

Main Features

- Microsoft Windows API
- Real-Time API
- CIA 402 Motion Library
- Powerful utility: NexECM Studio

Product Overview

NexECM is a NexCOBOT developed software EtherCAT master stack, NexECM runs on an RTOS platform and provides a precise communication cyclic frame from EtherCAT master to EtherCAT slave. NexECM provides all the basic EtherCAT communication functions which allow users to directly access standard EtherCAT slaves, such as process data access, mail box data access and support CoE (CANOpen over EtherCAT).

For users who want to configure EtherCAT slaves, NexECM also provides a powerful EtherCAT configuration tool called NexECM Studio. NexECM Studio help users scan EtherCAT slaves and create ENI (EtherCAT Network Information) files. For servo motor applications and digital I/O applications, NexECM Configuration Tool also provides a friendly user interface to directly control digital I/O, and servo motors based on the CiA402 standard.

NexECM provides Microsoft Windows APIs for users to build their own EtherCAT applications. For EtherCAT slaves synchronization control, ECM synchronizes with Distributed Clocks (DC) including master synchronization.

Specifications

Realtime OS

- INtime

Comm. Cycle

- Min. cycle time up to 250µs

Slave No.

- 64

Motion API

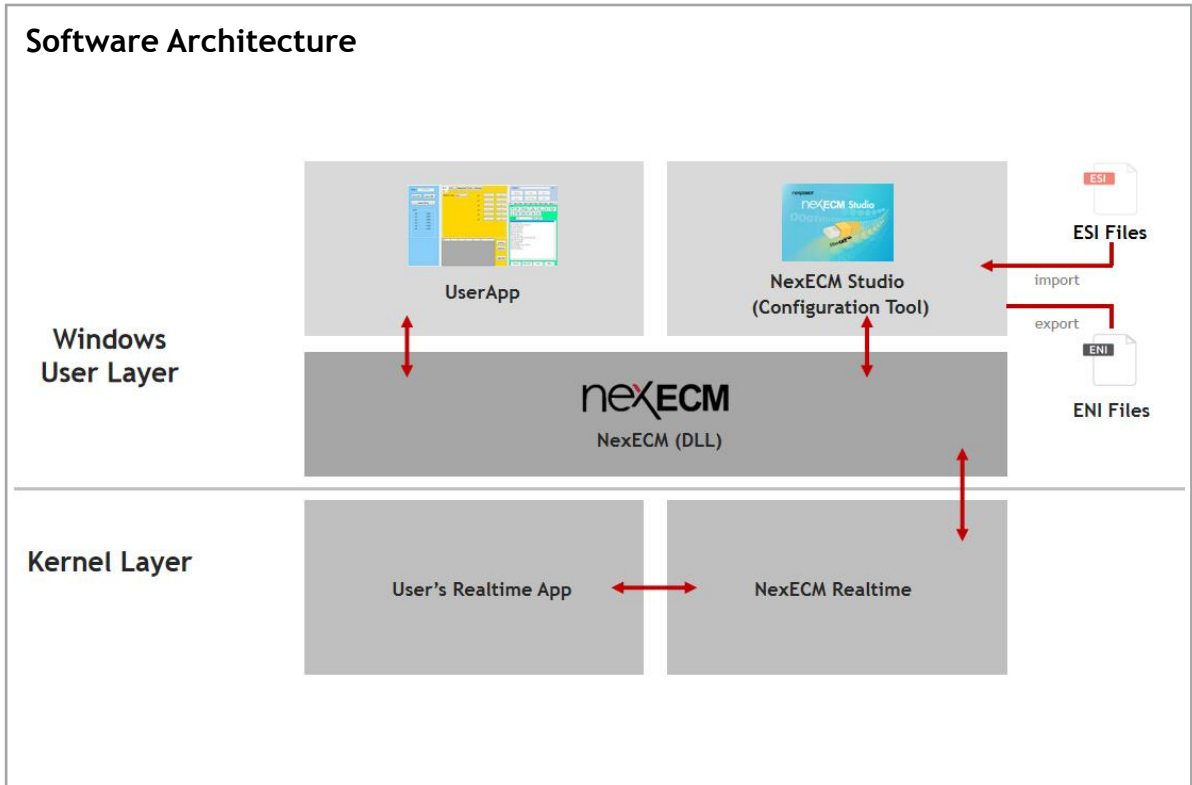
- CiA 402 Motion Library

Example

- VB6/VC/VB.NET

Powerful Utility

- NexECM Studio
Scan EtherCAT slave devices
Import ESI File, and export ENI file
Configure EtherCAT slave devices
Monitor EtherCAT communication quality
Test functions for EtherCAT slave devices



Ordering Information

NexECM (P/N:98ROBO000003F)
NexECM Realtime Software