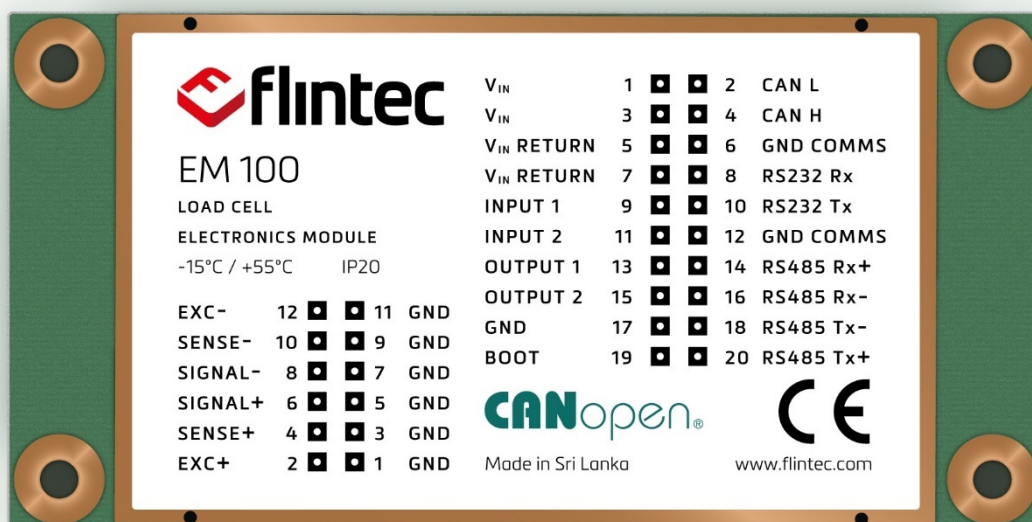


User Manual



EM100-A

v1.2 June 2019

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1. EM100 Module

1.1. Introduction

The Electronics Module, EM100-A, is a precise amplifier with integral 24-bit sigma-delta analogue-to-digital converter for weighing and force measurements with strain gauge sensors. The module includes an extensive selection of standard weighing and calibration functions for accurate static or dynamic weighing applications. It is therefore the ideal instrument for high-precision and high-resolution measurements applications using AC excitation to achieve outstanding stability and performance.

The EM100-A model is an approved accuracy class II module examined under OIML R76. The measurement module forms part of an approved (*'legal-for-trade'*) weighing system. The EM100-A can be used in *'legal-for-trade'* and industrial applications.

The device features a CAN interface with support for the CANopen protocol as well as full-duplex RS-232 and RS-485 interfaces. A USB interface has been included for ease of use and is only for configuration, setup and firmware upgrade.

Communication to the module is based on ASCII characters sent to a variety of serial interfaces making it easy to connect to a PC, PLC or other devices. Setup of the module is simple using a terminal emulation program or FDC application software (*available from Flintec.com*).

1.2. Disclaimer

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NOTICE: The contents of this manual are subject to change without notice.

1.3. Safety Instructions



CAUTION: READ this manual BEFORE operating or servicing this equipment. FOLLOW these instructions carefully. SAVE this manual for future reference. DO NOT allow untrained personnel to operate, clean, inspect, maintain, service, or tamper with this equipment. ALWAYS DISCONNECT this equipment from the power source before cleaning or performing maintenance.

CALL Flintec for parts, information, and service.



WARNING: Only permit qualified personnel to service this equipment. Exercise care when making checks, tests and adjustments that must be made with power on. Failing to observe these precautions can result in bodily harm.



WARNING: For continued protection against shock hazard connect to properly grounded outlet only. Do not remove the ground prong.



WARNING: Disconnect all power to this unit before removing the fuse or servicing.



WARNING: Before connecting/disconnecting any internal electronic components or interconnecting wiring between electronic equipment always remove power and wait at least thirty (30) seconds before any connections or disconnections are made. Failure to observe these precautions could result in damage to or destruction of the equipment or bodily harm.



CAUTION: Observe precautions for handling electrostatic sensitive devices.

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2. Specification

EM100-A	
Application	Accurate-Weighing (NAWI)
Bridge Excitation	5V _{AC}
Load-Cell/Sensor	4-Wire or 6-Wire
Accuracy Class	II
Weighing Range	Single Interval, Multi-Range or Multi-Interval
Verification Scale Interval	20,000
Minimum Input Sensitivity	0.02μV/Count
Certified Accuracy	0.1μV/vsi
Resolution (External)	±1,000,000 counts
Minimum Load Cell Impedance	58.3Ω (1x350Ω; 4x350Ω; 4x1100Ω; 6x350Ω)
Maximum Load Cell Impedance	1,100Ω
Maximum Analogue Input Range	±15mV Bipolar (±3mV/V @ 5V _{AC} Excitation)
Conversion Rate	2.5sps to 80sps (Dependent on Settings)
Communication Protocols	USB CDC (Config & Setup Only)
RS-232 (N-bits, Parity, Stop-bit)	9.6k, 14.4k, 19.2k, 38.4k, 57.6k, 115.2k, 230.4k, & 460.8kBits/s (8-N-1)
RS-485 (Half & Full-Duplex)	9.6k, 14.4k, 19.2k, 38.4k, 57.6k, 115.2k, 230.4k, & 460.8kBits/s
CANopen Data Rate	10k, 20k, 50k, 125k, 250k, 500k, 800k, 1MBit/s
Power Supply	+9.6V _{DC} to +32V _{DC}
Digital Input (30V _{DC} max, >10kΩ Input Impedance)	2
Digital Output (Open-Drain +30V _{DC} max, 300mWmax)	2
Filter Mode	Selectable FIR/IIR Filters
Calibration	Electronic Calibration in mV/V (eCal) or Test Weight(s)
Weight/Measurement Functions	Zero; Gross; Tare; Net; Filter etc.
Operating Temperature Range	-15°C to +55°C
Storage Temperature	-30°C to +70°C
Regulations/Standards	OIML R-761-1:2006 & EN 45501:2015
Dimensions (L x W x D in mm)	80 x 40 x 16.6mm
Weight	30g approx.
DIN Rail Mounting	Optional Adaptor Board Available
IP Protection Rating	IP20

3. Getting Started

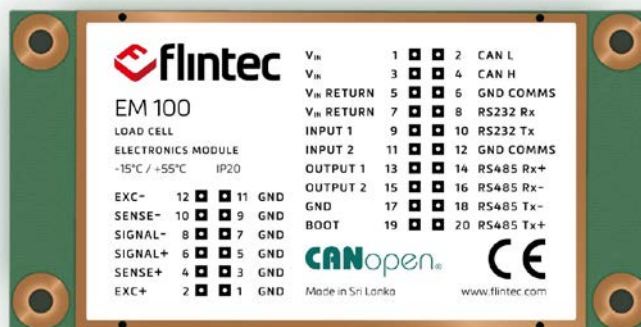
You will require:

- PC or PLC with RS-232, RS-485 or CANopen communication ports.
- Load-cell/scale with test weights or a load-cell simulator.
- +12V_{DC} to +24V_{DC} power supply capable of delivering approximately 200mA.
- A suitable ASCII communication software e.g. Hyper-Terminal, Putty, TeraTerm etc. or Flintec Device Configuration (FDC) application software. Download the latest copy of FDC from the Flintec website (www.flintec.com).

Note: The Flintec FDC application was developed in-conjunction with the '**Peak System**' USB to CAN adaptor. If using the CANopen interface AND the FDC application, only use the '**Peak System**' adaptor. See website below for more details. For all other interfaces listed above, generic adaptors can be used in accordance with the manufacturer's instructions and drivers.

<https://www.peak-system.com/PCAN-USB.199.0.html?&L=1>

3.1. Labelling

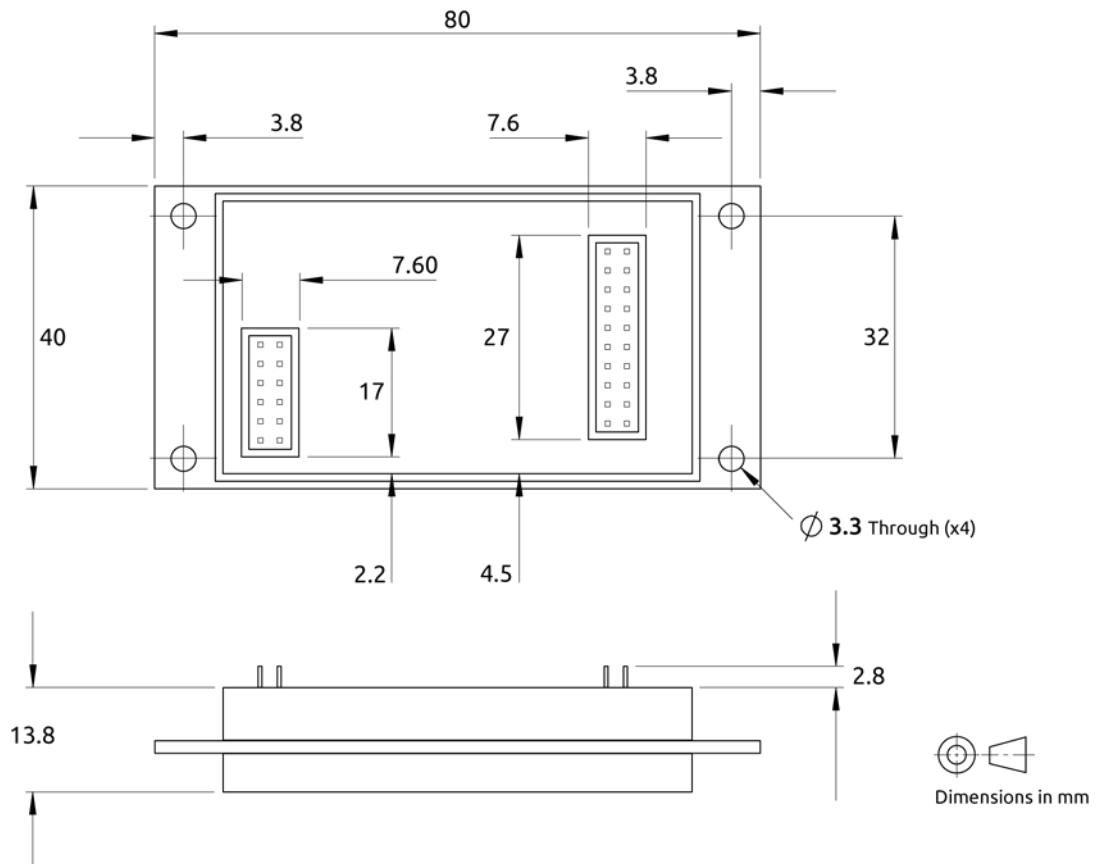


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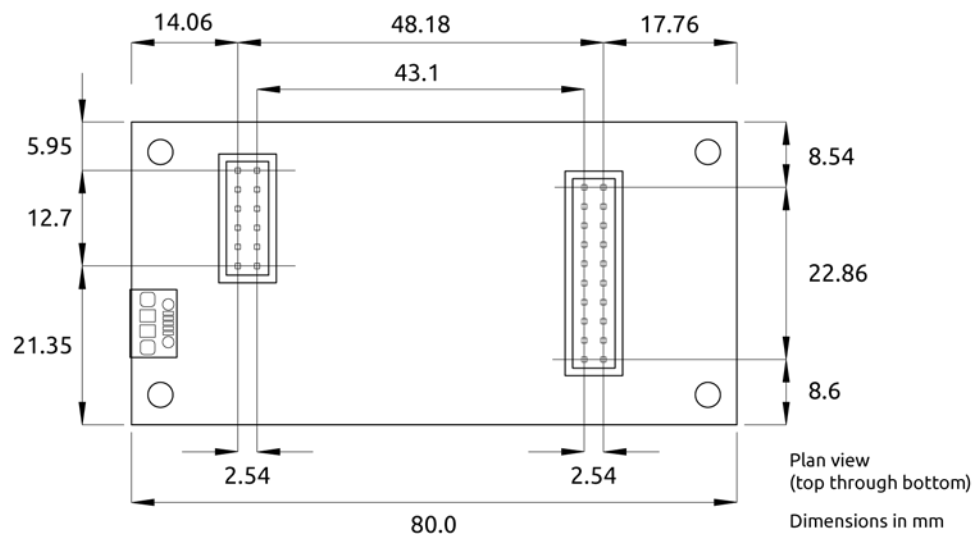
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3.2. Dimensions

External Dimensions



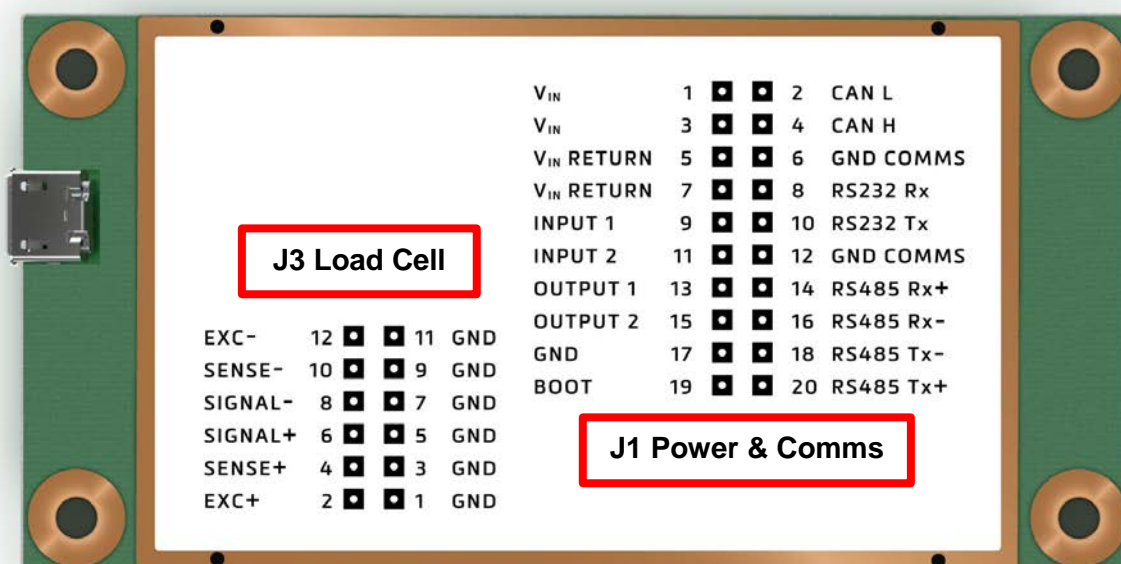
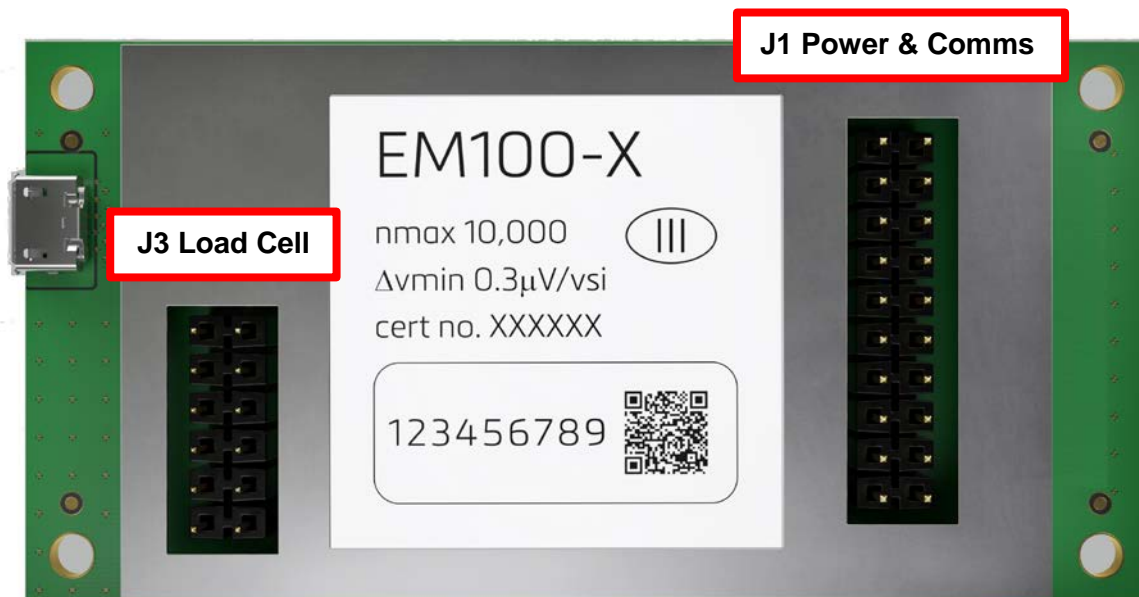
EM100 Pin Location Points



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3.3. Connections



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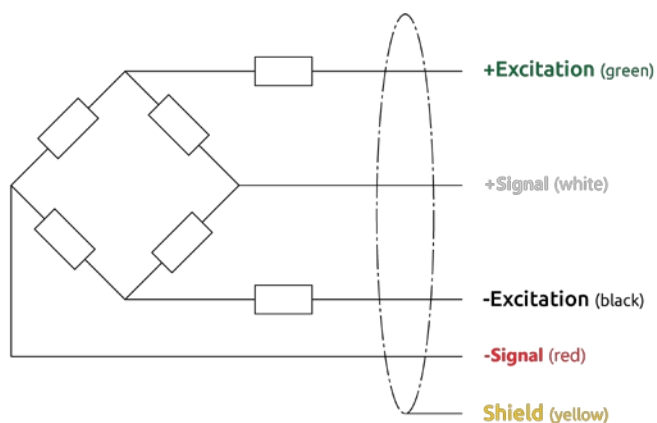
3.3.1. Load-Cell Connections

Connect the input using the colour coding for Load-cell connections:

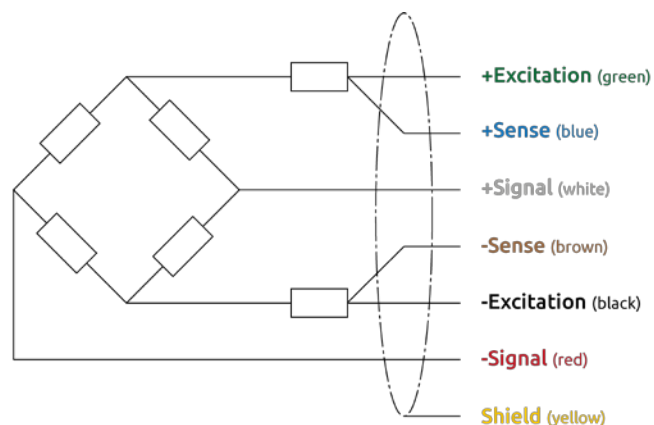
EM100 J3 Load-Cell Pin-Out	Function
2	Excitation+
4	Sense+
6	Signal+
8	Signal-
10	Sense-
12	Excitation-
1, 3, 5, 7, 9 & 11	GND

Note: If using 4-wire configuration, tie the Excitation+ (**EXC+**) to the Sense+ (**S+**) & Excitation- (**EXC-**) to the Sense- (**S-**) for correct configuration.

4-Wire Connection:



6-Wire Connection:



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3.3.2. Power Connection

The power supply is designed to accept a +12V_{DC} or +24V_{DC} supply. The power supply ground is not the same potential as the comms or main chassis ground pins. Only use the appropriate power and return pins for the supply, all comms and GPIOs pins to be referenced to the associated comms or main chassis ground.

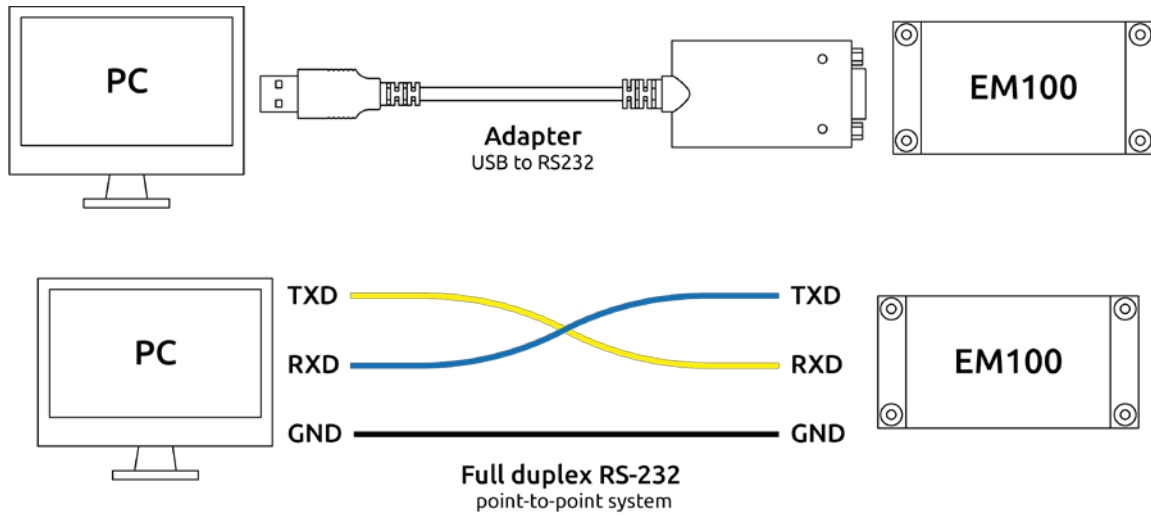
EM100 J1 Pin Number	Pin Name	Function
1 & 3	Vin	Power Supply Input.
5 & 7	Vin Return	Power Supply Input GND.
17	GND	Main Chassis GND.
6 & 12	GND C	Communications GND.
9	Input 1	GPIO Input.
11	Input 2	GPIO Input.
13	Output 1	GPIO Output (Open-Drain).
15	Output 2	GPIO Output (Open-Drain).
19	Boot	Firmware Upgrade Facility.
2	CAN L	CANopen Differential Pin-.
4	CAN H	CANopen Differential Pin+.
8	RS-232 RX	Serial Port Input.
10	RS-232 TX	Serial Port Output.
14	RS-485 RX+	Differential Rx+ Pin.
16	RS-485 RX-	Differential Rx- Pin.
20	RS-485 TX+	Differential Tx+ Pin.
18	RS-485 TX-	Differential Tx- Pin.

Note: If using the USB port to setup and configure, it should be noted when a power cycle or software reset (see '**SR**' command) is applied, the USB cable may require disconnecting, then reconnecting after powered up.

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3.3.3. RS-232 Connection



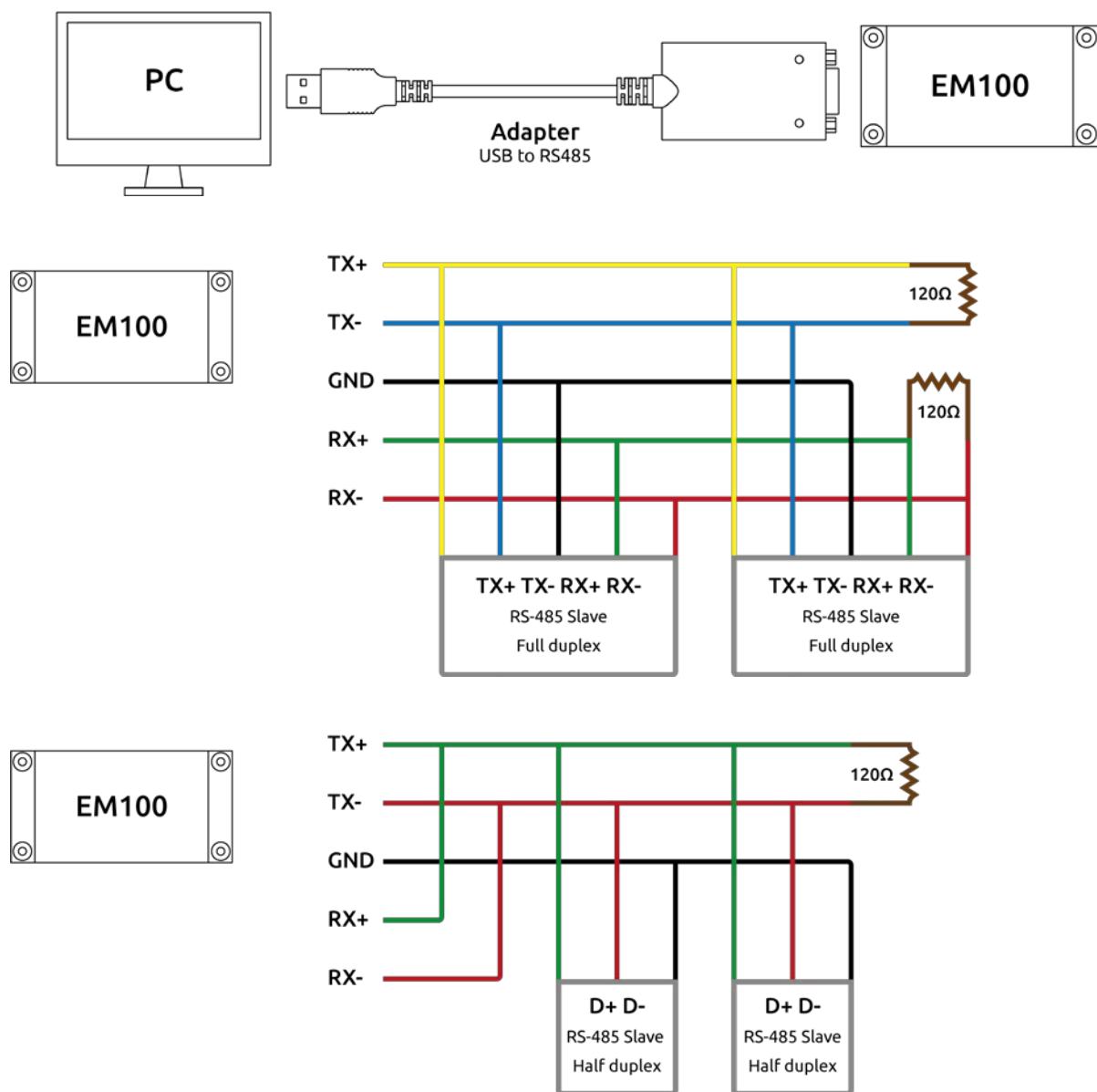
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3.3.4. RS-485 Connection

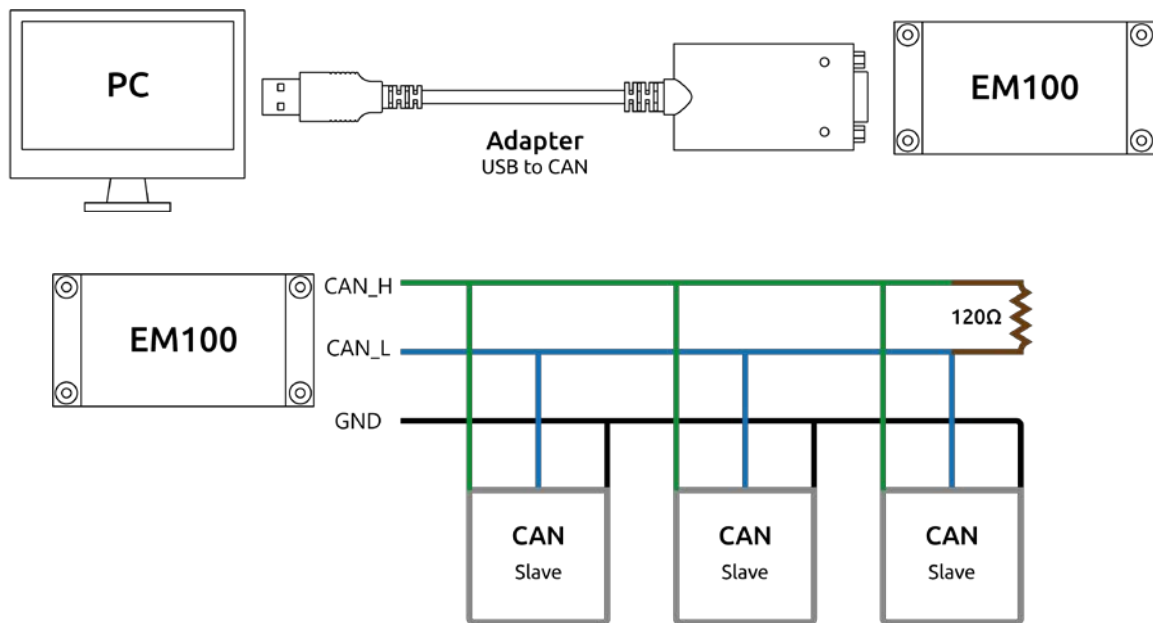
The RS-485 network requires a 120Ω termination resistor at both the host end (EM100) and at the furthest point in the network. The EM100 has a software selectable terminator built-in (see '**STR**' command).

Note: For half-duplex (RS-485) operation tie RS-485 TX+ with RS-485 RX+ and RS-485 TX- with RS-485 RX-.



3.3.5. CANopen Connection

Note: For the CAN network to operate properly, it is necessary to place a 120Ω termination resistor at both the host end (EM100) and at the furthest point in the network. The EM100 has a software selectable terminator built-in (see '**CTR**' command).



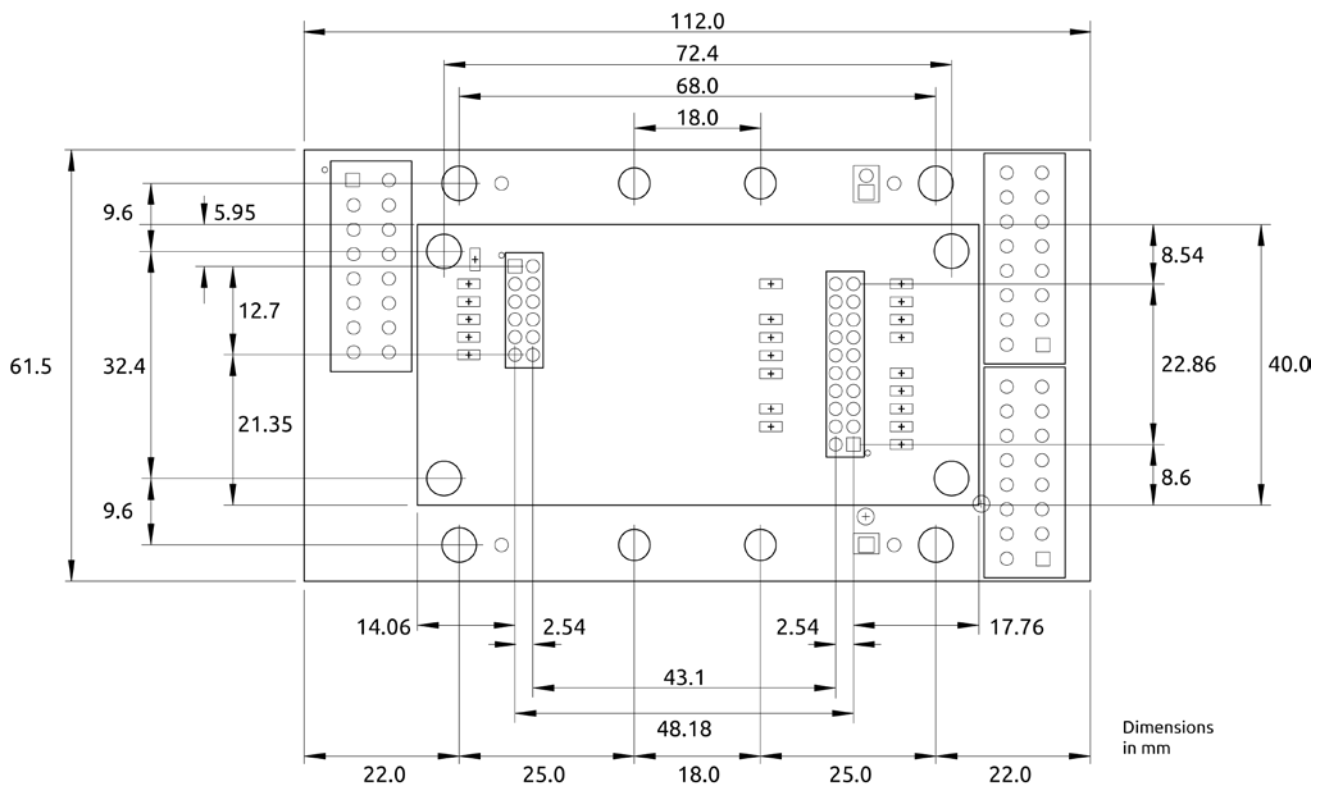
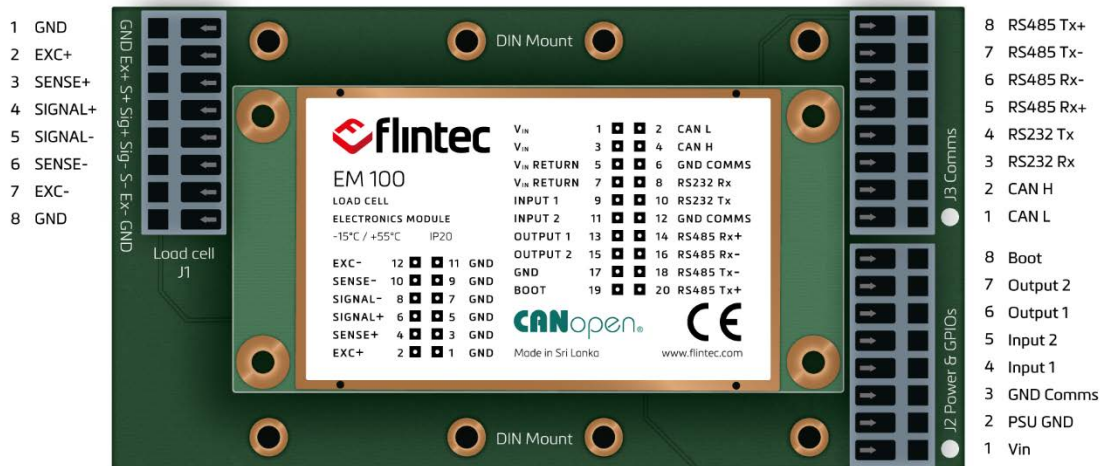
3.3.6. USB Connection



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3.3.7. EM100 with Adaptor Board



3.4. Driver Check

During the first session, it may be necessary for the PC to install appropriate drivers. If using a CAN adaptor or USB-to-serial converter, consult the manufacturer for instructions and latest drivers.

If using the USB CDC connection, the following driver from STMicroelectronics will need to be installed. View the ST.com website for the latest revision:

<http://www.st.com/en/development-tools/stsw-stm32102.html>

An installation manual is available from the Flintec website (www.flintec.com).

3.5. Calibration

3.5.1. Calibration Commands

The calibration of EM100 is only possible after opening a calibration sequence. See '**Calibration Commands**' Chapter for more details on the following commands.

Command CE :	Calibration Enable – Returns the current TAC value.
Command CM1/CM2/CM3 :	Calibrate Maximum Display – Sets the max. allowable display value.
Command CI :	Calibrate Minimum – Sets the minimum allowable display value.
Command MR :	Multi-Range/Multi-Interval.
Command DS :	Display Step Size – Sets the output incremental step size.
Command DP :	Decimal Point – Sets the position of the output decimal point.
Command CZ :	Calibrate Zero – Sets the system zero-point.
Command CG :	Calibrate Gain – Sets the system gain.
Command ZT :	Zero Tracking – Enabled/disabled.
Command IZ :	If applicable: Correction of System Zero.
Command TM :	If applicable: Tare Mode (check if ' <i>legal-for-trade</i> ' application).
Command ZR :	If applicable: Zero Range – sets the zero range manually.
Command ZI :	If applicable: Initial Zero Range.
Command WT :	If applicable: Warm-Up Time.
Command FD :	If applicable: Reset to factory default settings.
Command CS :	Save Calibration data (TAC automatically incremented by 1).

3.5.2. Preparing for Calibration

- Check the Maximum value of the display is set sufficiently for the application (see '**CM n**').
- Check the Minimum value of the display is set sufficiently for the application (see '**CI**').
- Check the Zero-Tracking has been turned off (see '**ZT**').
- Check the Warm-Up time is not set to a high value (see '**WT**').
- Check the No-Motion window conditions reasonably defined (**Default:** NR=1, NT=1000).

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3.5.3. Calibration Sequence

Example: Setup of zero-point, span and decimal point.

The chosen calibration weight has the value 5000 (increments). That could be 500g, 5kg or 5000kg. We calibrate with 500g. The decimal point is set up by command **DP'x'** (x=1, 2 or 3), here 1 figure after the decimal point. A measured weight of 500g is displayed as 500.0.

Master Sends	Slave Responds With	Meaning
CE┘	E+00019 (example)	TAC Counter=19.
Adjust Zero: The Scale must be Empty – No Load!		
CE 19┘	OK	Calibration Sequence Active.
CZ┘	OK	System Zero-Point Saved.
Adjust Gain: First put the Calibration Weight on the Scale (here 500g).		
CE 19┘	OK	Calibration Sequence Active.
CG 5000┘	OK	Setting Span.
CG┘	G+005000	Request: Span 5000divisions.
CE 19┘	OK	Calibration Sequence Active.
DP 1┘	OK	Setting Decimal Point 00000.0.
CE 19┘	OK	Calibration Sequence Active.
CS┘	OK	Save Calibration Data.

The zero-point, span and decimal point position were saved into the non-volatile memory; the calibration counter (TAC) will be incremented.

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4. Commands Overview

Command	Factory Default	Parameter Range	Description
AD	No Default.	0...255dec.	Set Device Address (0=perm active).
AG	20000.	±33000dec.	Absolute Gain Calibration.
AZ	Zero.	±33000dec.	Absolute Zero-Point Calibration.
BR	9600.	9600...460800dec.	Baud-Rate.
CE	No Default.	0...65535dec.	Open Calibration Sequence. Read TAC Counter.
CG	20000.	1...999999dec.	Set Calibration Gain (Span) at Load > Zero.
CI	-999999.	-999999...0dec.	Minimum Output Value.
CL	No Default.	None.	Close Device Communication.
CM1	999999.	1...999999dec.	Set Maximum Output Value (n=1).
CM2	Zero.	0...999999dec.	Set Maximum Output Value (n=2).
CM3	Zero.	0...999999dec.	Set Maximum Output Value (n=3).
CS	No Default.	N/A.	Save Calibration Data.
CTR	Zero.	0...1dec.	CAN Termination Resistor Selector.
CZ	No Default.	N/A.	Set Calibration Zero Point (No-Load).
DP	3.	0...5dec.	Set Decimal Point Position.
DS	1.	1, 2, 5, 10, 20, 50, 100, 200, 500dec.	Set Display Step Size.
DX	Zero.	0...1dec.	Set Full-Duplex.
FD	No Default.	N/A.	Restore Factory Default Settings.
FFV	0101.	N/A.	Identify Firmware Version.
FL	3.	0...8dec.	Filter Cut-Off Frequency.
FM	Zero.	0...1dec.	Filter Mode.
FPN	No Default.	N/A.	Get Device ID.
GG	No Default.	N/A.	Get Gross Value.
GH	No Default.	N/A.	Get Hold Weight Value.
GM	No Default.	N/A.	Get Peak Value.
GN	No Default.	N/A.	Get Net Value.
GO	No Default.	N/A.	Get Peak-to-Peak Value.
GS	No Default.	N/A.	Get ADC Sample Value.
GT	No Default.	N/A.	Get Tare Value.
GV	No Default.	N/A.	Get Valley Value.
GW	No Default.	N/A.	Get Data String (Net, Gross, Status).
HW	No Default.	N/A.	Hold Weight - Broadcast Message.
IN	No Default.	0000...0011bin.	External Input State.
IO	Zero.	0000...0011bin.	External Output State.

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IS	No Default.	N/A.	Get System Status.
IZ	No Default.	N/A.	Correction of System Zero.
MR	Zero.	0...1dec.	Set Multi-Range/Multi-Interval.
NA	1.	1...127dec.	CAN Network Address.
NR	1.	0...65535dec.	No-Motion Range Value.
NS 1	1.	1...127dec.	CAN Network Address (as NA).
NS 2	500.	10, 20, 50, 125, 250, 500, 800, 1000dec.	CAN Network Speed (kBits/sec).
NT	1000.	0...65535dec.	No-Motion Time-Period (ms).
OF	Zero.	0...3dec.	Output Format of Data String GW.
OM	Zero.	0000...0011bin.	External Output Mask.
OP	Zero.	0...255dec.	Open Communications.
RM	No Default.	N/A.	Reset Peak Value.
RS	No Default.	N/A.	Read Serial Number.
RT	No Default.	N/A.	Reset Tare.
RZ	No Default.	N/A.	Reset Zero Point.
SBR	Zero.	0...1dec.	RS-485 Biasing Resistor Selector.
SFQ	9.	0...255dec.	Synchronization Frequency.
SG	No Default.	N/A.	Send Gross Value Continuously.
SN	No Default.	N/A.	Send Net Value Continuously.
SP	Zero.	0...99999dec.	Preset Tare Value.
SR	No Default.	N/A.	Software Reset.
ST	No Default.	N/A.	Set Tare.
STR	Zero.	0...1dec.	RS-485 Termination Resistor Selector.
SW	No Default.	N/A.	Send Data String (Net, Gross, Status) Continuously.
SX	No Default.	N/A.	Send ADC Sample Continuously.
SYNC	Zero.	0...2dec.	Synchronization Mode.
SZ	No Default.	N/A.	System Zero.
TD	20.	0...255dec.	Transmit Delay (ms).
TH	None.	N/A.	Trigger Hold Value.
UR	Zero.	0...7dec.	Output Averaging Update Rate.
WP	No Default.	N/A.	Save Setup Data to Non-Volatile Memory.
WT	Zero.	0...65535dec.	Warm-Up Time (secs).
ZI	Zero.	0...999999dec.	Initial Zero Range.
ZN	Zero.	0...1dec.	Set/Clear Non-Volatile Zero.
ZR	Zero.	0...999999dec.	Manually Set Zero Range.
ZT	Zero.	0...255dec.	Enable/Disable Zero-Tracking.

5. Command Descriptions

5.1. System Diagnostic Commands – FPN, FFV, IS, SR, RS

Use these commands to get the model type, firmware version or device status. These commands are sent without parameters.

5.1.1. FPN Get Device Identity

Master Sends	Slave Responds With
FPN.␣	P: EM100-A.

The response to this request giving the identity of the device. This is particularly useful when trying to identify different model types on the same bus.

5.1.2. FFV Get Firmware Version

Master Sends	Slave Responds With
FFV.␣	V01.00 (example).

The response to this request gives the firmware version of the device.

5.1.3. IS Get Device Status

Master Sends	Slave Responds With
IS.␣	S:067000 (example).

The response to this request comprises of two 3-digit decimal values (067 and 000), which can be decoded according to the table below:

Leftmost 3-digit Value	Rightmost 3-digit Value
1 Signal Stable (No Motion).	1 (Not Used).
2 Zeroing Action Performed.	2 (Not Used).
4 Tare Active.	4 (Not Used).
8 Centre Zero.	8 (Not Used).
16 Input 1	16 (Not Used).
32 Input 2	32 (Not Used).
64 Output 1 Active.	64 (Not Used).
128 Output 2 Active.	128 (Not Used).

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- The example decodes the result **S:067000** as follows:
- Signal Stable (no motion) [=1].
- Zero Action Performed [=2].
- Tare Not Active [=0].
- Weight <> 0 [=0].
- Input 1 Not Active [=0].
- Input 2 Not Active [=0].
- Output 1 Active [=64].
- Output 2 Not Active [=0].

5.1.4. SR Software Reset

Master Sends	Slave Responds With
SR↵	OK.

This command will respond with '**OK**' and after maximum 400ms performs a complete reset. It has the same functionality as power cycle (OFF → ON). Any calibration, setup or setpoint changes must be preserved using the '**CS**', '**WP**' or '**SS**' commands.

5.1.5. RS Read Serial Number

Master Sends	Slave Responds With	Meaning
RS↵	S+12345678	Request: SN=12345678.

Issuing the '**RS**' command will return the serial number in the format S+12345678.

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5.2. Calibration Commands – CE, CM'n', CI, MR, DS, DP, CZ, CG, ZT, FD, IZ, ZR, ZI, ZN, AZ, AG, WT

Note: All changes to the calibration commands must be stored in non-volatile memory using the 'CS' command.

5.2.1. CE Read TAC* Counter/Open Calibration Sequence

With this command, you can read the TAC counter (TAC - Traceable Access Code) or you can open a calibration sequence.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	TAC Counter=11.
CE 11↓	OK	Calibration Sequence Active.

This command must be issued **PRIOR** to any attempt to set the parameters in the calibration group of commands. In 'legal-for-trade' applications the TAC counter can be used to check if critical parameters have been changed without re-verification. After each calibration save ('CS') the TAC counter increases by 1.

5.2.2. CM 'n' Set Maximum Output Value

The 'CM n' command with n=1, 2 or 3 is used to set up the maximum output values (respective switching point in multi range applications). Permitted values are from 0 to 999999.

Master Sends	Slave Responds With	Meaning
CM 1↓	M+030000	Request: CM 1=30000dec.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
CM 1 50000↓	OK	Setup: C<1=50000dec.

This value will determine the point at which the output will change to '0000000', signifying over-range condition.

Application	CM 1=Max 1	CM 2=Max 2	CM 3=Max 3
Single Range	CM 1=1...999999	CM 2=0 (means CM2 Not used)	CM 3=0 (means CM3 Not used).
Dual Range or Dual Interval (→ Command MR)	CM 1=1...MAX 1	CM 2=MAX 1...999999	CM 3=0 (means CM3 Not used).
Triple Range or Triple Interval (→ Command MR)	CM 1=1...MAX 1	CM 2=MAX1...MAX2	CM 3=MAX2...999999

It is necessary: $1 \leq \text{MAX1} < \text{MAX2} < \text{MAX3} \leq 999999$.

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Note: The range, in which a scale can be set to zero ('**SZ**') or automatic zero-tracking ('**ZT**') is active, is $\pm 2\%$ of **CM'n**' value.

Factory Default: CM 1=999999, CM 2=0, CM 3=0.

5.2.3. CI Set Minimum Output Value

This command is used to set up the minimum output value. Permitted values are -999999 to 0. This value will determine the point at which the output will change to '**uuuuuuu**', signifying 'under-range' condition.

Master Sends	Slave Responds With	Meaning
CI↵	I+000009	Request: CI=-9dec.
CE↵	E+00011 (example)	Request: TAC Counter CE11.
CE11↵	OK	Calibration Sequence Active.
CI -10000↵	OK	Setup: CI=-10000dec.

Note: In bipolar applications (e.g. force- or torque measurements) this parameter defines the max. output value for input signals with negative sign.

Factory Default: -999999.

5.2.4. MR Set Multi-Range/Multi-interval

This command is only relevant, if CM 2 > 0 or CM 3 > 0. If this the case, then this command defines the application is multi-range or multi-interval. Permitted values are 0 (Multi-interval) or 1 (Multi-range).

Master Sends	Slave Responds With	Meaning
MR↵	M+00000	Request: MR=0 (Multi-Interval).
CE↵	E+00011 (example)	Request: TAC Counter CE11.
CE 11↵	OK	Calibration Sequence Active.
MR 1↵	OK	Setup: MR=1 (Multi-Range).

Note: Single range applications ignore this parameter.

Factory Default: 0 [Single Range].

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5.2.5. DS Set Display Step Size

This command allows the output to step up or down by a unit other than 1. Permitted values are 1, 2, 5, 10, 20, 50, 100, 200 and 500.

Master Sends	Slave Responds With	Meaning
DS↓	S+00000	Request: Step Size 2.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
DS 50↓	OK	Setup: Step Size=50.

'Legal-for-trade' applications allow for up to 20,000 intervals. The allowed step size must be considered.

Factory Default: 1.

5.2.6. DP Set Decimal Point Position

This command allows the decimal point to be positioned anywhere between left-most and right-most digits of the 6-digit output result. Permitted values are 0, 1, 2, 3, 4, 5 and 6. Position 0 means the decimal point is on right of Gross/Net figure.

Master Sends	Slave Responds With	Meaning
DP↓	P+00003	Request: Position of Decimal Point.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
DP 0↓	OK	Setup: No Decimal Point.

Factory Default: 3.

5.2.7. CZ Set Calibration Zero Point

This is the reference point for all weight calculations and is subject to TAC control.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
CZ↓	OK	Setup: Zero Point.

Factory Default: Approx. 0mV/V input signal.

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5.2.8. CG Set Calibration Gain (Span)

This is the reference point for calibration under load and is subject to TAC control.

Permitted values are from 1 to 999999.

Master Sends	Slave Responds With	Meaning
CG↓	G+010000	Request: Calibration Weight=10000dec.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
CG 15000↓	OK	Setup: Calibration Weight=15000dec.

For calibrating an input signal near the display maximum ('**CM**') will give the best system performance. The minimum calibration load of at least 20% is recommended. If the calibration weight smaller than 1% of display maximum ('**CM**'), the EM100 will respond with an error message ('**ERR**').

Factory Default: 20,000=2.000mV/V input signal.

5.2.9. ZT Enable/Disable Zero Tracking

This command enables or disables the zero-tracking. ZT=0 disables the zero-tracking and ZT=1 or higher enables the zero-tracking. Issuing the command without any parameter returns the current '**ZT**' value.

Permitted values are 0 to 255.

Master Sends	Slave Responds With	Meaning
ZT↓	Z:001	Request: ZT Status.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
ZT 0↓	OK	Setup: ZT=Disable.

Zero-tracking will be performed only on results less than '**ZT**' range at a rate of 0.4 d/sec, where d=display step size (see '**DS**' command). The zero can only be tracked to +/- 2% of maximum (see '**CM n**' command).

ZT=1 means $\pm 0.5d$.

ZT=100 means $\pm 50d$.

Factory Default: 0 [Disabled].

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5.2.10. FD Reset to Factory Default Settings

This command puts the EM100 back to a known state. The data will be written to non-volatile memory and the TAC will be incremented by 1.

Note: All calibration and setup information will be lost by issuing this command! The Baud-rate will revert to 9600Baud after a factory reset.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
FD↓	OK	Factory Default Settings.

5.2.11. IZ Correction of System Zero

This command can correct the system zero after a successful calibration, e.g. to correct the unknown weight of a mounting accessory which was used to hold the calibration weight during the calibration procedure. A simple parallel shift of the gain curve the sensitivity of the scale will stay unaffected.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
IZ↓	OK	System Zero Corrected.

5.2.12. ZR Zero Range

Sets the zero range manually – this is the range in increments within which the weighing scale can be zeroed. Issuing the '**ZR**' command without any parameter will return the current value. Permitted values are between the lower limit of 0 and the upper limit of 999999. A value of zero enables the standard zero range of $\pm 2\%$ of max.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
ZR 100↓	OK	Setup: Zero Range=100dec.

Factory Default: 0.

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5.2.13. ZI Initial Zero Range

Define the initial zero range (0...999999dec.). If '**ZI**' is non-zero the device will perform an automatic Set-Zero when the weight stabilizes with the '*No-Motion*' settings and the weight is within the ZI range.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
ZI 100↓	OK	Setup: Initial Zero Range=100dec.

Factory Default: 0.

5.2.14. ZN Set/Clear Non-Volatile Zero

This command sets the zero mode to volatile or non-volatile. Value range is 0 or 1; Factory default is 0 (Volatile). If set to 1 (Non-Volatile), every set/clear zero will write the value directly to non-volatile memory.

Master Sends	Slave Responds With	Meaning
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
ZN↓	Z:000	Actual Setting: ZN=Volatile.
ZN 1↓	OK	Setup: ZN=Non-Volatile.

Factory Default: 0 [Volatile].

5.2.15. AZ Absolute Zero Point Calibration (eCal)

The command '**AZ**' is used as reference point for all weight calculations and will setup in mV/V. Permitted values are ± 33000 (± 3.3000 mV/V).

Master Sends	Slave Responds With	Meaning
AZ↓	Z+000796	Request: Zero Point @ 0.0796mV/V.
CE↓	E+00011 (example)	Request: TAC Counter CE11.
CE 11↓	OK	Calibration Sequence Active.
AZ 00500↓	OK	New: Zero Point @ 0.0500mV/V.

Factory Default: 000000dec. @ 0.0000mV/V input signal.

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5.2.16. AG Absolute Gain Calibration (eCal)

The command '**AG**' is used as absolute gain (or measuring range) for all weight calculations and will setup in mV/V. Permitted values are ± 33000 ($\pm 3.3000\text{mV/V}$).

Master Sends	Slave Responds With	Meaning
AG↵	G+001868+01000	Request: AG Status.
CE↵	E+00011 (example)	Request: TAC Counter CE11.
CE 11↵	OK	Calibration Sequence Active.
AG +011200 +005000↵	OK	New: Gain 5000dec. @ 1.12mV/V.

Factory Default: 20,000d @ 2.0000mV/V input signal.

5.2.17. WT Warm-Up Time

Sets the warm-up time – this command defines a time interval between 0 and 65535secs after power on where the output value will be set to '**uuuuuuu**' to avoid false readings during the initial stabilisation period.

Master Sends	Slave Responds With	Meaning
WT↵	W+00000	Request: Warm-Up Time=0sec.
CE↵	E+00011 (example)	Request: TAC Counter CE 11.
CE 11↵	OK	Calibration Sequence Active.
WT 20↵	OK	Setup: Warm-Up Time=20sec.
CE 17↵	OK	Calibration Sequence Active.
CS↵	OK	Calibration Values Saved.

Factory Default: 0 [0secs].

5.3. Motion Detection Commands – NR, NT

The motion detection facility provides a means of disabling certain functions whenever a condition of instability, or '*motion*', is detected. The '*no-motion*' or '*stable*' condition is achieved whenever the signal is steady for the time-period set by '**NT**', during which it cannot fluctuate by more than '**NR**' increments. The '*stable*' condition activates the relevant bit in the System Status '**IS**' result.

Following functions are disabled if motion is detected: Calibrate Zero '**CZ**' Calibrate Gain '**CG**' Set Zero '**SZ**' and Set Tare '**ST**'. After such a command, the system returns an error '**ERR**', if the signal is not '*stable*'.

5.3.1. NR Set No-Motion Range

This is the range within which the weighing signal fluctuates and still be considered as '*stable*'. Permitted values are from 0 to 65535.

Master Sends	Slave Responds With	Meaning
NR↵	R+000010	Request: NR=10dec.
NR 2↵	OK	Setup: NR=2dec.
WP↵	OK	Setup Saved.

Example: For NR=2 the fluctuations within a maximum of $\pm 2d$, in the period '**NT**', will be considered '*stable*'.

Factory Default: 1 [$\pm 1d$].

5.3.2. NT Set No-Motion Time

The time-period (in milliseconds) over which the weight signal is checked to be '*stable*' or not. The weight signal must vary by less than '**NR**' divisions over the time-period of '**NT**' to be considered '*stable*'.

Permitted values are from 0 to 65535ms.

Master Sends	Slave Responds With	Meaning
NT↵	T+001000	Request: NT=1000ms.
NT 500↵	OK	Setup: NT=500ms.
WP↵	OK	Setup Saved.

If the value of '**NT**=500ms, the output must not fluctuate more than '**NR**' increments within 500ms to be considered '*stable*'.

Factory Default: 1000 [1000ms].

5.4. Filter Setting Commands – FM, FL, UR

FIR or IIR Filters (selected with '**FM**' command) are provided to eliminate most unwanted disturbances. The command '**FL**' is used to define the filter settings, whilst the command '**UR**' is used to define an averaging of up to 128 measurement values. Please note that these filters are applied immediately after the A/D converter and therefore affect all aspects of the weighing operation.

5.4.1. FM Filter Mode

This command defines the filter mode. Choose the filter mode for your application.

Permitted values are '**0**' for IIR filter and '**1**' for FIR filter.

Master Sends	Slave Responds With	Meaning
FM↓	M+00000	Request: FM=0 (IIR Filter).
FM 1↓	OK	Setup: FM=1 (FIR Filter).
WP↓	OK	Setup Saved.

The IIR filter operates as 2nd order low pass filter with Butterworth characteristics. The attenuation is 40dB/decade (12 dB/octave). The digital FIR filter works as a low-pass filter with quick response (see Mode Characteristics tables).

Default Setting: 0 [IIR filter].

5.4.2. FL Filter Setting

This command defines the -3dB filter cut-off frequency.

Master Sends	Slave Responds With	Meaning
FL↓	F+00006	Request: FL=6 (1Hz Cut-Off).
FL 1↓	OK	Setup: FL=1.
WP↓	OK	Setup Saved.

The permitted settings are from 0 to 8 (IIR) or 0 to 9 (FIR) - (see Mode Characteristics tables).

Default Setting: 3 [Filter 3].

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Mode 0 (IIR Filter) Settings/Characteristics

'FL' Setting	Settling Time ms (0.1%)	-3dB Cut-Off Frequency (Hz)	Attenuation at 50Hz (dB)	Output Sampling Rate (samples/sec)*
0	80	18	>100	80
1	250	10	>100	40
2	300	5	>100	20
3	400	3	>100	12
4	450	2	>100	12
5	900	1.5	>100	5
6	1300	1	>100	5
7	3000	0.5	>100	2.5
8	4500	0.2	>100	2.5

Mode 1 (FIR Filter) Settings/Characteristics

'FL' Setting	Settling Time ms (0.1%)	-3dB Cut-Off Frequency (Hz)	Damping Frequency at -20dB (Hz)	Damping Frequency at -40dB (Hz)	Stopband Attenuation (dB)	Output Sampling Rate (samples/sec)*
0	No Filter	-	-	-	-	40
1	400	10	14.8	16.2	>100	40
2	1600	8	9.1	9.5	>100	40
3	1050	5	6.6	7.3	>100	40
4	1600	3	4.1	4.5	>100	40
5	1100	2	3.6	4.3	>100	40
6	960	1	3.3	4.1	>100	40
7	1450	0.5	1.9	2.4	>100	40
8	1400	0.2	1.7	2.3	>100	40
9	1300	0.1	1.7	2.3	>100	40

*Output Rate = $V_{ale}/2^{UR}$ samples/sec.

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5.4.3. UR Update Rate & Averaging

Depending on the selected filter mode this command defines an averaging for the output value. The permitted settings are from 0 to 7 (see table below). The average value is always calculated from 2^{UR} measurement values.

Master Sends	Slave Responds With	Meaning
UR↵	U+00003	Request: Averaging of 8 Values.
UR 7↵	OK	Setup: Averaging of 128 Values.
WP↵	OK	Setup Saved.

UR	0	1	2	3	4	5	6	7
Average of 2 ^{UR} Values	1	2	4	8	16	32	64	128

Factory Default: 0 [No Averaging].

5.5. Taring & Zeroing Commands – SZ, RZ, ST, RT, SP

The following commands allow you to set/reset the zero and tare values. The zero set up during calibration remains the 'true zero' but the new 'current zero' can be set up by using the '**SZ**' command. If the '**SZ**' command is issued and accepted, all weight values will then be based on the new 'current zero'. The zero value will be subject to the zero-tracking function if enabled. If the weight signal is not 'stable' (as defined by the No-Motion range '**NR**' and the No-Motion time '**NT**') then both the set zero '**SZ**' and set tare '**ST**' commands will be disabled. Also, the Set Zero '**SZ**' command is not allowed if the new zero value required and the 'calibration zero' differ by more than 2% of the '**CM**' value (maximum allowable value).

5.5.1. SZ Set System Zero

This command sets a new 'current zero' which is then the basis of all weight values until further updated by the zero-tracking function, another '**SZ**' command or the 'reset zero' command '**RZ**'.

Master Sends	Slave Responds With	Meaning
SZ↵	OK	Set Zero Performed.

The '**SZ**' command will fail (responding with '**ERR**') if the new 'current zero' is more than 2% (of the '**CM**' value) higher or lower than the 'true zero' set during calibration. The '**SZ**' command will also fail if the weight signal is not 'stable' as defined by the no-motion range ('**NR**') and the no-motion time ('**NT**'). If the weight signal is 'stable', the response to the Device Status command ('**IS**') will show the 'signal stable' bit active and the '**SZ**' command will be accepted ('**OK**'). If the 'signal stable' bit is not active, the '**SZ**' command will be rejected and the EM100 will respond with '**ERR**'.

5.5.2. RZ Reset Zero

This command cancels the '**SZ**' command and the zero reading reverts to that set by the '**CZ**' command during calibration.

Master Sends	Slave Responds With	Meaning
RZ↵	OK	Zero Point CZ Active.

The EM100 responds to the '**RZ**' command with either '**OK**'. If OK is returned, the 'zero action performed' bit in the Device Status ('**IS**') response will be set to '**0**'.

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5.5.3. ST Set Tare

This command will activate the net weighing function by storing the current weight value as a tare value. The weight signal must be '*stable*' within the limits set by '**NR**' (No-Motion Range) and '**NT**' (No-Motion Time) commands for the '*signal stable*' bit to be active and set tare command to be accepted.

Master Sends	Slave Responds With	Meaning
ST↵	OK	Tare Performed/Net Operation.

If the weight signal is '*stable*', the response to the Device Status command ('**IS**') will show the '*signal stable*' bit active and the '**ST**' command will be accepted ('**OK**'). If the '*signal stable*' bit is not active, the '**ST**' command will be rejected and the EM100 will respond with '**ERR**'.

5.5.4. RT Reset Tare

This command resets the tare and the weighing signal returns to gross mode.

Master Sends	Slave Responds With	Meaning
RT↵	OK	Tare De-Activated/Gross Performed.

The EM100 responds to the '**RT**' command with either '**OK**'. If OK is returned, the 'tare active' bit in the Device Status ('**IS**') response will be set to '**0**'.

5.5.5. SP Set Preset Tare

This command sets a tare value.

Master Sends	Slave Responds With	Meaning
SP↵	T+000000	Tare Value.
SP 1000↵	OK	Setup Tare Value 1000dec.

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5.6. Output Commands – GG, GN, GT, GS, GW, OF, GH, TH, GM, RM, GO, GV, HW

5.6.1. GG Get Gross Value

Master Sends	Slave Responds With	Meaning
GG↵	G+001.100	Gross Value: 1100dec.

5.6.2. GN Get Net Value

Master Sends	Slave Responds With	Meaning
GN↵	N+001.000	Net Value: 1000dec.

5.6.3. GT Get Tare Value

Master Sends	Slave Responds With	Meaning
GT↵	T+000.100	Tare Value: 100dec.

5.6.4. GS Get ADC Sample Value

This command retrieves the analogue to digital Converter (ADC) value. This can be useful during development or when calibrating to see how much of the ADC range is being used.

Master Sends	Slave Responds With	Meaning
GS↵	S+01257850	ADC Value: 01257850dec.

For service purposes, it may be helpful to note the GS values for the 'no-load' or 'zero' output and when the 'calibration load' is applied.

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5.6.5. GW Get Data String (Net, Gross & Status)

Issuing the '**GW**' command, which has no parameters, will return the net weight, the gross weight, the status and the checksum values, all combined into one single string in the format:

W+000100+001100010F.

The first two sections of the return string comprise the net weight and gross weight results, followed by two hexadecimal characters, which represent two bit-mapped status indicators. The last two hexadecimal characters represent the checksum, which is the inverse of the sum of all the ASCII values of the string, not including the checksum characters.

W	+000100	+001100	0	1	0F
Leading Character signifies the GW	Net Weight excluding decimal point.	Gross Weight excluding decimal point.	First Status Nibble	Second Status Nibble	Checksum

STATUS	Value=1	Value=2	Value=4	Value=8
Status Bit-1	Not Used.	Not Used.	Output 1 Active.	Output 2 Active.
Status Bit-2	Signal Stable.	Set Zero Performed.	Tare Active.	Not Used.

The check sum is the reciprocal value of the sum of all ASCII values within the data string without the check sum itself.

Master Sends	Slave Responds With	Meaning
GW↵	W+000100+0011005109 (example).	Net Value: +000100dec. (no decimal point). Gross Value: +001100dec. (no decimal point). Status bit 1: 5hex (Not Used). Status bit 2: 1hex. Checksum: 09hex.

5.6.6. OF Output Format for Data String

This command puts the range information and/or the decimal point into the '*long*' data strings of the '**GW**' output response.

Master Sends	Slave Responds With	Meaning
CE↵	E+00012 (example).	Request: TAC Counter CE12.
CE 12↵	OK	Calibration Sequence Active.
OF 1↵	OK	Setup: OF=1.

Note: Changes to this command must be saved using the '**CS**' command. This command also adds/removes the range field (decimal point is unaffected) for Get Gross '**GG**' and Get Net '**GN**' commands.

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Output Format

Parameter Setting	Range Information	Decimal Point in GW & GL Response
0 (Factory Default)	No.	No.
1	Yes.	No.
2	No.	Yes.
3	Yes.	Yes.

E.g. when the range information is selected, the data strings will change from G+000000 to Gn+000000, where $1 \leq n \leq 3$.

5.6.7. GH Get Hold Weight

Issuing the '**GH**' command without parameters will return the current hold weight in the format N+000100 from the currently addressed EM100. All other channels must be requested one-by-one.

Master Sends	Slave Responds With	Meaning
OP 1↓	OK	Open Device #1.
GH↓	N+01.100	Hold Weight Value: 1100dec.

5.6.8. TH Trigger Hold Value

Saves the weight value of the last '**GH**' reading (not a broadcast message).

Master Sends	Slave Responds With	Meaning
TH↓	OK	Save actual weight value.

5.6.9. GM Get Peak Value

The peak value is the maximum value since the last Reset Peak '**RM**' command was issued.

Master Sends	Slave Responds With	Meaning
GM↓	M+051.100	Peak Value: 51100dec.

5.6.10. RM Reset Peak Value

Resets the peak value

Master Sends	Slave Responds With	Meaning
RM↓	OK	Reset Peak Value.

5.6.11. GO Get Peak-to-Peak Value

The peak-to-peak value is the difference between the peak value and the valley value.

Master Sends	Slave Responds With	Meaning
GO↓	O+091.100	Peak-to-Peak Value: 91100dec.

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5.6.12. GV Get Valley Value

The valley value is the minimum value since the last Reset Peak '**RM**' command was issued.

Master Sends	Slave Responds With	Meaning
GV↵	V+000.100	Valley Value: 100dec.

5.6.13. HW Hold Weight

Issuing the '**HW**' command without parameters (broadcast command) will latch the current net weight in a register for later readout in all EM100s in a common network regardless of their individual addresses.

Master Sends	Slave Responds With	Meaning
HW↵	No Response	Hold Weight Value in Register.

Note: EM100 will not respond to the broadcast command '**HW**'.

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5.7. Auto-Transmit Commands – SG, SN, SX, SW

The following commands allow the gross weight or net weight values to be continuously sent. Continuous transmission starts as soon as the relevant command has been issued and finishes when any valid command (The new command is executed by the EM100). The continuous transmission will also stop when an invalid command is received responding with '**ERR**'.

5.7.1. SG Send Gross Value Continuously

Master Sends	Slave Responds With	Meaning
SG↓	G+001.100	Gross Value: 1100dec.

5.7.2. SN Send Net Value Continuously

Master Sends	Slave Responds With	Meaning
SN↓	N+001.000	Net Value: 1000dec.

5.7.3. SX Send ADC Sample Value Continuously

Master Sends	Slave Responds With	Meaning
SX↓	S+01257850	ADC Sample Value: 01257850dec.

5.7.4. SW Send Data String Continuously (Net, Gross & Status)

Issuing the '**SW**' command, which has no parameters, will return continuously the net weight, the gross weight, the status and the checksum values, all combined into one single string in the format:

W+000100+001100010F

For more detailed information of the data string see command '**GW**' (*chapter 5.6.5*).

Master Sends	Slave Responds With	Meaning
SW↓	W+000100+0011005109 (example).	Net Value: +000100dec. (no decimal point). Gross Value: +001100dec. (no decimal point). Status bit 1: 5hex (Not Used). Status bit 2: 1hex. Checksum: 09hex.

STATUS	Value=1	Value=2	Value=4	Value=8
Status Bit-1	Not Used.	Not Used.	Output 1 Active.	Output 2 Active.
Status Bit-2	Signal Stable.	Set Zero Performed.	Tare Active.	Not Used.

The checksum is the reciprocal value of the sum of all ASCII values within the data string without the check sum itself.

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5.8. External I/O Control Commands – IN, OM, IO

5.8.1. IN Read Status of Logic Inputs

Master Sends	Slave Responds With	Meaning
IN┐	IN:0000	Input 1 & 2 Low.
IN┐	IN:0001	Input 1 High, Input 2 Low.
IN┐	IN:0010	Input 1 Low, Input 2 High.

The status response is in the form of a 4-digit code where 0=false and 1=true (inputs are active 'high'). The least significant bit corresponds to Input 1.

5.8.2. OM Control of Logic Outputs by Host Application

The logic outputs can be controlled by the host application (as opposed to the normal internal set-points). They are enabled by the '**OM**' command (or '**IM**') and the appropriate 4-digit code. When '**OM**' is set to zero, the user controlled logical outputs are disabled defaulting back to operation with set-points.

Master Sends	Slave Responds With	Meaning
OM┐	OM:0001	Setting Output 1 Enabled.
OM┐	OM:0011	Setting Output 1 & 2 Enabled.

A logic '**1**' bit in the code enables the corresponding logic output to be controlled by the host application using the '**IO**' command (or '**IM**'). A logic '**0**' in the code leaves the corresponding logic output controlled by the internal set-point. Output 1 is the least significant bit.

Master Sends	Slave Responds With	Meaning
OM 0001┐	OK	Enable Output 1.
OM 0011┐	OK	Enable Outputs 1 & 2.

5.8.3. IO Read/Modify Status of Logic Outputs

This command reads and can modify the status of the logic outputs (if enabled by the '**OM**' command). The status response is in the form of a 4-digit code where 0=false and 1=true (outputs are normally open, open-drain MOSFETs), the least significant bit corresponds to Output 1.

Master Sends	Slave Responds With	Meaning
IO┐	IO:0001	Output 1 Set.
IO┐	IO:0010	Output 2 Set.

The status of the outputs can be changed by issuing the '**IO**' command with the appropriate 4-digit code e.g. IO 0001. The status of the logic outputs is normally determined by the internal set-points or manually setting the '**IO**' and '**OM**' (or '**IM**') output mask.

Master Sends	Slave Responds With	Meaning
IO 10┐	OK	Set Output 1 Set.
IO 11┐	OK	Set Outputs 1 & 2 Set.

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5.9. Communication Setup Commands – AD, NA, NS, BR, DX, CL, OP, TD, CTR, STR, SBR

Note: All changes to the communications commands must be stored to non-volatile memory using the '**WP**' command.

5.9.1. AD Device Address – Serial Channel

This command can set up the device address in the range from 0 to 255.

Master Sends	Slave Responds With	Meaning
AD↓	A:000	Request: Address 0.
AD 49↓	OK	Setup: Address 49.

Setting the device address to '**0**' will cause the device to be permanently active, listening and responding to every command on the bus without the need for an '**OP**' command.

Factory Default: 0.

5.9.2. NA Network Address – CANopen

Master Sends	Slave Responds With	Meaning
NA↓	A:001	Request: Show CANopen Interface Address.
NA 15↓	OK	Setup: Set CANopen Address to 15.

Factory Default: 1.

5.9.3. NS Network Settings – CANopen

The command **NS** [Param] [New Value] can be used to set up the CANopen address and bit rate.

Master Sends	Slave Responds With	Meaning
NS 0↓	D:1790	Request: Show Device Type.
NS 1↓	A:001	CANopen Address is 1.
NS 2↓	B:500	CANopen Address Bit-Rate 500kBits/sec.
NS 2 1000	OK	Set the CANopen Bit-Rate to 1MBits/sec.

Factory Default: NS 1=1, NS 2=500 [NS 1=1 CANopen Address 1; NS 2=500 500kBits/s].

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5.9.4. BR Baud Rate – Serial Channel

The following Baud-rates can be setup: 9600, 14400, 19200, 38400, 57600, 115200, 230400 and 460800Baud. The data-rate will only be active when the new Baud-rate has been saved with the '**WP**' command and a power cycle or software reset '**SR**' applied.

Master Sends	Slave Responds With	Meaning
BR↵	B 9600	Request: 9600 Baud.
BR 230400↵	OK	Setup: 230400Baud.

Factory Default: 9600 [9600Baud].

5.9.5. DX Full-Duplex – Serial Channel

Master Sends	Slave Responds With	Meaning
DX↵	X:000	Request: DX=0 (Half-Duplex).
DX 1↵	OK	Setup: DX=1 (Full-Duplex).

Factory Default: 0 [Half-Duplex].

5.9.6. CL Close Device Address 'n'

Master Sends	Slave Responds With	Meaning
CL 3↵	OK	Close Device #3.
CL↵	OK	Close All Connected Devices.

5.9.7. OP Open Device

This command, if sent without parameters, requests the address or device number of the active device on the bus. If sent with parameters, this enables the device defined by the parameters. The requested device acknowledges its readiness and responds to all bus commands until a further '**OP**' command arrives with a different address or a '**CL**' command is received.

Master Sends	Slave Responds With	Meaning
OP↵	O:00003	Request: Device #3 is Open.
OP 14↵	OK	Setup: Open Device #14.

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5.9.8. TD Transmission Delay

This command allows time delays from 0 to 255ms before any response from the EM100. This delay may be necessary in some two wire applications (half-duplex). The delay is only applicable when '**DX**' command is set to zero (half-duplex mode).

Master Sends	Slave Responds With	Meaning
TD↵	T:00020	Request: Delay Time 20ms.
TD 100↵	OK	Setup: Delay=100ms.

Factory Default: 20 [20ms].

5.9.9. CTR Set CAN Bus Termination Resistance

Master Sends	Slave Responds With	Meaning
CTR↵	T:000	Termination Z: Disabled.
CTR 0↵	OK	CAN Bus Termination Z Disabled.
CTR 1↵	OK	CAN Bus Termination Z Active.

Factory Default: 0 [Termination Off].

5.9.10.STR Set RS-485 Termination Resistance

Master Sends	Slave Responds With	Meaning
STR↵	T:000	Termination Resistor: Disabled.
STR 0↵	OK	RS-485 Termination Z Disabled.
STR 1↵	OK	RS-485 Termination Z Active.

Factory Default: 0 [Termination Off].

5.9.11. SBR Set RS-485 Biasing Resistance

Master Sends	Slave Responds With	Meaning
SBR↵	B:000	Biasing Resistors: Disabled.
SBR 0↵	OK	RS-485 Biasing Resistors Disabled.
SBR 1↵	OK	RS-485 Biasing Resistors Active.

Factory Default: 0 [Biasing Off].

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5.10. Save Calibration & Setup Data Commands – CS, WP

The calibration and setup parameters can be divided in 2 groups:

Calibration: 'CE', 'CM'n', 'CI', 'MR', 'DS', 'DP', 'CZ', 'CG', 'ZT', 'FD', 'IZ', 'ZR', 'ZI', 'ZN', 'AZ', 'AG', 'WT', & 'OF' saved by command 'CS'.

Setup: 'FL', 'FM', 'UR', 'NR', 'NT', 'AD', 'NA', 'NS', 'BR', 'DX', 'TD', 'CTR', 'STR', 'SBR', 'SYNC', 'SFQ', saved by command 'WP'.

Note: Calibration data can only be saved if the TAC code is known and precedes the 'CS' command. The setup data will be stored non-volatile memory using the 'WP' command.

5.10.1. CS Save Calibration Data

This command results in the calibration data being saved causing the TAC to be incremented.

Master Sends	Slave Responds With	Meaning
CE↵	E+00013	Request: TAC Counter CE13.
CE 13↵	OK	Calibration Sequence Active.
CS↵	OK	Calibration Values Saved.

The 'CS' command saves changes made using 'Calibration' group commands. The Output Format command 'OF' is also included. The command returns 'ERR' and has no updating action unless it is preceded by the 'CE xx'.

5.10.2. WP Save Setup Parameters

The settings of the following groups, 'Filter' ('FL', 'FM', 'UR'), 'No-motion' ('NR', 'NT'), 'Communications' ('AD', 'NA', 'NS', 'BR', 'DX', 'TD', 'CTR', 'STR', 'SBR), & 'Synchronization' ('SYNC', 'SFQ') group will be saved using the 'WP' command.

Master Sends	Slave Responds With	Meaning
WP↵	OK	Setup Data Saved.

5.11. Synchronization Commands – SYNC, SFQ

5.11.1. SYNC Synchronization Mode

Sync mode (0=Disabled; 1=Slave; 2=Master). This feature is only available on Input 1 or Output 1.

Master Sends	Slave Responds With	Meaning
SYNC ↵	S:000	Mode 0 – Sync Disabled.
SYNC 1 ↵	OK	Sets Slave Mode, Input 1 Used.
SYNC 2 ↵	OK	Sets Master Mode, Output 1 Used.

Note: the '**WP**' command must be used to save any changes.

5.11.2. SFQ Synchronization Frequency

This is the frequency of the master sync signal. A value of 100 will generate 100 trigger points per second. Each Sync Slave will perform a sample at each of these trigger points. This feature is only available on Input 1 or Output 1.

Master Sends	Slave Responds With	Meaning
SFQ ↵	F:00009	Frequency=9Hz.
SFQ 100 ↵	OK	Sets Frequency=100Hz.

Note: the '**WP**' command must be used to save any changes.

6. CANopen Interface

6.1. General Interface Specification

Interface	CAN2.0B
Identifiers Used	11-bit Transmit and Receive Identifiers. Tolerates 29-bit Identifiers.
Default Bit-Rate	500kBit/second.
NMT Mode	Slave. On start-up the EM100 waits for an NMT start message or SDO request before transmitting anything (Note: This does not conform exactly to the CIA standard).

EM100 uses both Node Guarding and Heartbeat modes.

Node Guarding

NMT master polls the network to obtain a data telegram from each node containing its current communication state and a toggle-bit. If a node does not respond to the request of the NMT-master within the '*node life time*', it is assumed the node has failed and is a '*node-guarding event*'. Also, the NMT-slaves monitor whether they have received a request from the NMT-master within their '*life time*'. If it takes longer than the '*life time*' of a node, the NMT-slave assumes that the NMT-master itself has failed and indicates this event as '*Life Guarding Event*'.

Guard Time is the time in ms.

Index [100C] and [100D] are used if index [1017] is zero.

Note: Where network bandwidth is limited, or the application is safety sensitive, heartbeat mode, is the preferred method to use node operation assurance.

Heartbeat

Heartbeat parameters are set by the NMT Master or the configuration tool in the slave nodes. The interval between two heartbeat messages '*heartbeat interval*' of a heartbeat producer is configured via index [1017]. A value of 0 disables the heartbeat mechanism. The so-called '*heartbeat consumer time*' of the network node is given in index [1016]. This time interval describes the maximum time within which the arrival of a heartbeat message is expected by a node.

Heartbeats save network bandwidth since it does not require the NMT master to poll the slaves. If index [1017] is non-zero the Heartbeat protocol is used, otherwise the Node-guard protocol is used.

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6.1.1. PDOs

Once set to 'Operational State', the EM100 will produce TPDOs constantly (see table below).

Depending on the data-rate set for the CANopen network, the high number of readings (>1200 per second) can exceed what can be consumed by the NMT master. Equally the update rate may be affected when there are multiple units on the network and/or lower communication speeds are used.

The '**UR**' command should be used to balance the network load by reducing the traffic.

PDO Definitions

PDO	Data	When
TPDO1 COB-ID 0x180-	Net/Gross.	Default TPDO at NMT start. Sent every time new reading is ready. Refresh time controlled by ' UR ' parameter.
TPDO2 COB-ID 0x280-	Average Weight (' GA ') Check-Weigher applications.	1. New measurement ready (' GA ') 2. Module waiting for trigger.
TPDO3 COB-ID 0x380-	Tare Weight (' GT ').	When new tare value set (' GT ').
RPDO1 COB-ID 0x200-	Command Select Gross/Net/Set Tare/Clear Tare/Set System Zero/Clear System Zero (All execute silently-no response is sent).	Sent by CAN Master Node.
RPDO2 COB-ID 0x300-	Command Start Measure/Stop Trigger. Check-Weigher mode Set Trigger: Start Filling cycle: Filling mode (All execute silently – no response is sent).	Sent by CAN Master Node.
RPDO3	Not used.	
RPDO4	Not used.	

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6.1.2. TPDO Frame (TPDO1, TPDO2 & TPDO3)

Sent: CAN Slave Node → CAN Master Node

32-bit	16-bit	8-bit	8-bit
Weight.	Status (see table below).	0	0

Status Values	Indication
0x0001	Under Range
0x0002	Over Range
0x0008	Centre Zero
0x0010	No Motion
0x0020	Tare Set
0x0080	ADC Error
0x0100	Set-Point 0
0x0200	Set-Point 1

6.1.3. Receive PDOs (RPDO1 & RPDO2)

Sent: CAN Master Node → Slave Node

RPDO1 - A PDO1 received by the EM100 will execute a single command selected by the bit set in the data frame (see below table).

Byte 0	b7	b6	b5	b4	b3	b2	b1	b0
Command								
Decimal								

Byte 1	b15	b14	b13	b12	b11	b10	b9	b8
Command	SG	SN			ST	RT	SZ	RZ
Decimal	128	64			08	04	02	01

RPDO2

A PDO2 received by the EM100 will execute a single command selected by the bit set in the data frame (see below table).

Byte 0	b7	b6	b5	b4	b3	b2	b1	b0
Command								
Decimal								

Byte 1	b15	b14	b13	b12	b11	b10	b9	b8
Command	TR							
Decimal	128							

6.1.4. SDOs

The CANopen SDO is a confirmed service, an over-run does not occur if the CANopen controller only communicates with the EM100 in the '*Pre-Operational*' state. When an SDO has been received by the controller no further communication takes place until the service has been acknowledged (or a timeout occurs).

SDOs

Are only available on request (see *complete Object Directory*).

They can be used for the complete setup of the EM100 via the CAN bus master e.g.:

Filter setting: Index 2100, Sub-index 4.

Filter Mode setting: Index 2100, Sub-index 9.

They can be used to get information regarding all the commands available e.g.:

Net Weight: Index 2900, Sub-index 2.

ADC Sample: Index 2900, Sub-index 7.

6.2. Communication Profile

Abbreviations used in tables:

ro	Read Only.
rw	Read/Write.
wo	Write Only.
const	Constant.
UI8	Unsigned Integer 8-bit.
UI16	Unsigned Integer 16-bit.
UI32	Unsigned Integer 32-bit.
REAL32	32-bit IEEE754 Floating Point.
STR	String.
TPDO	Transmit PDO.
RPDO	Receive PDO.
TAC	Traceable Access Code (incremented when saved). Get the current TAC value by reading index 2300,3. Write the same TAC value to this index to enable calibration. When the calibration is saved, the TAC value auto increments by one.

6.2.1. Object Dictionary

The EM100 object directory of the CANopen communication system is described below.

6.2.1.1. Communication Segment

Index	Sub Index	Name	Type	Attribute	Default Value	Description
1000	0	Device Type.	UI32	ro	0.	Non-standard device profile.
1001	0	Error Register.	UI8	ro	0.	Bit 0: Generic Error. Bit 1: Comms Error. Bit 2: Manufacturer Specific Error.
1002	0	Manufacturer Status Register.	UI32	ro	0.	Not Used.
1005	0	COB-ID Sync Message.	UI32	rw	80hex.	COB_ID of the Sync Message.
1006	0	Comms Cycle Period.	UI32	rw	0.	Not Used.
100C	0	Guard Time.	UI16	rw	320dec.	Cycle-Time in ms. Set by NMT master. 100Chex. and 100Dhex. are used if index 1017 is set to zero.
100D	0	Life Time Factor.	UI8	rw	3.	Set by NMT master.

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1014	0	COB_ID Emergency Message.	UI32	ro	80h+NodeID.	COMB_ID of the emergency object.
1017	0	Heartbeat Time.	UI16	rw	0.	Producer heartbeat time in ms. If index 1017hex. is non-zero, heartbeat protocol is used, otherwise Node Guard protocol is used.
1018	0	Identity Object.	UI8	ro	4.	Identity Object.
	1	Vendor ID.	UI32	ro	044Ahex.	Vendor ID.
	2	Product Code.	UI32	ro	-	Product code.
	3	Revision No.	UI32	ro	-	Revision No.
	4	Serial No.	UI32	ro	-	Serial No.
1400	0	No. of Entries.	UI8	ro	2.	Comms parameters of RPDO1
	1	COB-ID of PDO1.	UI32	rw	200H+NodeID.	Using CANopen Addressing
	2	Transmission Type.	UI8	rw	FEhex.	Asynchronous Comms.
1401	0	No. of Entries.	UI8	ro	2.	Comms parameters of RPDO2
	1	COB-ID of PDO2.	UI32	rw	300H+NodeID.	Using CANopen Addressing.
	2	Transmission Type.	UI8	rw	FEhex.	Asynchronous Comms.
1402	0	No. of Entries.	UI8	ro	2.	Comms parameters of RPDO3
	1	COB-ID of PDO3.	UI32	rw	400H+NodeID.	Using CANopen Addressing
	2	Transmission Type.	UI8	rw	FFhex.	Asynchronous Comms.
1403	0	No. of Entries.	UI8	ro	2.	Comms parameters of RPDO4
	1	COB-ID of PDO4.	UI32	rw	500H+NodeID.	Using CANopen Addressing
	2	Transmission Type.	UI8	rw	FFhex.	Asynchronous Comms.
1600	0	No. of Entries.	UI8	ro	1.	Parameter Mapping of RPDO1.
	1	Command Byte.	UI32	ro	20060308hex.	Bitwise Mapping.
1601	0	No. of Entries.	UI8	ro	1.	Parameter Mapping of RPDO2.
	1	Command Byte.	UI32	ro	20060408hex.	Bitwise Mapping.
1602	0	No. of Entries.	UI8	ro	0.	Parameter Mapping of RPDO3.
1603	0	No. of Entries.	UI8	ro	0.	Parameter Mapping of RPDO4.
1800	0	No. of Entries.	UI8	ro	3.	Comms Parameters TPDO1.
	1	COB-ID of PDO.	UI32	rw	180H+NodeID	
	2	Transmission Type.	UI8	rw	FFhex.	
	3	Inhibit Time.	UI16	rw	1hex.	
1801	0	No. of Entries.	UI8	ro	3.	Comms Parameters TPDO2.
	1	COB-ID of PDO.	UI32	rw	280H+NodeID.	
	2	Transmission Type.	UI8	rw	FFhex.	
	3	Inhibit Time.	UI16	rw	1hex.	
1802	0	No. of Entries.	UI8	ro	3.	Comms Parameters TPDO3.
	1	COB-ID of PDO.	UI32	rw	380H+NodeID.	

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	2	Transmission Type.	UI8	rw	FFhex.	
	3	Inhibit Time.	UI16	rw	1hex.	
1803	0	No. of Entries.	UI8	ro	3.	Comms Parameters TPDO4.
	1	COB-ID of PDO.	UI32	rw	480H+NodeID.	
	2	Transmission Type.	UI8	rw	FFhex.	
	3	Inhibit Time.	UI16	rw	1hex.	
1A00	0	No. of Entries Mapped TPDO1.	UI8	ro	2.	Mapping Parameters TPDO1. 32-bit IEEE 754 Floating Point Weight Reading. Weight Status.
	1	1 st Object.	UI32	const	29000120hex.	
	2	2 nd Object.	UI32	const	29000D20hex.	
1A01	0	No. of Entries Mapped TPDO2.	UI8	ro	2.	Mapping Parameters TPDO2. 32-bit IEEE 754 Floating Point Average Reading. Status.
	1	1 st Object.	UI32	const	29000630hex.	
	2	2 nd Object.	UI32	const	29000D20hex.	
1A02	0	No. of Entries Mapped TPDO3.	UI8	ro	2.	Mapping Parameters TPDO3. 32-bit IEEE 754 Floating Point Tare Reading. Status.
	1	1 st Object.	UI32	const	29000320hex.	
	2	2 nd Object.	UI32	const	29000D20hex.	
1A03	0	No. Mapped Entries in TPDO4.	UI8	ro	0.	Mapping Parameters TPDO4.

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6.2.1.2. Manufacturer Segment

6.2.1.2.1. Save Parameters

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2004	0	No. of Entries.	UI8	ro	5	No. of Entries.
	1	Dummy.	UI8	wo	-	Not Used.
	2	Save Calibration	UI8	wo	0.	Save Calibration Settings (TAC).
	3	Save General.	UI8	wo	0.	Save General Settings.
	4	Save Dosing.	UI8	wo	0.	Save Dosing Settings.
	5	Save Set-Point.	UI8	wo	0.	Save Set-Point Settings.

6.2.1.2.2. Gateway Parameters

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2006	0	No. of Entries.	UI8	ro	4.	No. System Entries.
	1	Dummy.	UI8	wo	-	Not Used.
	2	Set Factory Default.	UI8	wo	0.	Set Factory Defaults (TAC).
	3	Command Byte1.	UI8	wo	0.	See RPDO1.
	4	Command Byte2.	UI8	wo	0.	See RPDO2.

6.2.1.2.3. General Parameters

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2100	0	No. of Entries.	UI8	ro	24.	No. of Entries.
	1	Dummy.	I32	rw	-	Not Used.
	2	Dummy.	I32	rw	-	Not Used.
	3	Dummy.	I32	rw	-	Not Used.
	4	Filter Setting.	I32	rw	3.	Filter Setting.
	5	Dummy.	I32	rw	-	Not Used.
	6	Logic Outputs.	I32	rw	0.	Digital Outputs.
	7	Logic Inputs.	I32	ro	0.	Digital Inputs.
	8	Measure Time.	I32	rw	0.	Measuring Time.
	9	Filter Mode.	I32	rw	0.	Filter Mode.
	10	No-Motion Range.	I32	rw	1.	No Motion Range.
	11	No-Motion Time.	I32	rw	1000.	No Motion Time.
	12	Output Mask.	I32	rw	0.	Digital Outputs Mask.
	13	Dummy.	I32	rw	-	Not Used.
	14	Start Delay.	I32	rw	0.	Start Delay.
	15	Dummy.	I32	rw	-	Not Used.
	16	Dummy.	I32	rw	-	Not Used.
	17	Update Rate.	I32	rw	0.	Update Rate.
	18	Zero Tracking.	I32	rw	0.	Zero Track (TAC).
	19	Dummy.	I32	rw	-	Not Used.
	20	Dummy.	I32	rw	-	Not Used.
	21	Dummy.	I32	rw	-	Not Used.
	22	Reserved.	I32	rw	1.	Do Not Change.
	23	Preset Tare.	I32	rw	0.	Preset Tare.
	24	Warm-Up Time.	UI16	rw	0.	Transmit Readings Only When Time Elapsed.

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6.2.1.2.4. Calibration Parameters

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2300	0	No. of Entries.	UI8	ro	24.	No. of Entries.
	1	Absolute Gain.	I32	rw	20000.	Absolute Gain Calibrate (TAC).
	2	Absolute Zero.	I32	rw	0.	Absolute Zero Calibrate (TAC).
	3	Calibrate Enable.	I32	rw	0.	Calibrate Enable (Enable TAC).
	4	Calibrate Gain.	I32	rw	20000.	Calibrate Gain (TAC).
	5	Dummy.	I32	rw	-	Not Used.
	6	Dummy.	I32	rw	-	Not Used.
	7	Calibrate Max 1.	I32	rw	999999	Calibrate Max 1 (TAC).
	8	Calibrate Min.	I32	rw	-999999	Calibrate Min (TAC).
	9	Dummy.	I32	rw	-	Not Used.
	10	Calibrate Zero.	I32	rw	0.	Calibrate Zero (TAC).
	11	Decimal Point.	I32	rw	3.	Decimal Point (TAC).
	12	Display Step Size.	I32	rw	1.	Display Step Size (TAC).
	13	Multi Range.	I32	rw	0.	Multi-Range/Multi-Interval (TAC)
	14	Calibrate Max 2.	I32	rw	0.	Calibrate Max 2 (TAC).
	15	Calibrate Max 3.	I32	rw	0.	Calibrate Max 3 (TAC).
	16	Initial Zero Range.	I32	rw	0.	Initial Zero Range (TAC).
	17	Zero Range.	I32	rw	0.	Zero Range (TAC).
	18	Tare Mode.	I32	rw	0.	Tare Mode (TAC).
	19	Non-Volatile Tare.	I32	rw	0.	Non-Volatile Tare (TAC).
	20	Non-Volatile Zero.	I32	rw	0.	Non-Volatile Zero (TAC).
	21	ADC Counts Zero.	UI32	ro	0.	ADC Counts at Zero Calibrate.
	22	ADC Counts Span.	UI32	ro	0.	ECAL ADC Counts at Span Calibrate.
	23	Correct Zero.	UI32	wo	0.	Correct Zero Post-Cal (TAC).
	24	Calibration Weight.	UI32	rw	20000.	ECAL Weight Parameter (TAC).

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6.2.1.2.5. Data Access

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2900	0	No. of Entries.	UI8	ro	13	No. of Entries.
	1	Gross Weight.	Real32	ro	-	Gross Weight.
	2	Net Weight.	Real32	ro	-	Net Weight.
	3	Tare.	Real32	ro	-	Tare.
	4	Dosed Weight.	Real32	ro	-	Dosed Weight.
	5	Dosed Tare.	Real32	ro	-	Dosed Tare.
	6	Average Weight.	Real32	ro	-	Average Weight.
	7	ADC Sample.	I32	ro	-	ADC Sample.
	8	Device ID.	UI32	ro	-	Device ID.
	9	Firmware Version.	UI32	ro	-	Firmware Version.
	10	Device Status.	UI32	ro	-	Device Status.
	11	Dummy.	UI32	ro	-	Not Used.
	12	Serial No.	UI32	ro	-	Serial No.
	13	Qualifier.	UI32	ro	-	Extended Status – see TPDOs.

6.2.1.2.6. Sync Parameters

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2B00	0	No. of Entries.	UI8	ro	2.	No. of Entries.
	1	Sync Mode.	UI8	rw	0.	Sync Mode.
	2	Sync Frequency.	UI16	rw	1.	Sync Frequency.

6.2.1.2.7. Tare Zero Commands

Index	Sub Index	Name	Type	Attribute	Default Value	Description
2C00	0	No. of Entries.	UI8	ro	4	No. of Entries.
	1	Set Tare.	UI8	wo	0.	Set Tare (Tare ON).
	2	Reset Tare.	UI8	wo	0.	Reset Tare (Tare OFF)
	3	Set System Zero.	UI8	wo	0.	Set System Zero (Zero ON).
	4	Reset System Zero.	UI8	wo	0.	Reset System Zero (Zero OFF).

6.3. CANopen Frames

A CANopen data telegram or frame is constructed as below. The EM100 uses expedited transfer only i.e. each communication is contained within one frame (not sent over several).

For CANopen purposes an EM100 module is the 'Server' and CAN Master is the 'Client'.

6.3.1. SDO CAN Frame

This has 4 components:

The COB-ID uniquely identifies what communication type it is and its destination (request) OR origin node (response).

Specifier – indicates to the EM100 a command or response.

Parameter – which object (index) is to be read or written.

Data – the data read or written to the object.

COB-ID

Hex. Value	Transmission
600Hex.	Master → EM100.
580Hex.	EM100 → Master.

The node ID is added to this value so to communicate with node 4.

Master node → EM100 node uses 604Hex.

EM100 node → Master node uses 584Hex.

The command specifier is broken down as follows:

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
SP			Reserved	N		E	S

Where data is:

SP:

1 = Write object value to EM100 (SDO Download request)

2 = Read object value from EM100 (SDO Upload request and response)

3 = Confirmation of write (ACK)

4 = Abort SDO transfer.

When data is being written to or returned from the node the following applies:

for upload requests they are 0.

E: 1 = expedited i.e. data is in bytes 4-7 (always true).

S: =1 if data size is defined.

N: If S = 1, then the number of data bytes that do not contain data (of bytes 4-7).

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6.4. Overall CAN Frame

COB-ID	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
	Specifier	Parameter Location			Data			
	Specifier	Index Lo Byte	Index Hi Byte	Sub-Index	Data Byte 0	Data Byte 1	Data Byte 2	Data Byte 3

Examples using node ID 1: All values are Hexadecimal.

SDO READ

Master node requests the Vendor ID located at Index 1018, Sub Index 1.

Master Transmits

Transmit Master → EM100 COB-ID 600H+Node ID	Request	Index Lo	Index Hi	Sub-Index	Data 1	Data 2	Data 3	Data 4
601	40	18	10	1	00	00	00	00

EM100 Responds ACK

Transmit EM100 → Master COB-ID 580H+Node ID	Response	Index Lo	Index Hi	Sub-Index	Data 1	Data 2	Data 3	Data 4
581	43	18	10	1	4A	04	00	00

EM100 Responds NACK (example shows a response to an out of range sub-index)

Transmit EM100 → Master COB-ID 580H+Node ID	Response	Index Lo	Index Hi	Sub-Index	Data 1	Data 2	Data 3	Data 4
581	80	17	10	FF	11	00	09	06

Returned data shows the error 06090011 – Sub-Index FF does not exist.

In the CANopen standard, this is called an ‘SDO Abort Code’.

6.4.1. SDO Write

Master node write filter located at Index 1017, Sub Index 4.

Master Transmits

Transmit master → EM100 COB-ID 600H+Node ID	Request	Index Lo	Index Hi	Sub-Index	Data 1	Data 2	Data 3	Data 4
601	23	00	21	04	03	00	00	00

EM100 Responds ACK

Transmit EM100 → Master COB-ID 580H+Node ID	Response	Index Lo	Index Hi	Sub-Index	Data 1	Data 2	Data 3	Data 4
581	60	00	21	04	00	00	00	00

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EM100 Responds NACK (example shows a response to an out of range sub-index).

Transmit EM100 → Master COB-ID 580H+Node ID	Response	Index Lo	Index Hi	Sub- Index	Data 1	Data 2	Data 3	Data 4
581	80	00	21	FF	00	00	09	06

Returned data shows the SDO Abort Code 06090011 – Sub-Index FF does not exist.

6.4.2. NMT Master Message

The NMT master message is used by the master node to switch a node OR all nodes into a specified NMT state. There is no acknowledge response – the node will simply go to state (if possible).

COB- ID	Requested Action	Transmit master → EM100 Node ID
	Byte 1	Byte 2
000	01Hex. = Start. 02Hex. = Stop. 80Hex. = Pre-operational. 81Hex. = Reset Node. 82Hex. = Reset Communication.	01 – 127decimal. OR 00 (Broadcast).

6.4.3. Heartbeat Message

This is sent by an individual node when the heartbeat protocol is activated. It contains only one byte, indicating the NMT State.

COB-ID	NMT State
700 + Node ID.	0 = Boot-up. 4 = Stopped. 5 = Operational. 127 = Pre-Operational. Note: bit-7 is reserved.

6.4.4. Emergency Message

This is sent by an individual node to warn of an error condition in the internal functioning of that node.

Transmit EM100->Master COB-ID 80H+Node ID	Error Code		Error Registered	Manufacturer Specific Error				
	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
81	10	81	00	00	00	00	00	00

The above shows the error code 8110 which is CAN overrun (i.e. objects are lost).

Emergency Objects:

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Abort Code (Hex.)	Description
8110	Monitoring – CAN Over-run (objects lost).
8120	Monitoring – CAN in error passive mode.
8130	Monitoring – Node Guarding or heartbeat error.
8140	Monitoring – Recovering from bus off.
8210	Protocol – PDO not processed due to error length.
8220	Protocol – PDO length exceeded.

6.4.5. SDO Abort Codes

Abort Code (Hex.)	Description
05030000	Toggle Bit not alternated.
05040000	SDO Protocol timed out.
05040001	Client server command specifier not valid.
05040005	Out of memory.
06010000	Unsupported access to an object.
06010001	Attempt to read a write only object.
06010002	Attempt to write to a read only object.
06020000	Object does not exist in the object dictionary.
06040043	General parameter compatibility.
06040047	General internal compatibility in the device.
06060000	Access failed due to a hardware error.
06070010	Data type does not match. Length of service parameter does not match.
06070012	Data type does not match. Service parameter too long.
06070013	Data type does not match. Service parameter too short.
06090011	Sub-Index does not exist.
06090030	Out of range parameter (write access only).
06090031	Value of parameter is too high.
06090032	Value of parameter is too low.
06090036	Maximum value is less than the minimum.
08000000	General error.
08000020	Data cannot be transferred or stored to the application.

7. Approved Applications

The term '*Approved*' applies whenever the weighing application is intended to be used for '*legal-for-trade*' weighing – that is, trade transactions and certain medical applications. Such applications are bound by the legal metrology regulations of the relevant governments around the world, most countries will comply with either the relevant ENs (Euro Norms) or the relevant OIML (*Organisation Internationale de Métrologie Légale*) recommendations.

The EM100 has been approved as a component for use in weighing systems according to OIML recommendation R76, the highest performance level approved being Class II, 20,000 intervals (e) and $n \times 20,000$ intervals ($n=2, 3$). The notified approval body is the Danish Electronics, Light & Acoustics (DELTA/Force).

This approval will allow the use in approved weighing systems throughout Europe and in many other countries of the World. To achieve approval for an application, it will be necessary to satisfy the relevant governmental trading standards authority that the requirements of the various rules and regulations have been satisfied. This task is greatly simplified if the key components of the weighing system, namely the load cells and the weighing indicator or digitizer, are already approved as '*components*'. Usually, discussions with the appropriate weighing equipment approvals officers at the relevant national weights & measures office will then reveal the extent of any pattern testing that may be necessary to ensure compliance.

7.1. Restrictions in Approved Applications

Several performance restrictions must come into force. These restrictions are the number of display divisions, which become limited to 20,000 divisions and the sensitivity per display division which becomes $0.1\mu\text{V}$ per division. Once installed in the application, an '*approved*' application will require '*stamping*' by an officer of the relevant governmental department. This certifies the equipment or system as being in accordance to the relevant regulations and within calibration limits.

7.2. Traceable Access Code (TAC)

The user software must then provide a guard against improper access of the calibration commands (see '*Calibration Commands*' section). The EM100 features the '*Traceable Access Code*' or TAC method of controlling the access to the calibration commands group. This means a code is maintained within the device and is incremented whenever any change to any of the calibration commands is saved. When performing the '*stamping*' test, the appropriate officer will make a note of the TAC value and advise the user that any change to this code which occurs prior to the regular re-inspection by the trading standards office, will result in legal prosecution of the user. The user software is required as a condition of approval, to make the TAC available to the weight display indicator or console, on demand.