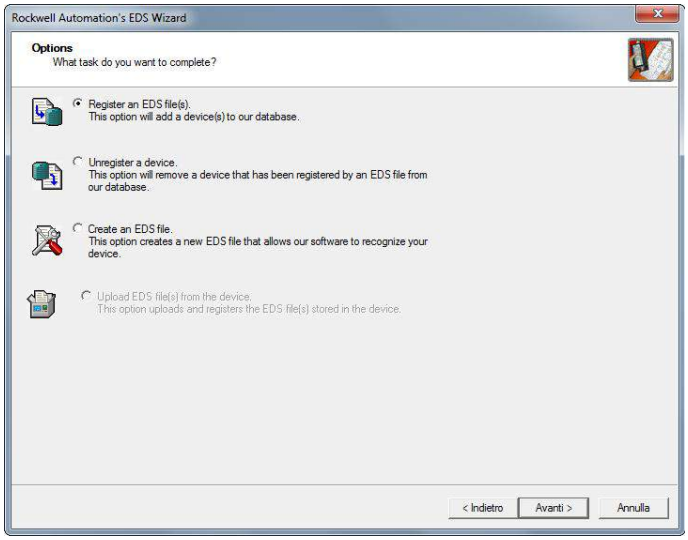


Figure 19 - EDS Wizard

On the **Registration** screen select **Register a single file** to register one EDS file at a time, and click **Browse** to select the EDS file corresponding to the device to be installed (for example IF55_ROT_EP_H1_S1.eds as in the screenshot Figure 20, please check the order code) and press **Next** button until the registration is finalized.

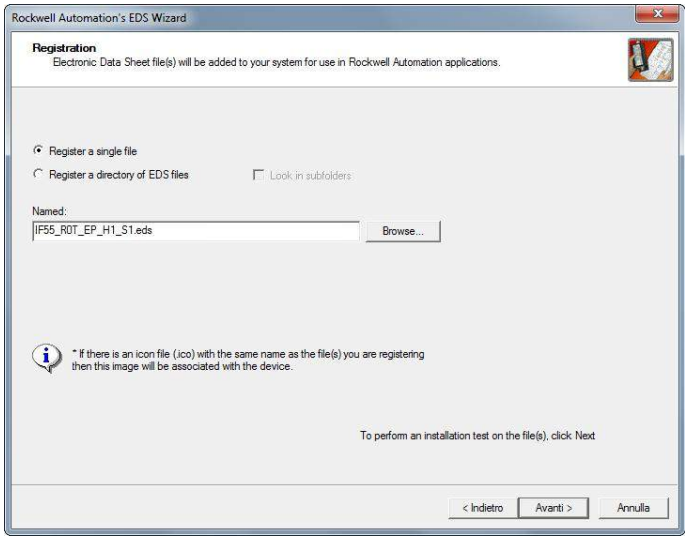


Figure 20 - EDS Wizard

5.5.7 Defining the communication path

To define a path to the controller click on the icon shown in Figure 21.

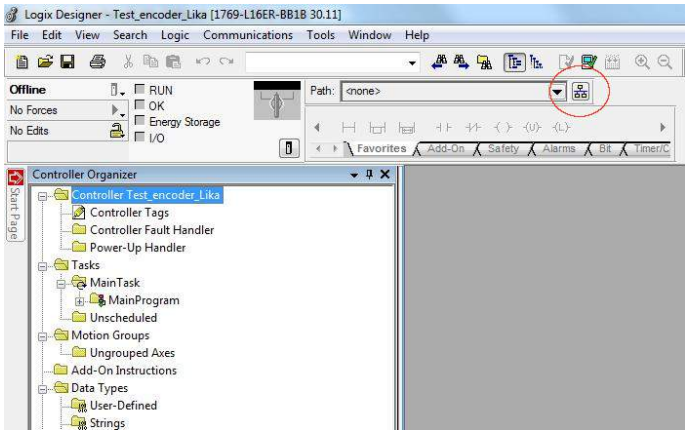


Figure 21 - Path to Controller

Browse to the Controller, select it and click the **Set Project Path** button.

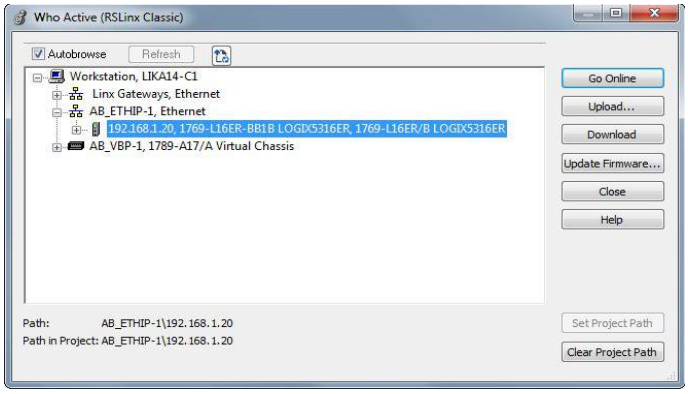


Figure 22 - Set Project Path

Close the dialog box: the selected path will appear on the main page.

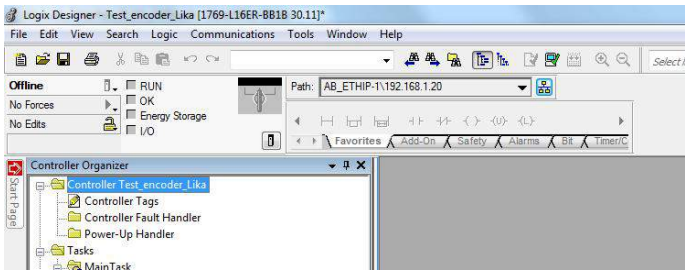


Figure 23 - Project Path set

5.5.8 Adding the converter to the project

On the **Controller Organizer**, right-click on **Ethernet** and select **New Module ...** from the pull-down menu.

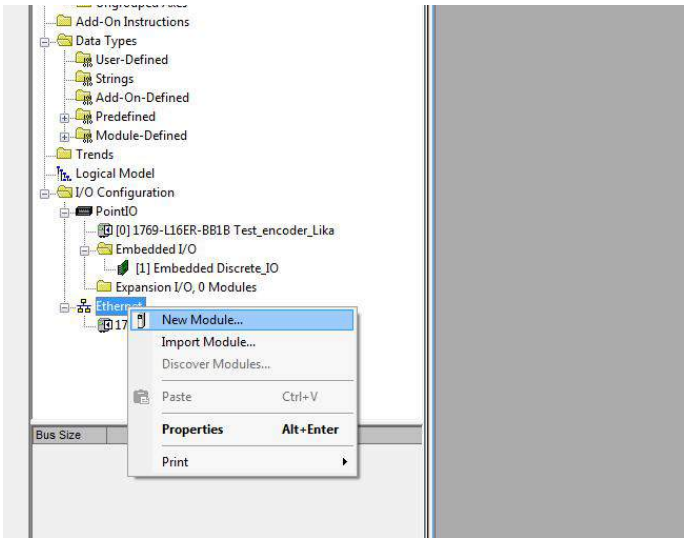


Figure 24 - New Module

On the **Select Module Type** dialog box select the installed converter module (IF55-ROT-EP in the screenshot, Figure 25). Click **Create**.

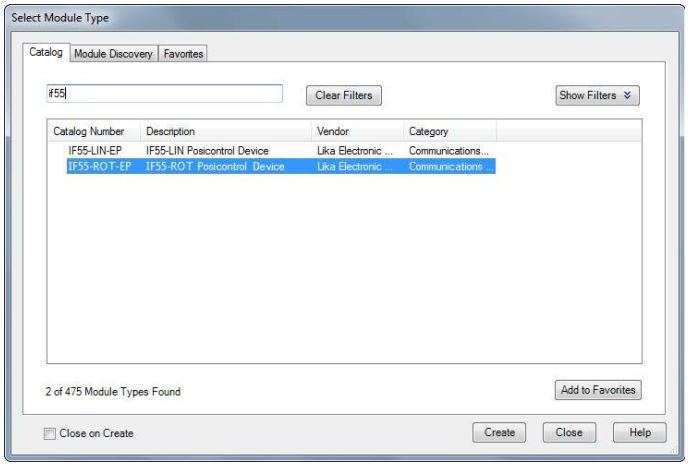


Figure 25 - Select Module Type

Configure the converter module by setting the required parameters **Name** and **Ethernet Address**. Then press the **Change...** button to select the connection type.

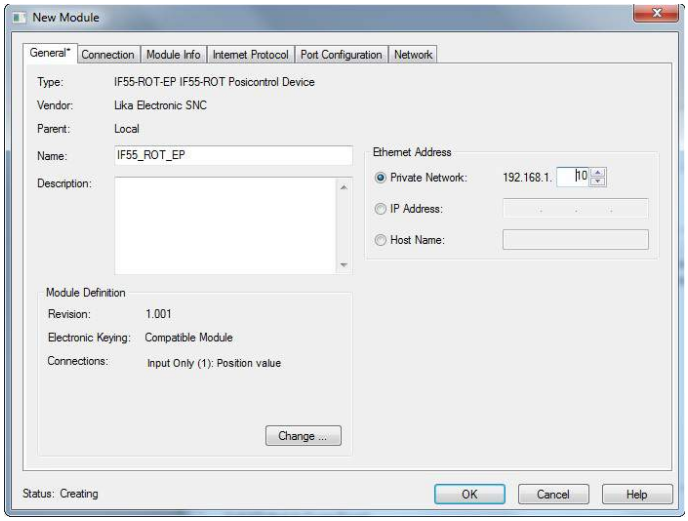


Figure 26 - New module configuration

Select the required connection type and then click **OK**. For more information on the available connection types refer to the "6.12.3.4 Supported connection types" section on page 92.

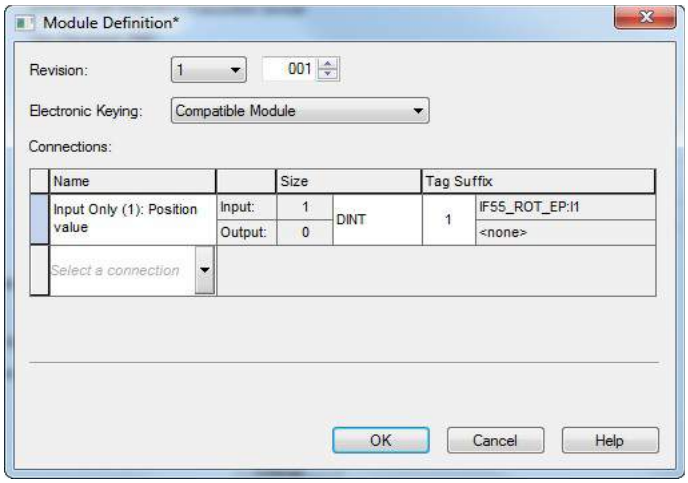


Figure 27 - Select connection type

In the example an Input Only connection has been set: the converter will send the position value (i.e. it produces instances) at switching on.
Set DINT data type in order to display properly the position value.
Press **OK** to finalize and **YES** in the next dialog box.

Close the **New Module** and **Select Module Type** dialog boxes.

5.5.9 Checking the communication

You can check whether the communication between the Controller and the converter is established properly by displaying the converter parameters.
On the **Controller Organizer**, double-click on **Controller Tags** in the **Controller Test_IF55_ROT_EP** folder: the converter parameters will be displayed in the **Monitor Tags** tabbed page. The **Monitor Tags** page displays the tags.

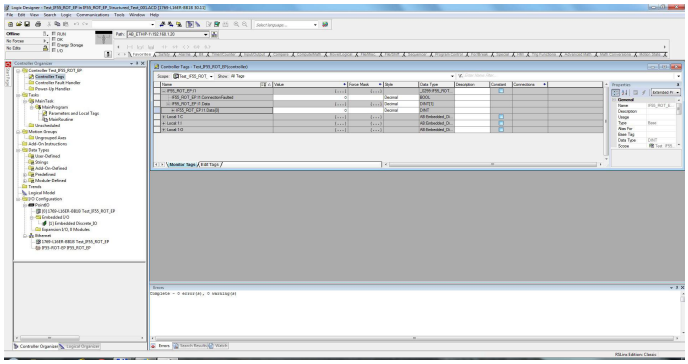


Figure 28 - Monitor Tags

5.5.10 Downloading the configuration to the Controller

To download the configuration to the Controller you must go online first.
Press the drop-down box between the **Offline** and **RUN** items and select **Go Online** in the pull-down menu.

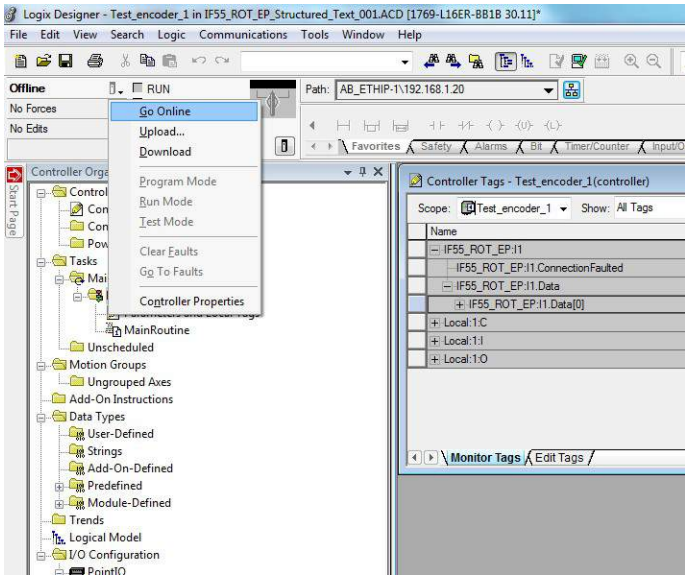


Figure 29 - Going online

Press **Download** in the **Who Active** window to start the download process; the **Download** window will be displayed. Before pressing the **Download** button once more please note the cautionary messages. Click **Download** to continue the download process.
When the download process is completed, the Controller may return to Remote Program mode or ask whether you want to return to Run mode. The message you see is determined by the state the Controller was in at the beginning of the download process.
If everything went well, the NS LED of the converter lights up green (the converter is online) while the MS LED blinks green (the Scanner is in **Idle** state). Refer to the "4.10 Diagnostic LEDs (Figure 4)" section on page 37).

5.5.11 Configuring the converter

Before executing the download process, you can set the configuration parameters of the converter.
On the **Controller Organizer**, right-click **Controller Tags** and choose **Monitor Tags**: the Tag Monitor displays the tags.
A blue arrow indicates that when you change the value, it immediately takes effect.
To see a value in a different style, select the desired style.
To change a value, click the **Value** cell, type the new value, and click **ENTER**.
To expand a tag and show its members, click the **+** sign.

WARNING
Parameters are not saved on the non-volatile memory. At next power-on you are required to send them again.
To save the parameters permanently you can choose among the following methods: by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1 and then back to 0, see on page 135; or by using the **Save Parameters** function in the **Set IF55-ROT-EP Registers** page of the Integrated Web Server, see the "7.6 Setting the attributes" section on page 161.

5.5.12 How to create a sample program and send parameters

Here follows a description of a simple program created using Ladder programming language. The program allows to send a preset "1000" to the connected encoder by means of EtherNet/IP explicit messages with CIP protocol. See also the **64-01-13 Preset Value** attribute on page 113.
Described program can be used as a base to build further programs: the procedure is exactly the same, you have just to change the Attribute value and the type of variable of the parameter.

NOTE

As previously stated, Lika Electronic EtherNet/IP converter documentation is complete with a **sample project** supplied free of charge. This program is designed to make your own project planning, programming, communication and diagnostics with Studio 5000 V30.00 design environment user-friendly and reliable. You can find it in the **SW_IF55_ROT_EP_Example.zip** compressed file. One demo program is available.

- **Test_IF55_ROT_Lika.acd** program allows the user to set and execute the preset (**64-01-13 Preset Value**). It is fully described in the following pages.

The program requires a main routine. Once you create your routines, assign a main routine for the program.

On the **Controller Organizer**, expand the **Tasks**, **MainTask** and **MainProgram** folders and double-click on **MainRoutine**: the **MainProgram – MainRoutine** ladder window appears.

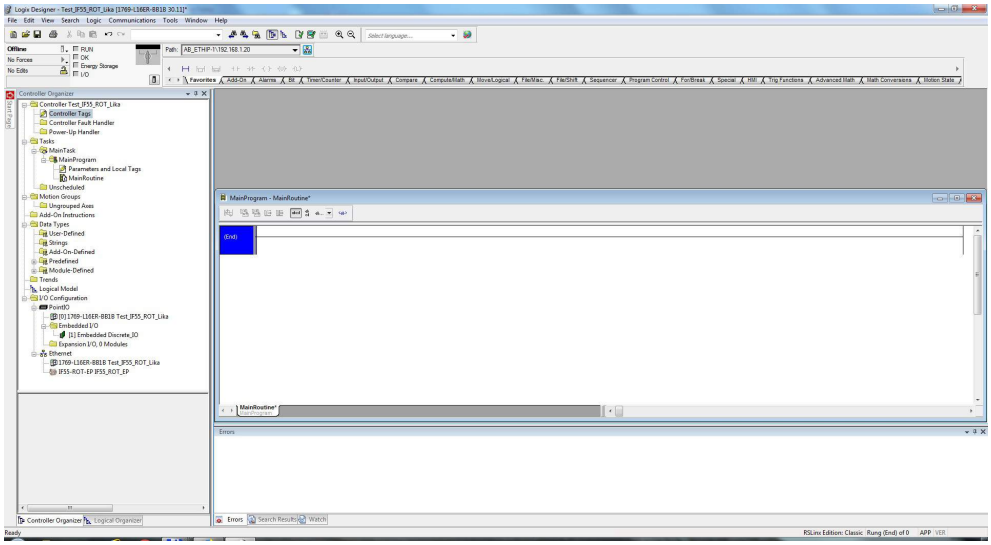


Figure 30 - MainProgram – MainRoutine ladder window

We need to create some tags (variables) that are needful for the program.
On the **Controller Organizer**, right-click on **Controller Tags** and select **New Tag...** from the pull-down menu.

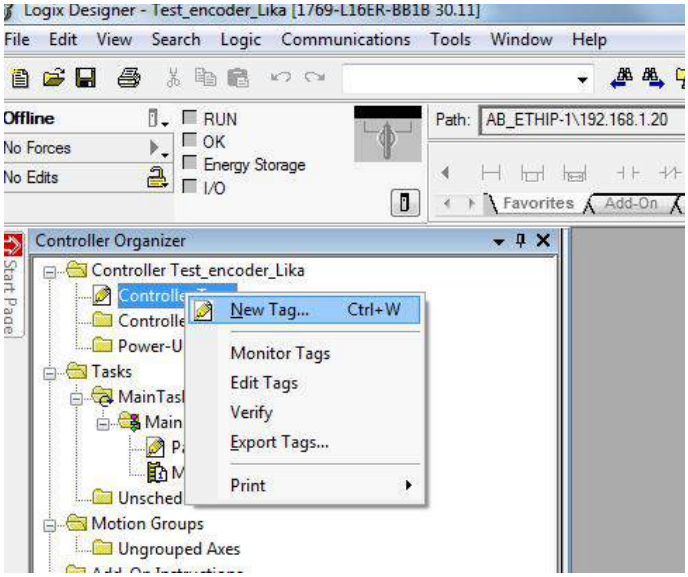
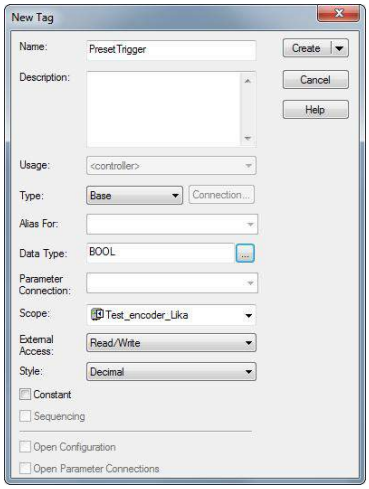


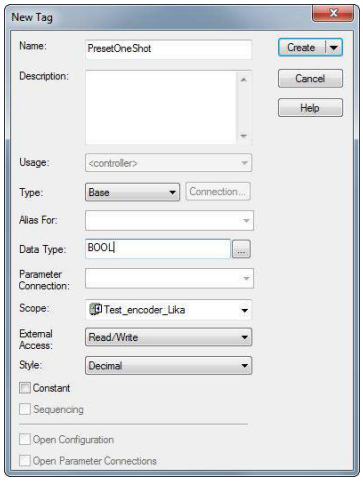
Figure 31 - New Tag

The following tags need to be created:

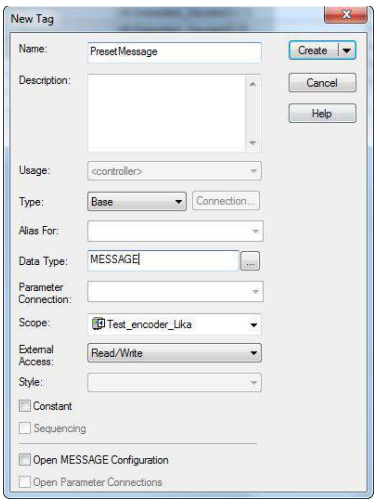
PresetTrigger tag, data type BOOL



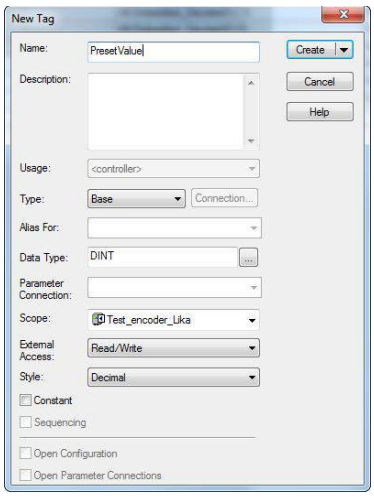
PresetOneShot tag, data type BOOL



PresetMessage tag, data type MESSAGE



PresetValue tag, data type DINT



NOTE
You can type any name for the tags.

Now we need to add ladder logics to the program. To enter logics you must drag buttons from the **Logic Element** toolbar to the desired location. A green dot shows a valid placement location (drop point).

Drag the "**Examine ON (XIC, Examine If Closed)**" logic element onto rung 0 until the green dot appears. Release the mouse button at the location you wish to place your instruction.
Repeat the operation to add a "**One Shot Block (ONS)**" logic element.

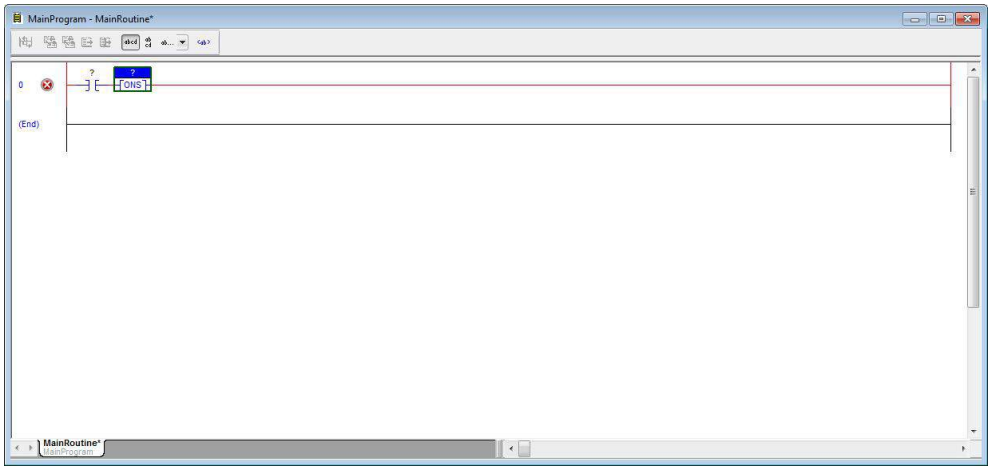


Figure 32 - Dragging logic elements

NOTE
If you place an instruction in the wrong location on a rung, simply click and hold on the instruction and drag it to the correct location.

Double-click the question mark in the "**Examine ON (XIC)**" logic to assign the **PresetTrigger** tag. Choose the tag from the variable list in the drop-down menu.

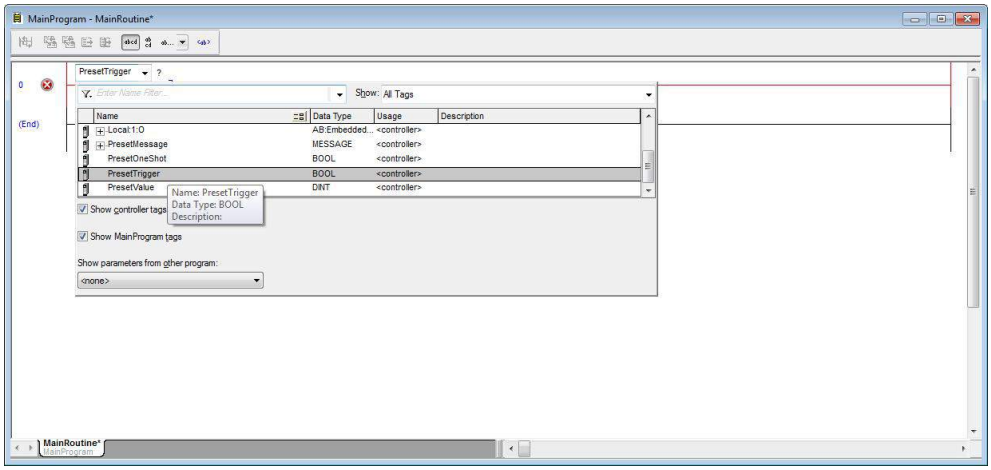


Figure 33 - Assigning tags

Double-click the question mark in the "**One Shot Block (ONS)**" logic to assign the **PresetOneShot** tag. Choose the tag from the variable list in the drop-down menu.

Finally you will get the following situation:

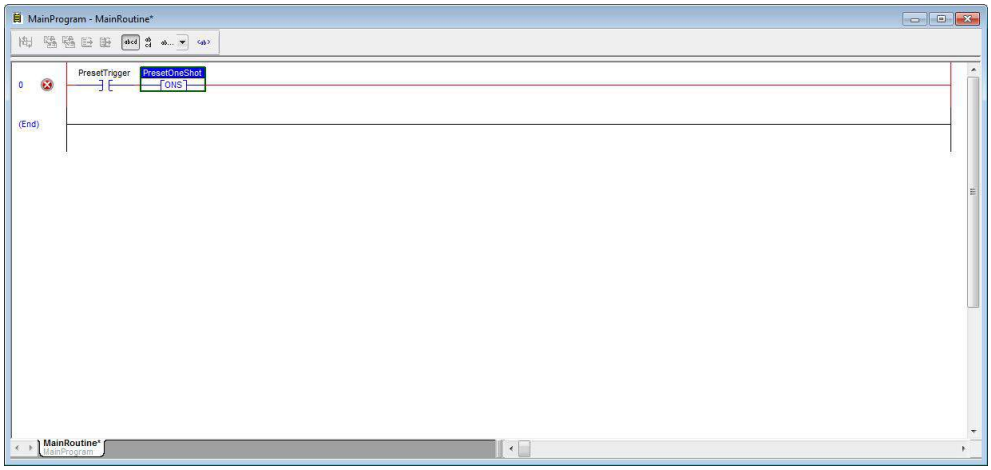


Figure 34 - Tags

Now drag a "**Message (MSG)**" logic from the **Logic Element** toolbar to the desired location. Assign the **PresetMessage** tag as described above.

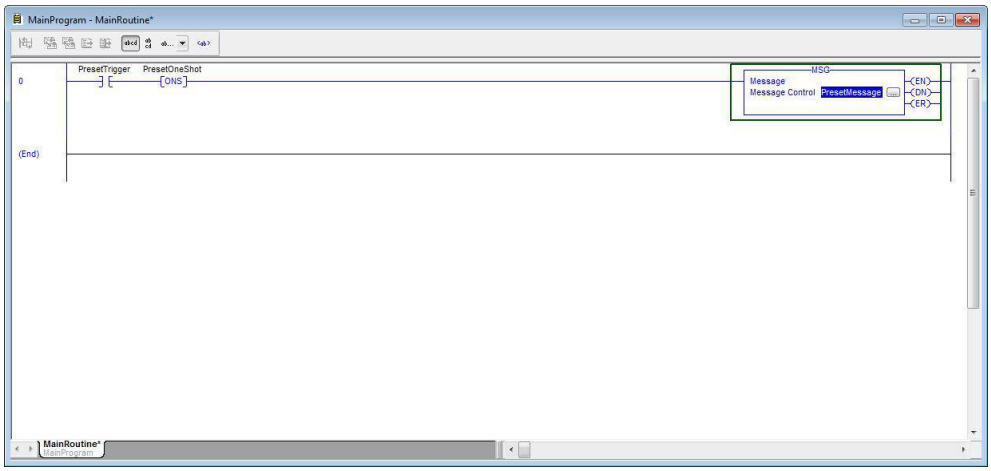
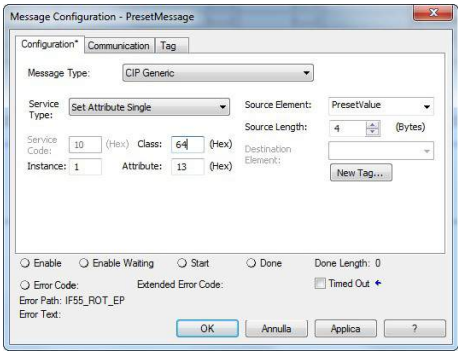


Figure 35 - Message logic element

Configure the message, press the  icon next to the **PresetMessage** label to open the **Message Configuration** dialog box.
Configure both the **Configuration** and the **Communication** tabbed pages as shown in the following screenshots, Figure 36.



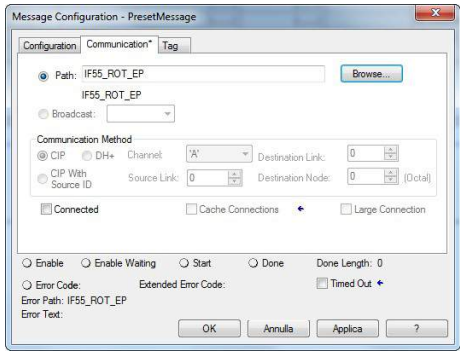


Figure 36 - Message Configuration

See the **64-01-13 Preset Value** attribute in the "6.12.5 Class 64h: Application Object" section on page 113.

On the **Controller Organizer**, double-click on **Controller Tags** in the **Controller Test_IF55_ROT_Lika** folder: the converter parameters will be displayed in the **Monitor Tags** tabbed page. The **Monitor Tags** page displays the tags.

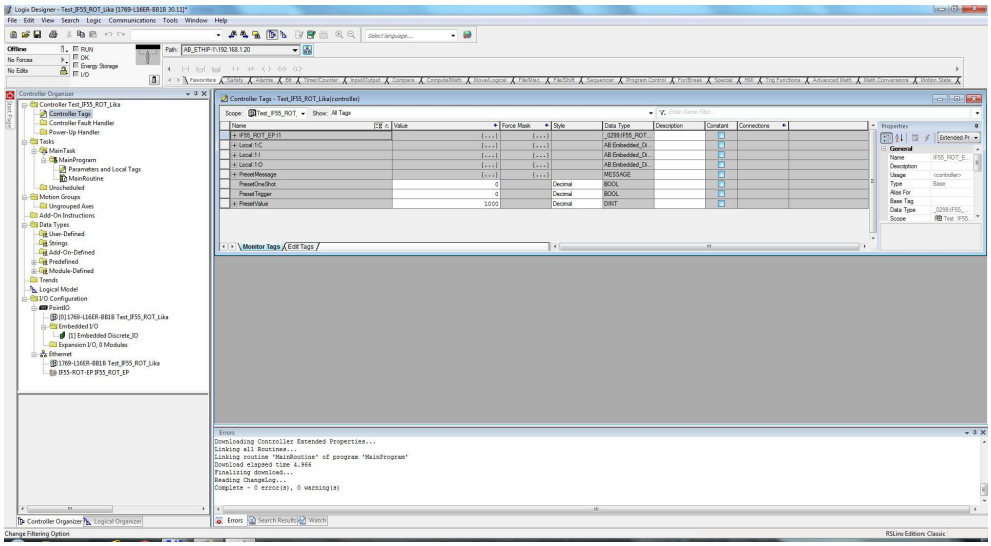


Figure 37 - Setting variables

Set the **PresetOneShot** variable to "0", the **PresetTrigger** variable to "0" and the **PresetValue** variable to "1000", as shown in the screenshot above, Figure 37. To change a value, click the **Value** cell, type the new value, and click **ENTER**. Click the **Style** cell and set the three variables to "Decimal".

Now go online, download data to the Controller and then put the Controller in Run mode.

On the **Controller Organizer**, expand the **Tasks**, **MainTask** and **MainProgram** folders and double-click on **MainRoutine**: the **MainProgram – MainRoutine** ladder window appears.

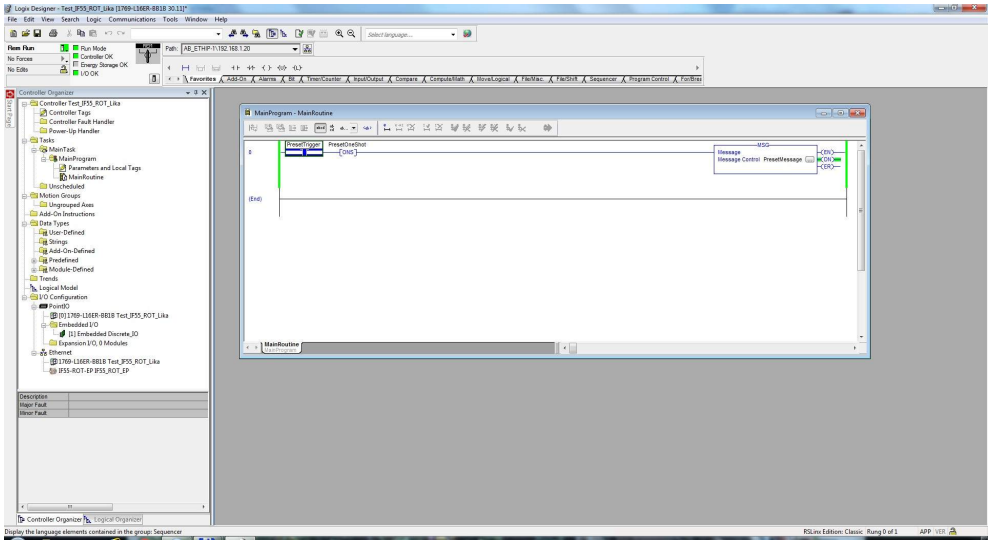


Figure 38 - MainProgram – MainRoutine ladder window

Right-click on the **PresetTrigger** logic element and select **Toggle Bit** from the pull-down menu. The position of the encoder will be preset to the value "1000".

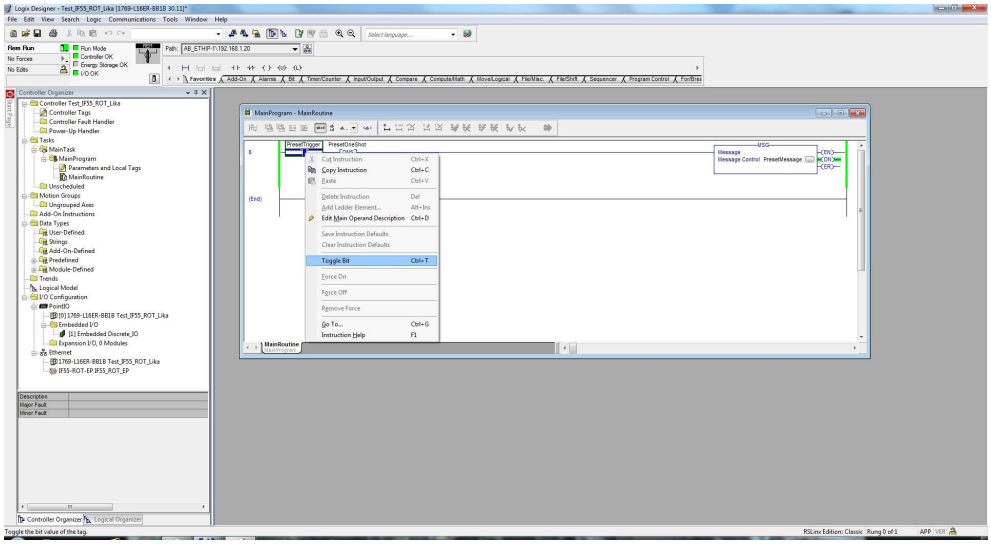


Figure 39 - Setting the Toggle bit

Both the **PresetOneShot** variable and the **PresetTrigger** variable in the **Monitor Tags** tabbed page will be set to "1".

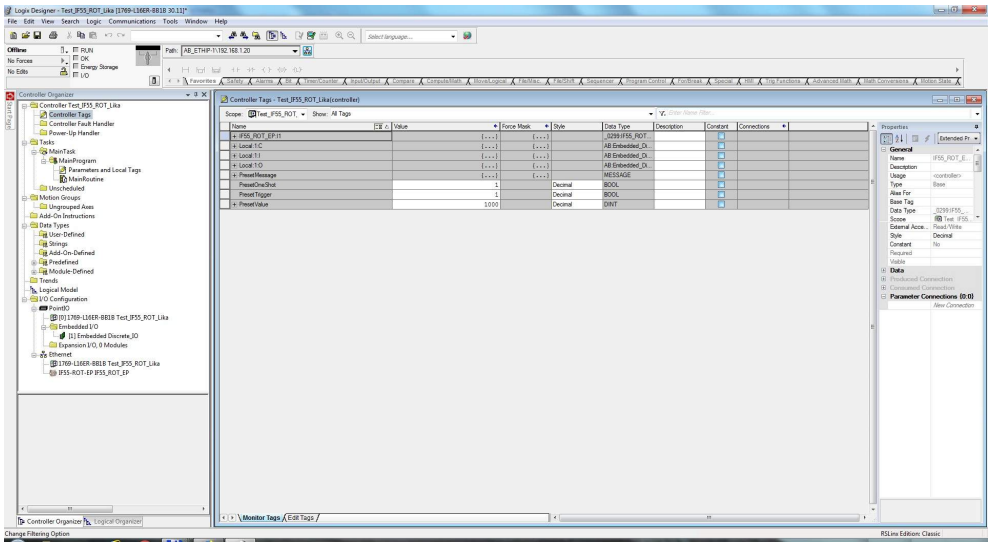


Figure 40 - Monitor Tags

Again right-click on the **PresetTrigger** logic element and select **Toggle Bit** from the pull-down menu to set the variables back to 0.

6 - EtherNet/IP interface

6.1 Introduction to EtherNet/IP

EtherNet/IP is the name given to the Common Industrial Protocol (CIP), as implemented over standard Ethernet (IEEE 802.3 and the TCP/IP protocol suite). EtherNet/IP was introduced in 2001 and today is the most developed, proven and complete industrial Ethernet network solution available for manufacturing automation, with rapid growth as users seek to harness the advantages of open technologies and the Internet. EtherNet/IP is a member of a family of networks that implements CIP at its upper layers.
EtherNet/IP and CIP are managed by ODVA, see later. ODVA publishes "The EtherNet/IP™ Specification" and helps ensure compliance through conformance testing.

6.2 CIP protocol

The Common Industrial Protocol (CIP) is a media independent, connection-based, object-oriented protocol designed for automation applications. It encompasses a comprehensive set of communication services for automation applications: control, safety, synchronization, motion, configuration and information. It allows users to integrate these applications with enterprise-level Ethernet networks and the Internet. CIP provides users with a unified communication architecture throughout the manufacturing enterprise. CIP allows users to benefit from the many advantages of open networks while protecting their existing automation investments when upgrading in the future.
CIP brings:

- Coherent integration of I/O control, device configuration and data collection.
- Seamless flow of information across multiple networks.
- Ability to implement multi-layer networks without the added cost and complexity of bridges and proxies.
- Minimized investment in system engineering, installation and commissioning.

The "IP" in "EtherNet/IP" refers to "Industrial Protocol". EtherNet/IP utilizes CIP over standard IEEE 802.3 and the TCP/IP protocol suite. Since EtherNet/IP uses standard Ethernet and TCP/IP technologies, it allows compatibility and coexistence with other applications and protocols.

6.3 CIP and International Standards

CIP technologies are compliant with a number of fieldbus-related international standards, and are generally referred to as members of CPF 2 (Communication Profile Family 2) of IEC 61158.

- IEC 61158: Specifies various fieldbus protocols for applications ranging from discrete manufacturing to process control. It includes the specifications for CIP, as well as EtherNet/IP and ControlNet-specific protocol elements, as Type 2.

- IEC 61784-1 and IEC 61784-2: Specify general-purpose and real time Ethernet fieldbus Communication Profiles (CPs) (i.e., how to build a specific communication network using IEC 61158 and other standards). ControlNet, EtherNet/IP and DeviceNet are defined respectively as CP 2/1, CP 2/2 (CP 2/2.1 with CIP Sync), and CP 2/3.
- IEC 61784-3: Specifies Functional Safety Communication Profiles (FSCPs), i.e., extensions of fieldbusses for use in safety related applications. CIP Safety is included as FSCP 2/1.
- IEC 61918 & IEC 61784-5: Specify general and fieldbus-specific cabling installation guidelines. IEC 61784-5 includes specific guidelines for ControlNet, EtherNet/IP and DeviceNet.
- IEC 61800-7: Specifies profiles for power drive systems and their mapping to existing communication systems by use of a generic interface. It includes CIP Motion and its mapping on ControlNet, EtherNet/IP and DeviceNet.
- ISO 15745: Defines elements and rules for application integration, including communication network profiles and the communication aspects of device profiles for some fieldbus technologies. EDS files used for device and network integration of DeviceNet, ControlNet or EtherNet/IP applications are compliant with the relevant parts of ISO 15745 (respectively Parts 2, 3 and 4).

Also:

- The lower layers of EtherNet/IP are based on the various RFC Internet standards for the TCP/UDP/IP suite, on the IEEE 802.3 and ISO Ethernet standards (ISO/IEC 8802-3), without modification or extension.
- CIP Safety (on EtherNet/IP) has been certified for use in applications in systems needing to meet the requirements of IEC 61508 up to and including SIL3.

6.4 EtherNet/IP adaptation to CIP

EtherNet/IP, like other CIP Networks, follows the Open Systems Interconnection (OSI) model, which defines a framework for implementing network protocols in seven layers: physical, data link, network, transport, session, presentation and application. Networks that follow this model define a complete suite of network functionality from the physical implementation through the application or user interface layer. As with all CIP Networks, EtherNet/IP implements CIP at the Session layer and above and adapts CIP to the specific EtherNet/IP technology at the Transport layer and below. This network architecture is shown in Figure 41.
Ethernet has the unique characteristic of being a network with an active infrastructure. Therefore, unlike typical device or control level networks—which generally have a passive infrastructure that limits the number of devices that can be connected and the way they can be connected—the EtherNet/IP network infrastructure can accommodate a virtually unlimited number of point-to-point nodes, providing users with unsurpassed flexibility in designing networks that accommodate their current requirements while enabling easy, cost-effective expansion in the future.

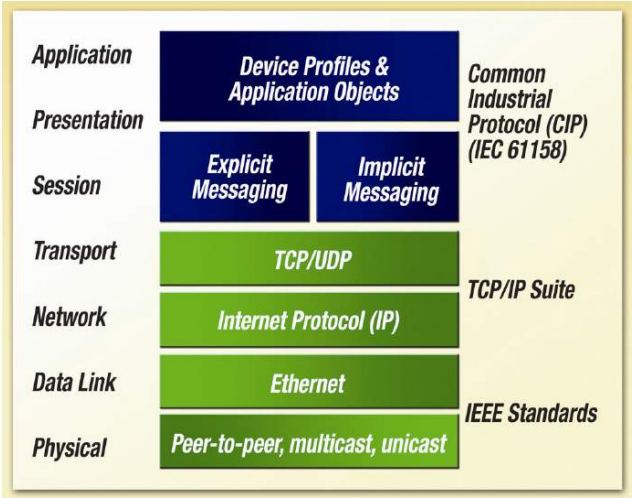


Figure 41 - EtherNet/IP adaptation to CIP

To further decrease complexity, EtherNet/IP systems require only a single point of connection for both configuration and control, because EtherNet/IP supports both I/O (or implicit) messages—those that typically contain time-critical control data—and explicit messages—those in which the data field carries both protocol information and instructions for service performance (see the "6.9.4 Types of EtherNet/IP communications" section on page 82). And, as a producer-consumer network that supports multiple communication hierarchies and message prioritization, EtherNet/IP provides more efficient use of bandwidth than a device network based on a source-destination model. EtherNet/IP systems can be configured to operate either in a Master/Slave or distributed control architecture using peer-to-peer communication.

6.5 The Physical Layer

EtherNet/IP uses standard IEEE 802.3 technology at the Physical and Data Link Layers. This standard provides a specification for physical media, defines a simple frame format for moving packets of data between devices and supplies a set of rules for determining how network devices respond when two devices attempt to use a data channel simultaneously. This is known as CSMA/CD (Carrier Sense Multiple Access/Collision Detection).
As a network with an active infrastructure, EtherNet/IP is typically configured using a series of network segments constructed of point-to-point connections in a star configuration. The core of this network topology is an interconnection of Ethernet Layer 2 and Layer 3 switches that can accommodate an unlimited number of point-to-point nodes.

6.6 The Data Link Layer

IEEE's 802.3 specification is also the standard used for transmitting packets of data from device to device on the EtherNet/IP Data Link Layer. Ethernet employs a CSMA/CD media access mechanism that determines how networked devices

share a common bus (i.e., cable), and how they detect and respond to data collisions.
Originally, Ethernet worked in a half-duplex mode of operation, meaning that a node could send or receive data, but it could not do both at the same time. This caused data traffic jams, which are unacceptable in time-critical control applications. With full-duplex Ethernet, networked devices can both send and receive packets of Ethernet data at the same time. This is one of several advances in Ethernet technology that has increased its level of determinism to the point where Ethernet can be used in an ever-increasing number of manufacturing applications.
The Media Access Control (MAC) protocol of the IEEE 802.3 specification is what actually allows devices to "talk" on the Ethernet network. Each device has a unique MAC address comprised of a 6-byte number that is regulated by IEEE and the product manufacturer to maintain uniqueness (refer also to the "5.4 MAC address" section on page 51). This MAC address is used in the source address (SA) field of the frame to indicate what node sent the frame, and it is used in the destination address (DA) field to indicate the destination of the frame. Setting the first bit to a "1" in the DA field indicates a packet of data for multiple destinations, and enables an Ethernet node to transmit a single data packet to broadcast to the various destinations.
A single frame of industrial EtherNet/IP can contain up to 1,500 bytes of data, depending on the application requirements. The combination of real-time control with high-data capacity makes industrial Ethernet increasingly attractive, as more intelligence is embedded into smaller and less-expensive devices.

6.7 Ethernet data packets

Ethernet data packets are sent in the format shown in Figure 42.

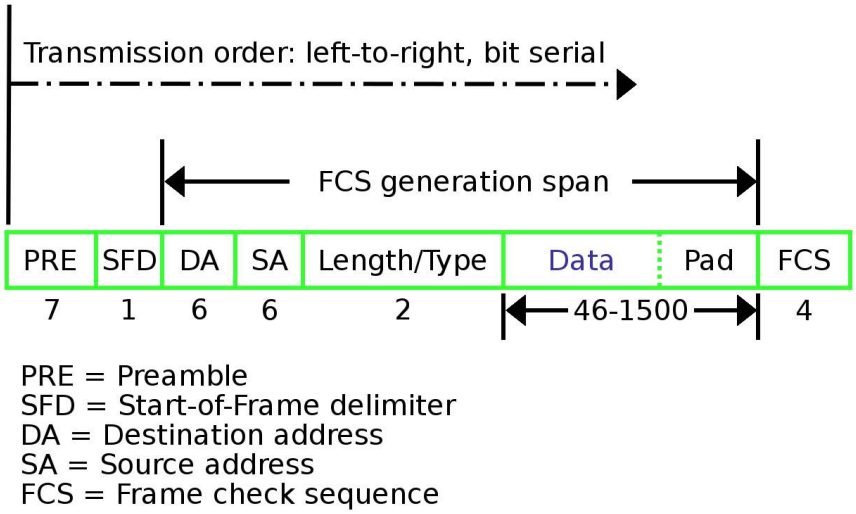


Figure 42 - Typical layout of an Ethernet Data Packet

This data format is used to implement the **Media Access Control (MAC)** protocol that allows a device to "talk" on the Ethernet network. Each MAC

device has a unique **Source Address (SA)** comprised of a 6-byte number (48 bits or 12 hexadecimal digits) that was assigned to it at the time of manufacture. The **Destination Address (DA)** is the target MAC address for which the packet of data is intended. Setting the first bit to a "1" in the DA field, indicates a packet of data for multiple destinations. This enables an Ethernet device to transmit one packet that can be received by multiple other devices.
There are a number of different types of Ethernet packets that can be sent and received on an Ethernet network. Some of these protocols are Novell's IPX/SPX, DECNET, UDP, TCP/IP, FTP, TELNET, and so on. All of these unique protocols use the MAC to do the physical sending and receiving of data packets. However, by defining how the "DATA" portion of the data packet is organized, different protocols and functions are created.

6.8 The Network and Transport Layers

At the Network and Transport Layers, EtherNet/IP utilizes the Internet standard known as the Transmission Control Protocol/Internet Protocol (TCP/IP) Suite to send messages between one or more devices. TCP/IP provides the necessary communication protocol features needed to implement fully functional networks (i.e., an addressing scheme and mechanisms for establishing a connection with a device and exchanging data) that the IEEE specification in and of itself lacks.
Also, at these layers, the standard CIP messages used by all CIP Networks are encapsulated. TCP/IP encapsulation allows a node on the network to embed a message as the data portion in an Ethernet message. The node then sends the message—TCP/IP protocol with the message inside—to an Ethernet communication chip (the Data Link Layer). By using TCP/IP, EtherNet/IP is able to send **explicit messages**, which are used to perform Client-Server type transactions between nodes.

The TCP/IP Suite consists of the following:

- The TCP portion of the TCP/IP protocol is a connection-oriented, unicast transport mechanism that provides data flow control, fragmentation reassembly and message acknowledgments. Nodes must interpret each message, execute the requested task and generate responses. Since TCP is ideal for the reliable transmission of large quantities of data, EtherNet/IP uses TCP/IP to encapsulate CIP explicit messages, which are generally used to transmit configuration, diagnostic and event data.
- The IP portion of the TCP/IP protocol is the mechanism that enables packet routing through multiple possible paths. The ability to send messages to their destinations even when the primary path is disrupted is the basis of the Internet. This same type of routing is used in industrial networks to maintain proper separation of control elements and other factory infrastructure through the use of managed switches and Layer 3 routers. All devices and infrastructure components with added diagnostic capabilities (managed switches and routers) on an industrial Ethernet-based system must be assigned an IP address. This is most commonly identified by the four-byte address listed in the "network properties" on personal computers that use TCP/IP as their Ethernet

network connection (e.g., 192.168.1.10). IP addresses must be unique on a given network (see also the "4.9 EtherNet/IP Node ID" section on page 34).

For real-time messaging, EtherNet/IP also employs UDP over IP, which allows messages to be multicast to a group of destination addresses. This is how CIP I/O data transfers (**implicit messaging**, see the "6.9.4 Types of EtherNet/IP communications" section later) are sent on EtherNet/IP. With implicit messaging, the data field contains no protocol information, only real-time I/O data. Since the meaning of the data is pre-defined at the time the connection is established, processing time is minimized during runtime. UDP is connectionless and makes no guarantee that data will get from one device to another; however, UDP messages are smaller and can be processed more quickly than explicit messages. As a result, EtherNet/IP uses UDP/IP to transport I/O messages that typically contain time-critical control data. The CIP Connection mechanism provides timeout mechanisms that can detect data delivery problems, a capability that is essential for reliable control system performance.

6.9 Upper Layers: Objects, Services, and Application Data

6.9.1 EtherNet/IP services

The CIP application layer defines a set of **application objects** and **device profiles** that define common interfaces and behaviors. In addition, CIP communication services enable end-to-end communication between devices on the different CIP networks. EtherNet/IP maps the CIP communication services to Ethernet and TCP/IP, enabling multi-vendor interoperability between devices on Ethernet as well as with the other CIP networks.

6.9.2 Simplified EtherNet/IP Object Model Overview

Within the CIP application layer, devices are represented using an object model (Figure 43). **Application objects** define how device data is represented and accessed in a common way. **Network-specific objects** define how parameters such as IP addresses are configured and EtherNet/IP specific functions.
Communication objects and services provide the means to establish communication associations and access device data and services over the network.

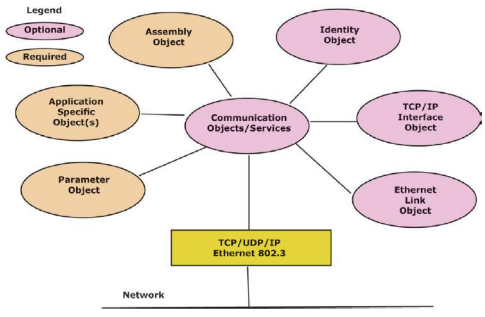


Figure 43 - EtherNet/IP Object Model

6.9.3 Exposing Application Data with CIP

Objects within a device are groups of related data and behavior associated with this data. CIP requires certain objects to describe a device, how it functions, communicates and its unique identity. The **Identity Object** (see on page 87), for example, contains identity data values called **attributes** that are used to store the identity information of a device. Attributes for the Identity Object include the Vendor ID, Device Type, device serial number and other identity data. CIP does not specify how object data is implemented, rather, which data values or attributes must be supported and made available to other CIP devices.

There are three types of objects defined by CIP:

- **Required Objects** must be included in all CIP devices. These objects include the Identity Object (page 87), the Message Router Object (page 91) and network-specific objects such as TCP/IP Interface Object (page 137) and Ethernet Link Object (page 142) for EtherNet/IP protocol.
- **Application Objects** describe how data is encapsulated by a device. These objects are specific to the Device Type and function. For example, an input device would have an input object with attributes that describe the value and fault status of a particular input point. See Application Object (page 97).
- **Vendor-specific Objects** describe services that are specific to a particular vendor; they are optional and not described in a predefined Device Profile.

Addressing data within a CIP device utilizes the same object-oriented view. A **class** (of objects) is a set of objects that represent the same type of system component (Figure 44). Sometimes it is necessary to have more than one 'copy' of an object, called **object instances**, within a device. This set of objects is called an **object class**. Each instance of the object class will have the same set of attributes, but will have a unique set of values. An object instance or an object class has **attributes**, providing services and implementing behavior.

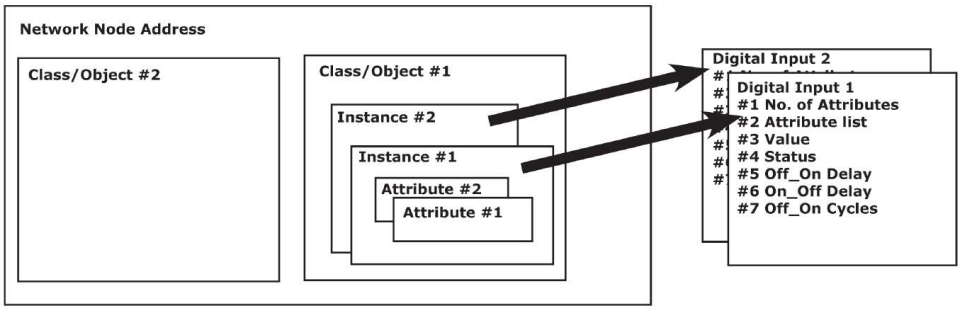


Figure 44 - CIP Object-oriented view of application data

The following Object Modeling related terms are used when describing CIP services and protocol.

- **Object** – An abstract representation of a particular component within a product.

- **Class** – A set of objects that all represent the same kind of system component. A class is a generalization of an object. All objects in a class are identical in form and behavior, but may contain different attribute values.
- **Instance** – A specific and real (physical) occurrence of an object. For example: New Zealand is an instance of the object class Country. The terms Object, Instance, and Object Instance all refer to a specific Instance.
- **Attribute** – A description of an externally visible characteristic or feature of an object. Typically, attributes provide status information or govern the operation of an Object. For example: the ASCII name of an object; and the repetition rate of a cyclic object.
- **Instantiate** - To create an instance of an object with all instance attributes initialized to zero unless default values are specified in the object definition.
- **Behavior** – A specification of how an object acts. Actions result from different events the object detects, such as receiving service requests, detecting internal faults or elapsing timers.
- **Service** – A function supported by an object and/or object class. CIP defines a set of common services and provides for the definition of Object Class and/or Vendor Specific services.
- **Communication Objects** - A reference to the Object Classes that manage and provide the runtime exchange of implicit (I/O) and explicit messages.
- **Application Objects** - A reference to multiple Object Classes that implement product-specific features.

Accessing data within a device using a non-time critical message (an explicit message – see "6.9.4 Types of EtherNet/IP communications" section on page 82) typically contains the following address information:

- Device network address
- Class ID
- Instance ID
- Attribute ID
- Service code (describing the action/service required)

The Class/Instance/Attribute ID form of addressing is also used in Electronic Data Sheets (EDS) to identify configurable parameters within a device.
In addition to specifying how device data is represented, CIP also specifies methods by which I/O data can be accessed, using triggers, such as cyclic or change-of-state. Vendors can also describe how data from different objects can be combined in an I/O or configuration message using the Assembly Object, refer to the "6.12.3 Class 04h: Assembly Object" section on page 92.

6.9.4 Types of EtherNet/IP communications

EtherNet/IP defines two primary types of communications: **explicit** and **implicit**.

CIP Message Type	CIP Communication Relationship	Transport Protocol	Communication Type	Typical Use	Example
Explicit	Connected or Unconnected	TCP/IP	Request/reply transactions	Non time-critical information data	Read/Write configuration parameters
Implicit	Connected	UDP/IP	I/O data transfers	Real-time I/O data	Real-time control data from a remote I/O device

- **Explicit Messaging** in general has a request/reply (or Client/Server) nature. This type of communication is **used for non-real-time data**, normally for information. Explicit messages include a description of their meaning (expressed explicitly), so the transmission is less efficient, but very flexible. It may be used by an HMI to collect data, or by a device programming tool. In CIP terms, with Explicit Messaging you request a service of a particular object, e.g., a read or a write service. For EtherNet/IP, Explicit Messaging uses TCP. Explicit Messaging can be done with or without prior establishment of a CIP connection.
- **Implicit Messaging** is also often referred to as **"I/O" and is time-critical** in nature. Typically this type of communication is used for **real-time data exchange**, where speed and low latency are important. Implicit messages include very little information about their meaning, so the transmission is more efficient, but less flexible than explicit. The interpretation of the transmitted data is fast. With Implicit Messaging you establish an association (a "CIP connection") between two devices and produce the Implicit Messages according to a predetermined trigger mechanism, typically at a specified packet rate. The devices both know and agree on the data formats they will use (i.e., the format is "implied"). For EtherNet/IP, Implicit Messaging uses UDP and can be multicast or unicast.

Connections are established using the ForwardOpen Request service of the Connection Manager Object, see the "6.12.4 Class 06h: Connection Manager Object" section on page 96. The ForwardOpen Request contains all of the connection parameters, including transport class, production trigger, timing information, electronic key and connection IDs. Connection clean-up takes place when a ForwardClose Request service request is issued or when either connection end point times out.
Implicit messaging can make use of the CIP Producer/Consumer communication model. With **Producer/Consumer**, the producing device transmits data once, regardless of the number of consumers. All interested consuming devices receive the same data. For EtherNet/IP the produced data is identified by the IP multicast address and the CIP Connection ID. The Producer/Consumer model

leads to greater network efficiency when multiple consumers need to receive the same data from a producer. For I/O connections, once the connection is established there is no request/response, the data with the ConnectionID is just produced and consumed at intervals determined by the Production Trigger which was specified at connection establishment. Triggers can be Cyclic (most common), Change of State (CoS) or Application.

6.9.5 Types of EtherNet/IP devices

Several device classifications, based on their general behavior and types of EtherNet/IP communications they support, have been defined:

- **Explicit Message Server**: An explicit message server responds to request/response oriented communications initiated by explicit message clients. An example of an explicit message server is a bar code reader.
- **Explicit Message Client**: An explicit message client initiates request/response oriented communications with other devices. Message rates and latency requirements are typically not too demanding. Examples of explicit message clients are HMI devices, programming tools, or PC or Linux based applications that gather data from control devices.
- **I/O Adapter**: An I/O adapter receives implicit communication connection requests from an I/O scanner then produces its I/O data at the requested rate. An I/O adapter is also an explicit message server. An I/O adapter can be a simple digital input device, or something more complex such as a modular pneumatic valve system.
- **I/O Scanner**: An I/O scanner initiates implicit communications with I/O adapter devices. A scanner is typically the most complex type of EtherNet/IP device, as it must deal with issues such as configuration of which connections to make, and how to configure the adapter device. Scanners also typically support initiating explicit messages. A programmable controller is an example of an I/O scanner.

6.10 ODVA

ODVA is an international association comprising members from the world's leading automation companies. Collectively, ODVA and its members support network technologies based on the Common Industrial Protocol (CIP™). These currently include DeviceNet™, EtherNet/IP™, CompoNet™, and ControlNet™, along with the major extensions to CIP – CIP Safety™, CIP Sync™ and CIP Motion™. ODVA manages the development of these open technologies, and assists manufacturers and users of CIP Networks through its activities in standards development, certification, vendor education and industry awareness.

For further information on ODVA, see the ODVA website: www.odva.org.

6.11 EDS file

The functionality of an EtherNet/IP device is always described in an EDS file (Electronic Data Sheet file). The Electronic Data Sheet File provides information

about the device basic communication and functional properties. It must be installed in the Controller.

Lika Electronic's EtherNet/IP converters for SSI rotary and linear encoders are supplied with their own EDS file. Please note that the rotary encoder converters and the linear encoder converters have different EDS files. Files for rotary encoders are marked with ROT- in the file name; while files for linear encoders are marked with LIN- in the file name.

The names of the files are:

- **IF55_ROT_EP_Hx_Sx.eds** converters for rotary encoders
- **IF55_LIN_EP_Hx_Sx.eds** converters for linear encoders

where:

- "IF55" is the converter series;
- "ROT" indicates that it is designed to interface SSI rotary encoders (while "LIN" type converters are designed to interface SSI linear encoders);
- "EP" is the Lika code that identifies the EtherNet/IP protocol;
- "Hx" is the hardware version of the converter;
- "Sx" is the software version of the converter.

The version of the EDS file is reported under the Version item inside the file.
EDS files can be paired with the **IF55_EP.ico** picture file available inside the file folder (the picture is also integrated into the EDS file).

Follow the path **www.lika.biz > DISPLAYS & INTERFACES > SIGNAL CONVERTERS & INTERFACES (POSICONTROL) > IF55** to download the EDS files from Lika's corporate web site.

6.12 Object Library

As previously stated, object modeling is used to represent the network visible behavior of devices (i.e. the converter). Devices are modeled as a collection of objects. Each class of objects is a collection of related services, attributes and behaviors. Services are the procedures that an object performs. Attributes are characteristics of objects represented by values, which can vary. An object's behavior is an indication of how the object responds to particular events. For more information refer to the "6.9.3 Exposing Application Data with CIP" section on page 80.
This section contains the description of the objects specific to Lika converters, including services and attributes.

In the following pages the Class Attributes are listed and described as follows:

Class-Attribute ID Attribute name
[Data type, Access Rule, NV]

While the Instance Attributes are listed and described as follows:
Class-Instance-Attribute ID Attribute name
[Data type, Access Rule, NV]

- Class, instance and attribute are expressed in hexadecimal notation.
- Data types are as shown in the following table:

Data type	Code	Name	Range
BOOL	C1h	Boolean	0 (FALSE) and 1 (TRUE)
SINT	C2h	Signed 8-bit integer	-128 to 127
INT	C3h	Signed 16-bit integer	-32,768 to 32,767
DINT	C4h	Signed 32-bit integer	-2^{31} to $2^{31}-1$
LINT	C5h	Signed 64-bit integer	-2^{63} to $2^{63}-1$
USINT	C6h	Unsigned 8-bit integer	0 to 255
UINT	C7h	Unsigned 16-bit integer	0 to 65,535
UDINT	C8h	Unsigned 32-bit integer	0 to $2^{31}-1$
ULINT	C9h	Unsigned 64-bit integer	0 to $2^{63}-1$
STRING	D0h	Character string	1 byte per character
BYTE	D1h	Bit string – 8 bits	$2\#b_{N-1}b_{N-2}...b_2b_1b_0$, where N is the number of bits in the bit string, b_{N-1} is the "most significant bit", and b_0 is the "least significant bit"
WORD	D2h	Bit string - 16 bits	
SHORT_STRING	DAh	Character string	1 byte per character, 1 byte length indicator
ENGUNIT	DDh	Engineering unit	0 to 65,535

- Access rule can be:

Get (Gettable): the same as "ro" = read only access. The attribute can be accessed by at least one of the get services.

Set (Settable): the same as "rw" = read and write access. The attribute shall be accessed by at least one of the set services. Settable attributes, unless otherwise specified by the object definition, shall also be accessed by get services.

- NV / V

It indicates whether an attribute value is maintained through power cycles. An entry of 'NV' indicates value shall be saved, 'V' means not saved.

- Default, Min. and Max. values

Default, Min. and Max. values are expressed in hexadecimal notation, unless otherwise indicated.

NOTE

All data bytes are sent from least significant byte (LSB) to most significant byte (MSB).

NOTE

In the following pages the attributes and parameters that are specific to converters for rotary encoders are marked with an R letter in brackets, for example **64-01-10 Measuring Units per Span (R)**; the attributes and parameters that are specific to converters for linear encoders are marked with an L letter in brackets, for example **64-01-10 Position Step Setting (L)**.

6.12.1 Class 01h: Identity Object

Class Code	Object Class	Access	Nr. of Instances
01h	Identity Object	Get	1

The Identity Object provides identification of and general information about the converter (e.g. Vendor ID, device type, product code, etc.). Instance 1, which is the only mandatory instance, describes the whole product. It is used by applications to determine what nodes are on the network and to match an EDS file with a product on the network.

6.12.1.1 Supported Class Services

The supported **Class Services** of the Identity Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.1.2 Class Attributes

01-01 Revision
[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0001h.
Default = 0001h

01-02 Max Instance
[UINT, Get, NV]
The largest instance number of a created object in this class.
Default = 0001h

01-03 Number of Instances
[UINT, Get, NV]
The number of object instances in this class.
Default = 0001h

6.12.1.3 Supported Instance Services

The supported **Instance Services** of the Identity Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.
05h = Reset: the following types of reset are defined:

0 = Power Cycle Reset	It emulates a power cycling of the converter.
1 = Return to Factory Defaults Reset	It returns to the factory default configuration of the converter parameters and communication link parameters and emulates a power cycling of the converter.

NOTE
After executing a Return to Factory Defaults reset (type 1), if the DIP A dip switches are all set to 0, the converter restarts using the IP address saved internally. If the DIP A dip switches are set to any value between 1 and 254, then the converter restarts using the address 192.168.1."dip switch setting". For more information refer to page 35.

6.12.1.4 Instance Attributes

01-01-01 Vendor ID
[UINT, Get, NV]
Identification of the vendor by its own number. Lika Vendor ID is 0299h = 665. Vendor IDs are managed by ODVA.
Default = 0299h = Lika Electronic Srl

01-01-02 Device type
[UINT, Get, NV]
The Device Type value is used to identify the device profile that a particular product is using. Device profiles are managed by ODVA and define minimum requirements a device must implement, as well as common options.
Default = 000Ch: Communications Adapter Device.

01-01-03 Product code
[UINT, Get, NV]
Product Code identifies a particular product within the Communications Adapter Device type.
The available product codes are:

- 0020h = IF55-ROT series converter
- 0021h = IF55-LIN series converter

01-01-04 Revision
[USINT/USINT, Get, NV]
The Revision attribute, which consists of Major and Minor Revisions, identifies the Revision of the item the Identity Object is representing. It is displayed as major firmware revision XX.minor firmware revision YY.

MSByte XX	LSByte YY
Major firmware revision	Minor firmware revision

Default = device dependent

01-01-05 Status

[WORD, Get, V]

This attribute represents the current status of the device. Its value changes as the state of the device changes. The Status attribute is a WORD, with the following bit definitions:

Bit(s)	Called	Definition
0	Owned	TRUE indicates the device (or an object within the device) has an owner. Within the Master/Slave paradigm the setting of this bit means that the Predefined Master/Slave Connection Set has been allocated to a Master. Outside the Master/Slave paradigm the meaning of this bit is TBD. 0 = no connection to the Master 1 = connection to the Master established
1	Reserved	Reserved, shall be 0
2	Configured	TRUE indicates the application of the device has been configured to do something different than the "out-of-box" default. This shall not include configuration of the communications. 0 = converter is set to default parameters 1 = converter is not set to default parameters
3	Reserved	Reserved, shall be 0
4-7	Extended device status	Bits are defined as follows: 0000 Unknown 0001 Reserved 0010 At least one faulted I/O connection 0011 No I/O connection established 0100 Non-Volatile Configuration bad (EEPROM) 0101 Major Fault – either bit 10 or bit 11 is TRUE (1) 0110 At least one I/O connection in run mode 0111 At least one I/O connection established, all in idle mode 1000 ... 1111 Reserved
8	Minor recoverable fault	TRUE indicates that the device detected a problem with itself, which is thought to be recoverable. The problem does not cause the device to go into one of the faulted states. Not implemented. For Alarms list refer to page 119
9	Minor unrecoverable fault	TRUE indicates that the device detected a problem with itself, which is thought to be unrecoverable. The problem does not cause the device to go into one of the faulted states. Not implemented. For Alarms list refer to

		page 119
10	Major recoverable fault	TRUE indicates that the device detected a problem with itself, which caused the device to go into the "Major Recoverable Fault" state. Not implemented. For Alarms list refer to page 119
11	Major unrecoverable fault	TRUE indicates that the device detected a problem with itself, which caused the device to go into the "Major Unrecoverable Fault" state. Not implemented. For Alarms list refer to page 119
12 ...15	Reserved	Reserved, shall be 0

For any further information on status instance attribute refer to the publication "The CIP Networks Library. Volume I. Common Industrial Protocol (CIP™)".

01-01-06 Serial number

[UDINT, Get, NV]
This attribute is a number used in conjunction with the Vendor ID to form a unique identifier for each device on any CIP network.
The Serial Number is shown in the following format: YYwwnnnnn.
YY = Year
ww = week
nnnnn = unique number in ascending order assigned by Lika Electronic
Default = device dependent

EXAMPLE
172100123 has to be intended as follows:
17 = Year of production = 2017
21 = Week of production = week 21
00123 = unique number in ascending order assigned by Lika Electronic

01-01-07 Product name

[SHORT_STRING, Get, NV]
This text string represents a short description of the product represented by the Product Code in attribute **01-01-03 Product code**.
Default = "IF55-ROT Posicontrol Device" converter for rotary encoders
"IF55-LIN Posicontrol Device" converter for linear encoders

6.12.2 Class 02h: Message Router Object

Class Code	Object Class	Access	Nr. of Instances
02h	Message Router Object	Get	1

This object provides a messaging connection point through which a Client may address a service to any object class or instance residing in the converter.

In Lika converters it is used internally to direct object requests.

6.12.3 Class 04h: Assembly Object

Class Code	Object Class	Access	Nr. of Instances
04h	Assembly Object	Get	4

The Assembly Object binds attributes of multiple objects, which allows data to or from each object to be sent or received over a single connection. Assembly objects can be used to bind input data or output data. The terms "input" and "output" are defined from the network's point of view. An input will produce data on the network and an output will consume data from the network.
Assembly objects instances are static: assemblies with member lists defined by the open device profile or vendor specific device profile. The Instance number, number of members, and member list are fixed.

6.12.3.1 Supported Class Services

The supported **Class Services** of the Assembly Object are:
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.3.2 Class Attributes

04-01 Revision

[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0002h.
Default = 0002h

04-02 Max Instance

[UINT, Get, NV]
The largest instance number of a created object in this class.
Default = 0096h

6.12.3.3 Supported Instance Services

The supported **Instance Services** of the Assembly Object are:
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.3.4 Supported connection types

Lika EtherNet/IP converters support "Input only" and "Listen Only" connections.

Input Only connection

This type of connection is used to read data from the converter without controlling the outputs. It does not depend on other connections.
Connection point O → T Assembly Object, instance 64h
Connection point T → O Assembly Object, instances 01h, 02h, 03h

T is the Target, i.e. the converter
O is the Origin, i.e. the Master

Listen Only connection
This type of connection requires an Input Only connection in order to exist. If the Input Only connection is closed, the Listen Only connection will be closed as well.
Connection point O → T Assembly Object, instance 65h
Connection point T → O Assembly Object, instances 01h, 02h, 03h
T is the Target, i.e. the converter
O is the Origin, i.e. the Master

Refer also to the "6.12.4 Class 06h: Connection Manager Object" section on page 96.

6.12.3.5 Instance Attributes

The following table identifies the I/O Assembly instances, which are supported by the converter device.

Instance ID	Attribute	Access	Description	Bits	Bytes
01h	03h	Get	64-01-03 Position value (R) & 64-01-03 Position value (L)	32	4
02h	03h	Get	64-01-03 Position value (R), 64-01-03 Position value (L), 64-01-31 Warning Flag, & 64-01-2E Alarm Flag	32 8	5
03h	03h	Get	64-01-03 Position value (R), 64-01-03 Position value (L), & 64-01-18 Velocity Value	32 32	8
6Ah	03h	Set/Get	**Configuration Assembly**	96	12

64-01-03 Position value (R), 64-01-03 Position value (L), 64-01-18 Velocity Value, 64-01-31 Warning Flag, 64-01-2E Alarm Flag, 64-01-0C Direction Counting Toggle (R), 64-01-0C Direction Counting Toggle (L), 64-01-0E Scaling Function Control (R), 64-01-0E Scaling Function Control (L), 64-01-10 Measuring Units per Span (R), 64-01-10 Position Step Setting (L), 64-01-11 Total Measuring Range (R), 64-01-11 Total Measuring Range (L), 64-01-19 Velocity Format (R), and 64-01-19 Velocity Format (L) attributes are fully described in the "6.12.5 Class 64h: Application Object" section on page 97.

6.12.3.6 I/O Assembly Data Attribute Format

The I/O assembly data attributes have the format shown below.

Instance	Byte	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
01h	0	64-01-03 Position value (R) 64-01-03 Position value (L) (low byte)							
	1								
	2								
	3	(high byte)							
02h	0	64-01-03 Position value (R) 64-01-03 Position value (L) (low byte)							
	1								
	2								
	3	(high byte)							
	4							64-01-31 Warning Flag	64-01-2E Alarm Flag
03h	0	64-01-03 Position value (R) 64-01-03 Position value (L) (low byte)							
	1								
	2								
	3	(high byte)							
	4	64-01-18 Velocity Value (low byte)							
	5								
	6								
	7	(high byte)							

6.12.3.7 Configuration Assembly

Instance	Byte	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Attribute ID
6Ah	0	64-01-0C Direction Counting Toggle (R) 64-01-0C Direction Counting Toggle (L)								0Ch
	1	64-01-0E Scaling Function Control (R) 64-01-0E Scaling Function Control (L)								0Eh
	2	64-01-10 Measuring Units per Span (R) (low byte)								10h
	3									

	4			
	5	64-01-10 Position Step Setting (L)	(high byte)	
	6	64-01-11 Total Measuring Range (R) 64-01-11 Total Measuring Range (L)	(low byte)	11h
	7			
	8			
	9		(high byte)	
	10	64-01-19 Velocity Format (R) 64-01-19 Velocity Format (L)	(low byte)	19h
	11		(high byte)	

6.12.4 Class 06h: Connection Manager Object

Class Code	Object Class	Access	Nr. of Instances
06h	Connection Manager Object	Get	1

The Connection Manager Class allocates and manages the internal resources associated to both "I/O Messages" and "Explicit Messaging Connections".

For complete information refer to "THE CIP NETWORKS LIBRARY, Volume 1, Common Industrial Protocol (CIP™), Chapter 3: Communication Object Classes".

6.12.5 Class 64h: Application Object

Class Code	Object Class	Access	Nr. of Instances
64h	Application Object	Set/Get	1

The Communications Adapter device type acts as a gateway from the CIP network to other technologies. Traditionally, a gateway connects to foreign networks (SSI, in the specific case) or backplanes (for example, VME).
This class is meant to describe the attributes used by the device, they are customer-specific. It contains all attributes for acyclic process data and for setting the converter.

6.12.5.1 Supported Class Services

The supported **Class Services** of the Application Object are:

05h = Reset: resets all parameter values to the factory default values (without saving them on flash memory). The following types of reset are defined:

0 = Power Cycle Reset	It emulates a power cycling of the converter.
1 = Return to Factory Defaults Reset	It returns to the factory default configuration of the converter parameters and communication link parameters and emulates a power cycling of the converter.

NOTE
After executing a Return to Factory Defaults reset (type 1), if the DIP A dip switches are all set to 0, the converter restarts using the IP address saved internally. If the DIP A dip switches are set to any value between 1 and 254, then the converter restarts using the address 192.168.1."dip switch setting". For more information refer to page 35.

0Eh = Get_Attribute_Single: used to read connection class attribute value.
15h = Restore: restores all parameter values from flash memory (without saving them).
16h = Save: saves all parameters to non-volatile memory.

6.12.5.2 Class Attributes

64-01 Revision
[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0002h.
Default = 0002h

6.12.5.3 Supported Instance Services

The supported **Instance Services** of the Application Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
10h = Set_Attribute_Single: used to write connection class attribute value.

6.12.5.4 Instance Attributes

NOTE
Please note that in the following pages the attributes specific to the rotary encoder are

64-01-03 Position value (R)

[UDINT, Get, V]
This attribute represents the absolute position detected by the connected encoder. If the scaling function is enabled (see on page 101), the output value is scaled according to the scaling parameters.

NOTE
Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "0h" = disabled, the position value read by the encoder can be processed according to needs, so the user can scale the value, set a preset and change the counting direction. On the contrary, if the **Bypass mode (R)** parameter is set to "1h" = enabled, the information from the encoder is transmitted "as it is" and not processed in any way. The preset, scaling, and counting direction functions -even if set and enabled- are ignored and the **64-01-10 Measuring Units per Span (R)** and **64-01-2B Number of Spans (R)** attributes are used to calculate the position information. If, for example, the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated. As soon as the "Bypass mode" is disabled, the preset, scaling, and counting direction functions -if set and enabled- become active and the **64-01-03 Position value (R)** will be accordingly.

64-01-03 Position value (L)

[UDINT, Get, V]
This attribute represents the absolute position detected by the connected encoder. If the scaling function is enabled (see on page 102), the output value is scaled according to the scaling parameters.

NOTE
Please consider that if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "0h" = disabled, the position value read by the encoder can be processed according to needs, so the

user can scale the value, set a preset and change the counting direction. On the contrary, if the **Bypass mode (L)** parameter is set to "1h" = enabled, the information from the encoder is transmitted "as it is" and not processed in any way. The preset, scaling, and counting direction functions -even if set and enabled- are ignored and the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute are used to calculate the position information. If, for example, the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated. As soon as the "Bypass mode" is disabled, the preset, scaling, and counting direction functions -if set and enabled- become active and the **64-01-03 Position value (L)** will be accordingly.

To convert the read position value into nanometres [nm] (and into micrometres or millimetres or other engineering unit afterwards) you must multiply the read position by the value set next to the **64-01-2A Physical Measuring Step (L)** attribute (if the **64-01-0E Scaling Function Control (L)** attribute is disabled = 00h); otherwise you must multiply the read position by the value set next to the **64-01-10 Position Step Setting (L)** object (if the **64-01-0E Scaling Function Control (L)** is enabled = 01h).

EXAMPLE
We have the following linear encoder: **SMA5-GA-50**.
64-01-0E Scaling Function Control (L) = 00h
64-01-2A Physical Measuring Step (L) = 0000 C350h = 50,000 nm = 0.05 mm
64-01-03 Position value (L) = 0001 1005h = 69,637 dec
Position = **64-01-03 Position value (L)** * **64-01-2A Physical Measuring Step (L)** = 0001 1005h * 0000 C350h = CF88 D090h = 3,481,850,000 nm
3,481,850,000 nm = 3,481,850 µm = 3,481.85 mm

EXAMPLE
We have the following linear encoder: **SMA5-GA-50**.
64-01-0E Scaling Function Control (L) = 01h
64-01-10 Position Step Setting (L) = 0001 86A0h = 100,000 nm = 0.1 mm
64-01-03 Position value (L) = 0000 1760h = 5,984 dec
Position = **64-01-03 Position value (L)** * **64-01-10 Position Step Setting (L)** = 0000 1760h * 0001 86A0h = 23AA DC00h = 598,400,000 nm
598,400,000 nm = 598,400 µm = 598.4 mm

64-01-0B Position Sensor type

[UINT, Get, NV]
This attribute specifies the type of device.
0002h: **multiturn** absolute encoder.
Default = 0002h (min. value 0002h, max. value 0002h)

64-01-0C Direction Counting Toggle (R)

[BOOL, Set, NV]

This attribute defines whether the position value output by the encoder increases (count up information) when the encoder shaft rotates clockwise (0 = CW) or counter-clockwise (1 = CCW). If the attribute is set to 00h, the absolute position value **increases** when the encoder shaft rotates **clockwise**; on the contrary, if the attribute is set to 01h, the absolute position value **increases** when the encoder shaft rotates **counter-clockwise**. CW and CCW rotations are viewed from shaft end.

00h: turning the shaft CW the position will increase;

01h: turning the shaft CCW the position will increase.

WARNING

Changing this value causes also the position calculated by the controller to be necessarily affected. Therefore it is mandatory to execute a new preset and save the attributes after setting this attribute.

NOTE

To know whether the **64-01-0C Direction Counting Toggle (R)** is currently set to 00h = CW or 01h = CCW, you can read the bit 0 **Counting direction (R)** of the **64-01-29 Operating Status (R)** attribute, see on page 116.

NOTE

Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the counting direction function -if set differently from default- is ignored.

Default = 00h (min. value 00h, max. value 01h)

64-01-0C Direction Counting Toggle (L)

[BOOL, Set, NV]

This attribute defines whether the position value output by the encoder increases (count up information) when the encoder moves in the standard direction (it is indicated in the encoder's manual) or when the encoder moves in reverse of the standard direction. If the attribute is set to 00h, the absolute position value **increases** when the encoder moves in the standard direction; on the contrary, if the attribute is set to 01h, the absolute position value **increases** when the encoder moves in the reverse of the standard direction.

For any information on the standard and inverted counting direction please refer to the specific manual of the encoder.

00: moving the sensor in the standard direction the position will increase;

01: moving the sensor in the opposite direction the position will increase.

WARNING
Changing this value causes also the position calculated by the controller to be necessarily affected. Therefore it is mandatory to execute a new preset and save the attributes after setting this attribute.

NOTE
To know whether the **64-01-0C Direction Counting Toggle (L)** is currently set to 00h = standard direction or 01h = reverse direction, you can read the bit 0 **Counting direction (L)** of the **64-01-29 Operating Status (L)** attribute, see on page 117.

NOTE
Please consider that if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the counting direction function -if set differently from default- is ignored.

Default = 00h (min. value 00h, max. value 01h)

64-01-0E Scaling Function Control (R)

[BOOL, Set, NV]
If this attribute is disabled (00h = OFF), the device uses the physical resolution (see the **64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)** attributes) to arrange the absolute position value; if it is enabled (01h = ON, default), the device uses the custom resolution set next to the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes in compliance with the following relation:

$$\text{Transmitted position} = \frac{\text{64-01-10 Measuring Units per Span (R)}}{\text{64-01-2A Physical Resolution Span (R)}} * \text{real position} \leq \text{64-01-11 Total Measuring Range (R)}$$

NOTE
To know whether the **64-01-0E Scaling Function Control (R)** is currently enabled, you can read the bit 1 **Scaling function (R)** of the **64-01-29 Operating Status (R)** attribute, see on page 116.

NOTE
Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the scaling function -even if enabled- is ignored.

WARNING
Every time you enable the scaling function and/or change the scaling values (see the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes), then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

Default = 01h (min. value 00h, max. value 01h)

64-01-0E Scaling Function Control (L)

[BOOL, Set, NV]
If this attribute is disabled (00h = OFF), the device uses the physical resolution and the max. number of physical information to arrange the absolute position information (see the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute; **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes are ignored).
On the contrary, if it is enabled (01h = ON), the custom resolution and the number of information set in the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes are used to calculate the position information.

NOTE
To know whether the **64-01-0E Scaling Function Control (L)** is currently enabled, you can read the bit 1 **Scaling function (L)** of the **64-01-29 Operating Status (L)** attribute, see on page 117.

WARNING
When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), please enter scaled values next to the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes that are consistent with the physical values.

WARNING
When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), a counting error, i.e. a jump in the position count, may occur if the following conditions arise:

- a physical zero setting has been performed in the encoder;
- the **64-01-10 Position Step Setting (L)** attribute value is not a multiple of the physical resolution as set next to the **64-01-2A Physical Measuring Step (L)** attribute;

- the measuring range (**64-01-11 Total Measuring Range (L)** parameter) is not a power of 2 submultiple of the maximum measuring range.

If the above described conditions arise, a counting error may occur when the sensor crosses the physical zero point.
If the scaling function is disabled (**64-01-0E Scaling Function Control (L)** = 00h), the transmitted position values are always consistent.
If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h) yet no physical zero setting has been performed in the linear sensor, the transmitted position values are always consistent.
If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h), the **64-01-10 Position Step Setting (L)** attribute value is a multiple of the physical resolution and the measuring range (**64-01-11 Total Measuring Range (L)** attribute) is a power of 2 submultiple of the maximum measuring range, the transmitted position values are consistent, regardless of the physical zero setting.

The **scaling conversion constant** (**k**) has to be as follows:

$$k = \frac{\text{64-01-2A Physical Measuring Step (L)}}{\text{64-01-10 Position Step Setting (L)}} \leq 1$$

The value in the **64-01-10 Position Step Setting (L)** attribute has to be equal to or greater than the value in the **64-01-2A Physical Measuring Step (L)** attribute.
If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h), the following condition has to be met:

64-01-11 Total Measuring Range (L) ≤ **k** * **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute

NOTE
Please consider that if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the scaling function -even if enabled- is ignored.

WARNING
Every time you enable the scaling function and/or change the scaling values (see the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes), then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

64-01-10 Measuring Units per Span (R)

[UDINT, Set, NV]

WARNING

This attribute is active only if the **64-01-0E Scaling Function Control (R)** attribute is enabled; otherwise it is ignored and the system uses the physical values (**64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)**) to calculate the position information.
Furthermore, if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the scaling function -even if enabled- and this **64-01-10 Measuring Units per Span (R)** attribute are ignored.

This attribute sets the custom number of measuring steps per revolution that are output for the absolute singleturn position value.
If you enter an out-of-range value, the number of measuring units per revolution is forced to the physical singleturn resolution and the **64-01-2F Warnings** attribute signals the error (see the bit 0 **Measuring Units per Span exceeded (R)** in the **64-01-67 Wrong Parameters List (R)** and the LEDs).

To avoid counting errors, check that:

$$\frac{\text{64-01-2A Physical Resolution Span (R)}}{\text{64-01-10 Measuring Units per Span (R)}} = \text{integer value.}$$

Allowed values must be less than or equal to the physical singleturn resolution (**64-01-2A Physical Resolution Span (R)**).

Default = 65,536 (min. = 1, max. = 65,536)

WARNING

When you set a new value next to the **64-01-10 Measuring Units per Span (R)** attribute, please always check also the **64-01-11 Total Measuring Range (R)** attribute value and be sure that the resulting number of revolutions complies with the physical number of revolutions of the device (see the **64-01-2B Number of Spans (R)** attribute).
Let's suppose that the encoder is programmed as follows:
64-01-10 Measuring Units per Span (R): 8,192 cpr
64-01-11 Total Measuring Range (R) = 33 554 432 = 8,192 (cpr) * 4,096 (rev.)
Let's set a new singleturn resolution, for instance: **64-01-10 Measuring Units per Span (R)** = 360.

If we do not change the **64-01-11 Total Measuring Range (R)** value at the same time, we will get the following result:

$$\text{Number of revolutions} = \frac{33\,554\,432\ (\text{64-01-11 Total Measuring Range (R)})}{360\ (\text{64-01-10 Measuring Units per Span (R)})} = 93{,}206.755...$$

As you can see, the encoder is required to carry out more than 93,000 revolutions, this cannot be because, as stated, the hardware number of revolutions can be max. 16,384 (see the **64-01-2B Number of Spans (R)** attribute). When this happens, the **64-01-2F Warnings** attribute signals the error (see also the **64-01-67 Wrong Parameters List (R)** attribute and the LEDs).

WARNING
Every time you change the value in this attribute then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

64-01-10 Position Step Setting (L)

[UDINT, Set, NV]

WARNING
This attribute is active only if the **64-01-0E Scaling Function Control (L)** attribute is enabled; otherwise it is ignored and the system uses the physical values (**64-01-2A Physical Measuring Step (L)** attribute and **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute) to calculate the position information.
Furthermore, if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the scaling function -even if enabled- and this **64-01-10 Position Step Setting (L)** attribute are ignored.

This attribute is used to set a custom resolution (otherwise referred to as measuring step) expressed in nanometers [nm].
The resolution can be defined as the smallest change in the underlying quantity that produces a response in the measurement, the response being the information that is provided to output.
The custom resolution must be grater than or equal to the physical resolution of the connected encoder.
We suggest setting a value that is a multiple of the physical resolution as set next to the **64-01-2A Physical Measuring Step (L)** attribute not to cause a

counting error, i.e. a jump in the position count when the sensor crosses the physical zero point (see the WARNING below).
Default = 10,000 (min. = 1, max. = 1,073,741,823)

WARNING
When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), please enter scaled values next to the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes that are consistent with the physical values.

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
As you can see in the product datasheet, "50" in the order code means a **0.05 mm resolution** = 50,000 nanometres resolution. The user has to confirm this value in the **64-01-2A Physical Measuring Step (L)** attribute; if the **64-01-0E Scaling Function Control (L)** attribute is disabled the system uses the physical resolution to calculate the position information. After enabling the **64-01-0E Scaling Function Control (L)** attribute the system uses the custom resolution set next to the **64-01-10 Position Step Setting (L)** attribute: it must be greater than or equal to 50,000.

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
As you can see in the product datasheet, "100" in the order code means a **0.1 mm resolution** = 100,000 nanometres resolution. The user has to confirm this value in the **64-01-2A Physical Measuring Step (L)** attribute; if the **64-01-0E Scaling Function Control (L)** attribute is disabled the system uses the physical resolution to calculate the position information. After enabling the **64-01-0E Scaling Function Control (L)** attribute the system uses the custom resolution set next to the **64-01-10 Position Step Setting (L)** attribute: it must be greater than or equal to 100,000.

WARNING
When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), a counting error, i.e. a jump in the position count, may occur if the following conditions arise:

- a physical zero setting has been performed in the encoder;
- the **64-01-10 Position Step Setting (L)** attribute value is not a multiple of the physical resolution as set next to the **64-01-2A Physical Measuring Step (L)** attribute;
- the measuring range (**64-01-11 Total Measuring Range (L)** parameter) is not a power of 2 submultiple of the maximum measuring range.

If the above described conditions arise, a counting error may occur when the sensor crosses the physical zero point.
If the scaling function is disabled (**64-01-0E Scaling Function Control (L)** = 00h), the transmitted position values are always consistent.
If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h) yet no physical zero setting has been performed in the linear sensor, the transmitted position values are always consistent.
If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h), the **64-01-10 Position Step Setting (L)** attribute value is a multiple of the physical resolution and the measuring range (**64-01-11 Total Measuring Range (L)** attribute) is a power of 2 submultiple of the maximum measuring range, the transmitted position values are consistent, regardless of the physical zero setting.

WARNING
Every time you change the value in this attribute then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

EXAMPLE
The main and default features of the **SMAX-BG-100** linear encoder are as follows:

- **Default resolution** = 0.1 mm = 100,000 nm
- **MTAX max. measuring length** = 600 mm
- **Max. number of information** = 6,000 (13 bits)

As stated, the max. number of information provided to output is calculated as follows:

$$\textbf{Number of information} = \frac{\textbf{Max. measuring length}}{\textbf{Resolution}}$$

Thus, in a default configuration the number of information is:

$$\textbf{Number of information} = \frac{\textbf{Max. measuring length}}{\textbf{Resolution}} = \frac{600}{0.1} = \textbf{6000}$$

Let's assume that you need **2,000 information** to be provided to output for the max. measuring length. It follows that you need to calculate and then set a custom resolution.

The resolution value results from the following calculation:

$$\text{Resolution} = \frac{\text{Max. measuring length}}{\text{Number of information}}$$

Thus, in the example the resolution will be:

$$\text{Resolution} = \frac{\text{Max. measuring length}}{\text{Number of information}} = \frac{600}{2{,}000} = 0.3$$

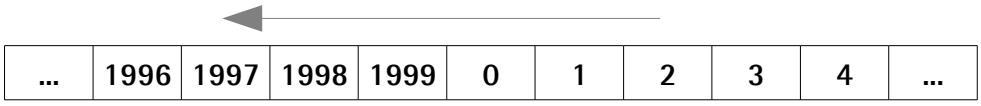
As the value next to the **64-01-10 Position Step Setting (L)** parameter has to be expressed in nanometres, then you have to enter the value **300,000**.

The complete programming sequence will be:

1. Enable the **64-01-0E Scaling Function Control (L)** = 01h
2. Set the custom resolution: **64-01-10 Position Step Setting (L)** = 300,000
3. Set the custom number of information: **64-01-11 Total Measuring Range (L)** = 2,000
4. Save the new values (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

NOTE

Please note that, if you set a preset along the path, when the encoder moves back and cross the zero, the value immediately after 0 will be 1,999 as shown below.



64-01-11 Total Measuring Range (R)

[UDINT, Set, NV]

WARNING

This attribute is active only if the **64-01-0E Scaling Function Control (R)** attribute is enabled; otherwise it is ignored and the system uses the physical values (**64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)**) to calculate the position information.
Furthermore, if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the scaling

function -even if enabled- and this **64-01-11 Total Measuring Range (R)** attribute are ignored.

This attribute sets a custom number of distinguishable steps over the total measuring range. The total resolution of the encoder results from the product of **64-01-10 Measuring Units per Span (R)** by the required **Number of revolutions**. Allowed values are less than or equal to **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**.

Default = 1 073 741 824 (min. = 1, max. = 1 073 741 824)

WARNING

When you set a new value next to the **64-01-11 Total Measuring Range (R)** attribute, please always check also the **64-01-10 Measuring Units per Span (R)** attribute value and be sure that the resulting number of revolutions complies with the physical **64-01-2B Number of Spans (R)** of the device.
Let's suppose that the encoder is programmed as follows:
64-01-10 Measuring Units per Span (R): 8,192 cpr
64-01-11 Total Measuring Range (R) = 134 217 728 = 8,192 (cpr) * 16,384 (rev.)
Let's set a new total resolution, for instance: **64-01-11 Total Measuring Range (R)** = 360.
As the **64-01-11 Total Measuring Range (R)** must be greater than or equal to the **64-01-10 Measuring Units per Span (R)**, the above setting is not allowed. When this happens, the **64-01-2F Warnings** attribute signals the error (see also the **64-01-67 Wrong Parameters List (R)** attribute and the LEDs).

WARNING

Every time you change the value in this attribute then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

EXAMPLE

We connect the HM58**16/16384** multiturn rotary encoder.

Its physical resolution is as follows (see the order code):

- Hardware counts per revolution: **Singleturn resolution (bits)** parameter in the **64-01-51 Encoder Resolution (R)** attribute = 16 bits, thus **64-01-2A Physical Resolution Span (R)** = 65,536 (2^{16})

- Hardware number of revolutions: **Multiturn resolution (bits)** parameter in the **64-01-51 Encoder Resolution (R)** attribute = 14 bits, thus **64-01-2B Number of Spans (R)** = 16,384 (2^{14})
- Total hardware resolution: **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)** = 1 073 741 824 ($2^{16+14=30}$)

In the specific installation 2,048 counts/rev. * 1,024 turns are required:

- Enable the scaling function: **64-01-0E Scaling Function Control (R)** attribute = "01h"
- Counts per revolution: **64-01-10 Measuring Units per Span (R)** = 2,048 (0000 0800h)
- Total resolution: **64-01-11 Total Measuring Range (R)** = 2,048 * 1,024 = 2 097 152 (0020 0000h)

NOTE
We suggest setting values which are power of 2 (2^n: 2, 4, ..., 2048, 4096, 8192,...) to be set in the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes to avoid counting errors.

WARNING
If **64-01-10 Measuring Units per Span (R)** and/or **64-01-11 Total Measuring Range (R)** values change, the **64-01-13 Preset Value** must be updated according to the new resolution. A new preset operation is also required.

64-01-11 Total Measuring Range (L)

[UDINT, Set, NV]

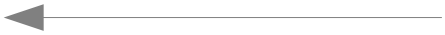
WARNING
This attribute is active only if the **64-01-0E Scaling Function Control (L)** attribute is enabled; otherwise it is ignored and the system uses the physical values (**64-01-2A Physical Measuring Step (L)** attribute and **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute) to calculate the position information.
Furthermore, if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the scaling function -even if enabled- and this **64-01-11 Total Measuring Range (L)** attribute are ignored.

This attribute sets the length of the travel the encoder has to measure. The value is expressed in number of information. It has to be comprised between 1 and 2^{30} = 1 073 741 824.
It can be either the number of information for the max. measuring length (for instance, if the application needs the whole path); or the number of information for just a part of the scale if the application only uses a section of the scale.

Thus this value must be less than or equal to the number of information resulting from the scale max. measuring length (**64-01-2A Physical Measuring Step (L)**).
We suggest setting a value that is a power of 2 submultiple of the maximum measuring range (**Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute) not to cause a counting error, i.e. a jump in the position count when the sensor crosses the physical zero point (see the WARNING below).
Default = 524,288 (min. = 1, max. = 1 073 741 824)

WARNING
When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), please enter scaled values next to the **64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)** attributes that are consistent with the physical values.

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
As you can see in the product datasheet, "50" in the order code means a 0.05 mm resolution. Let's say the mechanical travel of our application is the max. measuring length the SMA5 linear encoder is allowed to run on the MTA5 scale, i.e. 5,035 mm. Thus the max. number of information is 100,700 ≈ 17 bits (for the complete explanation refer to the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute). If you need a custom measuring range, you need to enable the **64-01-0E Scaling Function Control (L)** and then set a value lower than 2^{17} = 131,072 here.
If you set a preset along the path, when the encoder moves back and cross the zero, the value immediately after 0 will be $2^{\text{Physical Total Resolution (L)}}$ - 1, i.e. 131,071.



...	131069	131070	131071	0	1	2	...

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
As you can see in the product datasheet, "100" in the order code means a 0.1 mm resolution. Let's say the mechanical travel of our application is the max. measuring length the SMAX linear encoder is allowed to run on the MTAX scale, i.e. 600 mm. Thus the max. number of information is 6,000 ≈ 13 bits (for the complete explanation refer to the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute). If you need a custom measuring range, you need to enable the **64-01-0E Scaling Function Control (L)** and then set a value lower than 2^{13} = 8,192 here.
If you set a preset along the path, when the encoder moves back and cross the zero, the value immediately after 0 will be $2^{\text{Physical Total Resolution (L)}}$ - 1, i.e. 8,191.

...	8189	8190	8191	0	1	2	...

EXAMPLE

We need to connect an **SMA5-GA-50**, its physical resolution is 0.05 mm. Let's say the mechanical travel of our application is 1,000 mm. Thus the max. number of information is 20,000 ≈ 15 bits (for the complete explanation refer to the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute). Thus you must enable the **64-01-0E Scaling Function Control (L)** attribute and set here the value 20,000 (instead of the physical value 131,072).

In this way you will obtain several 20,000 information sections following each other all along the whole measuring length. The position information will be from 0 to 19,999; then again from 0 to 19,999 and so on.

...	19997	19998	19999	0	1	2	...	19997	19998	19999	0	1	2	...

← max measuring length →

WARNING

When you enable the scaling function (**64-01-0E Scaling Function Control (L)** = 01h), a counting error, i.e. a jump in the position count, may occur if the following conditions arise:

- a physical zero setting has been performed in the encoder;
- the **64-01-10 Position Step Setting (L)** attribute value is not a multiple of the physical resolution as set next to the **64-01-2A Physical Measuring Step (L)** attribute;
- the measuring range (**64-01-11 Total Measuring Range (L)** parameter) is not a power of 2 submultiple of the maximum measuring range.

If the above described conditions arise, a counting error may occur when the sensor crosses the physical zero point.

If the scaling function is disabled (**64-01-0E Scaling Function Control (L)** = 00h), the transmitted position values are always consistent.

If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h) yet no physical zero setting has been performed in the linear sensor, the transmitted position values are always consistent.

If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** = 01h), the **64-01-10 Position Step Setting (L)** attribute value is a multiple of the physical resolution and the measuring range (**64-01-11 Total Measuring Range (L)** attribute) is a power of 2 submultiple of the maximum measuring range, the transmitted position values are consistent, regardless of the physical zero setting.

WARNING

Every time you change the value in this attribute then you are required to set a new preset value (see the **64-01-13 Preset Value** attribute) and finally save the new parameters (by means of the Class Service 16h, see on page 97; or by setting the bit 6 **Save Parameters** in the **64-01-68 Command Register** attribute to 1, see on page 135).

64-01-13 Preset Value

[UDINT, Set, NV]

This attribute allows to set the encoder position to a Preset value. The Preset function is meant to assign a desired value to a physical position of the encoder. The chosen position will get the value set next to this object and all the previous and the following positions will get a value according to it. This function is useful, for example, when the zero position of the encoder and the zero position of the axis need to match. The preset value will be set and activated for the position of the encoder in the moment when the preset value is transmitted. We suggest setting the preset value while the encoder is in stop.

The preset value is activated as soon as the value is set.

If you need to activate a value already set next to the **64-01-13 Preset Value** in a different physical position of the encoder travel, you can use the bit 0 **Activate Preset** in the **64-01-68 Command Register** attribute, see on page 134.

Default = 0 (min. = 0, max. = 1 073 741 823 *)

* See the NOTE below.

EXAMPLE

Let's take a look at the following example to better understand the preset function and the meaning and use of the related objects: **64-01-13 Preset Value** and **64-01-33 Offset Value**.

The encoder position which is transmitted results from the following calculation:

Transmitted value = **read position** (it does not matter whether the position is physical or scaled) + **64-01-13 Preset Value** - **64-01-33 Offset Value**.

If you never set the **64-01-13 Preset Value** or performed the preset setting, then the transmitted value and the read position are necessarily the same as **64-01-13 Preset Value** = 0 and **64-01-33 Offset Value** = 0.

When you set the **64-01-13 Preset Value** or execute the preset setting, the system saves the current encoder position in the **64-01-33 Offset Value** attribute. It follows that the transmitted value and the **64-01-13 Preset Value** are the same as **read position** - **64-01-33 Offset Value** = 0; in other words, the value set next to the **64-01-13 Preset Value** attribute is paired with the current position of the encoder as you wish.

For example, let's assume that the value "50" is set next to the **64-01-13 Preset Value** attribute when the encoder position is "1000". In other words, you want to receive the value "50" when the encoder reaches the position "1000".

We will obtain the following information sequence:
Transmitted value = **read position** (="1000") + **64-01-13 Preset Value** (="50") - **64-01-33 Offset Value** (="1000") = 50.
The following transmitted value will be:
Transmitted value = **read position** (="1001") + **64-01-13 Preset Value** (="50") - **64-01-33 Offset Value** (="1000") = 51.
And so on.

NOTE

- If the scaling function is disabled (**64-01-0E Scaling Function Control (R)** attribute = 00h), then the **64-01-13 Preset Value** must be less than or equal to the "Total hardware resolution" - 1, i.e. (**64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**) - 1 (converter for rotary encoders).
- If the scaling function is disabled (**64-01-0E Scaling Function Control (L)** attribute = 00h), then the **64-01-13 Preset Value** must be less than or equal to the "Total hardware resolution" - 1, i.e. $2^{\text{Physical Total Resolution (L)}}$ - 1 (converter for linear encoders).
- If the scaling function is enabled (**64-01-0E Scaling Function Control (R)** attribute = 01h), then the **64-01-13 Preset Value** must be lower than or equal to the **64-01-11 Total Measuring Range (R)** - 1 (converter for rotary encoders).
- If the scaling function is enabled (**64-01-0E Scaling Function Control (L)** attribute = 01h), then the **64-01-13 Preset Value** must be lower than or equal to the **64-01-11 Total Measuring Range (L)** - 1 (converter for linear encoders).

NOTE

Please consider that if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) / the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the preset function -even if set and activated- is ignored. If the user sets a preset while the "Bypass mode" is enabled, the operation is not carried out.

WARNING

Check the value in the **64-01-13 Preset Value** attribute and perform the preset operation every time you set a new **64-01-0C Direction Counting Toggle (R)** or change the scaled values (**64-01-10 Measuring Units per Span (R)** and/or **64-01-11 Total Measuring Range (R)** -rotary encoder; **64-01-10 Position Step Setting (L)** and/or **64-01-11 Total Measuring Range (L)** -linear encoder).

64-01-18 Velocity Value

[DINT, Get, V]

This attribute shows the current output speed value detected by the encoder and calculated every 100 ms.

The value can be expressed in several engineering units according to the setting next to the following **64-01-19 Velocity Format (R)** / **64-01-19 Velocity Format (L)** attribute. As a default the velocity value is expressed in counts per second (cps).

64-01-19 Velocity Format (R)

[UINT, Set, NV]

This attribute defines the engineering unit for the velocity value of the rotary encoder (see the previous **64-01-18 Velocity Value** attribute).

1F04h = counts per second: number of steps per second; the minimum resolution is 10 cps (default);

1F05h = counts per millisecond: number of steps per millisecond; the minimum resolution is 1 cpms;

1F07h = counts per minute: number of steps per minute; the minimum resolution is 600 cpm;

1F0Eh = revolutions per second: number of revolutions per second; the minimum resolution is 1 rps;

1F0Fh = revolutions per minute: number of revolutions per minute; the minimum resolution is 1 rpm;

1F10h = revolutions per hour: number of revolutions per hour; the minimum resolution is 4 rph.

Default = 1F04h (min. = 1F04h, max. = 1F10h)

64-01-19 Velocity Format (L)

[UINT, Set, NV]

This attribute defines the engineering unit for the velocity value of the linear encoder (see the **64-01-18 Velocity Value** attribute above).

1F04h = counts per second: number of steps per second; the minimum resolution is 10 cps (default);

1F05h = counts per millisecond: number of steps per millisecond; the minimum resolution is 1 cpms;

1F07h = counts per minute: number of steps per minute; the minimum resolution is 600 cpm;

2B08h = millimeters per second: number of millimeters per second; the minimum resolution depends on the physical resolution of the connected sensor;
2B09h = millimeters per minute: number of millimeters per minute; the minimum resolution depends on the physical resolution of the connected sensor.
Default = 1F04h (min. = 1F04h, max. = 2B09h)

64-01-29 Operating Status (R)

[BYTE, Get, V]
This attribute contains the operating status of the converter for rotary encoders according to definitions in the following table.

Bit	Function	bit = 0	bit = 1
0	**Counting direction (R)**	CW Clockwise	CCW counter-clockwise
1	**Scaling function (R)**	Disabled	Enabled
2 ... 7	not used		

Counting direction (R)
It shows whether the code sequence is set to clockwise (CW) or counter-clockwise (CCW). If the bit is "=0" the output encoder position value has been set to increase (count up information) when the encoder rotates clockwise; if the bit is "=1" the output encoder position value has been set to increase when the encoder rotates counter-clockwise. To set the code sequence to either CW or CCW you must set the **64-01-0C Direction Counting Toggle (R)** attribute to 0 / 1, see on page 100.

Scaling function (R)
It shows whether the scaling function is disabled or enabled. If the value is "=0" the scaling function is disabled (i.e. the system uses the resolution physical values -**64-01-2A Physical Resolution Span (R)** and **64-01-2B Number of Spans (R)**- to calculate the position information); if the value is "=1" the scaling function is enabled (i.e. the system uses the custom values -**64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)**- to calculate the position information). To disable / enable the scaling function you must set the **64-01-0E Scaling Function Control (R)** attribute to 0 / 1, see on page 101.

64-01-29 Operating Status (L)

[BYTE, Get, V]

This attribute contains the operating status of the converter for linear encoders according to definitions in the following table.

Bit	Function	bit = 0	bit = 1
0	**Counting direction (L)**	Standard	Inverted
1	**Scaling function (L)**	Disabled	Enabled
2 ... 7	not used		

Counting direction (L)

It shows the value that is currently set in the **64-01-0C Direction Counting Toggle (L)** attribute. If the **64-01-0C Direction Counting Toggle (L)** attribute is set to "00h" the output encoder position value has been set to increase (count up information) when the sensor moves in the standard direction; if it is set to "01h" the output encoder position value has been set to increase when the sensor moves in reverse of the standard direction. To set the code sequence you must set the **64-01-0C Direction Counting Toggle (L)** attribute to 00h / 01h, see on page 100.

Scaling function (L)

It shows the value that is currently set in the **64-01-0E Scaling Function Control (L)** attribute. In other words, it is intended to show whether the scaling function is disabled or enabled. If the **64-01-0E Scaling Function Control (L)** attribute is set to "00h" the scaling function is disabled (i.e. the system uses the resolution physical values -**64-01-2A Physical Measuring Step (L)** and **Physical Total Resolution (L)** in **64-01-50 Encoder Settings (L)**- to calculate the position information); if the value is set to "01h" the scaling function is enabled (i.e. the system uses the custom values -**64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)**- to calculate the position information). To disable / enable the scaling function you must set the **64-01-0E Scaling Function Control (L)** attribute to 0 / 1, see on page 102.

64-01-2A Physical Resolution Span (R)

[UDINT, Get, NV]

WARNING

This attribute is active only if the **64-01-0E Scaling Function Control (R)** attribute is set to "=00h"; otherwise it is ignored and the system uses the custom values (**64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)**) to calculate the position information.

Furthermore, if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the scaling function -even if enabled- is ignored and the **64-01-10 Measuring Units per Span (R)** and **64-01-2B Number of Spans (R)** attributes are used to calculate the position information.

This attribute is intended to show the number of physical distinguishable steps provided per each turn by the hardware of the connected encoder (physical singleturn resolution). The physical singleturn resolution of the connected encoder must be set next to the **Singleturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute. As soon as the user confirms the value in the **Singleturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute, the program automatically sets the value in this attribute accordingly.
If you want to set a custom resolution see the **64-01-10 Measuring Units per Span (R)** attribute.

Default = according to the **Singleturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute.

64-01-2A Physical Measuring Step (L)

[UDINT, Get, NV]

WARNING
This attribute is active only if the **64-01-0E Scaling Function Control (L)** attribute is set to "=00h"; otherwise it is ignored and the system uses the custom values (**64-01-10 Position Step Setting (L)** and **64-01-11 Total Measuring Range (L)**) to calculate the position information.
Furthermore, if the **Bypass mode (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute (see on page 125) is set to "1h" = enabled, the scaling function -even if enabled- is ignored and the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute are used to calculate the position information.

This attribute is intended to show the physical resolution of the connected encoder expressed in nanometers [nm]. The physical resolution must be set next to the **64-01-51 Encoder Resolution (L)** attribute. As soon as the user confirms the value in the **64-01-51 Encoder Resolution (L)** attribute, the program automatically sets the value in this attribute accordingly. If you want to set a custom resolution see the **64-01-10 Position Step Setting (L)** attribute on page 105.
Default = according to **64-01-51 Encoder Resolution (L)**

64-01-2B Number of Spans (R)

[UINT, Get, NV]

WARNING
This attribute is active only if the **64-01-0E Scaling Function Control (R)** attribute is set to "=00h"; otherwise it is ignored and the system uses the custom values (**64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)**) to calculate the position information.

Furthermore, if the **Bypass mode (R)** parameter in the **64-01-50 Encoder Settings (R)** attribute (see on page 123) is set to "1h" = enabled, the scaling function -even if enabled- is ignored and the **64-01-10 Measuring Units per Span (R)** and **64-01-2B Number of Spans (R)** attributes are used to calculate the position information.

This attribute is intended to show the number of physical distinguishable turns provided by the hardware of the connected encoder (number of physical revolutions). The physical multiturn resolution of the connected encoder must be set next to the **Multiturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute. As soon as the user confirms the value in the **Multiturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute, the program automatically sets the value in this attribute accordingly.
The **Total hardware resolution** results from **64-01-2A Physical Resolution Span (R)** * **64-01-2B Number of Spans (R)**.
If you want to set a custom number of turns see the **64-01-10 Measuring Units per Span (R)** and **64-01-11 Total Measuring Range (R)** attributes.

Default = according to the **Multiturn resolution (bits)** parameter of the **64-01-51 Encoder Resolution (R)** attribute

64-01-2C Alarms

[UINT, Get, V]
An alarm indicates that a malfunction has occurred which could lead to an incorrect position value. It is set when a bit indicating a fault is set to true (high). The alarm remains active until the alarm is cleared and the device is able to provide an accurate position value. When an alarm is active, also the **64-01-2E Alarm Flag** attribute is set to 1. The attribute is defined according to the following table.
Refer also to the following **64-01-2D Supported Alarms** attribute.

Bit	Function	bit = 0	bit = 1
0	not used		
1	**Diagnostic error**	Alarm not active	Alarm active
2 ... 11	not used		
12	**Flash memory error**	Alarm not active	Alarm active
13 ... 15	not used		

Diagnostic error
It warns about an error that is specified in the Vendor Specific bits 12 ... 15. Only **Flash memory error** alarm is available.

Flash memory error
Internal error, it cannot be restored. The flash memory contains corrupted data; or maybe the flash memory is damaged.

64-01-2D Supported Alarms

[WORD, Get, NV]

This attribute contains information on the supported alarms. Refer to the previous **64-01-2C Alarms** attribute.

Bit	Function	bit = 0	bit = 1
0	not used		
1	Diagnostic error	Not supported	Supported
2 ... 11	not used		
12	Flash memory error	Not supported	Supported
13 ... 15	not used		

Default = 1002h (= 0001 0000 0000 0010 = alarms at bits 1 and 12 of the previous **64-01-2C Alarms** attribute are supported).

64-01-2E Alarm Flag

[BOOL, Get, V]

It indicates (1) that a fault occurred and an alarm has been triggered, see the defined alarms in the previous **64-01-2C Alarms** attribute.

64-01-2F Warnings

[UINT, Get, V]

The **64-01-2F Warnings** attribute indicates that tolerances for certain internal parameters of the converter have been exceeded. It does not imply incorrect position values. The warning is cleared if the tolerances are again within normal parameters. When a warning is active, also the **64-01-31 Warning Flag** attribute is set to 1. The attribute is defined according to the following table.
Refer also to the following **64-01-30 Supported Warnings** attribute.

Bit	Function	bit = 0	bit = 1
0 ... 12	not used		
13	Parameters Error	Warning not active	Warning active
14 and 15	not used		

Parameters Error

An out-of-tolerance parameter has been set. For more details about the specific out-of-tolerance parameter refer to the **64-01-67 Wrong Parameters List (R)** attribute, see on page 131 -converter for rotary encoders; to the **64-01-67 Wrong Parameters List (L)** attribute, see on page 132 -converter for linear encoders.

64-01-30 Supported Warnings

[WORD, Get, NV]

This attribute contains information on the supported warnings. Refer to the previous **64-01-2F Warnings** attribute.

Bit	Function	bit = 0	bit = 1
0 ... 12	not used		
13	Parameters Error	Not supported	Supported
14 and 15	not used		

Default = 2000h (= 0010 0000 0000 0000 = warning at bit 13 of the previous **64-01-2F Warnings** attribute is supported).

64-01-31 Warning Flag

[BOOL, Get, V]

The attribute indicates whether any of the defined warnings are active (1) or not (0).

64-01-32 Operating Time

[UDINT, Get, NV]

This attribute contains the information on the operating time and is incremented as long as the converter is powered. It is expressed in tenths of an hour. This attribute is not used currently.

64-01-33 Offset Value

[DINT, Get, NV]

The **64-01-33 Offset Value** attribute is calculated by the preset function and shifts the **64-01-03 Position value (R)** / **64-01-03 Position value (L)** attribute with the calculated value. It is stored automatically by the device and can be read from the converter for diagnostic purposes. To zero set the value in this attribute you must upload the factory default values (see the Class Service 15h on page 97 and the **Restore Parameters to Defaults** bit option in the **64-01-68 Command Register** attribute).

64-01-50 Encoder Settings (R)

[UINT, Set, NV]

This attribute contains information about the connected SSI encoder. Default values are highlighted in bold in the table.

Bit	Function	bit = 0	bit = 1
0	**SSI protocol (R)**	**LSB Right Aligned protocol**	MSB Left Aligned protocol
1 ... 3	not used		
4	**SSI output code (R)**	Binary code	**Gray code**
5 and 6	not used		
7	**Bypass mode (R)**	**Disabled**	Enabled
8 ... 15	**No of SSI clocks (R)**	**25**	

Default: 1910h = 0001 1001 0001 0000_2 (min. value 0100h, max. value 2091h)

SSI protocol (R)

It sets the SSI protocol used by the SSI encoder to arrange the absolute position information. The SSI protocol can be the "LSB Right Aligned" protocol (bit 0 = 0) or the "MSB Left Aligned" protocol (bit 0 = 1). For any information on the SSI protocol please refer to the "User's manual" of the connected encoder.
Default = 0h
Min. value = 0h "LSB Right Aligned" protocol
max. value = 1h "MSB Left Aligned" protocol

EXAMPLE
We need to connect the following rotary encoder: **MM36 12/8192 BB**.
MM36 encoder uses the 25-bit "LSB Right Aligned" protocol to arrange the absolute position information. Thus you have to set the value 0h in this entry. For further information refer to the encoder's "User's manual".

SSI output code (R)

It sets the output code used by the SSI encoder to output the absolute position information. The output code can be "Binary" (bit 4 = 0) or "Gray" (bit 4 = 1). For any information on the output code please refer to the "User's manual" of the connected encoder.
Default = 1h
Min. value = 0h Binary code
Max. value = 1h Gray code

EXAMPLE
We need to connect the following rotary encoder: **MM36 12/8192 BB**.
MM36...BB encoder uses the Binary code to output the absolute position information. Thus you have to set the value 0h = Binary in this entry. For further information refer to the encoder's "User's manual".

EXAMPLE
We need to connect the following rotary encoder: **AM58 13/4096-G**.
"G" in the order code means that Gray code is used to arrange the absolute position information. Thus you have to set the value 1h = Gray in this entry. For further information refer to the encoder's "User's manual".

Bypass mode (R)
If the bit 7 = 0h, the "Bypass mode" is disabled, that is: the position value (refer to the **64-01-03 Position value (R)** attribute on page 98) read by the encoder can be processed according to needs, so the user can scale the value, set a preset and change the counting direction.
If the bit 7 = 1h, the "Bypass mode" is enabled, that is: the information from the encoder is transmitted "as it is" and not processed in any way. The preset, scaling, and counting direction functions -even if set and enabled- are ignored and the **64-01-10 Measuring Units per Span (R)** and **64-01-2B Number of Spans (R)** attributes are used to calculate the position information. If, for example, the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated. As soon as the "Bypass mode" is disabled, the preset, scaling, and counting direction functions -if set and enabled- become active and the **64-01-03 Position value (R)** will be accordingly.
Default = 0h
Min. value = 0h disabled
Max. value = 1h enabled

No of SSI clocks (R)
It sets the number of SSI clocks required by the SSI encoder to send the complete data word. The number of clocks depends on the resolution of the encoder and the type of SSI protocol. For any information on the SSI clocks required please refer to the "User's manual" of the connected encoder.
Default = 19h
Min. value = 01h
Max. value = 20h

NOTE
If the **SSI protocol (R)** parameter is set to 1h = "MSB Left Aligned" protocol, the **No of SSI clocks (R)** parameter value must be equal to the number of bits of the **total physical resolution** (**Singleturn resolution (bits)** + **Multiturn resolution (bits)** parameters).

EXAMPLE
We need to connect the following rotary encoder: **MM36 12/8192**.
MM36 encoder always requires 25 clocks (the length of the word is always 25 bits, regardless of the max. number of information to provide). Thus you have to set 19h in this entry. For further information refer to the encoder's "User's manual".

EXAMPLE
We need to connect the following rotary encoder: **AM36 19/4096**.
AM36 encoder implements the "MSB Left Aligned" protocol and requires 31 clocks (the length of the word is 31 bits). Thus you have to set 1Fh in this entry. For further information refer to the encoder's "User's manual".

64-01-50 Encoder Settings (L)

[UDINT, Set, NV]
This attribute contains information about the connected SSI encoder. Default values are highlighted in bold in the table.

Bit	Function	bit = 0	bit = 1
0	**SSI protocol (L)**	**LSB Right Aligned protocol**	MSB Left Aligned protocol
1 ... 3	not used		
4	**SSI output code (L)**	Binary code	**Gray code**
5 and 6	not used		
7	**Bypass mode (L)**	**Disabled**	Enabled
8 ... 15	**Physical Total Resolution (L)**	**19**	
16 ... 23	**No of SSI clocks (L)**	**25**	
24 ... 31	not used		

Default: 0019 1310h = 0001 1001 0001 0011 0001 0000_2 (min. value 0001 0100h, max. value 0020 1E91h)

SSI protocol (L)
It sets the SSI protocol used by the SSI encoder to arrange the absolute position information. The SSI protocol can be the "LSB Right Aligned" protocol (bit 0 = 0h) or the "MSB Left Aligned" protocol (bit 0 = 1h). For any information on the SSI protocol please refer to the "User's manual" of the connected encoder.
Default = 0h
Min. value = 0h "LSB Right Aligned" protocol
max. value = 1h "MSB Left Aligned" protocol

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
SMA5 encoder uses the 25-bit "LSB Right Aligned" protocol to arrange the absolute position information. Thus you have to set the bit to 0h. For further information refer to the encoder's "User's manual".

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
"BG" in the order code means that "MSB Left Aligned" protocol and Binary code are used to arrange the absolute position information. Thus you have to set the bit to 1h. For further information refer to the encoder's "User's manual".

SSI output code (L)
It sets the output code used by the SSI encoder to output the absolute position information. The output code can be "Binary" (bit 4 = 0h) or "Gray" (bit 4 = 1h). For any information on the output code please refer to the "User's manual" of the connected encoder.
Default = 1h
Min. value = 0h Binary code
Max. value = 1h Gray code

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
SMA5 encoder uses the Gray code to output the absolute position information. Thus you have to set this bit to 1h = Gray. For further information refer to the encoder's "User's manual".

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
"BG" in the order code means that "MSB Left Aligned" protocol and Binary code are used to arrange the absolute position information. Thus you have to set this bit to 0h = Binary. For further information refer to the encoder's "User's manual".

Bypass mode (L)
If the bit 7 = 0h, the "Bypass mode" is disabled, that is: the position value (refer to the **64-01-03 Position value (L)** attribute on page 98) read by the encoder can be processed according to needs, so the user can scale the value, set a preset and change the counting direction.
If the bit 7 = 1h, the "Bypass mode" is enabled, that is: the information from the encoder is transmitted "as it is" and not processed in any way. The preset, scaling, and counting direction functions -even if set and enabled- are ignored and the **64-01-2A Physical Measuring Step (L)** attribute and the **Physical Total Resolution (L)** parameter in the **64-01-50 Encoder Settings (L)** attribute are used to calculate the position information. If, for example, the user sets a preset while the "Bypass mode" is enabled, the value is accepted, but not activated. As soon as the "Bypass mode" is disabled, the preset, scaling, and counting direction functions -if set and enabled- become active and the **64-01-03 Position value (L)** will be accordingly.
Default = 0h
Min. value = 0h disabled

Max. value = 1h enabled

Physical Total Resolution (L)

It sets the max. number of information (expressed in bits) the SSI encoder can output for the max. measuring length, i.e. the total physical resolution. The value depends on the encoder resolution and the max. measuring length. As soon as you confirm the value, the system automatically sets the default value of the **64-01-11 Total Measuring Range (L)** attribute accordingly. For any information on the max. number of information please refer to the "User's manual" of the connected encoder.

Default = 13h

Min. value = 01h

Max. value = 1Eh

EXAMPLE

We need to connect the following linear encoder: **SMA5-GA-50**. Its resolution is **0.05 mm** (see the order code).

The max. measuring length of the SMA5 linear encoder on the MTA5 scale is **5,050 mm**.

The max. number of information the encoder can output results from the following calculation:

$$\text{Max. No of Information} = \frac{\text{Max. measuring range}}{\text{Resolution}}$$

$$\text{Max. No of Information} = \frac{5{,}050}{0.05} = \mathbf{101{,}000}$$

Now you have to "round up" the result to the next highest power of 2, that is: 131,072 = 2^{17}. Thus the number of bits is "17". The value to set in this entry is 11h.

EXAMPLE

We need to connect the following linear encoder: **SMAX-BG-100**. Its resolution is **0.1 mm** (see the order code).

The max. measuring length of the SMAX linear encoder on the MTAX scale is **600 mm**.

The max. number of information the encoder can output results from the following calculation:

$$\text{Max. No of Information} = \frac{\text{Max. measuring range}}{\text{Resolution}}$$

$$\text{Max. No of Information} = \frac{600}{0.1} = \mathbf{6{,}000}$$

Now you have to "round up" the result to the next highest power of 2, that is: 8,192 = 2^{13}. Thus the number of bits is "13". The value to set in this entry is 0Dh.

No of SSI clocks (L)
It sets the number of SSI clocks required by the SSI encoder to send the complete data word. The number of clocks depends on the resolution of the encoder and the type of SSI protocol. For any information on the SSI clocks required please refer to the "User's manual" of the connected encoder.
Default = 19h
Min. value = 01h
Max. value = 20h

NOTE
If the **SSI protocol (L)** parameter is set to 1h = "MSB Left Aligned" protocol, the **No of SSI clocks (L)** parameter value must be equal to the number of bits of the **total physical resolution** (**Physical Total Resolution (L)** parameter).

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
SMA5 encoder always requires 25 clocks (the length of the word is always 25 bits, regardless of the max. number of information to provide). Thus you have to set 19h in this entry. For further information refer to the encoder's "User's manual".

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
The number of clocks depends on the max. number of information (see the example in the following parameter). Let's say the max. number of information is 6,000, thus it requires 13 clocks. You have to set 0Dh in this entry. For further information refer to the encoder's "User's manual".

64-01-51 Encoder Resolution (R)

[UINT, Set, NV]
This attribute contains information about the resolution of the connected SSI encoder.

Bit	Function	
0 ... 7	**Singleturn resolution (bits)**	**12**
8 ... 15	**Multiturn resolution (bits)**	**13**

Default: 0D0Ch = 0000 1101 0000 1100_2 (min. value 0001h, max. value 100Dh)

Singleturn resolution (bits)

It sets the physical singleturn resolution (the number of physical distinguishable steps per each revolution) of the SSI encoder expressed in bits.

The value has to be comprised between 01h and 12h. The physical resolution can be read in the order code (see the product datasheet). As soon as the user confirms the value, the system automatically sets the value in the **64-01-2A Physical Resolution Span (R)** attribute accordingly. For any information on the singleturn resolution please refer to the "User's manual" of the connected encoder.

Default = 0Ch

Min. value =01h

Max. value = 12h if **Multiturn resolution (bits)** = 01h

Max. value = 10h if **Multiturn resolution (bits)** > 01h and ≤ 0Eh

Max. value = 0Dh if **Multiturn resolution (bits)** > 0Eh

EXAMPLE

We need to connect the following rotary encoder: **MM36 12/8192**.

As you can easily infer from the order code, the hardware singleturn resolution is 12 bits. Thus the value to be set in this entry is 0Ch. For further information refer also to the encoder's "User's manual".

EXAMPLE

We need to connect the following rotary encoder: **HM58 16/16384**.

As you can easily infer from the order code, the hardware singleturn resolution is 16 bits. Thus the value to be set in this entry is 10h. For further information refer also to the encoder's "User's manual".

Multiturn resolution (bits)

It sets the physical multiturn resolution (the number of physical revolutions) of the SSI encoder expressed in bits.

The value has to be comprised between 01h and 10h. The physical resolution can be read in the order code (see the product datasheet). As soon as the user confirms the value, the system automatically sets the value in the **64-01-2B Number of Spans (R)** attribute accordingly. For any information on the multiturn resolution please refer to the "User's manual" of the connected encoder.

Default = 0Dh

Min. value =00h

Max. value = 10h if **Singleturn resolution (bits)** ≤ 0Dh

Max. value = 0Eh if **Singleturn resolution (bits)** > 0Dh

EXAMPLE
We need to connect the following rotary encoder: **MM36 12/8192**.
In the order code the hardware multiturn resolution is expressed in number of revolutions. To translate the number of revolutions into bits, you must calculate the power of 2 of the value: 8,192 = 2^{13}. Thus the value to be set in this entry is 0Dh. For further information refer also to the encoder's "User's manual".

EXAMPLE
We need to connect the following rotary encoder: **HM58 16/16384**.
In the order code the hardware multiturn resolution is expressed in number of revolutions. To translate the number of revolutions into bits, you must calculate the power of 2 of the value: 16,384 = 2^{14}. Thus the value to be set in this entry is 0Eh. For further information refer also to the encoder's "User's manual".

64-01-51 Encoder Resolution (L)

[UINT, Set, NV]
This attribute sets the physical resolution of the linear encoder expressed in nanometers (nm). The value has to be comprised between 01h and 3FFF FFFFh.
Usually the physical resolution can be read in the order code (see the product datasheet). As soon as the user confirms the value, the system automatically sets the default value of the **64-01-10 Position Step Setting (L)** and **64-01-2A Physical Measuring Step (L)** attributes accordingly.
Default = 2710h (min. = 01h, max. = 3FFF FFFFh)

EXAMPLE
We need to connect the following linear encoder: **SMA5-GA-50**.
As you can see in the product datasheet, "50" in the order code means 0.05 mm resolution = 50,000 nm resolution. Thus you have to set the value C350h in this attribute. For further information refer also to the encoder's "User's manual".

EXAMPLE
We need to connect the following linear encoder: **SMAX-BG-100**.
As you can see in the product datasheet, "100" in the order code means 0.1 mm resolution = 100,000 nm resolution. Thus you have to set the value 0001 86A0h in this attribute. For further information refer also to the encoder's "User's manual".

64-01-64 Application-DSC FW Version

[UDINT, Get, NV]
This attribute contains the firmware version of the Application DSC (Digital Signal Controller).
The meaning of the 32 bits in the attribute is as follows:

Bit	31 ... 16	15 ... 0
	Major version	Minor version

For example, the value 0001 0001 hex in hexadecimal notation corresponds to the binary representation 0000 0000 0000 0001 0000 0000 0000 0001 and has to be interpreted as: firmware version 1.1.

Default = Device dependent

64-01-65 Hardware Version

[UDINT, Get, NV]
This attribute contains the hardware version of electronics.
The meaning of the 32 bits in the attribute is as follows:

Bit	31 ... 16	15 ... 0
	Major version	Minor version

For example, the value 0002 0001 hex in hexadecimal notation corresponds to the binary representation 0000 0000 0000 0002 0000 0000 0000 0001 and has to be interpreted as: hardware version 2.1.

Default = Device dependent

64-01-66 Network-DSC FW Version

[UDINT, Get, NV]
This attribute contains the firmware version of the Network DSC (Digital Signal Controller).
The meaning of the 32 bits in the attribute is as follows:

Bit	31 ... 24	23 ... 16	15 ... 8	7 ... 0
	0	Major version	Minor version	Build number

For example, the value 0001 0001 hex in hexadecimal notation corresponds to the binary representation 0000 0000 0000 0001 0000 0000 0000 0001 and has to be interpreted as: firmware version 1.0.1.

Default = Device dependent

64-01-67 Wrong Parameters List (R)

[UINT, Get, NV]

The operator has entered invalid data and the **Parameters Error** warning in the **64-01-2F Warnings** attribute has been triggered. This variable is meant to show (bit value = HIGH) the list of the wrong parameters, according to the following table.

Please note that the normal work status can be restored only after having set proper values.

Bit	Function	bit = 0	bit = 1
0	Measuring Units per Span exceeded (R)	Warning not active	Warning active
1	Total Measuring Range exceeded (R)	Warning not active	Warning active
2	Preset Value exceeded (R)	Warning not active	Warning active
3	Offset Value exceeded (R)	Warning not active	Warning active
4	Encoder Settings parameters error (R)	Warning not active	Warning active
5	Encoder Resolution parameters error (R)	Warning not active	Warning active
6 ... 15	not used		

Byte 0

Measuring Units per Span exceeded (R)

bit 0 — Wrong data has been set next to the **64-01-10 Measuring Units per Span (R)** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Total Measuring Range exceeded (R)

bit 1 — Wrong data has been set next to the **64-01-11 Total Measuring Range (R)** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Preset Value exceeded (R)

bit 2 — Wrong data has been set next to the **64-01-13 Preset Value** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Offset Value exceeded (R)

bit 3 — Wrong data has been set next to the **64-01-13 Preset Value** attribute and the calculated **64-01-33 Offset Value** is out-of-tolerance. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Encoder Settings parameters error (R)

bit 4 — Wrong data has been set next to the parameters in the **64-01-50 Encoder Settings (R)** attribute. Set proper values to restore the normal work condition.

Encoder Resolution parameters error (R)

bit 5 — Wrong data has been set next to the parameters in the **64-01-51 Encoder Resolution (R)** attribute. Set proper values to restore the normal work condition.

bits 6 and 7 — Not used

Byte 1 — **Not used**

64-01-67 Wrong Parameters List (L)

[UINT, Get, NV]

The operator has entered invalid data and the **Parameters Error** warning in the **64-01-2F Warnings** attribute has been triggered. This variable is meant to show (bit value = HIGH) the list of the wrong parameters, according to the following table.

Please note that the normal work status can be restored only after having set proper values.

Bit	Function	bit = 0	bit = 1
0	Total Measuring Range exceeded (L)	Warning not active	Warning active
1	Position Step Setting exceeded (L)	Warning not active	Warning active
2	Preset Value exceeded (L)	Warning not active	Warning active
3	Offset Value exceeded (L)	Warning not active	Warning active
4	Encoder Settings parameters error (L)	Warning not active	Warning active
5	Encoder Resolution attribute error (L)	Warning not active	Warning active
6 ... 15	not used		

Byte 0

Total Measuring Range exceeded (L)

bit 0 — Wrong data has been set next to the **64-01-11 Total Measuring Range (L)** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Position Step Setting exceeded (L)

bit 1 — Wrong data has been set next to the **64-01-10 Position Step Setting (L)** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Preset Value exceeded (L)

bit 2 — Wrong data has been set next to the **64-01-13 Preset Value** attribute. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Offset Value exceeded (L)

bit 3 — Wrong data has been set next to the **64-01-13 Preset Value** attribute and the calculated **64-01-33 Offset Value** is out-of-tolerance. The tolerances for the parameter have been exceeded. Set proper values to restore the normal work condition. The warning is cleared if the tolerances are again within normal parameters.

Encoder Settings parameters error (L)

bit 4 — Wrong data has been set next to the parameters in the **64-01-50 Encoder Settings (L)** attribute. Set proper values to restore the normal work condition.

Encoder Resolution attribute error (L)

bit 5 — Wrong data has been set next to the **64-01-51 Encoder Resolution (L)** attribute. Set proper values to restore the normal work condition.

bits 6 and 7 — Not used

Byte 1 — **Not used**

64-01-68 Command Register

[BYTE, Set, V]

This attribute contains some commands to be sent in real time to the encoder in order to manage it.

Bit	Function	bit = 1	bit = 0
0	**Activate Preset**	Activate	Finalize
1 ... 5	not used		
6	**Save Parameters**	Activate	Finalize
7	**Restore Parameters to Defaults**	Activate	Finalize

Byte 0

Activate Preset

bit 0

This command is used to activate a preset value in the encoder. As soon as the command is sent, the position value which is transmitted for the current encoder position is the one set next to the **64-01-13 Preset Value** attribute and all the previous and following positions will get a value according to it. The operation is performed at each rising edge of the bit, i.e. each time this bit is switched from logic level low ("0") to logic level high ("1"). Then the bit must be switched back to logic level low ("0") to finalize the command. When the command is sent, the current encoder position is saved temporarily in the **64-01-33 Offset Value** attribute. For any further information on the preset function and the meaning and use of the related attributes and commands **64-01-13 Preset Value**, **64-01-33 Offset Value** and **Activate Preset** refer to page 113.

NOTE

Please note that as soon as the preset value is entered next to the **64-01-13 Preset Value** attribute, it is also automatically activated, so you do not need to use this command. Use the **Activate Preset** command to activate a preset value that has been already set next to the **64-01-13 Preset Value** attribute and you want to set for a different position of the travel.

WARNING

To save permanently the current encoder position in the **64-01-33 Offset Value** attribute, please execute the **Save Parameters** command. Should the power supply be turned off without saving data, the **64-01-33 Offset Value** that has not been saved will be lost!

bits 1 ... 5

Not used

Save Parameters

bit 6

This function allows to save all parameters on non-volatile memory. Data is saved on non-volatile memory at each rising edge of the bit; in other words, data save is performed each time this bit is switched from logic level low ("0") to logic level high ("1"). Then the bit must be switched back to logic level low ("0") to finalize the command.

NOTE

Always save the new values after setting in order to store them in the non-volatile memory permanently.
Should the power supply be turned off all data that has not been saved previously will be lost!

NOTE

To save the new values in the non-volatile memory permanently you can use also the Class Service 16h, see on page 97.

Restore Parameters to Defaults

bit 7

This function allows the operator to restore all parameters to default values (default values are set at the factory by Lika Electronic engineers to allow the operator to run the device for standard operation in a safe mode). This function can be useful, for instance, to restore the factory values in case the encoder is set incorrectly and you are not able to resume the proper operation.
Default parameters are restored at each rising edge of the bit; in other words, the default parameters uploading operation is performed each time this bit is switched from logic level low ("0") to logic level high ("1"). Then the bit must be switched back to logic level low ("0") to finalize the command. The complete list of machine data and relevant default parameters preset by Lika Electronic engineers is available on page 176.

WARNING

The execution of this command causes all parameters which have been set previously to be overwritten!

64-01-69 Warning/Alarm Flags

[BYTE, Get, NV]
This attribute is used in conjunction with the I/O assembly data attributes, refer to the "6.12.3.6 I/O Assembly Data Attribute Format" section on page 94.
Its value is **00h** ($0000\ 0000_2$) when neither warnings nor alarms are active.
Its value is **01h** ($0000\ 0001_2$) when alarms are active.
Its value is **02h** ($0000\ 0010_2$) when warnings are active.
Its value is **03h** ($0000\ 0011_2$) when both warnings and alarms are active.
See the byte 4 of Instance 02h on page 94.

64-01-6A Encoder Serial Number

[UDINT, Get, NV]
This attribute contains the serial number of the converter assigned by the manufacturer. This is not the same as the Identity Object's serial number (see **01-01-06 Serial number** attribute on page 90) which is used to uniquely identify the device in the network environment. It can be read in the label applied to the device enclosure.
The meaning of the 32 bits in the attribute is as follows:

Bit	31 ... 24	23 ... 16	15 ... 0
	YoP	WoP	Serial number

YoP: year of production.
Wop: week of production.
Serial number: serial number in ascending order.

Default = Device dependent

64-01-6C Network-DSC Serial Number

[UDINT, Get, NV]
This attribute contains the serial number of the Network DSC (Digital Signal Controller).
Default = Device dependent

6.12.6 Class F5h: TCP/IP Interface Object

Class Code	Object Class	Access	Nr. of Instances
F5h	TCP/IP Interface Object	Get	1

The TCP/IP Interface Object provides the mechanism to configure the TCP/IP network interface of a device. Examples of configurable items include the device's IP Address, Network Mask, and Gateway Address.
For complete information on TCP/IP Interface Object attributes refer to the publication "The CIP Networks Library. Volume 2. EtherNet/IP Adaptation of CIP".

6.12.6.1 Supported Class Services

The supported **Class Services** of the TCP/IP Interface Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.6.2 Class Attributes

F5-01 Revision

[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0004h.
Default = 0004h

F5-02 Max Instance

[UINT, Get, NV]
The largest instance number of a created object in this class.
Default = 0001h

F5-03 Number of Instances

[UINT, Get, NV]
The number of object instances in this class.
Default = 0001h

6.12.6.3 Supported Instance Services

The supported **Instance Services** of the TCP/IP Interface Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.
10h = Set_Attribute_Single: used to write connection class attribute value.

6.12.6.4 Instance Attributes

F5-01-01 Status

[DWORD, Get, V]

This attribute represents the current status of the interface. Its value changes as the state of the interface changes. The Status attribute is a DWORD, with the following bit definitions:

Bit(s)	Called	Definition
0 ... 3	Interface Configuration Status	It indicates the status of the F5-01-05 Interface Configuration attribute. 0 = the F5-01-05 Interface Configuration attribute has not been configured. 1 = the F5-01-05 Interface Configuration attribute contains configuration obtained from DHCP or non-volatile storage. 2 = the F5-01-05 Interface Configuration attribute contains configuration from hardware settings. 3 ... 15 = reserved for future use
4	Mcast Pending	If set to 1 it indicates a multicast pending configuration.
5	Interface Configuration Pending	If set to 1 it indicates an interface pending configuration. A new configuration will be loaded at next reset.
6	AcdStatus	It indicates when an IP address conflict has been detected by ACD. To enable/disable the ACD refer to F5-01-0A SelectAcd attribute on page 140.
7	AcdFault	It indicates when an IP address conflict has been detected by ACD or the defense failed, and that the current Interface Configuration cannot be used due to this conflict.
8 ... 31	Reserved	Reserved, shall be 0

F5-01-02 Configuration Capability

[DWORD, Get, NV]

It indicates the method of obtaining an initial IP address.

Bit(s)	Called	Definition
0 1 2 3	**BOOTP Client** **DNS Client** **DHCP Client** **DHCP-DNS Update**	It is set to 4 (0010_2): the converter is able of obtaining its network configuration via DHCP.
4	**Configuration Settable**	If set to 1, it indicates that the F5-01-05 Interface Configuration attribute is settable.

5	**Hardware Configurable**	The converter is hardware configurable when the bit is set to 1.
6	**Reset Required at change**	It is always set to 0.
7	**AcdCapable**	If set to 1, the converter is capable of detecting address conflicts (ACD capable). See the F5-01-0A SelectAcd attribute on page 140.
8 ... 31	Reserved	Reserved, shall be 0

F5-01-03 Configuration Control

[DWORD, Get/Set, NV]
It is used to control network configuration options.
When its value is **0**, the device shall use statically-assigned IP configuration values from non-volatile memory.
When its value is **2**, the device shall obtain the interface configuration values from DHCP.

F5-01-04 Physical Link Object

[Struct of, Get, NV]
This attribute identifies the object associated with the underlying physical communications interface.

Path size
[UINT] Size of path (0002h).

Path
[Padded EPATH] Path to Ethernet Link Object, F6-01-03 Physical Address instance, see on page 143 (20 F6 24 03h).

F5-01-05 Interface Configuration

[Struct of, Get/Set, V/NV]

IP Address
[UDINT] The device's IP address (192.168.1.10).

Network Mask
[UDINT] The device's network mask (255.255.255.0).

Gateway Address
[UDINT] The IP address of the device's default gateway (0.0.0.0).

Name Server
[UDINT] Primary DNS.

Name Server 2
[UDINT] Secondary DNS.

Domain Name
[STRING] The default domain name.

F5-01-06 Host Name

[STRING, Get/Set, NV]
It contains the device's host name, which can be used for informational purposes.

F5-01-08 TTL Value

[USINT, Get/Set, NV]
The device shall use the TTL value for the IP header Time-to-live field when sending EtherNet/IP packets via IP multicast.
Default = 1

F5-01-09 Mcast Config

[Struct of, Set, NV]
It contains the configuration of the device's IP multicast addresses to be used for EtherNet/IP multicast packets.

Alloc Control
[USINT] 0 = multicast addresses shall use be generated using the default allocation algorithm according to specifications. 1 = multicast addresses shall be allocated according to the values specified in **Num Mcast** and **Mcast Start Addr** parameters.

(reserved)
[USINT] set to 0, do not change.

Num Mcast
[UINT] Number of IP multicast addresses allocated (1).

Mcast Start Addr
[UDINT] Starting multicast address from which **Num Mcast** addresses are allocated.

F5-01-0A SelectAcd

[BOOL, Set, NV]
It allows to enable / disable Address Conflict Detection (ACD). If ACD is enabled, as soon as an address conflict is detected, the bit 6 **AcdStatus** in the **F5-01-01 Status** attribute will be set to 1 and NS Network State Error LED will light on red.
0 = Disable ACD
1 = Enable ACD
Default = 1

F5-01-0B LastConflictDetected

[Struct of, Set, NV]
It is a diagnostic attribute presenting information about the ACD state when the last IP address conflict was detected.

AcdActivity
[USINT] State of the ACD algorithm when the last IP address conflict was detected.

RemoteMAC
[Array of 6 USINTs] The IEEE 802.3 source MAC address from the header of the received Ethernet packet sent by the device when reporting the conflict.

ArpPDU
[Array of 28 USINTs] The ARP Response PDU in binary format.

F5-01-0C EtheNet/IP QuickConnect

[BOOL, Set, NV]
It shall enable (1) or disable (0) the EtherNet/IP QuickConnect feature. If EtherNet/IP QuickConnect is enabled, it will direct EtherNet/IP target devices to quickly power up and join an EtherNet/IP network.
Default = 0

F5-01-0D Encapsulation Inactivity Timeout

[UINT, Set, NV]
Number of seconds with no Encapsulation activity before the TCP connection is closed. It is disabled (0).
Default = 0 (min. value 0, max. value 3600)

6.12.7 Class F6h: Ethernet Link Object

Class Code	Object Class	Access	Nr. of Instances
F6h	Ethernet Link Object	Get	1

The EtherNet Link Object maintains link-specific counters and status information for an IEEE 802.3 communications interface such as transmission speed, interface status and the MAC address.

6.12.7.1 Supported Class Services

The supported **Class Services** of the Ethernet Link Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.7.2 Class Attributes

F6-01 Revision

[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0004h.
Default = 0004h

F6-02 Max Instance

[UINT, Get, NV]
The largest instance number of a created object in this class (1 or 3).
Default = 0003h

F6-03 Number of Instances

[UINT, Get, NV]
The number of object instances in this class (1 or 3).
Default = 0003h

6.12.7.3 Supported Instance Services

The supported **Instance Services** of the Ethernet Link Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.
10h = Set_Attribute_Single: used to write connection class attribute value.
4Ch = Get_And_Clear: used to get and then clear the specified attribute.

6.12.7.4 Instance Attributes

F6-01-01 Interface Speed

[UDINT, Get, V]
Interface speed currently in use, expressed in Mbps (10 or 100).

F6-01-02 Interface Flags

[DWORD, Get, V]
Interface status flags, according to the following table.

Bit(s)	Called	Definition
0	Link Status	It indicates whether or not the IEEE 802.3 communications interface is connected to an active network. 0 indicates an inactive link; 1 indicates an active link.
1	Half/Full Duplex	It indicates the duplex mode currently in use. 0 indicates the interface is running half duplex; 1 indicates full duplex. If the Link Status flag is 0, then the value of the Half/Full Duplex flag is indeterminate.
2 ... 4	Negotiation Status	It indicates the status of link auto-negotiation. 0 = Auto-negotiation in progress 1 = Auto-negotiation and speed detection failed. Using default values. Recommended defaults are 10 Mbps and half duplex. 2 = Auto-negotiation failed but detected speed. Duplex was defaulted. 3 = Successfully negotiated speed and duplex. 4 = Auto-negotiation not attempted. Forced speed and duplex.
5	Manual Setting Requires Reset	It is 0 when the interface can activate changes to link parameters during runtime. It is 1 when reset is required in order for changes to take effect.
6	Local Hardware Fault	0 indicates the interface detects no local hardware fault; 1 indicates a local hardware fault is detected.
7 ... 31	Reserved	Reserved, shall be 0

F6-01-03 Physical Address

[Array of 6 UINTs, Get, NV]
MAC ID. This attribute contains the physical network address, i.e. the assigned MAC address.

F6-01-04 Interface Counters

[Struct of, Get, V]
This attribute contains counters relevant to the receipt of packets on the interface.

In Octets
[UDINT] Octets received on the interface.

In Ucast Packets
[UDINT] Unicast packets received on the interface.

In NUcast Packets
[UDINT] Non-unicast packets received on the interface.

In Discards
[UDINT] Inbound packets received on the interface but discarded.

In Errors
[UDINT] Inbound packets that contain errors (does not include **In Discards**).

In Unknown Protos
[UDINT] Inbound packets with unknown protocol.

Out Octets
[UDINT] Octets sent on the interface.

Out Ucast Packets
[UDINT] Unicast packets sent on the interface.

Out NUcast Packets
[UDINT] Non-unicast packets sent on the interface.

Out Discards
[UDINT] Outbound packets discarded.

Out Errors
[UDINT] Outbound packets that contain errors (does not include **Out Discards**).

F6-01-05 Media Counters

[Struct of, Get, V]
This attribute contains counters specific to Ethernet media.

Alignment Errors
[UDINT] Frames received that are not integral number of octets in length.

FCS Errors
[UDINT] Frames received that do not pass the FCS check.

Single Collisions
[UDINT] Successfully transmitted frames which experienced exactly one collision.

Multiple Collisions
[UDINT] Successfully transmitted frames which experienced more than one collision.

SQE Test Errors
[UDINT] Number of times SQE test error message is generated.

Deferred Transmissions
[UDINT] Frames for which first transmission attempt is delayed because the medium is busy.

Late Collisions
[UDINT] Number of times a collision is detected later than 512 bit-times into the transmission of a packet.

Excessive Collisions
[UDINT] Frames for which transmission fails due to excessive collisions.

MAC Transmit Errors
[UDINT] Frames for which transmission fails due to an internal MAC sublayer transmit error.

Carrier Sense Errors
[UDINT] Times that the carrier sense condition was lost or never asserted when attempting to transmit a frame.

Frame Too Long
[UDINT] Frames received that exceed the maximum permitted frame size.

MAC Receive Errors
[UDINT] Frames for which reception on an interface fails due to an internal MAC sublayer receive error.

F6-01-06 Interface Control

[Struct of, Get/Set, NV]
This attribute is a structure consisting of the following parameters.

Control Bits
[WORD] Interface control bits.

Bit(s)	Called	Definition
0	**Auto-negotiate**	0 indicates that 802.3 link auto-negotiation is disabled. 1 indicates that auto-negotiation is enabled. If auto-negotiation is disabled,

		then the device shall use the settings indicated by the Forced Duplex Mode and Forced Interface Speed bits.
1	**Forced Duplex Mode**	If the **Auto-negotiate** bit is 0, the **Forced Duplex Mode** bit indicates whether the interface shall operate in full or half duplex mode. 0 indicates that the interface duplex should be half duplex. 1 indicates that the interface duplex should be full duplex. Interfaces not supporting the requested duplex shall return status code 0x09 (**Invalid Attribute Value**). If auto-negotiation is enabled, attempting to set the **Forced Duplex Mode** bit shall result in status code 0x0C (**Object State Conflict**).
2 ... 15	Reserved	Reserved, shall be 0

Forced Interface Speed
[UINT] If the **Auto-negotiate** bit is 0, the **Forced Interface Speed** bits indicate the speed at which the interface shall operate. Speed is specified in megabits per second (e.g., for 10 Mbps Ethernet, the Interface Speed shall be 10).

F6-01-07 Interface Type

[USINT, Get, NV]
This attribute indicates the type of the physical interface according to the following table.

Instance	Value	Type of interface
1	2	Twisted-pair
2	2	Twisted-pair
3	1	The interface is internal to the device

F6-01-08 Interface State

[USINT, Get, V]
This attribute indicates the current operational state of the interface according to the following table.

Value	Interface State
0	Unknown interface state
1	The interface is enabled and is ready to send and receive data
2	The interface is disabled
3	The interface is testing

4 ... 255	Reserved

F6-01-09 Admin State

[USINT, Set, V]
This attribute allows administrative setting of the interface state according to the following table.

Value	Admin State
0	Reserved
1	Enable the interface
2	Disable the interface
3 ... 255	Reserved

F6-01-0A Interface Label

[SHORT_STRING, Get, NV]
This attribute is a string that describes the interface according to the following table.

Instance	Value
1	Port 1
2	Port 2
3	Internal

F6-01-0B Interface Capability

[Struct of, Get, NV]
This attribute indicates the set of capabilities for the interface according to the following table.

Bit(s)	Called	Definition
0	**Manual Setting Requires Reset**	It indicates whether or not the device requires a reset to apply changes made to the F6-01-06 Interface Control attribute. 0 = It indicates that the device automatically applies changes made to the F6-01-06 Interface Control attribute and, therefore, does not require a reset in order for changes to take effect. This is the value this bit shall have when the F6-01-06 Interface Control attribute is not implemented. 1 = It indicates that the device does not automatically apply changes made to the F6-01-06 Interface Control attribute and,

		therefore, will require a reset in order for changes to take effect. Note: this bit shall also be replicated in the **F6-01-02 Interface Flags** attribute in order to retain backwards compatibility with previous object revisions.
1	**Auto-negotiate**	0 = It indicates that the interface does not support link auto-negotiation (internal interface) 1 = It indicates that the interface supports link auto-negotiation (external interface)
2	**Auto-MDIX**	0 = It indicates that the interface does not support auto MDIX operation (internal interface) 1 = It indicates that the interface supports auto MDIX operation (external interface)
3	**Manual Speed/Duplex**	0 = It indicates that the interface does not support manual setting of speed/duplex. The **F6-01-06 Interface Control** attribute shall not be supported (internal interface) 1 = It indicates that the interface supports manual setting of speed/duplex via the **F6-01-06 Interface Control** attribute (external interface)
4 ... 31	Reserved	Reserved, shall be 0

6.12.8 Class 47h: Device Level Ring (DLR) Object

Class Code	Object Class	Access	Nr. of Instances
47h	Device Level Ring (DLR) Object	Get	1

The Device Level Ring (DLR) Object provides the configuration and status information interface for the DLR protocol. The DLR protocol is a layer 2 protocol that enables the use of an Ethernet ring topology. The DLR Object provides the CIP application-level interface to the protocol. The DLR protocol is fully specified in Chapter 9 of the publication "THE CIP NETWORKS LIBRARY, Volume 2, EtherNet/IP Adaptation of CIP".

6.12.8.1 Supported Class Services

The supported **Class Services** of the Device Level Ring (DLR) Object are:
01h = Get_Attribute_All: used to read the value of all attributes.
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.8.2 Class Attributes

47-01 Revision

[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0003h.
Default = 0003h

6.12.8.3 Supported Instance Services

The supported **Instance Services** of the Device Level Ring (DLR) Object are:
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.8.4 Instance Attributes

47-01-01 Network Topology

[USINT, Get, V]
It indicates the current network topology mode. A value of "0" indicates "Linear" topology; a value of "1" indicates "Ring" topology.

47-01-02 Network Status

[USINT, Get, V]
This attribute provides current status of the network based on the device's view of the network, according to the following table.

Network Status value	Description
0	Normal operation in both Ring and Linear Network Topology modes.

1	Ring Fault. A ring fault has been detected. Valid only when **47-01-01 Network Topology** is "1" = Ring.
2	Unexpected Loop Detected. A loop has been detected in the network. Valid only when **47-01-01 Network Topology** is "0" = Linear.
3	Partial Network Fault. A network fault has been detected in one direction only. Valid only when **47-01-01 Network Topology** is "1" = Ring and the node is the active ring supervisor.
4	Rapid Fault/Restore Cycle. A series of rapid ring fault/restore cycles has been detected. Similar to the Partial Network Fault status (3), the supervisor remains in a state with forwarding blocked on its ring ports. The condition must be cleared explicitly via the "Clear Rapid Faults" service.

47-01-0A Active Supervisor Address

[Struct of, Get, V]

This attribute contains the IP address (IPv4) and/or Ethernet MAC address of the active ring supervisor. The initial values of IP address and Ethernet MAC address shall be 0, until the active ring supervisor is determined.

47-01-0C Capability Flags

[DWORD, Get, NV]

The Capability Flags describe the DLR capabilities of the device, according to the following table.

Bit(s)	Called	Definition
0	**Announce-based Ring Node**	It sets if device's ring node implementation is based on processing of Announce frames.
1	**Beacon-based Ring Node**	It sets if device's ring node implementation is based on processing of Beacon frames.
2 ... 4	Reserved	Reserved, shall be 0
5	**Supervisor Capable**	It sets if device is capable of providing the supervisor function.
6	**Redundant Gateway Capable**	It sets if device is capable of providing the redundant gateway function.
7	**Flush_Table Frame Capable**	It sets if device is capable of supporting the Flush_Tables frame.
8 ... 31	Reserved	Reserved, shall be 0

Default = 0082h = **Beacon-based Ring Node** + **Flush_Table Frame Capable**

6.12.9 Class 48h: Quality of Service (QoS) Object

Class Code	Object Class	Access	Nr. of Instances
48h	Quality of Service (QoS) Object	Get	1

The Quality of Service (QoS) Object is used to treat traffic streams with different relative priorities or other delivery characteristics. Standard QoS mechanisms include IEEE 802.1D/Q (Ethernet frame priority) and Differentiated Services (DiffServ) in the TCP/IP protocol suite.
The QoS Object provides a means to configure certain QoS-related behaviors in EtherNet/IP devices.
The QoS Object is required for devices that support sending EtherNet/IP messages with non-zero DiffServ code points (DSCP), or sending EtherNet/IP messages in 802.1Q tagged frames.

6.12.9.1 Supported Class Services

The supported **Class Services** of the Quality of Service (QoS) Object are:
0Eh = Get_Attribute_Single: used to read the value of an attribute.

6.12.9.2 Class Attributes

47-01 Revision

[UINT, Get, NV]
Object revision. The current value assigned to this attribute is 0001h.
Default = 0001h

6.12.9.3 Supported Instance Services

The supported **Instance Services** of the Quality of Service (QoS) Object are:
0Eh = Get_Attribute_Single: used to read the value of an attribute.
10h = Set_Attribute_Single: used to write connection class attribute value.

6.12.9.4 Instance Attributes

48-01-01 802.1Q Tag Enable

[USINT, Set, NV]
This attribute enables (1) or disables (0) sending 802.1Q frames on CIP and IEEE 1588 messages. When the attribute is enabled, the device shall send 802.1Q frames for all CIP and IEEE 1588 messages.

48-01-04 DSCP Urgent

[USINT, Set, NV]
DSCP value for CIP transport class 1 Urgent priority messages.
Default = 55

48-01-05 DSCP Scheduled

[USINT, Set, NV]
DSCP value for CIP transport class 1 Scheduled priority messages.
Default = 47

48-01-06 DSCP High

[USINT, Set, NV]
DSCP value for CIP transport class 1 High priority messages.
Default = 43

48-01-07 DSCP Low

[USINT, Set, NV]
DSCP value for CIP transport class 1 Low priority messages.
Default = 31

48-01-08 DSCP Explicit

[USINT, Set, NV]
DSCP value for CIP explicit messages (transport class 3 and UCMM) and all other EtherNet/IP encapsulation messages.
Default = 27

7 - Integrated Web Server

7.1 Integrated web server – Preliminary information

EtherNet/IP converters from Lika Electronic integrate a web server. This web-based user interface is designed to offer helpful functions and deliver complete information on the device that can be accessed through the Internet.
In particular it allows:

- to display and check the currently set parameters;
- to set the network communication parameters;
- to set some parameters such as the preset and the code sequence;
- to upgrade the firmware;
- to monitor the encoder and access some advanced maintenance functions.

The web server can be accessed from any PC running a web browser. Since its only requirement is a HTTP connection between the web browser and the web server running on the device, it is perfectly fitted also for remote access scenarios.

Before opening the EtherNet/IP converter web server please ascertain that the following requirements are fully satisfied:

- the converter is connected to the network;
- the converter has valid IP address;
- the PC is connected to the network;
- a web browser (Internet Explorer, Mozilla Firefox, Google Chrome, Opera, ...) is installed in the PC or in the device used for connection.

NOTE
This web server has been tested and verified using the following web browsers:

- Internet Explorer IE11 version 11.1593.14393.0
- Mozilla Firefox version 55.0.3
- Google Chrome version 60.0.3112.113
- Opera version 47.0.2631.80

NOTE
Please note that the snapshot look may vary depending on the used web browser. The following snapshots have been taken from Mozilla Firefox.

7.2 Web server Home page

To open the EtherNet/IP converter web server proceed as follows:

1. type the IP address of the converter you want to connect to (in the example: 192.168.1.10, this is the default software IP address set at Lika, see on page 34) in the address bar of your web browser and confirm by pressing **ENTER**;

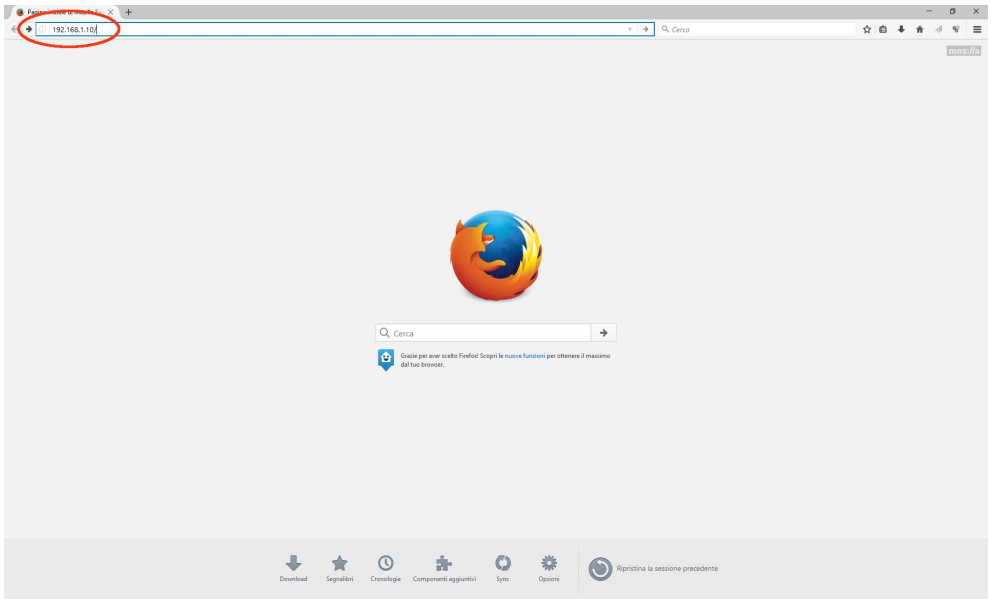


Figure 45 - Opening the web server

2. as soon as the connection is established, the web server **Home** page will appear on the screen;

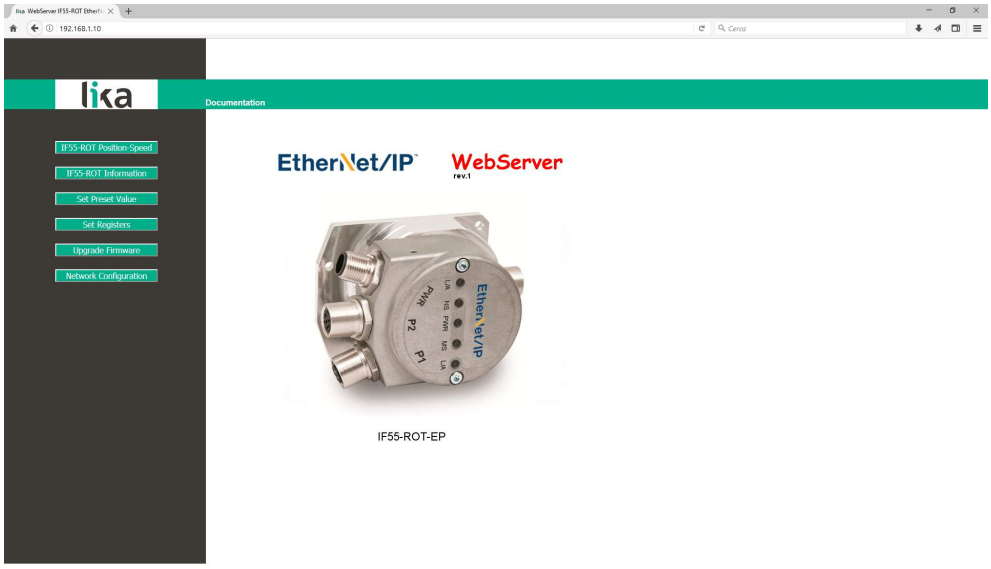


Figure 46 - Web server Home page (converter for rotary encoders)

Some commands are available in the menu bar of the **Home** page.
Press on the **Lika logo** to enter Lika's web site (www.lika.biz).

Press the **Documentation** command to enter the EtherNet/IP converter technical documentation page available on Lika's web site (http://www.lika.it/eng/prodotti.php?id_titolo=IF55) where specific technical information and documentation concerning the EtherNet/IP converter can be found.

Furthermore some commands are available in the left navigation bar. All the pages that can be entered through the commands in the bar are freely accessible except the **Upgrade firmware** page that is protected and requires a password to allow access.
These commands allow to enter specific pages where information and diagnostics on the connected encoder as well as useful functions can be achieved.
They are described in the following sections.

7.3 Encoder position and speed

Press the **IF55-ROT Position-Speed** / **IF55-LIN Position-Speed** command in the left navigation bar of the Web server **Home** page to enter the page where the current encoder position and the current encoder speed are displayed.

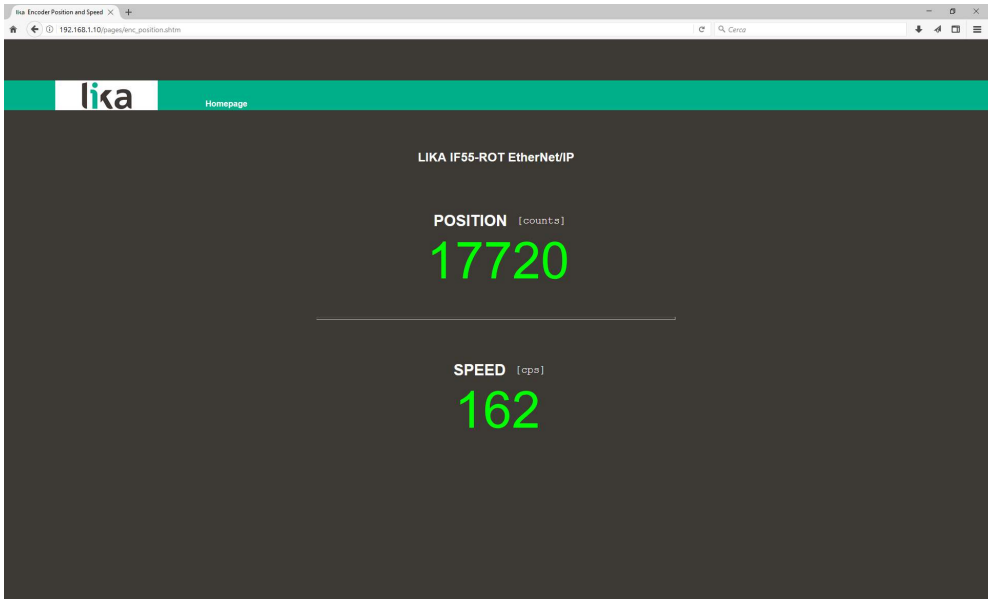


Figure 47 - Encoder position and speed page (converter for rotary encoders)

The current encoder position is expressed in counts. For any information refer to the **64-01-03 Position value (R)** attribute on page 98 -converter for rotary encoders; to the **64-01-03 Position value (L)** attribute on page 98 -converter for linear encoders.

The current rotary encoder speed is expressed according to the setting next the **64-01-19 Velocity Format (R)** attribute on page 115 (by default it is expressed in counts per second). For any information refer to the **64-01-18 Velocity Value** attribute on page 115.
The current linear encoder speed is expressed according to the setting next the **64-01-19 Velocity Format (L)** attribute on page 115 (by default it is expressed in counts per second). For any information refer to the **64-01-18 Velocity Value** attribute on page 115.

NOTE
The current encoder position and speed values are real-time processed and continuously updated (every 200 msec. on the screen).

Press the **Homepage** command to move back to the Web server **Home** page.

7.3.1 Specific notes on using Internet Explorer

The following options must be set properly on Internet Explorer in order to get the **Encoder position and speed** page to be continuously updated.

- Open the **Settings** menu;
- open the **Internet Options** property sheet;
- in the **General** tabbed page, press the **Setting** button available in the **History Browsing** section;
- under **Check for newer versions of stored pages**, click **Every time I visit the webpage**;
- press the **OK** button to confirm whenever requested.

7.4 Converter information (EtherNet/IP attributes)

Press the **IF55-ROT Information** command in the left navigation bar of the Web server **Home** page to enter the **IF55-ROT-EP Information** page (converter for rotary encoders). Press the **IF55-LIN Information** command in the left navigation bar of the Web server **Home** page to enter the **IF55-LIN-EP Information** page (converter for linear encoders). In this page the complete list of the available EtherNet/IP attributes is displayed. Attributes are expressed in decimal notation, values are expressed in either hexadecimal or decimal notation. The MAC address of the connected converter is shown under the name of the page.

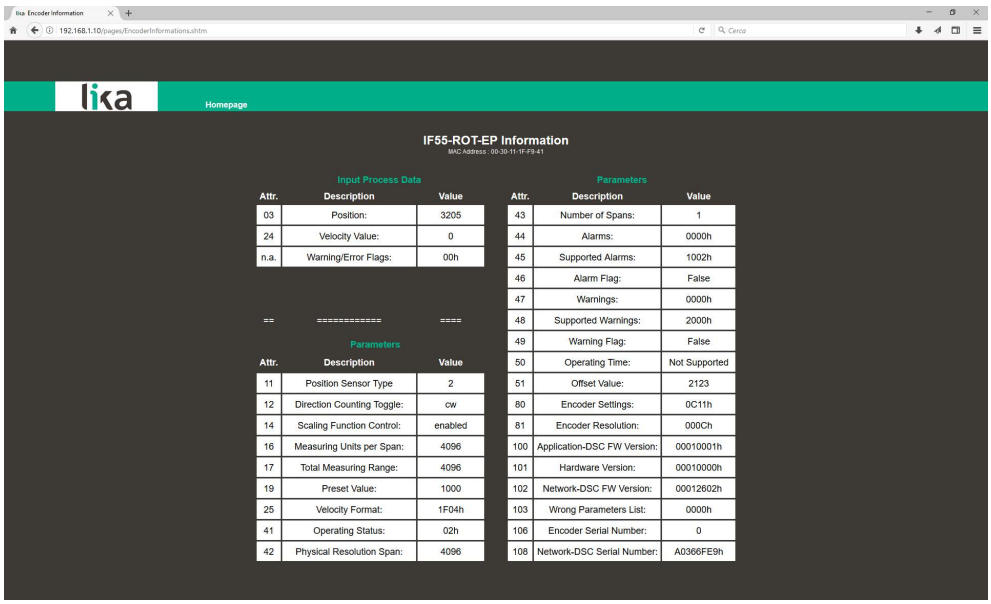


Figure 48 - IF55-ROT-EP Information page

Figure 49 - IF55-LIN-EP Information page

The attributes listed under the **Input Process Data** section are process data and read-only (Get) access values.
The attributes listed under the **Parameters** section are the converter configuration parameters; they can be either read-write (Set) or read-only (Get) access parameters.
For a complete description of the available converter attributes please refer to the "6.12.5 Class 64h: Application Object" section on page 97.

NOTE
Please note that the values shown in the **IF55-ROT-EP Information** / **IF55-LIN-EP Information** page are "frozen" in the moment when the page is displayed. To update the values you must refresh the web page.

NOTE
The attributes in the **IF55-ROT-EP Information** / **IF55-ROT-EP Information** page cannot be changed even though they are read-write access attributes. To change the set values please enter the **Set Registers** page (see on page 161).

Press the **Homepage** command to move back to the Web server **Home** page.

7.5 Setting the Preset value

Press the **Set Preset Value** command in the left navigation bar of the Web server **Home** page to enter the **Set IF55-ROT-EP Preset** / **Set IF55-LIN-EP Preset** page and set/activate a Preset value. For complete information on the preset function please refer to the **64-01-13 Preset Value** attribute on page 113.

A soon as you press the **Set Preset Value** command a warning message (**Are you sure you want to change Preset Value?**) appears on the screen: it warns the operator about the awkwardness of the operation, thus he is required to confirm the procedure before continuing.

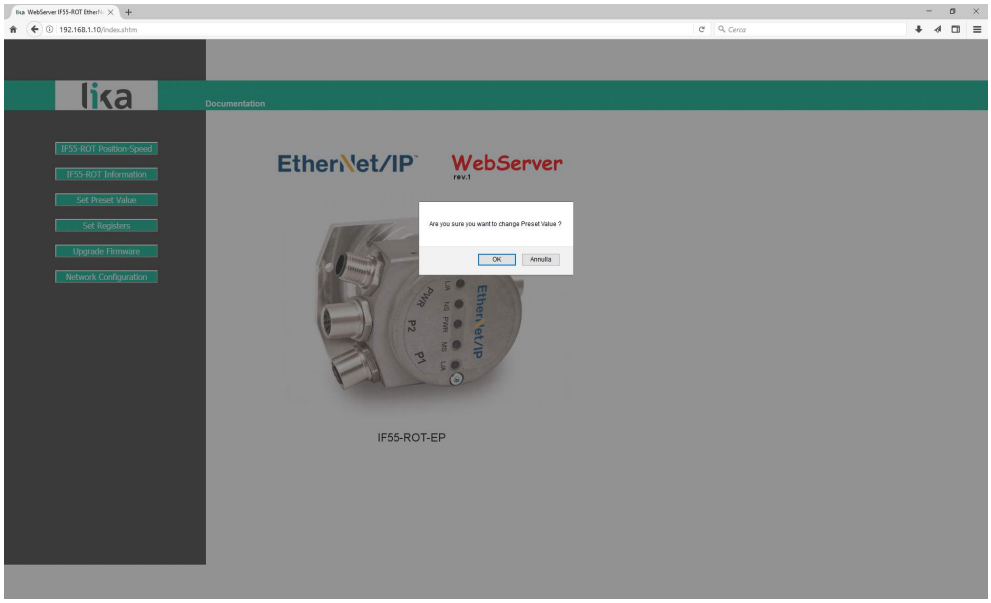


Figure 50 - Entering the Set IF55-ROT-EP Preset page (converter for rotary encoders)

Press the **OK** button to proceed.

Otherwise press the **EXIT** button to abort the procedure. The **Set Preset cancelled!** message will appear on the screen. Press the **OK** button to move back to the Web server **Home** page.

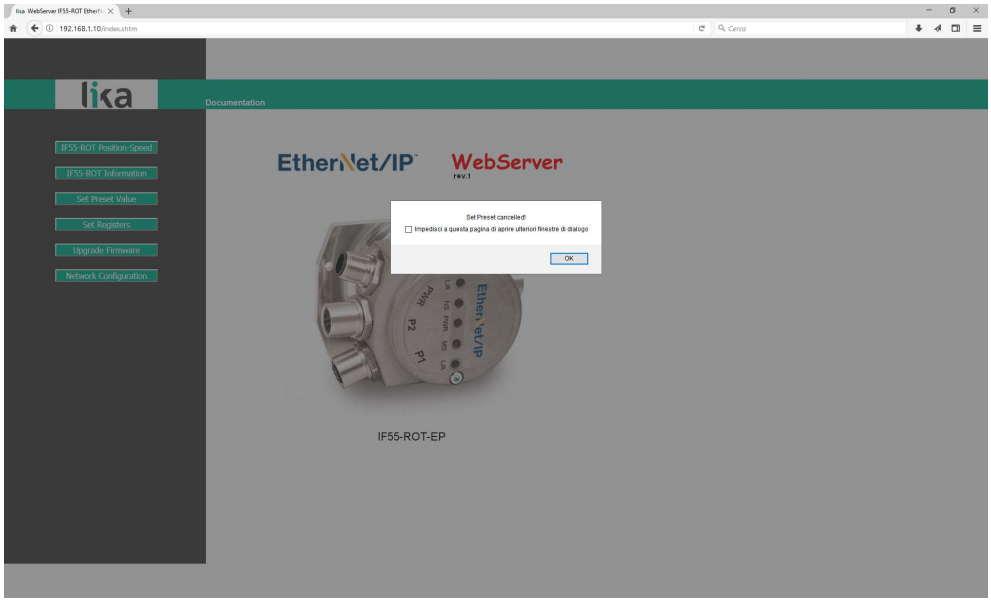


Figure 51 - Preset operation aborted (converter for rotary encoders)

If you confirm the procedure, the **Set IF55-ROT-EP Preset** / **Set IF55-LIN-EP Preset** page will appear on the screen:

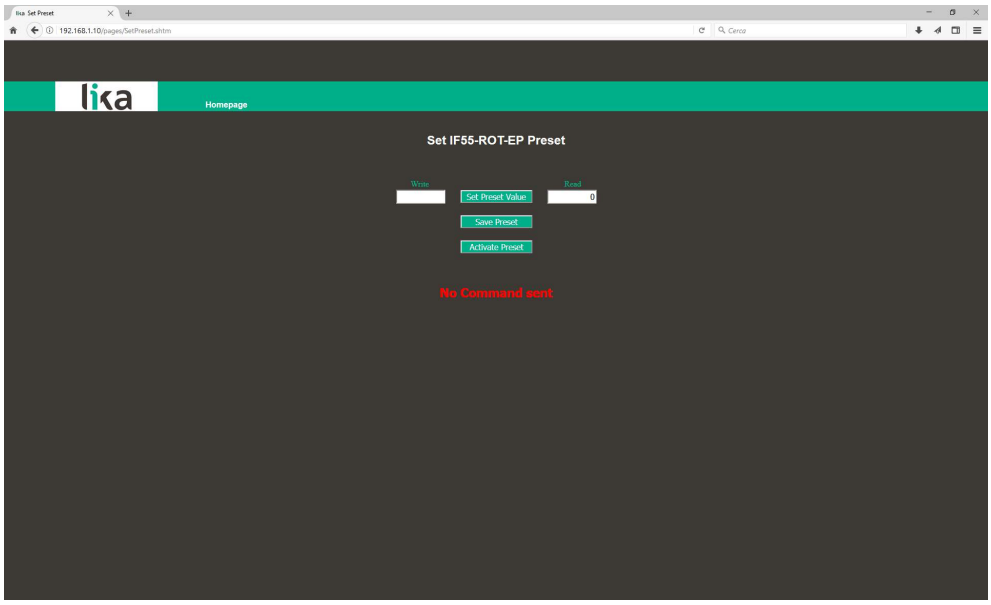


Figure 52 - Set IF55-ROT-EP Preset page (converter for rotary encoders)

The Preset value that is currently set in the encoder (see the 64-01-13 Preset Value attribute on page 113) will be displayed in the **READ** box.

To change the Preset enter a suitable value in the **WRITE** box and then press the **Set Preset Value** button to confirm. The value has to be set in decimal notation.

NOTE
Please note that the Preset value is now saved temporarily in the **64-01-13 Preset Value** attribute. To save permanently the set Preset value in the **64-01-13 Preset Value** attribute, please press the **Save Preset** button. Should the power supply be turned off without saving data, the Preset value that has not been saved on the Flash EEProm will be lost!

The preset value is set and activated for the position of the encoder in the moment when the preset value is transmitted. It is activated as soon as the value is confirmed by pressing the **Set Preset Value** button. We suggest activating the preset value when the encoder is in stop.
If you need to activate a value already set next to the **64-01-13 Preset Value** and displayed in the **READ** box in a different physical position of the encoder shaft, press the **Activate Preset** button, refer to the bit 0 **Activate Preset** in the **64-01-68 Command Register** attribute, see on page 134.

NOTE
At each confirmation and/or activation of the Preset setting, a message will appear under the buttons (see **No Command sent** message). It informs whether the operation has been accomplished properly or an error occurred (for example **Command was set correctly** if everything went well; or **Command Error!** if something went wrong).

Press the **Homepage** command to move back to the Web server **Home** page.

7.6 Setting the attributes

Press the **Set Registers** command in the left navigation bar of the Web server **Home** page to enter the **Set IF55-ROT-EP Registers** page (converter for rotary encoders); the **Set IF55-LIN-EP Registers** page (converter for linear encoders). In this page the read-write (Set) access EtherNet/IP converter attributes available in the Application Object (Class 64h) are displayed and their value can be changed.
For complete information on the converter attributes please refer to the "6.12.5 Class 64h: Application Object" section on page 97.

A soon as you press the **Set Registers** command a warning message (**Are you sure you want to change Registers Values?**) appears on the screen: it warns the operator about the awkwardness of the operation, thus he is required to confirm the procedure before continuing.

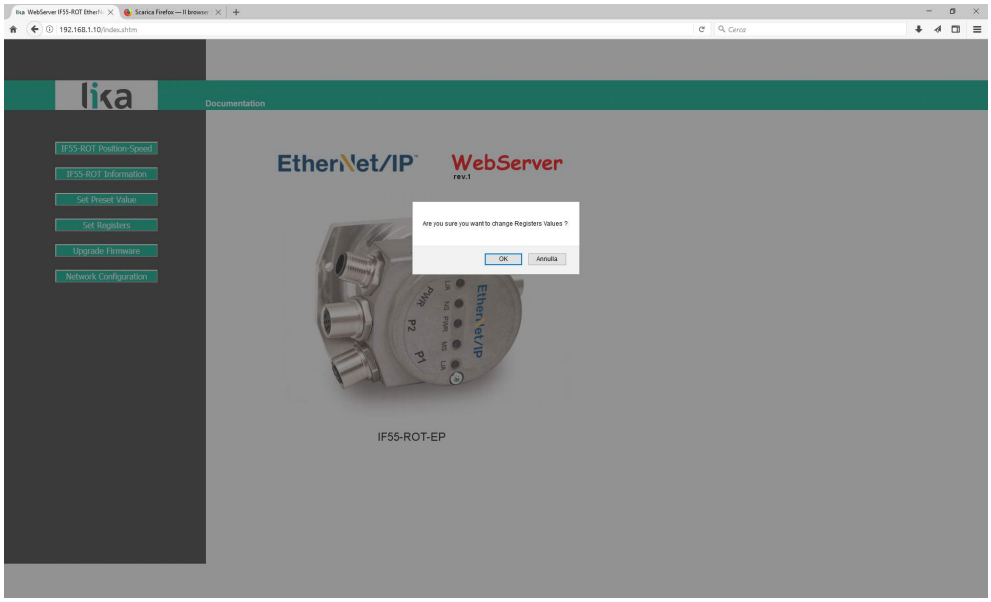


Figure 53 - Entering the Set IF55-ROT-EP Registers page (converter for rotary encoders)

Press the **OK** button to proceed, otherwise press the **EXIT** button to abort the procedure. The **Set Registers cancelled!** message will appear on the screen. Press the **OK** button to move back to the Web server **Home** page.

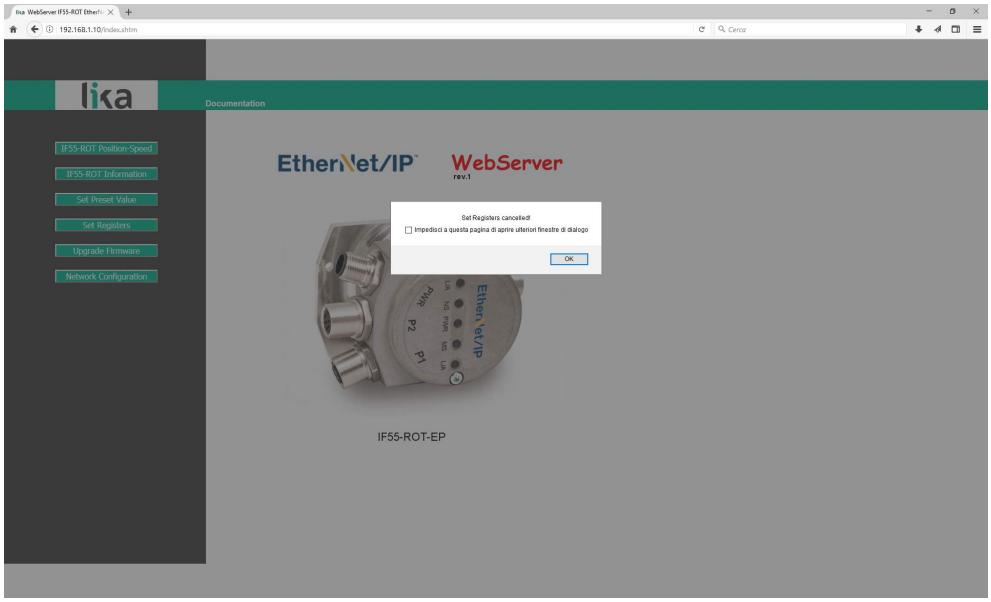


Figure 54 - Register setting operation aborted (converter for rotary encoders)

If you confirm the procedure, the **Set IF55-ROT-EP Registers** / **Set IF55-LIN-EP Registers** page will appear on the screen:

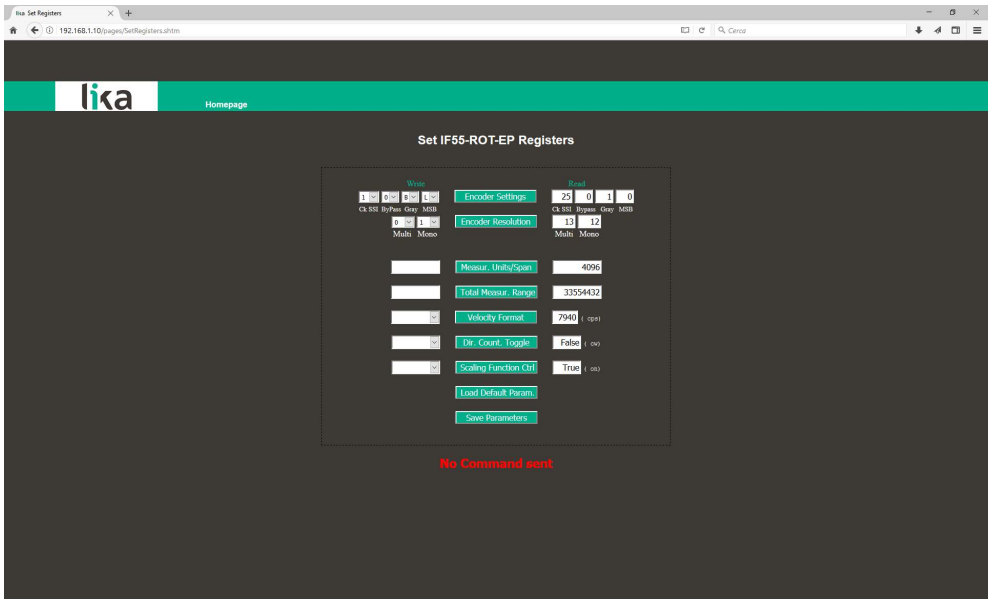


Figure 55 - Set IF55-ROT-EP Registers page (converter for rotary encoders)

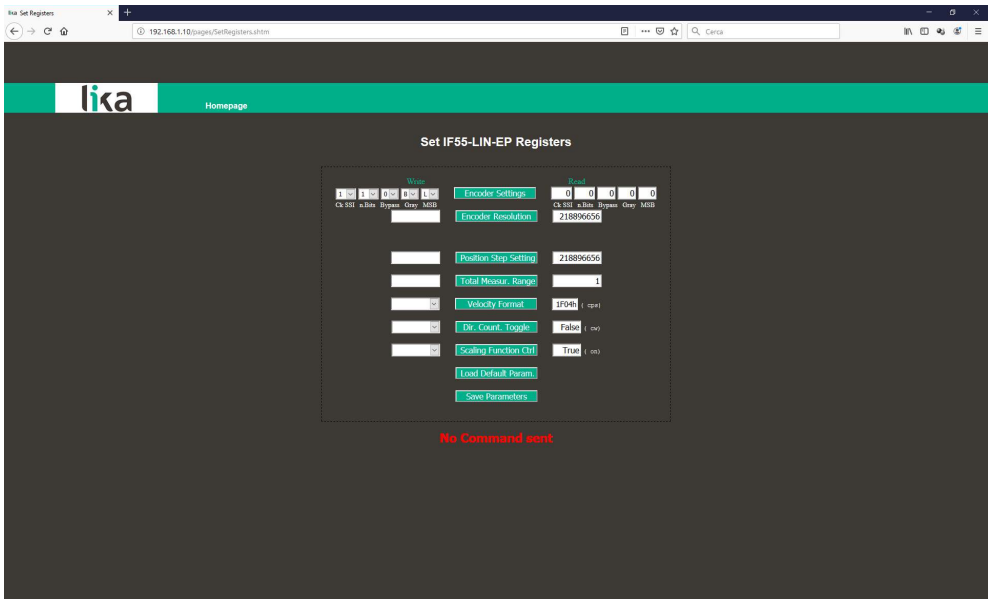


Figure 56 - Set IF55-LIN-EP Registers page (converter for linear encoders)

The values that are currently set in the converter are displayed in the **READ** box.

To change any value enter a suitable value in the **WRITE** box next to the desired parameter / attribute and then press the button between the boxes to confirm. The values have to be set either in decimal notation or by using the drop-down menu (when available).

For complete information on the available attributes please refer to the "6.12.5 Class 64h: Application Object" section on page 97.

EXAMPLE

The **64-01-10 Measuring Units per Span (R)** attribute is currently set to "**4096**" (see the **READ** box in the third line of the Figure 55 above). To change the set value enter a suitable value in the corresponding **WRITE** box of the same line and then press the **MEASUR. UNITS/SPAN** button to confirm.

EXAMPLE

The **64-01-10 Position Step Setting (L)** attribute is currently set to "**218896656**" (see the **READ** box in the third line of the Figure 56 above). To change the set value enter a suitable value in the corresponding **WRITE** box of the same line and then press the **POSITION STEP SETTING** button to confirm.

NOTE

Please note that, after pressing the button between the boxes, the set value is saved temporarily in the attribute. To save it permanently, please press the **Save Parameters** button. Should the power supply be turned off without saving data, the values that have not been saved on the Flash EEProm will be lost! For more information refer to the "5.1.8 Saving data" section on page 44.

Press the **Load Default Param.** button to restore all parameters to default values. Default values are set at the factory by Lika Electronic engineers to allow the operator to run the device for standard operation in a safe mode. This function can be useful, for instance, to restore the factory values in case the converter is set incorrectly and you are not able to resume the proper operation. For more information refer to the "5.1.9 Restoring defaults" section on page 44.

WARNING

The execution of this command causes all parameters which have been set previously to be overwritten!

NOTE

At each confirmation of the set parameters, a message will appear under the buttons (see **No Command sent** message). It informs whether the operation has been accomplished properly or an error occurred (for example **Command was set correctly** if everything went well; or **Command Error!** if something went wrong).

Press the **Homepage** command to move back to the Web server **Home** page.

7.7 Firmware upgrade

Press the **Upgrade Firmware** command in the left navigation bar of the Web server **Home** page to enter the **Firmware Upgrade** page. Please note that this is a password protected page, thus a password is requested to access the page.

WARNING
Firmware upgrading process must be accomplished by skilled and competent personnel. It is mandatory to perform the upgrade according to the instructions provided in this section.
Before installation always ascertain that the firmware program is compatible with the hardware and software of the device. Furthermore never turn off the power supply during the flash upgrade operation.

This operation allows to upgrade the unit firmware by downloading upgrading data to the flash memory.
The firmware is a software program which controls the functions and the operation of a device; the firmware program, sometimes referred to as "user program", is stored in the flash memory integrated inside the unit. These converters are designed so that the firmware can be easily updated by the user himself. This allows Lika Electronic to make new improved firmware programs available during the lifetime of the product.
Typical reasons for the release of new firmware programs are the necessity to make corrections, improve and even add new functionalities to the device.
The firmware upgrading program consists of a single file having .BIN extension. It is released by Lika Electronic Technical Assistance & After Sale Service.

If the latest firmware version is already installed in the unit, you do not need to proceed with any new firmware installation. The firmware version currently installed can be read next to the **Application-DSC FW Version** attribute in the **IF55-ROT-EP Information** / **IF55-LIN-EP Information** page after connection to the web server (see on page 157; see also the **64-01-64 Application-DSC FW Version** attribute on page 130).

NOTE
If you are not confident that you can perform the update successfully please contact Lika Electronic Technical Assistance & After Sale Service.

Before proceeding with the firmware upgrade please ascertain that the following requirements are fully satisfied:

- the converter is connected to the network;
- the converter has valid IP address;
- the PC is connected both to the network and the IO controller;

- a web browser (Internet Explorer, Mozilla Firefox, Google Chrome, Opera, ...) is installed in the PC or device used for connection;
- you have the SW_ETH_revX.Y.exe executable file;
- you have the .BIN file for firmware upgrade.

To upgrade the firmware program please proceed as follows.

1. Press the **Upgrade Firmware** command in the left navigation bar of the Web server **Home** page to enter the **Firmware Upgrade** page.
2. As soon as you press the **Upgrade Firmware** command a warning message (**Are you sure you want to update the flash?**) appears on the screen: it warns the operator about the awkwardness of the operation, thus he is required to confirm the procedure before continuing.

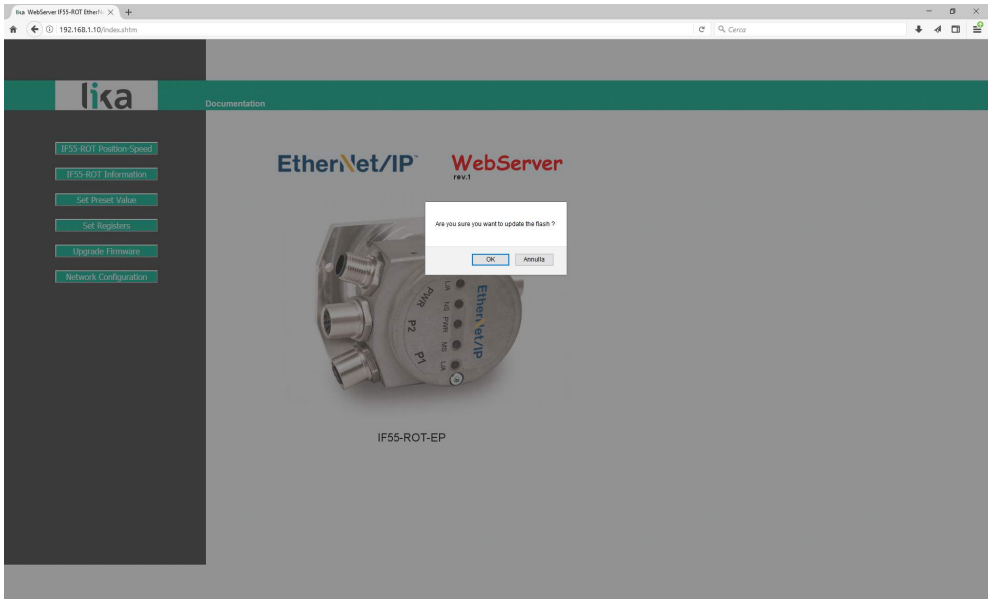


Figure 57 - Entering the Upgrade Firmware page (converter for rotary encoders)

3. Press the **OK** button to proceed, otherwise press the **EXIT** button to abort the procedure. The **Firmware upgrade cancelled!** message will appear on the screen. Press the **OK** button to move back to the Web server **Home** page.

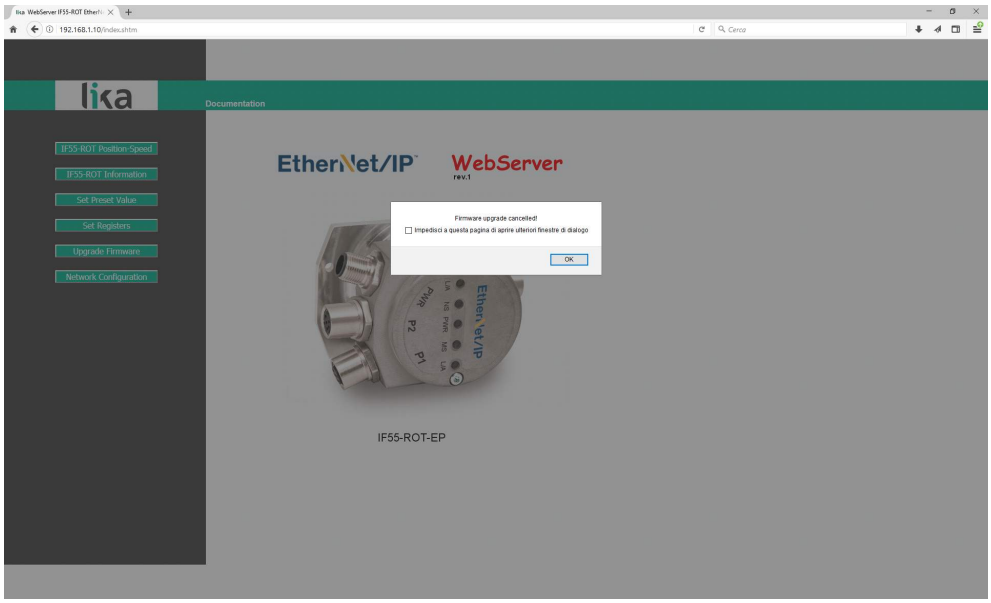


Figure 58 - Firmware upgrade operation aborted (converter for rotary encoders)

4. If you confirm the procedure, the **Firmware Upgrade** page will appear on the screen: the operator is requested to submit a password before starting the firmware upgrade procedure.
5. In the **Password** text box type the password **LIKA** (all uppercase letters) and then press the **Send Request** button.

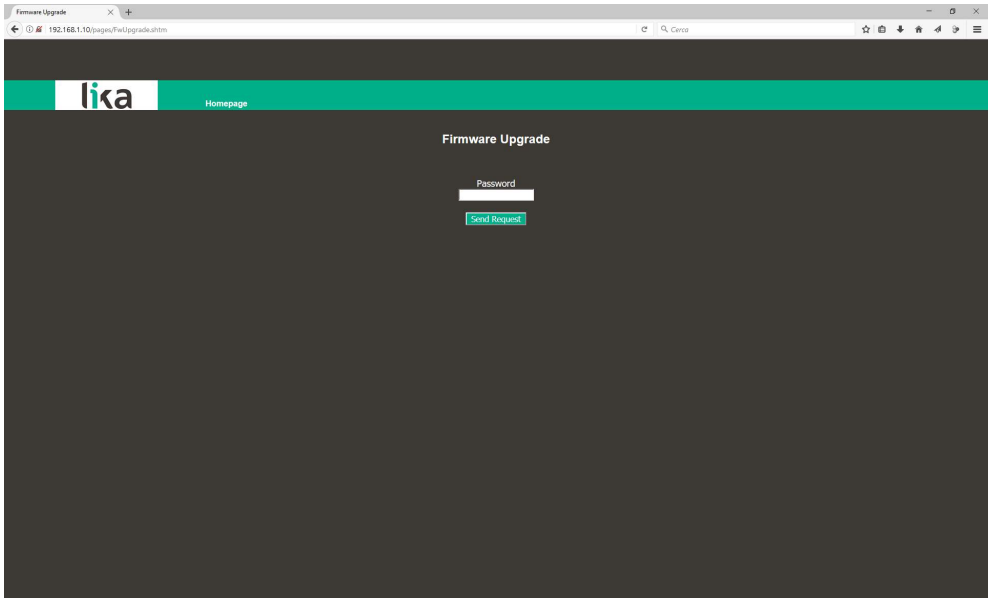


Figure 59 - Firmware Upgrade page

6. If the password you typed is wrong, the following warning message will appear on the screen: **THE PASSWORD INSERTED IS INCORRECT. PLEASE RETRY!**. Please retype the password and confirm.
7. If the password you typed is correct, the following message will appear on the screen: **THE PASSWORD INSERTED IS CORRECT. THE WEB SERVER OF THE ENCODER IS STOPPED. NOW LAUNCH THE PROGRAM SW_ETH_REVX_Y.EXE**.

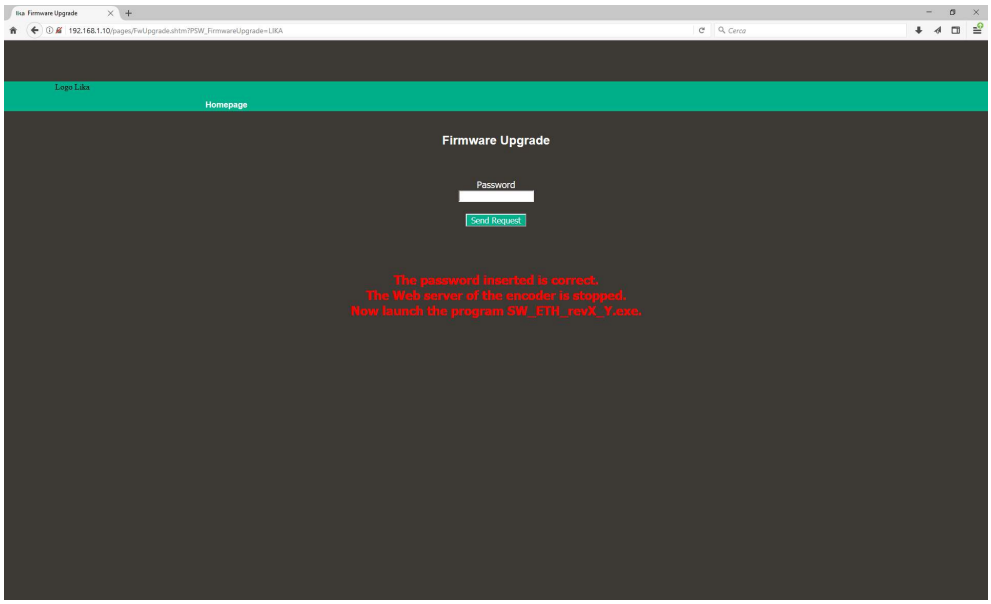


Figure 60 - Firmware Upgrade page – Correct password

8. The converter is now ready to accept the firmware program: the web server is stopped and the communication with the converter through the web browser is interrupted; if you need to exit the procedure and restore the communication you must switch the converter off and then on again.
9. Now you must launch the SW_ETH_REVX_Y.EXE executable file provided by Lika Electronic to continue with the procedure; X and Y indicate the version of the firmware upgrading program: REV1_0 is the version 1.0.

10. Launch the SW_ETH_REVX_Y.EXE executable file; the following page will appear:

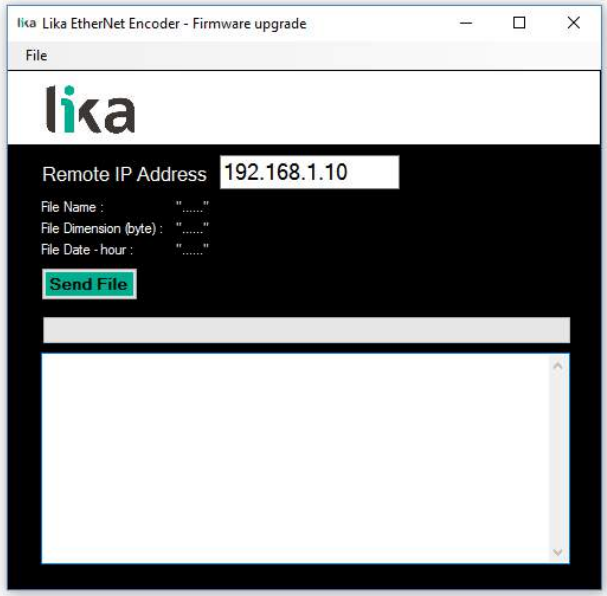


Figure 61 - Firmware upgrade executable file

11. Type the converter IP address in the **Remote IP Address** box. The default IP address set by Lika Electronic is 192.168.1.10.
12. Press the **FILE** command and then the **OPEN** command in the menu bar; once you press the **OPEN** command the **OPEN** dialog box appears on the screen: open the folder where the firmware upgrading .BIN file released by Lika Electronic is located, select the file and confirm. Hx in the file name shows the hardware version of the PCB; Sx shows the software version of the firmware upgrading file.

WARNING

Please pay attention to install the BIN file that perfectly matches the device to be updated.

IF55_ROT_EP_Hx_Sx.bin	for IF55 series for rotary encoders
IF55_LIN_EP_Hx_Sx.bin	for IF55 series for linear encoders

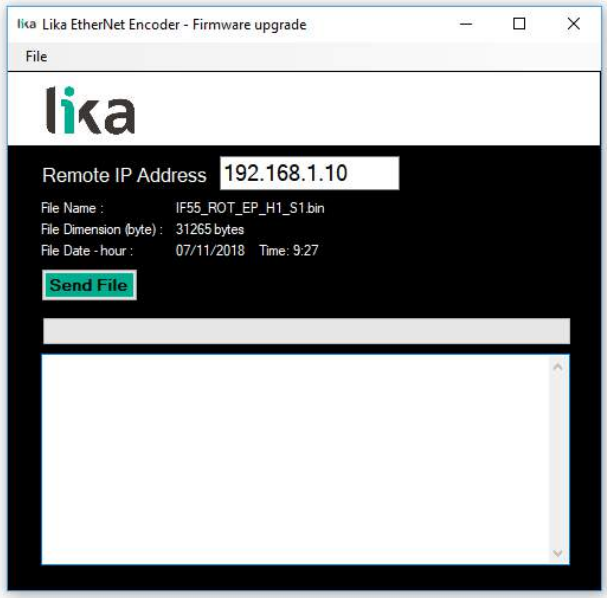


Figure 62 - Selecting the firmware upgrade .BIN file (converter for rotary encoders)

13. Some properties of the selected file are shown next to the relevant labels in the page: **File Name**, **File Dimension (byte)**, **File Date – hour**. Please check the file properties and ascertain that you are installing the correct upgrade file.

WARNING
Before installation always ascertain that the firmware program is compatible with the hardware and software of the device.
Never turn the power supply off during the flash upgrade operation.

14. Press the **Send File** button to start the firmware upgrade process.

15. A download progress bar as well as additional information are shown in the page while upgrading the firmware.

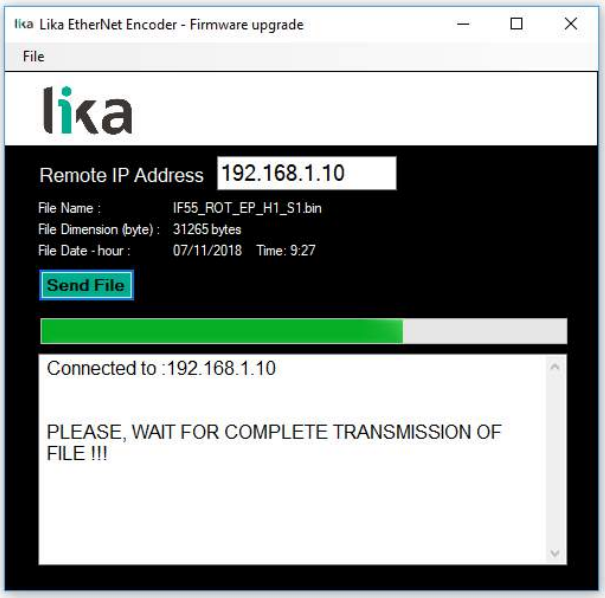


Figure 63 - Updating the firmware (converter for rotary encoders)

16. As soon as the operation is carried out successfully, the **FILE SENT CORRECTLY** message appears on the screen.

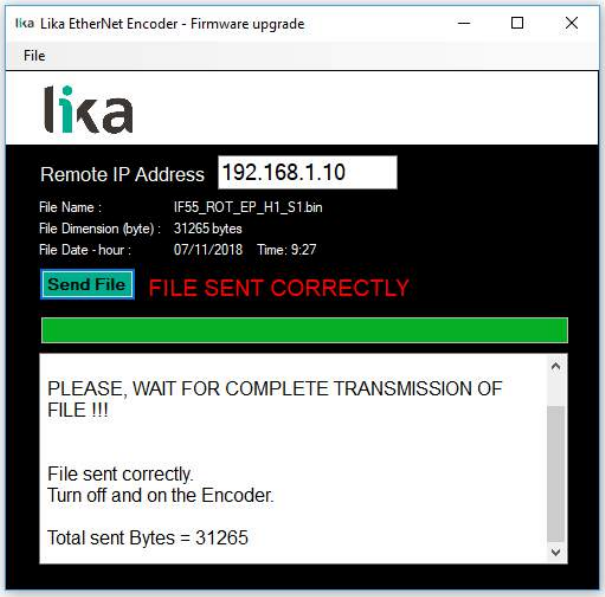


Figure 64 - Firmware upgrade process accomplished (converter for rotary encoders)

17. Now you are required to turn off and then on the power supply of the converter. Close the program.
18. Turn off and then on the power supply of the converter to complete the operation.

NOTE
While downloading the firmware upgrading program, unexpected conditions may arise which could lead to a failure of the installation process. When such a matter occurs, the download process cannot be carried out successfully and thus the operation is aborted; error messages are displayed. In case of flash upgrade error, please switch the converter off and then on again and retry the operation.

Press the **Homepage** command to move back to the Web server **Home** page.

7.8 Network configuration

Press the **Network Configuration** command in the left navigation bar of the Web server **Home** page to enter the **Network IP Configuration** page. This page allows the operator to configure the TCP/IP properties, that is how the converter communicates with other devices in the network.
For further information on the network communication parameters please refer to the "4.9 EtherNet/IP Node ID" section on page 34.

WARNING
The network configuration must be accomplished by skilled and competent personnel.

A soon as you press the **Network Configuration** command a warning message (**Are you sure you want to change Network Parameters?**) appears on the screen: it warns the operator about the awkwardness of the operation, thus he is required to confirm the procedure before continuing.

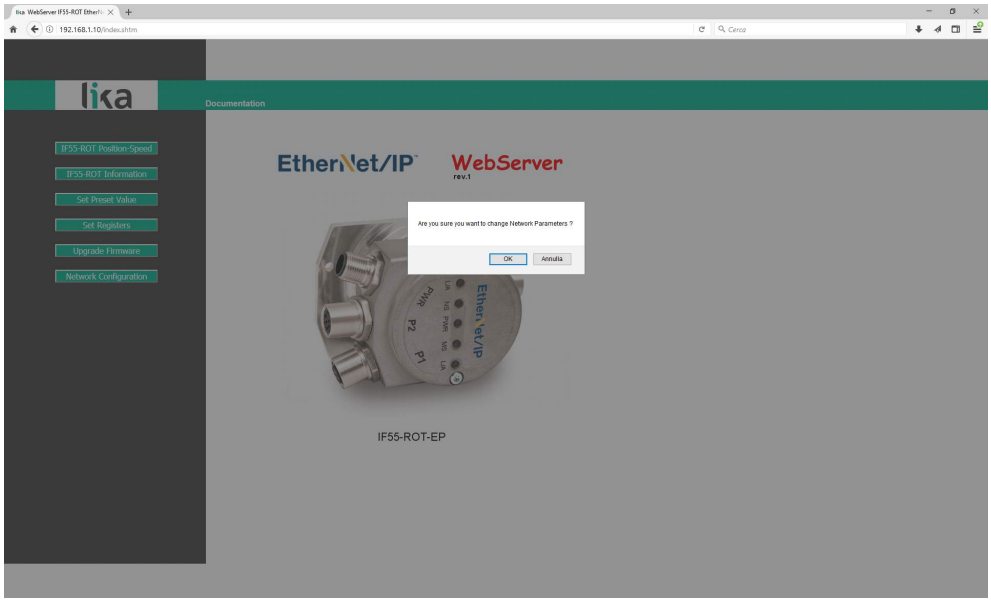


Figure 65 - Entering the Network Configuration page (converter for rotary encoders)

Press the **OK** button to proceed, otherwise press the **EXIT** button to abort the procedure. The **Set Network parameters cancelled!** message will appear on the screen. Press the **OK** button to move back to the Web server **Home** page.

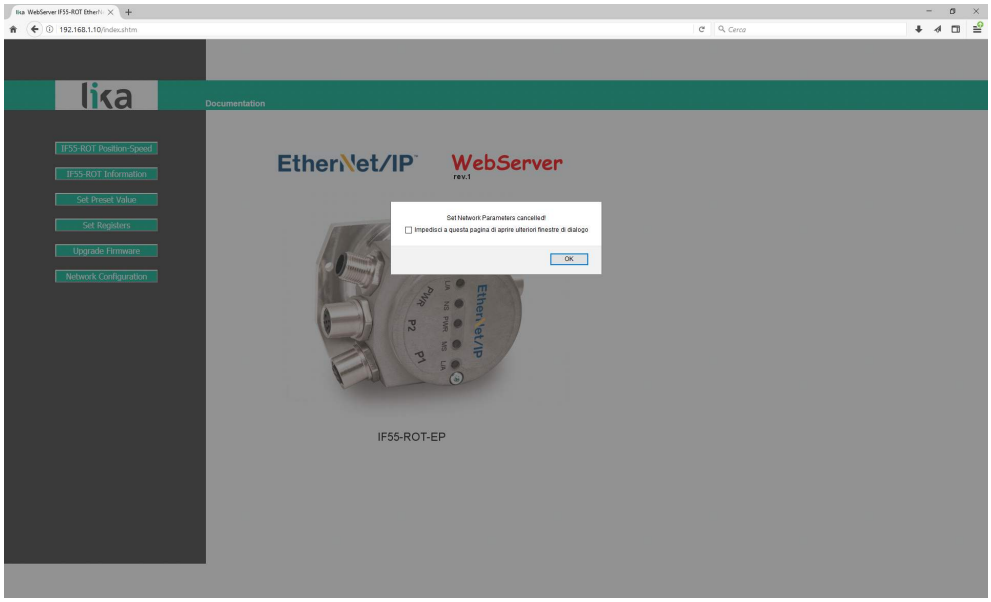


Figure 66 - Network configuration aborted (converter for rotary encoders)

If you confirm the procedure, the **Network Configuration** page will appear on the screen:

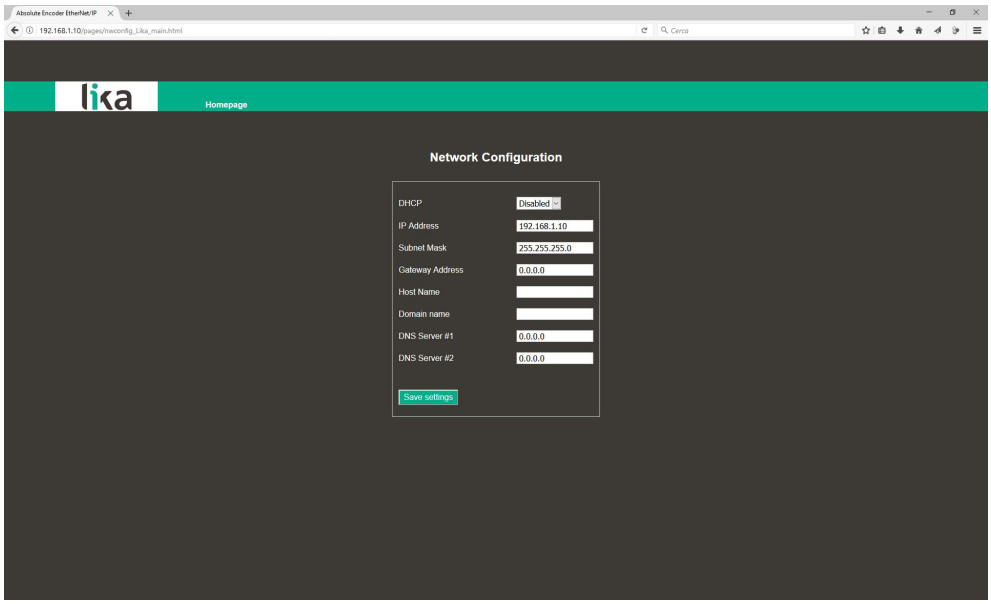


Figure 67 - Network Configuration page

WARNING

Only competent technicians, who are properly trained, have adequate experience and are familiar with computer architecture, network design and operating systems should configure the network communication parameters.
The inappropriate setting of the network parameters results in an incorrect operation of the system.

In this page it is possible to set the parameters that affect the proper communication of the converter in the TCP/IP network: IP address, Subnet mask, DHCP, DNS, etc.

The following table summarizes the default software IP address and the network configuration parameters.

IP Parameter	Value
IP address	192.168.1.10
Subnet mask	255.255.255.0
Default Gateway	0.0.0.0

To save the set values permanently, please press the **Save Settings** button. Should the power supply be turned off without saving data, the values that have not been saved on the Flash EEProm will be lost!

WARNING
After any setting please note down the configuration values to have access to the converter and the Web server pages in the future.

WARNING
If you enable the DHCP network protocol (DHCP = ENABLED), then the following default parameters are set for the converter:
IP ADDRESS = 0.0.0.0
SUBNET MASK = 0.0.0.0
Please check that these settings are allowed by the DHCP server and they are valid address values.

Press the **Homepage** command to move back to the Web server **Home** page.

8 - Default parameters list

Default values are expressed in hexadecimal (h) notation, unless otherwise indicated.

8.1 Attributes and parameters of the converter for rotary encoders

8.1.1 Attributes of the Class 01h Identity Object

Parameters list	Default values
01-01-01 Vendor ID	0299h = Lika Electronic
01-01-02 Device type	000Ch = Communications Adapter Device
01-01-03 Product code	0020h = IF55-ROT series converter
01-01-04 Revision	Device dependent
01-01-06 Serial number	Device dependent
01-01-07 Product name	IF55-ROT Posicontrol Device

8.1.2 Attributes of the Class 64h Communications Adapter Device Object

Parameters list	Default values
64-01-0B Position Sensor type	0002h = multiturn absolute rotary encoder
64-01-0C Direction Counting Toggle (R)	00h = CW rotation
64-01-0E Scaling Function Control (R)	01h = enabled
64-01-10 Measuring Units per Span (R)	65,536
64-01-11 Total Measuring Range (R)	1 073 741 824
64-01-13 Preset Value	0
64-01-19 Velocity Format (R)	1F04h = cps
64-01-2A Physical Resolution Span (R)	4,096
64-01-2B Number of Spans (R)	8,192
64-01-2D Supported Alarms	1002h
64-01-30 Supported Warnings	2000h
64-01-50 Encoder Settings (R)	1910h SSI protocol (R) = 0 = LSB Right Aligned protocol SSI output code (R) = 1 = Gray code Bypass mode (R) = 0 = disabled No of SSI clocks (R) = 19h
64-01-51 Encoder Resolution (R)	0D0Ch Singleturn resolution (bits) = 12 Multiturn resolution (bits) = 13
64-01-64 Application-DSC FW Version	Device dependent
64-01-65 Hardware Version	Device dependent
64-01-66 Network-DSC FW Version	Device dependent
64-01-6A Encoder Serial Number	Device dependent
64-01-6C Network-DSC Serial Number	Device dependent

8.2 Attributes and parameters of the converter for linear encoders

8.2.1 Attributes of the Class 01h Identity Object

Parameters list	Default values
01-01-01 Vendor ID	0299h = Lika Electronic
01-01-02 Device type	000Ch = Communications Adapter Device
01-01-03 Product code	0021h = IF55-LIN series converter
01-01-04 Revision	Device dependent
01-01-06 Serial number	Device dependent
01-01-07 Product name	IF55-LIN Posicontrol Device

8.2.2 Attributes of the Class 64h Communications Adapter Device Object

Parameters list	Default values
64-01-0B Position Sensor type	0002h = multiturn absolute rotary encoder
64-01-0C Direction Counting Toggle (L)	00h = standard direction
64-01-0E Scaling Function Control (L)	01h = enabled
64-01-10 Position Step Setting (L)	10,000
64-01-11 Total Measuring Range (L)	1 073 741 824
64-01-13 Preset Value	0
64-01-19 Velocity Format (L)	1F04h = cps
64-01-2A Physical Measuring Step (L)	10,000
64-01-2D Supported Alarms	1002h
64-01-30 Supported Warnings	2000h
64-01-50 Encoder Settings (L)	0019 3110h SSI protocol (L) = 0 = LSB Right Aligned protocol SSI output code (L) = 1 = Gray code Bypass mode (L) = 0 = disabled Physical Total Resolution (L) = 13 = 19 bits No of SSI clocks (L) = 19h = 25 clocks
64-01-51 Encoder Resolution (L)	10,000
64-01-64 Application-DSC FW Version	Device dependent
64-01-65 Hardware Version	Device dependent
64-01-66 Network-DSC FW Version	Device dependent
64-01-6A Encoder Serial Number	Device dependent
64-01-6C Network-DSC Serial Number	Device dependent

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Document release	Release date	Description	HW	SW	EDS file version
1.0	12.11.2018	First issue	1.0	1.0	1.0
1.1	22.11.2019	Byte order updated, rotary and linear encoders' documentation merged, new firmware, new EDS files, bypass function added and related parameters updated, setting range updated in some parameters, new POWER SUPPLY DIP switch	1.0	1.0	1.0
1.2	04.07.2022	"4.2 SSI connection (Figure 4)" section updated	1.0	1.0	1.0

Dispose separately

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