

Start Guide

OrientalMotor AZD4A-KED EtherCAT SubDevice (PP mode)



86Duino Coding IDE 501

EtherCAT Library

(Version 1.0)

Revision

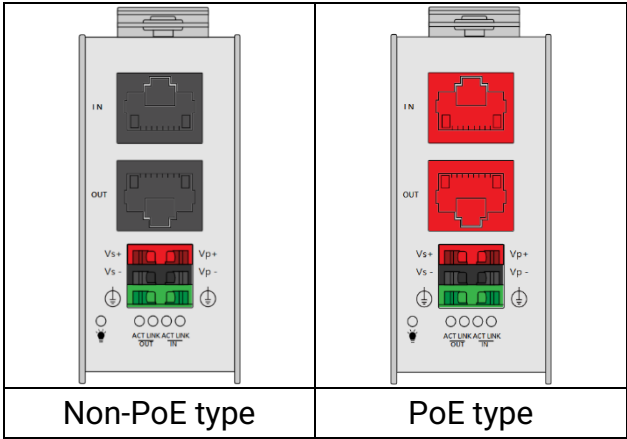
Date	Version	Description
2025/8/8	Version1.0	New Release.

Preface

In this guide, we will show you how to use the EtherCAT MDevice QEC-M-01 and the OrientalMotor 4-Axis AZ Series EtherCAT Controller AZD4A-KED.

Notes QEC’s PoE (Power over Ethernet)

In QEC product installations, users can easily distinguish between PoE and non-PoE: if the RJ45 house is red, it is PoE type, and if the RJ45 house is black, it is non-PoE type.



PoE (Power over Ethernet) is a function that delivers power over the network. QEC can be equipped with an optional PoE function to reduce cabling. In practice, PoE is selected based on system equipment, so please pay attention to the following points while evaluating and testing:

- 1. The PoE function of QEC is different and incompatible with EtherCAT P, and the PoE function of QEC is based on PoE Type B, and the pin functions are as follows:



- 2. When connecting PoE and non-PoE devices, make sure to disconnect Ethernet cables at pins 4, 5, 7, and 8 (e.g., when a PoE-supported QEC EtherCAT MDevice connects with a third-party EtherCAT SubDevice).
- 3. QEC’s PoE power supply is up to 24V/3A.

1. Connection and wiring hardware

The following devices are used here:

1. QEC-M-01 (EtherCAT MDevice)
2. AZD4A-KED, 4-Axis AZ Series EtherCAT Controller
3. AZM66MK, 2.36 in. (60 mm) AZ Series Stepper Motor with Absolute Mechanical Encoder (Brake Type) (DC Input)
4. AZM46A0K, 1.65 in. (42 mm) AZ Series Stepper Motor with Absolute Mechanical Encoder (DC Input)



1.1 QEC-M-01

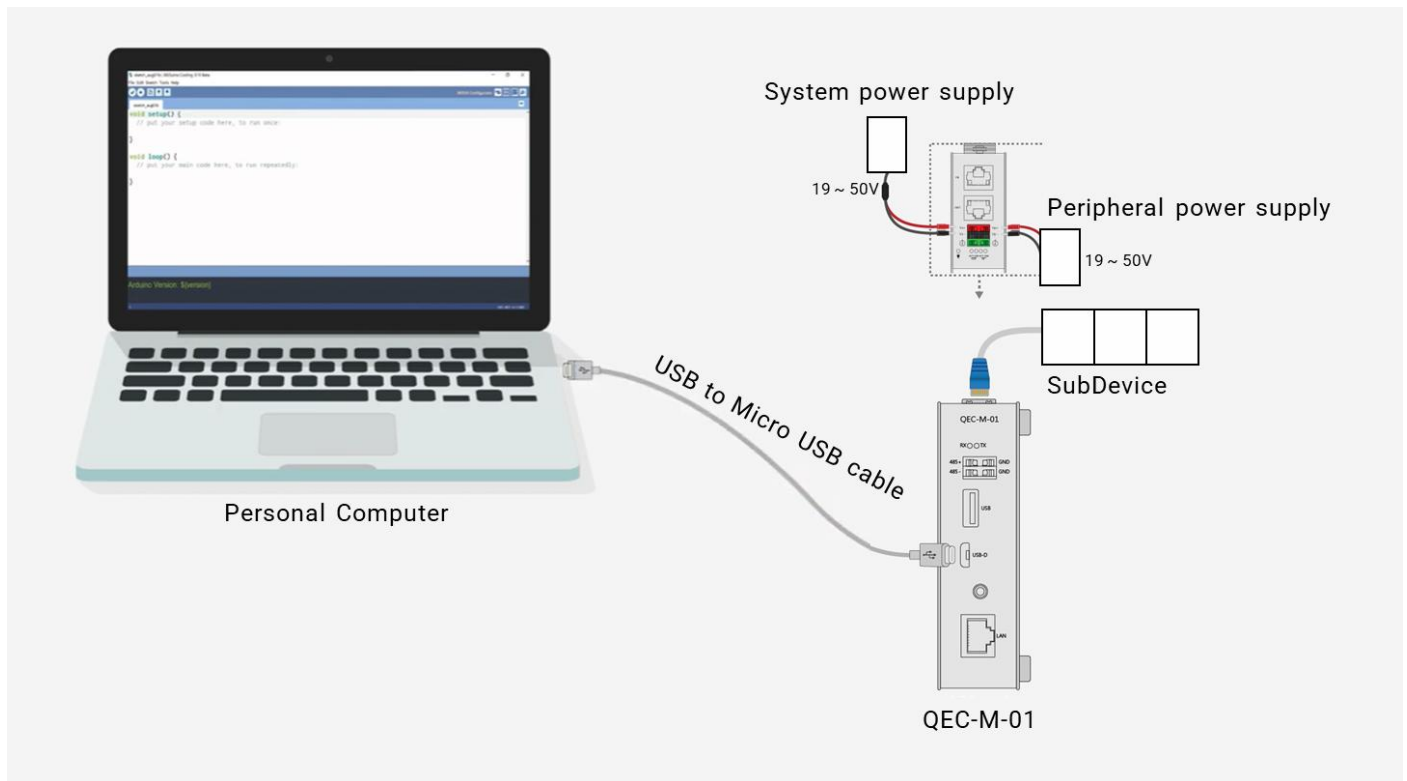
QEC EtherCAT MDevice.

1. Power Supply:

Connect to Vs+/Vs- and Vp+/Vp- power supplies via EU terminals for 24V power.

2. EtherCAT Connection:

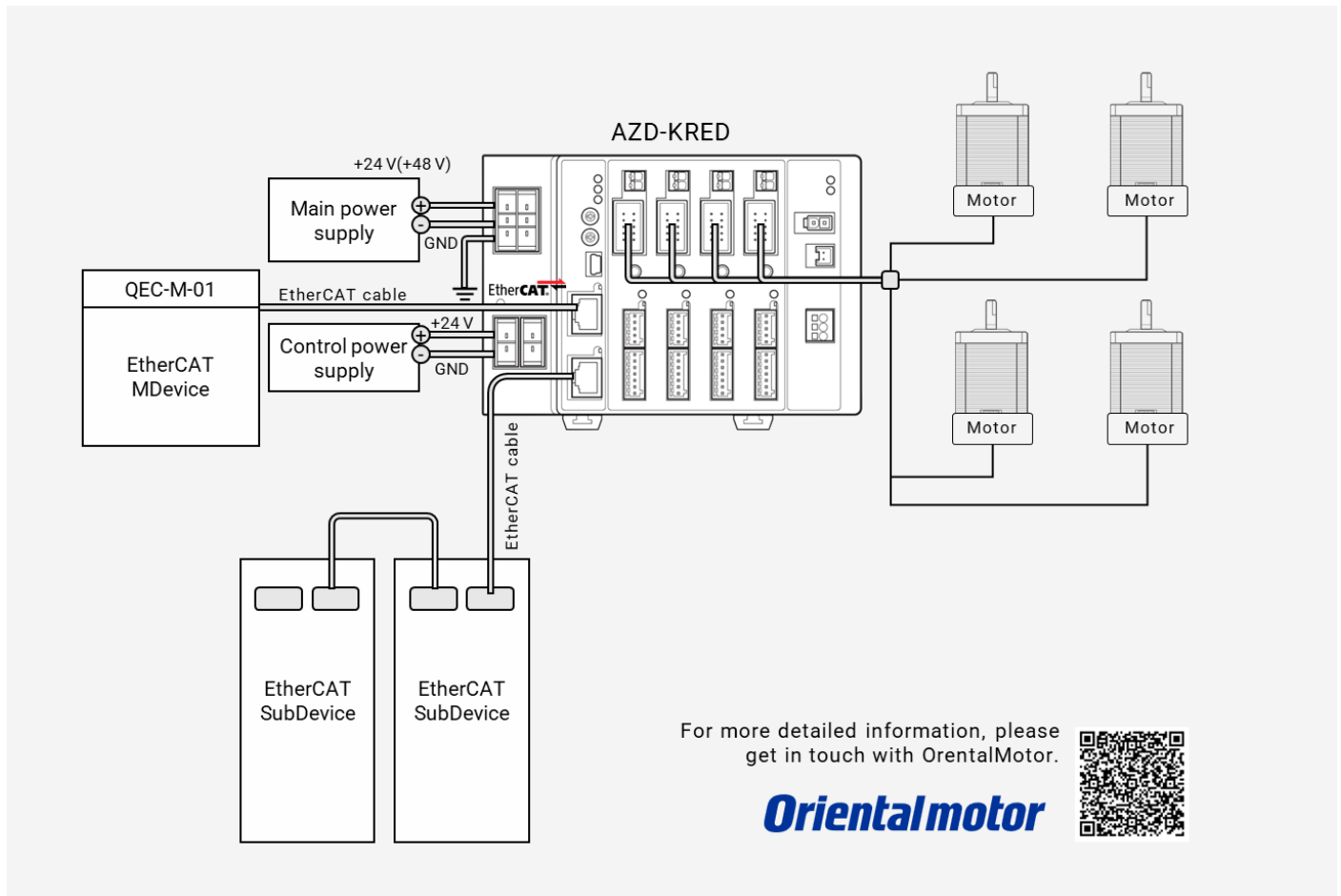
Using the EtherCAT Out port (On the top side) connected to the EtherCAT In port of AZD-KRED via RJ45 cable.



1.2 AZD4A-KED

AZD4A-KED, a 4-Axis AZ Series EtherCAT Controller / Driver (24/48 VDC).

This figure shows an example when the motors are connected.



1. It is an OrientalMotor cable. Purchase is required separately.
2. Connecting the control power supply allows you to continue monitoring even if the main power supply is shut off. Connect it as necessary.
3. It is recommended that a circuit breaker or a circuit protector is connected because incorrect wiring may cause the internal input circuit to short-circuit.

Note

- Connect the connectors securely. Insecure connections may cause malfunction or damage to the motor or the driver.
- When connecting the cables, secure them so that no load is applied to the connectors. Applying a load to the connector may result in a connection failure, causing the driver to malfunction.
- Keep **10 m (32.8 ft.)** or less for the wiring distance between a motor and a driver. Exceeding **10 m (32.8 ft.)** in the wiring distance may result in an increase of the electrical noise emitted from the driver.

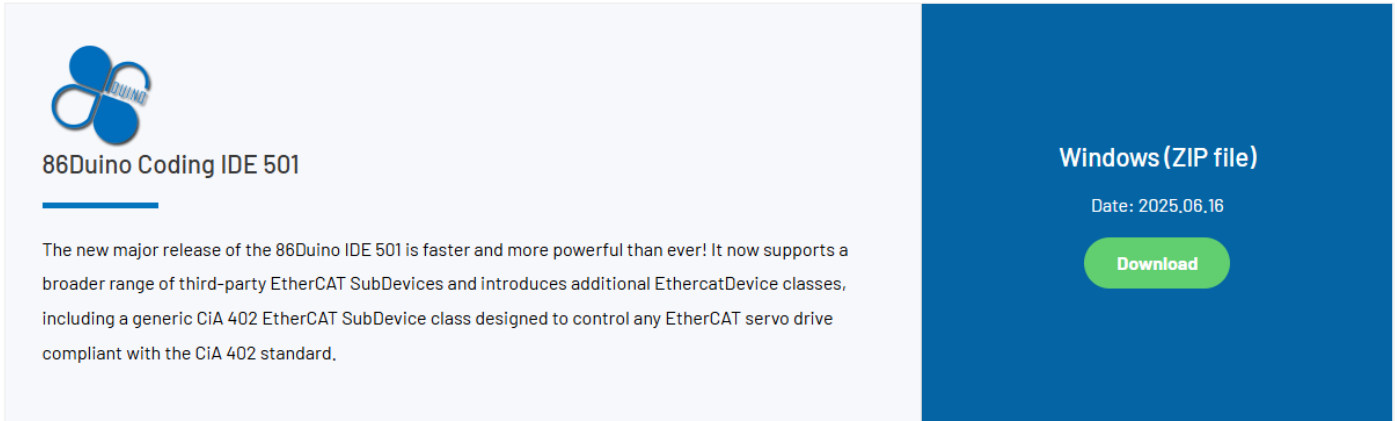
- Keep **2 m (6.6 ft.)** or less for the cable length of the main power supply and control power supply.

Memo

- Before connecting or disconnecting a connector, turn off the main power supply and the control power supply, and check the **PWR/ALM LED** has been turned off.
- When disconnecting the connector, pull out while pressing the latches on the connector with fingers.

2. Software/Development Environment

Download 86duino IDE from <https://www.qec.tw/software/>.



86Duino Coding IDE 501

The new major release of the 86Duino IDE 501 is faster and more powerful than ever! It now supports a broader range of third-party EtherCAT SubDevices and introduces additional EthercatDevice classes, including a generic CiA 402 EtherCAT SubDevice class designed to control any EtherCAT servo drive compliant with the CiA 402 standard.

Windows (ZIP file)

Date: 2025.06.16

[Download](#)

After downloading, please unzip the downloaded zip file, no additional software installation is required, just double-click 86duino.exe to start the IDE.



Note:

If Windows displays a warning, click Details once and then click the Continue Run button once.

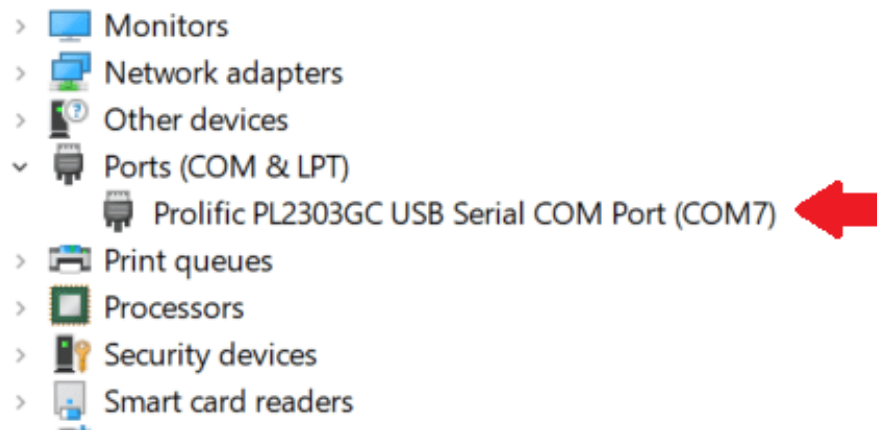
86Duino Coding IDE 501+ looks like below.



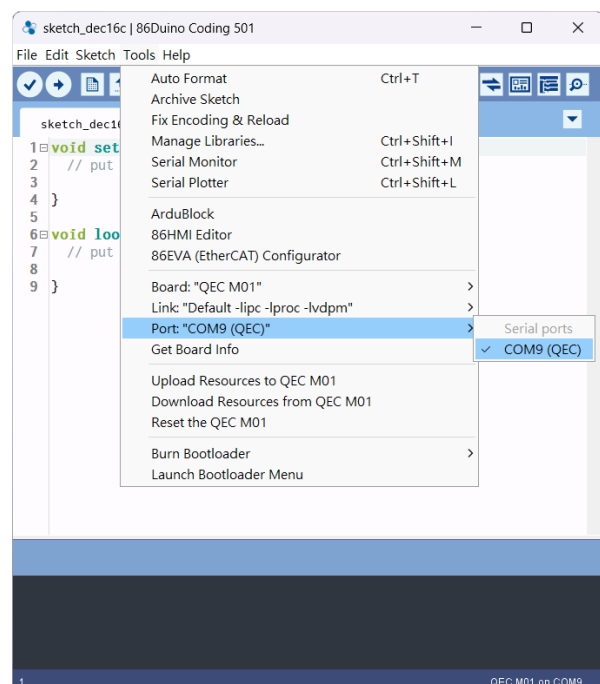
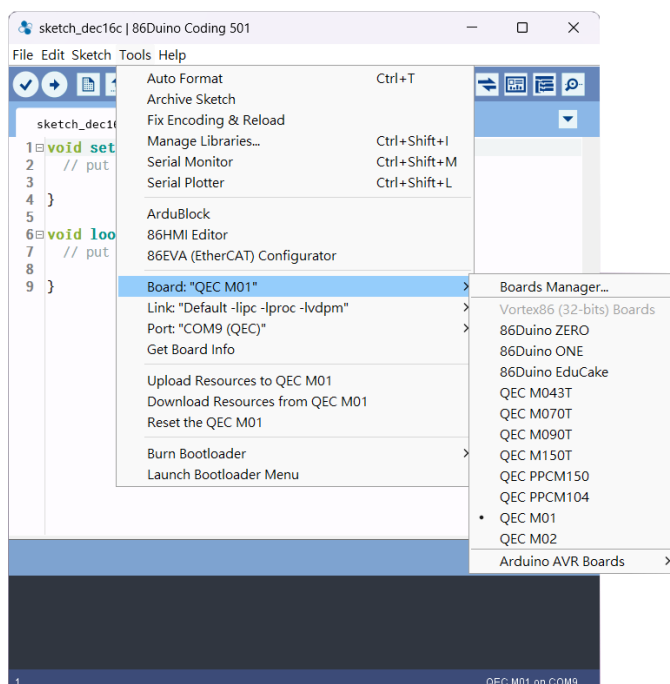
3. Connect to PC and set up the environment

Follow the steps below to set up the environment:

1. Connect the QEC-M-01 to your PC via a Micro USB to USB cable (86Duino IDE installed).
2. Turn on the QEC power.
3. Open "Device Manager" (select in the menu after pressing Win+X) -> "Ports (COM & LPT)" in your PC and expand the ports; you should see that the "Prolific PL2303GC USB Serial COM Port (COMx)" is detected; if not, you will need to install the required drivers.
(For Windows PL2303 driver, you can download [here](#))



4. Open the 86Duino IDE.
5. Select the correct board: In the IDE's menu, select Tools > Board > QEC-M-01 (or the QEC MDevice model you use).
6. Select Port: In the IDE's menu, select Tools > Port and select the USB port to connect to the QEC MDevice (in this case, COM9 (QEC)).



4. Write code

The EtherCAT MDevice (QEC-M-01) and the OrientalMotor 4-Axis AZ Series EtherCAT Controller (AZD4A-KED) can be configured and programmed via the EtherCAT library in the 86Duino IDE. The Arduino development environment has two main parts: `setup()` and `loop()`, which correspond to initialization and main programs. Before operating the EtherCAT network, you must configure it once. The process should be from Pre-OP to OP mode in EtherCAT devices.

The following program sets the AZD4A-KED driver into 4 CiA402 objects under Profile Position (PP) mode for continuous back-and-forth motion.

- EtherCAT Cycle time: 1 millisecond.
- EtherCAT mode: ECAT_SYNC.
- Distributed Clock: Open. Follow the cycle time.

The `EthercatMaster` object, `master`, represents QEC-M-01; And the `EthercatDevice_CiA402` object array: `motors[0]` to `motors[3]` represent the AZD4A-KED driver.

1. In Setup Function:

- Initializes the serial (115200).
- Begin the EtherCAT MDevice. Switch the EtherCAT to the PRE-OPERATIONAL state.
- Attach each AZD4A-KED axis to the EtherCAT network and configure in Profile Position (PP) mode.
- Configure each driver in DC mode and set the same cycle time as EtherCAT communication.
- For the AZD4A-KED configuration, we have to release Homing-related locks (according to the vendor object, this is a convenience) by `sdoDownload8(0x4148, I + 1, 0x01)`.
- Start the EtherCAT MDevice. Set the EtherCAT cycle time and mode in the `start()` function. Switch the EtherCAT state machine to the OPERATIONAL state.
- Enable each motors, changing CiA402 state to CIA402_OPERATION_ENABLED.
- Configure profile parameters: Velocity = 10,000, Acceleration = 5,000, Deceleration = 5,000.
- Use `delay(1000)` to wait for it to change successfully.

2. In Loop Function:

The loop continuously monitors each motor's position and manages its PP mode state machine.

For each motor:

- If the motor is idle (`isMoving == false`), calculate the next absolute target position based on its direction flag and send a `pp_Run()` command.
- If the target position is reached (`pp_IsTargetReached()`), reverse the direction and mark the motor as idle for the next move.
- Position values for all motors are printed to the serial monitor each cycle.

Each axis moves absolutely between +100,000 and -100,000 position units.

All four axes operate independently but concurrently.

The motion is non-blocking, meaning one motor's operation does not wait for another.

Here is the code:

```
#include "Ethercat.h"

#define CYCLETIME    (1000000)
#define MAX_DRIVES  (4)

EthercatMaster master;
EthercatDevice_CiA402 motors[MAX_DRIVES];

int direction[MAX_DRIVES] = {1, 1, 1, 1};
bool isMoving[MAX_DRIVES] = {false, false, false, false};
const int moveDistance = 100000;

void setup() {
    Serial.begin(115200);

    Serial.println(master.begin()); // Master begin

    for (int i = 0; i < MAX_DRIVES; i++) {
        Serial.println(motors[i].attach(0, i, master)); // Attach
        motors[i].setDc(CYCLETIME);
        motors[i].sdoDownload8(0x4148, i + 1, 0x01); // Homing object release
        motors[i].setCiA402Mode(CIA402_PP_MODE);
    }

    Serial.println(master.start(CYCLETIME, ECAT_SYNC)); // Master start

    for (int i = 0; i < MAX_DRIVES; i++)
    {
        Serial.print("Enable");
        Serial.print(i);
        Serial.print(": ");
        Serial.println(motors[i].enable());

        motors[i].pp_SetVelocity(10000);
        motors[i].pp_SetAcceleration(5000);
        motors[i].pp_SetDeceleration(5000);
    }
}
```

```

}

delay(1000);
}

void loop() {



  for (int i = 0; i < MAX_DRIVES; i++) {
    // Print out the position
    Serial.print("Motor");
    Serial.print(i);
    Serial.print(": ");
    Serial.print(motors[i].getPositionActualValue());
    Serial.print(" ");

    // Moving action by PP
    if (!isMoving[i]) {
      int target = direction[i] * moveDistance;
      motors[i].pp_Run(target, CIA402_PP_ABSOLUTE, true);
      isMoving[i] = true;
    }

    if (isMoving[i] && motors[i].pp_IsTargetReached()) {
      direction[i] *= -1;    // reverse
      isMoving[i] = false;  // reset
    }
  }
  Serial.println(" ");
  Serial.println(" ----- ");
}

```

Note:

Once the code is written, click on the toolbar to  compile, and to confirm that the compilation is complete and error-free, you can click  to upload.

File Edit Sketch Tools Help





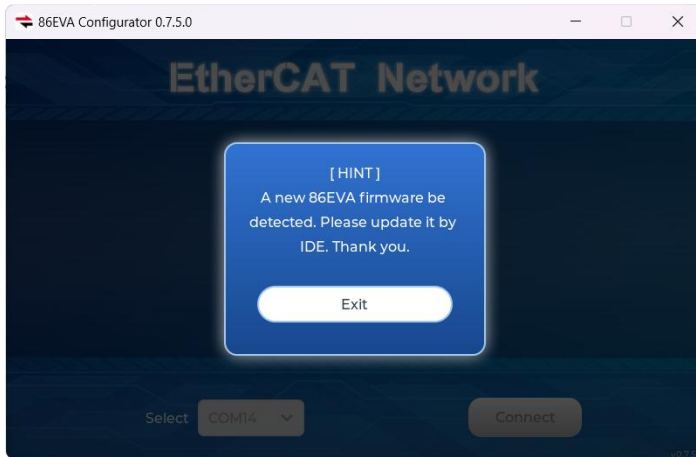
It will print each motors' current position to the serial monitor.

[illegible]

Troubleshooting

QEC-M-01 cannot successfully upload code

When you are unable to successfully upload code, please open 86EVA to check if your QEC EtherCAT MDevice's environment is abnormal. As shown in the figure below, please try updating your QEC EtherCAT MDevice's environment, which will include the following three items: Bootloader, EtherCAT firmware, and EtherCAT tool.



Now, we will further explain how to proceed with the update:

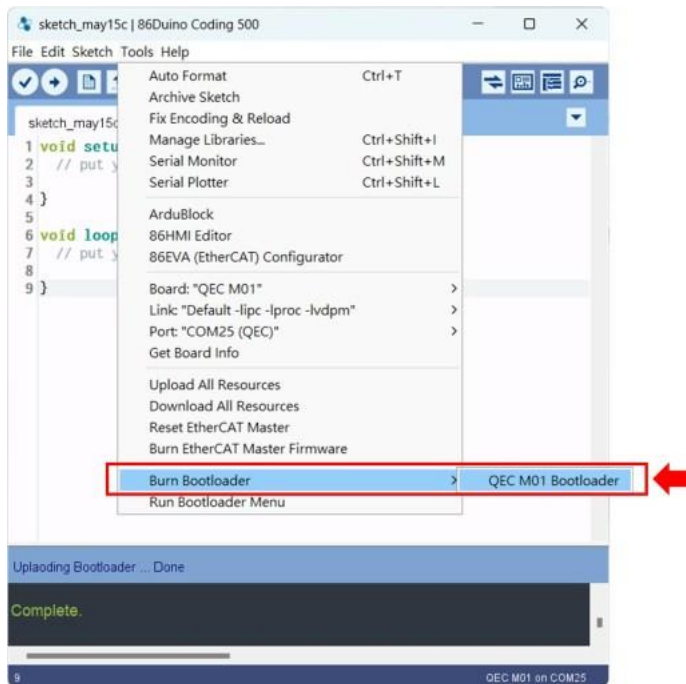
Step 1: Setting up QEC-M

1. Download and install 86Duino IDE 500 (or a newer version): You can download it from [Software](#).
2. Connect the QEC-M: Use a USB cable to connect the QEC-M to your computer.
3. Open 86Duino IDE: After the installation is complete, open the 86Duino IDE software.
4. Select Board: From the IDE menu, choose "Tools" > "Board" > "QEC-M-01" (or the specific model of QEC-M you are using).
5. Select Port: From the IDE menu, choose "Tools" > "Port" and select the USB port to which the QEC-M is connected.

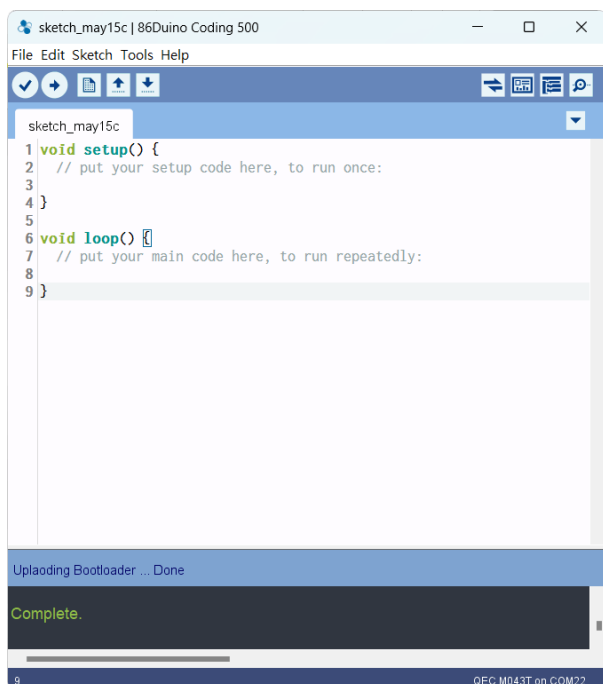
Step 2: Click “Burn Bootloader” button

After connecting to your QEC-M product, go to “Tools”> “Burn Bootloader”. The currently selected QEC-M name will appear. Clicking on it will start the update process, which will take approximately 5-20 minutes.

QEC-M-01:



Step 3: Complete the Update



After completing the above steps, your QEC-M has been successfully updated to the latest version of the development environment.

Warranty

This product is warranted to be in good working order for a period of one year from the date of purchase. Should this product fail to be in good working order at any time during this period, we will, at our option, replace or repair it at no additional charge except as set forth in the following terms. This warranty does not apply to products damaged by misuse, modifications, accident or disaster. Vendor assumes no liability for any damages, lost profits, lost savings or any other incidental or consequential damage resulting from the use, misuse of, originality to use this product. Vendor will not be liable for any claim made by any other related party. Return authorization must be obtained from the vendor before returned merchandise will be accepted. Authorization can be obtained by calling or faxing the vendor and requesting a Return Merchandise Authorization (RMA) number. Returned goods should always be accompanied by a clear problem description.

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