CANopen over EtherCAT

This page describes the **CANopen over EtherCAT (CoE)** profile of the GDi-EtherCAT motor. The motor uses the DS402 profile over EtherCAT, which provides the standard modes of operation and the PDO/SDO communication.

Mode of operation:
https://www.nilab.at/dokuwiki/doku.php?id=integrated_drive_motors:canopen_modes|

Standard PDOs: https://www.nilab.at/dokuwiki/doku.php?id=integrated_drive_motors:can_open_pdo|

Standard SDOs: https://www.nilab.at/dokuwiki/doku.php?id=integrated_drive_motors:canopen_sdo|

Error Codes: https://www.nilab.at/dokuwiki/doku.php?id=integrated_drive_motors:canopen_error|

How to use the CoE profile

- The **mode of operation** defines the motion behaviour (profile position, velocity, torque, etc.). - The **PDOs** are used for cyclic data exchange (commands and status); the **SDOs** are used for parameter access. - The **error codes** are read from the drive and used for diagnostics. - Refer to the linked pages for the detailed object definitions and the mapping.

From:
https://www.nilab.at/dokuwiki/ - **NiLAB GmbH Knowledgebase**

Permanent link:
https://www.nilab.at/dokuwiki/doku.php?id=en:gdi_ethercat:coe

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