
**acontis technologies GmbH**

**SOFTWARE**

# EC-Monitor

## User Manual

**V3.3**

**AT3401** **Edition: April 2, 2026**

# Contents

# 1 Introduction

## 1.1 What is EtherCAT®?

EtherCAT® (Ethernet for Control Automation Technology) is a high-performance Ethernet Fieldbus technology that provides a reliable, efficient, and cost-effective communication solution for a wide variety of industrial automation applications. Originally developed as an open technology by Beckhoff Automation in 2003, and subsequently turned over to an independent organization known as the EtherCAT® Technology Group, EtherCAT® has since become one of the most widely used industrial Ethernet protocols in the world.

**See also:**

A comprehensive introduction to EtherCAT® technology can be found at https://www.acontis.com/en/what-is-EtherCAT-communication-protocol.html.

## 1.2 The EC-Monitor - Features

## 1.3 Protected version

The EC-Monitor software is available in different protected versions:

**Protected**
: Binary with MAC protection

**Unrestricted**
: Binary without MAC protection

**Source**
: Source code

The protected version will automatically stop after about 30 minutes of continuous operation. In order to remove this restriction a valid runtime license key is required. The runtime license protection is based on the MAC address of the Ethernet controller used for the EtherCAT® protocol. With a valid License Key the protected version will automatically become an unrestricted version.

### 1.3.1 Licensing procedure for Development Licenses

1. Installation of EC-Monitor protected version
2. Determine the MAC Address by calling *emonGetSrcMacAddress()* or from a sticker applied on the hardware near the Ethernet controller
3. Send an Email with the subject "**Development License Key Request, Commission** *your commission number*" with the MAC address to sales@acontis.com
4. Acontis will create the license keys and return them in a **License Key Text File (CSV format)**.

```
Number;MAC Address;License Key
1;00-00-5A-11-77-FE;DA1099F2-15C249E9-54327FBC
2;64-31-50-80-20-4E;1B7C1F86-D08E40A8-4F96F2BA
```

5. Activate the License Key by calling *emonSetLicenseKey()* with the license key that corresponds to the MAC address on the hardware and check the return code. The license key is 26 characters long.

```
dwRes = emonSetLicenseKey(0, "DA1099F2-15C249E9-54327FBC");
```

### 1.3.2 Licensing procedure for Runtime Licenses

1. Installation of EC-Monitor protected version
2. Determine the MAC Address by calling *emonGetSrcMacAddress()* or from a sticker applied on the hardware near the Ethernet controller
3. Provide the MAC Addresses and numbers from **previously ordered and unused runtime license stickers** in a text file to acontis as described in the example below. Please use a separate line for each runtime license sticker number and MAC Address.

```
S/N; MAC Address
100-105-1-1/1603310001;00-00-5A-11-77-FE
100-105-1-1/1603310002;64-31-50-80-20-4E
```

4. Send an Email with the subject "**Runtime License Key Request, Commission** *your commission number*" with the MAC address to sales@acontis.com
5. Acontis will create the license keys and return them in a **License Key Text File (CSV format)**.

```
Number;MAC Address;License Key
1;00-00-5A-11-77-FE;DA1099F2-15C249E9-54327FBC
2;64-31-50-80-20-4E;1B7C1F86-D08E40A8-4F96F2BA
```

6. Activate the License Key by calling *emonSetLicenseKey()* with the license key that corresponds to the MAC address on the hardware and check the return code.

```
dwRes = emonSetLicenseKey(0, "DA1099F2-15C249E9-54327FBC");
```

## 1.4 License

### 1.4.1 EC-Monitor license

According to EC-Monitor Software License Agreement (SLA).

### 1.4.2 Free Open Source Software contained in EC-Monitor

#### 1.4.2.1 Expat XML parser license V2.6.0

```
Copyright (c) 1997-2000 Thai Open Source Software Center Ltd
Copyright (c) 2000      Clark Cooper <coopercc@users.sourceforge.net>
Copyright (c) 2000-2005 Fred L. Drake, Jr. <fdrake@users.sourceforge.net>
Copyright (c) 2001-2002 Greg Stein <gstein@users.sourceforge.net>
Copyright (c) 2002-2016 Karl Waclawek <karl@waclawek.net>
Copyright (c) 2016-2024 Sebastian Pipping <sebastian@pipping.org>
Copyright (c) 2016      Cristian Rodríguez <crrodriguez@opensuse.org>
Copyright (c) 2016      Thomas Beutlich <tc@tbeu.de>
Copyright (c) 2017      Rhodri James <rhodri@wildebeest.org.uk>
Copyright (c) 2022      Thijs Schreijer <thijs@thijsschreijer.nl>
Copyright (c) 2023      Hanno Böck <hanno@gentoo.org>
Copyright (c) 2023      Sony Corporation / Snild Dolkow <snild@sony.com>
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"Software"),  to  deal in  the  Software  without restriction,  including
without  limitation the  rights  to use,  copy,  modify, merge,  publish,
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```
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EXPRESS OR IMPLIED, INCLUDING BUT NOT LIMITED TO THE WARRANTIES OF
MERCHANTABILITY, FITNESS FOR A PARTICULAR PURPOSE AND NONINFRINGEMENT. IN
NO EVENT SHALL THE AUTHORS OR COPYRIGHT HOLDERS BE LIABLE FOR ANY CLAIM,
DAMAGES OR OTHER LIABILITY, WHETHER IN AN ACTION OF CONTRACT, TORT OR
OTHERWISE, ARISING FROM, OUT OF OR IN CONNECTION WITH THE SOFTWARE OR THE
USE OR OTHER DEALINGS IN THE SOFTWARE.
```

### 1.4.3 Free Open Source Software supported by EC-Monitor

The following components are not part of EC-Monitor, but relate to it:

#### 1.4.3.1 acontis atemsys Linux kernel module

The acontis atemsys is licensed under the GPL:

```
Copyright (c) 2009 - 2020 acontis technologies GmbH, Ravensburg, Germany
All rights reserved.

This program is free software; you can redistribute it and/or modify it
under the terms of the GNU General Public License as published by the
Free Software Foundation; either version 2 of the License, or (at your
option) any later version.
```

#### 1.4.3.2 WinPCap

The WinPCap library is supported, but not shipped with EC-Monitor.

#### 1.4.3.3 Npcap

The Npcap library is supported, but not shipped with EC-Monitor.

## 1.5 Versioning

EC-Monitor follows the following versioning scheme: **V***MAJOR***.** *MINOR***.** *SERVICEPACK***.** *BUILD* (e.g. V3.2.1.04).

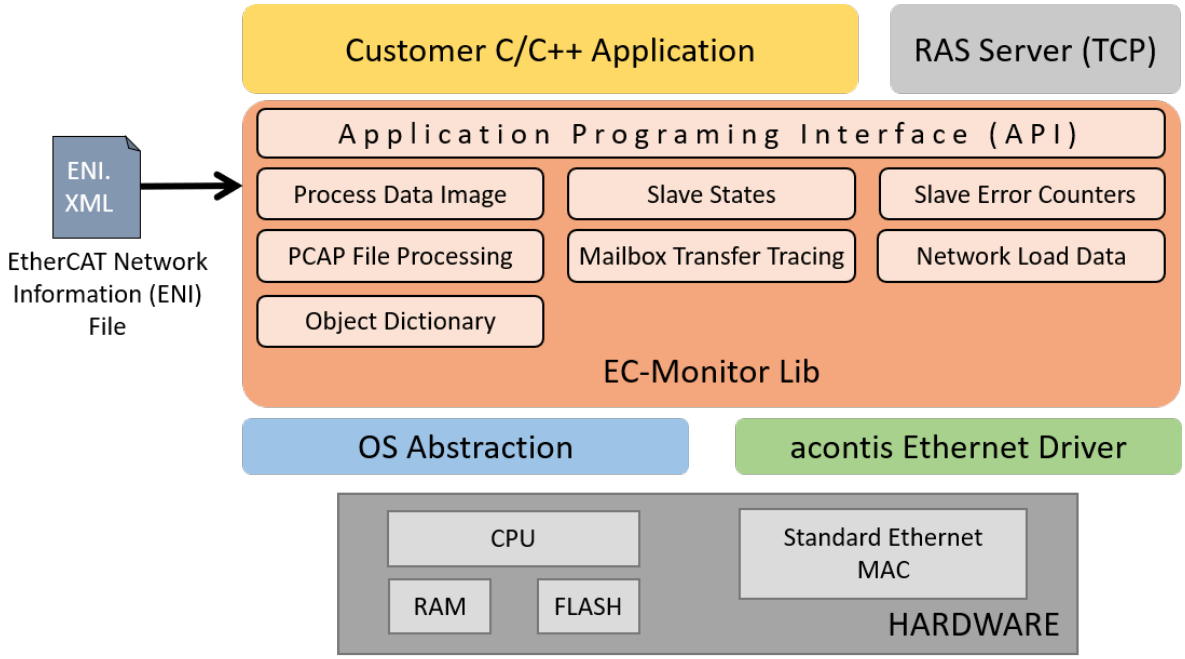
The libraries are binary compatible by unchanged *MAJOR* and *MINOR* digits. If *SERVICEPACK* increments, *BUILD* restarts with 01. *BUILD* 99 is reserved for test builds that have not been officially released for productive usage.

# 2 Architecture

The EC-Monitor Software Development Kit (SDK) offers the possibility for Data Tracing / Listening / Sniffing / Logging Diagnosis and Monitoring of EtherCAT® Networks. It's suitable for new (Greenfield) and existing (Brownfield) installations. Also it's independent from EtherCAT® MainDevice Software and Hardware.

EC-Monitor is implemented in C++ and can be easily ported to any embedded OS platforms using an appropriate C++ compiler. The API functions are C language interfaces, thus the EC-Monitor can be used in ANSI-C as well as in C++ environments.

The EC-Monitor is divided into modules, see diagram and descriptions below:




**EC-Monitor Library:**
In the core module cyclic (process data update) and acyclic (mailbox) EtherCAT® commands are received and processed.

**Configuration Layer:**
The EC-Monitor is configured using an XML file whose format is fixed in the EtherCAT® specification ETG.2100. EC-Monitor contains an OS independent XML parser.

**OS Abstraction Layer:**
All OS dependent system calls are encapsulated in a small OS layer. Most functions are that easy that they can be implemented using simple C macros.

**Real-time Ethernet Driver Layer:**
This driver receives Ethernet frames from the TAP devices.

## 2.1 EtherCAT® Network Configuration (ENI)

The EC-Monitor has to know about the EtherCAT® bus topology and the cyclic/acyclic frames which are exchanged by the third party EtherCAT® MainDevice with the SubDevices. This configuration is determined in a configuration file which has to be available in the EtherCAT® Network Information Format (ENI). This format is completely independent from EtherCAT® SubDevice vendors, from EtherCAT® MainDevice vendors and from EtherCAT® configuration tools. Thus inter-operability between those vendors is guaranteed.

## 2.2 Operating system configuration

The main task is to setup the operating system to support the appropriate network adapter for EtherCAT® usage and for some systems real-time configuration may be needed.

The operating system-specific settings and configurations are described in *Platform and Operating Systems (OS)*.

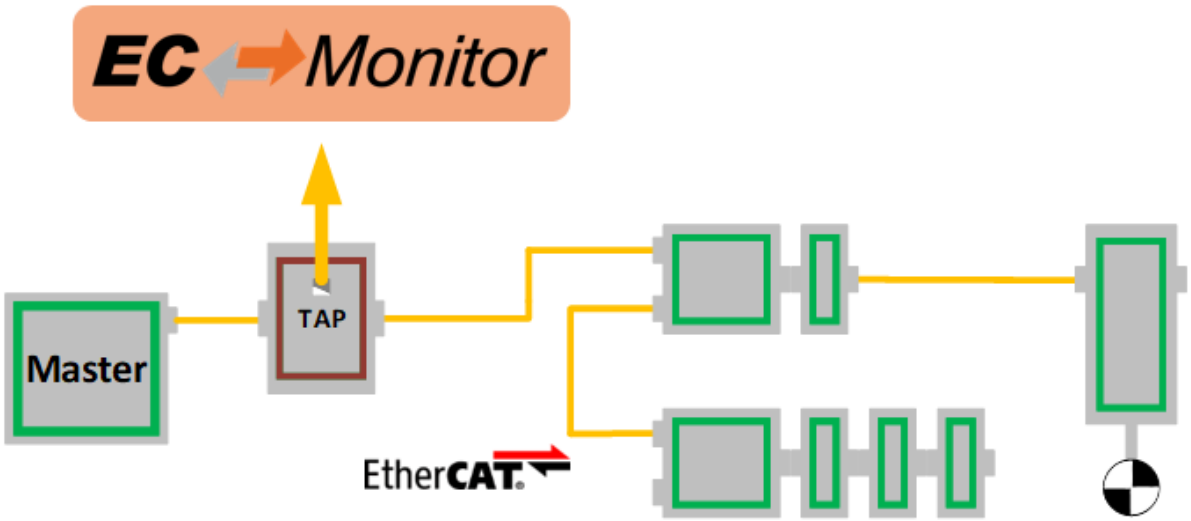
# 3 Ethernet TAP

To capture the EtherCAT® traffic, EC-Monitor supports a variety of different Ethernet Test Access Points (TAP). These can be special real-time optimized TAPs with minimal propagation delay and extended diagnostic options, or simple 100MBit/s Ethernet switches. The only requirement is that the input (RX) and output (TX) traffic is forwarded to the EC-Monitor via a common up-link port.

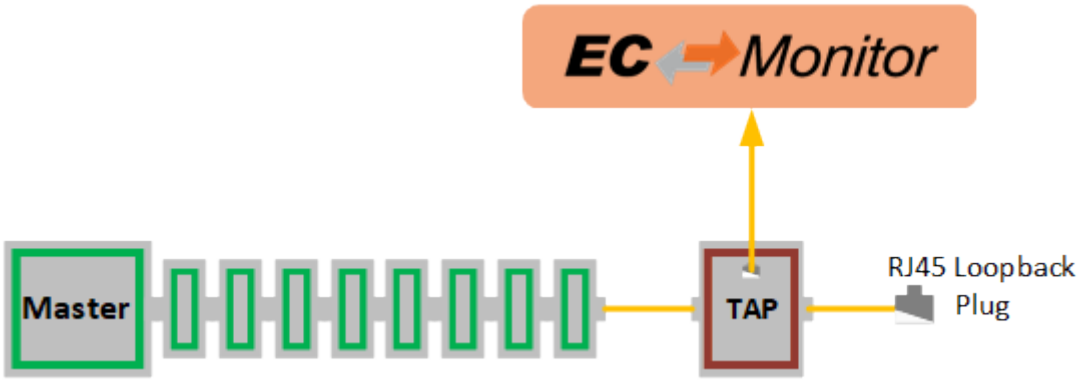
The various Ethernet TAP devices can be automatically detected by the EC-Monitor via *EC_T_MONITOR_INIT_PARMS::eEthTapType* set to *EC_T_ETHERNET_TAP_TYPE::eEthTap_AutoDetect*.

## 3.1 TAP positioning

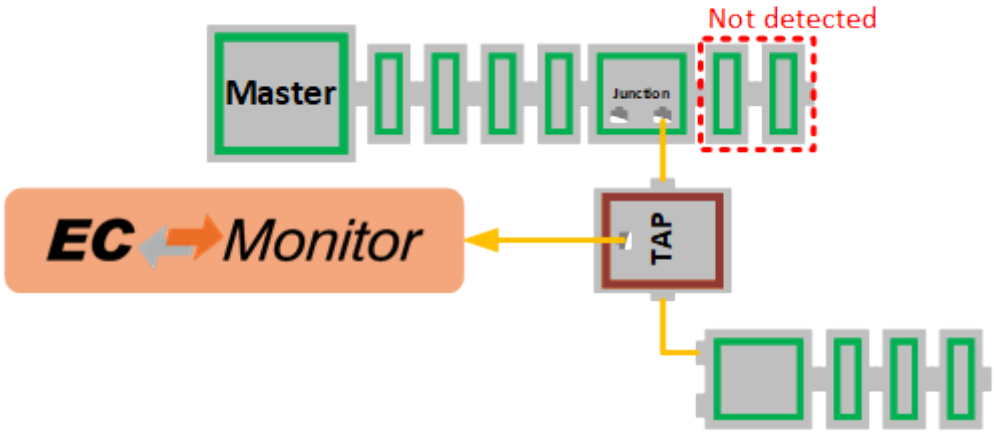
The Ethernet TAP device should be inserted in the network between the EtherCAT® MainDevice and SubDevices or, if this is not possible, between two SubDevices. The position of the Ethernet TAP is detected automatically and the EtherCAT® traffic is processed accordingly.




For configurations where the EtherCAT® MainDevice has a direct interface to the SubDevices without an RJ45 cable, e.g. Beckhoff IPCs it is possible to connect the input port of the Ethernet TAP device to the RJ45 port of the topologically last SubDevice. The output port of the Ethernet TAP device must be bridged using an RJ45 loopback plug so that the EtherCAT® frames are forwarded back to the MainDevice.



In configurations where the TAP can only be inserted at an EtherCAT® Junction SubDevice, the port closest to the end of the topology should be used. Any SubDevices connected to the subsequent port will no longer be detected.




**Warning:** Positioning the TAP within the topology can lead to inconsistencies in the process data image. This affects the outputs of the SubDevices preceding the TAP and that are read by a `Logical Read-Write` (`LRW`) command. The affected outputs are set to 0 by the EC-Monitor.

## 3.2 Generic 100MBit/s Ethernet Switch

A generic 100MBit/s Ethernet switch with at least 3 ports can be used with EC-Monitor. The propagation delay can be up to several hundred µs per port and should therefore only be used for slower cycle times.

To manually select this device set *EC_T_MONITOR_INIT_PARMS::eEthTapType* to *EC_T_ETHERNET_TAP_TYPE::eEthTap_Generic*.

## 3.3 Beckhoff ET2000

The Beckhoff ET2000 comes with propagation delay below 1 µs, a high-precision timestamp and extended frame error detection capabilities. The TAP offers the possibility to determine on which port the frame was received. The EC-Monitor uses this to evaluate whether it is a TX or RX frame. Therefore, the outgoing connection from the EtherCAT® MainDevice should be connected to either port `X1.0`, `X2.0`, `X3.0` or `X4.0`.

To manually select this device set *EC_T_MONITOR_INIT_PARMS::eEthTapType* to *EC_T_ETHERNET_TAP_TYPE::eEthTap_Beckhoff_ET2000*.

To filter frames by line, set *EC_T_MONITOR_INIT_PARMS::wMainTapPortIn* and *EC_T_MONITOR_INIT_PARMS::wMainTapPortOut* accordingly.

## 3.4 Dualcomm ETAP-1000

The Dualcomm ETAP-1000 has a propagation delay below 1 µs. Since it has no other extended capabilities it can be used as generic Ethernet TAP *EC_T_ETHERNET_TAP_TYPE::eEthTap_Generic*.

## 3.5 Kunbus TAP Curious

The Kunbus TAP Curious comes with propagation delay below 1 µs, a high-precision timestamp and extended frame error detection capabilities. The TAP offers the possibility to determine on which port the frame was received. The EC-Monitor uses this to evaluate whether it is a TX or RX frame. Therefore, the outgoing connection from the EtherCAT® MainDevice should be connected to either port `A` or `C`.

To manually select this device set *EC_T_MONITOR_INIT_PARMS::eEthTapType* to *EC_T_ETHERNET_TAP_TYPE::eEthTap_Kunbus_TapCurious*.

To filter frames by line, set *EC_T_MONITOR_INIT_PARMS::wMainTapPortIn* and *EC_T_MONITOR_INIT_PARMS::wMainTapPortOut* accordingly.

## 3.6 ProfiTap ProfiShark

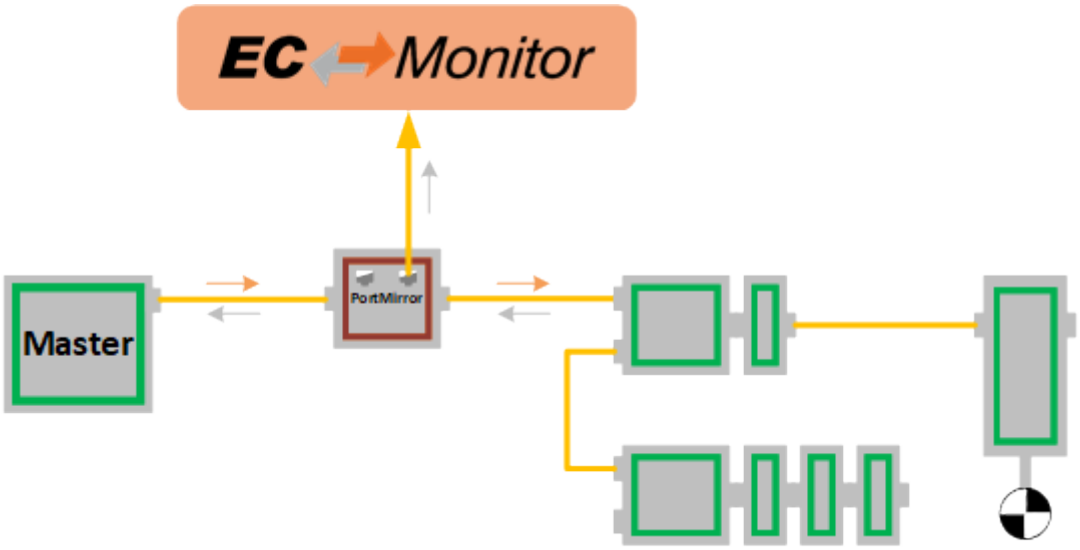
The ProfiTap ProfiShark devices are USB3.0 based Ethernet TAPs with a propagation delay below 1 µs. To use it with EC-Monitor, the Hardware Timestamping feature must be disabled in the Featues Tab of ProfiShark Manager.

As the device appear as a virtual Ethernet interface in the operating system, it can be used as a generic Ethernet TAP *EC_T_ETHERNET_TAP_TYPE::eEthTap_Generic*.

## 3.7 Port Mirror

A TAP or switch with port mirroring functionality can also be used with EC-Monitor. Typically, a port mirroring device has four Ethernet ports, two input ports for the network and two mirroring output ports. Incoming traffic on the respective network port is mirrored to the corresponding mirror port.

In the EtherCAT® use case, this means that the Ethernet frames outgoing from the EtherCAT® MainDevice are mirrored on one port and the Ethernet frames returning from the EtherCAT® SubDevices are output on another port. Since EC-Monitor currently only supports one port for connecting to the TAP, the mirror port with the returning Ethernet frames must be connected.



This network adapter must be selected manually by setting *EC_T_MONITOR_INIT_PARMS::eEthTapType* to *EC_T_ETHERNET_TAP_TYPE::eEthTap_PortMirror*.

**Warning:** Since only the returning frames are processed, inconsistencies occur in the process data image of the outputs for EtherCAT® frames with `LRW` commands.

# 4 EtherCAT® MainDevices

In principle, all EtherCAT® MainDevices with ENI are supported. EtherCAT® MainDevices without ENI are currently not supported.

All tested EtherCAT® MainDevices are listed below, as well as special EC-Monitor parameters that are necessary for operation.

## 4.1 Acontis EC-Master

Fully supported without any special parameter settings.

## 4.2 Beckhoff TwinCAT®

Fully supported without any special parameter settings.

## 4.3 CODESYS®

Supported starting from version V3.5 SP17 and above, with the CODESYS EtherCAT® Module requiring version 4.2.0.0 or later. In some topologies, the actual number of cyclical commands on the bus differs from the configuration in the ENI. To fix this discrepancy, the EC-Monitor parameter *EC_T_MONITOR_INIT_PARMS::bProcessRestructuredCyclicCmds* must be set to *EC_TRUE*.

## 4.4 KPA EtherCAT® MainDevice

Supported.

# 5 Getting Started

To enable a quick and easy start, every EC-Monitor package comes with a pre-compiled EcMonitorDemo executable. This example application handles the following tasks:

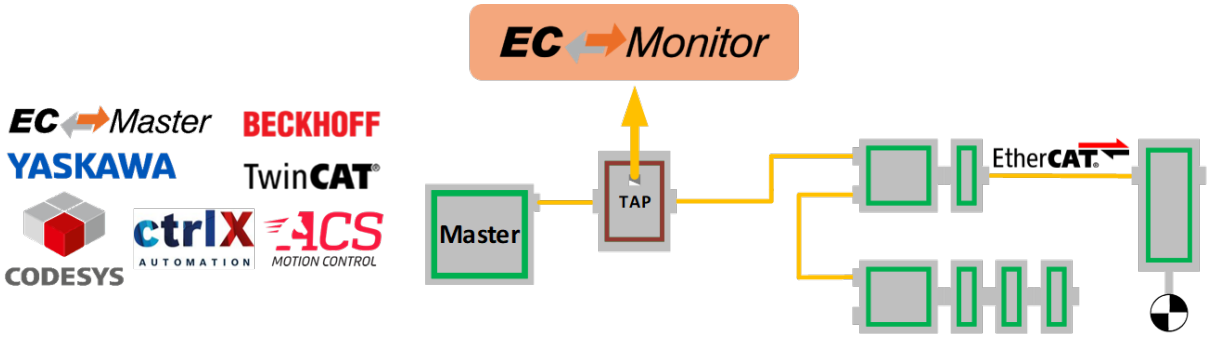
- EC-Monitor initialization
- Process Data acquisition with EC-DAQ
- Periodic Job Task in polling or interrupt mode
- Record and replay wireshark traces
- Logging

**See also:**

*Example application* for detailed explanation

## 5.1 Running EcMonitorDemo

To capture the EtherCAT® traffic insert a TAP device between the EtherCAT® adapter of the MainDevice and the first SubDevice.




Start the EcMonitorDemo from the command line to process the captured EtherCAT® frames. At least a Real-time Ethernet Driver and a ENI file must be specified.

```
> EcMonitorDemo -ndis 192.168.157.2 1 -f eni.xml -t 0 -v 3
```

**See also:**

*Platform and Operating Systems (OS)* for OS specific additional instructions to run the demo application

### 5.1.1 Command line parameters

```
EcMonitorDemo <LinkLayer> [-f ENI-FileName] [-t time] [-b cy-
cle time] [-a affinity] [-v level] [-perf] [-log pre-
fix [msg cnt]] [-lic key] [-sp [port]] [-rec [pre-
fix]] [-play pcap-FileName] [-daqrec file name]
```

The parameters are as follows:

**-f** <ENI-FileName>
: Path to ENI file

**-t** <time>
: Running duration [ms]. When the time expires the demo application exits completely.

**<time>**
Time [ms], 0 = forever (default = 120000)

**-b** <cycle time>
Specifies the bus cycle time. Defaults to 1000 µs (1 ms).

**<cycle time>**
Bus cycle time in µsec

**-a** <affinity>
The CPU affinity specifies which CPU the demo application ought to use.

**<affinity>**
0 = first CPU, 1 = second, …

**-v** <level>
The verbosity level specifies how much console output messages will be generated by the demo application. A high verbosity level leads to more messages.

**<level>**
Verbosity level: 0=off (default), 1..n=more messages

**-perf** [<level>]
Enable max. and average time measurement in µs for all EtherCAT® jobs (e.g. ProcessAllRxFrames).

**<level>**
Depending on level the performance histogram can be activated as well.

**-log** <prefix> [<msg cnt>]
Use given file name prefix for log files.

**<prefix>**

**<msg cnt>**
Messages count for log buffer allocation

**-lic** <key>
Set License key.

**<key>**
License key string

**-oem** <key>
Use OEM key

**<key>**
64 bit OEM key.

**-sp** [<port>]
If platform has support for IP Sockets, this command-line option enables the Remote API Server to be started. The Remote API Server is going to listen on TCP Port 6000 (or port parameter if given) and is available for connecting Remote API Clients.

**<port>**
RAS server port

**-rec** [<prefix>]
Packet capture file recording

**<prefix>**
File name prefix

**-play** <FileName>
Packet capture file processing

**<FileName>**
File name (*.pcapl*.pcapng)

**-genebi** <FileName>
Export ENI Builder config on demo stop

**<FileName>**
File name (*.xml)

**-mqtt** <BrokerAddress>
Publish process data to MQTT broker. EcMonitorDemoMqtt only

**<BrokerAddress>**
MQTT broker address

**-mqttCycTime** <Msec>
Minimum time between cyclic messages for a variable. EcMonitorDemoMqtt only

**<Msec>**
Time in milliseconds

**-mqttChgTime** <Msec>
Minimum time between change-detection based messages for a variable. EcMonitorDemoMqtt only

**<Msec>**
Time in milliseconds

**-daqrec** <FileName>

**<FileName>**
Configuration file

#### 5.1.1.1 Link Layer

Using one of the following demo application Link Layer options, the EC-Monitor will dynamically load the network driver for the specified network adapter card and use the appropriate network driver to access the Ethernet adapter for EtherCAT®. `ShowSyntaxLinkLayer()` in `Common/EcSelectLinkLayer.cpp` is called automatically if the Demo application is started without parameters and lists the possibilities.

---

**Note:** Not all link layers are available on all operating systems or architectures. A detailed view in the form of a matrix can be found in the developer center.

---

**-intelgbe** <instance> <mode> [--tts <sendoffset>|--tmr] [--nophyctrlonconnect]

**Hardware: Intel Pro/1000 network adapter card**

**<Instance>**
Device instance 1 = first, 2 = second, …

**<Mode>**
0 = Interrupt mode | 1 = Polling mode

**Optional:**

**--tts**
Enable Real-time Ethernet Driver Time Triggered Send (TTS)

**<SendOffset>**
TTS cyclic frame send offset from cycle start (usec)

**or**

**--tmr**
Enable Real-time Ethernet Driver Timer

**Optional:**

**--nophyctrlonconnect**
Disable PHY control (e.g. PHY reset, PHY PM settings, Gbits Ctrl) on link connection detected

`-ndis <ipaddress> <mode> [--name <adaptername>] [--disablepromiscuousmode] \ [--disableforcebroadcast]`

**Hardware: Hardware independent, only available for Windows.**

**<IpAddress>**
IP address of network adapter card, e.g. 192.168.157.2 or 0.0.0.0 if name given

**<Mode>**
0 = Interrupt mode | 1 = Polling mode

**Optional:**

**--name**
Select network adapter by name

**<AdapterName>**
Service name from HKEY_LOCAL_MACHINE\SOFTWARE\Microsoft\Windows NT\CurrentVersion\NetworkCards

**Optional:**

**--disablepromiscuousmode**
Disable promiscuous mode

**Optional:**

**--disableforcebroadcast**
Disable force broadcast

`-remote <instance> <mode> <src ip> <src port> <dst ip> <dst port> [--mac <address>] \ [--rxbuffercnt <count>]`

Hardware: Hardware independent. Tunnels EtherCAT frames through a TCP socket

**<Instance>**
Device instance 1 = first, 2 = second, …

**<Mode>**
1 = Polling mode

**<Src ip>**
Source adapter IP address (listen)

**<Src port>**
Source port number (listen)

**<Dst ip>**
Destination adapter IP address (connect)

**<Dst port>**
Destination port number (connect)

**Optional:**

**--mac**
MAC Address

**<Address>**
formatted as xx:xx:xx:xx:xx:xx or xx-xx-xx-xx-xx-xx

**Optional:**

**--rxbuffercnt**
Frame buffer count for interrupt service thread (IST)

**<Count>**
Buffer count

**-snarf** <adaptername>

**Hardware: Hardware independent, only available for VxWorks**

**<AdapterName>**
Adapter name, e.g. fei0

**-sockraw** <device> [<mode>] [--nommaprx] [--promiscuousmode]

**Hardware: Hardware independent, only available for Linux.**

**<Device>**
Network adapter, e.g. eth1

**Optional:**

**<Mode>**
0 = Interrupt mode | 1 = Polling mode

**Optional:**

**--nommaprx**
Disable PACKET_MMAP for receive

**Optional:**

**--promiscuousmode**
Enable promiscuous mode

**-tap** <instance> <mode> <adaptername>

**OpenVPN's Windows TAP**

**<Instance>**
Device instance 1 = first, 2 = second, …

**<Mode>**
0 = Interrupt mode | 1 = Polling mode

**<AdapterName>**
Adapter name

**-winpcap** <ipaddress> <mode>

**Hardware: Hardware independent, only available for Windows.**

**<IpAddress>**
IP address of network adapter card, e.g. 192.168.157.2

**<Mode>**
0 = Interrupt mode | 1 = Polling mode

## 5.2 Running EcMonitorDemoMqtt

The EcMonitorDemoMqtt includes additional functionality to publish process data to an MQTT broker, for example Eclipse Mosquitto (https://mosquitto.org). It additionally requires at least the MQTT broker address.

```
> EcMonitorDemoMqtt -ndis 192.168.157.2 1 -f eni.xml -mqtt localhost -t 0 -v 3
```

The Eclipse Paho MQTT C client library is also required. The EcMonitorDemoMqtt has been developed and tested with version 1.3.10.

A dynamic library file is required in the directory `<InstallPath>/Bin/<OS>/<Arch>`.

- Eclipse Paho MQTT C 1.3.10 download: https://github.com/eclipse-paho/paho.mqtt.c/releases/tag/v1.3.10
- For Linux, the file `paho-mqtt3c.so.1` is included in the binary release.
- For Windows, the file `paho-mqtt3c.dll` must be built from source, see the file `README.md` section *"Building with CMake"* in the source code.

The EcMonitorDemoMqtt publishes process data cyclically and on change detection. The frequency of these messages can be configured, see *Command line parameters*. Each SubDevice variable is assigned a separate MQTT topic:

```
/EtherCAT/Monitor<instance ID>/slavebyname/<slave name>/variable/[output/input]/
↪<variable name>
```

The payload is a raw byte buffer beginning with a 4-byte unsigned integer payload version. The structure of the following bytes is version-specific.

### 5.2.1 Payload version 0

The payload contains the process image data of the variable. Because the size differs for each variable, this data is also of variable size, but is always rounded up to full bytes. E.g. a 1-bit variable will be sent as a `BYTE`.

| Variable type | Offset | Description | Hint |
|---|---|---|---|
| `UINT32` | 0 bytes | Payload version (0) | Little-endian |
| `UINT64` | 4 bytes | Data timestamp in nanoseconds | Little-endian |
| Variable data | 12 bytes | Process image data of the variable | Variable size rounded up to full bytes |

## 5.3 Compiling the EcMonitorDemo

The following main rules can be used to generate the example applications for all operating systems.

- `<OS>` is a placeholder for the operating system used.
- `<ARCH>` for the architecture. If different architectures are supported.

### 5.3.1 Software Development Kit (SDK)

The EC-Monitor development kit is needed to write applications based on the EC-Monitor core. The EC-Monitor core is shipped as a library which is linked together with the application.

The following components are supplied together with an SDK:

- `/Bin`: Executables containing the EC-Monitor core
- `/Doc`: Documentation
- `/Examples`: Example applications as source code
- `/SDK`: EtherCAT® Software Development Kit containing libraries and header files to build C/C++-applications
- `/SDK/INC`: Header files to be included with the application
- `/SDK/LIB`: Libraries to be linked with the application
- `/SDK/FILES`: Additional files for platform integration
- `/Sources/Common`: Shared source code

### 5.3.2 Include search path

The header files are located in the following directories:

```
<InstallPath>/SDK/INC/<OS>/<ARCH>
<InstallPath>/SDK/INC
<InstallPath>/Sources/Common
```

### 5.3.3 Libraries

The libraries are delivered as static, dynamic or both. This is depending on the operating system. They are located in the following directories:

**Static libraries**

```
<InstallPath>/SDK/LIB/<OS>/<ARCH>
```

**EC-Monitor core**

```
libEcMonitor.a
```

**EC-Monitor RAS server (optional)**

```
libEcMonitorRasServer.a
```

**Dynamic libraries**

```
<InstallPath>/Bin/<OS>/<ARCH>
```

**EC-Monitor core**

```
libEcMonitor.so
```

**EC-Monitor RAS server (optional)**

```
libEcMonitorRasServer.so
```

Whether it is a Shared Object `*.so` or a Dynamic Link Library `*.dll` depends on the operating system.

### 5.3.4 Preprocessor definitions

The following preprocessor directives must be set in the build environment or project:

```
EC_MONITOR
```

Exclude the EC-DAQ support in the demo:

```
EXCLUDE_DAQ_SUPPORT
```

# 6 Software Integration

For the integration of the EC-Monitor, the EcMonitorDemo can be seen as an application framework, serve as a template and be expanded accordingly.

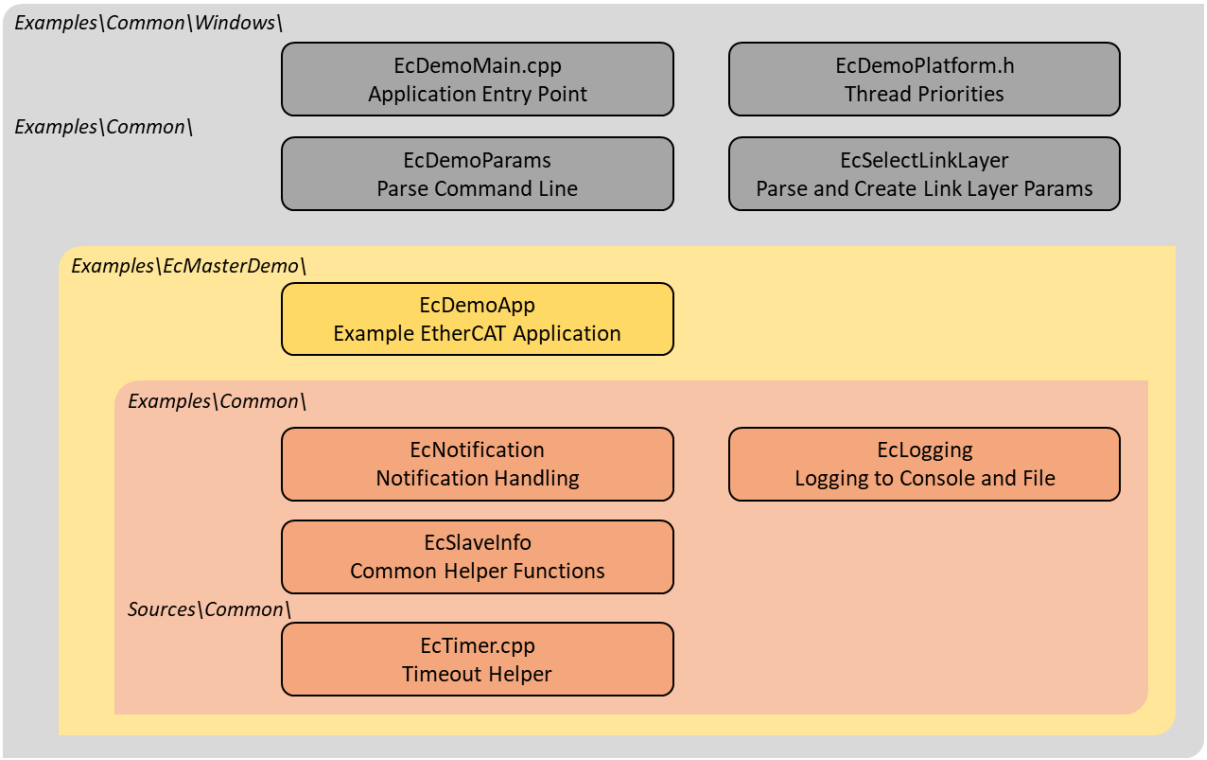
## 6.1 Example application

The example application will handle the following tasks:

- EC-Monitor initialization
- Process Data acquisition with EC-DAQ
- Periodic Job Task in polling or interrupt mode
- Thread with periodic tasks and application thread already implemented
- Record and replay wireshark traces
- Logging. The output messages of the demo application will be printed on the console as well as in some files
- “Out of the box” solution for different operating systems: Windows, Linux …

### 6.1.1 File reference

The EcMonitorDemo application consists of the following files:



| | |
|---|---|
| EcDemoMain.cpp | Entry point for the different operating systems |
| EcDemoPlatform.h | Operating system specific settings (task priorities, timer settings) |
| EcDemoApp.cpp | Initialize, start and terminate EC-Monitor |
| EcDemoApp.h | Application specific settings for EcDemoApp |
| EcDemoParms.cpp | Parsing of command line parameters |
| EcDemoParms.h | Basic configuration parameters |
| EcSelectLinkLayer.cpp | Common Functions which abstract the command line parsing into Real-time Ethernet Driver parameter |
| EcNotification.cpp | SubDevice monitoring and error detection (function `ecatNotify()` ) |
| EcSlaveInfo.cpp | SubDevice information services |
| EcLogging.cpp | Message logging functions |
| EcTimer.cpp | Start and monitor timeouts |

### 6.1.2 EC-Monitor life cycle

Basically the operation of the EC-Monitor is wrapped between the functions

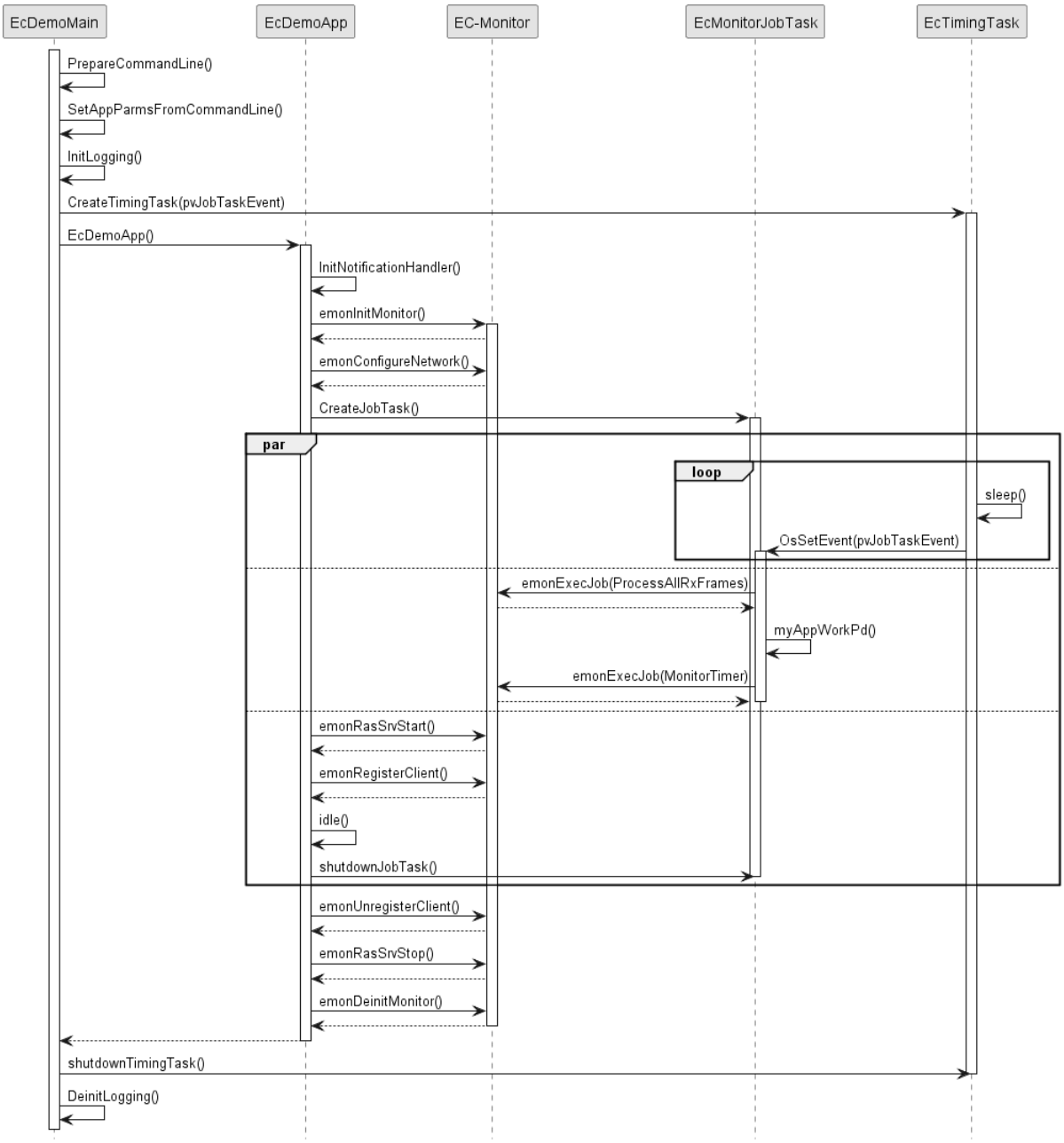
- *emonInitMonitor()*
- *emonConfigureNetwork()*

and

- *emonDeinitMonitor()*

The EC-Monitor is made ready for operation and started with the first two functions mentioned. During this preparation, a thread is set up and started that handles all the cyclic tasks of the EC-Monitor. The last function stops the EC-Monitor and clears the memory.

An overview of the complete life cycle as a sequence diagram:




A more detailed description of the functions:

**EcDemoMain()**
: A wrapper to start the demo from the respective operating system. In addition to initializing the operating system, parsing command line parameters and initializing logging it also starts the timing task.

**EcDemoApp()**
: Demo application. The function takes care of starting and stopping the EC-Monitor and all related tasks. In between, the function runs idle, while all relevant work is done by the EcMonitorJobTask().

**EcMonitorJobTask()**
: Thread that does the necessary periodic work. Very important here is myAppWorkPd() between *eUsrJob_ProcessAllRxFrames* and *eUsrJob_MonitorTimer*. Application-specific access to the process data image can be made here, which is synchronous with the bus cycle.

**EcTimingTask()**
: Timing Thread. This thread sets the timing event that triggers the EcMonitorJobTask for the next cycle.

***emonInitMonitor()***
Prepare the EC-Monitor for operation and set operational parameters, e.g. used Real-time Ethernet Driver, buffer sizes, maximum number of SubDevices, … .

***emonConfigureNetwork()***
Loads the configuration from the ENI (XML file).

***emonRegisterClient()***
Register the application as a client at the EC-Monitor to receive event notifications.

***emonDeinitMonitor()***
Clean up.

## 6.2 Event notification

The EC-Monitor provides event notification for a great number of events. These events are for example:

- Bus state change
- Link state change
- Working counter errors
- …

Any thread can register for these events to be notified. This is achieved by calling the API function

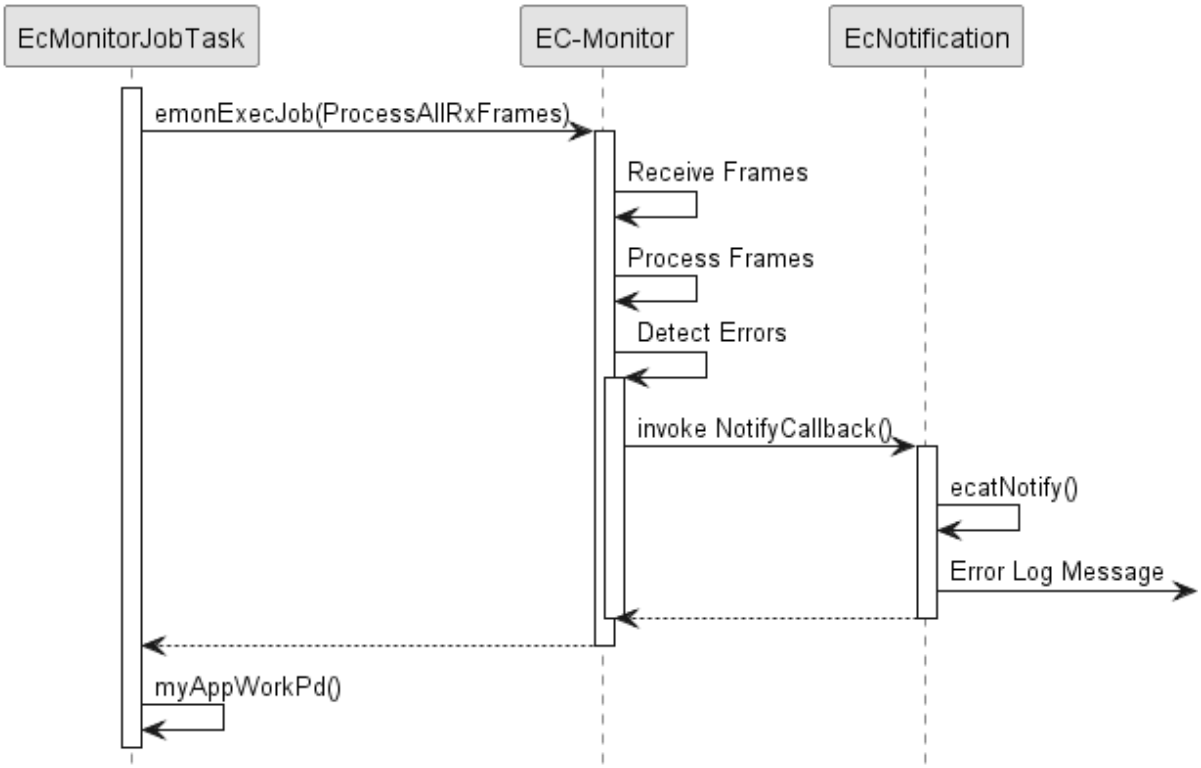
*EC_T_DWORD emonRegisterClient*(*EC_T_DWORD* dwInstanceID, *EC_PF_NOTIFY* pfnNotify, EC_T_VOID *pCallerData, *EC_T_REGISTERRESULTS* *pRegResults)

An example implementation for processing notifications is contained in the class `CEmNotification` of the EcMonitorDemo example, see `Examples/Common/EcNotification.cpp`. It implements the full framework to catch and process the EC-Monitor notifications. The class is instantiated once and registered at the EC-Monitor with the call *emonRegisterClient()*. It contains the method `ecatNotify()` as major entry point (or callback function) for every event notification.

There are two different ways events can be handled. The method of handling an event is primarily determined by the time required to handle the event and the processing context in which the event is to be handled.

### 6.2.1 Direct event notification handling

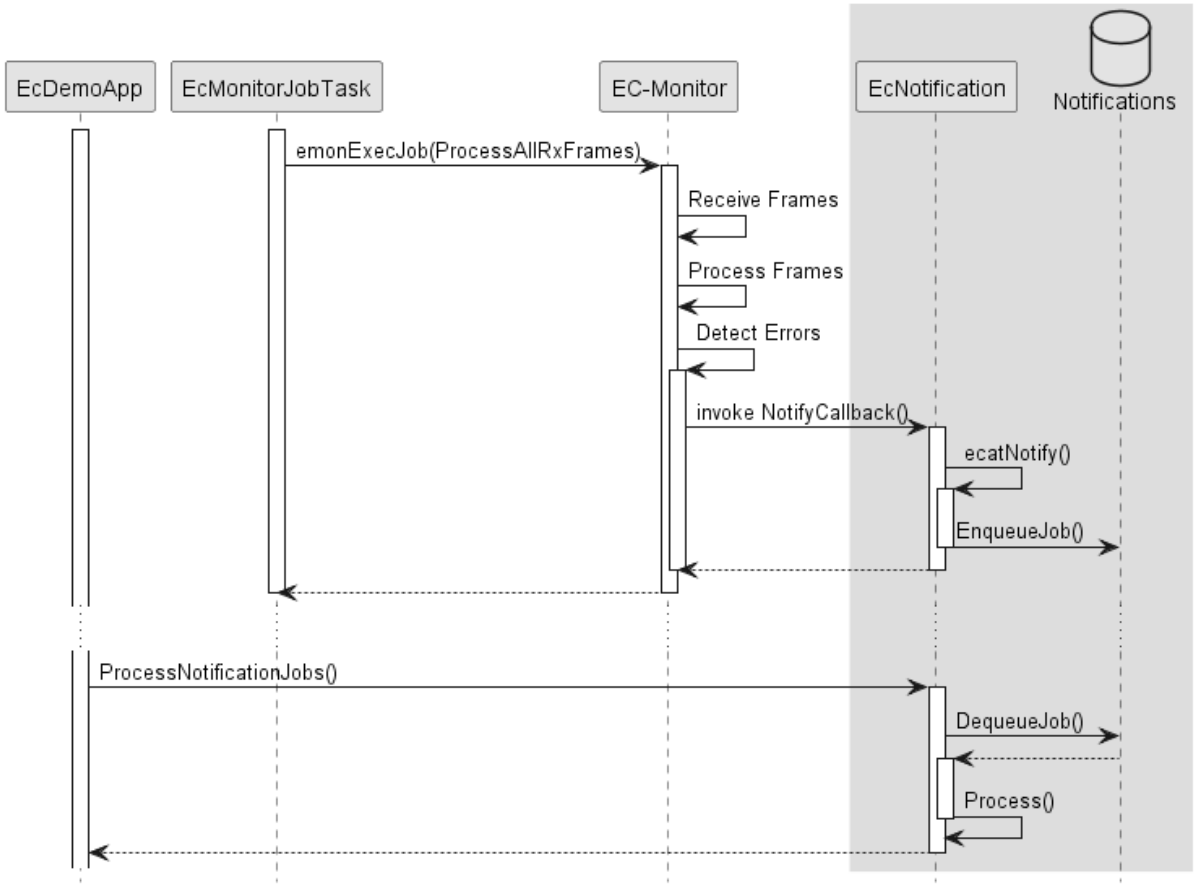
Minor events that take a very short time to process can be handled directly in the context in which they are recognized. A possible example of such an event is the detection of a false working counter (WKC).




The event handling is reduced to simply issuing a log message, which is not time critical. The event is handled directly within the context of the *emonExecJob()* function.

### 6.2.2 Postponed notification handling

Events that require more time-consuming processing cannot be handled directly in the context in which they are detected. The handling or processing of the event must be postponed. This is accomplished through a queue, which is also readily implemented using the `CEmNotification` class.




By calling periodically `CEmNotification::ProcessNotificationJobs()`, the application checks and handles all queued notifications.

---

**Important:** The call of `CEmNotification::ProcessNotificationJobs()` shall NOT be executed in the context of `EcMonitorJobTask()`. As the CPU time consumption may be high, this would have a high impact to the real-time behavior of the cyclic operation.

---

## 6.3 Logging

The EC-Monitor offers a logging interface for a more detailed analysis of application errors, problems in the EtherCAT® network and for diagnosing internal processes. The log messages are passed from the EC-Monitor to the application via the callback *EC_T_LOG_PARMS::pfLogMsg* given at *EC_T_MONITOR_INIT_PARMS::LogParms*.

typedef *EC_T_DWORD* (**EC_PF_LOGMSGHK*)(EC_T_LOG_CONTEXT *pContext, *EC_T_DWORD* dwLogMsgSeverity, const *EC_T_CHAR* *szFormat, ...)

The level of detail of the logging output can be set via *EC_T_LOG_PARMS::dwLogLevel*. The log levels are firmly defined:

EC_LOG_LEVELS

- **EC_LOG_LEVEL_SILENT**
- **EC_LOG_LEVEL_ANY**
- **EC_LOG_LEVEL_CRITICAL**
- **EC_LOG_LEVEL_ERROR**
- **EC_LOG_LEVEL_WARNING**
- **EC_LOG_LEVEL_INFO**
- **EC_LOG_LEVEL_INFO_API**
- **EC_LOG_LEVEL_VERBOSE**
- **EC_LOG_LEVEL_VERBOSE_ACYC**
- **EC_LOG_LEVEL_VERBOSE_CYC**
- **EC_LOG_LEVEL_UNDEFINED**

For performance reasons, the log messages are automatically filtered based on the log level and then passed to the callback.

**Example**

The `EcMonitorDemo` examples demonstrate how log messages can be processed by the application, see `Examples/Common/EcLogging.cpp`. The messages processed by `EcLogging.cpp` are of different types, e.g. EC-Monitor log messages and application messages are logged to the console and/or files. Identical messages are skipped automatically by default.

---

**Note:** With some operating systems, logging in files is deactivated, e.g. because a file system is not available.

---

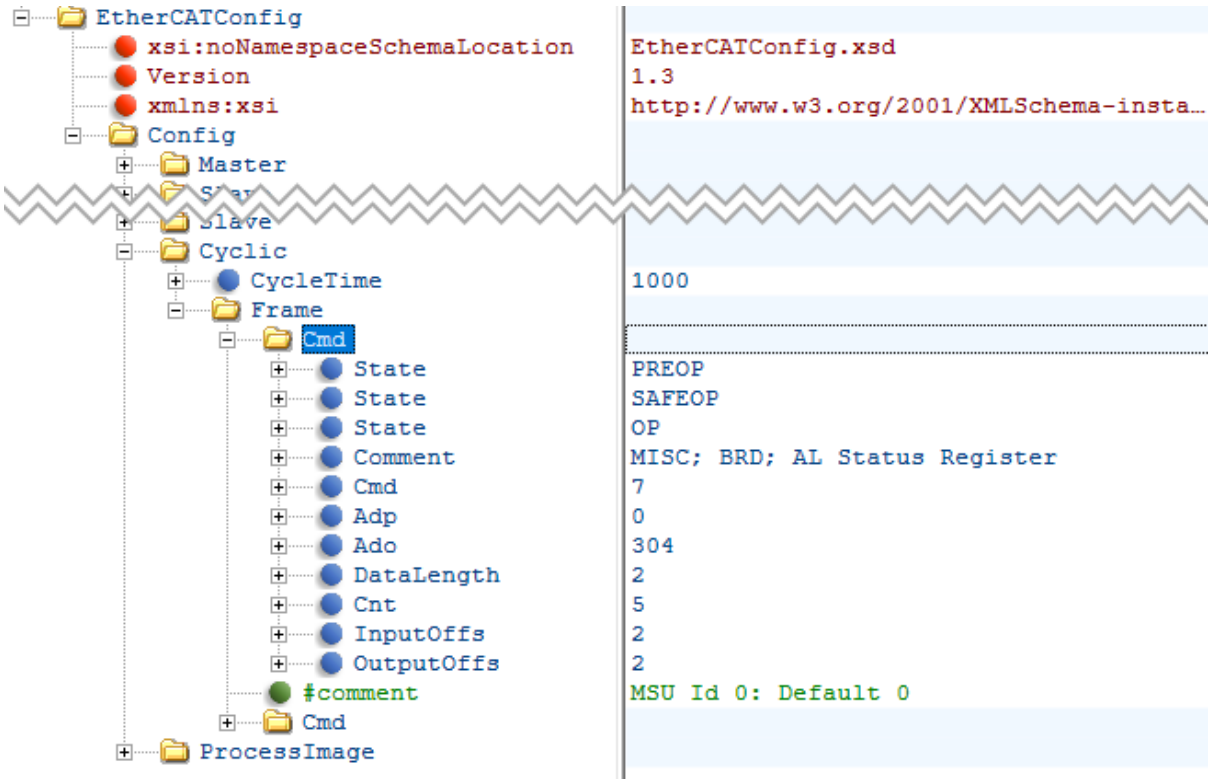
The verbosity of the `EcMonitorDemo` is specified as a `-v` command line parameter. It is used to determine the log level of the application, see `EcDemoMain.cpp`. `EcLogging.cpp` has various parameters beside the log level, like Roll Over setting, log task priority, CPU affinity, log buffer size and etc.

## 6.4 EtherCAT® Network Configuration ENI

The EtherCAT® configuration file ENI contains one or more *Cyclic* entries for reading new input data values and output data values (process data update). These entries contain one or more frames, so-called cyclic frames, which are to be sent cyclically by the EtherCAT® MainDevice. Within the cyclic frames are one or more EtherCAT® datagrams that contain logical read/write commands for accessing the process data values.

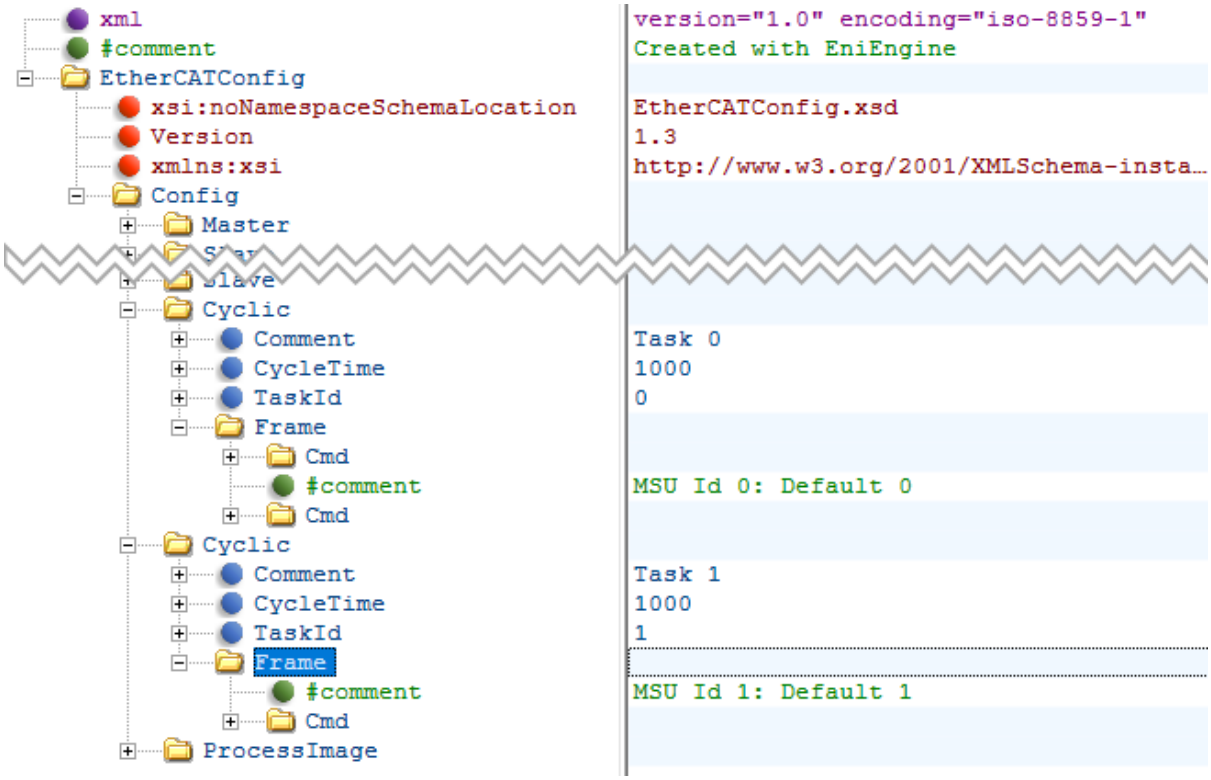
### 6.4.1 Single cyclic entry configuration

In the simplest case, there is only a single cyclic entry with one or more cyclic frames.



### 6.4.2 Multiple cyclic entries configuration

For more complex scenarios it is possible to configure the system using multiple cyclic entries with one or more cyclic frames for each cyclic entry.




## 6.5 Process Data Access

The process data that is exchanged between an EtherCAT® MainDevice and the SubDevices in each cycle is stored in the process data image. There are two separate memory areas, one for the input data and one for the output data. The base addresses of these areas are provided by calling the functions *emonGetProcessImageInputPtr()* and *emonGetProcessImageOutputPtr()*. The size of the process data input image is defined in the ENI file under `EtherCATConfig/Config/ProcessImage/Inputs/ByteSize` and `EtherCATConfig/Config/ProcessImage/Outputs/ByteSize` and is returned by *emonRegisterClient()* at *EC_T_REGISTERRESULTS::dwPDOutSize* and *EC_T_REGISTERRESULTS::dwPDInSize*.

### 6.5.1 Process Data Access Functions

Process data variables that are packed as array of bits are bit aligned and not byte aligned in process data. Accessing bits that are bit aligned and not byte aligned should be done using *EC_GETBITS*. See *EC_COPYBITS* for how to copy data areas with bit offsets that are not byte aligned. Corresponding aligned variables, e.g. of the types *EC_T_BYTE*, *EC_T_WORD*, *EC_T_DWORD*, *EC_T_UINT64*, can be accessed more efficiently using the appropriate macros according to the following table.

---

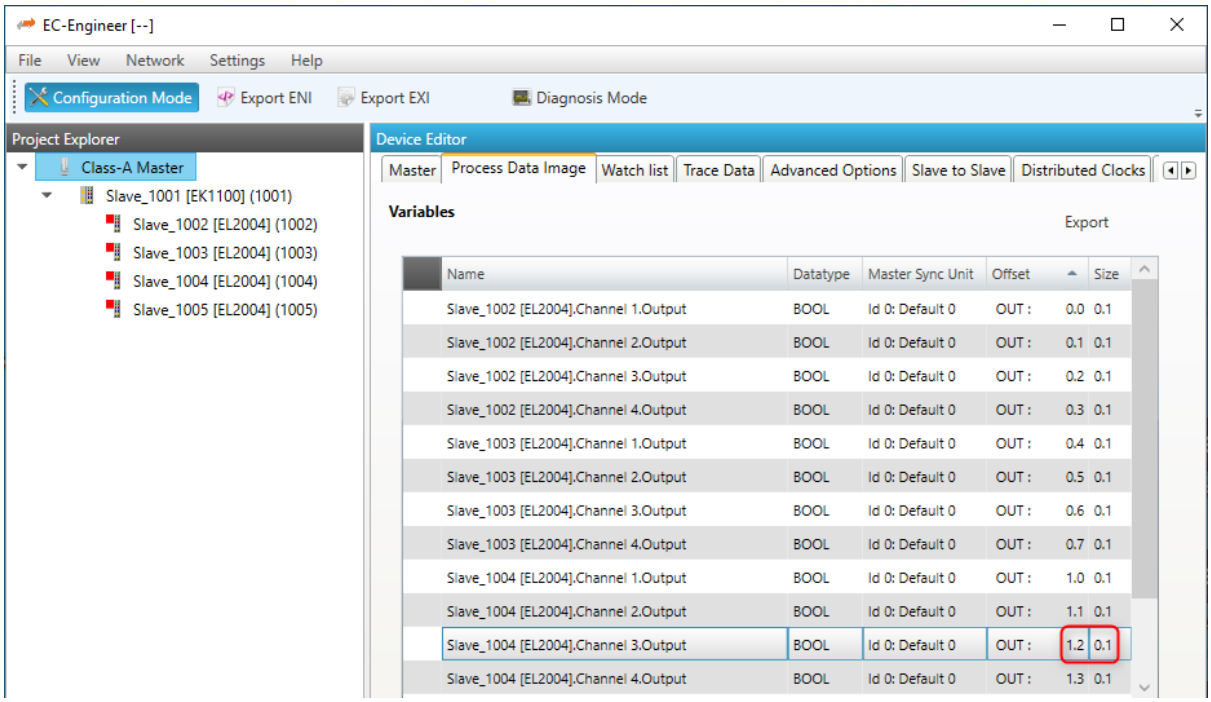
**Note:** Process data is typically transmitted as little endian and must therefore be swapped on big endian systems in order to be correctly interpreted.

---

| Variable type | Bit size | Macro | Hint |
|---|---|---|---|
| Bit | 1 | *EC_GETBITS* | Contains swap for big endian systems |
| *EC_T_BYTE* | 8 | N/A | Bytes can be directly addressed at pbyBuffer[BitOffset/8] |
| *EC_T_WORD* | 16 | *EC_GET_FRM_WORD* | Contains swap for big endian systems |
| *EC_T_DWORD* | 32 | *EC_GET_FRM_DWORD* | Contains swap for big endian systems |
| *EC_T_UINT64* | 64 | *EC_GET_FRM_QWORD* | Contains swap for big endian systems |

### 6.5.2 Process variables' offset and size

The following screenshot shows variables' offset and size within the Process Data Image:




Accessing the process data of a specific SubDevice always works by adding an offset to the base address. All offsets are given as bit offsets!

There are different ways possible to get this offset. The offset values will not change until a new configuration is provided, therefore it is sufficient to load them once right after *emonConfigureNetwork()*, it is not needed every cycle.

### 6.5.3 Process variable access via hard coded offsets

The offset value can be determined from an EtherCAT® configuration tool. It is not recommended to use fixed values as the offsets will change as SubDevices are added/removed from the configuration.

As shown in the screenshot above, *SubDevice_1004 [EL2004].Channel 3.Output* is at offset 1.2 with size 0.1 in the example.

**The numbering is *Byte.Bit* so the offset in the example is *Byte 1*, *Bit 2*, Bit offset:**

$$8 * 1 + 2 = 10$$

**Bit size**

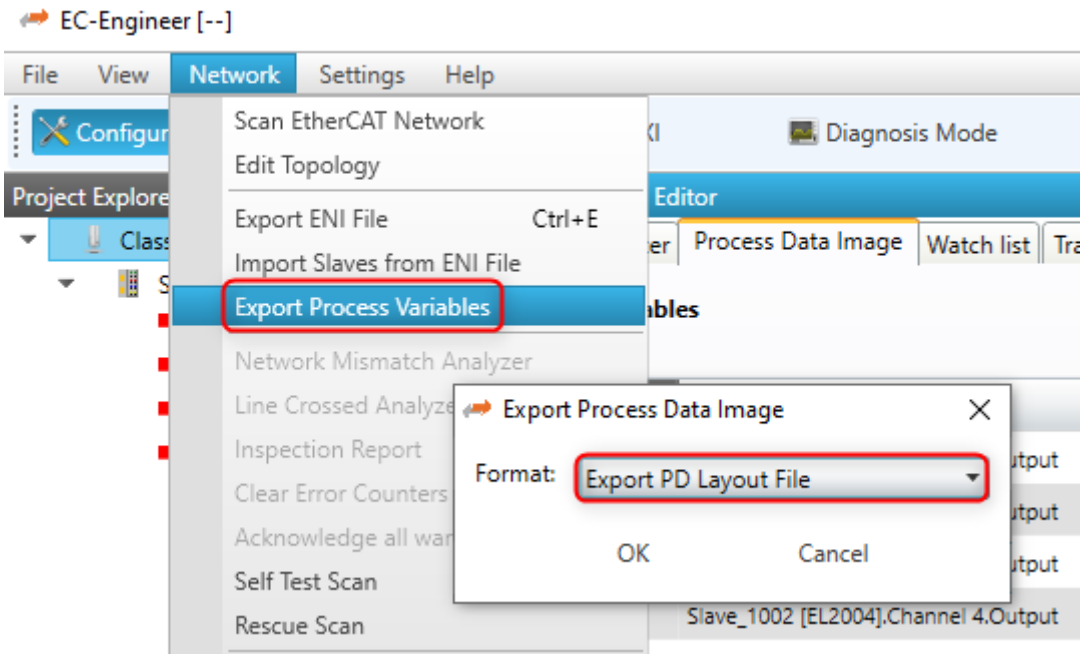
$$0 * 8 + 1 = 1$$

```
EC_T_BYTE* pbyPdOut = emonGetProcessImageInputPtr(dwInstanceId);
EC_T_BYTE  byValue = 0x00;
EC_T_DWORD dwBitOffset = 10;
EC_T_DWORD dwBitSize = 1;

/* get variable in process data */
EC_GETBITS(pbyPdOut, &byValue, dwBitOffset, dwBitSize);
```

### 6.5.4 Process variable access via generated PD Layout

The EC-Engineer / EC-Inspector can export the process variables to a PD-Layout C-Header via the menu item *Network* ▸ *Export Process Variables* as shown in the following screenshot:




This will generate a header file containing the SubDevices' variables as follows:

```
#include EC_PACKED_INCLUDESTART(1)
#define PDLAYOUT_OUT_OFFSET_SLAVE_2002 22
    typedef struct _T_PDLAYOUT_OUT_SLAVE_2002
    {
        EC_T_SWORD  swChannel_1_Output; // Slave_2002 [EL4132].Channel 1.Output ...
        EC_T_SWORD  swChannel_2_Output; // Slave_2002 [EL4132].Channel 2.Output ...
    } EC_PACKED(1) T_PDLAYOUT_OUT_SLAVE_2002;
#include EC_PACKED_INCLUDESTOP
```

Example how a value can be accessed:

```
EC_T_BYTE* pbyPdOut = emonGetProcessImageOutputPtr(dwInstanceId);
T_PDLAYOUT_OUT_SLAVE_2002* pPdOutSlave2002 = (T_PDLAYOUT_OUT_SLAVE_2002*)(pbyPdOut␣
↪+ PDLAYOUT_OUT_OFFSET_SLAVE_2002);

EC_T_WORD wChannel1Out = EC_GET_FRM_WORD(&pPdOutSlave2002->swChannel_1_Output);
```

### 6.5.5 Process variable access dynamically from ENI

#### 6.5.5.1 emonGetCfgSlaveInfo

The SubDevice offsets can be determined dynamically with the function *emonGetCfgSlaveInfo()*. The offsets are stored in *EC_T_CFG_SLAVE_INFO::dwPdOffsIn* and *EC_T_CFG_SLAVE_INFO::dwPdOffsOut*.

Example of how *SubDevice_1004 [EL2004].Channel 3.Output* can be accessed:

```
EC_T_CFG_SLAVE_INFO SlaveInfo;
dwRes = emonGetCfgSlaveInfo(dwInstanceId, EC_TRUE, 1004, &SlaveInfo);

EC_T_BYTE* pbyPdOut = emonGetProcessImageOutputPtr(dwInstanceId);
EC_T_BYTE  byValue = 0x00;
EC_T_DWORD dwBitOffset = SlaveInfo.dwPdOffsOut + 2;
EC_T_DWORD dwBitSize = 1;

/* get variable in process data */
EC_GETBITS(pbyPdOut, &byValue, dwBitOffset, dwBitSize);
```

#### 6.5.5.2 emonGetSlaveOutpVarInfo

All variables of a specific SubDevice can be determined dynamically with the functions *emonGetSlaveInpVarInfoEx()* or *emonGetSlaveOutpVarInfoEx()*. The offset is stored in *EC_T_PROCESS_VAR_INFO_EX::nBitOffs*.

Example of how *SubDevice_1004 [EL2004].Channel 3.Output* can be accessed:

```
EC_T_WORD wNumSlaveVars = 0;
EC_T_WORD wNumVarsRead = 0;
EC_T_PROCESS_VAR_INFO_EX* aProcVarInfo = EC_NULL;

/* get number of output variables */
dwRes = emonGetSlaveOutpVarInfoNumOf(dwInstanceId, EC_TRUE, 1004, &wNumSlaveVars);

/* allocate buffer for the variable info structs */
aProcVarInfo = (EC_T_PROCESS_VAR_INFO_EX*)OsMalloc(sizeof(EC_T_PROCESS_VAR_INFO_
↪EX) * wNumSlaveVars);
OsMemset(aProcVarInfo, 0, sizeof(EC_T_PROCESS_VAR_INFO_EX) * wNumSlaveVars);

/* read all variables of the slave at once */
dwRes = emonGetSlaveOutpVarInfoEx(dwInstanceId, EC_TRUE, 1004, wNumSlaveVars,␣
↪aProcVarInfo, &wNumVarsRead);

EC_T_BYTE* pbyPdOut = emonGetProcessImageOutputPtr(dwInstanceId);
EC_T_BYTE  byValue = 0x00;

/* get variable in process data */
EC_GETBITS(pbyPdOut, &byValue, aProcVarInfo[0].nBitOffs, aProcVarInfo[0].nBitSize);
```

#### 6.5.5.3 emonFindOutpVarByName

The variable offsets can be determined dynamically using the names with the functions *emonFindInpVarByNameEx()* or *emonFindOutpVarByNameEx()*. Each input or output has a unique variable name, all variable names are stored in the ENI file under `EtherCATConfig/Config/ProcessImage/[Inputs|Outputs]/Variable`. The offset is stored in *EC_T_PROCESS_VAR_INFO_EX::nBitOffs*.

Example of how *SubDevice_1004 [EL2004].Channel 3.Output* can be accessed:

```
EC_T_PROCESS_VAR_INFO_EX ProcVarInfo;
dwRes = emonFindOutpVarByNameEx(dwInstanceId, "Slave_1004 [EL2004].Channel 3.Output
↪", &ProcVarInfo);

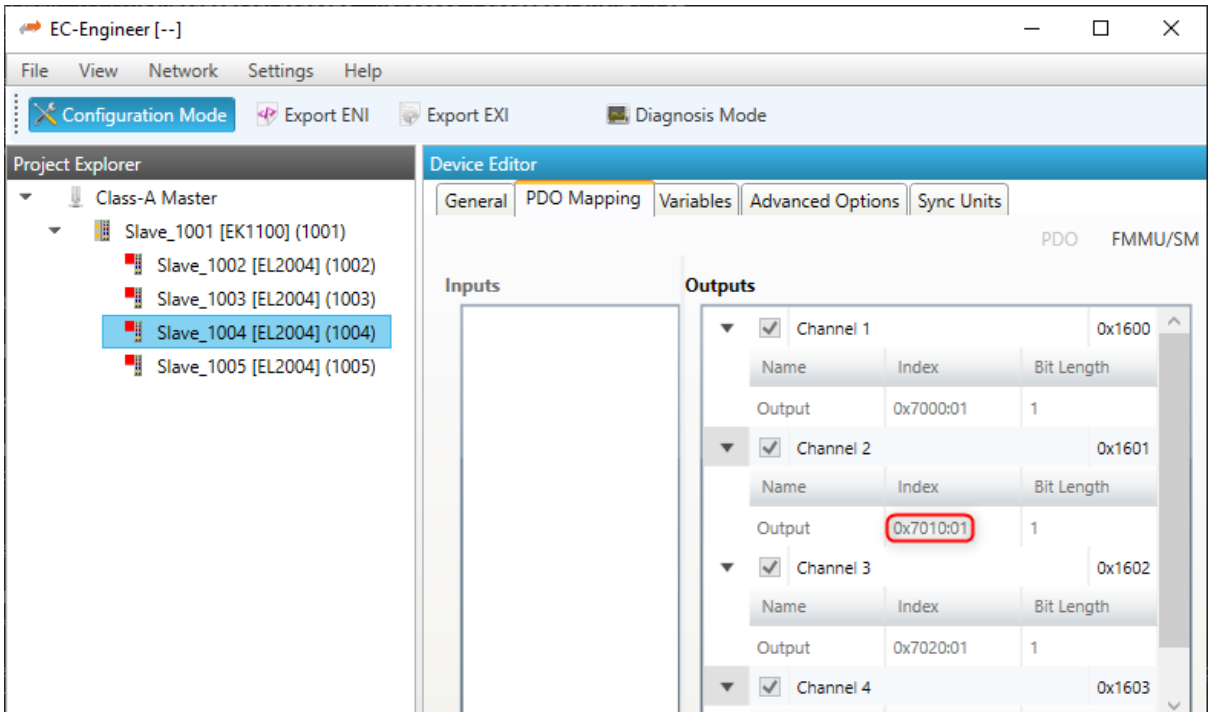
EC_T_BYTE* pbyPdOut = emonGetProcessImageOutputPtr(dwInstanceId);
EC_T_BYTE  byValue = 0x00;

/* get variable in process data */
EC_GETBITS(pbyPdOut, &byValue, ProcVarInfo.nBitOffs, ProcVarInfo.nBitSize);
```

#### 6.5.5.4 emonGetSlaveOutpVarByObjectEx

The variable offsets can be determined dynamically using the object index and subindex with the functions *emonGetSlaveInpVarByObjectEx()* or *emonGetSlaveOutpVarByObjectEx()*.

The object index and subindex can be got with EC-Engineer:




Example of how *SubDevice_1004 [EL2004].Channel 3.Output* can be accessed:

```
EC_T_PROCESS_VAR_INFO_EX ProcVarInfo;
dwRes = emonGetSlaveOutpVarByObjectEx(dwInstanceId, EC_TRUE, 1004, 0x7010, 0x01, &
↪ProcVarInfo);

EC_T_BYTE* pbyPdOut = emonGetProcessImageOutputPtr(dwInstanceId);
EC_T_BYTE  byValue = 0x00;
```

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```
/* get variable in process data */
EC_GETBITS(pbyPdOut, &byValue, ProcVarInfo.nBitOffs, ProcVarInfo.nBitSize);
```

## 6.6 Diagnosis

EtherCAT® offers comprehensive diagnostic capabilities at both hardware and software levels. Errors that can impact a network can be classified into two main categories:

**Hardware errors**

1. Interruptions in the physical medium or unexpected changes in network topology, resulting in frames not reaching all network SubDevices or failing to return to the MainDevice. Examples include damaged cables, loose contacts, or SubDevice resets during operation.
2. All SubDevices are reached by frames, but the correct bit sequence is corrupted. Caused by factors such as electromagnetic disturbances or faulty devices.

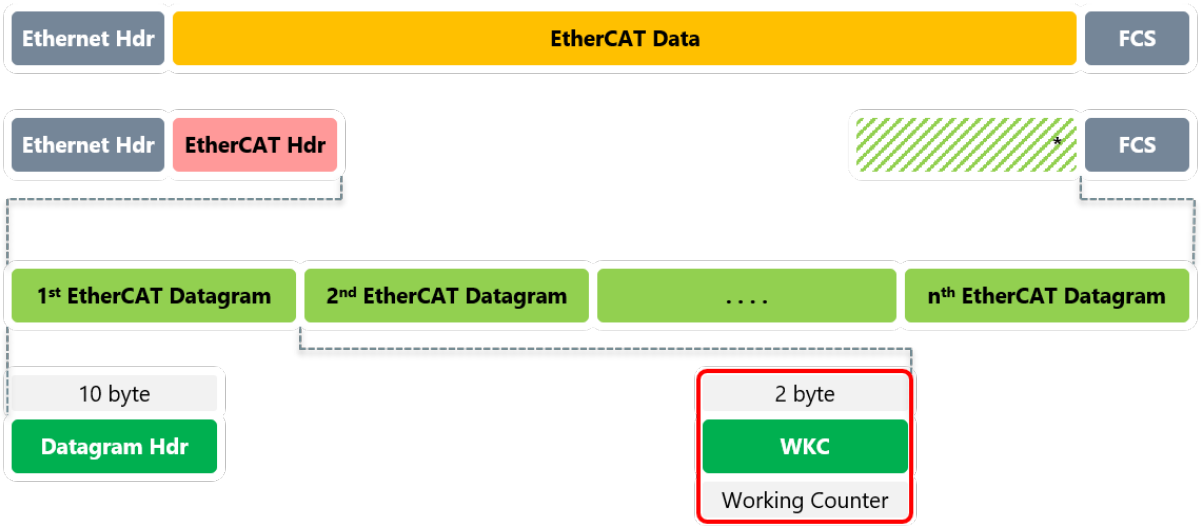
**Software errors**

1. Incorrect or mismatched parameters sent by the MainDevice during the start-up phase, failing to meet SubDevice expectations. This may include errors in process data size/configuration or unsupported cycle times.
2. Previously error-free SubDevices detecting issues during operation, such as synchronization loss or watchdog expiration.

These errors can be diagnosed cyclically or acyclically.

### 6.6.1 Working Counter

Every datagram within an EtherCAT® frame ends with a 16-bit Working Counter (WKC), which increments for each SubDevice that the datagram addresses.




The Working Counter is always received by the EC-Monitor together with the corresponding datagram, and enables therefore an immediate reaction in case of invalid or inconsistent data. The information regarding the Working Counter is essentially digital (*WKC correct* vs. *WKC invalid*), and does not differentiate between various error causes. An invalid WKC can result from several situations:

- One or more SubDevices are not physically connected to the network, or they are not reached by the frames.
- One or more SubDevices have been reset.
- One or more SubDevices are not in the Operational state.

If a datagram returns to the EC-Monitor with an unexpected WKC, the EC-Monitor discards the input data carried by that datagram. The application will be informed by an *emonNotify - EC_NOTIFY_CYCCMD_WKC_ERROR* notification.

In addition to notification, it is also possible to evaluate the WKC states of the individual SubDevices and their process data sections. The following example demonstrates how to evaluate the WKC state of the SubDevice inputs:

```
EC_T_BYTE* pbyDiagnosisImage = emonGetDiagnosisImagePtr(dwInstanceId);
EC_T_CFG_SLAVE_INFO CfgSlaveInfo;

dwRes = emonGetCfgSlaveInfo(dwInstanceId, EC_TRUE, 1002, &CfgSlaveInfo);

for (EC_T_DWORD i = 0; i < EC_CFG_SLAVE_PD_SECTIONS; i++)
{
    if (0xFFFF == CfgSlaveInfo.wWkcStateDiagOffsIn[i])
    {
        /* offset not available */
        break;
    }

    if (EC_TESTBIT(pbyDiagnosisImage, CfgSlaveInfo.wWkcStateDiagOffsIn[i]))
    {
        /* ... error ... */
    }
}
```

**See also:**

*emonGetDiagnosisImagePtr()*, *emonGetCfgSlaveInfo()*

### 6.6.2 MainDevice Sync Units

EtherCAT® configurators can optionally group network SubDevices into disjoint subsets called MainDevice Sync Units. SubDevices in different MainDevice Sync Units are served by separate datagrams and are thus independent from each other in terms of Working Counter diagnostics.

The following example demonstrates how to evaluate the WKC state of the MainDevice Sync Unit 0:

```
EC_T_BYTE* pbyDiagnosisImage = emonGetDiagnosisImagePtr(dwInstanceId);
EC_T_MSU_INFO MsuInfo;

dwRes = emonGetMasterSyncUnitInfo(dwInstanceId, 0, &MsuInfo);

if (EC_TESTBIT(pbyDiagnosisImage, MsuInfo.wWkcStateDiagOffsIn))
{
    /* ... error ... */
}
```

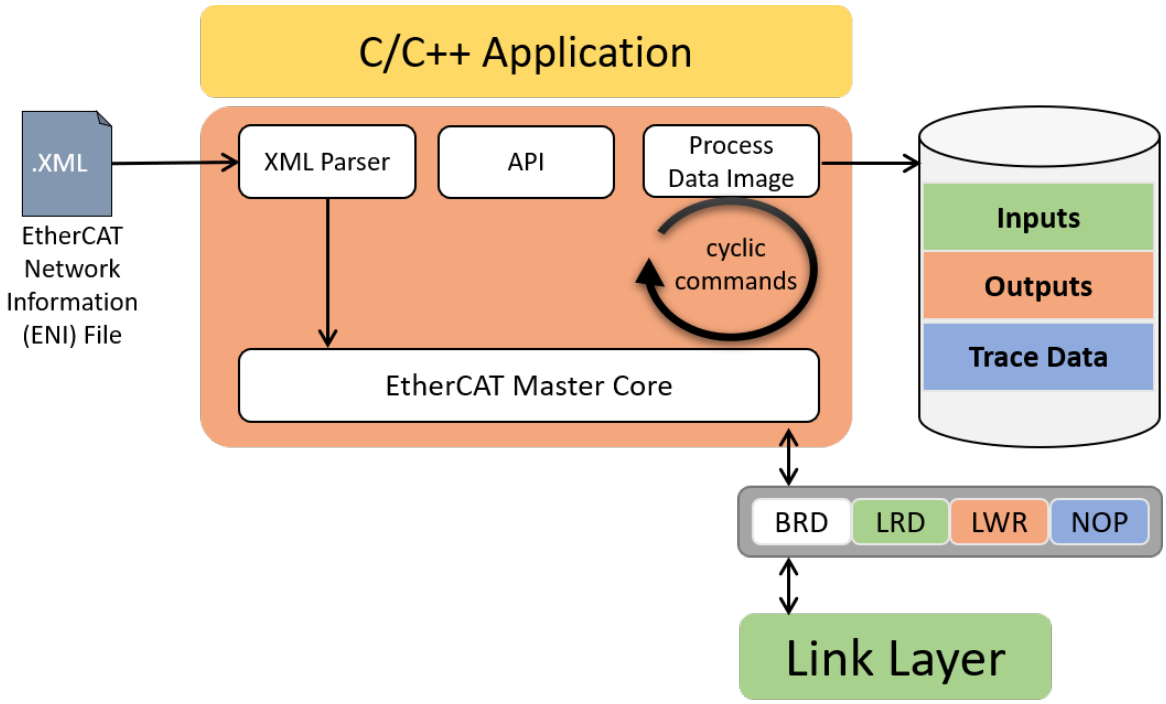
**See also:**

*emonGetDiagnosisImagePtr()*, *emonGetMasterSyncUnitInfo()*

## 6.7 MainDevice Variables

MainDevice variables are an EC-Master extension that allows applications to trace data in real time on the network. To ensure real-time transmission, it is implemented as part of the cyclic process data. They are placed behind the SubDevice output data in the output area of the process data image of the EtherCAT® application. The MainDevice variables can be configured via the ENI with the help of the EC-Engineer.

MainDevice variables can be captured with a network monitoring tool like Wireshark.




To transfer the data, an additional NOP command is appended to the end of the cyclic EtherCAT® frame. The NOP command has ADP 0 and ADO 0x4154. The EC-Master automatically fills the data area of the NOP command with the current MainDevice variables when sending cyclic frames. Since the MainDevice variables are transferred to the network as NOP command, they are not evaluated by any ESC. Therefore, the WKC of the MainDevice variables remains 0 and the application cannot validate the data.

The easiest and most comfortable way to create MainDevice variables is with the help of the EC-Engineer. The necessary NOP command and the process data variables are automatically created and exported to the ENI. The process variables can be accessed as usual using the `emonFindOutpVarByNameEx()` function.

## 6.8 Operation without ENI

The EC-Monitor can operate on a reduced feature set without an ENI file. This is particularly useful in cases where an ENI file is unavailable or inaccessible. To operate the EC-Monitor in this mode, configure the network using the **`eCnfType_GenEBI`** configuration type.

In this mode, the EC-Monitor is able to observe basic information on the bus such as the network topology, SubDevice descriptions and registers. The application can retrieve this information using *emonGetBusSlaveInfo* and *emonReadSlaveRegister* respectively. Because the EC-Monitor does not store or access EtherCAT® SubDevice Information (ESI) files, it does not have a process data image, and APIs which depend on configuration data will be limited or non-functional.

The EC-Monitor supports exporting an ENI Builder (*.ebi) configuration file. This file contains the observed network topology and SubDevice descriptions and can be imported in the acontis EC-Engineer, which can export an ENI file in turn. This ENI file can then be used to operate the EC-Monitor on its full feature set.

**See also:**

- *emonConfigureNetwork*
- *emonExportEniBuilderConfig*

## 6.9 EC-Monitor Source Code

In a source code delivery the EC-Monitor sources are divided into 4 parts:

- SDK Header files
- Real-time Ethernet Driver files (multiple Real-time Ethernet Drivers may be shipped)
- Link OS layer files (only valid for the Real-time Ethernet Drivers)
- EC-Monitor files (configuration, core and interface layer)
- OS layer files

The EC-Monitor can be ported to several different operating systems and CPU architectures with different compilers and development environments. Typically no supported build environment files like IDE projects are shipped with the source code.

To build the EC-Monitor the appropriate build environment for the target operating system has to be used. If an integrated development environment (IDE) exists (Visual Studio, Eclipse, etc.) several projects containing all necessary files are needed to build the artefacts. If no integrated development environment is available makefiles and dependency rules may have to be created which contain the necessary EC-Monitor source and header files.

For most platforms three separate independent binaries will have to be generated:

1. Real-time Ethernet Driver Binary. The Real-time Ethernet Driver binary will be dynamically bound to the application at runtime.
2. EC-Monitor Library
3. Remote API Server Library

### 6.9.1 Real-time Ethernet Driver Binaries

The following files have to be included into an IDE project or makefile:

- Real-time Ethernet Driver files. Only one single Real-time Ethernet Driver must be selected even if multiple Real-time Ethernet Driver are shipped. For each Real-time Ethernet Driver a separate binary has to be created.
- Link OS layer files
- Windows: a dynamic link library (.dll) has to be created. The name of the DLL has to be emllXxxx.dll where Xxxx shall be replaced by the Link Layer type (e.g. emllI8255x.dll for the I8255x Link Layer).

### 6.9.2 EC-Monitor Binaries

The following files have to be included into an IDE project or makefile:

- EC-Monitor files
- OS layer files
- For all platforms a static library has to be created. This library will have to be linked together with the application.

### 6.9.3 Remote API Server Binaries:

The following files have to be included into an IDE project or makefile:

- Remote API server files.
- For all platforms a static library has to be created. This library will have to be linked together with the application.

**See also:**

*Platform and Operating Systems (OS)* for required tool chain settings

# 7 Platform and Operating Systems (OS)

## 7.1 Linux

### 7.1.1 OS optimizations

Linux itself is not real-time capable, so it is recommended to use it with the additional *PREEMPT_RT* patch.

The power management can disrupt cyclical processing, it is advisable to disable the *CPUIDLE sub-system* and *CPUFREQ sub-system*. The sub-systems can be disabled by changing the kernel command line parameters in the boot loader. On x86, x86_64 systems this is usually *GRUB*, on embedded devices with ARM, ARM64 is usually *u-boot*. It is also possible to build a custom kernel without these sub-systems.

Running an EC-Monitor application on a dedicated CPU core that is isolated from the Linux scheduler (*ISOLCPUS*) can provide additional stability.

#### 7.1.1.1 CPUIDLE sub-system

**Check if CPUFREQ sub-system is enabled:**

```
$ ls /sys/devices/system/cpu/
```

If `cpuidle` appears in the list, it is enabled.

**Disable CPUIDLE via the kernel command-line in GRUB:**

```
linux  /boot/vmlinuz-4.19.0-16-rt-amd64 cpuidle.off=1
```

#### 7.1.1.2 CPUFREQ sub-system

**Check if CPUFREQ sub-system is enabled:**

```
$ ls /sys/devices/system/cpu/
```

If `cpufreq` appears in the list, it is enabled.

**Disable CPUFREQ sub-system via the kernel command-line GRUB:**

```
linux  /boot/vmlinuz-4.19.0-16-rt-amd64 cpufreq.off=1
```

If CPUFREQ is not to be deactivated, the governor should be set to `performance`.

**The currently active governor can be determined as follows:**

```
$ cat /sys/devices/system/cpu/cpu*/cpufreq/scaling_governor
```

**The available governors with:**

```
$ cat /sys/devices/system/cpu/cpu*/cpufreq/scaling_available_governors
```

**To change governor use:**

```
$ echo performance > /sys/devices/system/cpu/cpu0/cpufreq/scaling_governor
```

#### 7.1.1.3 ISOLCPUS

**Isolate CPU core number 4 of a quad-core processor via the kernel command-line GRUB:**

```
linux  /boot/vmlinuz-4.19.0-16-rt-amd64 isolcpus=3
```

`isolcpus` alone removes scheduler tasks from selected CPUs, but does not prevent timer interrupts, RCU callbacks, or network adapter IRQs. To fully isolate a CPU for real-time workloads, `nohz_full`, `rcu_nocbs`, and `irqaffinity` should be used together to eliminate kernel noise and ensure deterministic execution.

**Enhanced isolation of CPU core 4 via the kernel command-line GRUB:**

```
linux  /boot/vmlinuz-4.19.0-16-rt-amd64 isolcpus=3 nohz_full=3 rcu_nocbs=3 rcu_
↪nocb_poll irqaffinity=0-2
```

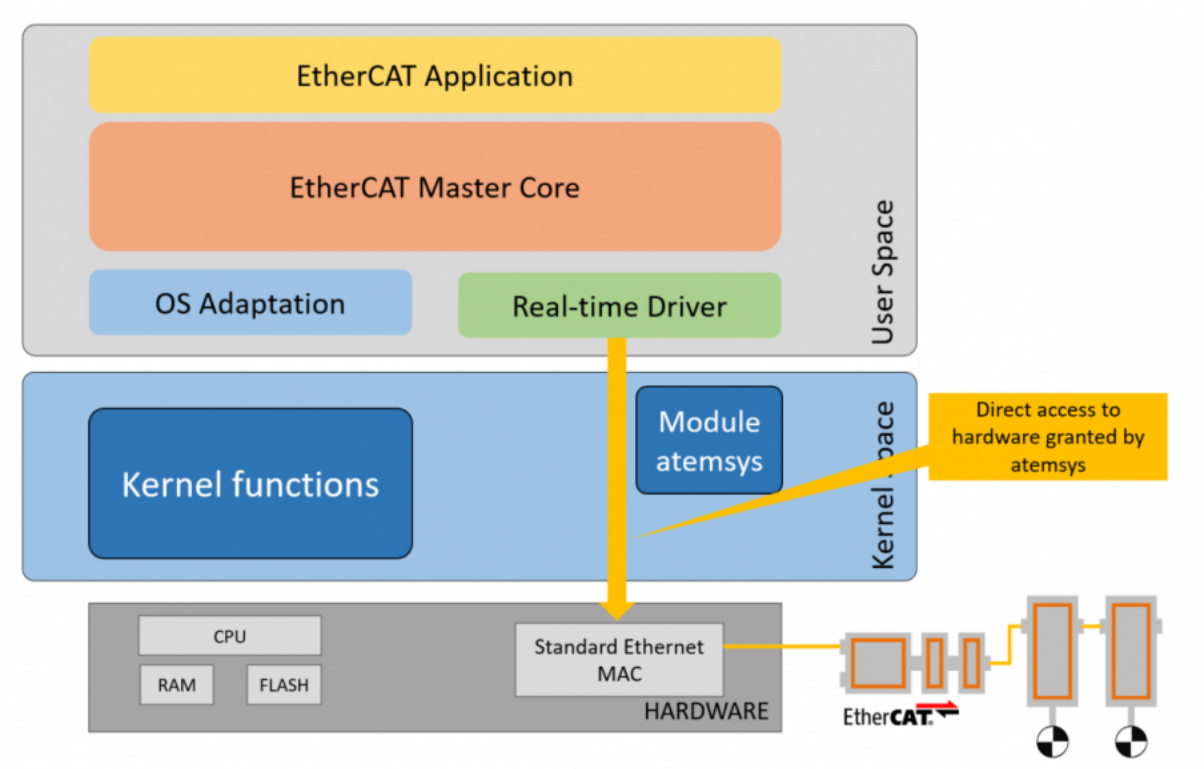
**Running EcMonitorDemo on the isolated CPU core by setting the CPU affinity `-a`:**

```
$ ./EcMonitorDemo -a 3
```

### 7.1.2 atemsys kernel module

To use Real-time Ethernet Drivers under Linux, the atemsys kernel module must be compiled and loaded. atemsys grants direct access to hardware to improve the performance.

All necessary scripts, source code and a detailed description of the installation can be found on https://github.com/acontis/atemsys. A ready-to-use Yocto recipe is also available on https://github.com/acontis/meta-acontis



#### 7.1.2.1 atemsys as Device Tree Ethernet Driver

atemsys can also be used as a device tree driver to avoid certain conflicts between the Real-time Ethernet Driver and the Linux kernel, e.g. power management, shared MDIO bus, etc..

A detailed guide on how to customize the device tree accordingly can also be found on https://github.com/acontis/atemsys. Example device tree modifications for different Real-time Ethernet Drivers/SoC can be found in https://github.com/acontis/atemsys/wiki.

---

**Note:** This is the preferred solution on all embedded devices with device tree support.

---

#### 7.1.2.2 atemsys and PHY OS Driver

To use the PHY OS Driver, the acontis kernel module atemsys has to be included in the kernel device tree as an official driver for the Ethernet controller and doesn't require any additional configuration at the application level. As a result atemsys can interact with Linux drivers.

### 7.1.3 Unbind Ethernet Driver instance

Ethernet Driver instances used by Real-time Ethernet Drivers may not be bound by kernel driver modules! Unbind can be done by unloading the kernel driver module, via the unbind interface of the driver or by modifying the device tree.

#### 7.1.3.1 Unbind from kernel driver

The following command unbinds an instance without unloading the kernel driver module:

**PCI**

```
$ echo "<Instance-ID>" > /sys/bus/pci/drivers/<driver-name>/unbind
```

Example:

```
$ echo "0000:00:19.0" > /sys/bus/pci/drivers/e1000e/unbind
```

This call requires the PCI bus, device, function codes (in the above example it is 0000:00:19.0). The codes can be found using Linux commands like, for example:

```
$ ls /sys/bus/pci/drivers/e1000e
```

**SoC**

```
$ echo "<Instance-ID>" > /sys/bus/platform/drivers/<driver-name>/unbind
```

Example:

```
$ echo "2188000.ethernet" > /sys/bus/platform/drivers/fec/unbind
```

#### 7.1.3.2 Unload kernel driver

Not all drivers allow unbinding of network interfaces. If unbinding is not supported the corresponding Linux kernel driver must not be loaded.

The following command lists the loaded kernel modules that may conflict with Real-time Ethernet Driver:

```
$ lsmod | egrep "<module-name>"
```

Example:

```
$ lsmod | egrep "e1000|e1000e|igb"
```

PCI/PCIe: The command *lspci -v* shows which driver is assigned to which network card, e.g.:

```
$ lspci -v
```

```
...
11:0a.0 Ethernet controller: Intel Corporation 82541PI Gigabit Ethernet Controller␣
↪(rev 05)
...
Kernel driver in use: e1000e
```

Modules can be prevented from loading with the following commands:

```
$ echo blacklist <module-name> | sudo tee -a /etc/modprobe.d/blacklist.conf
$ update-initramfs -k all -u
$ sudo reboot
```

The following table shows the Kernel modules related to the Real-time Ethernet Driver:

| Chip | Real-time Ethernet Driver | Kernel driver(s) | Remarks |
|---|---|---|---|
| Broadcom Genet | emllBcmGenet | genet | Unbind not supported |
| Beckhoff CCAT | emllCCAT | ec_bhf | |
| CPSW | emllCPSW | ti_cpsw | |
| Generic | emllDpdk | | |
| DesignWare 3504 | emllDW3504 | stmmac | |
| | emllEG20T | | |
| Freescale TSEC/eTSEC v1/2 | emllETSEC | gianfar_driver | |
| Freescale FEC and ENET controller | emllFslFec | fec, fec_ptp | |
| Cadence GEM/MACB | emllGEM | gem, macb | |
| Intel Pro/1000 | emllI8254x | igb, e1000, e1000e | |
| Intel Pro/1000 | emllIntelGbe | igb, e1000, e1000e | |
| Intel Pro/100 | emllI8255x | e100 | |
| ICSS | emllICSS | prueth,pruss | Unbind not supported |
| RDC R6040 | emllR6040 | | |
| Realtek RTL8139 | emllRTL8139 | 8139too, 8139cp | |
| Realtek RTL8169 / RTL8111 / RTL8168 | emllRTL8169 | r8169 | Unbind not supported |
| SuperH | emllSHEth | sh_eth | Unbind not supported |
| Generic | emllSockRaw | | |
| Generic | emllSockXdp | | |

### 7.1.4 Docker

It is possible to operate EC-Monitor within a Docker container with realtime priority. The atemsys kernel module should be installed on the host in order to operate the container with the lowest possible capabilities and privileges.

The following additional settings, permissions for `docker run` are required:

**Add atemsys device to container**

```
--device=/dev/atemsys:/dev/atemsys
```

**Allow max realtime priority**

```
--ulimit rtprio=99
```

**Add capability to set priority an lock memory**

```
--cap-add=sys_nice
--cap-add=ipc_lock
```

**Publish RAS server port *6000***

```
-p 6000:6000
```

### 7.1.5 Setting up and running EcMonitorDemo

1. Unbind Ethernet Driver instance, e.g.

   ```
   $ echo 0000:00:19.0 > /sys/bus/pci/drivers/e1000e/unbind
   ```

2. Load atemsys kernel module

   ```
   $ insmod atemsys.ko
   ```

3. Copy files from EC-Monitor package `/bin` and a `eni.xml` to directory e.g. `/tmp`.

4. Adjust *LD_LIBRARY_PATH* search locations for Real-time Ethernet Driver if necessary, e.g.

   ```
   $ export LD_LIBRARY_PATH=/tmp:$LD_LIBRARY_PATH
   ```

5. Run EcMonitorDemo

   ```
   $ cd /tmp
   $ ./EcMonitorDemo -intelgbe 1 1 -f eni.xml -perf
   ```

**See also:**

*Running EcMonitorDemo*

#### 7.1.5.1 Run in Docker container

1. Unbind Ethernet Driver instance and load atemsys on the host.
2. Create a directory on the host (e.g. `~/docker`) and copy files from EC-Monitor package `/bin` and `exi.xml` into this directory.
3. **Start bash console in container**

   ```
   $ sudo docker run -it      --name atem_container
   ↪  --device=/dev/atemsys:/dev/atemsys      --ulimit rtprio=99
   ↪  --cap-add=sys_nice --cap-add=ipc_lock      -v ~/docker:/home/docker
   ↪  -p 6000:6000      ubuntu bash
   ```

   **Command line arguments:**

   - `-it` Allocate a pseudo-TTY and run container
   - `--name atem_container` Container name
   - `--device=/dev/atemsys:/dev/atemsys` Add *atemsys* device to container
   - `--ulimit rtprio=99` Allow max realtime priority
   - `--cap-add=sys_nice` Add Linux capability to set priority
   - `--cap-add=ipc_lock` Add Linux capability to lock memory

- `-v ~/docker:/home/docker` Mount previously create directory to container
- `-p 6000:6000` Publish RAS server port *6000*
- `ubuntu bash` Use Docker image ubuntu and start bash

4. Run EcMonitorDemo in container

```
# cd /home/docker
# export LD_LIBRARY_PATH=.
# ./EcMonitorDemo -intelgbe 2 1 -f eni.xml -perf
```

### 7.1.6 OS Compiler settings

Besides the general settings from *Compiling the EcMonitorDemo* the following settings are necessary to build the example application for Linux

**Possible ARCHs (see ATECAT_ARCHSTR in `SDK/INC/Linux/EcOsPlatform.h`):**

- aarch64 (ARM 64Bit)
- armv4t-eabi (ARM 32Bit)
- armv6-vfp-eabihf (ARM 32Bit)
- armv7-vfp-eabihf (ARM 32Bit)
- PPC (PPC 32Bit with “-te500v2”)
- riscv64 (RISC-V 64Bit)
- x64 (x86 64Bit)
- x86 (x86 32Bit)

**The ARM 32Bit architectures *armv4t-eabi* and *armv6-vfp-eabihf/armv7-vfp-eabihf* are incompatible with each other. An ARM VFP system returns success on**

```
$ readelf -A /proc/self/exe | grep Tag_ABI_VFP_args
```

**Extra include paths**

```
<InstallPath>/Examples/Common/Linux
<InstallPath>/SDK/INC/Linux
```

**Extra source paths**

```
<InstallPath>/Examples/Common/Linux
<InstallPath>/Sources/OsLayer/Linux
```

**Extra library paths to the main EtherCAT® components**

```
<InstallPath>/SDK/LIB/Linux/<Arch>
```

**Extra libraries (in this order)**

```
EcMonitor pthread dl rt
```

### 7.1.7 Build using cmake on Linux

Example usage to build Linux x64 Debug with cmake:

```
$ cmake -DEC_OS=Linux -DEC_ARCH=x64
$ cmake --build .
```

### 7.1.8 Cross-platform development under Windows

The following steps describe how to develop Linux cross-platform developing on Windows for Linux:

```
-DEC_OS=Windows -DEC_ARCH=x64
```

1. **Install MinGW**

   - Download the latest version of MinGW from the MinGW official website https://osdn.net/projects/mingw/
   - Install the mingw-get-setup.exe tool to C:\MinGW
   - Select the "Basic Setup"
   - Apply changes

2. **Install a cross platform toolchain**

   - Download a cross-platform toolchain from e.g. the Linaro release storage server https://releases.linaro.org/components/toolchain/gcc-linaro/
   - Unpack it to C:\MinGW\opt

3. **Build using cmake on Linux**

   Example usage to build for Linux x64 Debug on Windows with cmake and ninja:

   ```
   $ cmake -DEC_OS=Linux -DEC_ARCH=x64 -DCMAKE_BUILD_TYPE=Debug .
   $ cmake --build .
   ```

4. **Build for LxWin using cmake on Linux**

   Example usage to build EcMasterDemo for Linux x64 Debug on Windows with cmake and ninja:

   ```
   Workspace/LxWin/cmake/x64/Debug> cmake.exe -G Ninja ../../../../..
   ↪  -DCMAKE_TOOLCHAIN_FILE=../../../../Linux/Toolchain.cmake -DEC_OS=LxWin
   ↪  -DEC_ARCH=x64 -DCMAKE_BUILD_TYPE=Debug
   Workspace/LxWin/cmake/x64/Debug> ninja.exe EcMasterDemo
   ```

5. **Cross build using cmake for Linux on Windows**

   Example usage to build EcMasterDemo for Linux x64 Debug on Windows with cmake and ninja:

   ```
   Workspace/Linux/cmake/x64/Debug> cmake.exe -G Ninja ../../../../..
   ↪  -DCMAKE_TOOLCHAIN_FILE=../../../Toolchain.cmake -DEC_OS=Linux -DEC_ARCH=x64
   ↪  -DCMAKE_BUILD_TYPE=Debug
   Workspace/Linux/cmake/x64/Debug> ninja.exe EcMasterDemo
   ```

6. **Cross build using Eclipse CDT on Windows**

   - Download and install the latest version of Eclipse CDT from the Eclipse official website https://projects.eclipse.org/projects/tools.cdt
   - Create a start batch file for eclipse

```
set PATH=C:\MinGW\bin;C:\MinGW\msys\1.0\bin;%LINUX_CROSS_GCC_ARM_PATH%;
↪%PATH%
set LINUX_CROSS_GCC_ARM_PATH=C:\MinGW\opt\gcc-linaro-7.3.1-2018.05-i686-
↪mingw32_aarch64-linux-gnu\bin
set CFLAGS=-IC:\MinGW\opt\gcc-linaro-7.3.1-2018.05-i686-mingw32_aarch64-
↪linux-gnu\aarch64-linux-gnu\libc\usr\include
set CROSS_COMPILE=aarch64-linux-gnu-
set ARCH=aarch64
eclipse.exe
```

## 7.2 QNX Neutrino

### 7.2.1 Thread priority

QNX supports a total of 256 scheduling priority levels. A non-root thread can set its priority to a level from 1 to 63 (the highest priority).

Using priorities higher than 63 is only possible if the allowed priority range is changed for non-root processes:

```
$ procnto -P priority
```

For more information on changing the priority range refer to the QNX documentation.

**Attention:** Not changing the priority range leads to poor timing performance!

### 7.2.2 Unbind Ethernet Driver instance

The network interface must be unloaded if it is used by an operating system driver. Depending on the QNX version, a corresponding command must be executed in the QNX Shell or the QNX Build Script.

**QNX >= 6.5**

```
ifconfig en1 destroy
```

**QNX >= 7.1**

```
umount /dev/io-sock/devs-em.so/em1
```

### 7.2.3 IOMMU/SMMU support

For systems that have to use an IOMMU/SMMU for security reasons, it is possible to create a predefined typed memory region that is used by the Real-time Ethernet Driver. The definition has to be done in the QNX BSP build file and the name must match following pattern:

**smm_** *LinkLayerName* **-** *InstanceNumber(32Bit Hex)*

**Example: Real-time Ethernet Driver emllIntelGbe with instance number 1**

```
smm_emllIntelGbe-0x00000001
```

A separate typed memory region must be defined for each Real-time Ethernet Driver instance. The typed memory is automatically used by the Real-time Ethernet Driver if it matches the pattern, otherwise the default memory is used.

### 7.2.4 Setting up and running EcMonitorDemo

1. QNX Neutrino OS configuration

   In order to get real-time priority (e.g. 250), see *Thread priority* and also set JOBS_PRIORITY. The application needs root privileges to increase the priority above 63.

2. Unbind Ethernet Driver instance, e.g.

   ```
   $ ifconfig en1 destroy
   ```

3. Copy files from EC-Monitor package `/bin` and `eni.xml` to directory, e.g. `/tmp`.

4. Adjust *LD_LIBRARY_PATH* search locations for Real-time Ethernet Driver if necessary, e.g.

   ```
   $ export LD_LIBRARY_PATH=/tmp:$LD_LIBRARY_PATH
   ```

5. Run EcMonitorDemo

   ```
   $ cd /tmp
   $ ./EcMonitorDemo -intelgbe 1 1 -f eni.xml -perf
   ```

**See also:**

*Running EcMonitorDemo*

### 7.2.5 OS Compiler settings

Besides the general settings from *Compiling the EcMonitorDemo* the following settings are necessary to build the example application for QNX Neutrino.

**Extra include paths**

```
<InstallPath>/SDK/INC/QNX
<InstallPath>/Examples/Common/QNX
```

**Extra source paths**

```
<InstallPath>/Examples/Common/QNX
<InstallPath>/Sources/OsLayer/QNX
```

**Extra library paths to the main EtherCAT® components**

```
<InstallPath>/SDK/LIB/QNX/<Arch>
```

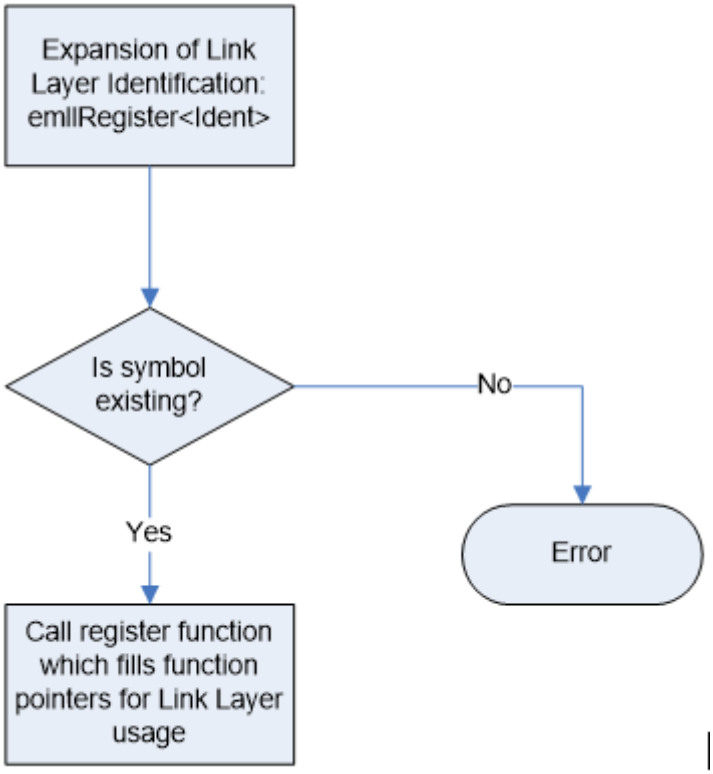
**Extra libraries (in this order)**

```
EcMonitor socket
```

## 7.3 Windriver VxWorks

Real-time Ethernet Drivers for VxWorks are available. If none of the Real-time Ethernet Drivers can be used, the SNARF Ethernet Driver must be selected.

The identification of the Real-time Ethernet Driver is done like this:




### 7.3.1 VxWorks native

The BSP has to be prepared to support Real-time Ethernet Driver:

1. To use a Real-time Ethernet Driver the adapter memory has to be mapped into VxWorks memory space (VxWorks 5.x only). I.e. for the Intel Pro/100 Ethernet Driver this can be achieved by setting the INCLUDE_FEI_END macro in the BSP configuration file config.h.
2. To avoid conflicts with the VxWorks network driver which normally will be loaded when INCLUDE_FEI_END is set the file configNet.h has to be adjusted in a way that the network driver is not loaded. The network driver entry has to be removed from the endDevTbl[]:

```
END_TBL_ENTRY endDevTbl [] =
    {
    :       :       :
    :       :       :
    :       :       :
/*
#ifdef INCLUDE_FEI_END
    {0, FEI82557_LOAD_FUNC, FEI82557_LOAD_STRING, FEI82557_BUFF_LOAN,
    NULL, FALSE},
#endif /* INCLUDE_FEI_END */
*/
    :       :       :
    :       :       :
```

**Warning:** Do not call `muxDevUnload()` for a network adapter managed by a VxBus driver. VxBus drivers expect to call `muxDevUnload()` themselves in their {vxbDrvUnlink}() methods, and instability may result if `muxDevUnload()` is called for a VxBus network device instance by other code.

**See also:**

The VxWorks Device Driver Developer's Guide for more information about unloading VxBus devices

### 7.3.2 SNARF Ethernet Driver

The SNARF Ethernet Driver is only needed if none of the Real-time Ethernet Driver can be used. The appropriate network adapter drivers have to be added to the VxWorks image.

### 7.3.3 Setting up and running EcMonitorDemo

1. **VxWorks OS configuration**
   See sections above.
2. **Determine the network interface**
   Using the command line option the network interface card and Real-time Ethernet Driver to be used in the example application can be determined.
3. **Connection of the EtherCAT® SubDevices**
   The SubDevices have to be connected with the VxWorks system using an Ethernet switch or a patch cable. Local IT infrastructure should not be mixed with EtherCAT® modules at the same switch as the EC-Monitor will send many broadcast packets! EtherCAT® requires a 100Mbit/s connection. If the VxWorks network adapter card does not support this speed a 100Mbit/s (!) Ethernet switch has to be used.
4. **Download a Real-time Ethernet Driver module**
   The Real-time Ethernet Driver library (e.g. `emllIntelGbe.out`) which contains hardware support for the corresponding NIC must be downloaded. By default the Ethernet Driver emllSnarfGpp are contained in the binary delivery.
5. **Download the example application**
   The target has to be started and a target-server connection will have to be established. After this the example application can be downloaded into the target.
6. **Set up an FTP server connection on host**
   The demo application needs to load an XML file (`eni.xml`) for the configuration of the EC-Monitor. This file can be accessed using an FTP server. The screen shot below shows how to configure the FTP server. The directory contents can be checked via FTP using the `ls` command. The file `eni.xml` will have to be accessed using the default directory.
7. **Check for exclusive hardware access**
   Be sure that the network adapter instance dedicated to EtherCAT® is not controlled by a VxWorks driver, this can be verified using:

   ```
   -> muxShow
   ```

   If it is needed, first unload the driver using: (e.g. first instance of the Intel Pro/100):

   ```
   -> muxDevUnload "fei", 1
   ```

   (e.g. second instance of the Intel Pro/1000):

   ```
   -> muxDevUnload "gei", 2
   ```

   (e.g. first instance of the Realtek 8139):

   ```
   -> muxDevUnload "rtl", 1
   ```

   (e.g. first instance of the Realtek 8169):

```
-> muxDevUnload "rtg", 1
```

(e.g. first instance of the FEC on Freescale iMX platform):

```
-> muxDevUnload "motfec", 1
```

(e.g. first instance of the ETSEC on Freescale PPC platform):

```
-> muxDevUnload "motetsec", 1
```

8. **Run the example application**
   The downloadable module `EcMonitorDemo.out` has to be executed. The configuration file `eni.xml` will be used and thus has to be accessible in the current working directory. The appropriate Real-time Ethernet Driver and network adapter card have to be selected. If the log files shall be written the global variable `bLogFileEnb` has to be set to 1 prior to starting the demo.

   Loading and running the demo:

```
-> ld<EcMonitorDemo.out
-> sp EcMasterAppMain,"-intelgbe 1 1 -f eni.xml"
```

**See also:**

*Running EcMonitorDemo*

### 7.3.4 OS Compiler settings

Besides the general settings from *Compiling the EcMonitorDemo* the following settings are necessary to build the example application for VxWorks.

**Extra include paths**

```
<InstallPath>/SDK/INC/VxWorks
<InstallPath>/Examples/Common/VxWorks
```

**Extra source paths**

```
<InstallPath>/Examples/Common/VxWorks
<InstallPath>/Sources/OsLayer/VxWorks
```

**Extra library paths to the main EtherCAT® components**

```
<InstallPath>/SDK/LIB/VxWorks/<ARCH>
```

**GNU/PowerPC**

`-mlongcall` compiler option may be needed to avoid relocation offset errors when downloading `.out` files.

## 7.4 Microsoft Windows

### 7.4.1 EcMonitorDemo

1. **Install EC-Monitor**
   Run `setup.exe` from EC-Monitor package, which will guide you through the installation process.
2. **Determine the network interface**
   For example the option *-ndis 192.168.1.1 1* will be using the network adapter card with the IP address 192.168.1.1.
3. Insert a TAP device after the MainDevice Controller to capture the EtherCAT® traffic and start the EtherCAT® MainDevice

4. **Run the example application**
   Execute EcMonitorDemo.exe from `<InstallPath>/Bin/Windows/<Arch>/`. At least an Ethernet Driver option has to be given.

   ```
   C:
   > EcMonitorDemo -ndis 192.168.1.1 1 -f D:/eni.xml -sp
   ```

**See also:**

*Running EcMonitorDemo* for a detailed description of the demo application.

### 7.4.2 EcMonitorDemoGuiDotNet (.NET) - Microsoft Windows

1. **Prerequisites**
   To run the `EcMonitorDemoGuiDotNet.exe`, the libraries `EcMonitor.dll`, `EcWrapperDotNet.dll`, `EcWrapper.dll` and `emllNdis.dll` from `Bin/Windows/x64` are needed in `Bin/Windows/x64/Release`, `Bin/Windows/x64/Debug`
2. **Visual Studio C#-project**
   The C#-project for VS2015 or higher is located at `Workspace/WindowsVS2015/EcMonitorDemoGuiDotNet/EcMonitorDemoGuiDotNet.csproj`
3. If the reference EcWrapperDotNet is missing, it must be re-added from `Bin/Windows/x64/EcWrapperDotNet.dll`
4. EcMonitorDemoGuiDotNet is now prepared for Run/Debug

### 7.4.3 OS Compiler settings

Besides the general settings from *Compiling the EcMonitorDemo* the following settings are necessary to build the example application for Windows.

**Extra include paths**

```
<InstallPath>\SDK\INC\Windows
<InstallPath>\Examples\Common\Windows
```

**Extra source paths**

```
<InstallPath>\Examples\Common\Windows
<InstallPath>\Sources\OsLayer\Windows
```

**Extra library paths to the main EtherCAT® components**

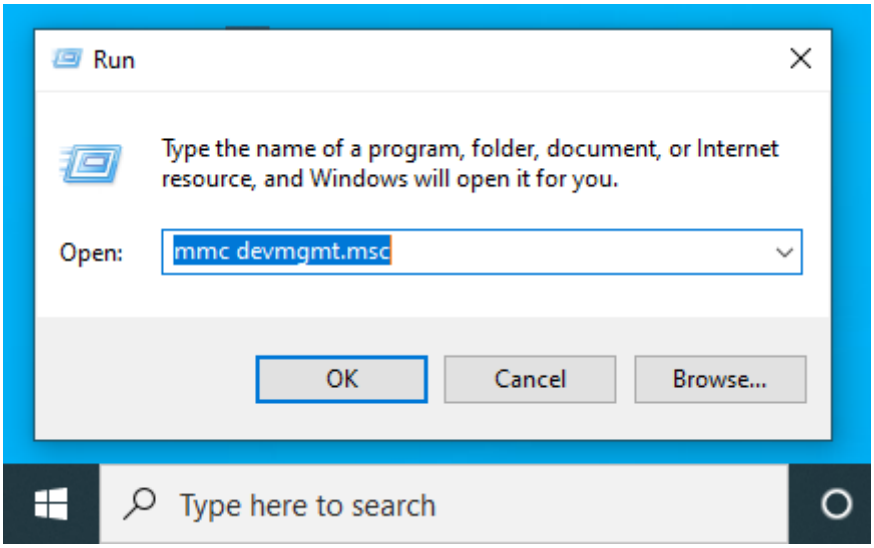
```
<InstallPath>\SDK\LIB\Windows
```

### 7.4.4 RtaccDevice for Real-time Ethernet Driver

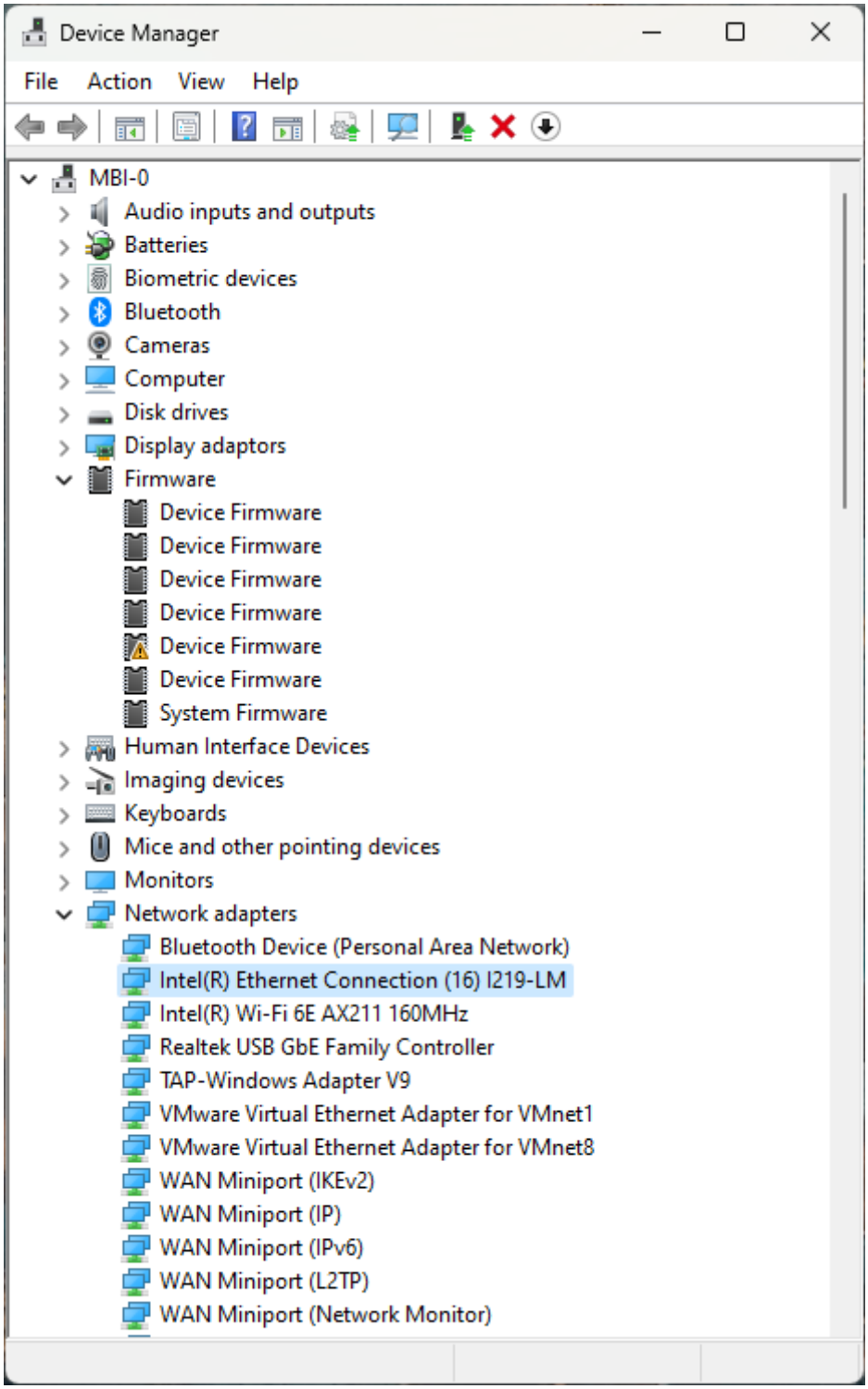
As alternative to the NDIS based or Pcap based Ethernet Driver, an optional Real-time Ethernet Driver on Windows can be installed. The Real-time Ethernet Driver replaces the original Windows driver and also requires an extra license.

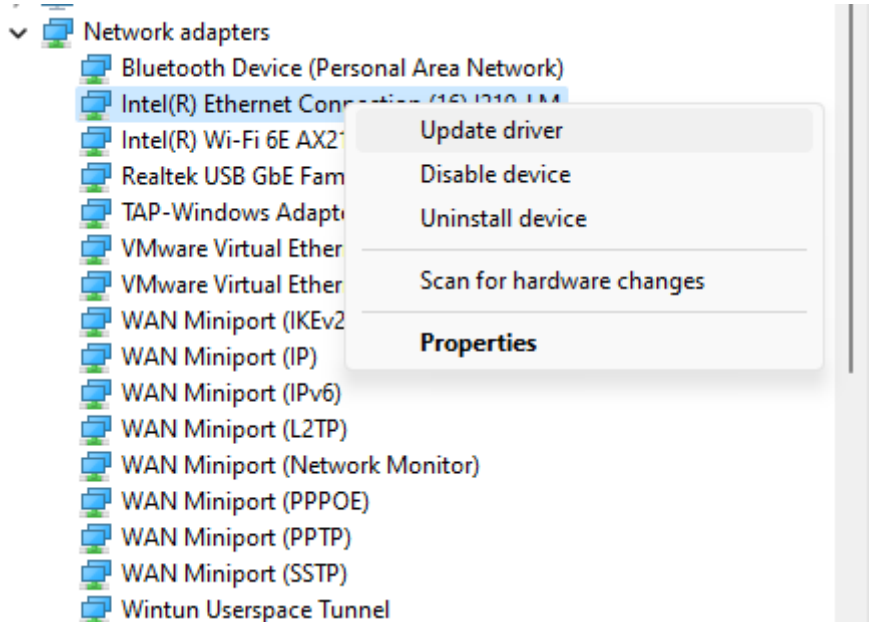
To **use the Real-time Ethernet Driver under Windows**, it is necessary to install the RtaccDevice driver included in the Real-time Ethernet Driver delivery:

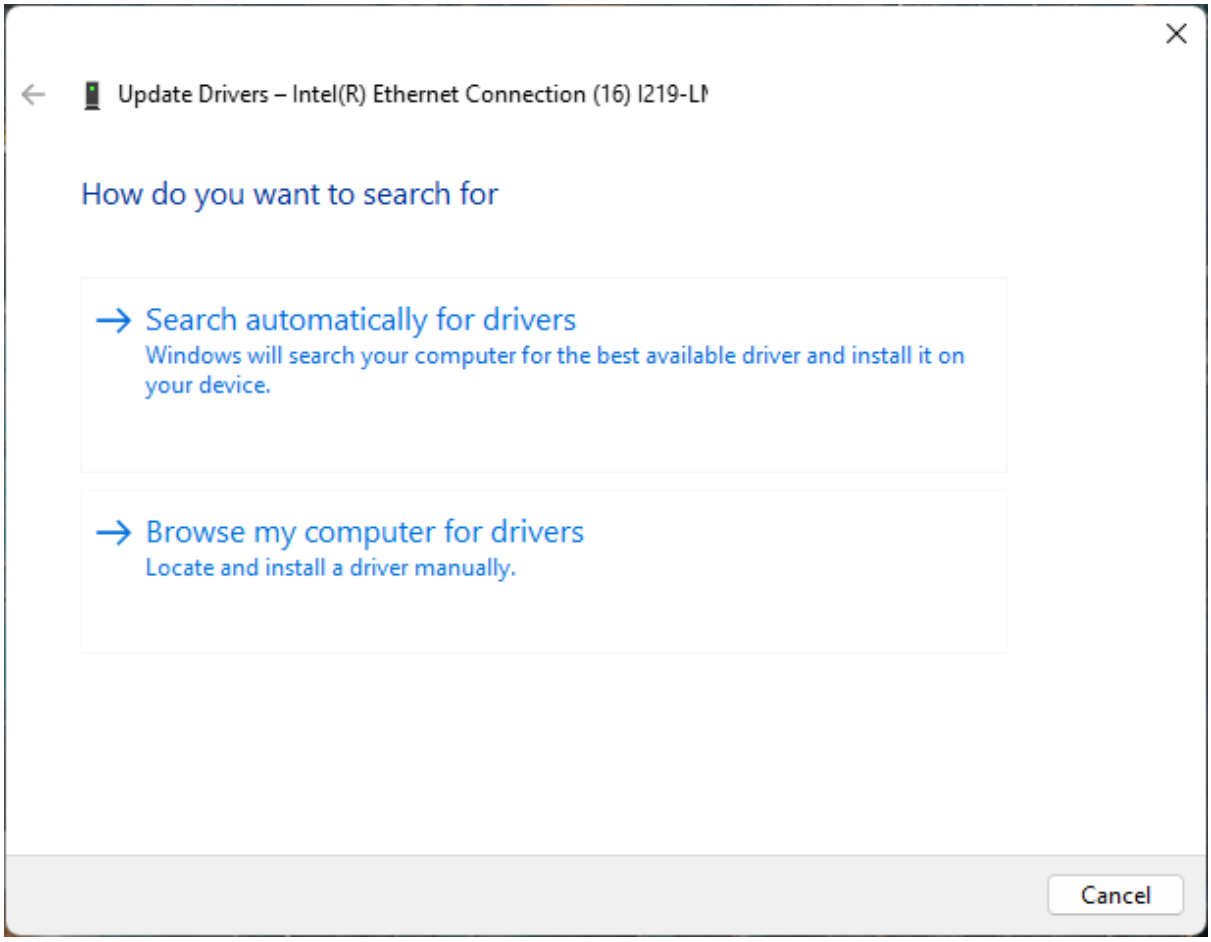
1. **Start the “Device Manager”**



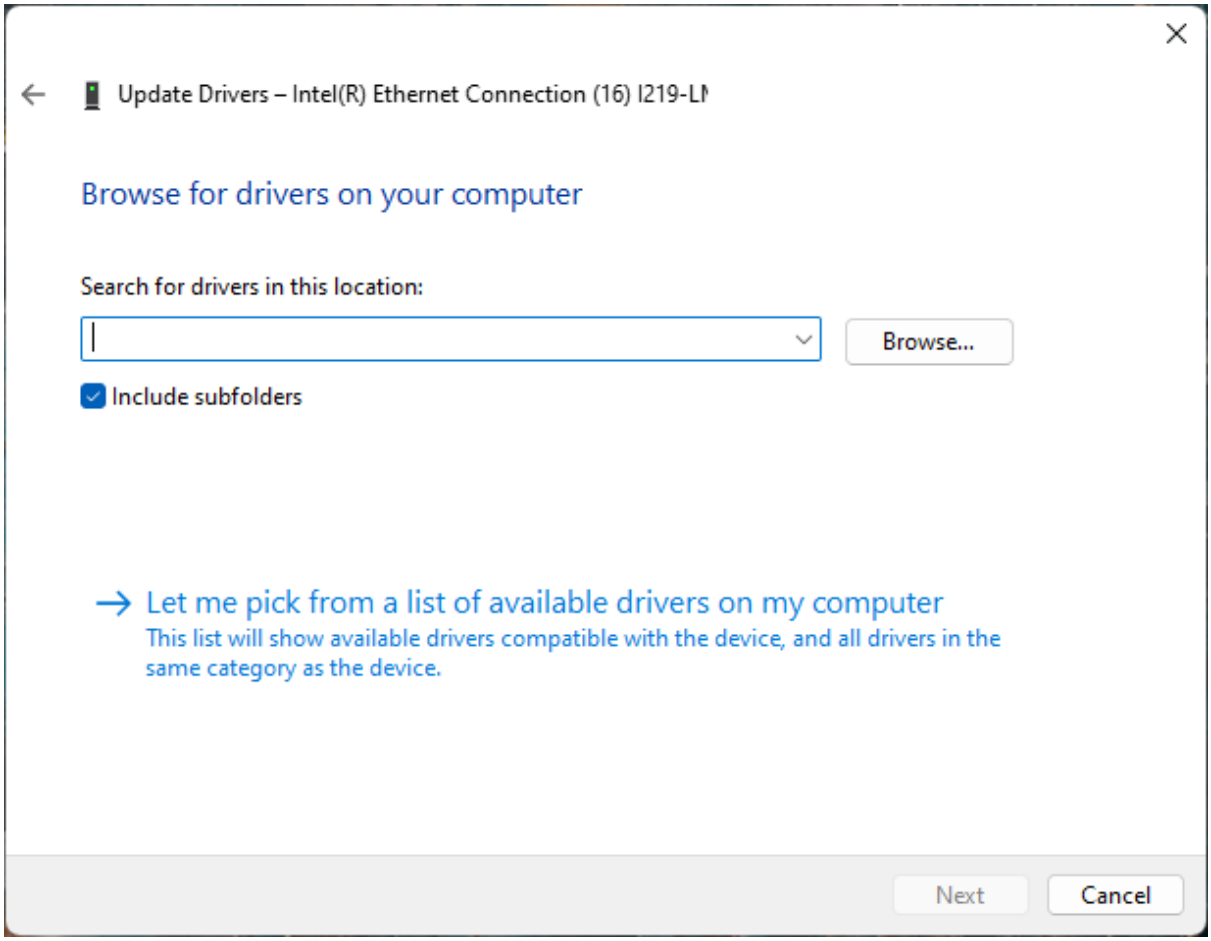

2. **Assign RtaccDevice to the network adapter**


Device Manager
File
Action
View
Help
MBI-0
Audio inputs and outputs
Batteries
Biometric devices
Bluetooth
Cameras
Computer
Disk drives
Display adaptors
Firmware
Device Firmware
Device Firmware
Device Firmware
Device Firmware
Device Firmware
Device Firmware
System Firmware
Human Interface Devices
Imaging devices
Keyboards
Mice and other pointing devices
Monitors
Network adapters
Bluetooth Device (Personal Area Network)
Intel(R) Ethernet Connection (16) I219-LM
Intel(R) Wi-Fi 6E AX211 160MHz
Realtek USB GbE Family Controller
TAP-Windows Adapter V9
VMware Virtual Ethernet Adapter for VMnet1
VMware Virtual Ethernet Adapter for VMnet8
WAN Miniport (IKEv2)
WAN Miniport (IP)
WAN Miniport (IPv6)
WAN Miniport (L2TP)
WAN Miniport (Network Monitor)

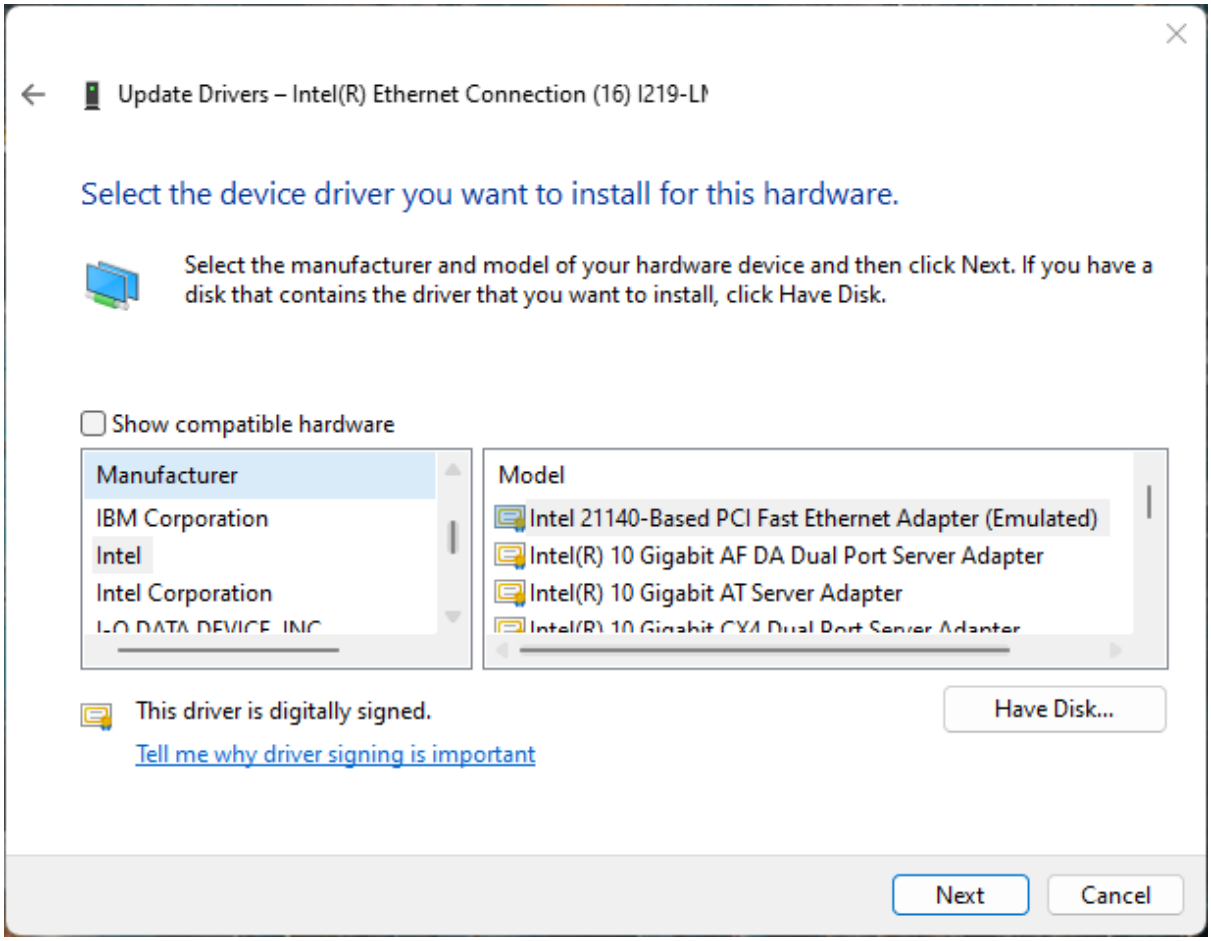



Click on “Browse my computer for drivers”



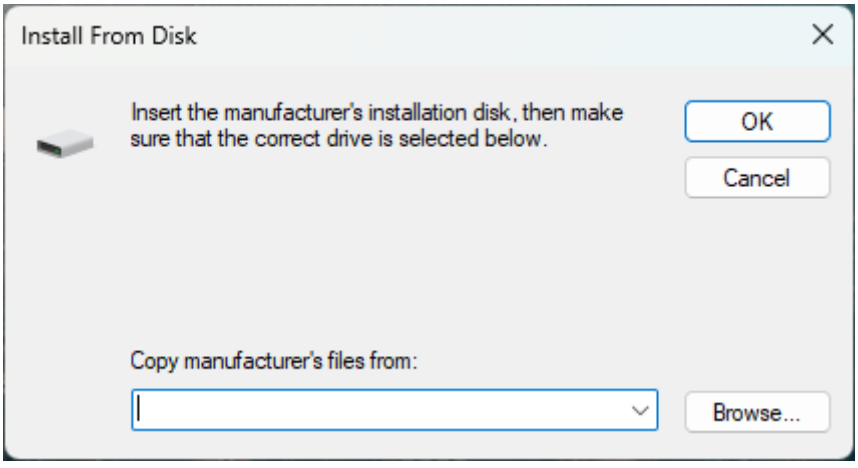

Click on “Let me pick…”




Click on “Have Disk…”

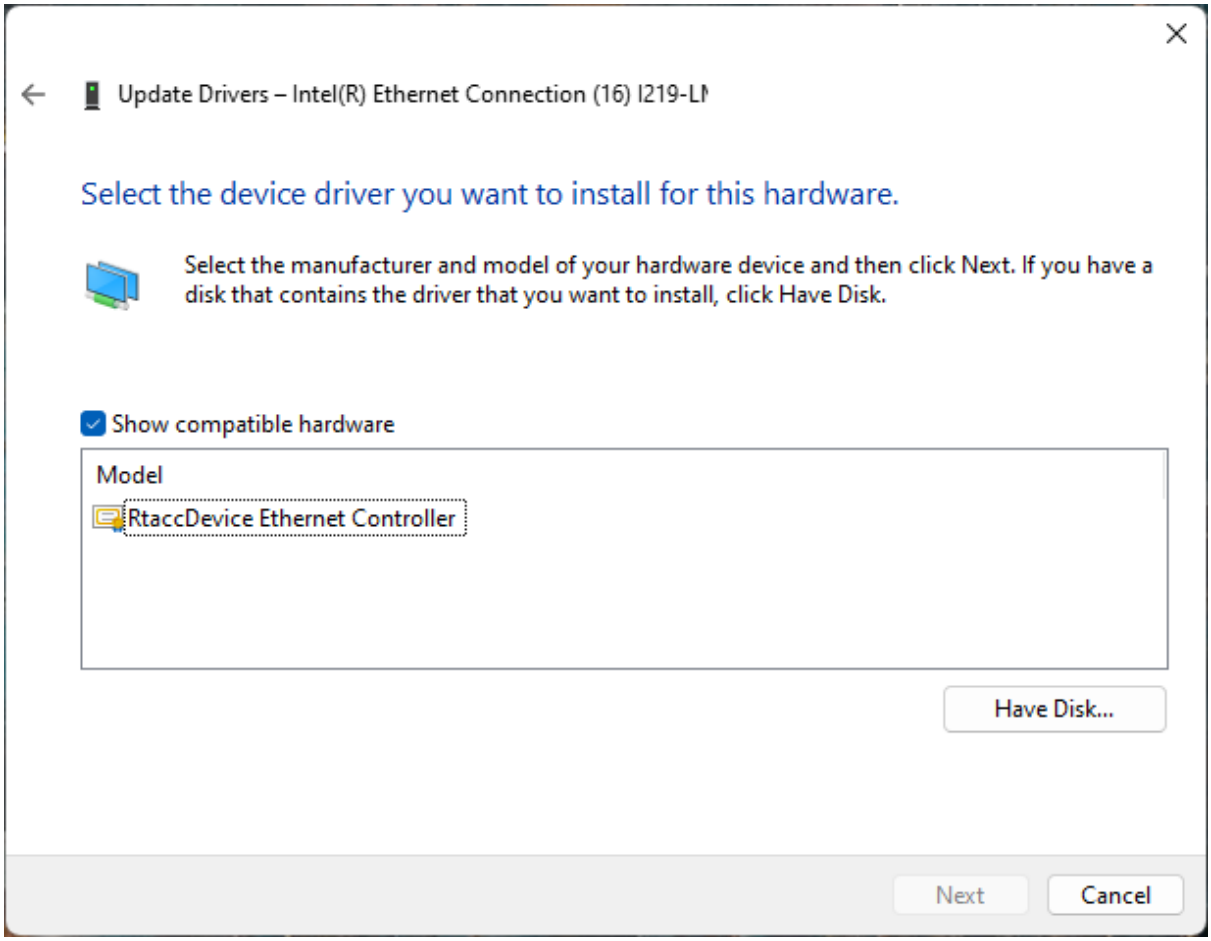
3. Enter the directory of RtaccDevice Driver

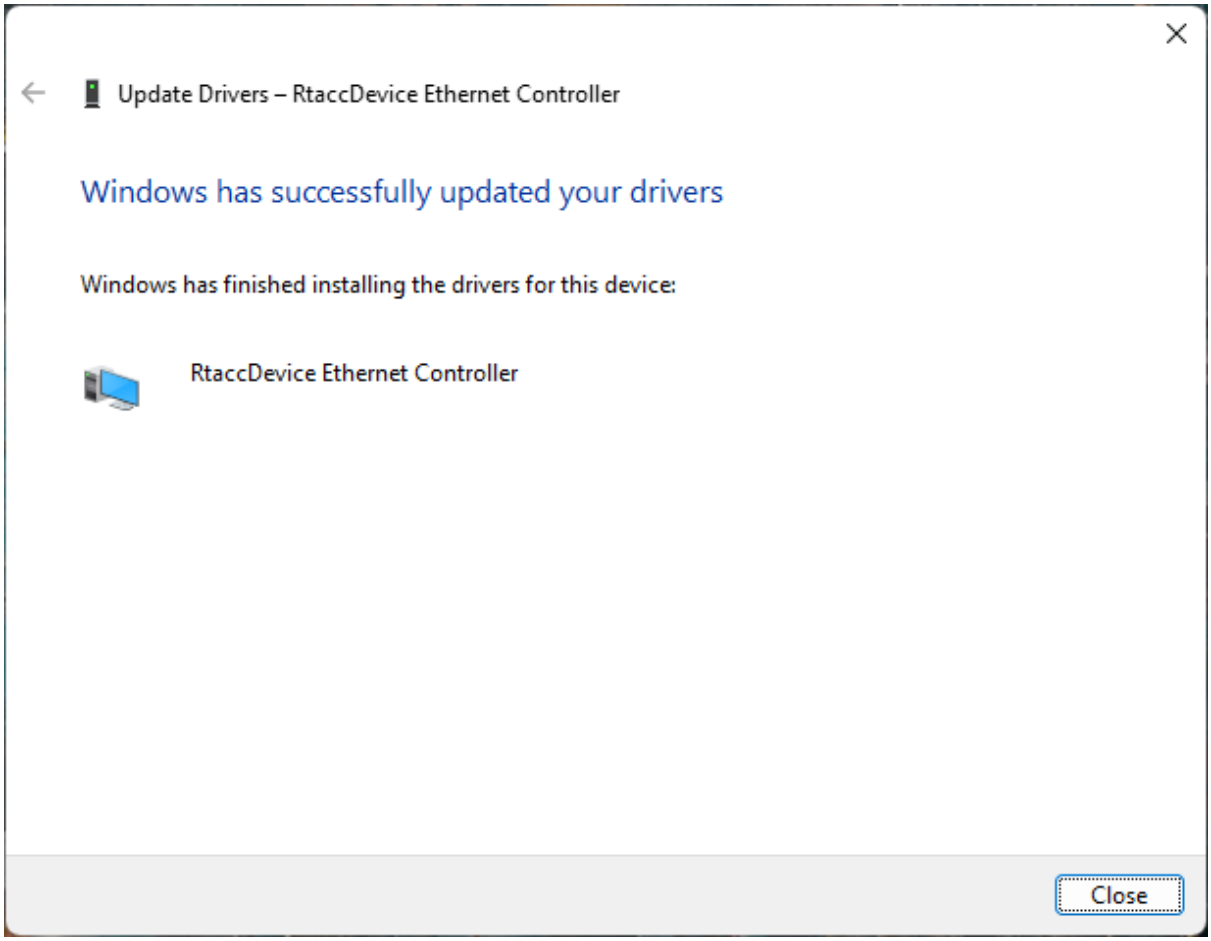
   The default folder if not changed is `<InstallPath>\Bin\Windows\x64`




   Enter the correct directory at the input box and press OK to proceed.

4. **Choose the RtaccDevice Driver and click “Next” and confirm the installation**


Update Drivers – Intel(R) Ethernet Connection (16) I219-LM
Select the device driver you want to install for this hardware.
Select the manufacturer and model of your hardware device and then click Next. If you have a disk that contains the driver that you want to install, click Have Disk.
Show compatible hardware
Model
RtaccDevice Ethernet Controller
Have Disk...
Next
Cancel

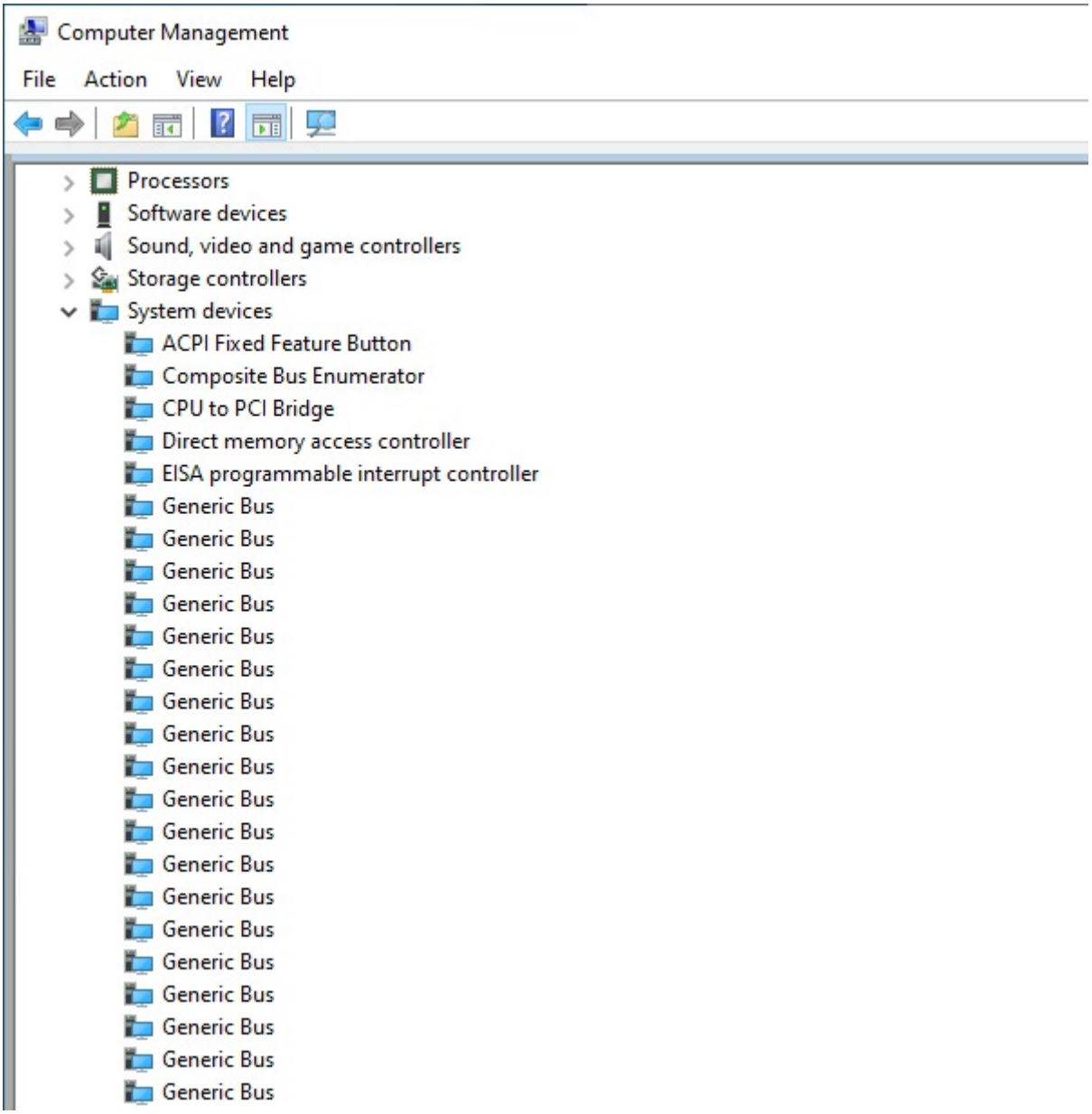


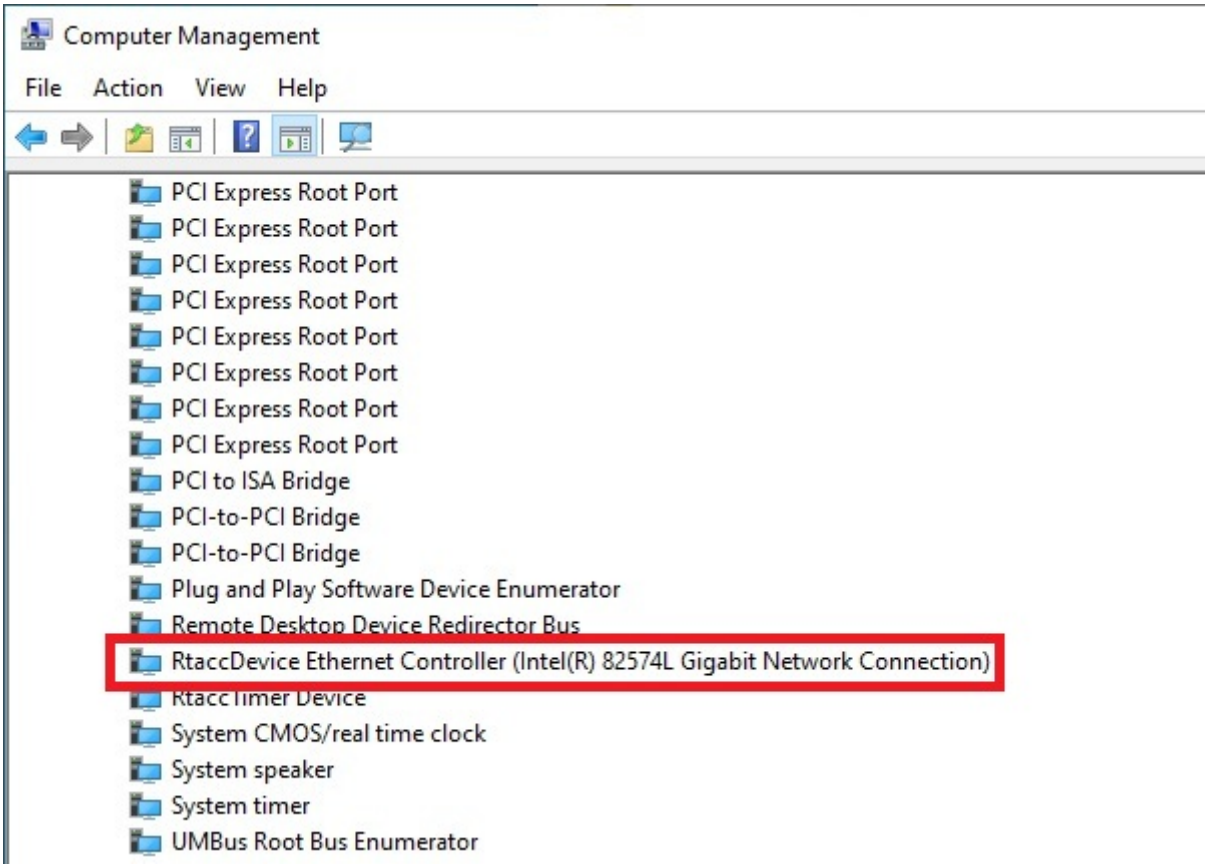

Optionally modify the search location of the Real-time Ethernet Driver

Search locations for Real-time Ethernet Driver can be adjusted using the PATH environment variable.

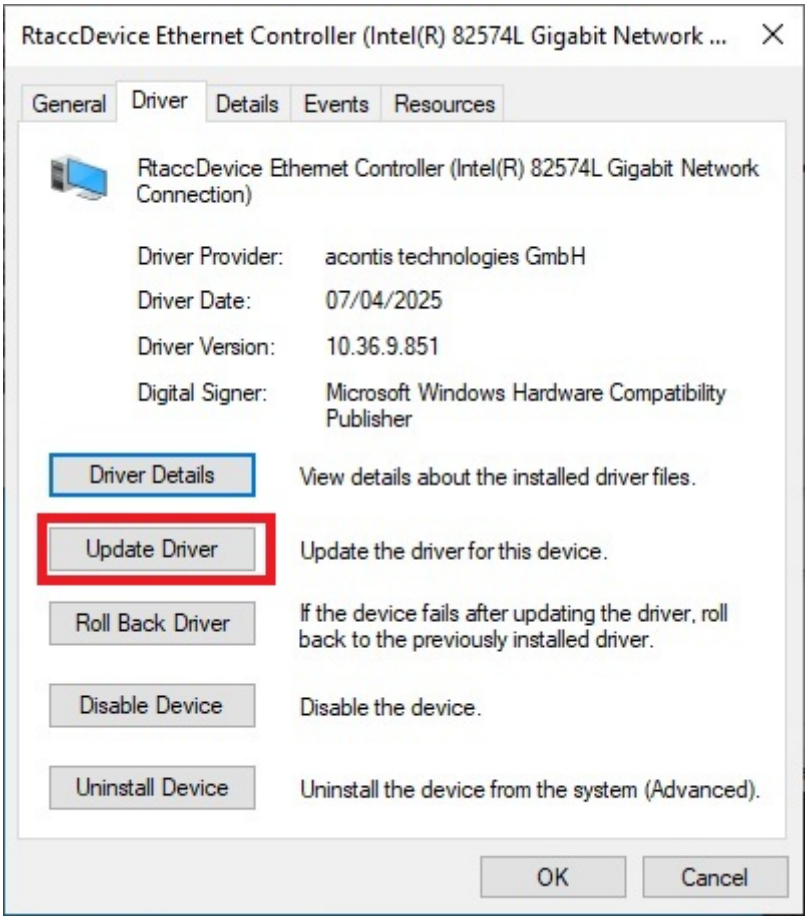
The RtaccDevice must be assigned to the network adapter for Real-time Ethernet Driver usage on Windows. In this case it is exclusively bound for EtherCAT® usage. The assignment can be reverted using the following steps:

1. Open the Windows device manager (Computer Management), then go to System devices. The RtaccDevice should be listed there:

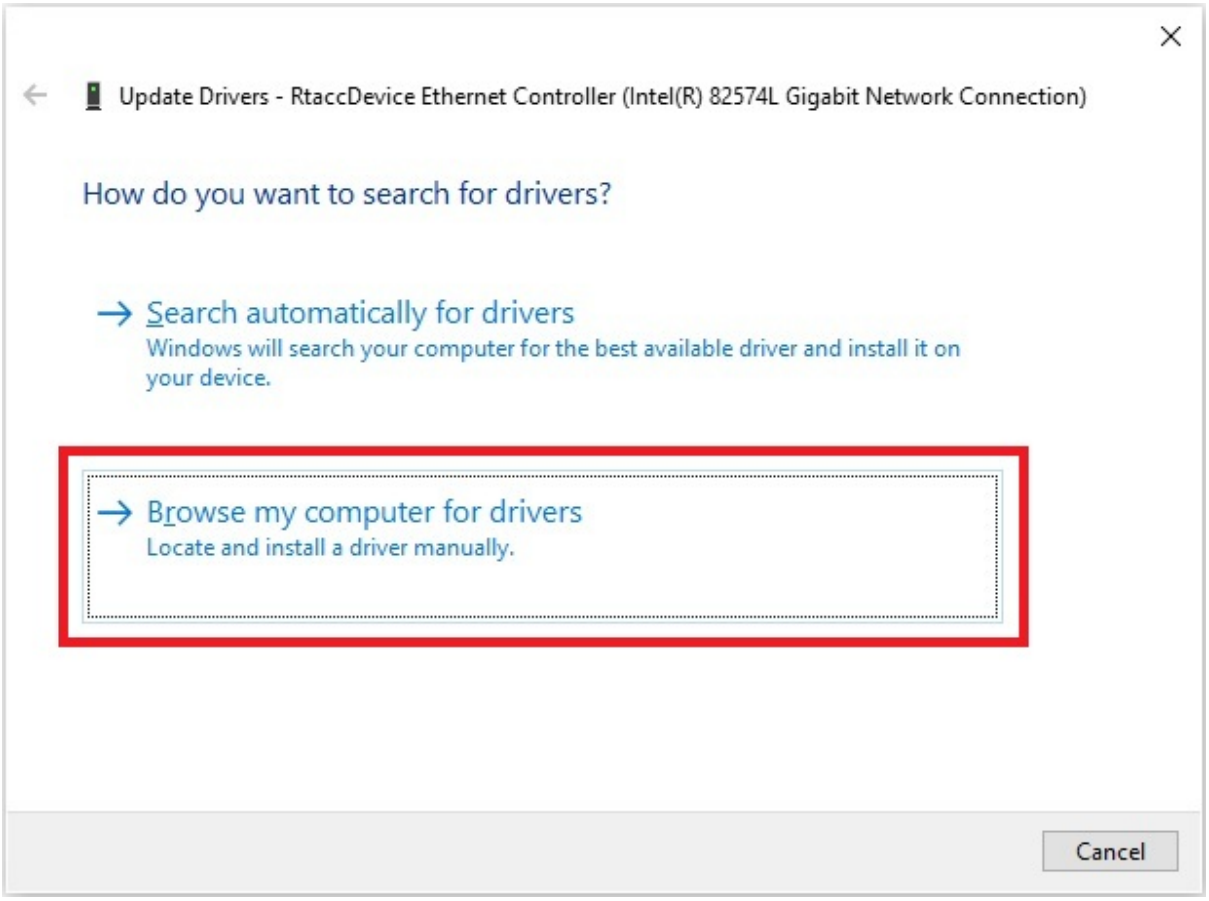




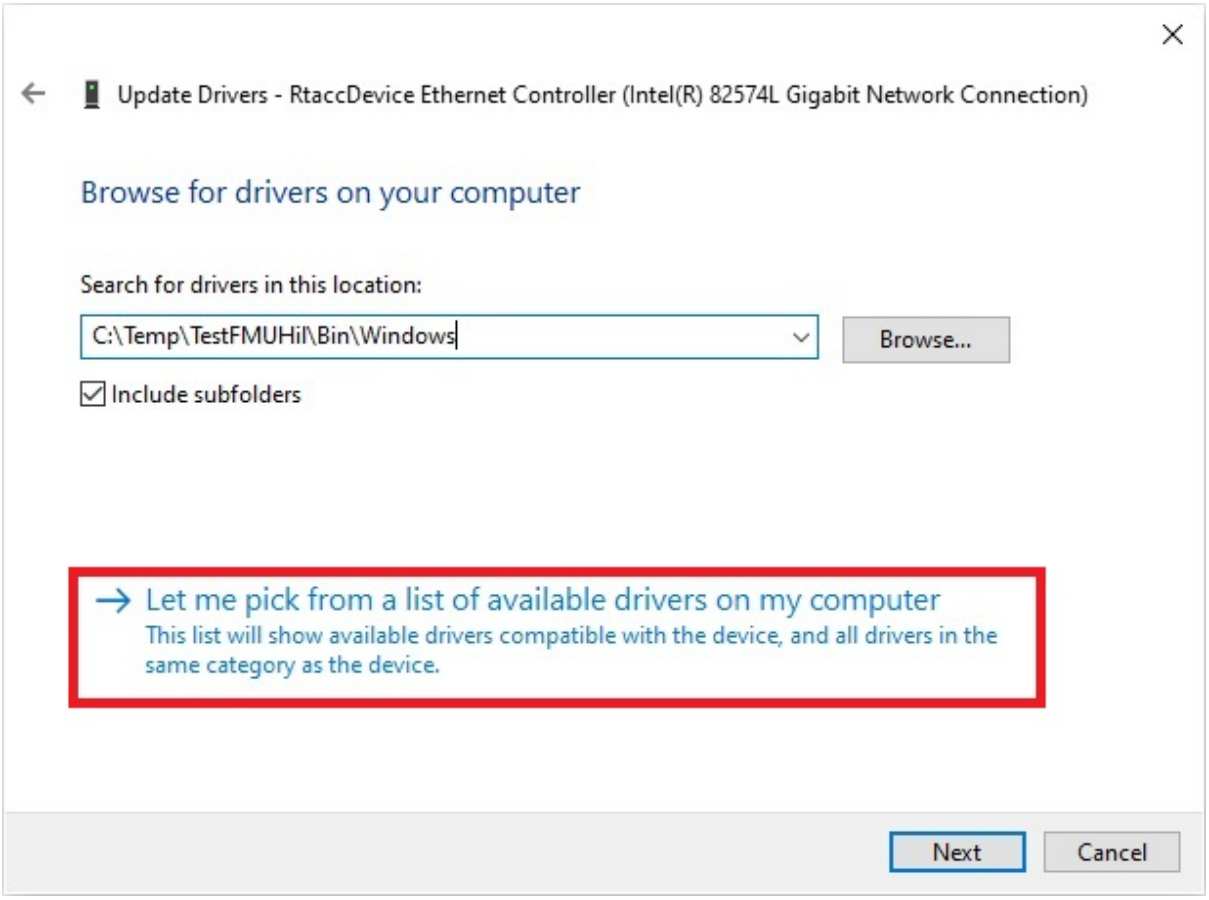

2. Right click on the RtaccDevice Ethernet Controller, then click on Properties:



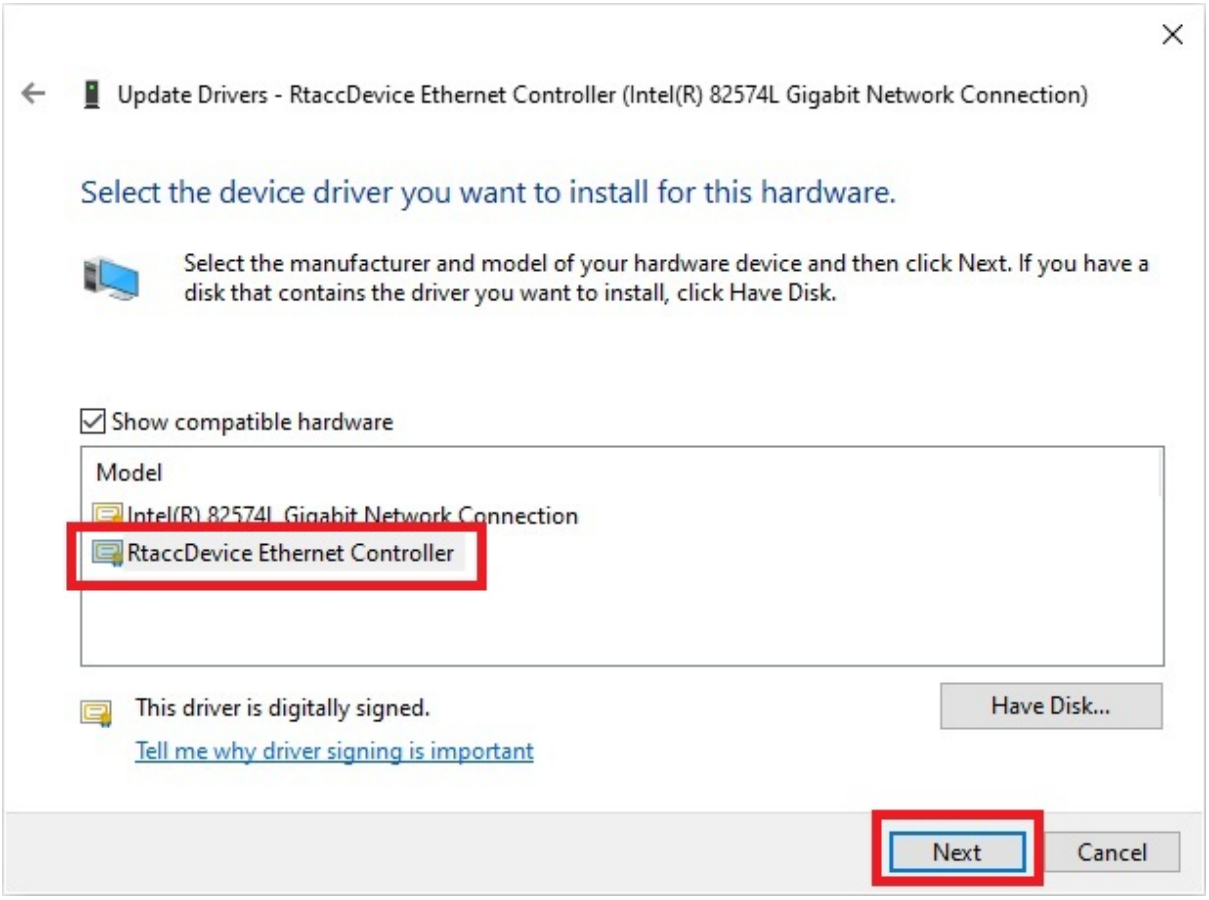

3. Switch to the tab “Driver”, then click the button “Update driver”:




4. Click on “Browse my computer for drivers”:




5. Click on “Let me pick from a list of available drivers on my computer”:




Select the network adapter and click “Next”.

The assignment is now reverted.

# 8 Real-time Ethernet Driver

## 8.1 Real-time Ethernet Driver selection

The EC-Monitor currently supports a variety of different Real-time Ethernet Driver modules, each contained in a single library file, which is loaded by the core library dynamically. The EC-Monitor shipment consist of a core library and one (or more) libraries each containing support for one specific Real-time Ethernet Driver module (type of hardware card). Which library actually is loaded depends on the Real-time Ethernet Driver parameters at runtime.

Real-time means operating directly on the network adapter's register set instead of using the operating system's native driver.

The principle of Real-time Ethernet Driver selection is that the name of the Real-time Ethernet Driver (Real-time Ethernet Driver Identification) is used to determine the location and name of a registration function, which is called by the EC-Monitor and registers function pointers which allow access to the Real-time Ethernet Driver functional entries.

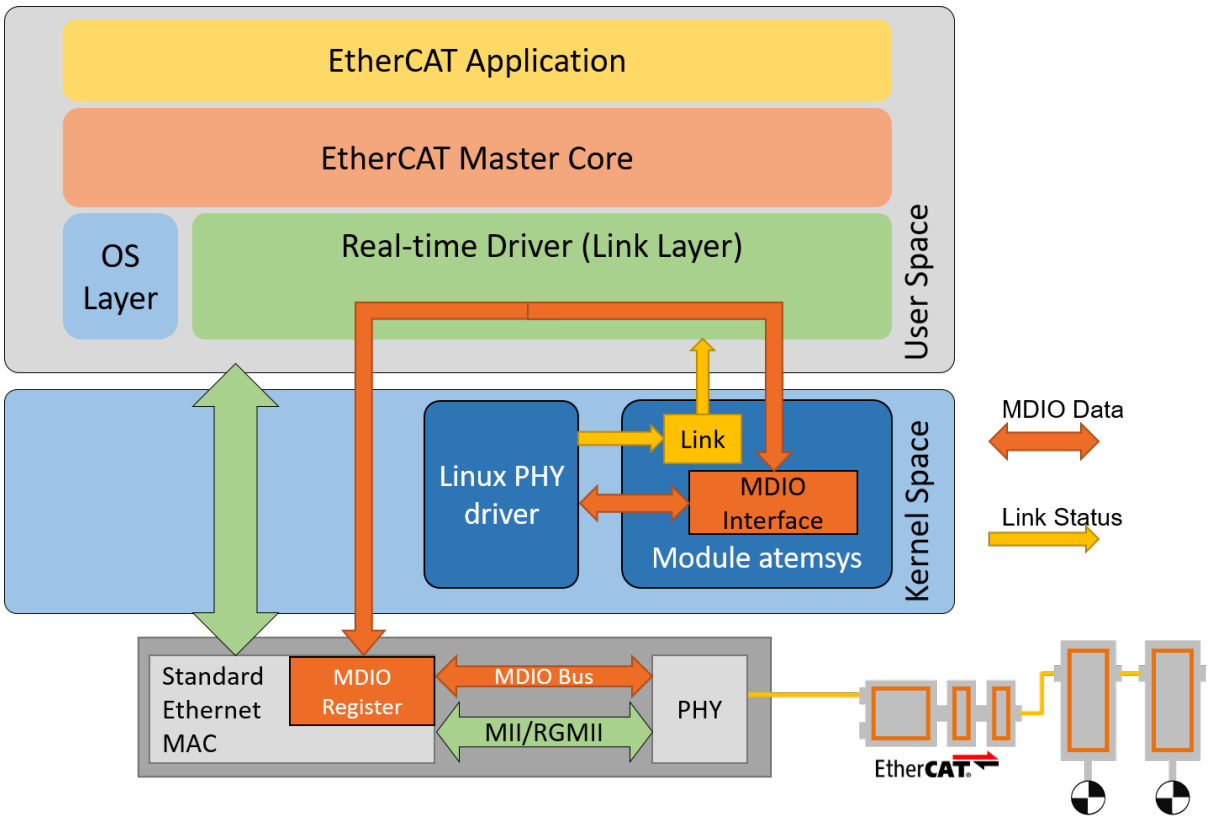
The EtherCAT® Real-time Ethernet Driver will be initialized using a Real-time Ethernet Driver specific configuration parameter set. A pointer to this parameter set is part of the EC-Monitor initialization settings.

The EC-Monitor supports two Real-time Ethernet Driver operating modes:

- Interrupt mode all received Ethernet frames will be processed immediately in the context of the Real-time Ethernet Driver receiver task.
- Polling mode the EC-Monitor will call the Real-time Ethernet Driver receiver polling function prior to processing received frames.

### 8.1.1 Real-time Ethernet Driver and PHY OS Driver

Some operating systems, e.g. Linux and Xenomai, provide drivers for most common Ethernet controllers and their related physical transceivers (PHY). The manufacturer specific PHY circuits can be handled by a dedicated driver. Using the PHY OS Driver interface it is possible to use the manufacturer's dedicated PHY driver without modification of the Real-time Ethernet Driver driver. Depending on the hardware architecture, an additional module from acontis, e.g. atemsys for Linux, grants access to the MDIO bus to the OS drivers, or request MDIO operations from the OS drivers.




**Note:** Real-time Ethernet Driver modules not listed here may be available if purchased additionally

### 8.1.2 Real-time Ethernet Driver selection and initialization

The different Real-time Ethernet Driver modules are selected and parameterized by a common structure *EC_T_LINK_PARMS* shared by all Real-time Ethernet Driver and a Real-time Ethernet Driver specific structure, pointed to by an element within the common structure. This parameter set is given to *EC_T_MONITOR_INIT_PARMS::pLinkParms* with the call of *emonInitMonitor()*.

struct **EC_T_LINK_PARMS**

#### Public Members

*EC_T_DWORD* **dwSignature**
[in] Signature of the adapter specific structure containing the *EC_T_LINK_PARMS* structure

*EC_T_DWORD* **dwSize**
[in] Size of the adapter specific structure containing the *EC_T_LINK_PARMS* structure

*EC_T_LOG_PARMS* **LogParms**
[in] Logging parameters

*EC_T_CHAR* **szDriverIdent**[EC_DRIVER_IDENT_NAME_SIZE]
[in] Name of Link Layer module (driver identification) for Link Layer Selection

*EC_T_DWORD* **dwInstance**
[in] Instance of the adapter. If EC_LINKUNIT_PCILOCATION is set: contains PCI address.

EC_T_LINKMODE **eLinkMode**
[in] Mode of operation

EC_T_CPUSET **cpuIstCpuAffinityMask**
[in] Interrupt service thread CPU affinity mask

*EC_T_DWORD* **dwIstPriority**
[in] Task priority of the interrupt service task (not used in polling mode)

*EC_T_DWORD* **dwIstStackSize**
[in] Task stack size

*EC_T_DWORD* **dwLinkSpeed**
[in] 10, 100, 1000 Mbit\s

*EC_T_LINKLAYER_TIMINGTASK* **oLinkLayerTimingTask**
[in] LinkLayer timimg task parameters

*EC_T_CHAR* **szLoadPath**[EC_DRIVER_PATH_SIZE]
[in] Path from which the libraries should be loaded

struct **EC_T_LINKLAYER_TIMINGTASK**

### Public Members

EC_T_LINKLAYER_TIMING **eLinkLayerTiming**
[in] LinkLayer timing task mode

*EC_T_DWORD* **dwCycleTimeNsec**
[in] Cycle time between 2 pfnStartCycle calls in ns. Will be set by the master stack for the link layer.

EC_T_LINK_STARTCYCLE_CALLBACK **pfnStartCycle**
[in] Callback function called cyclically according to dwCycleTimeNsec

EC_T_VOID ***pvStartCycleContext**
[in] Context passed to each pfnStartCycle call

*EC_T_DWORD* **dwTtsSendOffsetUsec**
[in] Time between pfnStartCycle call and TTS frame transmission

*EC_T_UINT64* **nSystemTime**
[in] System

### 8.1.3 Real-time Ethernet Driver instance selection via PCI location

For some operating systems it is possible to address the Real-time Ethernet Driver instance using its PCI address as an alternative. To do this, EC_LINKUNIT_PCILOCATION (0x01000000) and the PCI location must be set as *EC_T_LINK_PARMS::dwInstance*.

On Linux the PCI address can be shown using e.g.:

```
$ lspci | grep Ethernet
```

```
$ 00:19.0 Ethernet controller: Intel Corporation Ethernet Connection I217-LM (rev 04)
$ 04:00.0 Ethernet controller: Intel Corporation 82574L Gigabit Network Connection
$ 05:00.0 Ethernet controller: Intel Corporation 82574L Gigabit Network Connection
```

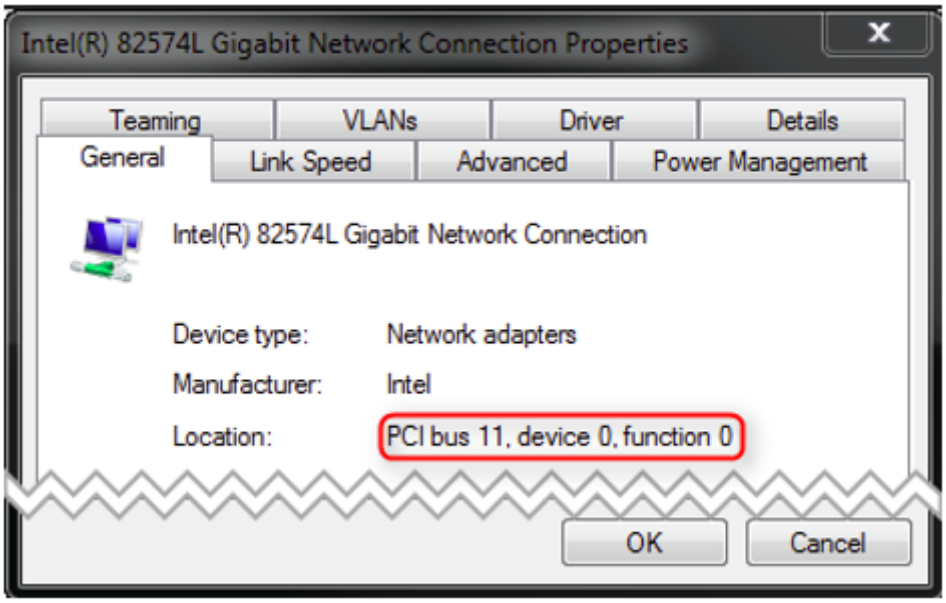
The format of *EC_T_LINK_PARMS::dwInstance* using PCI bus address is:

***0x01bbddff***

- *bb* Bus Number
- *dd* Device Number
- *ff* Function Number

```
EC_T_LINK_PARMS::dwInstance = 0x01001900; //"0000:00:19.0"
```

On Windows the integer value displayed in properties dialog must be converted to HEX. E.g the number from the following dialog *(PCI bus 11, device 0, function 0)* corresponds to *0x010B0000* (bus *0x0B*).




## 8.2 Intel Pro/1000 - emllIntelGbe

The parameters to the Real-time Ethernet Driver Intel Pro/1000 are setup-specific. The function “CreateLinkParmsFromCmdLineIntelGbe” in `EcSelectLinkLayer.cpp` demonstrates how to initialize the Real-time Ethernet Driver instance.

struct **EC_T_LINK_PARMS_INTELGBE**

#### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_INTELGBE.

*EC_T_WORD* **wRxBufferCnt**
Receive buffer count, 0: default to 96

*EC_T_WORD* **wRxBufferSize**
Receive buffer size for a single Ethernet frame. 0: buffer optimized for standard Ethernet frame.

*EC_T_WORD* **wTxBufferCnt**
Transmit buffer count, 0: default to 96

*EC_T_WORD* **wTxBufferSize**
Transmit buffer size for a single Ethernet frame. 0: buffer optimized for standard Ethernet frame.

*EC_T_BOOL* **bDisableLocks**
Disable locks

*EC_T_DWORD* **dwAutoNegTimeout**
Timeout [ms] for auto negotiation

*EC_T_BOOL* **bNotUseDmaBuffers**
EC_FALSE: Use buffers from DMA for receive (default), EC_TRUE: use buffers from heap for receive. EcLinkAllocSendFrame is not supported if bNotUseDmaBuffers = EC_TRUE.

*EC_T_BOOL* **bNoPhyCtrlOnConnect**
EC_TRUE: No PHY control (e.g. PHY reset, PHY PM settings, Gbits Ctrl) on link connection detected

NICs equipped with 82577, 82579 or 82567 may need HardCodedPhySettings. This must be set after `emInitMaster()`, before using the NIC, e.g.:

```
{
    emIoCtl(dwInstanceId, EC_IOCTL_LINKLAYER_MAIN + EC_LINKIOCTL_FORCELINKMODE, EC_
↪NULL + 0x20103, sizeof(EC_T_DWORD), EC_NULL, 0, EC_NULL);
    OsSleep(1000);
}
```

### 8.2.1 TTS Feature

The IntelGbe Real-time Ethernet Driver can optionally use Time-Triggered Send (TTS) feature. Ethernet/EtherCAT® frames are sent and time stamped according to the NIC timer instead of the CPU timer. Which is usually more accurate.

**See also:**

*EC_T_LINKLAYER_TIMINGTASK*, EC_T_LINKLAYER_TIMING

### 8.2.2 Supported PCI devices

Intel PRO-1000 PCI specific definitions (VendorId, DeviceId)

- **PCI_DEVICE_I82540EM_DESKTOP** (0x8086, 0x100E)
- **PCI_DEVICE_I82545EM_COPPER** (0x8086, 0x100F)
- **PCI_DEVICE_I82546EB_COPPER_DUAL** (0x8086, 0x1010)
- **PCI_DEVICE_I82541EI_COPPER** (0x8086, 0x1013)
- **PCI_DEVICE_I82547GI_COPPER** (0x8086, 0x1019)
- **PCI_DEVICE_I82545GM_COPPER** (0x8086, 0x1026)
- **PCI_DEVICE_I82566MM** (0x8086, 0x1049)
- **PCI_DEVICE_I82566DM** (0x8086, 0x104A)
- **PCI_DEVICE_I82566MC** (0x8086, 0x104D)
- **PCI_DEVICE_N1E5132_SERVER** (0x8086, 0x105E)
- **PCI_DEVICE_I82547EI** (0x8086, 0x1075)
- **PCI_DEVICE_I82541GI_COPPER** (0x8086, 0x1076)
- **PCI_DEVICE_I82541GI_MOBILE** (0x8086, 0x1077)
- **PCI_DEVICE_I82541ER** (0x8086, 0x1078)
- **PCI_DEVICE_I82546GB_COPPER_DUAL** (0x8086, 0x1079)
- **PCI_DEVICE_I82541PI_DESKTOP** (0x8086, 0x107C)
- **PCI_DEVICE_I82572EI** (0x8086, 0x107D)
- **PCI_DEVICE_I82573E** (0x8086, 0x108B)
- **PCI_DEVICE_I82573** (0x8086, 0x108C)
- **PCI_DEVICE_I82573L** (0x8086, 0x109A)
- **PCI_DEVICE_I82571GB_QUAD** (0x8086, 0x10A4)
- **PCI_DEVICE_I82575_ZOAR** (0x8086, 0x10A7)
- **PCI_DEVICE_I82572GI** (0x8086, 0x10B9)
- **PCI_DEVICE_I82571GB_QUAD_2** (0x8086, 0x10BC)
- **PCI_DEVICE_I82566L** (0x8086, 0x10BD)
- **PCI_DEVICE_I82576** (0x8086, 0x10C9)
- **PCI_DEVICE_I82567V** (0x8086, 0x10CE)
- **PCI_DEVICE_I82574L** (0x8086, 0x10D3)
- **PCI_DEVICE_I82567LM3** (0x8086, 0x10DE)
- **PCI_DEVICE_I82577LM** (0x8086, 0x10EA)
- **PCI_DEVICE_I82577LC** (0x8086, 0x10EB)
- **PCI_DEVICE_I82578DM** (0x8086, 0x10EF)
- **PCI_DEVICE_I82578DC** (0x8086, 0x10F0)
- **PCI_DEVICE_I82567LM** (0x8086, 0x10F5)
- **PCI_DEVICE_I82567V3** (0x8086, 0x1501)
- **PCI_DEVICE_I82579LM** (0x8086, 0x1502)
- **PCI_DEVICE_I82579V** (0x8086, 0x1503)
- **PCI_DEVICE_I82576NS** (0x8086, 0x150A)
- **PCI_DEVICE_I82583V** (0x8086, 0x150C)
- **PCI_DEVICE_I82580_QUAD** (0x8086, 0x150E)
- **PCI_DEVICE_I350** (0x8086, 0x1521)
- **PCI_DEVICE_I82576_ET2** (0x8086, 0x1526)
- **PCI_DEVICE_I82580_QUAD_FIBRE** (0x8086, 0x1527)
- **PCI_DEVICE_I210AT** (0x8086, 0x1531)
- **PCI_DEVICE_I210AT_2** (0x8086, 0x1532)
- **PCI_DEVICE_I210_COPPER** (0x8086, 0x1533)
- **PCI_DEVICE_I210IT** (0x8086, 0x1535)
- **PCI_DEVICE_I210_SERDES** (0x8086, 0x1537)
- **PCI_DEVICE_I211AT** (0x8086, 0x1539)
- **PCI_DEVICE_I210_COPPER_FLASHLESS** (0x8086, 0x157B)
- **PCI_DEVICE_I210_BACKPLANE** (0x8086, 0x157C)
- **PCI_DEVICE_I217LM** (0x8086, 0x153A)
- **PCI_DEVICE_I217V** (0x8086, 0x153B)
- **PCI_DEVICE_I218LM** (0x8086, 0x155A)
- **PCI_DEVICE_I218V** (0x8086, 0x1559)
- **PCI_DEVICE_I218LM_2** (0x8086, 0x15A0)
- **PCI_DEVICE_I218V_2** (0x8086, 0x15A1)
- **PCI_DEVICE_I218LM_3** (0x8086, 0x15A2)
- **PCI_DEVICE_I218V_3** (0x8086, 0x15A3)
- **PCI_DEVICE_I219LM** (0x8086, 0x156F)
- **PCI_DEVICE_I219LM_2** (0x8086, 0x15B7)
- **PCI_DEVICE_I219LM_3** (0x8086, 0x15B9)
- **PCI_DEVICE_I219LM_4** (0x8086, 0x15D7)
- **PCI_DEVICE_I219LM_5** (0x8086, 0x15E3)
- **PCI_DEVICE_I219LM_6** (0x8086, 0x15BD)
- **PCI_DEVICE_I219LM_7** (0x8086, 0x15BB)
- **PCI_DEVICE_I219LM_8** (0x8086, 0x15DF)
- **PCI_DEVICE_I219LM_9** (0x8086, 0x15E1)
- **PCI_DEVICE_I219V** (0x8086, 0x1570)
- **PCI_DEVICE_I219V_2** (0x8086, 0x15B8)
- **PCI_DEVICE_I219V_4** (0x8086, 0x15D8)
- **PCI_DEVICE_I219V_5** (0x8086, 0x15D6)
- **PCI_DEVICE_I219V_6** (0x8086, 0x15BE)
- **PCI_DEVICE_I219V_7** (0x8086, 0x15BC)
- **PCI_DEVICE_I219V_8** (0x8086, 0x15E0)
- **PCI_DEVICE_I219V_9** (0x8086, 0x15E2)
- **PCI_DEVICE_I219LM_10** (0x8086, 0x0D4E)
- **PCI_DEVICE_I219V_10** (0x8086, 0x0D4F)
- **PCI_DEVICE_I219LM_11** (0x8086, 0x0D4C)
- **PCI_DEVICE_I219V_11** (0x8086, 0x0D4D)
- **PCI_DEVICE_I219LM_12** (0x8086, 0x0D53)
- **PCI_DEVICE_I219V_12** (0x8086, 0x0D55)
- **PCI_DEVICE_I219LM_18** (0x8086, 0x0DC5)
- **PCI_DEVICE_I219V_18** (0x8086, 0x0DC6)
- **PCI_DEVICE_I219LM_19** (0x8086, 0x0DC7)
- **PCI_DEVICE_I219V_19** (0x8086, 0x0DC8)
- **PCI_DEVICE_I219LM_13** (0x8086, 0x15FB)
- **PCI_DEVICE_I219V_13** (0x8086, 0x15FC)

- **PCI_DEVICE_I219LM_14** (0x8086, 0x15F9)
- **PCI_DEVICE_I219V_14** (0x8086, 0x15FA)
- **PCI_DEVICE_I219LM_15** (0x8086, 0x15F4)
- **PCI_DEVICE_I219V_15** (0x8086, 0x15F5)
- **PCI_DEVICE_I219LM_16** (0x8086, 0x1A1E)
- **PCI_DEVICE_I219V_16** (0x8086, 0x1A1F)
- **PCI_DEVICE_I219LM_17** (0x8086, 0x1A1C)
- **PCI_DEVICE_I219V_17** (0x8086, 0x1A1D)
- **PCI_DEVICE_I219LM_20** (0x8086, 0x550A)
- **PCI_DEVICE_I219V_20** (0x8086, 0x550B)
- **PCI_DEVICE_I219LM_21** (0x8086, 0x550C)
- **PCI_DEVICE_I219V_21** (0x8086, 0x550D)
- **PCI_DEVICE_I219LM_22** (0x8086, 0x550E)
- **PCI_DEVICE_I219V_22** (0x8086, 0x550F)
- **PCI_DEVICE_I219LM_23** (0x8086, 0x5510)
- **PCI_DEVICE_I219V_23** (0x8086, 0x5511)
- **PCI_DEVICE_I219LM_24** (0x8086, 0x57A0)
- **PCI_DEVICE_I219V_24** (0x8086, 0x57A1)
- **PCI_DEVICE_I225LM** (0x8086, 0x15F2)
- **PCI_DEVICE_I225V** (0x8086, 0x15F3)
- **PCI_DEVICE_I225I** (0x8086, 0x15F8)
- **PCI_DEVICE_I225K** (0x8086, 0x3100)
- **PCI_DEVICE_I225K_2** (0x8086, 0x3101)
- **PCI_DEVICE_I225LMVP** (0x8086, 0x5502)
- **PCI_DEVICE_I225IT** (0x8086, 0x0D9F)
- **PCI_DEVICE_I226LM** (0x8086, 0x125B)
- **PCI_DEVICE_I226V** (0x8086, 0x125C)
- **PCI_DEVICE_I226IT** (0x8086, 0x125D)

## 8.3 Windows NDIS - emllNdis

As default EC-Monitor for Windows contains `emllNdis.dll` to use a native Windows driver for EtherCAT®.

The acontis ECAT Protocol Driver is needed to use the Ethernet Driver NDIS and can be installed from

- `Bin/Windows/x64/EcatNdisSetup-x86_64Bit.msi` or
- `Bin/Windows/x86/EcatNdisSetup-x86_32Bit.msi`

respectively depend on the Windows Operating System Type of 64 Bit or 32 Bit.

IPv4 must be installed for the network adapter as the Ethernet Driver NDIS uses the IP address to identify the network adapter.

The parameters to the Ethernet Driver NDIS are setup-specific. The function `CreateLinkParmsFromCmdLineNDIS()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the Ethernet Driver instance.

struct **EC_T_LINK_PARMS_NDIS**

### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_NDIS.

*EC_T_CHAR* **szAdapterName**[EC_NDIS_ADAPTER_NAME_SIZE]
ServiceName of network adapter, see HKLM\SOFTWARE\Microsoft\Windows NT\CurrentVersion\NetworkCards in registry (zero terminated)

*EC_T_BYTE* **abyIpAddress**[4]
IP address of network adapter

*EC_T_BOOL* **bDisablePromiscuousMode**
Disable adapter promiscuous mode

*EC_T_BOOL* **bDisableForceBroadcast**
Don't change target MAC address to FF:FF:FF:FF:FF:FF

In case of problems while using the Ethernet Driver, it is advised to set the windows registry entry DontSetPromiscuousMode of the ECAT NDIS Protocol driver. This option is available since V3.1.3.02 of the driver. This can be done through the following steps:

- Install ECAT NDIS Protocol driver (V3.1.3.02 or newer version)
- Open the registry editor
- Switch to Computer\HKEY_LOCAL_MACHINE\SYSTEM\CurrentControlSet\Services\Ecatndis, or just look for Ecatndis in the editor
- Create a new DWORD entry named DontSetPromiscuousMode
- Set the value of DontSetPromiscuousMode to 1
- Close the registry editor and restart your computer

## 8.4 Windows WinPcap - emllPcap

An Ethernet Driver based on the WinPcap library is shipped with the EC-Monitor. This Ethernet Driver is implemented using a network filter driver that enables the software to send and receive raw Ethernet frames. Using this Ethernet Driver any Windows standard network drivers can be used. The Windows network adapter card has to be assigned a unique IP address (private IP address range). This IP address is used by the EtherCAT® WinPcap Ethernet Driver driver to select the appropriate adapter.

It is recommended to use a separate network adapter to connect EtherCAT® devices. If the network adapter is used for both EtherCAT® and the local area network, it may significantly impact local area network operation. A static private IP address (e.g., 192.168.x.y) must be assigned to the EtherCAT® network adapter.

The parameters to the Ethernet Driver WinPcap are setup-specific. The function `CreateLinkParmsFromCmdLineWinPcap()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the Ethernet Driver instance.

struct **EC_T_LINK_PARMS_WINPCAP**

### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_WINPCAP.

*EC_T_BYTE* **abyIpAddress**[4]
IP address

*EC_T_CHAR* **szAdapterId**[MAX_LEN_WINPCAP_ADAPTER_ID]
Adapter ID, format: {XXXXXXXX-XXXX-XXXX-XXXX-XXXXXXXXXXXX}

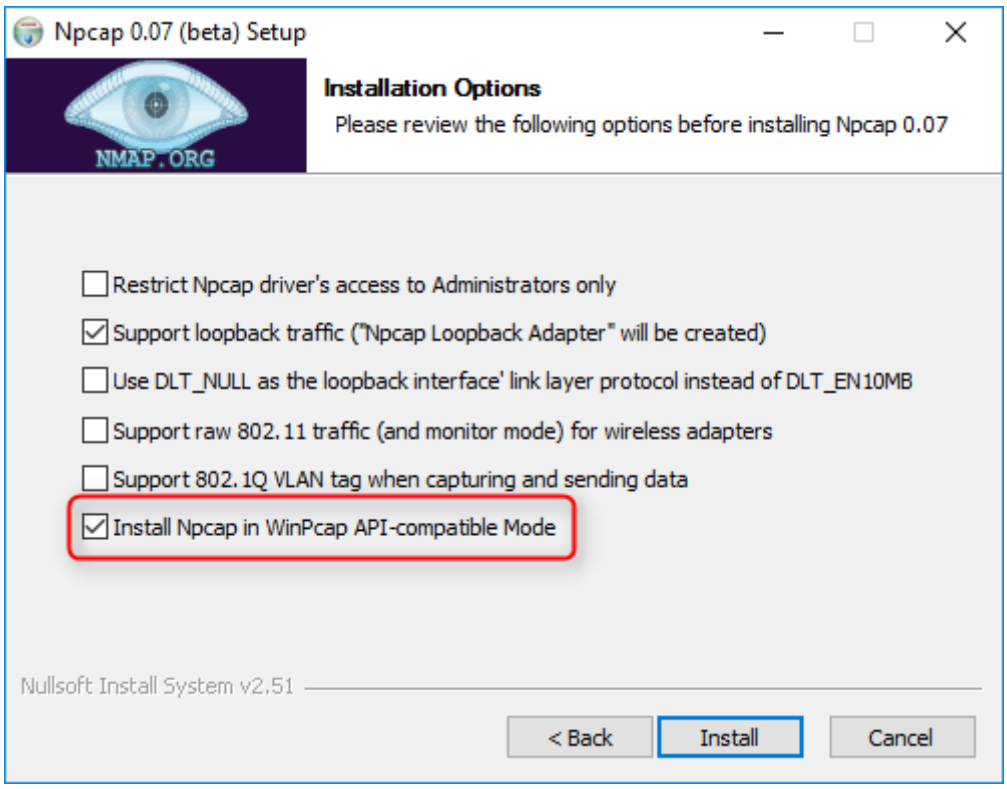
*EC_T_BOOL* **bFilterInput**
Filter input if EC_TRUE. This is needed on some system if the winpcap library notify the sent frames to the network adapter.

### 8.4.1 WinPcap, Npcap support

At least WinPcap version 4.1.2 or Npcap 0.07 r17 must be used. WinPcap version 4.1.2 is the preferred library.

The EC-Monitor installer installs WinPcap by default.

If using Npcap 0.07 r17, the WinPcap API-compatible mode must be chosen:




## 8.5 emllRemote

The emllRemote is used to tunnel EtherCAT® frames within a TCP socket between EC-Master and EC-Simulator.

The emllRemote is used to receive EtherCAT® frames tunneled through TCP sockets.

The parameters to the Remote Driver are setup-specific. The function `CreateLinkParmsFromCmdLineRemote()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the driver instance.

struct **EC_T_LINK_PARMS_REMOTE**

#### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_REMOTE.

*EC_T_DWORD* **dwSocketType**
Socket type. Must be set to 1 (emrassocktype_tcp).

*EC_T_BYTE* **abySrcIpAddress**[4]
Source adapter IP address (listen)

*EC_T_WORD* **wSrcPort**
Source port number (listen)

*EC_T_BYTE* **abyDstIpAddress**[4]
Destination adapter IP address (connect)

*EC_T_WORD* **wDstPort**
Destination port number (connect)

*EC_T_BYTE* **abyMac**[6]
MAC address

*EC_T_DWORD* **dwRxBufferCnt**
Frame buffer count for interrupt service thread (IST)

While EC-Monitor listens on the given port using emllRemote, the EC-Master can connect to it using emllRemote.

**EcMonitorDemo command line example:**

```
EcMonitorDemo -remote 1 0 0.0.0.0 10001 0.0.0.0 0 -f eni.xml
```

**EcMasterDemo command line example:**

```
$ EcMasterDemo -integbe 1 1 -f eni.xml -mirror -remote 1 1 0.0.0.0 0 127.0.0.1
↪ 10001
```

## 8.6 VxWorks SNARF - emllSNARF

Using the EC-Monitor stack's SNARF Real-time Ethernet Driver it is possible to use any of the standard network drivers shipped with VxWorks. In VxWorks every network adapter is identified using a short string and a unit number in case of multiple identical network adapters. The unit numbers start with a value of 0. For example the string for the Intel Pro/100 network adapter driver is "fei". The first unit is identified using the string "fei0":

The network adapter driver has to be loaded prior to initializing the EC-Monitor stack.

Using the Real-time Ethernet Driver SNARF has some disadvantages. As the VxWorks network layering is involved in this architecture, the drivers are usually not optimized for realtime behavior and the needed CPU time is often too high to reach cycle times less than 300 to 500 microseconds. Additionally there is an impact if in parallel to EtherCAT® traffic the VxWorks application needs to use a second network card for transferring TCP/IP data. The single tNetTask is shared by all network drivers. Using a dedicated EtherCAT® driver these disadvantages can be overcome.

The parameters to the Real-time Ethernet Driver SNARF are setup-specific. The function `CreateLinkParmsFromCmdLineSNARF()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the Real-time Ethernet Driver instance.

struct **EC_T_LINK_PARMS_SNARF**

### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_SNARF.

*EC_T_CHAR* **szAdapterName**[EC_SNARF_ADAPTER_NAME_SIZE]
SNARF adapter name (zero terminated)

*EC_T_DWORD* **dwRxBuffers**
Receive buffer count, only used in RTP context, 0: default to 20

```
#include "EcLink.h"
EC_T_LINK_PARMS_SNARF oLinkParmsAdapter;

OsMemset(&oLinkParmsAdapter, 0, sizeof(EC_T_LINK_PARMS_SNARF));
oLinkParmsAdapter.linkParms.dwSignature = EC_LINK_PARMS_SIGNATURE_SNARF;
oLinkParmsAdapter.linkParms.dwSize      = sizeof(EC_T_LINK_PARMS_SNARF);
OsStrncpy(oLinkParmsAdapter.linkParms.szDriverIdent,
        EC_LINK_PARMS_IDENT_SNARF, MAX_DRIVER_IDENT_LEN - 1);
OsStrncpy(oLinkParmsAdapter.szAdapterName, "fei0", MAX_DRIVER_IDENT_LEN - 1);
```

## 8.7 Linux SockRaw - emllSockRaw

emllSockRaw is part of EC-Monitor for Linux. emllSockRaw uses the network interface of the native driver, e.g., eth0, eth1, etc. The network adapter must be exclusively used for EtherCAT® and cannot be used for LAN (local area network) at the same time. Because the native Linux driver for the network adapter type is typically not fully real-time capable, it cannot be used for real time applications. If possible, an acontis Real-time Ethernet Driver, e.g. emllIntelGbe, should be used instead. emllSockRaw does not need the atemsys driver.

---

**Note:** Root privileges are required. A cycle time of 4 ms or higher may be needed.

---

**To run the application without root privileges, set the Linux capability 'cap_net_raw' to the application.**

```
$ sudo setcap 'cap_net_raw+pe' ./EcMasterDemo
```

**To run python scripts without root privileges, create a Python environment and set the Linux capability 'cap_net_raw' to the python interpreter.**

```
$ cd Bin/Linux
$ python3 -m venv --copies PyEnv/
$ source PyEnv/bin/activate
$ sudo setcap 'cap_net_raw+pe' PyEnv/bin/python3
```

The parameters to emllSockRaw are setup-specific. The function `CreateLinkParmsFromCmdLineSockRaw()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the parameters.

struct **EC_T_LINK_PARMS_SOCKRAW**

#### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_SOCKRAW.

*EC_T_CHAR* **szAdapterName**[EC_SOCKRAW_ADAPTER_NAME_SIZE]
Native ETH device name, e.g. “eth0” (zero terminated)

*EC_T_BOOL* **bDisableForceBroadcast**
Don’t change target MAC address to FF:FF:FF:FF:FF:FF

*EC_T_BOOL* **bReplacePaddingWithNopCmd**
Prevent adding Ethernet padding to work-around EtherCAT corruption bugs from native Linux driver(s)

*EC_T_BOOL* **bUsePacketMmapRx**
Use PACKET_MMAP PACKET_RX_RING for receive

*EC_T_BOOL* **bSetCoalescingParms**
Set Coalescing parameters to enhance the link layer performance

*EC_T_BOOL* **bSetPromiscuousMode**
Enable promiscuous mode at network adapter

## 8.8 Windows TAP - emllTap

The parameters to the Windows TAP Real-time Ethernet Driver are setup-specific. The function `CreateLinkParmsFromCmdLineTap()` in `EcSelectLinkLayer.cpp` demonstrates how to initialize the Real-time Ethernet Driver instance.

struct **EC_T_LINK_PARMS_TAP**

#### Public Members

*EC_T_LINK_PARMS* **linkParms**
Common link parameters. Signature must be set to EC_LINK_PARMS_SIGNATURE_TAP.

*EC_T_CHAR* **szAdapterName**[EC_TAP_ADAPTER_NAME_SIZE]
Native tap device name, e.g. “tap0” (zero terminated)

*EC_T_CHAR* **szAdapterGuid**[EC_TAP_ADAPTER_GUID_SIZE]
GUID of virtual interface to connect (zero terminated)

*EC_T_BYTE* **abyMac**[6]
MAC address

*EC_T_DWORD* **dwRxBufferCnt**
Frame buffer count for IST

The adapter must be manually installed as described in the OpenVPN’s Windows TAP-driver manual, see https://community.openvpn.net/openvpn/wiki/GettingTapWindows .

While EC-Monitor is connected to the adapter using emllTap, the MainDevice can use it with e.g. emllNdis.

# 9 Application programming interface, reference

Function prototypes, definitions etc. of the API can be found in the header file `EcMonitor.h` which is the main header file to include when using EC-Monitor.

## Fundamental types

typedef void ***EC_T_PVOID**
Pointer of type void

typedef int **EC_T_BOOL**
Boolean

typedef char **EC_T_CHAR**
Character, 8 bit

typedef unsigned short **EC_T_WCHAR**
Wide-character, 16 bit

typedef unsigned char **EC_T_BYTE**
Byte, unsigned integer 8 bit

typedef unsigned char ***EC_T_PBYTE**
Pointer of type EC_T_BYTE

typedef unsigned short **EC_T_WORD**
Word, unsigned integer 16 bit

typedef unsigned int **EC_T_DWORD**
Double word, unsigned integer 32 bit

typedef signed char **EC_T_SBYTE**
Signed-Byte, signed integer 8 bit

typedef signed short **EC_T_SWORD**
Signed-Word, signed integer 16 bit

typedef signed int **EC_T_SDWORD**
Signed-Double-Word, signed integer 32 bit

typedef int **EC_T_INT**
Integer

typedef unsigned int **EC_T_UINT**
Unsigned-Integer

typedef short **EC_T_SHORT**
Short

typedef unsigned short **EC_T_USHORT**
Unsigned-Short

typedef float **EC_T_REAL**
Real, floating point

typedef double **EC_T_LREAL**
long Real, floating point

typedef unsigned long long **EC_T_UINT64**
Unsigned integer 64 bits

typedef signed long long **EC_T_INT64**
Signed integer 64 bits

**EC_T_VOID**
Void type

#### Macros

**EC_TRUE**
Boolean value: True

**EC_FALSE**
Boolean value: False

**EC_NULL**
Null pointer constant

## 9.1 General functions

### 9.1.1 emonInitMonitor

*EC_T_DWORD* **emonInitMonitor** (
*EC_T_DWORD* dwInstanceId,
*EC_T_MONITOR_INIT_PARMS* *pParms
)
Initialize EC-Monitor.

This function has to be called prior to calling any other function of EC-Monitor.

**Parameters**

- **dwInstanceId** – [in] Instance ID
- **pParms** – [in] Monitor initialization parameters

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_MONITOR_INIT_PARMS**

### Public Members

*EC_T_DWORD* **dwSignature**
[in] Set to MONITOR_SIGNATURE

*EC_T_DWORD* **dwSize**
[in] Set to sizeof(EC_T_MONITOR_INIT_PARMS)

*EC_T_LOG_PARMS* **LogParms**
[in] Logging parameters

*EC_T_OS_PARMS* ***pOsParms**
[in] Operation system layer parameters

*EC_T_LINK_PARMS* ***pLinkParms**
[in] Link layer parameters

*EC_T_ETHERNET_TAP_TYPE* **eEthTapType**
[in] Type of Ethernet TAP

*EC_T_WORD* **wMainTapPortIn**
[in] TAP IN port. For ET2000: X1.0 = 10, X1.1 = 11, X2.0 = 20, …, X4.1 = 41. For other supported TAPs, this is the port number starting from 0. If both wMainTapPortIn and wMainTapPortOut are 0, no filtering is performed

*EC_T_WORD* **wMainTapPortOut**
[in] TAP OUT port. See wMainTapPortIn

*EC_T_DWORD* **dwBusCycleTimeNsec**
[in] Bus cycle time [ns]

*EC_T_DWORD* **dwMaxBusSlaves**
[in] Maximum pre-allocated bus slave objects

*EC_T_DWORD* **dwBacktraceFrames**
[in] Number of frames held in backtrace buffer. Total memory requirements of the buffer: $2 \times dwBacktraceFrames \times 1536bytes$.

*EC_T_PERF_MEAS_INTERNAL_PARMS* **PerfMeasInternalParms**
[in] Internal performance measurement parameters

*EC_T_WORKER_THREAD_PARMS* **WorkerThreadParms**
[in] Internal worker thread parameters

*EC_T_DWORD* **dwCommunicationTimeoutMsec**
[in] Timeout [ms] for communication on the Ethernet TAP. 0: defaults to 3 sec, EC_WAITINFINITE: disables monitoring.

*EC_T_BOOL* **bApiLockByApp**
[in] Lock pending API against emonDeinitMonitor(). EC_FALSE (default): locked internally. EC_TRUE: application is responsible for locking.

*EC_T_CHAR* **szFileStoragePath**[EC_FILESTORAGE_PATH_SIZE]
[in] Path used to store records and files, e.g. FoE transfers. EC_NULL: defaults to "".

*EC_T_MBX_PARMS* **MbxParms**
[in] Mailbox monitoring parameters

*EC_T_BOOL* **bProcessRestructuredCyclicCmds**
[in] Support processing of restructured cyclic command layout. All cyclic commands are processed as long as they are within the process data boundary of the ENI.

enum **EC_T_ETHERNET_TAP_TYPE**
*Values:*

enumerator **eEthTap_Unknown**
Unknown type

enumerator **eEthTap_AutoDetect**
Auto detect TAP type. If no suitable type is detected, eEthTap_Generic is used.

enumerator **eEthTap_Generic**
Generic Ethernet switch

enumerator **eEthTap_Beckhoff_ET2000**
Beckhoff ET2000 Ethernet probe

enumerator **eEthTap_Kunbus_TapCurious**
Kunbus TAP Curious Ethernet probe

enumerator **eEthTap_PortMirror**
Port mirror Ethernet probe with separate monitoring ports for TX and RX. Only RX port supported.

enumerator **eEthTap_Dummy**

struct **EC_T_OS_PARMS**

### Public Members

*EC_T_DWORD* **dwSignature**
[in] Set to EC_OS_PARMS_SIGNATURE

*EC_T_DWORD* **dwSize**
[in] Set to sizeof(EC_T_OS_PARMS)

*EC_T_LOG_PARMS* ***pLogParms**
[in] Pointer to logging parameters

EC_PF_SYSTIME **pfSystemTimeGet**
[in] Function to get host time in nanoseconds since 1st January 2000. Used as time base for DC Initialization.

*EC_T_DWORD* **dwSupportedFeatures**
[in/out] Reserved

EC_PF_QUERY_MSEC_COUNT **pfSystemQueryMsecCount**
[in] Function to get system's ms count

struct **EC_T_LOG_PARMS**

### Public Members

*EC_T_DWORD* **dwLogLevel**
[in] Log level. See *EC_LOG_LEVEL...*

*EC_PF_LOGMSGHK* **pfLogMsg**
[in] Log callback function called on every message

EC_T_LOG_CONTEXT ***pLogContext**
[in] Log context to be passed to log callback

**EC_LOG_LEVEL_SILENT**

**EC_LOG_LEVEL_ANY**

**EC_LOG_LEVEL_CRITICAL**

**EC_LOG_LEVEL_ERROR**

**EC_LOG_LEVEL_WARNING**

**EC_LOG_LEVEL_INFO**

**EC_LOG_LEVEL_INFO_API**

**EC_LOG_LEVEL_VERBOSE**

**EC_LOG_LEVEL_VERBOSE_ACYC**

**EC_LOG_LEVEL_VERBOSE_CYC**

**EC_LOG_LEVEL_UNDEFINED**

typedef *EC_T_DWORD* (***EC_PF_LOGMSGHK**)(EC_T_LOG_CONTEXT *pContext, *EC_T_DWORD* dwLogMsgSeverity, const *EC_T_CHAR* *szFormat, ...)

**Param pContext**
[in] Context pointer. This pointer is used as parameter when the callback function is called.

**Param dwLogMsgSeverity**
[in] Log message severity, EC_LOG_LEVEL_…

**Param szFormat**
[in] String that contains the text to be written. It can optionally contain embedded format specifiers that are replaced by the values specified in subsequent additional arguments and formatted as requested.

**Return**
*EC_E_NOERROR* or error code

struct **EC_T_PERF_MEAS_INTERNAL_PARMS**

### Public Members

*EC_T_BOOL* **bEnabled**
[in] Enable/disable internal performance counters

*EC_T_PERF_MEAS_COUNTER_PARMS* **CounterParms**
[in] Timer function settings. When not provided OsMeasGetCounterTicks is used.

*EC_T_PERF_MEAS_HISTOGRAM_PARMS* **HistogramParms**
[in] Histogram settings. When not provided the histogram is disabled.

struct **EC_T_PERF_MEAS_COUNTER_PARMS**

### Public Members

*EC_PF_PERF_MEAS_GETCOUNTERTICKS* **pfGetCounterTicks**
[in] Function returning the current counter ticks

EC_T_VOID ***pvGetCounterTicksContext**
[in] Context passed into GetCounterTicks

*EC_T_UINT64* **qwFrequency**
[in] Frequency in Hz used by the timer in GetCounterTicks

typedef *EC_T_UINT64* (***EC_PF_PERF_MEAS_GETCOUNTERTICKS**)(EC_T_VOID *pvContext)

**Param pvContext**
**[in]** Arbitrarily application-defined parameter passed to callback

struct **EC_T_PERF_MEAS_HISTOGRAM_PARMS**

### Public Members

*EC_T_DWORD* **dwBinCount**
[in] Amount of bins to use for the histogram

*EC_T_UINT64* **qwMinTicks**
[in] Results below qwMinTicks are stored in the first bin

*EC_T_UINT64* **qwMaxTicks**
[in] Results above qwMaxTicks are stored in the last bin

struct **EC_T_WORKER_THREAD_PARMS**

### Public Members

*EC_T_DWORD* **dwPrio**
[in] Priority to use for the worker thread

EC_T_CPUSET **cpuAffinityMask**
[in] CPU affinity to use for the worker thread

struct **EC_T_MBX_PARMS**

### Public Members

*EC_T_DWORD* **dwMemoryPoolSize**
[in] Memory for each slave supporting mailbox communication to record e.g. the CoE dictionary. The memory is asynchronously increased by dwBufferSize by the WorkerThread when it is over 80% full. 0: defaults to 1kb

*EC_T_MBX_PARMS_COE* **Coe**
[in] CoE parameters

*EC_T_MBX_PARMS_FOE* **Foe**
[in] FoE parameters

struct **EC_T_MBX_PARMS_COE**

### Public Members

*EC_T_BOOL* **bDisableNotifications**
[in] Disable all CoE related EC_NOTIFY_MBOXRCV notifications

*EC_T_BOOL* **bDisableODStorage**
[in] Disable storage of CoE objects in the internal object dictionary

struct **EC_T_MBX_PARMS_FOE**

#### Public Members

*EC_T_BOOL* **bDisableNotifications**
[in] Disable all FoE related EC_NOTIFY_MBOXRCV notifications

*EC_T_BOOL* **bDisableFileStorage**
[in] Disable storage of FoE transfers as a file on the file system

*EC_T_DWORD* **dwMaxQueuedMbxTransfers**
[in] Maximum number of queued single FoE mailbox transfers that be used as a file write buffer. 0: defaults to 32.

### 9.1.2 emonDeinitMonitor

*EC_T_DWORD* **emonDeinitMonitor** (*EC_T_DWORD* dwInstanceId)
Deinitialize EC-Monitor.

Waits for pending API calls if *emonInitMonitor()* was called with *EC_T_MONITOR_INIT_PARMS::bApiLockByApp* = EC_FALSE (default).

**Parameters**
**dwInstanceId** – [in] Instance ID

**Returns**
*EC_E_NOERROR* or error code

### 9.1.3 emonConfigureNetwork

*EC_T_DWORD* **emonConfigureNetwork** (
*EC_T_DWORD* dwInstanceID,
*EC_T_CNF_TYPE* eCnfType,
*EC_T_PBYTE* pbyCnfData,
*EC_T_DWORD* dwCnfDataLen
)
Configure the Network.

This function must be called after the initialization. Among others the EtherCAT topology defined in the given XML configuration file will be stored internally.

---

**Note:** A client must not be registered prior to calling this function. Existing client registrations will be dropped.

---

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **eCnfType** – [in] Type of configuration data provided
- **pbyCnfData** – [in] Filename / configuration data, or EC_NULL if eCnfType is eCnfType_GenEBI
- **dwCnfDataLen** – [in] Length of configuration data in byte, or zero if eCnfType is eCnfType_GenEBI

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized or eCnfType is eCnfType_GenPreopENI or eCnfType_GenOpENI and link is disconnected
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or pParms is EC_NULL contains some values out of range
- *EC_E_LINK_DISCONNECTED* if link is disconnected
- *EC_E_FEATURE_DISABLED* if a configured feature is not included in the license key
- *EC_E_NOTSUPPORTED* if a configured feature is not supported (e.g not compiled in the library)
- *EC_E_CFGFILENOTFOUND* if the ENI file cannot be found
- *EC_E_WRONG_FORMAT* if format errors have been detected in the ENI or EEPROM in case of eCnfType_GenPreopENI or eCnfType_GenOpENI
- *EC_E_OEM_SIGNATURE_MISMATCH* if the OEM signature in the ENI file doesn't match the used OEM key
- *EC_E_ENI_ENCRYPTION_WRONG_VERSION* if the ENI encryption version is not supported (e.g. the library is too old)
- *EC_E_ENI_ENCRYPTED* if the ENI is encrypted and no OEM key has been set
- *EC_E_XML_CYCCMDS_MISSING* if the ENI doesn't contain cyclic commands
- *EC_E_XML_ALSTATUS_READ_MISSING* if the ENI doesn't contain any read AL status command
- *EC_E_XML_CYCCMDS_SIZEMISMATCH* if the size of the cyclic commands in the ENI mismatch
- *EC_E_XML_INVALID_INP_OFF* if some input offsets in the ENI are invalid
- *EC_E_XML_INVALID_OUT_OFF* if some output offsets in the ENI are invalid
- *EC_E_XML_INVALID_CMD_WITH_RED* if the ENI contains LRW commands and cable redundancy is configured
- *EC_E_XML_PREV_PORT_MISSING* if some previous port information are missing in the ENI
- *EC_E_XML_DC_CYCCMDS_MISSING* if the DC related cyclic commands are missing in the ENI
- *EC_E_XML_AOE_NETID_INVALID* if the ENI contains some invalid NetID

enum **EC_T_CNF_TYPE**

*Values:*

enumerator **eCnfType_Unknown**

enumerator **eCnfType_Filename**

pbyCnfData: ENI filename to read

enumerator **eCnfType_Data**

pbyCnfData: ENI data

enumerator **eCnfType_Datadiag**

pbyCnfData: ENI data for diagnosis

enumerator **eCnfType_GenPreopENI**
Generate ENI based on bus-scan result to get into PREOP state

enumerator **eCnfType_GenPreopENIWithCRC**
Same as eCnfType_GenPreopENI with CRC protection

enumerator **eCnfType_GenOpENI**
Generate ENI based on bus-scan result to get into OP state. The default PDO mapping read from the slaves is activated. See ETG2010 "SII Specification", Table 14 "Structure Category TXPDO and RXPDO for each PDO".

enumerator **eCnfType_None**
Reset configuration

enumerator **eCnfType_ConfigData**
pbyCnfData: Binary structured configuration

enumerator **eCnfType_GenOpENINoStrings**
Generate ENI based on bus-scan result to get into OP state, does not read strings from EEPROM

enumerator **eCnfType_FileByApp**
File access provided by user application, See EC_T_CNF_FILEBYAPP_DESC

enumerator **eCnfType_GenEBI**
Generate EBI based on bus-scan result

### 9.1.4 emonGetMonitorStatus

*EC_T_DWORD* **emonGetMonitorStatus** (
*EC_T_DWORD* dwInstanceID,
*EC_T_MONITOR_STATUS* *pStatus
)

Get current Monitor status.

Information about the current status of the EtherCAT frame / cycle processing

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pStatus** – [out] Monitor status descriptor

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized
- *EC_E_INVALIDPARM* if pStatus invalid

struct **EC_T_MONITOR_STATUS**

### Public Members

*EC_T_BOOL* **bNextFramesReceived**
[out] Indicates whether further unprocessed frames form the next EtherCAT cycle were received

*EC_T_DWORD* **dwCyclesProcessed**
[out] Number of EtherCAT cycles processed

*EC_T_WORD* **wEthTapPositionAutoIncAddr**
[out] Ethernet tap position as auto increment address

*EC_T_BOOL* **bNextCyclicEntryReceived**
[out] Indicates whether all frames from the next EtherCAT cycle have been received and have not yet been processed

*EC_T_ETHERNET_TAP_TYPE* **eEthTapType**
[out] Type of Ethernet TAP. Detected TAP if *EC_T_MONITOR_INIT_PARMS::eEthTapType* = eEthTap_AutoDetect is set.

*EC_T_BOOL* **bTopologyKnown**
[out] Topology successfully detected and validated

*EC_T_BOOL* **bPdoAssigned**
[out] PDO assignment of all slaves detected and validated

*EC_T_BOOL* **bPdoMapped**
[out] PDO mapping (SyncSM/FMMU) of all slaves detected and validated

*EC_T_BOOL* **bPdCommunicationDetected**
[out] Process Data communication detected

*EC_T_WORD* **wDeviceStatesDetected**
[out] Bit mask that indicates which slave states already detected/monitored, see *Slave device state's*

**Slave device state's**

**DEVICE_STATE_UNKNOWN**
Slave in unknown state

**DEVICE_STATE_INIT**
Slave in INIT state

**DEVICE_STATE_PREOP**
Slave in PREOP state

**DEVICE_STATE_BOOTSTRAP**
Slave in BOOTSTRAP state

**DEVICE_STATE_SAFEOP**
Slave in SAFEOP state

**DEVICE_STATE_OP**
Slave in OP state

**DEVICE_STATE_ERROR**
Slave in error state

### 9.1.5 emonSetLicenseKey

*EC_T_DWORD* **emonSetLicenseKey** (
*EC_T_DWORD* dwInstanceID,
const *EC_T_CHAR* *szLicenseKey
)

Sets the license key for the protected version of EC-Master.

Must be called after initialization and before configuration. This function may not be called if a non protected version is used.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **szLicenseKey** – [in] License key as zero terminated string with 26, 53 or 56 characters

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range
- *EC_E_INVALIDSIZE* if the format of the license key is wrong. The correct length is 26, 53 or 56 characters.
- *EC_E_LICENSE_MISSING* if the license key doesn't match the MAC Address

#### Example

```
dwRes = emonSetLicenseKey(dwInstanceId, "DA1099F2-15C249E9-54327FBC");
if (dwRes != EC_E_NOERROR)
{
    EcLogMsg(EC_LOG_LEVEL_ERROR, (pEcLogContext, EC_LOG_LEVEL_ERROR, "ERROR:␣
↪Cannot set license key: %s (0x%lx))\n",
        ecatGetText(dwRes), dwRes));
}
```

**See also:**

- *emonInitMonitor()*
- *emonConfigureNetwork()*

### 9.1.6 emonRegisterClient

*EC_T_DWORD* **emonRegisterClient** (
*EC_T_DWORD* dwInstanceID,
*EC_PF_NOTIFY* pfnNotify,
EC_T_VOID *pCallerData,
*EC_T_REGISTERRESULTS* *pRegResults
)

Registers a client on the EC-Master.

It must be called after configuration, otherwise the registration handle is lost. This function may not be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pfnNotify** – [in] Notification callback function. This function will be called every time a state change occurs, an error occurs or a mailbox transfer terminates.
- **pCallerData** – [in] Pointer to a caller data area which will be passed to the client on every notification callback
- **pRegResults** – [out] Registration results, a pointer to a structure of type *EC_T_REGISTERRESULTS*

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointer is EC_NULL
- *EC_E_NOMEMORY* if some memory cannot be allocated

typedef *EC_T_DWORD* (***EC_PF_NOTIFY**)(*EC_T_DWORD* dwCode, *EC_T_NOTIFYPARMS* *pParms)

**Param dwCode**
**[in]** Notification code, see EC_NOTIFY_…

**Param pParms**
**[in]** Notification code depending data

struct **EC_T_REGISTERRESULTS**

#### Public Members

*EC_T_DWORD* **dwClntId**
[out] Client ID

*EC_T_BYTE* ***pbyPDIn**
[out] Pointer to process data input memory

*EC_T_DWORD* **dwPDInSize**
[out] Size of process data input memory (in bytes)

*EC_T_BYTE* ***pbyPDOut***
[out] Pointer to process data output memory

*EC_T_DWORD* **dwPDOutSize**
[out] Size of process data output memory (in bytes)

### 9.1.7 emonUnregisterClient

*EC_T_DWORD* **emonUnregisterClient** (*EC_T_DWORD* dwInstanceID, *EC_T_DWORD* dwClntId)
Unregister a client from the EtherCAT master.

This function may not be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwClntId** – [in] Client ID determined when registering with the master

**Returns**
*EC_E_NOERROR* or error code

### 9.1.8 emonGetSrcMacAddress

*EC_T_DWORD* **emonGetSrcMacAddress** (
*EC_T_DWORD* dwInstanceID,
*ETHERNET_ADDRESS* *pMacSrc
)
Gets the source MAC address.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMacSrc** – [out] 6-byte buffer to write source MAC address to

**Returns**
*EC_E_NOERROR* or error code

struct **ETHERNET_ADDRESS**

#### Public Members

*EC_T_BYTE* **b**[6]
MAC address

**See also:**

*EC_T_MONITOR_INIT_PARMS::pLinkParms*

### 9.1.9 emonExecJob

*EC_T_DWORD* **emonExecJob** (
*EC_T_DWORD* dwInstanceID,
*EC_T_USER_JOB* eUserJob,
*EC_T_USER_JOB_PARMS* *pUserJobParms
)

Execute or initiate the requested job.

To achieve maximum speed, this function is implemented non re-entrant. It is highly recommended that only one single task is calling all required jobs to run the stack. If multiple tasks are calling this function, the calls have to be synchronized externally. Calling it in a context that doesn't support operating system calls can lead to unpredictable behavior.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **eUserJob** – [in] User requested job
- **pUserJobParms** – [in] Optional user job parameters

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointer is EC_NULL
- *EC_E_LINK_DISCONNECTED* if the link is disconnected
- *EC_E_FEATURE_DISABLED* for eUsrJob_SwitchEoeFrames if EC_IOCTL_SET_EOE_DEFFERED_SWITCHING_ENABLED hasn't be called before
- *EC_E_ADS_IS_RUNNING* if the ADS server is running

*Brief job overview:*

enum **EC_T_USER_JOB**
*Values:*

enumerator **eUsrJob_Undefined**

enumerator **eUsrJob_ProcessAllRxFrames**

enumerator **eUsrJob_SendAllCycFrames**

enumerator **eUsrJob_MasterTimer**

enumerator **eUsrJob_SendAcycFrames**

enumerator **eUsrJob_SendCycFramesByTaskId**

enumerator **eUsrJob_MasterTimerMinimal**

enumerator **eUsrJob_ProcessRxFramesByTaskId**

enumerator **eUsrJob_ProcessAcycRxFrames**

enumerator **eUsrJob_SwitchEoeFrames**

enumerator **eUsrJob_StartTask**

enumerator **eUsrJob_StopTask**

enumerator **eUsrJob_StampSendAllCycFrames**

enumerator **eUsrJob_StampSendCycFramesByTaskId**

enumerator **eUsrJob_SimulatorTimer**

enumerator **eUsrJob_MonitorTimer**

union **EC_T_USER_JOB_PARMS**

### Public Members

*EC_T_BOOL* **bAllCycFramesProcessed**

*EC_T_DWORD* **dwNumFramesSent**

*EC_T_DWORD* **dwTaskIdToSend**

struct *EC_T_USER_JOB_PARMS*::*_SEND_CYCFRAME_BY_TASKID* **SendCycFramesByTaskId**

struct *EC_T_USER_JOB_PARMS*::*_PROCESS_RXFRAME_BY_TASKID* **ProcessRxFramesByTaskId**

struct *EC_T_USER_JOB_PARMS*::*_SWITCH_EOE_FRAMES* **SwitchEoeFrames**

struct *EC_T_USER_JOB_PARMS*::*_START_TASK* **StartTask**

struct *EC_T_USER_JOB_PARMS*::*_STOP_TASK* **StopTask**

struct **_PROCESS_RXFRAME_BY_TASKID**

#### Public Members

*EC_T_BOOL* **bCycFramesProcessed**

*EC_T_DWORD* **dwTaskId**

struct **_SEND_CYCFRAME_BY_TASKID**

#### Public Members

*EC_T_DWORD* **dwTaskId**

struct **_START_TASK**

#### Public Members

*EC_T_DWORD* **dwTaskId**

struct **_STOP_TASK**

#### Public Members

*EC_T_DWORD* **dwTaskId**

struct **_SWITCH_EOE_FRAMES**

#### Public Members

*EC_T_DWORD* **dwMaxPortsToProcess**

*EC_T_DWORD* **dwNumFramesProcessed**

*Detailed job description:*

1. ***eUsrJob_ProcessAllRxFrames***
   When the Real-time Ethernet Driver operates in polling mode this call will process all currently received frames, when the Real-time Ethernet Driver operates in interrupt mode all received frames are processed immediately and this call just returns with nothing done.

   ```
   pUserJobParms->bAllCycFramesProcessed
   ```

   If this flag is set to a value of *EC_TRUE* it indicates that all previously initiated cyclic frames ( *eUsrJob_SendAllCycFrames* ) are received and processed within this call. Not used if pUserJobParms set to *EC_NULL*.

   Return: *EC_E_NOERROR* if successful, error code in case of failures.

2. ***eUsrJob_MonitorTimer***
   To trigger the monitor and SubDevice state machines as well as the mailbox handling this call has to be executed cyclically. The monitor cycle time is determined by the period between calling *emonExecJob()* ( *eUsrJob_MonitorTimer*). The state-machines are handling the EtherCAT® state change transfers.

   Return: *EC_E_NOERROR* if successful, error code in case of failures.

### 9.1.10 emonGetMonitorParms

*EC_T_DWORD* **emonGetMonitorParms** (
    *EC_T_DWORD* dwInstanceID,
    *EC_T_MONITOR_INIT_PARMS* *pParms,
    *EC_T_DWORD* dwParmsBufSize
)

Gets current Monitor Init Parameters.

If the given buffer is larger than the actual size of the struct *EC_T_MONITOR_INIT_PARMS*, the parameters of *EC_T_MONITOR_INIT_PARMS.pOsParms*, *EC_T_MONITOR_INIT_PARMS.pLinkParms* are appended.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pParms** – [out] Buffer to store parameters
- **dwParmsBufSize** – [in] Size of the buffer in bytes

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized
- *EC_E_INVALIDPARM* if buffer pParms is too small

### Example

```
/* Read all monitor init parameters, including OS and Link parameters */
EC_T_BYTE abyBuffer[sizeof(EC_T_MONITOR_INIT_PARMS) + sizeof(EC_T_OS_PARMS) + 512 /
↪* LinkLayer parameters */];
EC_T_MONITOR_INIT_PARMS* pParms = (EC_T_MONITOR_INIT_PARMS*)abyBuffer;
OsMemset(abyBuffer, 0, sizeof(abyBuffer));

dwRes = emonGetMonitorParms(dwInstanceId, pParms, sizeof(abyBuffer));
if (EC_E_NOERROR != dwRes)
{
    EcLogMsg(EC_LOG_LEVEL_ERROR, (pEcLogContext, EC_LOG_LEVEL_ERROR, "Cannot get␣
↪monitor parameters: %s (0x%lx))\n",
        ecatGetText(dwRes), dwRes));
}
```

**See also:**

*emonInitMonitor()*

## 9.1.11 emonSetMonitorParms

*EC_T_DWORD* **emonSetMonitorParms** (
*EC_T_DWORD* dwInstanceID,
*EC_T_MONITOR_INIT_PARMS* *pParms
)

Change Monitor Init Parameters.

OS parms, Main Link parms cannot be changed.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pParms** – [in] New Monitor init parameters

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized

**See also:**

*emonInitMonitor()*

## 9.1.12 emonGetVersion

*EC_T_DWORD* **emonGetVersion** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* *pdwVersion,
*EC_T_DWORD* *pdwVersionType
)

Gets the version information.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

- **pdwVersion** – [out] Pointer to EC_T_DWORD to carry out version number as a 32-bit value
- **pdwVersionType** – [out] Pointer to EC_T_DWORD to carry out version type. See EC_VERSION_TYPE.

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointer is EC_NULL

### 9.1.13 emonGetText

const *EC_T_CHAR* ***emonGetText** (*EC_T_DWORD* dwInstanceID, *EC_T_DWORD* dwTextId)

Return text tokens by ID.

**Parameters**

**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**

Textual description of the given ID

### 9.1.14 emonGetMemoryUsage

*EC_T_DWORD* **emonGetMemoryUsage** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* *pdwCurrentUsage,
*EC_T_DWORD* *pdwMaxUsage
)

Returns information about memory usage.

All calls to malloc/free and new/delete are monitored.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pdwCurrentUsage** – [out] Current memory usage in Bytes at the time where this function is called
- **pdwMaxUsage** – [out] Maximum memory usage in Bytes since initialization at the time where this function is called

**Returns**

*EC_E_NOERROR* or error code

### 9.1.15 emonGetMasterState

*EC_T_STATE* **emonGetMasterState** (*EC_T_DWORD* dwInstanceID)
Get the EtherCAT master current state.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
EtherCAT master state

enum **EC_T_STATE**
*Values:*

enumerator **eEcatState_UNKNOWN**

enumerator **eEcatState_INIT**

enumerator **eEcatState_PREOP**

enumerator **eEcatState_SAFEOP**

enumerator **eEcatState_OP**

enumerator **eEcatState_BOOTSTRAP**

### 9.1.16 emonGetMasterStateEx

*EC_T_DWORD* **emonGetMasterStateEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* *pwCurrState,
*EC_T_WORD* *pwReqState
)
Get the EtherCAT master current and requested state. Possible return values for current and requested state:

- *DEVICE_STATE_UNKNOWN*
- *DEVICE_STATE_INIT*
- *DEVICE_STATE_PREOP*
- *DEVICE_STATE_SAFEOP*
- *DEVICE_STATE_OP*

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pwCurrState** – [out] Current master state
- **pwReqState** – [out] Requested master state

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointers are EC_NULL

---

**Limitation**

Since it is not possible to determine the actual requested MainDevice state, the highest SubDevice state of all SubDevices is assumed to be the requested MainDevice state.

---

### 9.1.17 emonFindInpVarByName - "Inputs.DevicesState"

The device status of all SubDevices (OR-linked) is part of the process data with name "Inputs.DevicesState".

*EC_T_DWORD emonFindInpVarByName*(*EC_T_DWORD* dwInstanceID, const *EC_T_CHAR* *szVariableName, *EC_T_PROCESS_VAR_INFO* *pProcessVarInfoEntry)

### 9.1.18 emonFindInpVarByName - "Inputs.BusTime"

The DC system time (written to ESC register 0x0910) is part of the process data with name "Inputs.BusTime".

*EC_T_DWORD emonFindInpVarByName*(*EC_T_DWORD* dwInstanceID, const *EC_T_CHAR* *szVariableName, *EC_T_PROCESS_VAR_INFO* *pProcessVarInfoEntry)

### 9.1.19 emonExportEniBuilderConfig

*EC_T_DWORD* **emonExportEniBuilderConfig**(
    *EC_T_DWORD* dwInstanceID,
    const *EC_T_CHAR* *szFileName
)

Export an EniBuilder file describing the observed network topology.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **szFileName** – [in] null-terminated export file path

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDPARM* if parameter file name invalid
- *EC_E_OPENFAILED* if file could not be opened
- *EC_E_NOMEMORY* if not enough memory available

**See also:**

*Operation without ENI*

### 9.1.20 emonIoCtl

With `emonIoCtl` a generic control interface exists between the application and the EC-Monitor and its Real-time Ethernet Drivers.

*EC_T_DWORD* **emonIoCtl** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwCode,
const EC_T_VOID *const pbyInBuf,
*EC_T_DWORD* dwInBufSize,
EC_T_VOID *const pbyOutBuf,
*EC_T_DWORD* dwOutBufSize,
*EC_T_DWORD* *const pdwNumOutData
)

A generic control interface between the application, the EtherCAT stack and its Link Layers.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwCode** – [in] IOCTL code (EC_IOCTL…)
- **pbyInBuf** – [in] IOCTL input parameters
- **dwInBufSize** – [in] Size of IOCTL input parameters in bytes
- **pbyOutBuf** – [out] Buffer for IOCTL output
- **dwOutBufSize** – [in] Size of buffer at pbyOutBuf in bytes
- **pdwNumOutData** – [out] Amount of bytes written to pbyOutBuf by IOCTL. EC_NULL: amount not set by IOCTL.

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer
- *EC_E_NOMEMORY* if memory cannot be allocated
- *EC_E_ADS_IS_RUNNING* if the ADS server is running

### 9.1.21 emonIoCtl - EC_IOCTL_REGISTER_CYCFRAME_RX_CB

**EC_IOCTL_REGISTER_CYCFRAME_RX_CB**

This function call registers a callback function which is called after the cyclic frame is received. Typically this is used when the Real-time Ethernet Driver operates in interrupt mode to get an event when the new input data (cyclic frame) is available. The callback function has to be registered after the stack initialisation and before starting the job task.

**Parameters**

- **pbyInBuf** – [in] Cyclic frame received callback descriptor (*EC_T_CYCFRAME_RX_CBDESC*)
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL

- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_CYCFRAME_RX_CBDESC**

### Public Members

EC_T_VOID ***pCallbackContext**
[in] Context pointer. This pointer is used as parameter every time the callback function is called.

*EC_PF_CYCFRAME_RECV* **pfnCallback**
[in] This function will be called after the cyclic frame is received, if there is more than one cyclic frame after the last frame. The application has to assure that these functions will not block.

typedef EC_T_VOID (***EC_PF_CYCFRAME_RECV**)(*EC_T_DWORD* dwTaskId, EC_T_VOID *pvContext)

**Param dwTaskId**
[in] Task id of the received cyclic frame

**Param pvContext**
[in] Context pointer. This pointer is used as parameter every time when the callback function is called.

**See also:**

*emonIoCtl()*

## 9.1.22 emonIoCtl - EC_IOCTL_GET_CYCLIC_CONFIG_INFO

**EC_IOCTL_GET_CYCLIC_CONFIG_INFO**
Determine cyclic configuration details from ENI configuration file. It can be called only after configuring the network.

**Parameters**

- **pbyInBuf** – [in] Pointer to dwCycEntryIndex: Cyclic entry index for which to get information
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Pointer to *EC_T_CYC_CONFIG_DESC* data type
- **dwOutBufSize** – [in] Size of the output buffer provided at pbyOutBuf in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_CYC_CONFIG_DESC**

#### Public Members

*EC_T_DWORD* **dwNumCycEntries**
[out] Total number of cyclic entries

*EC_T_DWORD* **dwTaskId**
[out] Task ID of selected cyclic entry (ENI: Cyclic/TaskId)

*EC_T_DWORD* **dwPriority**
[out] Priority of selected cyclic entry

*EC_T_DWORD* **dwCycleTime**
[out] Cycle time of selected cyclic entry

**See also:**

*emonIoCtl()*

### 9.1.23 emonIoCtl - EC_IOCTL_IS_SLAVETOSLAVE_COMM_CONFIGURED

**EC_IOCTL_IS_SLAVETOSLAVE_COMM_CONFIGURED**
Determine if any slave to slave communication is configured.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Pointer to EC_T_DWORD. If value is EC_TRUE slave to slave communication is configured, if EC_FALSE it is not.
- **dwOutBufSize** – [in] Size of the output buffer in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*emonIoCtl()*

## 9.2 Packet Capture

### 9.2.1 emonOpenPacketCapture

*EC_T_DWORD* **emonOpenPacketCapture** (
*EC_T_DWORD* dwInstanceID,
*EC_T_PACKETCAPTURE_PARMS* *pParms
)
Open packet capture file (PCAP).

Opens a PCAP trace for further processing within the JobTask. No LinkLayer must have been loaded.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pParms** – [in] Packet capture parameter

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized or link layer loaded
- *EC_E_INVALIDPARM* if parameter file name invalid
- *EC_E_OPENFAILED* if file could not be opened
- *EC_E_NOMEMORY* if not enough memory available

struct **EC_T_PACKETCAPTURE_PARMS**

### Public Members

*EC_T_CHAR* **szFileName**[EC_PACKETCAPTURE_FILE_NAME_SIZE]
[in] File name. Supported formats are .pcap or .pcapng.

*EC_T_BOOL* **bReadMultipleFiles**
[in] Read multiple contiguous files. File name format must be "fileName.nnnnn.pcap[ng]", e.g. wireshark.00000.pcap.

*EC_T_DWORD* **dwMaxFrameCnt**
[in] Creates a new file every time the number of frames written exceeds this limit. Disabled with a value set to 0.

*EC_T_DWORD* **dwMaxFileSize**
[in] Creates a new file every time the number of bytes written exceeds this limit. Disabled with a value set to 0.

*EC_T_DWORD* **dwRingBufferFileCnt**
[in] Form a ring buffer of the capture files with the given number of files. Only if *EC_T_PACKETCAPTURE_PARMS::dwMaxFrameCnt* or *EC_T_PACKETCAPTURE_PARMS::dwMaxFileSize* are set. Disabled with a value set to 0.

### Example

```
EC_T_PACKETCAPTURE_PARMS PacketCaptureParms;
OsMemset(&PacketCaptureParms, dwInstanceId, sizeof(EC_T_PACKETCAPTURE_PARMS));

OsSafeStrcpy(PacketCaptureParms.szFileName, "C:\\ecat.pcap");
dwRes = emonOpenPacketCapture(0, &PacketCaptureParms);
if (EC_E_NOERROR != dwRes)
{
    EcLogMsg(EC_LOG_LEVEL_ERROR, (pEcLogContext, EC_LOG_LEVEL_ERROR, "Cannot open␣
↪packet capture: %s (0x%lx))\n",
        ecatGetText(dwRes), dwRes));
}
```

### 9.2.2 emonClosePacketCapture

*EC_T_DWORD* **emonClosePacketCapture** (*EC_T_DWORD* dwInstanceID)
Close packet capture file (PCAP).

**Parameters**
**dwInstanceID** – [in] Instance ID

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized or link layer loaded

### 9.2.3 emonGetPacketCaptureInfo

*EC_T_DWORD* **emonGetPacketCaptureInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_PACKETCAPTURE_INFO* *pInfo
)
Get packet capture file processing status information.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pInfo** – [out] Packet capture info descriptor

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized or link layer loaded

struct **EC_T_PACKETCAPTURE_INFO**

#### Public Members

*EC_T_PACKETCAPTURE_STATUS* **eStatus**
[out] Status of packet capture processing

*EC_T_CHAR* **szFileName**[EC_PACKETCAPTURE_FILE_NAME_SIZE]
[out] File name of current processed capture

*EC_T_UINT64* **qwFrameNumberTotal**
[out] Total number of processed frames from all capture files

*EC_T_UINT64* **qwFrameNumberCur**
[out] Last processed frame number from the current packet capture file

*EC_T_UINT64* **qwBytesProcessed**
[out] Number of processed bytes from the current packet capture file

*EC_T_UINT64* **qwFileSize**
[out] File size[bytes] of the current packet capture

*EC_T_UINT64* **qwTimeStamp**
[out] Time stamp [ns] of the last processed frame from the current packet capture file

*EC_T_DWORD* **dwCyclesProcessed**
[out] Number of EtherCAT cycles processed

enum **EC_T_PACKETCAPTURE_STATUS**
*Values:*

enumerator **ePcapStatus_Unknown**
Unknown packet capture status

enumerator **ePcapStatus_NotLoaded**
No packet capture loaded

enumerator **ePcapStatus_Running**
Packet capture processing running

enumerator **ePcapStatus_Finished**
Packet capture processing finished

enumerator **ePcapStatus_Dummy**

### 9.2.4 emonStartLivePacketCapture

*EC_T_DWORD* **emonStartLivePacketCapture** (
*EC_T_DWORD* dwInstanceID,
*EC_T_PACKETCAPTURE_PARMS* *pParms
)
Start live packet capture (PCAP).

Starts a live recording of the EtherCAT frames in a specified PCAP file.

**Note:** Only the PCAP file format is currently supported.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pParms** – [in] Packet capture parameter

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDPARM* if parameter file name invalid
- *EC_E_OPENFAILED* if file could not be opened
- *EC_E_NOMEMORY* if not enough memory available

### 9.2.5 emonStopLivePacketCapture

*EC_T_DWORD* **emonStopLivePacketCapture** (*EC_T_DWORD* dwInstanceID)

Stop live packet capture (PCAP).

Stops a previously started live recording of the EtherCAT frames.

**Parameters**

**dwInstanceID** – [in] Instance ID

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_INVALIDSTATE* if Monitor isn't initialized or no recording is in progress

### 9.2.6 emonBacktracePacketCapture

*EC_T_DWORD* **emonBacktracePacketCapture** (
*EC_T_DWORD* dwInstanceID,
*EC_T_PACKETCAPTURE_PARMS* *pParms
)

Dump packet capture (PCAP) from backtrace buffer.

Writes a backtrace of the received frames in a specified PCAP file. The number of frames in the backtrace buffer is parameterized via *EC_T_MONITOR_INIT_PARMS::dwBacktraceFrames*.

**Note:** Only the PCAP file format is currently supported.

**Parameters**

- **dwInstanceID** – [in] Instance ID
- **pParms** – [in] Packet capture parameter

**Returns**

- *EC_E_NOERROR* on success
- *EC_E_BUSY* if another dump is in progress
- *EC_E_INVALIDSTATE* if backtrace buffer is not initialized
- *EC_E_INVALIDPARM* if parameter file name invalid
- *EC_E_OPENFAILED* if file could not be opened
- *EC_E_NOMEMORY* if not enough memory available

**See also:**

*emonInitMonitor()*

## 9.3 Process Data functions

### 9.3.1 emonGetProcessData

*EC_T_DWORD* **emonGetProcessData** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bOutputData,
*EC_T_DWORD* dwOffset,
*EC_T_BYTE* *pbyData,
*EC_T_DWORD* dwDataLen,
*EC_T_DWORD* dwTimeout
)

Blocking function to retrieve consistent process data from outside the JobTask context.

This function requests a copy of the process data (stored in RAM). The actual memcpy operation is executed by the JobTask to ensure data consistency. While waiting for the copy to complete, the calling context blocks and repeatedly calls sleep with an interval of at least the cycle time or one millisecond, whichever is greater. The function returns either with the requested process data once the copy is finished, or when the specified timeout has expired.

---

**Note:** The function is blocking and should be used carefully in time-sensitive contexts and may not be called from within the JobTask context. If process data are required outside the cyclic monitor job task (which is calling emonExecJob), direct access to the process data is not recommended as data consistency cannot be guaranteed. A call to this function will send a data read request to the monitor stack and then check every millisecond whether new data is provided. The monitor stack will provide new data after calling emonExecJob(eUsrJob_MonitorTimer) within the job task. This function is usually only called remotely (using the Remote API).

---

---

**Note:** This function may not be called from within the JobTask's context.

---

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bOutputData** – [in] EC_TRUE: read output data, EC_FALSE: read input data
- **dwOffset** – [in] Byte offset in Process data to read from
- **pbyData** – [out] Buffer receiving transferred data
- **dwDataLen** – [in] Buffer length [bytes]
- **dwTimeout** – [in] Timeout [ms]

**Returns**

*EC_E_NOERROR* or error code

### 9.3.2 emonGetProcessDataBits

*EC_T_DWORD* **emonGetProcessDataBits** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bOutputData,
*EC_T_DWORD* dwBitOffsetPd,
*EC_T_BYTE* *pbyData,
*EC_T_DWORD* dwDataBitLen,
*EC_T_DWORD* dwTimeout
)

Reads a specific number of bits from the process image to the given buffer with a bit offset (synchronized).

This function may not be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bOutputData** – [in] EC_TRUE: read output data, EC_FALSE: write input data
- **dwBitOffsetPd** – [in] Bit offset in Process data image
- **pbyData** – [out] Buffer receiving transferred data
- **dwDataBitLen** – [in] Buffer length [bit]
- **dwTimeout** – [in] Timeout [ms]. The timeout value must not be set to EC_NOWAIT.

**Returns**

*EC_E_NOERROR* or error code

**See also:**

*emonGetProcessData()*

### 9.3.3 emonGetProcessImageInputPtr

*EC_T_BYTE* ***emonGetProcessImageInputPtr** (*EC_T_DWORD* dwInstanceID)

Gets the process data input image pointer.

**Parameters**

**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**

Process data input image pointer

### 9.3.4 emonGetProcessImageOutputPtr

*EC_T_BYTE* ***emonGetProcessImageOutputPtr** (*EC_T_DWORD* dwInstanceID)

Gets the process data output image pointer.

**Parameters**

**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**

Process data output image pointer

### 9.3.5 emonFindInpVarByName

*EC_T_DWORD* **emonFindInpVarByName** (
*EC_T_DWORD* dwInstanceID,
const *EC_T_CHAR* *szVariableName,
*EC_T_PROCESS_VAR_INFO* *pProcessVarInfoEntry
)

Finds an input process variable information entry by the variable name.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **szVariableName** – [in] Variable name
- **pProcessVarInfoEntry** – [out] Process variable information entry

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO*

### 9.3.6 emonFindInpVarByNameEx

*EC_T_DWORD* **emonFindInpVarByNameEx** (
*EC_T_DWORD* dwInstanceID,
const *EC_T_CHAR* *szVariableName,
*EC_T_PROCESS_VAR_INFO_EX* *pProcessVarInfoEntry
)

Finds an input process variable extended information entry by the variable name.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **szVariableName** – [in] Variable name
- **pProcessVarInfoEntry** – [out] Process variable extended information entry

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO_EX*

### 9.3.7 emonFindOutpVarByName

*EC_T_DWORD* **emonFindOutpVarByName** (
*EC_T_DWORD* dwInstanceID,
const *EC_T_CHAR* *szVariableName,
*EC_T_PROCESS_VAR_INFO* *pProcessVarInfoEntry
)

Finds an output process variable information entry by the variable name.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

- **szVariableName** – [in] Variable name
- **pProcessVarInfoEntry** – [out] Process variable information entry

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO*

### 9.3.8 emonFindOutpVarByNameEx

*EC_T_DWORD* **emonFindOutpVarByNameEx** (
*EC_T_DWORD* dwInstanceID,
const *EC_T_CHAR* *szVariableName,
*EC_T_PROCESS_VAR_INFO_EX* *pProcessVarInfoEntry
)

Finds an output process variable extended information entry by the variable name.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **szVariableName** – [in] Variable name
- **pProcessVarInfoEntry** – [out] Process variable extended information entry

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO_EX*

### 9.3.9 emonIoCtl - EC_IOCTL_GET_PDMEMORYSIZE

**EC_IOCTL_GET_PDMEMORYSIZE**

Get the process data image size. This information may be used to provide process data image storage from outside the core. This IOCTL is to be called after network configuration.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Pointer to memory where the memory size information will be stored (type: *EC_T_MEMREQ_DESC*)
- **dwOutBufSize** – [in] Size of the output buffer in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_MEMREQ_DESC**

#### Public Members

*EC_T_DWORD* **dwPDOutSize**
Size of the output process data image

*EC_T_DWORD* **dwPDInSize**
Size of the input process data image

**See also:**

*emonIoCtl()*

### 9.3.10 Process Data access functions

#### 9.3.10.1 EC_COPYBITS

**EC_COPYBITS** (pbyDst, nDstBitOffs, pbySrc, nSrcBitOffs, nBitSize)
Copies a block of bits from a source buffer to a destination buffer.

---

**Note:** The memory buffers must be allocated before. The buffers must be big enough to hold the block starting at the given offsets! The buffers are not checked for overrun.

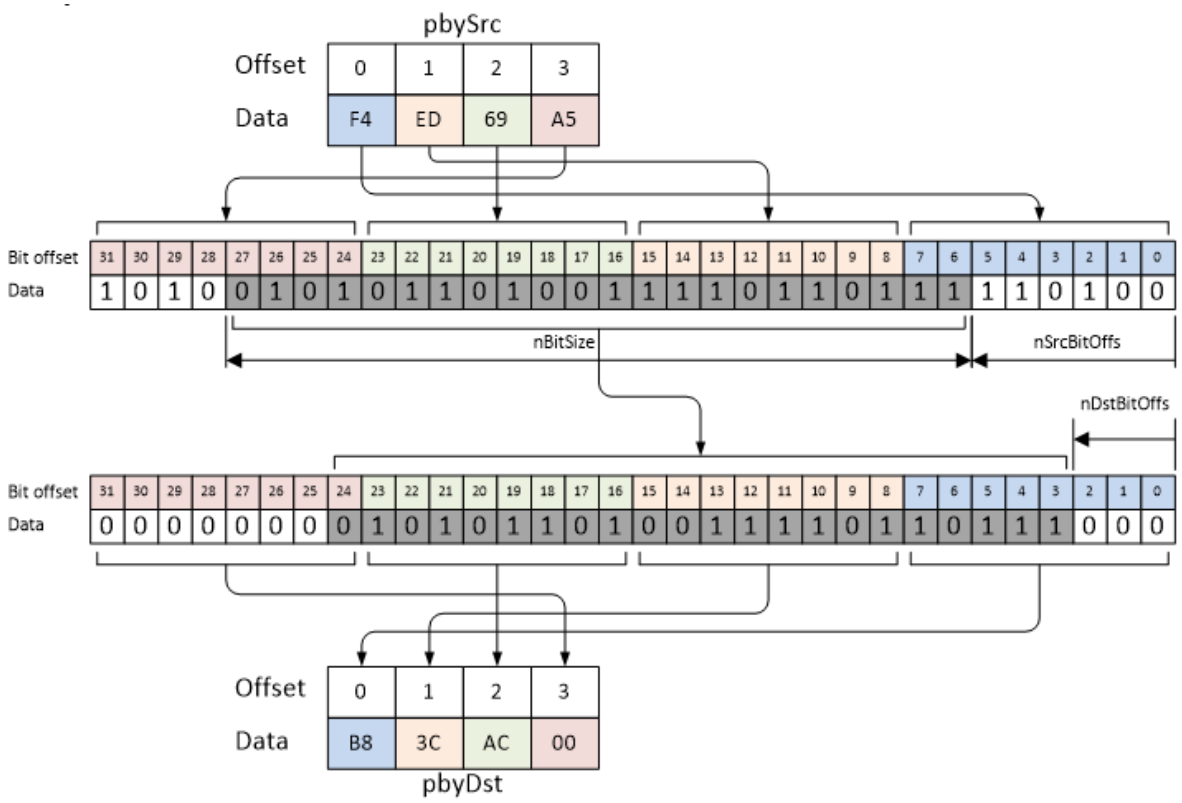
---

**Parameters**

- **pbyDst** – [out] Destination buffer
- **nDstBitOffs** – [in] Bit offset within destination buffer
- **pbySrc** – [in] Source buffer
- **nSrcBitOffs** – [in] Bit offset within source buffer
- **nBitSize** – [in] Block size in bits

**See also:**

- EC_SETBITS
- *EC_GETBITS*




```
EC_T_BYTE pbySrc[] = {0xF4, 0xED, 0x69, 0xA5};
EC_T_BYTE pbyDst[] = {0x00, 0x00, 0x00, 0x00};
EC_COPYBITS(pbyDst, 3, pbySrc, 6, 22);

/* pbyDst now contains 0xB8 0x3C 0xAC 0x00 */
```

#### 9.3.10.2 EC_GET_FRM_WORD

**EC_GET_FRM_WORD** (ptr)

Reads a value of type EC_T_WORD (16 bit) at given pointer. The value is swapped on big endian systems.

**Parameters**

- **ptr** – [in] Source buffer

**Returns**

EC_T_WORD value (16 bit) from buffer

```
EC_T_BYTE byFrame[] = {0x01, 0xF4, 0xDD, 0x85, 0x03, 0x00, 0x60, 0xC1, 0x00};
EC_T_WORD wResult = 0;

wResult = EC_GET_FRM_WORD(byFrame);
/* wResult is 0xF401 on little endian systems */

wResult = EC_GET_FRM_WORD(byFrame + 5);
/* wResult is 0x6000 on little endian systems */

wResult = EC_GET_FRM_WORD(byFrame + 2);
/* wResult is 0x85DD on little endian systems */
```

#### 9.3.10.3 EC_GET_FRM_DWORD

**EC_GET_FRM_DWORD** (ptr)

Reads a value of type EC_T_DWORD (32 bit) at given pointer. The value is swapped on big endian systems.

**Parameters**

- **ptr** – [in] Source buffer

**Returns**

EC_T_DWORD value (32 bit) from buffer

```
EC_T_BYTE byFrame[] = {0x01, 0xF4, 0xDD, 0x85, 0x03, 0x00, 0x60, 0xC1, 0x00};
EC_T_DWORD dwResult = 0;

dwResult = EC_GET_FRM_DWORD(byFrame);
/* dwResult is 0x85DDF401 on little endian systems */

dwResult = EC_GET_FRM_DWORD(byFrame + 5);
/* dwResult is 0x00C16000 on little endian systems */

dwResult = EC_GET_FRM_DWORD(byFrame + 2);
/* dwResult is 0x000385DD on little endian systems */
```

#### 9.3.10.4 EC_GET_FRM_QWORD

**EC_GET_FRM_QWORD** (ptr)

Reads a value of type EC_T_QWORD (64 bit) at given pointer. The value is swapped on big endian systems.

**Parameters**

- **ptr** – [in] Source buffer

**Returns**

EC_T_QWORD value (64 bit) from buffer

```
EC_T_BYTE byFrame[] = {0x01, 0xF4, 0xDD, 0x85, 0x03, 0x00, 0x60, 0xC1, 0x00};
EC_T_UINT64 ui64Result = 0;

ui64Result = EC_GET_FRM_QWORD(byFrame + 1);
/* wResult is 0x00C160000385DDF4 on little endian systems */
```

#### 9.3.10.5 EC_GETBITS

**EC_GETBITS** (pbySrcBuf, pbyDstData, nSrcBitOffs, nBitSize)

Reads a given number of bits from source buffer starting at given bit offset to destination buffer.

---

**Note:** This function should only be used to get bit-aligned data. For byte-aligned data the corresponding functions should be used.

---

**Parameters**

- **pbySrcBuf** – [in] Source buffer to be copied
- **pbyDstData** – [out] Destination buffer where data is copied to
- **nSrcBitOffs** – [in] Source bit offset where data is copied from

- **nBitSize** – [in] Bit count to be copied

**See also:**

- *EC_GET_FRM_WORD*
- *EC_GET_FRM_DWORD*
- *EC_GET_FRM_QWORD*

### 9.3.11 EC_TESTBIT

**EC_TESTBIT**(pbyBuf, nBitOffs)
Test whether a bit in the buffer is set.

**Parameters**

- **pbyBuf** – Source buffer.
- **nBitOffs** – Bit offset to test.

**Returns**
EC_TRUE if bit is set, otherwise EC_FALSE.

### 9.3.12 emonIoCtl - EC_IOCTL_SET_IGNORE_INPUTS_ON_WKC_ERROR

**EC_IOCTL_SET_IGNORE_INPUTS_ON_WKC_ERROR**
Set ignore inputs on WKC error.

**Parameters**

- **pbyInBuf** – [in] Pointer to value of EC_T_BOOL. EC_TRUE: Ignore inputs on WKC error.
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

Calling this IOCTL with *EC_TRUE* as parameter will ignore input data of cyclic commands on WKC error. By default input data are updated if WKC is non zero. If WKC is not matching the expected value a notification *emonNotify - EC_NOTIFY_CYCCMD_WKC_ERROR* is generated and the application must consider this status for the current cycle.

**See also:**

*emonIoCtl()*

### 9.3.13 emonIoCtl - EC_IOCTL_SET_ZERO_INPUTS_ON_WKC_ERROR

**EC_IOCTL_SET_ZERO_INPUTS_ON_WKC_ERROR**
Set inputs to zero on WKC error.

**Parameters**

- **pbyInBuf** – [in] Pointer to value of EC_T_BOOL. EC_TRUE: Inputs are set to zero on WKC error.
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

Calling this IOCTL with *EC_TRUE* as parameter will set inputs to zero on WKC error. By default input data are updated if WKC is non zero. If WKC is not matching the expected value a notification *emonNotify - EC_NOTIFY_CYCCMD_WKC_ERROR* is generated and the application must consider this status for the current cycle.

**See also:**

*emonIoCtl()*

### 9.3.14 emonIoCtl - EC_IOCTL_SET_ZERO_INPUTS_ON_WKC_ZERO

**EC_IOCTL_SET_ZERO_INPUTS_ON_WKC_ZERO**
Set inputs to zero if WKC is zero.

**Parameters**

- **pbyInBuf** – [in] Pointer to value of EC_T_BOOL. EC_TRUE: Set inputs to zero if WKC is zero.
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

Calling this IOCTL with *EC_TRUE* as parameter will set inputs to zero on WKC is zero. By default input data are ignored on WKC is zero and remain unchanged. If WKC is not matching the expected value a notification *emonNotify - EC_NOTIFY_CYCCMD_WKC_ERROR* is generated and the application must consider this status for the current cycle.

### 9.3.15 emonIoCtl - EC_IOCTL_SET_ZERO_INPUTS_ON_FRAME_LOSS

**EC_IOCTL_SET_ZERO_INPUTS_ON_FRAME_LOSS**
Set inputs to zero on frame loss.

**Parameters**

- **pbyInBuf** – [in] Pointer to value of EC_T_BOOL. EC_TRUE: Set inputs to zero on frame loss
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

Calling this IOCTL with *EC_TRUE* as parameter will set inputs to zero on frame loss. By default input data are ignored on frame loss and remain unchanged.

**See also:**

*emonIoCtl()*

## 9.4 SubDevice status functions

### 9.4.1 emonGetNumConfiguredSlaves

*EC_T_DWORD* **emonGetNumConfiguredSlaves** (*EC_T_DWORD* dwInstanceID)
Returns the number of slaves which are configured in the ENI.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
Number of slaves

### 9.4.2 emonGetNumConnectedSlaves

*EC_T_DWORD* **emonGetNumConnectedSlaves** (*EC_T_DWORD* dwInstanceID)
Get number of currently connected slaves.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
Number of connected slaves

### 9.4.3 emonGetSlaveId

*EC_T_DWORD* **emonGetSlaveId** (*EC_T_DWORD* dwInstanceID, *EC_T_WORD* wStationAddress)

Determines the slave ID using the slave station address.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **wStationAddress** – [in] Station address of the slave

**Returns**

Slave ID or INVALID_SLAVE_ID if the slave could not be found or the stack is not initialized

### 9.4.4 emonGetSlaveIdAtPosition

*EC_T_DWORD* **emonGetSlaveIdAtPosition** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* wAutoIncAddress
)

Determines the slave ID using the slave auto increment address.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **wAutoIncAddress** – [in] Auto increment address of the slave

**Returns**

Slave ID or INVALID_SLAVE_ID if no slave matching wAutoIncAddress can be found

### 9.4.5 emonGetSlaveState

*EC_T_DWORD* **emonGetSlaveState** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_WORD* *pwCurrDevState,
*EC_T_WORD* *pwReqDevState
)

Get the slave state.

The slave state is always read automatically from the AL_STATUS register whenever necessary. It is not forced by calling this function. This function may be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave ID
- **pwCurrDevState** – [out] Current slave state
- **pwReqDevState** – [out] Requested slave state

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized

- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointers are EC_NULL
- *EC_E_SLAVE_NOT_PRESENT* if the slave is not present
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found

**Limitation**

Since it is not possible to determine the actual requested SubDevice state from the MainDevice, the highest SubDevice state of all SubDevices is assumed to be the requested state.

**See also:**

- *emonGetSlaveId()*
- *emonNotify - EC_NOTIFY_SLAVE_STATECHANGED*

### 9.4.6 emonIsSlavePresent

*EC_T_DWORD* **emonIsSlavePresent** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_BOOL* *pbPresence
)

Returns whether a specific slave is currently connected to the Bus.

This function may be called from within the JobTask.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave ID
- **pbPresence** – [out] EC_TRUE if the slave is currently connected to the bus, EC_FALSE if not

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found

**See also:**

- *emonGetSlaveId()*
- *emonNotify - EC_NOTIFY_SLAVE_PRESENCE*

### 9.4.7 emonGetSlaveProp

*EC_T_BOOL* **emonGetSlaveProp** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_SLAVE_PROP* *pSlaveProp
)

Determines the properties of the slave device.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave ID
- **pSlaveProp** – [out] Slave properties

**Returns**
EC_TRUE if the slave exists, EC_FALSE if no slave matching dwSlaveId can be found

struct **EC_T_SLAVE_PROP**

#### Public Members

*EC_T_WORD* **wStationAddress**
Configured station address or INVALID_FIXED_ADDR

*EC_T_WORD* **wAutoIncAddr**
Configured auto increment address or INVALID_AUTO_INC_ADDR

*EC_T_CHAR* **achName**[MAX_STD_STRLEN]
Configured name of the slave device (NULL terminated string)

**See also:**

*emonGetSlaveId()*

### 9.4.8 emonGetProcessVarInfoNumOf, emonGetProcessVarInfoEx

*EC_T_DWORD* **emonGetProcessVarInfoNumOf** (
*EC_T_DWORD* dwInstanceID,
*EC_T_VAR_DIRECTION* eVarDirection,
*EC_T_VAR_SOURCE* eVarSource,
*EC_T_BOOL* bFixedAddress,
*EC_T_WORD* wSlaveAddress,
*EC_T_DWORD* *pdwProcessVarInfoNumOf
)

Get process variables information.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **eVarDirection** – [in] INPUTs, OUTPUTs, … . See *EC_T_VAR_DIRECTION* .
- **eVarSource** – [in] Slave, Master, … . See *EC_T_VAR_SOURCE* .

- **bFixedAddress** – [in] Use station address if EC_TRUE. Otherwise use AutoInc address.
- **wSlaveAddress** – [in] Slave address according to bFixedAddress
- **pdwProcessVarInfoNumOf** – [out] Process variables count

**Returns**
*EC_E_NOERROR* or error code

*EC_T_DWORD* **emonGetProcessVarInfoEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_VAR_DIRECTION* eVarDirection,
*EC_T_VAR_SOURCE* eVarSource,
*EC_T_BOOL* bFixedAddress,
*EC_T_WORD* wSlaveAddress,
*EC_T_PROCESS_VAR_INFO_EX* *aoVarInfoEx,
*EC_T_DWORD* dwMaxVarInfoCnt,
*EC_T_DWORD* *pdwVarInfoCnt
)

Get process variables information.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **eVarDirection** – [in] INPUTs, OUTPUTs, … . See *EC_T_VAR_DIRECTION* .
- **eVarSource** – [in] Slave, Master, … . See *EC_T_VAR_SOURCE* .
- **bFixedAddress** – [in] Use station address if EC_TRUE. Otherwise use AutoInc address.
- **wSlaveAddress** – [in] Slave address according to bFixedAddress
- **aoVarInfoEx** – [out] The read process variable extended information entries
- **dwMaxVarInfoCnt** – [in] Maximum number of variables that can be stored at aoVarInfoEx
- **pdwVarInfoCnt** – [out] Number process variable entries that have been stored in aoVarInfoEx

**Returns**
*EC_E_NOERROR* or error code

The following example demonstrates how to get all process data variables:

### emonGetProcessVarInfoEx() Example

```
EC_T_DWORD dwProcessVarInfoNumOf = 0;
dwRes = emonGetProcessVarInfoNumOf(dwInstanceId, eVarDirection_All, eVarSource_All,
↪ EC_FALSE, 0, &dwProcessVarInfoNumOf);
/* ... */
EC_T_PROCESS_VAR_INFO_EX* aoVarInfoEx = (EC_T_PROCESS_VAR_INFO_
↪EX*)OsMalloc(dwProcessVarInfoNumOf * sizeof(EC_T_PROCESS_VAR_INFO_EX));
dwRes = emonGetProcessVarInfoEx(dwInstanceId, eVarDirection_All, eVarSource_All,␣
↪EC_FALSE, 0, aoVarInfoEx, dwProcessVarInfoNumOf, EC_NULL);
/* ... */
OsSafeFree(aoVarInfoEx);
```

**EC_T_VAR_DIRECTION**

enum **EC_T_VAR_DIRECTION**
*Values:*

enumerator **eVarDirection_Undefined**
Undefined Direction

enumerator **eVarDirection_INPUT**
INPUTs

enumerator **eVarDirection_OUTPUT**
OUTPUTs

enumerator **eVarDirection_All**
INPUTs and OUTPUTs

enumerator **eVarDirection_BCppDummy**

### EC_T_VAR_SOURCE

enum **EC_T_VAR_SOURCE**
*Values:*

enumerator **eVarSource_Undefined**
Undefined Source

enumerator **eVarSource_All**
Slaves and Master/Monitor/Simulator

enumerator **eVarSource_AllSlaves**
All Slaves

enumerator **eVarSource_Slave**
Slave

enumerator **eVarSource_Master**
Master

enumerator **eVarSource_Monitor**
Monitor

enumerator **eVarSource_Simulator**
Simulator

enumerator **eVarSource_BCppDummy**

### 9.4.9 emonGetSlaveInpVarInfoNumOf

*EC_T_DWORD* **emonGetSlaveInpVarInfoNumOf** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* *pwSlaveInpVarInfoNumOf
)

Gets the number of input variables of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **pwSlaveInpVarInfoNumOf** – [out] Number of found process variable entries

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointer is EC_NULL
- *EC_E_NOTFOUND* if no slave matching bFixedAddressing / wSlaveAddress can be found

**See also:**

- *emonGetSlaveInpVarInfo()*
- *emonGetSlaveInpVarInfoEx()*

### 9.4.10 emonGetSlaveInpVarInfo

*EC_T_DWORD* **emonGetSlaveInpVarInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wNumOfVarsToRead,
*EC_T_PROCESS_VAR_INFO* *pSlaveProcVarInfoEntries,
*EC_T_WORD* *pwReadEntries
)

Gets the process variable information entries of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wNumOfVarsToRead** – [in] Number process variable entries that have been stored in pSlaveProcVarInfoEntries
- **pSlaveProcVarInfoEntries** – [out] The read process variable information entries

- **pwReadEntries** – [out] The number of read process variable information entries

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_PROCESS_VAR_INFO**

### Public Members

*EC_T_CHAR* **szName**[MAX_PROCESS_VAR_NAME_LEN]
[out] Name of the found process variable

*EC_T_WORD* **wDataType**
[out] Data type of the found process variable (according to ETG.1000, section 5). See also EcType.h, DEFTYPE_BOOLEAN.

*EC_T_WORD* **wFixedAddr**
[out] Station address of the slave that is owner of this variable

*EC_T_INT* **nBitSize**
[out] Size in bits of the found process variable

*EC_T_INT* **nBitOffs**
[out] Bit offset in the process data image

*EC_T_BOOL* **bIsInputData**
[out] Determines whether the found process variable is an input variable or an output variable

**MAX_PROCESS_VAR_NAME_LEN**
Maximum length of a process variable name: 71 characters

## 9.4.11 emonGetSlaveInpVarInfoEx

*EC_T_DWORD* **emonGetSlaveInpVarInfoEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wNumOfVarsToRead,
*EC_T_PROCESS_VAR_INFO_EX* *pSlaveProcVarInfoEntriesEx,
*EC_T_WORD* *pwReadEntries
)
Gets the input process variable extended information entries of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wNumOfVarsToRead** – [in] Number process variable entries that have been stored in pSlaveProcVarInfoEntries

- **pSlaveProcVarInfoEntriesEx** – [out] The read process variable extended information entries
- **pwReadEntries** – [out] The number of read process variable information entries

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the output pointer is EC_NULL
- *EC_E_NOTFOUND* if no slave matching bFixedAddressing / wSlaveAddress can be found

struct **EC_T_PROCESS_VAR_INFO_EX**

### Public Members

*EC_T_CHAR* **szName**[MAX_PROCESS_VAR_NAME_LEN_EX]
[out] Name of the found process variable

*EC_T_WORD* **wDataType**
[out] Data type of the found process variable (according to ETG.1000, section 5). See also EcType.h, DEFTYPE_BOOLEAN.

*EC_T_WORD* **wFixedAddr**
[out] Station address of the slave that is owner of this variable

*EC_T_INT* **nBitSize**
[out] Size in bits of the found process variable

*EC_T_INT* **nBitOffs**
[out] Bit offset in the process data image

*EC_T_BOOL* **bIsInputData**
[out] Determines whether the found process variable is an input variable or an output variable

*EC_T_WORD* **wIndex**
[out] Object index

*EC_T_WORD* **wSubIndex**
[out] Object sub index

*EC_T_WORD* **wPdoIndex**
[out] Index of PDO (process data object)

*EC_T_WORD* **wWkcStateDiagOffs**
[out] Bit offset in the diagnostic image (API GetDiagnosisImagePtr)

*EC_T_WORD* **wMasterSyncUnit**
[out] Master Sync Unit ID (ENI: Slave/ProcessData/RxPdo[1..4]@Su, Slave/ProcessData/TxPdo[1..4]@Su, comment at Cyclic/Frame/Cmd)

*EC_T_DWORD* **dwTaskId**
[out] ID of task where process variable is located

EC_T_CYC_COPY_INFO **CopyInfo**
[out] Copy Info if applied to the variable

**MAX_PROCESS_VAR_NAME_LEN_EX**
Maximum length of an extended process variable name: 127 characters

### 9.4.12 emonGetSlaveOutpVarInfoNumOf

*EC_T_DWORD* **emonGetSlaveOutpVarInfoNumOf** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* *pwSlaveOutpVarInfoNumOf
)
Gets the number of output variables of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **pwSlaveOutpVarInfoNumOf** – [out] Number of found process variables

**Returns**
*EC_E_NOERROR* or error code

**See also:**

- *emonGetSlaveOutpVarInfo()*
- *emonGetSlaveOutpVarInfoEx()*

### 9.4.13 emonGetSlaveOutpVarInfo

*EC_T_DWORD* **emonGetSlaveOutpVarInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wNumOfVarsToRead,
*EC_T_PROCESS_VAR_INFO* *pSlaveProcVarInfoEntries,
*EC_T_WORD* *pwReadEntries
)
Gets the output process variable information entries of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing

- **wNumOfVarsToRead** – [in] Number of found process variable entries
- **pSlaveProcVarInfoEntries** – [out] The read process variable information entries
- **pwReadEntries** – [out] The number of read process variable information entries

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO*

### 9.4.14 emonGetSlaveOutpVarInfoEx

*EC_T_DWORD* **emonGetSlaveOutpVarInfoEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wNumOfVarsToRead,
*EC_T_PROCESS_VAR_INFO_EX* *pSlaveProcVarInfoEntriesEx,
*EC_T_WORD* *pwReadEntries
)

Gets the output process variable extended information entries of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wNumOfVarsToRead** – [in] Number of process variable information entries
- **pSlaveProcVarInfoEntriesEx** – [out] The read process extended variable entries
- **pwReadEntries** – [out] The number of read process variable information entries

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO_EX*

### 9.4.15 emonGetSlaveInpVarByObjectEx

*EC_T_DWORD* **emonGetSlaveInpVarByObjectEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wIndex,
*EC_T_WORD* wSubIndex,
*EC_T_PROCESS_VAR_INFO_EX* *pProcessVarInfoEntry
)

Gets the input process variable extended information entry by object index, subindex of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wIndex** – [in] Object index
- **wSubIndex** – [in] Object sub index
- **pProcessVarInfoEntry** – [out] Process variable extended information entry

**Returns**

*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO_EX*

### 9.4.16 emonGetSlaveOutpVarByObjectEx

*EC_T_DWORD* **emonGetSlaveOutpVarByObjectEx** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wIndex,
*EC_T_WORD* wSubIndex,
*EC_T_PROCESS_VAR_INFO_EX* *pProcessVarInfoEntry
)

Gets the input process variable extended information entry by object index, subindex of a specific slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wIndex** – [in] Object index
- **wSubIndex** – [in] Object sub index
- **pProcessVarInfoEntry** – [out] Process variable extended information entry

**Returns**

*EC_E_NOERROR* or error code

**See also:**

*EC_T_PROCESS_VAR_INFO_EX*

### 9.4.17 emonReadSlaveRegister

*EC_T_DWORD* **emonReadSlaveRegister** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_WORD* wRegisterOffset,
*EC_T_BYTE* *pbyData,
*EC_T_WORD* wLen,
*EC_T_DWORD* dwTimeout
)

Reads data from the ESC memory that have so far been transferred to a slave and received by the EC-Monitor.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **wRegisterOffset** – [in] Register offset. I.e. use 0x0130 to read the AL Status register.
- **pbyData** – [out] Buffer receiving transfered data
- **wLen** – [in] Number of bytes to receive
- **dwTimeout** – [in] Timeout [ms]

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range or the command is not supported or the timeout value is set to EC_NOWAIT
- *EC_E_SLAVE_NOT_PRESENT* if the slave is not present
- *EC_E_NOTFOUND* if no slave matching bFixedAddressing / wSlaveAddress can be found
- *EC_E_TIMEOUT* if dwTimeout elapsed during the API call
- *EC_E_BUSY* if another transfer request is already pending or the master or the corresponding slave is currently changing its operational state
- *EC_E_NOTREADY* if the working counter was not set when sending the command (slave may not be connected or did not respond)
- *EC_E_INVALIDSIZE* if the size of the complete command does not fit into a single Ethernet frame. The maximum amount of data to transfer must not exceed 1486 bytes.

### 9.4.18 emonGetCfgSlaveInfo

*EC_T_DWORD* **emonGetCfgSlaveInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_CFG_SLAVE_INFO* *pSlaveInfo
)

Return information about a configured slave from the ENI file.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **pSlaveInfo** – [out] Information about the slave

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_CFG_SLAVE_INFO**

#### Public Members

*EC_T_DWORD* **dwSlaveId**
[out] Slave's ID to bind bus slave and config slave information

*EC_T_CHAR* **abyDeviceName**[ECAT_DEVICE_NAMESIZE]
[out] Slave's configured name (80 Byte) (from ENI file)

*EC_T_DWORD* **dwHCGroupIdx**
[out] Index of Hot Connect group, 0 for mandatory

*EC_T_BOOL* **bIsPresent**
[out] Slave present on bus

*EC_T_BOOL* **bIsHCGroupPresent**
[out] Slave's Hot Connect group present on bus

*EC_T_DWORD* **dwVendorId**
[out] Vendor identification (from ENI file)

*EC_T_DWORD* **dwProductCode**
[out] Product code (from ENI file)

*EC_T_DWORD* **dwRevisionNumber**
[out] Revision number (from ENI file)

*EC_T_DWORD* **dwSerialNumber**
[out] Serial number (from ENI file)

*EC_T_WORD* **wStationAddress**
[out] Slave's configured station address (from ENI file)

*EC_T_WORD* **wAutoIncAddress**
[out] Slave's auto increment address (may differ from ENI file)

*EC_T_DWORD* **dwPdOffsIn**
[out] Process input data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeIn**
[out] Process input data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsOut**
[out] Process output data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeOut**
[out] Process output data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsIn2**
[out] 2nd sync unit process input data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeIn2**
[out] 2nd sync unit process input data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsOut2**
[out] 2nd sync unit process output data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeOut2**
[out] 2nd sync unit process output data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsIn3**
[out] 3rd sync unit process input data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeIn3**
[out] 3rd sync unit process input data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsOut3**
[out] 3rd sync unit process output data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeOut3**
[out] 3rd sync unit process output data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsIn4**
[out] 4th sync unit process input data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeIn4**
[out] 4th sync unit process input data bit size (from ENI file)

*EC_T_DWORD* **dwPdOffsOut4**
[out] 4th sync unit process output data bit offset (from ENI file)

*EC_T_DWORD* **dwPdSizeOut4**
[out] 4th sync unit process output data bit size (from ENI file)

*EC_T_DWORD* **dwMbxSupportedProtocols**
[out] Mailbox protocols supported by the slave (from ENI file). Combination of *Supported mailbox protocols* flags.

*EC_T_DWORD* **dwMbxOutSize**
[out] Mailbox output byte size (from ENI file)

*EC_T_DWORD* **dwMbxInSize**
[out] Mailbox input byte size (from ENI file)

*EC_T_DWORD* **dwMbxOutSize2**
[out] Bootstrap mailbox output byte size (from ENI file)

*EC_T_DWORD* **dwMbxInSize2**
[out] Bootstrap mailbox input byte size (from ENI file)

*EC_T_BOOL* **bDcSupport**
[out] Slave supports DC (from ENI file)

*EC_T_WORD* **wNumProcessVarsInp**
[out] Number of input process data variables (from ENI file)

*EC_T_WORD* **wNumProcessVarsOutp**
[out] Number of output process data variables (from ENI file)

*EC_T_WORD* **wPrevStationAddress**
[out] Station address of the previous slave (from ENI file)

*EC_T_WORD* **wPrevPort**
[out] Connected port of the previous slave (from ENI file)

*EC_T_WORD* **wIdentifyAdo**
[out] ADO used for identification command (from ENI file)

*EC_T_WORD* **wIdentifyData**
[out] Identification value to be validated (from ENI file)

*EC_T_BYTE* **byPortDescriptor**
[out] Port descriptor (ESC register 0x0007) (from ENI file)

*EC_T_WORD* **wWkcStateDiagOffsIn**[EC_CFG_SLAVE_PD_SECTIONS]
[out] Offset of WkcState bit in diagnosis image (ENI: ProcessData/Recv[1..4]/BitStart): 0xFFFFFFFF = offset not available. WkcState bit values: 0 = Data valid, 1 = Data invalid.

*EC_T_WORD* **wWkcStateDiagOffsOut**[EC_CFG_SLAVE_PD_SECTIONS]
[out] Offset of WkcState bit in diagnosis image (ENI: ProcessData/Send[1..4]/BitStart): 0xFFFFFFFF = offset not available. WkcState bit values: 0 = Data valid, 1 = Data invalid.

*EC_T_WORD* **awMasterSyncUnitIn**[EC_CFG_SLAVE_PD_SECTIONS]
[out] Sync Unit (ENI: ProcessData/TxPdo[1..4]@Su)

*EC_T_WORD* **awMasterSyncUnitOut**[EC_CFG_SLAVE_PD_SECTIONS]
[out] Sync Unit (ENI: ProcessData/RxPdo[1..4]@Su)

*EC_T_BOOL* **bDisabled**
[out] Slave disabled by API SetSlaveDisabled / SetSlavesDisabled.

*EC_T_BOOL* **bDisconnected**
[out] Slave disconnected by API SetSlaveDisconnected / SetSlavesDisconnected.

*EC_T_BOOL* **bExtended**
[out] Slave generated by API ConfigExtend

*EC_T_BOOL* **bDcReferenceClock**
[out] Slave is reference clock (from ENI file)

*EC_T_BOOL* **bDcPotentialRefClock**
[out] Slave can be used as a reference clock (from ENI file)

*EC_T_DWORD* **dwDcCycleTime0**
[out] Cycle time of Sync0 event [ns] (from ENI file)

*EC_T_DWORD* **dwDcCycleTime1**
[out] Calculated value dwDcCycleTime1 [ns] = Cycle time of Sync1 event - Cycle time of Sync1 event + Shift time of Sync0 event (from ENI file)

*EC_T_INT* **nDcShiftTime**
[out] Shift time of Sync0 event [ns] (from ENI file)

**Flags EC_MBX_PROTOCOL_**

**EC_MBX_PROTOCOL_AOE**

**EC_MBX_PROTOCOL_EOE**

**EC_MBX_PROTOCOL_COE**

**EC_MBX_PROTOCOL_FOE**

**EC_MBX_PROTOCOL_SOE**

**EC_MBX_PROTOCOL_VOE**

### 9.4.19 emonGetCfgSlaveSmInfo

*EC_T_DWORD* **emonGetCfgSlaveSmInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_CFG_SLAVE_SM_INFO* *pSlaveSmInfo
)

Return SyncManager information of a configured slave from the ENI file.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **pSlaveSmInfo** – [out] Information about the slave.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_CFG_SLAVE_SM_ENTRY**

#### Public Members

*EC_T_WORD* **wPhysAddr**
[out] ESC (0x800 + y * 8)

*EC_T_WORD* **wLength**
[out] ESC (0x802 + y * 8)

*EC_T_BYTE* **byOpMode**
[out] Bits 0..1 ESC (0x804 + y * 8)

*EC_T_BYTE* **byDirection**
[out] Bits 2..3 ESC (0x804 + y * 8)

*EC_T_DWORD* **dwPdBitOffs**
[out] Process input data bit offset (from ENI file)

*EC_T_DWORD* **dwPdBitSize**
[out] Process input data bit size (from ENI file)

*EC_T_WORD* **wWkcStateDiagBitOffs**
[out] Offset of WkcState bit in diagnosis image

*EC_T_WORD* **wMasterSyncUnit**
[out] Sync Unit (ENI: ProcessData/TxPdo[1..4]@Su)

struct **EC_T_CFG_SLAVE_SM_INFO**

#### Public Members

*EC_T_DWORD* **dwSlaveId**
[out] Slave ID

*EC_T_DWORD* **dwSmInfoNumOf**
[out] Number of available sync managers

*EC_T_CFG_SLAVE_SM_ENTRY* **aoSmInfos**[ECREG_SYNCMANAGER_MAX_NUMOF]
[out] Sync managers info

#### Example

```
/* get information about slave's sync managers configured in ENI file */
EC_T_CFG_SLAVE_SM_INFO oSlaveSmInfo;
OsMemset(&oSlaveSmInfo, 0, sizeof(EC_T_CFG_SLAVE_SM_INFO));
dwRes = emonGetCfgSlaveSmInfo(dwInstanceId, EC_TRUE, 1001, &oSlaveSmInfo);
```

### 9.4.20 emonGetBusSlaveInfo

*EC_T_DWORD* **emonGetBusSlaveInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bFixedAddressing,
*EC_T_WORD* wSlaveAddress,
*EC_T_BUS_SLAVE_INFO* *pSlaveInfo
)
Return information about a slave connected to the EtherCAT bus.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bFixedAddressing** – [in] EC_TRUE: use station address, EC_FALSE: use AutoInc address
- **wSlaveAddress** – [in] Slave address according bFixedAddressing
- **pSlaveInfo** – [out] Information from the slave

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range
- *EC_E_NOTFOUND* if no slave matching bFixedAddressing / wSlaveAddress can be found

struct **EC_T_BUS_SLAVE_INFO**

### Public Members

*EC_T_DWORD* **dwSlaveId**
[out] The slave's ID to bind bus slave and config slave information

*EC_T_DWORD* **adwPortSlaveIds**[ESC_PORT_COUNT]
[out] The slave's ID of the slaves connected to ports. See *Port slave ID's*.

*EC_T_WORD* **wPortState**

[out] Port link state. Format: wwww xxxx yyyy zzzz (each nibble : port 3210)

wwww : Signal detected 1=yes, 0=no

xxxx : Loop closed 1=yes, 0=no

yyyy : Link established 1=yes, 0=no

zzzz : Slave connected 1=yes, 0=no (zzzz = logical result of w,x,y)

*EC_T_WORD* **wAutoIncAddress**
[out] The slave's auto increment address

*EC_T_BOOL* **bDcSupport**
[out] Slave supports DC (Bus Topology Scan)

*EC_T_BOOL* **bDc64Support**
[out] Slave supports 64 Bit DC (Bus Topology Scan)

*EC_T_DWORD* **dwVendorId**
[out] Vendor Identification stored in the EEPROM at offset 0x0008

*EC_T_DWORD* **dwProductCode**
[out] Product Code stored in the EEPROM at offset 0x000A

*EC_T_DWORD* **dwRevisionNumber**
[out] Revision number stored in the EEPROM at offset 0x000C

*EC_T_DWORD* **dwSerialNumber**
[out] Serial number stored in the EEPROM at offset 0x000E

*EC_T_BYTE* **byESCType**
[out] Type of ESC (Value of slave ESC register 0x0000)

*EC_T_BYTE* **byESCRevision**
[out] Revision number of ESC (Value of slave ESC register 0x0001)

*EC_T_WORD* **wESCBuild**
[out] Build number of ESC (Value of slave ESC register 0x0002)

*EC_T_BYTE* **byPortDescriptor**
[out] Port descriptor (Value of slave ESC register 0x0007)

*EC_T_WORD* **wFeaturesSupported**
[out] Features supported (Value of slave ESC register 0x0008)

*EC_T_WORD* **wStationAddress**
[out] The slave's station address (Value of slave ESC register 0x0010)

*EC_T_WORD* **wAliasAddress**
[out] The slave's alias address (Value of slave ESC register 0x0012)

*EC_T_WORD* **wAlStatus**
[out] AL status (Value of slave ESC register 0x0130)

*EC_T_WORD* **wAlStatusCode**
[out] AL status code. (Value of slave ESC register 0x0134 during last error acknowledge). This value is reset after a slave state change.

*EC_T_DWORD* **dwSystemTimeDifference**
[out] System time difference. (Value of slave ESC register 0x092C)

*EC_T_WORD* **wMbxSupportedProtocols**
[out] Supported Mailbox Protocols stored in the EEPROM at offset 0x001C

*EC_T_WORD* **wDlStatus**
[out] DL status (Value of slave ESC register 0x0110)

*EC_T_WORD* **wPrevPort**
[out] Connected port of the previous slave

*EC_T_WORD* **wIdentifyData**
[out] Last read identification value see *EC_T_CFG_SLAVE_INFO.wIdentifyAdo*

*EC_T_BOOL* **bLineCrossed**
[out] Line crossed was detected at this slave

*EC_T_DWORD* **dwSlaveDelay**
[out] Delay behind slave [ns]. This value is only valid if a DC configuration is used.

*EC_T_DWORD* **dwPropagDelay**
[out] Propagation delay [ns]. ESC register 0x0928.This value is only valid if a DC configuration is used.

*EC_T_BOOL* **bIsRefClock**
[out] Slave is reference clock

*EC_T_BOOL* **bIsDeviceEmulation**
[out] Slave without Firmware. ESC register 0x0141, enabled by EEPROM offset 0x0000.8.

*EC_T_WORD* **wLineCrossedFlags**
[out] Combination of *Line crossed flags*

*EC_T_DWORD* **dwCyclicWkcErrorCnt**
[out] Counter for Cyclic WC Error

*EC_T_DWORD* **dwSlaveAbsentCnt**
[out] Counter for Absent/Not Present Slaves

*EC_T_DWORD* **dwUnexpectedStateCnt**
[out] Counter for Abnormal State Change

**Port SubDevice ID's**

**MASTER_SLAVE_ID**

**SIMULATOR_SLAVE_ID**

**MASTER_RED_SLAVE_ID**

**EL9010_SLAVE_ID**

**FRAMELOSS_SLAVE_ID**

**JUNCTION_RED_FLAG**

**Flags EC_LINECROSSED_**

**EC_LINECROSSED_NOT_CONNECTED_PORTA**

**EC_LINECROSSED_UNEXPECTED_INPUT_PORT**

**EC_LINECROSSED_UNEXPECTED_JUNCTION_RED**

**EC_LINECROSSED_UNRESOLVED_PORT_CONNECTION**

**EC_LINECROSSED_HIDDEN_SLAVE_CONNECTED**

**EC_LINECROSSED_PHYSIC_MISMATCH**

**EC_LINECROSSED_INVALID_PORT_CONNECTION**

## 9.5 Diagnosis

### 9.5.1 emonGetDiagnosisImagePtr

*EC_T_BYTE* ***emonGetDiagnosisImagePtr** (*EC_T_DWORD* dwInstanceID)

Gets the diagnosis image pointer.

**Parameters**

**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**

Diagnosis image pointer

**See also:**

- *EC_T_CFG_SLAVE_INFO::wWkcStateDiagOffsIn*
- *EC_T_CFG_SLAVE_INFO::wWkcStateDiagOffsOut*

### 9.5.2 emonGetDiagnosisImageSize

*EC_T_DWORD* **emonGetDiagnosisImageSize** (*EC_T_DWORD* dwInstanceID)
Gets the diagnosis image size.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
Diagnosis image size

**See also:**

- *EC_T_CFG_SLAVE_INFO::wWkcStateDiagOffsIn*
- *EC_T_CFG_SLAVE_INFO::wWkcStateDiagOffsOut*

### 9.5.3 emonGetMasterSyncUnitInfoNumOf

*EC_T_DWORD* **emonGetMasterSyncUnitInfoNumOf** (*EC_T_DWORD* dwInstanceID)
Get number of Master Sync Units info entries.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
Number of Master Sync Units info entries

### 9.5.4 emonGetMasterSyncUnitInfo

*EC_T_DWORD* **emonGetMasterSyncUnitInfo** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* wMsuId,
*EC_T_MSU_INFO* *pMsuInfo
)
Get information about a specific Master Sync Unit.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **wMsuId** – [in] Master Sync Unit to get the information from
- **pMsuInfo** – [out] Pointer to an *EC_T_MSU_INFO* structure receiving the Master Sync Unit information

**Returns**
*EC_E_NOERROR* or error code

`MSU_ID_ALL_INFO_ENTRIES` retrieves the information from all MainDevice sync units at once. The application must ensure that pMsuInfo is capable for all entries.

struct **EC_T_MSU_INFO**

#### Public Members

*EC_T_WORD* **wMsuId**
[out] Master Sync Unit ID (ENI: Slave/ProcessData/RxPdo[1..4]@Su, Slave/ProcessData/TxPdo[1..4]@Su, comment at Cyclic/Frame/Cmd)

*EC_T_DWORD* **dwBitOffsIn**
[out] Process Data Image INPUTs bit offset

*EC_T_DWORD* **dwBitSizeIn**
[out] Process Data Image INPUTs bit length

*EC_T_DWORD* **dwBitOffsOut**
[out] Process Data Image OUTPUTs bit offset

*EC_T_DWORD* **dwBitSizeOut**
[out] Process Data Image OUTPUTs bit length

*EC_T_WORD* **wWkcStateDiagOffsIn**
[out] INPUTs WkcState bit offset in Diagnosis Image. (Bit values: 0 = Process Data valid, 1 = Process Data invalid)

*EC_T_WORD* **wWkcStateDiagOffsOut**
[out] OUTPUTs WkcState bit offset in Diagnosis Image. (Bit values: 0 = Process Data valid, 1 = Process Data invalid)

*EC_T_DWORD* **adwReserved**[16]
reserved

**See also:**

*emonGetMasterSyncUnitInfoNumOf()*

### 9.5.5 emonGetSlaveStatistics

*EC_T_DWORD* **emonGetSlaveStatistics** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_SLVSTATISTICS_DESC* *pSlaveStatisticsDesc
)
Get Slave's statistics counter.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave id
- **pSlaveStatisticsDesc** – [out] Pointer to structure *EC_T_SLVSTATISTICS_DESC*

**Returns**
*EC_E_NOERROR* or error code

**See also:**

- *emonIoCtl - EC_IOCTL_GET_SLVSTATISTICS*
- *emonGetSlaveId()*

- *emonIoCtl()*

### 9.5.6 emonBadConnectionsDetect

*EC_T_DWORD* **emonBadConnectionsDetect** (
*EC_T_DWORD* dwInstanceID,
*EC_T_BOOL* bRefreshSlaveStatistics,
*EC_T_DWORD* dwTimeout
)

Detects bad connections.

Analyzes the slave ESC error counters:

- Invalid Frame Counter (0x0300),
- RX Error Counter (0x0301),
- Lost Link Counter (0x0310),

whether there is a problem in the area PHY - connector - cable - connector - PHY. If one of the above error counters shows a value not equal to zero, an EC_NOTIFY_BAD_CONNECTION is generated, which contains the exact position of the faulty connection.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **bRefreshSlaveStatistics** – [in] Not supported by EC-Monitor, set to EC_FALSE
- **dwTimeout** – [in] Timeout [ms]. Not currently used by EC-Monitor, but may not be EC_NOWAIT!

**Returns**
*EC_E_NOERROR* or error code

### 9.5.7 emonIoCtl - EC_IOCTL_GET_SLVSTATISTICS

**EC_IOCTL_GET_SLVSTATISTICS**
Get Slave's statistics counter. Counters are collected on a regular basis (default: off) and show errors on Ethernet layer.

**Parameters**

- **pbyInBuf** – [in] Pointer to an EC_T_DWORD type variable containing the slave id
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Pointer to struct *EC_T_SLVSTATISTICS_DESC*
- **dwOutBufSize** – [in] Size of the output buffer provided at pbyOutBuf in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_SLVSTATISTICS_DESC**

#### Public Members

*EC_T_BYTE* **abyInvalidFrameCnt**[ESC_PORT_COUNT]
[out] Invalid Frame Counters per Slave Port

*EC_T_BYTE* **abyRxErrorCnt**[ESC_PORT_COUNT]
[out] RX Error Counters per Slave Port

*EC_T_BYTE* **abyFwdRxErrorCnt**[ESC_PORT_COUNT]
[out] Forwarded RX Error Counters per Slave Port

*EC_T_BYTE* **byProcessingUnitErrorCnt**
[out] Processing Unit Error Counter

*EC_T_BYTE* **byPdiErrorCnt**
[out] PDI Error Counter

*EC_T_WORD* **wAlStatusCode**
[out] AL Status Code

*EC_T_BYTE* **abyLostLinkCnt**[ESC_PORT_COUNT]
[out] Lost Link Counters per Slave Port

*EC_T_UINT64* **qwReadTime**
[out] Timestamp of the last read [ns]

*EC_T_UINT64* **qwChangeTime**
[out] Timestamp of the last counter change [ns]

**See also:**

*emonIoCtl()*

### 9.5.8 emonClearSlaveStatistics

*EC_T_DWORD* **emonClearSlaveStatistics** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId
)
Clears all error registers of a slave.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave Id, INVALID_SLAVE_ID clears all slaves

**Returns**
*EC_E_NOERROR* or error code

---

**Note:** Only the buffered error register values are deleted. The actual counters on the SubDevices remain unchanged.

---

**See also:**

*emonGetSlaveId()*

### 9.5.9 emonIoCtl - EC_IOCTL_CLR_SLVSTATISTICS

**EC_IOCTL_CLR_SLVSTATISTICS**
Clear all error registers in all slaves.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

**See also:**

*emonIoCtl()*

### 9.5.10 emonIoCtl - EC_IOCTL_SB_STATUS_GET

**EC_IOCTL_SB_STATUS_GET**
This call will get the status of the last bus scan.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Pointer to *EC_T_SB_STATUS_NTFY_DESC*
- **dwOutBufSize** – [in] Size of the output buffer in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

**See also:**

- *emonNotify - EC_NOTIFY_SB_STATUS*
- *emonIoCtl()*

## 9.6 Real-time Ethernet Driver Control Interface

### 9.6.1 emonIoCtl - EC_IOCTL_ISLINK_CONNECTED

**EC_IOCTL_ISLINK_CONNECTED**
Determine whether the link between the stack and the first slave is connected.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Pointer to EC_T_DWORD. If value is EC_TRUE link is connected, if EC_FALSE it is not.
- **dwOutBufSize** – [in] Size of the output buffer in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_LINK_CONNECTED_INFO**

#### Public Members

*EC_T_BOOL* **bConnected**
[out] MAIN or RED link detected

*EC_T_BOOL* **bSendEnabled**
[out] Send enabled on MAIN or RED

*EC_T_BOOL* **bMainConnected**
[out] MAIN link detected

*EC_T_BOOL* **bMainMasked**
[out] MAIN link not used for sending, because topology changed delay not elapsed yet

*EC_T_BOOL* **bRedConnected**
[out] RED link detected

*EC_T_BOOL* **bRedMasked**
[out] RED link not used for sending, because topology changed delay not elapsed yet

**See also:**

*emonIoCtl()*

### 9.6.2 emonIoCtl - EC_IOCTL_GET_LINKLAYER_MODE

**EC_IOCTL_GET_LINKLAYER_MODE**
This call allows the application to determine whether the Real-time Ethernet Driver is currently running in polling or in interrupt mode.

**Parameters**

- **pbyInBuf** – [in] Should be set to EC_NULL
- **dwInBufSize** – [in] Should be set to 0
- **pbyOutBuf** – [out] Pointer to struct *EC_T_LINKLAYER_MODE_DESC*
- **dwOutBufSize** – [in] Size of the output buffer in bytes

- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_LINKLAYER_MODE_DESC**

#### Public Members

EC_T_LINKMODE **eLinkMode**
[out] Operation mode of main interface

EC_T_LINKMODE **eLinkModeRed**
[out] Operation mode of redundancy interface

**See also:**

*emonIoCtl()*

### 9.6.3 emonIoCtl - EC_LINKIOCTL...

The generic control interface provides access to the main network adapter when adding `EC_IOCTL_LINKLAYER_MAIN` to the `EC_LINKIOCTL` parameter at dwCode.

```
EC_T_DWORD dwCode = (EC_IOCTL_LINKLAYER_MAIN | EC_LINKIOCTL_GET_ETHERNET_ADDRESS);
```

### 9.6.4 emonIoCtl - EC_LINKIOCTL_GET_ETHERNET_ADDRESS

Provides MAC addresses of main or red line.

**emonIoCtl - EC_LINKIOCTL_GET_ETHERNET_ADDRESS**

**Parameter**

- `pbyInBuf`: [in] Should be set to EC_NULL
- `dwInBufSize`: [in] Should be set to 0
- `pbyOutBuf`: [out] Pointer to MAC address buffer (6 bytes)
- `dwOutBufSize`: [in] Size of the output buffer in bytes (at least 6)
- `pdwNumOutData`: [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**See also:**

*emonIoCtl()*

### 9.6.5 emonIoCtl - EC_LINKIOCTL_GET_SPEED

**emonIoCtl - EC_LINKIOCTL_GET_SPEED**

**Parameter**

- `pbyInBuf`: [in] Should be set to EC_NULL
- `dwInBufSize`: [in] Should be set to 0
- `pbyOutBuf`: [out] Pointer to EC_T_DWORD. Set by Real-time Ethernet Driver to 10/100/1000.
- `dwOutBufSize`: [in] Size of the output buffer in bytes
- `pdwNumOutData`: [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**See also:**

*`emonIoCtl()`*

## 9.7 EtherCAT® Mailbox Transfer

To be able to initiate a mailbox transfer the client has to create a mailbox transfer object first. This mailbox transfer object also contains the memory where the data to be transferred is stored. The one client that initiated the mailbox transfer will be notified about a mailbox transfer completion by the `emonNotify()` callback function.

To be able to identify the transfer which was completed the client has to assign a unique transfer identifier for each mailbox transfer. The mailbox transfer object can only be used for one single mailbox transfer. If multiple transfers shall be initiated in parallel the client has to create one transfer object for each. The transfer object can be re-used after mailbox transfer completion.

Typical mailbox transfer sequence:

1. Record a mailbox transfer.
2. **Create a transfer object (for example an SDO download transfer object).**

```
MbxTferDesc.dwMaxDataLen = 10

MbxTferDesc.pbyMbxTferDescData = (EC_T_PBYTE)OsMalloc(MbxTferDesc.
↪dwMaxDataLen)

pMbxTfer = emonMbxTferCreate(&MbxTferDesc)
    state of the transfer object = Idle
```

3. **Set the location to write the transferred data to, determine the transfer ID, store the client ID in the object and initiate the transfer (e.g. a SDO upload). A transfer may only be initiated if the state of the transfer object is Idle.**

```
pMbxTfer->dwDataLen = MbxTferDesc.dwMaxDataLen;

pMbxTfer->pbyMbxTferData = MbxTferDesc.pbyMbxTferDescData

pMbxTfer->dwTferId = 1;

pMbxTfer->dwClntId = dwClntId;


dwResult = emonCoeSdoUplodadReq(pMbxTfer, dwSlaveId, wObIndex, ...);
    state of the transfer object = Pend or TferReqError
```

The state will then be set to Pend to indicate that this mailbox transfer object currently is in use and the transfer is not completed. If the mailbox transfer cannot be initiated the MainDevice will set the object into the state TferReqError - in such cases the client is responsible to set the state back into Idle.

4. **If the mailbox transfer is completed the notification callback function of the corresponding client ( `emonNotify()` ) will be called with a pointer to the mailbox transfer object. The state of the transfer object is set to TferDone prior to calling `emonNotify()`.**

```
if( dwResult != EC_E_NOERROR ) { ... }

emonNotify( EC_NOTIFY_MBOXRCV, pParms )
    state of the transfer object = TferDone
```

5. **In case of errors the appropriate error handling has to be executed. The application must set the transfer object state to Idle.**

```
if( pMbxTfer->dwErrorCode != EC_E_NOERROR ) { ... }
    In emonNotify: application may set transfer object state to Idle
```

6. **Delete the transfer object. Alternatively this object can be used for the next transfer.**

```
emonMbxTferDelete(pMbxTfer);
```

### 9.7.1 Mailbox transfer object states

The following states exist for a mailbox transfer object:

enum **`EC_T_MBXTFER_STATUS`**
*Values:*

enumerator **`eMbxTferStatus_Idle`**
Mailbox transfer object not in use

enumerator **`eMbxTferStatus_Pend`**
Mailbox transfer in process

enumerator **`eMbxTferStatus_TferDone`**
Mailbox transfer completed

enumerator **`eMbxTferStatus_TferReqError`**
Mailbox transfer request error

enumerator **`eMbxTferStatus_TferWaitingForContinue`**
Mailbox transfer waiting for continue, object owned by application

A mailbox transfer will be processed by the monitor independently from the client's timeout setting. Some types of mailbox transfers can be cancelled by the client, e.g. if the client's timeout elapsed.

After completion of the mailbox transfer (with timeout) the client may finally set the transfer object into the state *`EC_T_MBXTFER_STATUS::eMbxTferStatus_Idle`*. New mailbox transfers can only be requested if the object is in the state *`EC_T_MBXTFER_STATUS::eMbxTferStatus_Idle`*.

### 9.7.2 emonMbxTferCreate

*EC_T_MBXTFER* ***emonMbxTferCreate*** (
*EC_T_DWORD* dwInstanceID,
*EC_T_MBXTFER_DESC* *pMbxTferDesc
)

Creates a mailbox transfer object.

While a mailbox transfer is in process the related transfer object and the corresponding memory may not be accessed. After a mailbox transfer completion the object may be used for the next transfer. The mailbox transfer object has to be deleted by calling ecatMbxTferDelete if it is not needed any more.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMbxTferDesc** – [in] Pointer to the mailbox transfer descriptor. Determines details of the mailbox transfer.

**Returns**

- Pointer to the created mailbox transfer object if successful
- EC_NULL on error (No memory left)

struct **EC_T_MBXTFER_DESC**

#### Public Members

*EC_T_DWORD* **dwMaxDataLen**
Maximum amount of data bytes that shall be transferred using this object. A mailbox transfer type without data transfer will ignore this parameter.

*EC_T_BYTE* ***pbyMbxTferDescData**
Pointer to byte stream carrying in and out data of mailbox content

struct **EC_T_MBXTFER**

#### Public Members

*EC_T_DWORD* **dwClntId**
[] Client ID

*EC_T_MBXTFER_DESC* **MbxTferDesc**
[out] Mailbox transfer descriptor. All elements of pMbxTferDesc will be stored here.

*EC_T_MBXTFER_TYPE* **eMbxTferType**
[] This type of information is written to the Mailbox Transfer Object by the last call to a mailbox command function. It may be used as information, and is required to fan out consecutive notifications. This value is only valid until the next relevant mailbox API call, where this value may be overwritten.

*EC_T_DWORD* **dwDataLen**
[] Amount of data bytes for the next mailbox download transfer. If the mailbox transfer does not transfer data to the slave this parameter will be ignored. This element has to be set to an appropriate value every time prior to initiating a new download request. When either a download or upload transfer is completed (emNotify) this value will contain the amount of data that was actually transferred.

*EC_T_BYTE* ***pbyMbxTferData**
[in/out] Pointer to data. In case of a download transfer the client has to store the data in this location. In case of an upload transfer this element points to the received data. Access to data that was uploaded from a slave is only valid within the notification function because the buffer will be re-used by the master. These data have to be copied into a separate buffer in case it has to be used later by the client.

*EC_T_MBXTFER_STATUS* **eTferStatus**
[out] Transfer state. After a new transfer object is created the state will be set to eMbxTferStatus_Idle.

*EC_T_DWORD* **dwErrorCode**
[out] Error code of a mailbox transfer that was terminated with error

*EC_T_DWORD* **dwTferId**
[] Transfer ID. For every new mailbox transfer a unique ID has to be assigned. This ID can be used after mailbox transfer completion to identify the transfer.

*EC_T_MBX_DATA* **MbxData**
[] Mailbox data. This element contains mailbox transfer data, e.g. the CoE object dictionary list.

enum **EC_T_MBXTFER_TYPE**
*Values:*

enumerator **eMbxTferType_COE_SDO_DOWNLOAD**
CoE SDO download

enumerator **eMbxTferType_COE_SDO_UPLOAD**
CoE SDO upload

enumerator **eMbxTferType_COE_GETODLIST**
CoE Get object dictionary list

enumerator **eMbxTferType_COE_GETOBDESC**
CoE Get object description

enumerator **eMbxTferType_COE_GETENTRYDESC**
CoE Get object entry description

enumerator **eMbxTferType_COE_EMERGENCY**
CoE emergency request

enumerator **eMbxTferType_COE_RX_PDO**
CoE RxPDO

enumerator **eMbxTferType_FOE_FILE_UPLOAD**
FoE upload

enumerator **eMbxTferType_FOE_FILE_DOWNLOAD**
FoE download

enumerator **eMbxTferType_SOE_READREQUEST**
SoE read request

enumerator **eMbxTferType_SOE_READRESPONSE**
SoE read response

enumerator **eMbxTferType_SOE_WRITEREQUEST**
SoE write request

enumerator **eMbxTferType_SOE_WRITERESPONSE**
SoE write response

enumerator **eMbxTferType_SOE_NOTIFICATION**
SoE notification

enumerator **eMbxTferType_SOE_EMERGENCY**
SoE emergency

enumerator **eMbxTferType_VOE_MBX_READ**
VoE read

enumerator **eMbxTferType_VOE_MBX_WRITE**
VoE write

enumerator **eMbxTferType_AOE_READ**
AoE read

enumerator **eMbxTferType_AOE_WRITE**
AoE write

enumerator **eMbxTferType_AOE_READWRITE**
AoE read/write

enumerator **eMbxTferType_AOE_WRITECONTROL**
AoE write control

enumerator **eMbxTferType_RAWMBX**
Raw mbx

enumerator **eMbxTferType_FOE_SEG_DOWNLOAD**
FoE segmented download

enumerator **eMbxTferType_FOE_SEG_UPLOAD**
FoE segmented upload

enumerator **eMbxTferType_S2SMBX**
S2S mbx

enumerator **eMbxTferType_FOE_UPLOAD_REQ**
FoE upload request

enumerator **eMbxTferType_FOE_DOWNLOAD_REQ**
FoE download request

enumerator **eMbxTferType_EOE_SEND_FRAME**
EoE send frame

enumerator **eMbxTferType_EOE_RECEIVE_FRAME**
EoE receive frame

enumerator **eMbxTferType_EOE_SET_IP**
EoE set IP address

union **EC_T_MBX_DATA**
*#include <EcInterfaceCommon.h>*

### Public Members

EC_T_AOE_CMD_RESPONSE **AoE_Response**
AoE

*EC_T_MBX_DATA_COE* **CoE**
CoE

*EC_T_COE_ODLIST* **CoE_ODList**
CoE Object Dictionary list

EC_T_COE_OBDESC **CoE_ObDesc**
CoE object description

*EC_T_COE_ENTRYDESC* **CoE_EntryDesc**
CoE entry description

*EC_T_COE_EMERGENCY* **CoE_Emergency**
CoE emergency data

EC_T_MBX_DATA_COE_INITCMD **CoE_InitCmd**
CoE InitCmd

*EC_T_MBX_DATA_FOE* **FoE**
FoE

*EC_T_MBX_DATA_FOE_REQ* **FoE_Request**
FoE request

EC_T_MBX_DATA_SOE **SoE**
SoE

EC_T_SOE_NOTIFICATION **SoE_Notification**
SoE notification request

EC_T_SOE_EMERGENCY **SoE_Emergency**
SoE emergency request

### 9.7.3 emonMbxTferAbort

*EC_T_DWORD* **emonMbxTferAbort** (*EC_T_DWORD* dwInstanceID, *EC_T_MBXTFER* *pMbxTfer)
Abort a running mailbox transfer.

This function may not be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMbxTfer** – [in] Mailbox transfer object created with emMbxTferCreate

**Returns**
*EC_E_NOERROR* if successful

Currently only supported for FoE Transfer, CoE Download and CoE Upload.

### 9.7.4 emonMbxTferDelete

EC_T_VOID **emonMbxTferDelete** (*EC_T_DWORD* dwInstanceID, *EC_T_MBXTFER* *pMbxTfer)
Deletes a mailbox transfer object.

A transfer object may only be deleted if it is in the Idle state.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMbxTfer** – [in] Mailbox transfer object created with emMbxTferCreate

**Returns**
*EC_E_NOERROR* or error code

### 9.7.5 emonNotify - EC_NOTIFY_MBOXRCV

Indicates a mailbox transfer completion.

**emonNotify - EC_NOTIFY_MBOXRCV**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The element *EC_T_MBXTFER::dwClntId* contains the corresponding ID of the client that is notified, the corresponding transfer ID can be found in *EC_T_MBXTFER::dwTferId*. The transfer result is stored in *EC_T_MBXTFER::dwErrorCode*.

On error *EC_T_MBXTFER::eTferStatus* is *eMbxTferStatus_TferReqError*, on success *eMbxTferStatus_TferDone*. In order to reuse the transfer object the application must set it back to *eMbxTferStatus_Idle*.

The *EC_T_MBXTFER::eMbxTferType* element determines the mailbox transfer type (e.g. *eMbxTferType_COE_SDO_DOWNLOAD* for a completion of a CoE SDO download transfer).

### 9.7.6 emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR

Indicates a WKC error during a mailbox write. Detailed error information is stored in structure *EC_T_WKCERR_DESC* which is part of *EC_T_ERROR_NOTIFICATION_DESC*.

**emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_ERROR_NOTIFICATION_DESC
- `dwInBufSize`: [in] Size of the error description provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

### 9.7.7 emonNotify - EC_NOTIFY_AOE_MBXSND_WKC_ERROR

See *emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR*

### 9.7.8 emonNotify - EC_NOTIFY_EOE_MBXSND_WKC_ERROR

See *emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR*

### 9.7.9 emonNotify - EC_NOTIFY_FOE_MBXSND_WKC_ERROR

See *emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR*

### 9.7.10 emonNotify - EC_NOTIFY_SOE_MBXSND_WKC_ERROR

See *emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR*

### 9.7.11 emonNotify - EC_NOTIFY_VOE_MBXSND_WKC_ERROR

See *emonNotify - EC_NOTIFY_COE_MBXSND_WKC_ERROR*

## 9.8 CAN application protocol over EtherCAT® (CoE)

The EC-Monitor can forward CoE transfers to the application in real time via the notifications *emonNotify - eMbxTferType_COE_SDO_DOWNLOAD*, *emonNotify - eMbxTferType_COE_SDO_UPLOAD* and *emonNotify - eMbxTferType_COE_EMERGENCY*.

There is also the option of storing the recorded data from the CoE transfers in an internal object dictionary. This object dictionary is structured analogously to that from the SubDevices and can be read out via the functions *emonCoeSdoUpload()* / *emonCoeSdoUploadReq()* and *emonCoeGetODListReq()*.

The notifications for CoE can be deactivated using the *EC_T_MBX_PARMS_COE::bDisableNotifications* parameter if they are not required or to save computing time. In order to reduce memory consumption, the internal memory for the CoE data can be deactivated using the *EC_T_MBX_PARMS_COE::bDisableODStorage* parameter.

If both parameters *EC_T_MBX_PARMS_COE::bDisableNotifications* and *EC_T_MBX_PARMS_COE::bDisableODStorage* are set, the CoE monitoring is completely deactivated.

### 9.8.1 emonNotify - eMbxTferType_COE_SDO_DOWNLOAD

SDO download transfer completion.

**emonNotify - eMbxTferType_COE_SDO_DOWNLOAD**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The transfer result is stored in *EC_T_MBXTFER::dwErrorCode*. The requested parameters stored in element *EC_T_MBX_DATA::CoE* of type *EC_T_MBX_DATA_COE* are part of *EC_T_MBXTFER::MbxData*. The SDO data stored in *EC_T_MBXTFER::pbyMbxTferData*.

struct **EC_T_MBX_DATA_COE**

**Public Members**

*EC_T_WORD* **wStationAddress**
Station address of the slave

*EC_T_WORD* **wIndex**
Object index

*EC_T_BYTE* **bySubIndex**
Object subindex

*EC_T_BOOL* **bCompleteAccess**
Complete access

### 9.8.2 emonNotify - eMbxTferType_COE_SDO_UPLOAD

SDO upload transfer completion.

**emonNotify - eMbxTferType_COE_SDO_UPLOAD**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The transfer result is stored in *EC_T_MBXTFER::dwErrorCode*. The request parameters stored in element *EC_T_MBX_DATA::CoE* of type *EC_T_MBX_DATA_COE* are part of *EC_T_MBXTFER::MbxData*. The SDO data stored in *EC_T_MBXTFER::pbyMbxTferData*.

### 9.8.3 CoE Emergency (emonNotify - eMbxTferType_COE_EMERGENCY)

Indication of a CoE emergency request. A *emonNotify - EC_NOTIFY_MBOXRCV* is given with *EC_T_MBXTFER::eMbxTferType* = *EC_T_MBXTFER_TYPE::eMbxTferType_COE_EMERGENCY*.

**emonNotify - eMbxTferType_COE_EMERGENCY**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

In case of an emergency notification all registered clients will get this notification. The corresponding mailbox transfer object will be created. *EC_T_MBXTFER::dwTferId* is undefined as it is not needed by the client. The transfer result is stored in *EC_T_MBXTFER::dwErrorCode*.

The emergency data stored in element *EC_T_MBX_DATA::CoE_Emergency* of type *EC_T_COE_EMERGENCY* is part of *EC_T_MBXTFER::MbxData* and may have to be buffered by the client. Access to the memory area *EC_T_MBXTFER::MbxData* outside of the notification caller context is illegal and the results are undefined.

struct **EC_T_COE_EMERGENCY**

#### Public Members

*EC_T_WORD* **wErrorCode**
Error code according to EtherCAT specification

*EC_T_BYTE* **byErrorRegister**
Error register

*EC_T_BYTE* **abyData**[EC_COE_EMERGENCY_DATASIZE]
Error data

*EC_T_WORD* **wStationAddress**
Slave node address of the faulty slave

**See also:**

A more detailed description of the values can be found in the EtherCAT® specification ETG.1000, section 5.

### 9.8.4 emonCoeSdoUpload

*EC_T_DWORD* **emonCoeSdoUpload** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_WORD* wObIndex,
*EC_T_BYTE* byObSubIndex,
*EC_T_BYTE* *pbyData,
*EC_T_DWORD* dwDataLen,
*EC_T_DWORD* *pdwOutDataLen,
*EC_T_DWORD* dwTimeout,
*EC_T_DWORD* dwFlags
)

Execute a CoE SDO upload from an EtherCAT slave device to the master.

This function may not be called from within the JobTask's context.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave ID
- **wObIndex** – [in] Object index
- **byObSubIndex** – [in] Object sub index. If Complete Access only 0 or 1 allowed.
- **pbyData** – [out] Buffer receiving transferred data
- **dwDataLen** – [in] Buffer length [bytes]
- **pdwOutDataLen** – [out] Length of received data [byte]
- **dwTimeout** – [in] Timeout [ms]
- **dwFlags** – [in] Mailbox Flags. Bit 0: set if Complete Access (EC_MAILBOX_FLAG_SDO_COMPLETE).

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized

- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer, or dwTimeout is EC_NOWAIT
- *EC_E_NOMEMORY* if the mailbox protocol queue of the slave is full
- *EC_E_SLAVE_NOT_PRESENT* if slave not present
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found
- *EC_E_NO_MBX_SUPPORT* if slave has no mailbox support
- *EC_E_INVALID_SLAVE_STATE* if slave is in an invalid state for mailbox transfer
- *EC_E_MASTER_RED_STATE_INACTIVE* if Master Redundancy is configured and master is inactive
- *EC_E_ADS_IS_RUNNING* if ADS server is running
- *CoE SDO error code*

---

**Limitation**

- Only CoE entries which have been received by the EC-Monitor can be retrieved.
- CoE objects received via complete access can only be retrieved as complete access and vice versa.
- When the access method of a received object changes, the object is erased.

---

**See also:**

*emonGetSlaveId()*

### 9.8.5 emonCoeSdoUploadReq

*EC_T_DWORD* **emonCoeSdoUploadReq** (
*EC_T_DWORD* dwInstanceID,
*EC_T_MBXTFER* *pMbxTfer,
*EC_T_DWORD* dwSlaveId,
*EC_T_WORD* wObIndex,
*EC_T_BYTE* byObSubIndex,
*EC_T_DWORD* dwTimeout,
*EC_T_DWORD* dwFlags
)

Initiates a CoE SDO upload from an EtherCAT slave device to the master and returns immediately.

A unique transfer ID must be written into *EC_T_MBXTFER.dwTferId*. EC_NOTIFY_MBOXRCV is given on completion.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMbxTfer** – [in] Mailbox transfer object created with emMbxTferCreate
- **dwSlaveId** – [in] Slave ID
- **wObIndex** – [in] Object index
- **byObSubIndex** – [in] Object sub index. If Complete Access only 0 or 1 allowed.
- **dwTimeout** – [in] Timeout [ms]
- **dwFlags** – [in] Mailbox Flags. Bit 0: set if Complete Access (EC_MAILBOX_FLAG_SDO_COMPLETE).

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer, or dwTimeout is EC_NOWAIT
- *EC_E_NOMEMORY* if the mailbox protocol queue of the slave is full
- *EC_E_SLAVE_NOT_PRESENT* if slave not present
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found
- *EC_E_NO_MBX_SUPPORT* if slave has no mailbox support
- *EC_E_INVALID_SLAVE_STATE* if slave is in an invalid state for mailbox transfer
- *EC_E_MASTER_RED_STATE_INACTIVE* if Master Redundancy is configured and master is inactive
- *EC_E_ADS_IS_RUNNING* if the ADS server is running
- *CoE SDO error code*

---

**Limitation**

- Only CoE entries which have been received by the EC-Monitor can be retrieved.
- CoE objects received via complete access can only be retrieved as complete access and vice versa.
- When the access method of a received object changes, the object is erased.

---

**See also:**

- *emonNotify - eMbxTferType_COE_SDO_UPLOAD*
- `emonGetSlaveId()`

### 9.8.6 emonIoCtl - EC_IOCTL_MONITOR_SET_COESDO_CLEAR_ON_READ

**`EC_IOCTL_MONITOR_SET_COESDO_CLEAR_ON_READ`**

This IO control can be used to activate a clear on read of the CoE SDO data. If clear on read is activated, the data is automatically deleted after each read of the CoE SDO index, subindex via : *emonCoeSdoUpload()* or *emonCoeSdoUploadReq()*. The IO - Control must be called after : *emonConfigureNetwork()*.

**Parameters**

- **`pbyInBuf`** – [in] Pointer to value of EC_T_BOOL. EC_TRUE : Enables clear on read.
- **`dwInBufSize`** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **`pbyOutBuf`** – [out] Should be set to EC_NULL
- **`dwOutBufSize`** – [in] Should be set to 0
- **`pdwNumOutData`** – [out] Should be set to EC_NULL

**Returns**

*EC_E_NOERROR* or error code

**See also:**

`emonIoCtl()`

### 9.8.7 emonCoeGetODList

*EC_T_DWORD* **emonCoeGetODList** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwSlaveId,
*EC_T_COE_ODLIST_TYPE* eListType,
*EC_T_BYTE* *pbyData,
*EC_T_DWORD* dwDataLen,
*EC_T_COE_ODLIST* *poOdList,
*EC_T_DWORD* dwTimeout
)

Gets a list of object IDs that have so far been transferred to a slave and received by the EC-Monitor.

This function may not be called from within the JobTask's context.

---

**Note:** The data buffer will receive the slave response containing the list type followed by the list itself. Therefore the buffer must be 2 bytes bigger than the expected list size.

---

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwSlaveId** – [in] Slave ID
- **eListType** – [in] Which object types shall be transferred
- **pbyData** – [out] Buffer receiving transferred data
- **dwDataLen** – [in] Buffer length in bytes
- **poOdList** – [out] Received OD list object
- **dwTimeout** – [in] Timeout [ms]

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if master isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer, or dwTimeout is EC_NOWAIT
- *EC_E_NOMEMORY* if the mailbox protocol queue of the slave is full
- *EC_E_SLAVE_NOT_PRESENT* if slave not present
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found
- *EC_E_NO_MBX_SUPPORT* if slave has no mailbox support
- *EC_E_INVALID_SLAVE_STATE* if slave is in an invalid state for mailbox transfer
- *EC_E_MASTER_RED_STATE_INACTIVE* if Master Redundancy is configured and master is inactive
- *EC_E_ADS_IS_RUNNING* if ADS server is running
- *CoE SDO error code*

enum **EC_T_COE_ODLIST_TYPE**
*Values:*

enumerator **eODListType_Lengths**
Lengths of each list type

enumerator **eODListType_ALL**
List contains all objects

enumerator **eODListType_RxPdoMap**
List with PDO mappable objects

enumerator **eODListType_TxPdoMap**
List with objects that can be changed

enumerator **eODListType_StoredFRepl**
Only stored for a device replacement objects

enumerator **eODListType_StartupParm**
Only startup parameter objects

**See also:**

- *emonGetSlaveId()*

### 9.8.8 emonCoeGetODListReq

*EC_T_DWORD* **emonCoeGetODListReq** (
*EC_T_DWORD* dwInstanceID,
*EC_T_MBXTFER* *pMbxTfer,
*EC_T_DWORD* dwSlaveId,
*EC_T_COE_ODLIST_TYPE* eListType,
*EC_T_DWORD* dwTimeout
)

Initiates retrieval of a list of object IDs that have so far been transferred to a slave and received by the EC-Monitor and returns immediately.

---

**Note:** The mailbox transfer object will receive the slave response containing the list type followed by the list itself. Therefore the buffer must be 2 bytes bigger than the expected list size.

---

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **pMbxTfer** – [in] Mailbox transfer
- **dwSlaveId** – [in] Slave ID
- **eListType** – [in] Which object types shall be transferred
- **dwTimeout** – [in] Timeout [ms]

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer, or dwTimeout is EC_NOWAIT

- *EC_E_NOMEMORY* if the mailbox protocol queue of the slave is full
- *EC_E_SLAVE_NOT_PRESENT* if slave not present
- *EC_E_NOTFOUND* if no slave matching dwSlaveId can be found
- *EC_E_NO_MBX_SUPPORT* if slave has no mailbox support
- *EC_E_INVALID_SLAVE_STATE* if slave is in an invalid state for mailbox transfer
- *EC_E_MASTER_RED_STATE_INACTIVE* if Master Redundancy is configured and master is inactive
- *EC_E_ADS_IS_RUNNING* if ADS server is running
- *CoE SDO error code*

**See also:**

- *emonMbxTferCreate()*
- *emonGetSlaveId()*

### 9.8.9 emonNotify - eMbxTferType_COE_GETODLIST

Notification of a detected CoE SDO information service transfer for an object dictionary list.

**emonNotify - eMbxTferType_COE_GETODLIST**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER
- `dwInBufSize`: [in] Size of the transfer object in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The transfer result is stored in *EC_T_MBXTFER::dwErrorCode*.

The object list stored in element *EC_T_MBX_DATA::CoE_ODList* of type *EC_T_COE_ODLIST* is part of *EC_T_MBXTFER::MbxData* and may have to be buffered by the client. Access to the memory area *EC_T_MBXTFER::MbxData* outside of the notification caller context is illegal and the results are undefined.

struct **EC_T_COE_ODLIST**

#### Public Members

*EC_T_COE_ODLIST_TYPE* **eOdListType**
List type

*EC_T_WORD* **wLen**
Amount of object IDs

*EC_T_WORD* **wStationAddress**
Station address of the slave

*EC_T_WORD* ***pwOdList***
Array containing object IDs

### 9.8.10 emonNotify - eMbxTferType_COE_GETENTRYDESC

Notification of a detected CoE SDO information service transfer for an object entry description.

**emonNotify - eMbxTferType_COE_GETENTRYDESC**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER
- `dwInBufSize`: [in] Size of the transfer object in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The transfer result is stored in *`EC_T_MBXTFER::dwErrorCode`*.

The object entry description stored in element *`EC_T_MBX_DATA::CoE_EntryDesc`* of type *`EC_T_COE_ENTRYDESC`* is part of *`EC_T_MBXTFER::MbxData`* and may have to be buffered by the client. Access to the memory area *`EC_T_MBXTFER::MbxData`* outside of the notification caller context is illegal and the results are undefined.

struct **EC_T_COE_ENTRYDESC**

#### Public Members

*EC_T_WORD* **wObIndex**
Index in the object dictionary

*EC_T_BYTE* **byObSubIndex**
Sub index in the object dictionary

*EC_T_BYTE* **byValueInfo**
Bit mask which information is included in pbyData. See *Value info flags*.

*EC_T_WORD* **wDataType**
Object data type according to ETG.1000

*EC_T_WORD* **wBitLen**
Object size (number of bits)

*EC_T_BYTE* **byObAccess**
Access rights. See *Object access flags*.

*EC_T_BOOL* **bRxPdoMapping**
Object is mappable in a RxPDO

*EC_T_BOOL* **bTxPdoMapping**
Object is mappable in a TxPDO

*EC_T_BOOL* **bObCanBeUsedForBackup**
Object can be used for backup

*EC_T_BOOL* **bObCanBeUsedForSettings**
Object can be used for settings

*EC_T_WORD* **wStationAddress**
Station address of the slave

*EC_T_WORD* **wDataLen**
Size of the remaining object data

*EC_T_BYTE* ***pbyData**

Remaining object data: dwUnitType, pbyDefaultValue, pbyMinValue, pbyMaxValue, pbyDescription

(see ETG.1000.5 and ETG.1000.6)

**Value info flags**

**EC_COE_ENTRY_ObjAccess**
Object access

**EC_COE_ENTRY_ObjCategory**
Object category

**EC_COE_ENTRY_PdoMapping**
PDO mapping

**EC_COE_ENTRY_UnitType**
Unit type

**EC_COE_ENTRY_DefaultValue**
Default value

**EC_COE_ENTRY_MinValue**
Minimum value

**EC_COE_ENTRY_MaxValue**
Maximum value

**Object access flags**

**EC_COE_ENTRY_Access_R_PREOP**
Read access in Pre-Operational state

**EC_COE_ENTRY_Access_R_SAFEOP**
Read access in Safe-Operational state

**EC_COE_ENTRY_Access_R_OP**
Read access in Operational state

**EC_COE_ENTRY_Access_W_PREOP**
Write access in Pre-Operational state

**EC_COE_ENTRY_Access_W_SAFEOP**
Write access in Safe-Operational state

**EC_COE_ENTRY_Access_W_OP**
Write access in Operational state

**See also:**

A more detailed description of the values can be found in the EtherCAT® specification ETG.1000, section 5 and 6.

## 9.9 File access over EtherCAT® (FoE)

The EC-Monitor can record file transfers via the FoE protocol between an EtherCAT® MainDevice and a SubDevice. These FoE transfers can be forwarded to the application as segmented packets in real time via the notifications *emonNotify - eMbxTferType_FOE_SEG_DOWNLOAD* and *emonNotify - eMbxTferType_FOE_SEG_UPLOAD*.

**In addition, the FoE transfers can be stored as a file on the file system. The files are automatically created and stored in *EC_T_MONITOR_INIT_PARMS::szFileStoragePath*. The file name consists of the following:**

```
<TimeStamp[msec]>_Slave<StationAddress>_<FoeFileName>
```

**For example:**

```
0123456789_Slave1001_firmware.bin
```

The notifications for FoE can be deactivated using the *EC_T_MBX_PARMS_FOE::bDisableNotifications* parameter if they are not required or to save computing time. If no file system is available or file storage is not desired, it can be disabled using the *EC_T_MBX_PARMS_FOE::bDisableFileStorage* parameter.

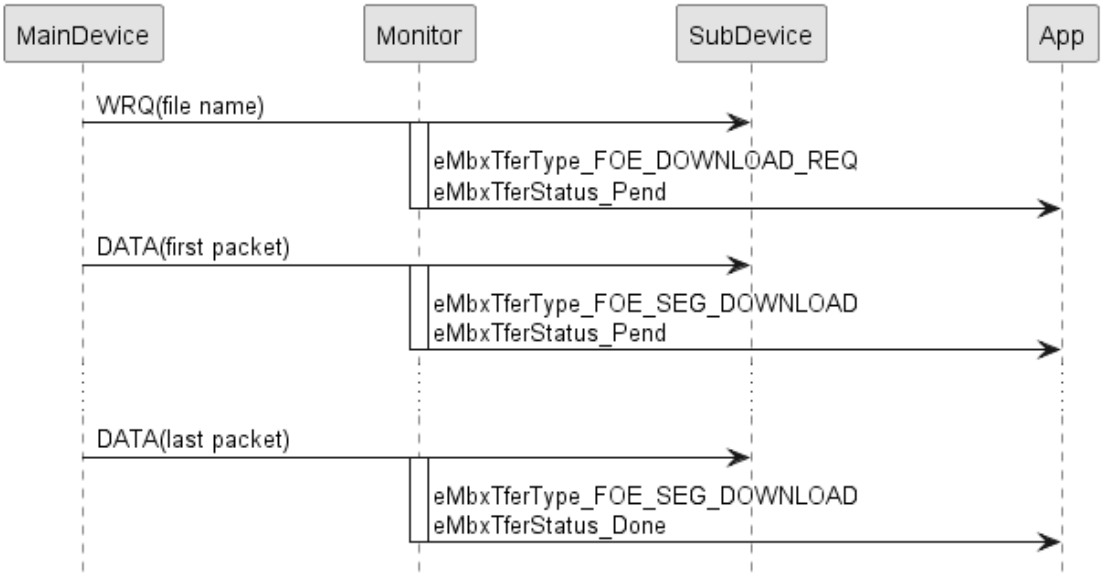
If both parameters *EC_T_MBX_PARMS_FOE::bDisableNotifications* and *EC_T_MBX_PARMS_FOE::bDisableFileStorage* are set, the FoE monitoring is completely deactivated.

### 9.9.1 Notification sequence

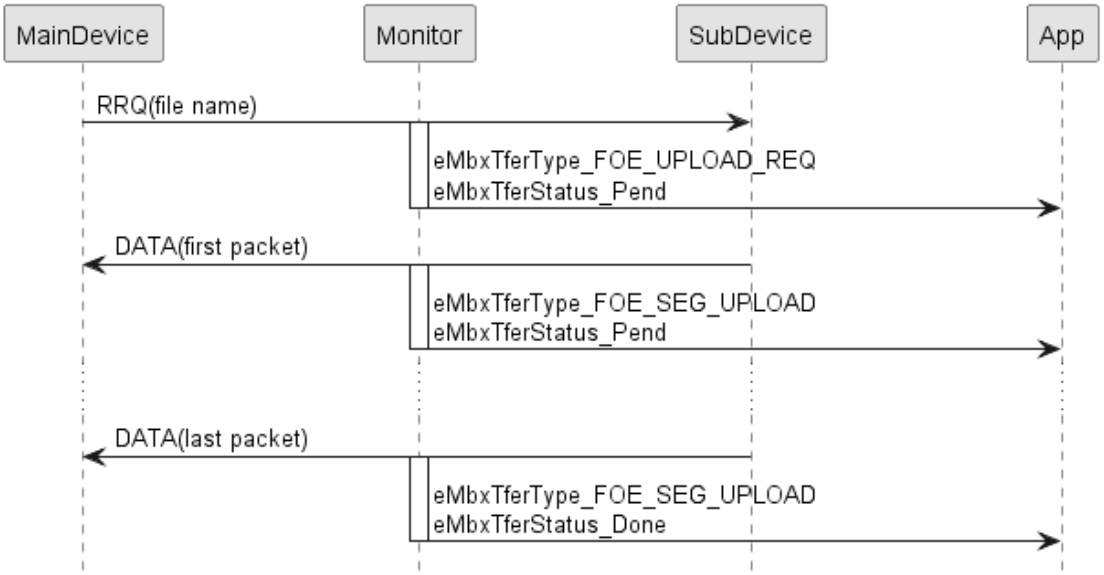
Once the EC-Monitor detects an FoE transfer, the application is notified via an *emonNotify - eMbxTferType_FOE_DOWNLOAD_REQ* or *emonNotify - eMbxTferType_FOE_UPLOAD_REQ* notification. This notification contains basic information about the upcoming transfer, e.g. requested file name.

After that, each individual packet is transmitted via an *emonNotify - eMbxTferType_FOE_SEG_DOWNLOAD* or *emonNotify - eMbxTferType_FOE_SEG_UPLOAD* notification. The end of the transfer is set via the *EC_T_MBXTFER::eTferStatus* = *eMbxTferStatus_TferDone*.

**Download**




**Upload**




### 9.9.2 emonNotify - eMbxTferType_FOE_DOWNLOAD_REQ

Notifies an FoE download request from the EtherCAT® MainDevice to a SubDevice.

**emonNotify - eMbxTferType_FOE_DOWNLOAD_REQ**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The parameters that the MainDevice has requested from the SubDevice are stored in the structure *EC_T_MBX_DATA::FoE_Request* which is part of *EC_T_MBXTFER::MbxData*.

struct **EC_T_MBX_DATA_FOE_REQ**

#### Public Members

*EC_T_WORD* **wStationAddress**
[out] Station address of the slave

*EC_T_DWORD* **dwPassword**
[out] FoE read/write request password

*EC_T_CHAR* **szFileName**[EC_MAX_FILE_NAME_SIZE]
[out] Name of the file to be read/write

### 9.9.3 emonNotify - eMbxTferType_FOE_SEG_DOWNLOAD

Transmits a data segment of the ongoing FoE download.

**emonNotify - eMbxTferType_FOE_SEG_DOWNLOAD**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The FoE download data segment is stored at *EC_T_MBXTFER::pbyMbxTferData* with size *EC_T_MBXTFER::dwDataLen* and may have to be buffered by the application. Access to the memory area *EC_T_MBXTFER::pbyMbxTferData* outside of the notification caller context is illegal and the results are undefined.

Information about the current transfer is stored in the structure *EC_T_MBX_DATA::FoE* which is part of *EC_T_MBXTFER::MbxData*. Among other things, it contains the SubDevice station address *EC_T_MBX_DATA_FOE::wStationAddress* and the number of bytes already transmitted *EC_T_MBX_DATA_FOE::dwTransferredBytes*.

struct **EC_T_MBX_DATA_FOE**

#### Public Members

*EC_T_DWORD* **dwTransferredBytes**
[out] Amount of transferred bytes

*EC_T_DWORD* **dwRequestedBytes**
[out] Amount of bytes to be provided by the application

*EC_T_DWORD* **dwBusyDone**
[out] If slave is busy: 0 … dwBusyEntire

*EC_T_DWORD* **dwBusyEntire**
[out] If dwBusyEntire > 0: Slave is busy

*EC_T_CHAR* **szBusyComment**[EC_FOE_BUSY_COMMENT_SIZE]
[out] Busy Comment from slave

*EC_T_DWORD* **dwFileSize**
[out] File size

*EC_T_WORD* **wStationAddress**
[out] Station address of the slave

---

**Note:** The elements *EC_T_MBX_DATA_FOE::dwRequestedBytes* and *EC_T_MBX_DATA_FOE::dwFileSize* are not used by the EC-Monitor because they are not known at runtime.

---

### 9.9.4 emonNotify - eMbxTferType_FOE_UPLOAD_REQ

Notifies an FoE upload request from the EtherCAT® MainDevice to a SubDevice.

**emonNotify - eMbxTferType_FOE_DOWNLOAD_REQ**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The parameters that the MainDevice has requested from the SubDevice are stored in the structure *EC_T_MBX_DATA::FoE_Request* which is part of *EC_T_MBXTFER::MbxData*.

struct *EC_T_MBX_DATA_FOE_REQ*

*EC_T_WORD wStationAddress*

*EC_T_DWORD dwPassword*

*EC_T_CHAR szFileName*[EC_MAX_FILE_NAME_SIZE]

### 9.9.5 emonNotify - eMbxTferType_FOE_SEG_UPLOAD

Transmits a data segment of the ongoing FoE upload.

**emonNotify - eMbxTferType_FOE_SEG_UPLOAD**

**Parameter**

- `pbyInBuf`: [in] Pointer to a structure of type EC_T_MBXTFER, containing the corresponding mailbox transfer object
- `dwInBufSize`: [in] Size of the transfer object pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The FoE upload data segment is stored at *EC_T_MBXTFER::pbyMbxTferData* with size *EC_T_MBXTFER::dwDataLen* and may have to be buffered by the application. Access to the memory area *EC_T_MBXTFER::pbyMbxTferData* outside of the notification caller context is illegal and the results are undefined.

Information about the current transfer is stored in the structure *EC_T_MBX_DATA::FoE* which is part of *EC_T_MBXTFER::MbxData*. Among other things, it contains the SubDevice station address *EC_T_MBX_DATA_FOE::wStationAddress* and the number of bytes already transmitted *EC_T_MBX_DATA_FOE::dwTransferredBytes*.

struct *EC_T_MBX_DATA_FOE*

*EC_T_DWORD dwTransferredBytes*

*EC_T_DWORD dwRequestedBytes*

*EC_T_DWORD dwBusyDone*

*EC_T_DWORD dwBusyEntire*

*EC_T_CHAR szBusyComment*[EC_FOE_BUSY_COMMENT_SIZE]

*EC_T_DWORD dwFileSize*

*EC_T_WORD wStationAddress*

---

**Note:** The elements *EC_T_MBX_DATA_FOE::dwRequestedBytes* and *EC_T_MBX_DATA_FOE::dwFileSize* are not used by the EC-Monitor because they are not known at runtime.

---

### 9.9.6 emonNotify - EC_NOTIFY_FOE_MBSLAVE_ERROR

This error will be indicated in case an FoE mailbox SubDevice sends an error message. Detailed error information is stored in the structure *EC_T_MBOX_FOE_ABORT_DESC* which is part of *EC_T_ERROR_NOTIFICATION_DESC*.

struct **EC_T_MBOX_FOE_ABORT_DESC**

#### Public Members

*EC_T_SLAVE_PROP* **SlaveProp**
Slave properties

*EC_T_DWORD* **dwErrorCode**
Error code

*EC_T_CHAR* **achErrorString**[MAX_STD_STRLEN]
FoE error string

### 9.9.7 emonConvertEcErrorToFoeError

*EC_T_DWORD* **emonConvertEcErrorToFoeError** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwErrorCode
)
Convert master error code to FoE error code.

**Returns**
FoE error code according to ETG1000.6 Table 92 - Error codes of FoE

## 9.10 Hot Connect

### 9.10.1 emonHCGetNumGroupMembers

*EC_T_DWORD* **emonHCGetNumGroupMembers** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwGroupIndex
)
Get number of slaves belonging to a specific Hot-Connect group.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwGroupIndex** – [in] Index of Hot-Connect group, 0 is the mandatory group

**Returns**
Number of slaves

### 9.10.2 emonHCGetSlaveIdsOfGroup

*EC_T_DWORD* **emonHCGetSlaveIdsOfGroup** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwGroupIndex,
*EC_T_DWORD* *adwSlaveId,
*EC_T_DWORD* dwMaxNumSlaveIds
)

Get a list of Slave ID's belonging to a specific Hot-Connect group.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwGroupIndex** – [in] Index of Hot-Connect group, 0 is the mandatory group
- **adwSlaveId** – [out] Preallocated Slave ID list buffer
- **dwMaxNumSlaveIds** – [in] Size of Slave ID list buffer

**Returns**
*EC_E_NOERROR* or error code

### 9.10.3 emonNotify - EC_NOTIFY_HC_DETECTADDGROUPS

This notification is raised when HotConnect group detection is finished, after SubDevice addition.

**emonNotify - EC_NOTIFY_HC_DETECTADDGROUPS**

**Parameter**

- `pbyInBuf`: [in] Pointer to notification descriptor EC_T_HC_DETECTALLGROUP_NTFY_DESC
- `dwInBufSize`: [in] sizeof(EC_T_HC_DETECTALLGROUP_NTFY_DESC)
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_HC_DETECTALLGROUP_NTFY_DESC**

#### Public Members

*EC_T_DWORD* **dwResultCode**
Result of Group detection

*EC_T_DWORD* **dwGroupCount**
Total number of Groups

*EC_T_DWORD* **dwGroupsPresent**
Number of connected groups

*EC_T_DWORD* **dwGroupMask**
Bitmask of first 32 Groups. 1 = present, 0 = absent.

*EC_T_DWORD* **adwGroupMask**[100]
Bitmask of first 3200 Groups

### 9.10.4 emonNotify - EC_NOTIFY_HC_PROBEALLGROUPS

This notification is raised when HotConnect Group Detection is finished, after SubDevice Disappearance.

**emonNotify - EC_NOTIFY_HC_PROBEALLGROUPS**

**Parameter**

- `pbyInBuf`: [in] Pointer to notification descriptor EC_T_HC_DETECTALLGROUP_NTFY_DESC
- `dwInBufSize`: [in] sizeof(EC_T_HC_DETECTALLGROUP_NTFY_DESC)
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct *EC_T_HC_DETECTALLGROUP_NTFY_DESC*

*EC_T_DWORD dwResultCode*

*EC_T_DWORD dwGroupCount*

*EC_T_DWORD dwGroupsPresent*

*EC_T_DWORD dwGroupMask*

*EC_T_DWORD adwGroupMask*[100]

### 9.10.5 emonNotify - EC_NOTIFY_HC_TOPOCHGDONE

This notification is raised when HotConnect has completely processed a topology change.

**emonNotify - EC_NOTIFY_HC_TOPOCHGDONE**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_DWORD (EC_E_NOERROR on success, Error code otherwise)
- `dwInBufSize`: [in] sizeof(EC_T_DWORD)
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

The notification is raised when the SubDevices reached the current bus state.

## 9.11 Configuration adjustments

The Configuration adjustments allows to adapt the configuration without generating a new ENI file. The base ENI file contains a superset of all the possible connected SubDevices. Possible use cases are:

**Optional SubDevices**
ENI contains several optional SubDevices that can be excluded depending on their presence.

**Alternative SubDevices**
ENI contains several different alternatives for a SubDevice at a certain position.

According to the use case the application can exclude SubDevices from this superset.

### 9.11.1 emonConfigLoad

*EC_T_DWORD* **emonConfigLoad** (
*EC_T_DWORD* dwInstanceID,
*EC_T_CNF_TYPE* eCnfType,
*EC_T_PBYTE* pbyCnfData,
*EC_T_DWORD* dwCnfDataLen
)

Load the network configuration.

In combination with emConfigApply, this function replaces emConfigureNetwork and must be called after the initialization. Among others the EtherCAT topology defined in the given XML configuration file will be stored internally.

---

**Note:** A client must not be registered prior to calling this function. Existing client registrations will be dropped.

---

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **eCnfType** – [in] Type of configuration data provided
- **pbyCnfData** – [in] Configuration data
- **dwCnfDataLen** – [in] Length of configuration data in byte

**Returns**

- *EC_E_NOERROR* if successful
- *EC_E_INVALIDSTATE* if EtherCAT stack isn't initialized
- *EC_E_INVALIDPARM* if dwInstanceID is out of range, the input pointer is EC_NULL or contains EC_NULL pointer
- *EC_E_NOMEMORY* if some memory cannot be allocated
- *EC_E_ADS_IS_RUNNING* if the ADS server is running

enum *EC_T_CNF_TYPE*

enumerator *eCnfType_Unknown*

enumerator *eCnfType_Filename*

enumerator *eCnfType_Data*

enumerator *eCnfType_Datadiag*

enumerator *eCnfType_GenPreopENI*

enumerator *eCnfType_GenPreopENIWithCRC*

enumerator *eCnfType_GenOpENI*

enumerator *eCnfType_None*

enumerator *eCnfType_ConfigData*

enumerator *eCnfType_GenOpENINoStrings*

enumerator *eCnfType_FileByApp*

enumerator *eCnfType_GenEBI*

### 9.11.2 emonConfigExcludeSlave

*EC_T_DWORD* **emonConfigExcludeSlave** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* wStationAddress
)

Exclude a slave from the network configuration.

It has to be called after emConfigLoad and prior to calling emConfigApply.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **wStationAddress** – [in] Station address of the slave to be excluded. A value of 0 excludes all slaves.

**Returns**
*EC_E_NOERROR* or error code

### 9.11.3 emonConfigIncludeSlave

*EC_T_DWORD* **emonConfigIncludeSlave** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* wStationAddress
)

Include a slave in the network configuration.

Slaves that were previously excluded with emConfigSlaveExclude can be added again. It has to be called after emConfigLoad and prior to calling emConfigApply.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

- **wStationAddress** – [in] Station address of the slave to be included. A value of 0 includes all slaves.

**Returns**
*EC_E_NOERROR* or error code

### 9.11.4 emonConfigSetPreviousPort

*EC_T_DWORD* **emonConfigSetPreviousPort** (
*EC_T_DWORD* dwInstanceID,
*EC_T_WORD* wStationAddress,
*EC_T_WORD* wStationAddressPrev,
*EC_T_WORD* wPortPrev
)

Set previous port information of a slave.

It has to be called after emConfigLoad and prior to calling emConfigApply.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **wStationAddress** – [in] Station address of the slave
- **wStationAddressPrev** – [in] Previous slave station address
- **wPortPrev** – [in] Previous port

**Returns**
*EC_E_NOERROR* or error code

### 9.11.5 emonConfigApply

*EC_T_DWORD* **emonConfigApply** (*EC_T_DWORD* dwInstanceID)

Apply the network configuration.

It has to be called after emConfigLoad.

**Parameters**
**dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)

**Returns**
*EC_E_NOERROR* or error code

# 10 Generic notification interface

One of the parameters the client has to set when registering with the EC-Monitor is a generic notification callback function ( `emonNotify()`). This function is called every time an event occurs about which the client needs to be informed.

Within this callback function the client must not call any active EtherCAT® functions which finally would lead to send EtherCAT® commands (e.g. initiation of mailbox transfers, starting/stopping the MainDevice, sending raw commands). In such cases the behavior is undefined. Only EtherCAT® functions which are explicitly marked to be callable within `emonNotify()` may be called.

This callback function is usually called in the context of the EC-Monitor timer thread or the EtherCAT® Real-time Ethernet Driver receiver thread. To avoid dead-lock situations the notification callback handler may not use mutex semaphores.

As the whole EtherCAT® operation is blocked while calling this function the error handling must not use much CPU time or even call operating system functions that may block. Usually the error handling will be done in a separate application thread.

## 10.1 Notification callback

typedef *EC_T_DWORD* (**EC_PF_NOTIFY*)(*EC_T_DWORD* dwCode, *EC_T_NOTIFYPARMS* *pParms)

struct **EC_T_NOTIFYPARMS**
Data structure filled with detailed information about the according notification.

### Public Members

EC_T_VOID ***pCallerData**
[in] Client depending caller data parameter. This pointer is one of the parameters when the client registers.

*EC_T_BYTE* ***pbyInBuf**
[in] Notification input parameters

*EC_T_DWORD* **dwInBufSize**
[in] Size of notification input parameters in bytes

*EC_T_BYTE* ***pbyOutBuf**
[out] Buffer for notification output (result)

*EC_T_DWORD* **dwOutBufSize**
[in] Size of buffer at pbyOutBuf in bytes

*EC_T_DWORD* ***pdwNumOutData**
[out] Amount of bytes written to pbyOutBuf by notification. EC_NULL: amount not set by notification.

## 10.2 emonNotifyApp

By calling this function the generic notification callback function setup by *emonRegisterClient()* is called.

*EC_T_DWORD* **emonNotifyApp** (
*EC_T_DWORD* dwInstanceID,
*EC_T_DWORD* dwCode,
*EC_T_NOTIFYPARMS* *pParms
)

Calls the notification callback functions of all registered clients.

**Note:** EC_E_ERROR and EC_E_INVALIDPARM from registered clients' callback functions are ignored.

**Parameters**

- **dwInstanceID** – [in] Instance ID (Multiple EtherCAT Network Support)
- **dwCode** – [in] Application specific notification code. dwCode must be <= EC_NOTIFY_APP_MAX_CODE. The callback functions get "EC_NOTIFY_APP | dwCode" as parameter.
- **pParms** – [in] Parameter to all callback functions. Note: Output parameters are not transferred from RAS client to RAS server.

**Returns**

*EC_E_ERROR* or first error code different from *EC_E_ERROR* and *EC_E_INVALIDPARM* of registered clients' callback functions

The maximum value for dwCode is defined by `EC_NOTIFY_APP_MAX_CODE`

## 10.3 Enable/Disable notifications

All notifications can be enabled or disabled. By default, all notifications are enabled except for:

EC_NOTIFY_SLAVE_STATECHANGED

EC_NOTIFY_SLAVES_STATECHANGED

EC_NOTIFY_SLAVES_PRESENCE

EC_NOTIFY_REFCLOCK_PRESENCE

EC_NOTIFY_SLAVES_UNEXPECTED_STATE

EC_NOTIFY_SLAVES_ERROR_STATUS

EC_NOTIFY_COE_INIT_CMD

EC_NOTIFY_SLAVE_REGISTER_TRANSFER

### 10.3.1 emonIoCtl - EC_IOCTL_SET_NOTIFICATION_ENABLED

**EC_IOCTL_SET_NOTIFICATION_ENABLED**
Set notification enabled state. With *EC_T_SET_NOTIFICATION_ENABLED_PARMS::dwCode* set to *EC_ALL_NOTIFICATIONS*, all notifications can be changed at once. *EC_T_SET_NOTIFICATION_ENABLED_PARMS::dwEnabled* set to *EC_NOTIFICATION_DEFAULT*, resets to default.

**Parameters**

- **pbyInBuf** – [in] Pointer to *EC_T_SET_NOTIFICATION_ENABLED_PARMS*.
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Should be set to EC_NULL
- **dwOutBufSize** – [in] Should be set to 0
- **pdwNumOutData** – [out] Should be set to EC_NULL

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_SET_NOTIFICATION_ENABLED_PARMS**

#### Public Members

*EC_T_DWORD* **dwClientId**
[in] Client ID, 0: Master

*EC_T_DWORD* **dwCode**
[in] Notification code or *EC_ALL_NOTIFICATIONS*

*EC_T_DWORD* **dwEnabled**
[in] Enable, disable or reset to default notification. See *EC_NOTIFICATION_* flags.

**EC_NOTIFICATION_DISABLED**
Disable notification

**EC_NOTIFICATION_ENABLED**
Enable notification

**EC_NOTIFICATION_DEFAULT**
Reset notification to default

**EC_ALL_NOTIFICATIONS**
Notification code to change all notifications

**See also:**

*emonIoCtl()*

### 10.3.2 emonIoCtl - EC_IOCTL_GET_NOTIFICATION_ENABLED

**EC_IOCTL_GET_NOTIFICATION_ENABLED**
The enabled state of notifications can be retrieved using *EC_IOCTL_GET_NOTIFICATION_ENABLED*.

**Parameters**

- **pbyInBuf** – [in] Pointer to *EC_T_GET_NOTIFICATION_ENABLED_PARMS*
- **dwInBufSize** – [in] Size of the input buffer provided at pbyInBuf in bytes
- **pbyOutBuf** – [out] Pointer to EC_T_BOOL to carry out current enable set
- **dwOutBufSize** – [in] Size of the output buffer provided at pbyOutBuf in bytes
- **pdwNumOutData** – [out] Pointer to EC_T_DWORD. Amount of bytes written to the output buffer.

**Returns**
*EC_E_NOERROR* or error code

struct **EC_T_GET_NOTIFICATION_ENABLED_PARMS**

#### Public Members

*EC_T_DWORD* **dwClientId**
[in] Client ID, 0: Master

*EC_T_DWORD* **dwCode**
[in] Notification code

**See also:**

*emonIoCtl()*

## 10.4 Status notifications

### 10.4.1 emonNotify - EC_NOTIFY_STATECHANGED

Notification about a change in the MainDevice's operational state.

**emonNotify - EC_NOTIFY_STATECHANGED**

**Parameter**

- `pbyInBuf`: [in] Pointer to data of type EC_T_STATECHANGE which contains the old and the new MainDevice operational state
- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_STATECHANGE**

#### Public Members

*EC_T_STATE* **oldState**
Old operational state

*EC_T_STATE* **newState**
New operational state

### 10.4.2 emonNotify - EC_NOTIFY_SB_STATUS

Scan bus status notification.

**emonNotify - EC_NOTIFY_SB_STATUS**

#### Parameter

- `pbyInBuf`: [in] Pointer to EC_T_SB_STATUS_NTFY_DESC
- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_SB_STATUS_NTFY_DESC**

#### Public Members

*EC_T_DWORD* **dwResultCode**
[in] *EC_E_NOERROR*: success, *EC_E_NOTREADY*: no bus scan executed, *EC_E_BUSCONFIG_MISMATCH*: bus configuration mismatch result of scanbus

*EC_T_DWORD* **dwSlaveCount**
[in] Number of slaves connected to the bus

### 10.4.3 emonNotify - EC_NOTIFY_SB_MISMATCH

This notification is triggered when the bus scan detects a discrepancy between connected SubDevices and configuration due to unexpected SubDevices or missing mandatory SubDevices. In case of permanent frame loss no SubDevices can be found although the SubDevices are connected.

**emonNotify - EC_NOTIFY_SB_MISMATCH**

#### Parameter

- `pbyInBuf`: [in] Pointer to EC_T_SB_MISMATCH_DESC

- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_SB_MISMATCH_DESC**

### Public Members

*EC_T_WORD* **wPrevFixedAddress**
[in] Previous slave station address

*EC_T_WORD* **wPrevPort**
[in] Previous slave station address

*EC_T_WORD* **wPrevAIncAddress**
[in] Previous slave auto-increment address

*EC_T_WORD* **wBusAIncAddress**
[in] Unexpected slave (bus) auto-inc address

*EC_T_DWORD* **dwBusVendorId**
[in] Unexpected slave (bus) vendor ID

*EC_T_DWORD* **dwBusProdCode**
[in] Unexpected slave (bus) product code

*EC_T_DWORD* **dwBusRevisionNo**
[in] Unexpected slave (bus) revision number

*EC_T_DWORD* **dwBusSerialNo**
[in] Unexpected slave (bus) serial number

*EC_T_WORD* **wBusFixedAddress**
[in] Unexpected slave (bus) station address

*EC_T_BOOL* **bIdentificationError**
[in] Identification command sent to slave but failed

*EC_T_WORD* **wIdentificationAdo**
[in] Identification register

*EC_T_WORD* **wIdentificationVal**
[in] Last identification value read from slave according to the last used identification method

*EC_T_WORD* **wIdentificationValExpected**
[in] Identification expected value

*EC_T_WORD* **wCfgFixedAddress**
[in] Missing slave (config) station Address

*EC_T_WORD* **wCfgAIncAddress**
[in] Missing slave (config) Auto-Increment Address

*EC_T_DWORD* **dwCfgVendorId**
[in] Missing slave (config) Vendor ID

*EC_T_DWORD* **dwCfgProdCode**
[in] Missing slave (config) Product code

*EC_T_DWORD* **dwCfgRevisionNo**
[in] Missing slave (config) Revision Number

*EC_T_DWORD* **dwCfgSerialNo**
[in] Missing slave (config) Serial Number

### 10.4.4 emonNotify - EC_NOTIFY_HC_TOPOCHGDONE

This notification is triggered when a topology change was completely processed.

**emonNotify - EC_NOTIFY_HC_TOPOCHGDONE**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_DWORD (EC_E_NOERROR on success, Error code otherwise)
- `dwInBufSize`: [in] sizeof(EC_T_DWORD)
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

### 10.4.5 emonNotify - EC_NOTIFY_SLAVE_PRESENCE

This notification is given when a SubDevice appears at or disappears from the network.

**emonNotify - EC_NOTIFY_SLAVE_PRESENCE**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_SLAVE_PRESENCE_NTFY_DESC
- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

Disconnecting the SubDevice from the network, powering it off or a bad connection can produce this notification.

struct **EC_T_SLAVE_PRESENCE_NTFY_DESC**

#### Public Members

*EC_T_WORD* **wStationAddress**
Slave station address

*EC_T_BYTE* **bPresent**
EC_TRUE: present, EC_FALSE: absent

### 10.4.6 emonNotify - EC_NOTIFY_SLAVE_STATECHANGED

This notification is triggered when a SubDevice has changed its EtherCAT® state. This notification is disabled by default.

**emonNotify - EC_NOTIFY_SLAVE_STATECHANGED**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_SLAVE_STATECHANGED_NTFY_DESC
- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_SLAVE_STATECHANGED_NTFY_DESC**

#### Public Members

*EC_T_SLAVE_PROP* **SlaveProp**
Slave properties

*EC_T_STATE* **newState**
New slave state

**See also:**

*emonIoCtl - EC_IOCTL_SET_NOTIFICATION_ENABLED* to enable notification.

### 10.4.7 emonNotify - EC_NOTIFY_SLAVE_REGISTER_TRANSFER

This notification is triggered when a SubDevice register transfer is completed.

To avoid excessive triggering of the notification, registers that are read by the EtherCAT® MainDevice at regular intervals are not notified. These are the following registers:

AL-Status (0x0130)

RX Error Counter, Forwarded RX Error Counter, ECAT Processing Unit Error Counter, PDI Error Counter, PDI Error Code, Lost Link Counter (0x0300:0x0314)

SII EEPROM Interface (0x0500:0x050F)

Registers above 0x1000

This notification is disabled by default.

**emonNotify - EC_NOTIFY_SLAVE_REGISTER_TRANSFER**

**Parameter**

- `pbyInBuf`: [in] Pointer to EC_T_SLAVEREGISTER_TRANSFER_NTFY_DESC
- `dwInBufSize`: [in] Size of the input buffer provided at pbyInBuf in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_SLAVEREGISTER_TRANSFER_NTFY_DESC**

### Public Members

*EC_T_DWORD* **dwTferId**
Transfer ID. For every new slave register transfer a unique ID has to be assigned. This ID can be used after completion to identify the transfer.

*EC_T_DWORD* **dwResult**
Result of Slave register transfer

*EC_T_BOOL* **bRead**
EC_TRUE: Read register, EC_FALSE: Write register transfer

*EC_T_WORD* **wFixedAddr**
Station address of slave

*EC_T_WORD* **wRegisterOffset**
Register offset

*EC_T_WORD* **wLen**
Length of slave register transfer

*EC_T_BYTE* ***pbyData**
Pointer to the data read

*EC_T_WORD* **wWkc**
Received working counter

**See also:**

*emonIoCtl - EC_IOCTL_SET_NOTIFICATION_ENABLED* to enable notification.

## 10.5 Error notifications

For each error an error ID (error code) will be defined. This error ID will be used as the notification code when `emonNotify()` is called. In addition to this notification code the second parameter given to `emonNotify()` contains a pointer to an error notification descriptor of type *EC_T_ERROR_NOTIFICATION_DESC*. This error notification descriptor contains detailed information about the error.

struct **EC_T_ERROR_NOTIFICATION_DESC**

### Public Members

*EC_T_DWORD* **dwNotifyErrorCode**
Error ID (same value as the notification code)

*EC_T_CHAR* **achErrorInfo**[MAX_ERRINFO_STRLEN]
Additional error string (may be empty)

union **_EC_T_ERROR_NOTIFICATION_PARM**

#### Public Members

*EC_T_WKCERR_DESC* **WkcErrDesc**
WKC error descriptor

*EC_T_FRAME_RSPERR_DESC* **FrameRspErrDesc**
Frame response error descriptor

EC_T_INITCMD_ERR_DESC **InitCmdErrDesc**
Master/Slave init command error descriptor

*EC_T_SLAVE_ERROR_INFO_DESC* **SlaveErrInfoDesc**
Slave Error Info Descriptor

EC_T_SLAVES_ERROR_DESC **SlavesErrDesc**
Slaves Error Descriptor

EC_T_MBOX_SDO_ABORT_DESC **SdoAbortDesc**
SDO Abort

EC_T_RED_CHANGE_DESC **RedChangeDesc**
Redundancy Descriptor

*EC_T_MBOX_FOE_ABORT_DESC* **FoeErrorDesc**
FoE error code and string

EC_T_MBXRCV_INVALID_DATA_DESC **MbxRcvInvalidDataDesc**
Invalid mailbox data received descriptor

*EC_T_PDIWATCHDOG_DESC* **PdiWatchdogDesc**
PDI watchdog expired

EC_T_SLAVE_NOTSUPPORTED_DESC **SlaveNotSupportedDesc**
Slave not supported

EC_T_SLAVE_UNEXPECTED_STATE_DESC **SlaveUnexpectedStateDesc**
Slave in unexpected state

EC_T_SLAVES_UNEXPECTED_STATE_DESC **SlavesUnexpectedStateDesc**
Slaves in unexpected state

EC_T_EEPROM_CHECKSUM_ERROR_DESC **EEPROMChecksumErrorDesc**
EEPROM checksum error

EC_T_JUNCTION_RED_CHANGE_DESC **JunctionRedChangeDesc**
Junction redundancy change descriptor

EC_T_FRAMELOSS_AFTER_SLAVE_NTFY_DESC **FramelossAfterSlaveDesc**
Frameloss after Slave descriptor

EC_T_S2SMBX_ERROR_DESC **S2SMbxErrorDesc**
S2S Mailbox Error descriptor

EC_T_BAD_CONNECTION_NTFY_DESC **BadConnectionDesc**
Bad connection descriptor

*EC_T_COMMUNICATION_TIMEOUT_NTFY_DESC* **CommunicationTimeoutDesc**
Communication timeout descriptor

*EC_T_TAP_LINK_STATUS_NTFY_DESC* **TapLinkStatusDesc**
Tap link status

If the pointer to this descriptor exists the detailed error information (e.g. information about the SubDevice) is stored in the appropriate structure of a union. These error information structures are described in the following sections.

### 10.5.1 emonNotify - EC_NOTIFY_NOT_ALL_DEVICES_OPERATIONAL

When processing cyclic frames the EtherCAT® MainDevice checks whether all SubDevices are still in OPERATIONAL state. If at least one SubDevice is not OPERATIONAL this error will be indicated.

### 10.5.2 emonNotify - EC_NOTIFY_ALL_DEVICES_OPERATIONAL

When processing cyclic frames the EtherCAT® MainDevice checks whether all SubDevices are still in OPERATIONAL state. This will be notified after *emonNotify - EC_NOTIFY_NOT_ALL_DEVICES_OPERATIONAL* and all the SubDevices are back in OPERATIONAL state.

### 10.5.3 emonNotify - EC_NOTIFY_CLIENTREGISTRATION_DROPPED

This notification will be indicated if the client registration was dropped because *emonConfigureNetwork()* was called by another thread.

```
EC_T_DWORD dwDeinitForConfiguration; /* 0 = terminating MainDevice, 1 = restarting␣
↪MainDevice */
```

### 10.5.4 emonNotify - EC_NOTIFY_CYCCMD_WKC_ERROR

To update the process data some EtherCAT® commands will be sent cyclically by the external MainDevice. These commands will address one or multiple SubDevices. These EtherCAT® commands contain a working counter which has to be incremented by each SubDevice that is addressed. The working counter will be checked after the EtherCAT® command is received by the monitor. If the expected working counter will not match the working counter of the received command the error *EC_NOTIFY_CYCCMD_WKC_ERROR* will be indicated. The working counter value expected by the monitor is determined by the EtherCAT® configuration (XML) file for each cyclic EtherCAT® command (section Config/Cyclic/Frame/Cmd/Cnt). Detailed error information are stored in structure *EC_T_WKCERR_DESC* of *EC_T_ERROR_NOTIFICATION_DESC*.

struct **EC_T_WKCERR_DESC**

#### Public Members

*EC_T_SLAVE_PROP* **SlaveProp**
Slave properties, content is undefined in case of cyclic WKC_ERROR

*EC_T_BYTE* **byCmd**
EtherCAT command type

*EC_T_DWORD* **dwAddr**
Logical address or physical address (ADP/ADO)

*EC_T_WORD* **wWkcSet**
Working counter set value

*EC_T_WORD* **wWkcAct**
Working counter actual value

*EC_T_DWORD* **dwTaskId**
Cyclic Task ID (ENI: Cyclic/TaskId)

*EC_T_WORD* **wMsuId**
Master Sync Unit ID (ENI: Slave/ProcessData/RxPdo[1..4]@Su, Slave/ProcessData/TxPdo[1..4]@Su, comment at Cyclic/Frame/Cmd)

struct *EC_T_SLAVE_PROP*

*EC_T_WORD wStationAddress*

*EC_T_WORD wAutoIncAddr*

*EC_T_CHAR achName*[MAX_STD_STRLEN]

### 10.5.5 emonNotify - EC_NOTIFY_FRAME_RESPONSE_ERROR

This notification will be indicated if the actually received Ethernet frame does not match the expected frame or if an expected frame was not received.

struct **EC_T_FRAME_RSPERR_DESC**

#### Public Members

*EC_T_BOOL* **bIsCyclicFrame**
Indicates whether the lost frame was a cyclic frame

*EC_T_FRAME_RSPERR_TYPE* **EErrorType**
Frame response error type

*EC_T_BYTE* **byEcCmdHeaderIdxSet**
Expected IDX value, this value is valid only for acyclic frames in case EErrorType is not equal to eRspErr_UNEXPECTED

*EC_T_BYTE* **byEcCmdHeaderIdxAct**
Actually received IDX value, this value is only valid for acyclic frames in case of EErrorType is equal to: eRspErr_WRONG_IDX and eRspErr_UNEXPECTED

*EC_T_WORD* **wCycFrameNum**
Number of the lost cyclic frame from the ENI

*EC_T_DWORD* **dwTaskId**
Cyclic Task ID (ENI: Cyclic/TaskId). Only valid if bIsCyclicFrame is set

enum **EC_T_FRAME_RSPERR_TYPE**
*Values:*

enumerator **eRspErr_UNDEFINED**
Undefined

enumerator **eRspErr_NO_RESPONSE**
No Ethernet frame received (timeout, frame loss)

enumerator **eRspErr_WRONG_IDX**
Wrong IDX value in acyclic frame

enumerator **eRspErr_UNEXPECTED**
Unexpected frame was received

enumerator **eRspErr_FRAME_RETRY**
Ethernet frame will be re-sent (timeout, frame loss)

enumerator **eRspErr_RETRY_FAIL**
All retry mechanism fails to re-sent acyclic frames

enumerator **eRspErr_FOREIGN_SRC_MAC**
Frame with MAC from other Master received

enumerator **eRspErr_NON_ECAT_FRAME**
Non EtherCAT frame received

enumerator **eRspErr_CRC**
Ethernet frame with CRC error received

### 10.5.6 emonNotify - EC_NOTIFY_STATUS_SLAVE_ERROR

When processing cyclic frames, the EC-Monitor checks whether the ERROR bit in the AL-STATUS register is set for at least one SubDevice. In this case, this notification is triggered. If the EtherCAT® MainDevice determines the error information of the SubDevice(s) signal an error, another notification *emonNotify - EC_NOTIFY_SLAVE_ERROR_STATUS_INFO* with more precise error information is triggered.

### 10.5.7 emonNotify - EC_NOTIFY_SLAVE_ERROR_STATUS_INFO

This notification will be indicated if the EtherCAT® MainDevice reads the AL-STATUS and AL-STATUSCODE registers and the SubDevice signals an error in them. Detailed error information is stored in structure *EC_T_SLAVE_ERROR_INFO_DESC* of *EC_T_ERROR_NOTIFICATION_DESC*.

struct **EC_T_SLAVE_ERROR_INFO_DESC**

#### Public Members

*EC_T_SLAVE_PROP* **SlaveProp**
Slave properties

*EC_T_WORD* **wStatus**
Slave Status (AL Status)

*EC_T_WORD* **wStatusCode**
Error status code (AL STATUS CODE)

### 10.5.8 emonNotify - EC_NOTIFY_PDIWATCHDOG

This notification will be indicated every time a PDI watchdog error is detected. Detailed error information is stored in structure *EC_T_PDIWATCHDOG_DESC* of *EC_T_ERROR_NOTIFICATION_DESC*.

struct **EC_T_PDIWATCHDOG_DESC**

#### Public Members

*EC_T_SLAVE_PROP* **SlaveProp**
Slave properties

### 10.5.9 emonNotify - EC_NOTIFY_COMMUNICATION_TIMEOUT

This notification will be indicated if the EC-Monitor does not detect any EtherCAT® communication on the Ethernet tap for a parameterizable timeout. The descriptor of the notification contains information on which port of the Ethernet tap the timeout occurred.

struct **EC_T_COMMUNICATION_TIMEOUT_NTFY_DESC**

#### Public Members

*EC_T_BOOL* **bMainTapPortIn**
EC_TRUE: Timeout occurred at the input port of the Ethernet TAP for the EtherCAT main line

*EC_T_BOOL* **bMainTapPortOut**
EC_TRUE: Timeout occurred at the output port of the Ethernet TAP for the EtherCAT main line

**See also:**

*EC_T_MONITOR_INIT_PARMS::dwCommunicationTimeoutMsec*

### 10.5.10 emonNotify - EC_NOTIFY_TAP_LINK_STATUS

This notification will be indicated if the link status between EC-Monitor and Ethernet TAP device has changed.

struct **EC_T_TAP_LINK_STATUS_NTFY_DESC**

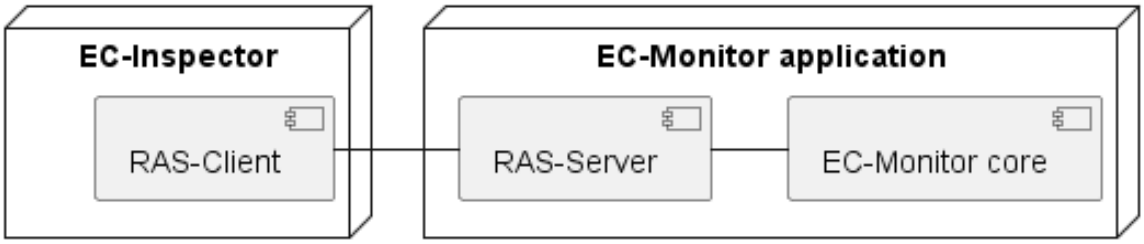
#### Public Members

*EC_T_BOOL* **bLinkConnected**
Link status of EC-Monitor - Ethernet Tap connection

# 11 RAS-Server for EC-Inspector and EC-Engineer

## 11.1 Integration Requirements

To use the diagnosis tool EC-Inspector with a customer application, some modifications have to be made during integration of the EC-Monitor. The task is to integrate and start the Remote API Server system within the custom application, which provides a socket based uplink, which later on is connected by the EC-Inspector.




An example on how to integrate the Remote API Server within the application is given with the example application, which in this case is pre-configured to listen for EC-Inspector on TCP Port 6000 when command line parameter "-sp" is given.

To clarify the steps which are needed within a custom application, the following pseudo-code segment may be used as a point of start. The Remote API Server library "EcMonitorRasServer.lib" (or respectively "EcMonitorRasServer.a") must be linked.

## 11.2 Application programming interface

### 11.2.1 emonRasSrvStart

*EC_T_DWORD* EC_NAMESPACE::**emonRasSrvStart** (
*EC_T_RAS_SERVER_PARMS* *pParms,
*EC_T_PVOID* *ppHandle
)

Initializes and starts a remote API Server Instance.

**Parameters**

- **pParms** – [in] Server start-up parameters
- **ppHandle** – [out] Handle to opened instance, used for ctrl access

**Returns**

*EC_E_NOERROR* or error code

struct **EC_T_RAS_SERVER_PARMS**

### Public Members

*EC_T_DWORD* **dwSignature**
[in] Set to EC_RAS_SERVER_SIGNATURE

*EC_T_DWORD* **dwSize**
[in] Set to sizeof(EC_T_RAS_SERVER_PARMS)

*EC_T_LOG_PARMS* **LogParms**
[in] Logging parameters

*EC_T_IPADDR* **oAddr**
[in] Remote Access Server (RAS) listen IP address

*EC_T_WORD* **wPort**
[in] Remote Access Server (RAS) listen port

*EC_T_WORD* **wMaxClientCnt**
[in] Max. clients in parallel (0: unlimited)

*EC_T_DWORD* **dwCycleTime**
[in] Cycle Time of RAS Network access (acceptor, worker)

*EC_T_DWORD* **dwCommunicationTimeout**
[in] Timeout [ms] before automatically closing connection

EC_T_CPUSET **oAcceptorThreadCpuAffinityMask**
[in] Acceptor Thread CPU affinity mask

*EC_T_DWORD* **dwAcceptorThreadPrio**
[in] Acceptor Thread Priority

*EC_T_DWORD* **dwAcceptorThreadStackSize**
[in] Acceptor Thread Stack Size

EC_T_CPUSET **oClientWorkerThreadCpuAffinityMask**
[in] Client Worker Thread CPU affinity mask

*EC_T_DWORD* **dwClientWorkerThreadPrio**
[in] Client Worker Thread Priority

*EC_T_DWORD* **dwClientWorkerThreadStackSize**
[in] Client Worker Thread Stack Size

*EC_T_DWORD* **dwMaxQueuedNotificationCnt**
[in] Amount of concurrently queue able Notifications

*EC_T_DWORD* **dwMaxParallelMbxTferCnt**
[in] Amount of concurrent active mailbox transfers

*EC_PF_NOTIFY* **pfnRasNotify**
[in] Function pointer called to notify error and status information generated by Remote API Layer

EC_T_VOID *pvRasNotifyCtxt
[in] Notification context returned while calling pfNotification

*EC_T_DWORD* dwCycErrInterval
[in] Interval which allows cyclic Notifications

*EC_T_DWORD* dwMaxQueuedNotificationSize
[in] Size of concurrent active mailbox transfers

EC_PF_CHECK_TOKEN pfCheckToken
[in] Function pointer called to check token

EC_T_VOID *pvCheckTokenContext
[in] Check token context

*EC_T_BYTE* *pbyTlsCert
[in] TLS certificate filename string

*EC_T_DWORD* dwTlsCertSize
[in] Size of TLS certeficate

EC_T_TLS_CERT_TYPE eTlsCertType
[in] TLS certeficate type

*EC_T_BYTE* *pbyTlsPrivKey
[in] TLS private key filename string

*EC_T_DWORD* dwTlsPrivKeySize
[in] Size of TLS private key

EC_T_TLS_PRIVKEY_TYPE eTlsPrivKeyType
[in] TLS certeficate type

union **EC_T_IPADDR**
*#include <EthernetServices.h>*

### Public Members

*EC_T_INNER_IPADDR* sAddr
IPv4 address (endianness independent)

*EC_T_DWORD* dwAddr
Reserved, use EC_T_IPADDR::sAddr.by instead. OS-Layer socket API calls (SOCK-ADDR_IN::sin_addr).

struct **EC_T_INNER_IPADDR**

#### Public Members

*EC_T_BYTE* **by**[4]
IPv4 address (endianness independent)

### 11.2.2 emonRasSrvStop

*EC_T_DWORD* EC_NAMESPACE::**emonRasSrvStop**(
*EC_T_PVOID* pvHandle,
*EC_T_DWORD* dwTimeout
)
Stop and de-initialize remote API Server Instance.

**Parameters**

- **pvHandle** – [in] Handle to previously started Server
- **dwTimeout** – [in] Timeout [ms] used to shut down all spawned threads, it's multiplied internally by the amount of threads spawned

**Returns**
*EC_E_NOERROR* or error code

### 11.2.3 emonRasNotify

Callback function called by Remote API Server in case of State changes or error situations.

typedef *EC_T_DWORD* (**EC_PF_NOTIFY*)(*EC_T_DWORD* dwCode, *EC_T_NOTIFYPARMS* *pParms)

### 11.2.4 emonRasNotify - EC_RAS_NOTIFY_CONNECTION

Notification about a change in the Remote API's state.

**emonRasNotify - EC_T_RAS_CONNOTIFYDESC**

**Parameter**

- `pbyInBuf`: [in] Pointer to data of type EC_T_RAS_CONNOTIFYDESC
- `dwInBufSize`: [in] Size of the input buffer in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_RAS_CONNOTIFYDESC**

#### Public Members

*EC_T_DWORD* **dwCause**
[in] Cause of state connection state change

*EC_T_DWORD* **dwCookie**
[in] Unique identification cookie of connection instance

### 11.2.5 emonRasNotify - EC_RAS_NOTIFY_REGISTER

Notification that a connected application registered a client to the EC-Monitor.

**emonRasNotify - EC_RAS_NOTIFY_REGISTER**

#### Parameter

- `pbyInBuf`: [in] Pointer to data of type EC_T_RAS_REGNOTIFYDESC
- `dwInBufSize`: [in] Size of the input buffer in bytes
- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

struct **EC_T_RAS_REGNOTIFYDESC**

#### Public Members

*EC_T_DWORD* **dwCookie**
[in] Unique identification cookie of connection instance

*EC_T_DWORD* **dwResult**
[in] Result of registration request

*EC_T_DWORD* **dwInstanceId**
[in] Master Instance client registered to

*EC_T_DWORD* **dwClientId**
[in] Client ID of registered client

### 11.2.6 emonRasNotify - EC_RAS_NOTIFY_UNREGISTER

Notification that a connected application un-registered a client from the EC-Monitor.

**emonRasNotify - EC_RAS_NOTIFY_UNREGISTER**

#### Parameter

- `pbyInBuf`: [in] Pointer to data of type EC_T_RAS_REGNOTIFYDESC
- `dwInBufSize`: [in] Size of the input buffer in bytes

- pbyOutBuf: [out] Should be set to EC_NULL
- dwOutBufSize: [in] Should be set to 0
- pdwNumOutData: [out] Should be set to EC_NULL

**See also:**

*EC_T_RAS_REGNOTIFYDESC*

### 11.2.7 emonRasNotify - EC_RAS_NOTIFY_MARSHALERROR

Notification about an error during marshalling in Remote API Server connection layer.

**emonRasNotify - EC_RAS_NOTIFY_MARSHALERRORDESC**

**Parameter**

- pbyInBuf: [in] Pointer to data of type EC_T_RAS_MARSHALERRORDESC
- dwInBufSize: [in] Size of the input buffer in bytes
- pbyOutBuf: [out] Should be set to EC_NULL
- dwOutBufSize: [in] Should be set to 0
- pdwNumOutData: [out] Should be set to EC_NULL

struct **EC_T_RAS_MARSHALERRORDESC**

#### Public Members

*EC_T_DWORD* **dwCookie**
[in] Unique identification cookie of connection instance

*EC_T_DWORD* **dwCause**
[in] Cause of the command marshalling error

*EC_T_DWORD* **dwLenStatCmd**
[in] Length of the faulty command

*EC_T_DWORD* **dwCommandCode**
[in] Command code of the faulty command

### 11.2.8 emonRasNotify - EC_RAS_NOTIFY_ACKERROR

Notification about an error during creation of ack / nack packet.

**emonRasNotify - EC_RAS_NOTIFY_ACKERROR**

**Parameter**

- pbyInBuf: [in] Pointer to EC_T_DWORD containing error code
- dwInBufSize: [in] Size of the input buffer in bytes
- pbyOutBuf: [out] Should be set to EC_NULL

- dwOutBufSize: [in] Should be set to 0
- pdwNumOutData: [out] Should be set to EC_NULL

### 11.2.9 emonRasNotify - EC_RAS_NOTIFY_NONOTIFYMEMORY

Notification given, when no empty buffers for notifications are available in the pre-allocated notification store. This points to a configuration error.

**emonRasNotify - EC_RAS_NOTIFY_NONOTIFYMEMORY**

**Parameter**

- pbyInBuf: [in] Pointer to EC_T_DWORD containing unique identification cookie of connection instance
- dwInBufSize: [in] Size of the input buffer in bytes
- pbyOutBuf: [out] Should be set to EC_NULL
- dwOutBufSize: [in] Should be set to 0
- pdwNumOutData: [out] Should be set to EC_NULL

### 11.2.10 emonRasNotify - EC_RAS_NOTIFY_STDNOTIFYMEMORYSMALL

Notification given when the buffer size for standard notifications available in pre-allocated notification store is too small to carry a specific notification. This points to a configuration error.

**emonRasNotify - EC_RAS_NOTIFY_STDNOTIFYMEMORYSMALL**

**Parameter**

- pbyInBuf: [in] Pointer to EC_T_DWORD containing unique identification cookie of connection instance
- dwInBufSize: [in] Size of the input buffer in bytes
- pbyOutBuf: [out] Should be set to EC_NULL
- dwOutBufSize: [in] Should be set to 0
- pdwNumOutData: [out] Should be set to EC_NULL

### 11.2.11 emonRasNotify - EC_RAS_NOTIFY_MBXNOTIFYMEMORYSMALL

Notification given when the buffer size for Mailbox notifications available in pre-allocated notification store is too small to carry a specific notification. This points to a configuration error. This is a serious error. If this error is given, Mailbox Transfer objects may have become out of sync and therefore no longer valid. Mailbox notifications should be dimensioned correctly, see emonRasSrvStart()

**emonRasNotify - EC_RAS_NOTIFY_MBXNOTIFYMEMORYSMALL**

**Parameter**

- pbyInBuf: [in] Pointer to EC_T_DWORD containing unique identification cookie of connection instance
- dwInBufSize: [in] Size of the input buffer in bytes

- `pbyOutBuf`: [out] Should be set to EC_NULL
- `dwOutBufSize`: [in] Should be set to 0
- `pdwNumOutData`: [out] Should be set to EC_NULL

# 12 Error Codes

## 12.1 Groups

| No. | Group | Abbr. | Description |
|---|---|---|---|
| 1 | Application Error | APP | Error within application, running the Monitor<br>E.g. API function call with invalid parameters |
| 2 | EtherCAT® network information file problem | ENI | Monitor configuration XML file mismatches SubDevice configuration on bus<br>E.g. Bus Topology Scan cannot detect all SubDevices configured within network information file |
| 3 | Monitor parameter configuration | CFG | Monitor configuration parameters erroneous<br>E.g. mailbox command queue not large enough |
| 4 | Bus/SubDevice Error | SLV | SubDevice error<br>E.g. Working Counter Error |
| 5 | Real-time Ethernet Driver | LLA | Real-time Ethernet Driver error (network interface driver)<br>E.g. Intel Pro/1000 NIC could not be found |
| 6 | Remote API | RAS | Remote API error<br>E.g. connection to Remote API server is not possible from client |
| 7 | Internal software error | ISW | Monitor internal error<br>E.g. Monitor state machine in undefined state |
| 8 | DC Monitor Sync | DCM | DC SubDevice and host time synchronization |
| 9 | Pass-Through-Server | PTS | Initialization/De-Initialization errors |
| 10 | System Setup | SYS | Errors from Operating System or obviously due to System Setup |

## 12.2 Generic Error Codes

**EC_E_NOERROR**
0x00000000: No Error

**EC_E_ERROR**
0x98110000: Unspecific Error

**EMRAS_E_ERROR**
0x98110180: Unspecific RAS Error

**EC_E_NOTSUPPORTED**
0x98110001: APP: Feature not supported (e.g. function or property not available)

**EC_E_INVALIDINDEX**
0x98110002: APP: Invalid index (e.g. CoE: invalid SDO index)

**EC_E_INVALIDOFFSET**
0x98110003: ISW: Invalid offset (e.g. invalid offset while accessing Process Data Image)

**EC_E_CANCEL**
0x98110004: APP: Cancel (e.g. EtherCAT stack should abort current mailbox transfer)

**EC_E_INVALIDSIZE**
0x98110005: APP: Invalid size

**EC_E_INVALIDDATA**
0x98110006: ISW: Invalid data (multiple error sources)

**EC_E_NOTREADY**
0x98110007: ISW: Not ready (multiple error sources)

**EC_E_BUSY**
0x98110008: APP: Busy (e.g. EtherCAT stack is currently busy and not available to process the API request. The function may be called again later)

**EC_E_ACYC_FRM_FREEQ_EMPTY**
0x98110009: ISW: Cannot queue acyclic EtherCAT command (Acyclic command queue is full. Possible solution: Increase of configuration value dwMaxQueuedEthFrames)

**EC_E_NOMEMORY**
0x9811000A: CFG: No memory left (e.g. memory full / fragmented))

**EC_E_INVALIDPARM**
0x9811000B: APP: Invalid parameter (e.g. API function called with erroneous parameter set)

**EC_E_NOTFOUND**
0x9811000C: APP: Not found (e.g. Network Information File ENI not found or API called with invalid slave ID)

**EC_E_DUPLICATE**
0x9811000D: ISW: Duplicated fixed address detected (handled internally)

**EC_E_INVALIDSTATE**
0x9811000E: ISW: Invalid state (EtherCAT stack not initialized or not configured)

**EC_E_TIMER_LIST_FULL**
0x9811000F: ISW: Cannot add slave to timer list (slave timer list full)

**EC_E_TIMEOUT**
0x98110010: Timeout

**EC_E_OPENFAILED**
0x98110011: ISW: Open failed

**EC_E_SENDFAILED**
0x98110012: LLA: Frame send failed

**EC_E_INSERTMAILBOX**
0x98110013: CFG: Insert Mailbox error (internal limit MAX_QUEUED_COE_CMDS: 20)

**EC_E_INVALIDCMD**
0x98110014: ISW: Invalid Command (Unknown mailbox command code)

**EC_E_UNKNOWN_MBX_PROTOCOL**
0x98110015: ISW: Unknown Mailbox Protocol Command (Unknown Mailbox protocol or mailbox command with unknown protocol association)

**EC_E_ACCESSDENIED**
0x98110016: ISW: Access Denied (e.g. master internal software error)

**EC_E_IDENTIFICATIONFAILED**
0x98110017: ENI: Identification failed (e.g. identification command failed)

**EC_E_LOCK_CREATE_FAILED**
0x98110018: SYS: Create lock failed (e.g. OsCreateLockTyped failed)

**EC_E_VERSION_MISMATCH**
0x98110019: APP: Version mismatch for loaded library

**EC_E_PRODKEY_INVALID**
0x9811001A: CFG: Product Key Invalid (e.g. application using protected version of the stack, which stops operation after the evaluation time limit reached if a license is not provided)

**EC_E_WRONG_FORMAT**
0x9811001B: ENI: Wrong configuration format (e.g. Network information file empty or malformed), SLV: Malformed EEPROM content

**EC_E_FEATURE_DISABLED**
0x9811001C: APP: Feature disabled (e.g. Application tried to perform a missing or disabled API function)

**EC_E_SHADOW_MEMORY**
0x9811001D: Shadow memory requested in wrong mode

**EC_E_BUSCONFIG_MISMATCH**
0x9811001E: ENI: Bus configuration mismatch (e.g. Network information file and currently connected bus topology does not match)

**EC_E_CONFIGDATAREAD**
0x9811001F: ENI: Error reading configuration file (e.g. Network information file could not be read)

**EC_E_ENI_NO_SAFEOP_OP_SUPPORT**
0x98110020: Configuration doesn't support SAFEOP and OP requested state

**EC_E_XML_CYCCMDS_MISSING**
0x98110021: ENI: Cyclic commands are missing (e.g. Network information file does not contain cyclic commands)

**EC_E_XML_ALSTATUS_READ_MISSING**
0x98110022: ENI: AL_STATUS register read missing in XML file for at least one state (e.g. Read of AL Status register is missing in cyclic part of given network information file)

**EC_E_MCSM_FATAL_ERROR**
0x98110023: ISW: Fatal internal McSm (master control state machine is in an undefined state)

**EC_E_SLAVE_ERROR**
0x98110024: SLV: Slave error (e.g. A slave error was detected. See also EC_NOTIFY_STATUS_SLAVE_ERROR and EC_NOTIFY_SLAVE_ERROR_STATUS_INFO)

**EC_E_FRAME_LOST**
0x98110025: SLV: Frame lost, IDX mismatch (EtherCAT frame(s) lost on bus, means the response was not received. In case this error shows frequently a problem with the wiring could be the cause)

**EC_E_CMD_MISSING**
0x98110026: SLV: At least one EtherCAT command is missing in the received frame (e.g. received EtherCAT

frame incomplete)

**EC_E_CYCCMD_WKC_ERROR**
0x98110027: Cyclic command WKC error

**EC_E_INVALID_DCL_MODE**
0x98110028: APP: IOCTL EC_IOCTL_DC_LATCH_REQ_LTIMVALS invalid in DCL auto read mode (this function cannot be used if DC Latching is running in mode “Auto Read”)

**EC_E_AI_ADDRESS**
0x98110029: SLV: Auto increment address increment mismatch (e.g. Network information file and bus topology doesn’t match any more. Error shows only, if an already recognized slave isn’t present any more)

**EC_E_INVALID_SLAVE_STATE**
0x9811002A: APP: Slave in invalid state, e.g. not in OP (API not callable in this state) (mailbox commands are not allowed in current slave state)

**EC_E_SLAVE_NOT_ADDRESSABLE**
0x9811002B: SLV: Station address lost (or slave missing) - FPRD to AL_STATUS failed (e.g. Slave had a power cycle)

**EC_E_CYC_CMDS_OVERFLOW**
0x9811002C: ENI: Too many cyclic commands in XML configuration file (e.g. EC_T_INIT_MASTER_PARMS.dwMaxAcycFramesQueued too small)

**EC_E_LINK_DISCONNECTED**
0x9811002D: SLV: Ethernet link cable disconnected (e.g. EtherCAT bus segment not connected to network interface)

**EC_E_MASTERCORE_INACCESSIBLE**
0x9811002E: RAS: Master core not accessible (e.g. Connection to remote server was terminated or master instance has been stopped on remote side)

**EC_E_COE_MBXSND_WKC_ERROR**
0x9811002F: SLV: CoE mailbox send: working counter (e.g. CoE mailbox couldn’t be read on slave, slave didn’t read out mailbox since last write)

**EC_E_COE_MBXRCV_WKC_ERROR**
0x98110030: SLV: CoE mailbox receive: working counter (e.g. CoE mailbox couldn’t be read from slave)

**EC_E_NO_MBX_SUPPORT**
0x98110031: APP: No mailbox support (e.g. Slave does not support mailbox access)

**EC_E_NO_COE_SUPPORT**
0x98110032: ENI: CoE protocol not supported (e.g. Configuration error or slave information file doesn’t match slave firmware)

**EC_E_NO_EOE_SUPPORT**
0x98110033: ENI: EoE protocol not supported (e.g. Configuration error or slave information file doesn’t match slave firmware)

**EC_E_NO_FOE_SUPPORT**
0x98110034: ENI: FoE protocol not supported (e.g. Configuration error or slave information file doesn’t match slave firmware)

**EC_E_NO_SOE_SUPPORT**
0x98110035: ENI: SoE protocol not supported (e.g. Configuration error or slave information file doesn't match slave firmware)

**EC_E_NO_VOE_SUPPORT**
0x98110036: ENI: VoE protocol not supported (e.g. Configuration error or slave information file doesn't match slave firmware)

**EC_E_EVAL_VIOLATION**
0x98110037: ENI: Configuration violates Evaluation limits (obsolete)

**EC_E_EVAL_EXPIRED**
0x98110038: CFG: Evaluation Time limit reached (e.g. License not provided and evaluation period (1 hour) of protected version exceeded)

**EC_E_LICENSE_MISSING**
0x98110039: License key invalid or missing

**EC_E_CFGFILENOTFOUND**
0x98110070: CFG: Network configuration file not found (e.g. path to configuration file (XML) was wrong or the file is not available)

**EC_E_EEPROMREADERROR**
0x98110071: SLV: Command error while EEPROM upload (read slave EEPROM)

**EC_E_EEPROMWRITEERROR**
0x98110072: SLV: Command error while EEPROM download (write slave EEPROM)

**EC_E_XML_CYCCMDS_SIZEMISMATCH**
0x98110073: ENI: Cyclic command wrong size (too long) (size in network configuration file (XML) does not match size of process data)

**EC_E_XML_INVALID_INP_OFF**
0x98110074: ENI: Invalid input offset in cyclic command, please check InputOffs

**EC_E_XML_INVALID_OUT_OFF**
0x98110075: ENI: Invalid output offset in cyclic command, please check OutputOffs

**EC_E_PORTCLOSE**
0x98110076: Port close failed

**EC_E_PORTOPEN**
0x98110077: Port open failed

**EC_E_SLAVE_NOT_PRESENT**
0x9811010E: APP / SLV: command not executed (slave not present on bus) (e.g. slave disappeared or was never present)

**EC_E_EEPROMRELOADERROR**
0x98110110: Command error while EEPROM reload

**EC_E_SLAVECTRLRESETERROR**
0x98110111: Command error while Reset Slave Controller

**EC_E_SYSDRIVERMISSING**
0x98110112: SYS: Cannot open system driver (e.g. system driver was not loaded)

**EC_E_BUSCONFIG_TOPOCHANGE**
0x9811011E: Bus configuration not detected, Topology changed (e.g. Topology changed while scanning bus)

**EC_E_EOE_MBX_WKC_ERROR**
0x9811011F: EoE: Mailbox receive: working counter

**EC_E_FOE_MBX_WKC_ERROR**
0x98110120: FoE: Mailbox receive: working counter

**EC_E_SOE_MBX_WKC_ERROR**
0x98110121: SoE: mailbox receive: working counter

**EC_E_AOE_MBX_WKC_ERROR**
0x98110122: AoE: Mailbox receive: working counter

**EC_E_VOE_MBX_WKC_ERROR**
0x98110123: SLV: VoE mailbox send: working counter (VoE mailbox couldn't be written)

**EC_E_EEPROMASSIGNERROR**
0x98110124: SLV: EEPROM assignment failed

**EC_E_MBX_ERROR_TYPE**
0x98110125: SLV: Unknown mailbox error code received in mailbox

**EC_E_REDLINEBREAK**
0x98110126: SLV: Redundancy line break (e.g. cable break between slaves or between EtherCAT network adapter and first slave)

**EC_E_XML_INVALID_CMD_WITH_RED**
0x98110127: ENI: Invalid EtherCAT command in cyclic frame with redundancy (e.g. BRW commands are not allowed with redundancy)

**EC_E_XML_PREV_PORT_MISSING**
0x98110128: ENI: <PreviousPort>-tag is missing (e.g. if the auto increment address is not the first slave on the bus we check if a previous port tag OR a hot connect tag is available)

**EC_E_XML_DC_CYCCMDS_MISSING**
0x98110129: DC enabled and DC cyclic commands missing (e.g. access to 0x0900)

**EC_E_DLSTATUS_IRQ_TOPOCHANGED**
0x98110130: SLV: Data link (DL) status interrupt because of changed topology (automatically handled by master)

**EC_E_PTS_IS_NOT_RUNNING**
0x98110131: PTS: Pass Through Server is not running (Pass-Through-Server was tried to be enabled/disabled or stopped without being started)

**EC_E_PTS_IS_RUNNING**
0x98110132: PTS: Pass Through Server is running (obsolete, replaced by EC_E_ADS_IS_RUNNING)

**EC_E_ADS_IS_RUNNING**
0x98110132: PTS: ADS adapter (Pass Through Server) is running (API call conflicts with ADS state (running))

**EC_E_PTS_THREAD_CREATE_FAILED**
0x98110133: PTS: Could not start the Pass Through Server

**EC_E_PTS_SOCK_BIND_FAILED**
0x98110134: PTS: The Pass Through Server could not bind the IP address with a socket (e.g. Possibly because the IPaddress (and Port) is already in use or the IP-address does not exist)

**EC_E_PTS_NOT_ENABLED**
0x98110135: PTS: The Pass Through Server is running but not enabled

**EC_E_PTS_LL_MODE_NOT_SUPPORTED**
0x98110136: PTS: The Link Layer mode is not supported by the Pass Through Server (e.g. The Master is running in interrupt mode but the Pass-Through-Server only supports polling mode)

**EC_E_VOE_NO_MBX_RECEIVED**
0x98110137: SLV: No VoE mailbox received yet from specific slave

**EC_E_DC_REF_CLOCK_SYNC_OUT_UNIT_DISABLED**
0x98110138: DC (time loop control) unit of reference clock disabled

**EC_E_DC_REF_CLOCK_NOT_FOUND**
0x98110139: SLV: Reference clock not found! May happen if reference clock is removed from network.

**EC_E_MBX_CMD_WKC_ERROR**
0x9811013B: SLV: Mailbox command working counter error (e.g. Mailbox init command Retry Count exceeded)

**EC_E_NO_AOE_SUPPORT**
0x9811013C: APP / SLV: AoE: Protocol not supported (e.g. Application calls AoE-API although not implemented at slave)

**EC_E_AOE_INV_RESPONSE_SIZE**
0x9811013D: AoE: Invalid AoE response received

**EC_E_AOE_ERROR**
0x9811013E: AoE: Common AoE device error

**EC_E_AOE_SRVNOTSUPP**
0x9811013F: AoE: Service not supported by server

**EC_E_AOE_INVALIDGRP**
0x98110140: AoE: Invalid index group

**EC_E_AOE_INVALIDOFFSET**
0x98110141: AoE: Invalid index offset

**EC_E_AOE_INVALIDACCESS**
0x98110142: AoE: Reading/writing not permitted

**EC_E_AOE_INVALIDSIZE**
0x98110143: AoE: Parameter size not correct

**EC_E_AOE_INVALIDDATA**
0x98110144: AoE: Invalid parameter value(s)

**EC_E_AOE_NOTREADY**
0x98110145: AoE: Device not in a ready state

**EC_E_AOE_BUSY**
0x98110146: AoE: Device busy

**EC_E_AOE_INVALIDCONTEXT**
0x98110147: AoE: Invalid context

**EC_E_AOE_NOMEMORY**
0x98110148: AoE: Out of memory

**EC_E_AOE_INVALIDPARM**
0x98110149: AoE: Invalid parameter value(s)

**EC_E_AOE_NOTFOUND**
0x9811014A: AoE: Not found

**EC_E_AOE_SYNTAX**
0x9811014B: AoE: Syntax error in command or file

**EC_E_AOE_INCOMPATIBLE**
0x9811014C: AoE: Objects do not match

**EC_E_AOE_EXISTS**
0x9811014D: AoE: Object already exists

**EC_E_AOE_SYMBOLNOTFOUND**
0x9811014E: AoE: Symbol not found

**EC_E_AOE_SYMBOLVERSIONINVALID**
0x9811014F: AoE: Symbol version invalid

**EC_E_AOE_INVALIDSTATE**
0x98110150: AoE: Server in invalid state

**EC_E_AOE_TRANSMODENOTSUPP**
0x98110151: AoE: AdsTransMode not supported

**EC_E_AOE_NOTIFYHNDINVALID**
0x98110152: AoE: Notification handle invalid

**EC_E_AOE_CLIENTUNKNOWN**
0x98110153: AoE: Notification client not registered

**EC_E_AOE_NOMOREHDLS**
0x98110154: AoE: No more notification handles

**EC_E_AOE_INVALIDWATCHSIZE**
0x98110155: AoE: Size for watch to big

**EC_E_AOE_NOTINIT**
0x98110156: AoE: Device not initialized

**EC_E_AOE_TIMEOUT**
0x98110157: AoE: Device has a timeout

**EC_E_AOE_NOINTERFACE**
0x98110158: AoE: Query interface failed

**EC_E_AOE_INVALIDINTERFACE**
0x98110159: AoE: Wrong interface required

**EC_E_AOE_INVALIDCLSID**
0x9811015A: AoE: Class ID invalid

**EC_E_AOE_INVALIDOBJID**
0x9811015B: AoE: Object ID invalid

**EC_E_AOE_PENDING**
0x9811015C: AoE: Request pending

**EC_E_AOE_ABORTED**
0x9811015D: AoE: Request aborted

**EC_E_AOE_WARNING**
0x9811015E: AoE: Signal warning

**EC_E_AOE_INVALIDARRAYIDX**
0x9811015F: AoE: Invalid array index

**EC_E_AOE_SYMBOLNOTACTIVE**
0x98110160: AoE: Symbol not active -> release handle and try again

**EC_E_AOE_ACCESSDENIED**
0x98110161: AoE: Access denied

**EC_E_AOE_INTERNAL**
0x98110162: AoE: Internal error

**EC_E_AOE_TARGET_PORT_NOT_FOUND**
0x98110163: AoE: Target port not found

**EC_E_AOE_TARGET_MACHINE_NOT_FOUND**
0x98110164: AoE: Target machine not found

**EC_E_AOE_UNKNOWN_CMD_ID**
0x98110165: AoE: Unknown command ID

**EC_E_AOE_PORT_NOT_CONNECTED**
0x98110166: AoE: Port not connected

**EC_E_AOE_INVALID_AMS_LENGTH**
0x98110167: AoE: Invalid AMS length

**EC_E_AOE_INVALID_AMS_ID**
0x98110168: AoE: invalid AMS Net ID

**EC_E_AOE_PORT_DISABLED**
0x98110169: AoE: Port disabled

**EC_E_AOE_PORT_CONNECTED**
0x9811016A: AoE: Port already connected

**EC_E_AOE_INVALID_AMS_PORT**
0x9811016B: AoE: Invalid AMS port

**EC_E_AOE_NO_MEMORY**
0x9811016C: AoE: No memory

**EC_E_AOE_VENDOR_SPECIFIC**
0x9811016D: AoE: Vendor specific AoE device error

**EC_E_XML_AOE_NETID_INVALID**
0x9811016E: ENI: AoE: Invalid NetID (e.g. Error from Configuration Tool)

**EC_E_MAX_BUS_SLAVES_EXCEEDED**
0x9811016F: CFG: Error: Maximum number of bus slave has been exceeded (The maximum number of preallocated bus slave objects is too small. The maximum number can be adjusted by the master initialization parameter EC_T_INITMASTERPARMS.dwMaxBusSlaves)

**EC_E_MBXERR_SYNTAX**
0x98110170: SLV: Mailbox error: Syntax of 6 octet Mailbox header is wrong (Slave error mailbox return value: 0x01)

**EC_E_MBXERR_UNSUPPORTEDPROTOCOL**
0x98110171: SLV: Mailbox error: The Mailbox protocol is not supported (Slave error mailbox return value: 0x02)

**EC_E_MBXERR_INVALIDCHANNEL**
0x98110172: SLV: Mailbox error: Field contains wrong value (Slave error mailbox return value: 0x03)

**EC_E_MBXERR_SERVICENOTSUPPORTED**
0x98110173: SLV: Mailbox error: The addressed service in the mailbox protocol is not supported (Slave error mailbox return value: 0x04)

**EC_E_MBXERR_INVALIDHEADER**
0x98110174: SLV: Mailbox error: The mailbox protocol header of the mailbox protocol is wrong (Slave error mailbox return value: 0x05)

**EC_E_MBXERR_SIZETOOSHORT**
0x98110175: SLV: Mailbox error: Length of received mailbox data is too short (Slave error mailbox return value: 0x06)

**EC_E_MBXERR_NOMOREMEMORY**
0x98110176: SLV: Mailbox error: Mailbox protocol can not be processed because of limited resources (Slave error mailbox return value: 0x07)

**EC_E_MBXERR_INVALIDSIZE**
0x98110177: SLV: Mailbox error: The length of data is inconsistent (Slave error mailbox return value: 0x08)

**EC_E_DC_SLAVES_BEFORE_REF_CLOCK**
0x98110178: ENI: Slaves with DC configured present on bus before reference clock (e.g. The first DC Slave was not configured as potential reference clock)

**EC_E_DATA_TYPE_CONVERSION_FAILED**
0x98110179: Data type conversion failed

**EC_E_LINE_CROSSED**
0x9811017B: Line crossed (cabling wrong)

**EC_E_LINE_CROSSED_SLAVE_INFO**
0x9811017C: Line crossed at slave (obsolete)

**EC_E_ADO_NOT_SUPPORTED**
0x9811017E: SLV: ADO for slave identification not supported (e.g. Request ID mechanism (ADO 0x134) not supported by slave)

**EC_E_FRAMELOSS_AFTER_SLAVE**
0x9811017F: Frameloss after Slave (opening port destroys communication)

**EC_E_OEM_SIGNATURE_MISMATCH**
0x98130008: ENI, OEM: Manufacturer signature mismatch

**EC_E_ENI_ENCRYPTION_WRONG_VERSION**
0x98130009: ENI, OEM: ENI encryption algorithm version not supported

**EC_E_ENI_ENCRYPTED**
0x9813000A: OEM: Loading encrypted ENI needs OEM key

**EC_E_OEM_KEY_MISMATCH**
0x9813000B: RAS, APP: OEM key mismatch

**EC_E_OEM_KEY_MISSING**
0x9813000C: APP: OEM key access needs OEM key set (e.g. Application must call esSetOemKey (HiL) or set EC_T_LINK_PARMS_SIMULATOR::qwOemKey (SiL))

**EC_E_S2SMBX_NOT_CONFIGURED**
0x98130020: S2S: Not Configured

**EC_E_S2SMBX_NO_MEMORY**
0x98130021: S2S: No Memory

**EC_E_S2SMBX_NO_DESCRIPTOR**
0x98130022: S2S: No Descriptor

**EC_E_S2SMBX_DEST_SLAVE_NOT_FOUND**
0x98130023: S2S: Destination Slave not found

**EC_E_MASTER_RED_STATE_INACTIVE**
0x98130024: APP: Master Redundancy State is INACTIVE (e.g. API not allowed in current Master Redundancy State)

**EC_E_MASTER_RED_STATE_ACTIVE**
0x98130025: APP: Master Redundancy State is ACTIVE (e.g. API not allowed in current Master Redundancy State)

**EC_E_JUNCTION_RED_LINE_BREAK**
0x98130026: Junction redundancy line break

**EC_E_VALIDATION_ERROR**
0x98130027: Validation error (validation data mismatch)

**EC_E_TIMEOUT_WAITING_FOR_DC**
0x98130028: Timeout waiting for DC

**EC_E_TIMEOUT_WAITING_FOR_DCM**
0x98130029: Timeout waiting for DCM

**EC_E_SIGNATURE_MISMATCH**
0x98130030: Signature mismatch

**EC_E_PDIWATCHDOG**
0x98130031: PDI watchdog expired

**EC_E_BAD_CONNECTION**
0x98130032: Bad connection

**EC_E_XML_INCONSISTENT**
0x98130033: ENI: Inconsistent content

## 12.3 DCM Error Codes

**DCM_E_ERROR**
0x981201C0: Unspecific DCM Error

**DCM_E_NOTINITIALIZED**
0x981201C1: Not initialized

**DCM_E_MAX_CTL_ERROR_EXCEED**
0x981201C2: DCM controller - synchronization out of limit

**DCM_E_NOMEMORY**
0x981201C3: Not enough memory

**DCM_E_INVALID_HWLAYER**
0x981201C4: Hardware layer - (BSP) invalid

**DCM_E_TIMER_MODIFY_ERROR**
0x981201C5: Hardware layer - error modifying timer

**DCM_E_TIMER_NOT_RUNNING**
0x981201C6: Hardware layer - timer not running

**DCM_E_WRONG_CPU**
0x981201C7: Hardware layer - function called on wrong CPU

**DCM_E_INVALID_SYNC_PERIOD**
0x981201C8: Invalid DC sync period length (invalid clock master?)

**DCM_E_INVALID_SETVAL**
0x981201C9: DCM controller SetVal too small

**DCM_E_DRIFT_TO_HIGH**
0x981201CA: DCM controller - Drift between local timer and ref clock to high

**DCM_E_BUS_CYCLE_WRONG**
0x981201CB: DCM controller - Bus cycle time (dwBusCycleTimeUsec) doesn't match real cycle

**DCX_E_NO_EXT_CLOCK**
0x981201CC: DCX controller - No external synchronization clock found

**DCM_E_INVALID_DATA**
0x981201CD: DCM controller - Invalid data

## 12.4 ADS over EtherCAT® (AoE) Error Codes

**EC_E_AOE_NO_RTIME**
0x9813000D: AoE: No Rtime

**EC_E_AOE_LOCKED_MEMORY**
0x9813000E: AoE: Allocation locked memory

**EC_E_AOE_MAILBOX**
0x9813000F: AoE: Insert mailbox error

**EC_E_AOE_WRONG_HMSG**
0x98130010: AoE: Wrong receive HMSG

**EC_E_AOE_BAD_TASK_ID**
0x98130011: AoE: Bad task ID

**EC_E_AOE_NO_IO**
0x98130012: AoE: No IO

**EC_E_AOE_UNKNOWN_AMS_COMMAND**
0x98130013: AoE: Unknown ADS command

**EC_E_AOE_WIN32**
0x98130014: AoE: Win 32 error

**EC_E_AOE_LOW_INSTALL_LEVEL**
0x98130015: AoE: Low installation level

**EC_E_AOE_NO_DEBUG**
0x98130016: AoE: No debug available

**EC_E_AOE_AMS_SYNC_WIN32**
0x98130017: AoE: Sync Win 32 error

**EC_E_AOE_AMS_SYNC_TIMEOUT**
0x98130018: AoE: Sync Timeout

**EC_E_AOE_AMS_SYNC_AMS**
0x98130019: AoE: Sync AMS error

**EC_E_AOE_AMS_SYNC_NO_INDEX_MAP**
0x9813001A: AoE: Sync no index map

**EC_E_AOE_TCP_SEND**
0x9813001B: AoE: TCP send error

**EC_E_AOE_HOST_UNREACHABLE**
0x9813001C: AoE: Host unreachable

**EC_E_AOE_INVALIDAMSFRAGMENT**
0x9813001D: AoE: Invalid AMS fragment

**EC_E_AOE_NO_LOCKED_MEMORY**
0x9813001E: AoE: No allocation locked memory

**EC_E_AOE_MAILBOX_FULL**
0x9813001F: AoE: Mailbox full

## 12.5 CAN application protocol over EtherCAT® (CoE) SDO Error Codes

**EC_E_SDO_ABORTCODE_TOGGLE**
0x98110040: SLV: SDO: Toggle bit not alternated (CoE abort code 0x05030000 of slave)

**EC_E_SDO_ABORTCODE_TIMEOUT**
0x98110041: SLV: SDO: Protocol timed out (CoE abort code 0x05040000 of slave)

**EC_E_SDO_ABORTCODE_CCS_SCS**
0x98110042: SLV: SDO: Client/server command specifier not valid or unknown (CoE abort code 0x05040001 of slave)

**EC_E_SDO_ABORTCODE_BLK_SIZE**
0x98110043: SLV: SDO: Invalid block size (block mode only) (CoE abort code 0x05040002 of slave)

**EC_E_SDO_ABORTCODE_SEQNO**
0x98110044: SLV: SDO: Invalid sequence number (block mode only) (CoE abort code 0x05040003 of slave)

**EC_E_SDO_ABORTCODE_CRC**
0x98110045: SLV: SDO: CRC error (block mode only) (CoE abort code 0x05040004 of slave)

**EC_E_SDO_ABORTCODE_MEMORY**
0x98110046: SLV: SDO: Out of memory (CoE abort code 0x05040005 of slave)

**EC_E_SDO_ABORTCODE_ACCESS**
0x98110047: SLV: SDO: Unsupported access to an object (CoE abort code 0x06010000 of slave)

**EC_E_SDO_ABORTCODE_WRITEONLY**
0x98110048: SLV: SDO: Attempt to read a write only object (CoE abort code 0x06010001 of slave)

**EC_E_SDO_ABORTCODE_READONLY**
0x98110049: SLV: SDO: Attempt to write a read only object (CoE abort code 0x06010002 of slave)

**EC_E_SDO_ABORTCODE_INDEX**
0x9811004A: SLV: SDO: Object does not exist in the object dictionary (CoE abort code 0x06020000 of slave)

**EC_E_SDO_ABORTCODE_PDO_MAP**
0x9811004B: SLV: SDO: Object cannot be mapped to the PDO (CoE abort code 0x06040041 of slave)

**EC_E_SDO_ABORTCODE_PDO_LEN**
0x9811004C: SLV: SDO: The number and length of the objects to be mapped would exceed PDO length (CoE abort code 0x06040042 of slave)

**EC_E_SDO_ABORTCODE_P_INCOMP**
0x9811004D: SLV: SDO: General parameter incompatibility reason (CoE abort code 0x06040043 of slave)

**EC_E_SDO_ABORTCODE_I_INCOMP**
0x9811004E: SLV: SDO: General internal incompatibility in the device (CoE abort code 0x06040047 of slave)

**EC_E_SDO_ABORTCODE_HARDWARE**
0x9811004F: SLV: SDO: Access failed due to a hardware error (CoE abort code 0x06060000 of slave)

**EC_E_SDO_ABORTCODE_DATA_LENGTH_NOT_MATCH**
0x98110050: SLV: SDO: Data type does not match, length of service parameter does not match (CoE abort code 0x06070010 of slave)

**EC_E_SDO_ABORTCODE_DATA_LENGTH_TOO_HIGH**
0x98110051: SLV: SDO: Data type does not match, length of service parameter too high (CoE abort code 0x06070012 of slave)

**EC_E_SDO_ABORTCODE_DATA_LENGTH_TOO_LOW**
0x98110052: SLV: SDO: Data type does not match, length of service parameter too low (CoE abort code 0x06070013 of slave)

**EC_E_SDO_ABORTCODE_OFFSET**
0x98110053: SLV: SDO: Sub-index does not exist (CoE abort code 0x06090011 of slave)

**EC_E_SDO_ABORTCODE_VALUE_RANGE**
0x98110054: SLV: SDO: Value range of parameter exceeded (only for write access) (CoE abort code 0x06090030 of slave)

**EC_E_SDO_ABORTCODE_VALUE_TOO_HIGH**
0x98110055: SLV: SDO: Value of parameter written too high (CoE abort code 0x06090031 of slave)

**EC_E_SDO_ABORTCODE_VALUE_TOO_LOW**
0x98110056: SLV: SDO: Value of parameter written too low (CoE abort code 0x06090032 of slave)

**EC_E_SDO_ABORTCODE_MINMAX**
0x98110057: SLV: SDO: Maximum value is less than minimum value (CoE abort code 0x06090036 of slave)

**EC_E_SDO_ABORTCODE_GENERAL**
0x98110058: SLV: SDO: General error (CoE abort code 0x08000000 of slave)

**EC_E_SDO_ABORTCODE_TRANSFER**
0x98110059: SLV: SDO: Data cannot be transferred or stored to the application (CoE abort code 0x08000020 of slave)

**EC_E_SDO_ABORTCODE_TRANSFER_LOCAL_CONTROL**
0x9811005A: SLV: SDO: Data cannot be transferred or stored to the application because of local control (CoE abort code 0x08000021 of slave)

**EC_E_SDO_ABORTCODE_TRANSFER_DEVICE_STATE**
0x9811005B: SLV: SDO: Data cannot be transferred or stored to the application because of the present device state (CoE abort code 0x08000022 of slave)

**EC_E_SDO_ABORTCODE_DICTIONARY**
0x9811005C: SLV: SDO: Object dictionary dynamic generation fails or no object dictionary is present (e.g. object dictionary is generated from file and generation fails because of an file error) (CoE abort code 0x08000023 of slave)

**EC_E_SDO_ABORTCODE_UNKNOWN**
0x9811005D: SLV: SDO: Unknown code (Unknown CoE abort code of slave)

**EC_E_SDO_ABORTCODE_MODULE_ID_LIST_NOT_MATCH**
0x9811005E: Detected Module Ident List (0xF030) and Configured Module Ident list (0xF050) does not match

**EC_E_SDO_ABORTCODE_SI_NOT_WRITTEN**
0x98130004: SLV: SDO: Sub Index cannot be written, SI0 must be 0 for write access (CoE abort code 0x06010003 of slave)

**EC_E_SDO_ABORTCODE_CA_TYPE_MISM**
0x98130005: SLV: SDO: Complete access not supported for objects of variable length such as ENUM object types (CoE abort code 0x06010004 of slave)

**EC_E_SDO_ABORTCODE_OBJ_TOO_BIG**
0x98130006: SLV: SDO: Object length exceeds mailbox size (CoE abort code 0x06010005 of slave)

**EC_E_SDO_ABORTCODE_PDO_MAPPED**
0x98130007: SLV: SDO: Object mapped to RxPDO, SDO Download blocked (CoE abort code 0x06010006 of slave)

## 12.6 File Transfer over EtherCAT® (FoE) Error Codes

**EC_E_FOE_ERRCODE_NOTDEFINED**
0x98110060: SLV: ERROR FoE: not defined (FoE Error Code 0 (0x8000) of slave)

**EC_E_FOE_ERRCODE_NOTFOUND**
0x98110061: SLV: ERROR FoE: not found (FoE Error Code 1 (0x8001) of slave)

**EC_E_FOE_ERRCODE_ACCESS**
0x98110062: SLV: ERROR FoE: access denied (FoE Error Code 2 (0x8002) of slave)

**EC_E_FOE_ERRCODE_DISKFULL**
0x98110063: SLV: ERROR FoE: disk full (FoE Error Code 3 (0x8003) of slave)

**EC_E_FOE_ERRCODE_ILLEGAL**
0x98110064: SLV: ERROR FoE: illegal (FoE Error Code 4 (0x8004) of slave)

**EC_E_FOE_ERRCODE_PACKENO**
0x98110065: SLV: ERROR FoE: packet number wrong (FoE Error Code 5 (0x8005) of slave)

**EC_E_FOE_ERRCODE_EXISTS**
0x98110066: SLV: ERROR FoE: already exists (FoE Error Code 6 (0x8006) of slave)

**EC_E_FOE_ERRCODE_NOUSER**
0x98110067: SLV: ERROR FoE: no user (FoE Error Code 7 (0x8007) of slave)

**EC_E_FOE_ERRCODE_BOOTSTRAPONLY**
0x98110068: SLV: ERROR FoE: bootstrap only (FoE Error Code 8 (0x8008) of slave)

**EC_E_FOE_ERRCODE_NOTINBOOTSTRAP**
0x98110069: SLV: ERROR FoE: Downloaded file name is not valid in Bootstrap state (FoE Error Code 9 (0x8009) of slave)

**EC_E_FOE_ERRCODE_INVALIDPASSWORD**
0x9811006A: SLV: ERROR FoE: no rights (FoE Error Code 10 (0x800A) of slave)

**EC_E_FOE_ERRCODE_PROGERROR**
0x9811006B: SLV: ERROR FoE: program error (FoE Error Code 11 (0x800B) of slave)

**EC_E_FOE_ERRCODE_INVALID_CHECKSUM**
0x9811006C: FoE: Wrong checksum

**EC_E_FOE_ERRCODE_INVALID_FIRMWARE**
0x9811006D: SLV: ERROR FoE: Firmware does not fit for Hardware (FoE Error Code 13 (0x800D) of slave)

**EC_E_FOE_ERRCODE_NO_FILE**
0x9811006F: SLV: ERROR FoE: No file to read (FoE Error Code 15 (0x800F) of slave)

**EC_E_NO_FOE_SUPPORT_BS**
0x9811010F: APP: ERROR FoE: Protocol not supported in boot strap (e.g. Application requested FoE in Bootstrap although slave does not support this)

**EC_E_FOE_ERRCODE_MAX_FILE_SIZE**
0x9811017A: APP: ERROR FoE: File is bigger than max file size (e.g. Slave returned more data than the buffer provided by application can store.)

**EC_E_FOE_ERRCODE_FILE_HEAD_MISSING**
0x98130001: SLV: ERROR FoE: File header does not exist (FoE Error Code 16 (0x8010) of slave)

**EC_E_FOE_ERRCODE_FLASH_PROBLEM**
0x98130002: SLV: ERROR FoE: Flash problem (FoE Error Code 17 (0x8011) of slave)

**EC_E_FOE_ERRCODE_FILE_INCOMPATIBLE**
0x98130003: SLV: ERROR FoE: File incompatible (FoE Error Code 18 (0x8012) of slave)

## 12.7 Servo Drive Profil over EtherCAT® (SoE) Error Codes

**EC_E_SOE_ERRORCODE_INVALID_ACCESS**
0x98110078: ERROR SoE: Invalid access to element 0

**EC_E_SOE_ERRORCODE_NOT_EXIST**
0x98110079: ERROR SoE: Does not exist

**EC_E_SOE_ERRORCODE_INVL_ACC_ELEM1**
0x9811007A: ERROR SoE: Invalid access to element 1

**EC_E_SOE_ERRORCODE_NAME_NOT_EXIST**
0x9811007B: ERROR SoE: Name does not exist

**EC_E_SOE_ERRORCODE_NAME_UNDERSIZE**
0x9811007C: ERROR SoE: Name undersize in transmission

**EC_E_SOE_ERRORCODE_NAME_OVERSIZE**
0x9811007D: ERROR SoE: Name oversize in transmission

**EC_E_SOE_ERRORCODE_NAME_UNCHANGE**
0x9811007E: ERROR SoE: Name unchangeable

**EC_E_SOE_ERRORCODE_NAME_WR_PROT**
0x9811007F: ERROR SoE: Name currently write-protected

**EC_E_SOE_ERRORCODE_UNDERS_TRANS**
0x98110080: ERROR SoE: Attribute undersize in transmission

**EC_E_SOE_ERRORCODE_OVERS_TRANS**
0x98110081: ERROR SoE: Attribute oversize in transmission

**EC_E_SOE_ERRORCODE_ATTR_UNCHANGE**
0x98110082: ERROR SoE: Attribute unchangeable

**EC_E_SOE_ERRORCODE_ATTR_WR_PROT**
0x98110083: ERROR SoE: Attribute currently write-protected

**EC_E_SOE_ERRORCODE_UNIT_NOT_EXIST**
0x98110084: ERROR SoE: Unit does not exist

**EC_E_SOE_ERRORCODE_UNIT_UNDERSIZE**
0x98110085: ERROR SoE: Unit undersize in transmission

**EC_E_SOE_ERRORCODE_UNIT_OVERSIZE**
0x98110086: ERROR SoE: Unit oversize in transmission

**EC_E_SOE_ERRORCODE_UNIT_UNCHANGE**
0x98110087: ERROR SoE: Unit unchangeable

**EC_E_SOE_ERRORCODE_UNIT_WR_PROT**
0x98110088: ERROR SoE: Unit currently write-protected

**EC_E_SOE_ERRORCODE_MIN_NOT_EXIST**
0x98110089: ERROR SoE: Minimum input value does not exist

**EC_E_SOE_ERRORCODE_MIN_UNDERSIZE**
0x9811008A: ERROR SoE: Minimum input value undersize in transmission

**EC_E_SOE_ERRORCODE_MIN_OVERSIZE**
0x9811008B: ERROR SoE: Minimum input value oversize in transmission

**EC_E_SOE_ERRORCODE_MIN_UNCHANGE**
0x9811008C: ERROR SoE: Minimum input value unchangeable

**EC_E_SOE_ERRORCODE_MIN_WR_PROT**
0x9811008D: ERROR SoE: Minimum input value currently write-protected

**EC_E_SOE_ERRORCODE_MAX_NOT_EXIST**
0x9811008E: ERROR SoE: Maximum input value does not exist

**EC_E_SOE_ERRORCODE_MAX_UNDERSIZE**
0x9811008F: ERROR SoE: Maximum input value undersize in transmission

**EC_E_SOE_ERRORCODE_MAX_OVERSIZE**
0x98110090: ERROR SoE: Maximum input value oversize in transmission

**EC_E_SOE_ERRORCODE_MAX_UNCHANGE**
0x98110091: ERROR SoE: Maximum input value unchangeable

**EC_E_SOE_ERRORCODE_MAX_WR_PROT**
0x98110092: ERROR SoE: Maximum input value currently write-protected

**EC_E_SOE_ERRORCODE_DATA_NOT_EXIST**
0x98110093: ERROR SoE: Data item does not exist

**EC_E_SOE_ERRORCODE_DATA_UNDERSIZE**
0x98110094: ERROR SoE: Data item undersize in transmission

**EC_E_SOE_ERRORCODE_DATA_OVERSIZE**
0x98110095: ERROR SoE: Data item oversize in transmission

**EC_E_SOE_ERRORCODE_DATA_UNCHANGE**
0x98110096: ERROR SoE: Data item unchangeable

**EC_E_SOE_ERRORCODE_DATA_WR_PROT**
0x98110097: ERROR SoE: Data item currently write-protected

**EC_E_SOE_ERRORCODE_DATA_MIN_LIMIT**
0x98110098: ERROR SoE: Data item less than minimum input value limit

**EC_E_SOE_ERRORCODE_DATA_MAX_LIMIT**
0x98110099: ERROR SoE: Data item exceeds maximum input value limit

**EC_E_SOE_ERRORCODE_DATA_INCOR**
0x9811009A: ERROR SoE: Data item incorrect

**EC_E_SOE_ERRORCODE_PASWD_PROT**
0x9811009B: ERROR SoE: Data item protected by password

**EC_E_SOE_ERRORCODE_TEMP_UNCHANGE**
0x9811009C: ERROR SoE: Data item temporary unchangeable (in AT or MDT)

**EC_E_SOE_ERRORCODE_INVL_INDIRECT**
0x9811009D: ERROR SoE: Invalid indirect

**EC_E_SOE_ERRORCODE_TEMP_UNCHANGE1**
0x9811009E: ERROR SoE: Data item temporary unchangeable (parameter or opmode)

**EC_E_SOE_ERRORCODE_ALREADY_ACTIVE**
0x9811009F: ERROR SoE: Command already active

**EC_E_SOE_ERRORCODE_NOT_INTERRUPT**
0x98110100: ERROR SoE: Command not interruptible

**EC_E_SOE_ERRORCODE_CMD_NOT_AVAIL**
0x98110101: ERROR SoE: Command not available (in this phase)

**EC_E_SOE_ERRORCODE_CMD_NOT_AVAIL1**
0x98110102: ERROR SoE: Command not available (invalid parameter)

**EC_E_SOE_ERRORCODE_DRIVE_NO**
0x98110103: ERROR SoE: Response drive number not identical with requested drive number

**EC_E_SOE_ERRORCODE_IDN**
0x98110104: ERROR SoE: Response IDN not identical with requested IDN

**EC_E_SOE_ERRORCODE_FRAGMENT_LOST**
0x98110105: ERROR SoE: At least one fragment lost

**EC_E_SOE_ERRORCODE_BUFFER_FULL**
0x98110106: ERROR SoE: RX buffer full (EtherCAT call with to small data-buffer)

**EC_E_SOE_ERRORCODE_NO_DATA**
0x98110107: ERROR SoE: No data state

**EC_E_SOE_ERRORCODE_NO_DEFAULT_VALUE**
0x98110108: ERROR SoE: No default value

**EC_E_SOE_ERRORCODE_DEFAULT_LONG**
0x98110109: ERROR SoE: Default value transmission too long

**EC_E_SOE_ERRORCODE_DEFAULT_WP**
0x9811010A: ERROR SoE: Default value cannot be changed, read only

**EC_E_SOE_ERRORCODE_INVL_DRIVE_NO**
0x9811010B: ERROR SoE: Invalid drive number

**EC_E_SOE_ERRORCODE_GENERAL_ERROR**
0x9811010C: ERROR SoE: General error

**EC_E_SOE_ERRCODE_NO_ELEM_ADR**
0x9811010D: ERROR SoE: No element addressed

## 12.8 Remote API Error Codes

**EC_E_SOCKET_DISCONNECTED**
0x9811017D: RAS: Socket disconnected (e.g. IP connection terminated or lost)

**EMRAS_E_INVALIDCOOKIE**
0x98110181: RAS: Invalid Cookie (e.g.obsolete)

**EMRAS_E_MULSRVDISMULCON**
0x98110183: RAS: Connect 2nd server denied because Multi Server support is disabled (obsolete)

**EMRAS_E_LOGONCANCELLED**
0x98110184: RAS: Logon canceled (Server-side connection reject while opening a client connection.)

**EMRAS_E_INVALIDVERSION**
0x98110186: RAS: Invalid Version (Connection reject because of using mismatching protocol versions on client and server side)

**EMRAS_E_INVALIDACCESSCONFIG**
0x98110187: RAS: Access configuration is invalid (e.g. SPoC access configuration invalid)

**EMRAS_E_ACCESSLESS**
0x98110188: RAS: No access to this call at this access level (e.g. a higher SPoC access level is needed to use the called Remote API function)

**EMRAS_E_INVALIDDATARECEIVED**
0x98110189: RAS: Invalid data received (communication corrupted)

**EMRAS_EVT_SERVERSTOPPED**
0x98110191: RAS: Server stopped (e.g. connection dropped because of Remote API Server stop)

**EMRAS_EVT_WDEXPIRED**
0x98110192: RAS: Watchdog expired (e.g. connection dropped because of missing keep-alive messages)

**EMRAS_EVT_RECONEXPIRED**
0x98110193: RAS: Reconnect expired (obsolete)

**EMRAS_EVT_CLIENTLOGON**
0x98110194: RAS Server: Client logged on

**EMRAS_EVT_RECONNECT**
0x98110195: RAS: obsolete

**EMRAS_EVT_SOCKCHANGE**
0x98110196: RAS: Socket exchanged after reconnect (obsolete)

**EMRAS_EVT_CLNTDISC**
0x98110197: RAS: Client disconnect

**EMRAS_E_ACCESS_NOT_FOUND**
0x98110198: RAS: Access not configured for this call (e.g. SPoC access configuration missing)

**EMRAS_E_TOKEN_MISSING**
0x98110199: RAS: Token missing

**EMRAS_E_TOKEN_INVALID**
0x9811019A: RAS: Token invalid

**EMRAS_E_TOKEN_DENIED**
0x9811019B: RAS: Token denied

**EMRAS_E_TLS_CERTIFICATE_ERROR**
0x9811019C: RAS: TLS certificate error

**EMRAS_E_TLS_PRIVATEKEY_ERROR**
0x9811019D: RAS: TLS private key error

**EMRAS_E_TLS_HANDSHAKE_FAILED**
0x9811019E: RAS: TLS handshake failed