AMIS−30523

Product Preview

CAN Micro−Stepping Motor Driver

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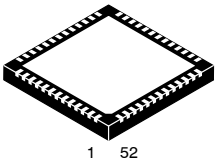
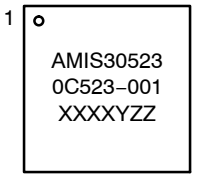


QFN52, 8x8
CASE 485M

MARKING DIAGRAM



0C523−001	= Specific Device Code
XXXX	= Date Code
WL	= Wafer Lot
Y	= Assembly Location
ZZ	= Traceability Code

ORDERING INFORMATION

See detailed ordering and shipping information in the package dimensions section on page 34 of this data sheet.

Introduction

The AMIS−30523 is a micro−stepping stepper motor driver for bipolar stepper motors with an embedded CAN transceiver.

The motor driver is connected through I/O pins and a SPI interface with an external microcontroller. It has an on−chip voltage regulator, reset−output and watchdog reset, able to supply peripheral devices. It contains a current−translation table and takes the next micro−step depending on the clock signal on the “NXT” input pin and the status of the “DIR” (=direction) register or input pin.

The CAN transceiver is the interface between a (CAN) protocol controller and the physical bus. It provides differential transmit capability to the bus and differential receive capability to the CAN controller. To cope with the long bus delay the communication speed needs to be low. The integrated transceiver allows low transmit data rates down 10 kbit/s or lower.

The AMIS−30523 is ideally suited for general−purpose stepper motor applications in the automotive, industrial, medical, and marine environment. With the on−chip voltage regulator and embedded CAN transceiver it further reduces the BOM for mechatronic stepper applications.

Key Features

Motor Driver

- Dual H−Bridge for 2−Phase Stepper Motors
- Programmable Peak−Current up to 1.2 A Continuous (1.6 A for a Short Time)*
- On−Chip Current Translator
- SPI Interface
- Seven Step Modes from Full Step up to 32 Micro−Steps
- PWM Current Control with Automatic Selection of Fast and Slow Decay and Fully Integrated Current−Sense
- Full Output Protection and Diagnosis
- Thermal Warning and Shutdown
- Integrated 5 V Regulator to Supply External Microcontroller

CAN Transceiver

- Compatible with the ISO 11898 Standard
- Wide Range of Bus Communication Speed (0 up to 1 Mbit/s)
- Allows Low Transmit Data Rate in Networks Exceeding 1 km
- Extremely Low Current Standby Mode with Wake−up via the Bus
- Low EME: Common−Mode Choke is No Longer Required
- Differential Receiver with Wide common−mode range (±35 V)
- Voltage Source via V_{SPLIT} Pin for Stabilizing the Recessive Bus Level
- No Disturbance of the Bus Lines with an Un−Powered Node
- Logic Level Inputs Compatible with 3.3 V Devices
- These are Pb−Free Devices

*Output Current Level May be Limited by Ambient Temperature and Heat Sinking

This document contains information on a product under development. ON Semiconductor reserves the right to change or discontinue this product without notice.

BLOCK DIAGRAM

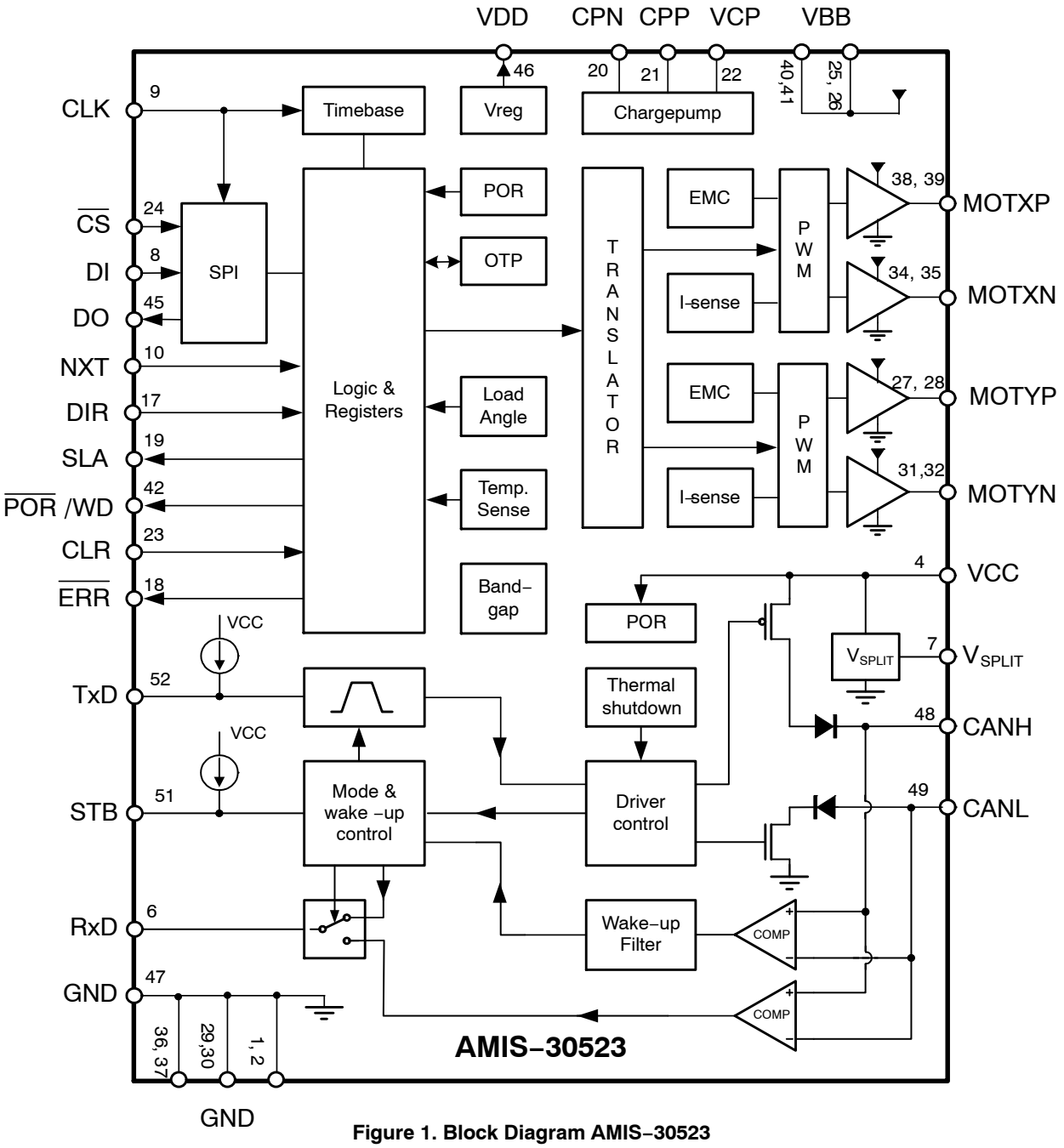


Figure 1. Block Diagram AMIS−30523

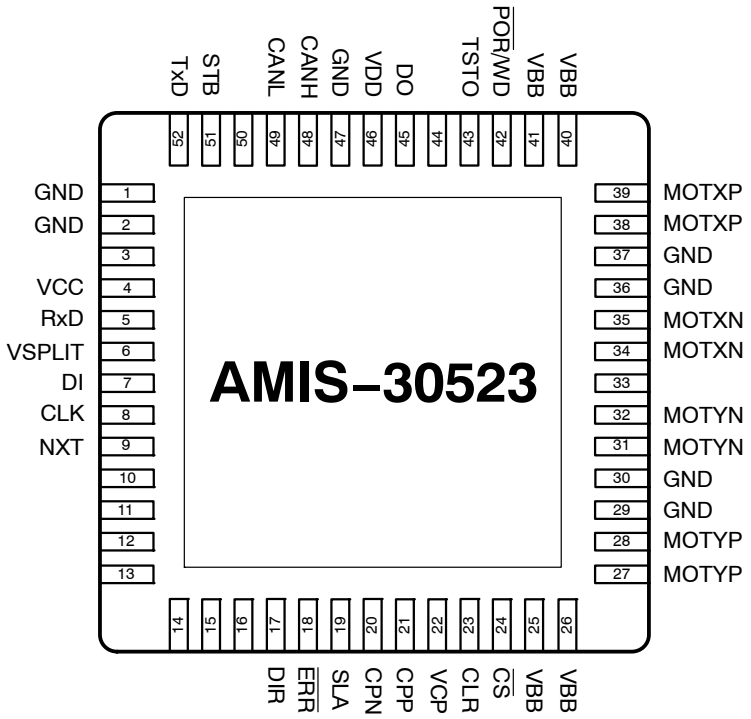


Figure 2. Pin Out AMIS−30523

Table 1. PIN DESCRIPTION

Name	Pin	Description	Type	Equivalent Schematic
GND	1, 2	Ground	Supply	
/	3	No function (to be left open in normal operation)		
VCC	4	CAN Supply voltage	Supply	
/	5	No function (to be left open in normal operation)		
RXD	6	CAN Receive data output; dominant transmitter → low output	Digital Output	
VSPLIT	7	CAN common−mode stabilization output	Supply	
DI	8	SPI Data In	Digital Input	Type 2
CLK	9	SPI Clock Input	Digital Input	Type 2
NXT	10	Next micro−step input	Digital Input	Type 2
/	11 .. 16	No function (to be left open in normal operation)		
DIR	17	Direction input	Digital Input	Type 2
ERRB	18	Error output (open drain)	Digital Output	Type 4
SLA	19	Speed load angle output	Analog Output	Type 5
CPN	20	Negative connection of charge pump capacitor	High Voltage	
CPP	21	Positive connection of charge pump capacitor	High Voltage	
VCP	22	Charge pump filter−capacitor	High Voltage	
CLR	23	“Clear” = chip reset input	Digital Input	Type 1
CSB	24	SPI chip select input	Digital Input	Type 2
VBB	25, 26	High voltage supply Input	Supply	Type 3
MOTYP	27, 28	Negative end of phase Y coil output	Driver Output	
GND	29, 30	Ground, heat sink	Supply	

Table 1. PIN DESCRIPTION

Name	Pin	Description	Type	Equivalent Schematic
MOTYN	31, 32	Positive end of phase Y coil output	Driver Output	
/	33	No function (to be left open in normal operation)		
MOTXN	34, 35	Positive end of phase X coil output	Driver Output	
GND	36, 37	Ground, heat sink	Supply	
MOTXP	38, 39	Negative end of phase X coil output	Driver Output	
VBB	40, 41	High voltage supply input	Supply	Type 3
PORB/WD	42	Power−on−reset and watchdog reset output (open drain)	Digital Output	Type 2
TST0	43	Test pin input (to be tied to ground in normal operation)	Digital Input	
/	44	No function (to be left open in normal operation)		
DO	45	SPI data output (open drain)	Digital Output	Type 4
VDD	46	5V Logic Supply Output (needs external decoupling capacitor)	Supply	Type 6
GND	47	Ground	Supply	
CANH	48	High−level CAN bus line (high in dominant mode)	Analog Output	
CANL	49	Low−level CAN bus line (low in dominant mode)	Analog Output	
/	50	No function (to be left open in normal operation)		
STB	51	CAN stand−by mode control input	Digital Input	
TXD	52	CAN transmit data input; low input → dominant driver; internal pull−up current	Digital Input	

Table 2. ABSOLUTE MAXIMUM RATINGS

Symbol	Parameter	Min	Max	Unit
V_{BB}	Analog DC supply voltage (Note 1)	−0.3	+40	V
V_{CC}	CAN Supply voltage	−0.3	+7	V
V_{CANH}, V_{CANL}, V_{SPLIT}	DC voltage CANH ,CANL and VSPLIT (Note 2)	−50	+50	V
V_{TRANS}	Transient voltage CANH, CANL and VSPLIT (Note 3)	−300	+300	V
T_{ST}	Storage temperature	−55	+150	°C
T_J	Junction Temperature under bias (Note 4)	−40	+170	°C
V_{ESD}	Electrostatic discharges on component level, All pins (Note 5)	−2	+2	kV
V_{ESD}	Electrostatic discharges on component level, All pins (Note 7)	−500	+500	V
V_{ESD}	Electrostatic discharges on CANH, CANL and VSPLIT (Note 6)	−6	+6	kV
V_{ESD}	Electrostatic discharges on CANH and CANL (Note 7)	−500	+500	V
V_{ESD}	Electrostatic discharges on component level, HiV pins (Note 6)	−6	+6	kV
Latch−up	Static latch−up at all pins		100	mA

Stresses exceeding Maximum Ratings may damage the device. Maximum Ratings are stress ratings only. Functional operation above the Recommended Operating Conditions is not implied. Extended exposure to stresses above the Recommended Operating Conditions may affect device reliability.

1. For limited time < 0.5 s.
2. For 0 < V_{CC} < 5.25 V unlimited time
3. Applied transient waveforms in accordance with ISO 7637 part 3, test pulses 1, 2, 3a, and 3b.
4. Circuit functionality not guaranteed.
5. Standardized Human body model (100 pF via 1.5 kΩ, according to JEDEC EIA−JESD22−A114−B).
6. Standardized human body model electrostatic discharge (ESD) pulses (100 pF via 1.5 kΩ) stressed pin to ground.
7. Standardized charged device model ESD pulses when tested according to ESD STM5.3.1−1999.

Table 3. THERMAL RESISTANCE

Package	Thermal Resistance			Unit
	Junction−to−Exposed Pad (Rth_{J-EP})	Junction−to−Ambient (Rth_{J-A})		
		1S0P Board	2S2P Board	
QFN−52	0.95	60	30	K/W

EQUIVALENT SCHEMATICS

Following figure gives the equivalent schematics of the user relevant inputs and outputs. The diagrams are simplified representations of the circuits used.

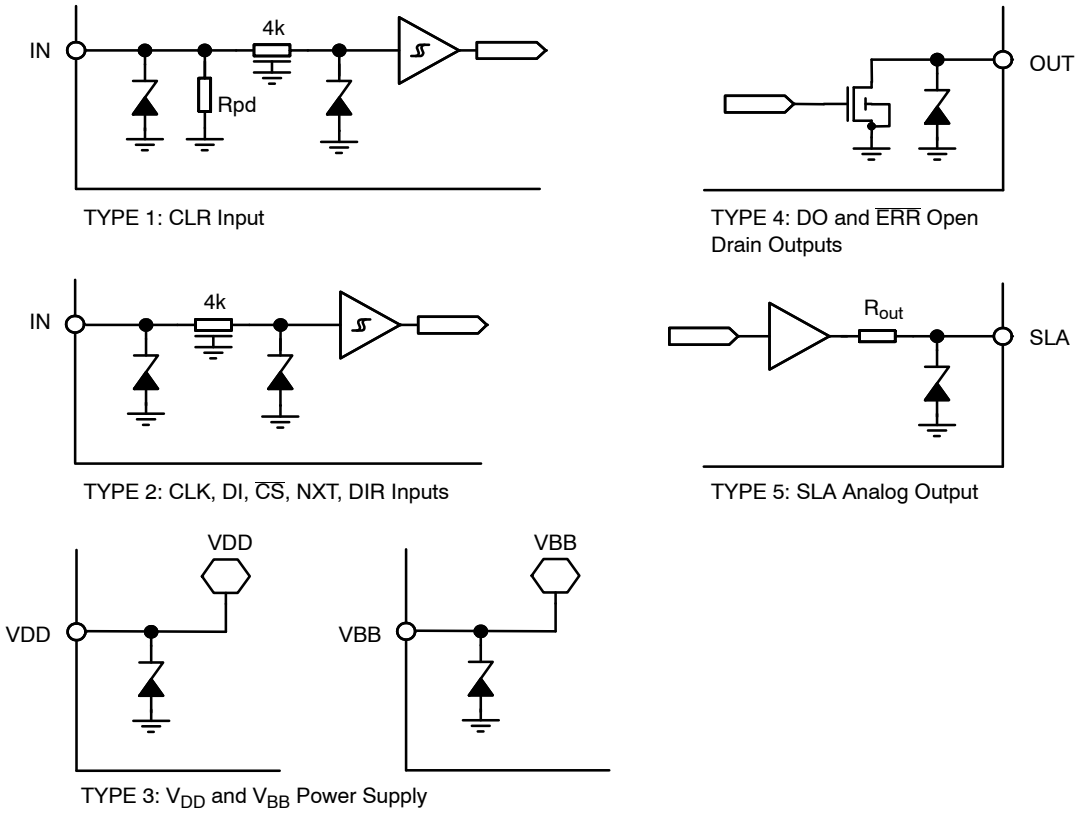


Figure 3. In− and Output Equivalent Diagrams

PACKAGE THERMAL CHARACTERISTICS

The AMIS−30523 is available in a QFN−52 package. For cooling optimizations, the QFN has an exposed thermal pad which has to be soldered to the PCB ground plane. The ground plane needs thermal vias to conduct the heat to the bottom layer. Figure 4 gives an example for good power distribution solutions.

For precise thermal cooling calculations the major thermal resistances of the device are given. The thermal media to which the power of the devices has to be given are:

- Static environmental air (via the case)
- PCB board copper area (via the exposed pad)

The thermal resistances are presented in Table 5: DC Parameters Motor Driver.

The major thermal resistances of the device are the Rth from the junction to the ambient (Rth_{J-A}) and the overall Rth from the junction to exposed pad (Rth_{J-EP}). In Table 3 one can find the values for the Rth_{J-A} and Rth_{J-EP}, simulated according to JESD−51:

The Rth_{J-A} for 2S2P is simulated conform JEDEC JESD−51 as follows:

- A 4−layer printed circuit board with inner power planes and outer (top and bottom) signal layers is used
- Board thickness is 1.46 mm (FR4 PCB material)
- The 2 signal layers: 70 μm thick copper with an area of 5500 mm^2 copper and 20% conductivity

- The 2 power internal planes: 36 μm thick copper with an area of 5500 mm^2 copper and 90% conductivity

The Rth_{J-A} for 1S0P is simulated conform JEDEC JESD−51 as follows:

- A 1−layer printed circuit board with a single power and signal layer
- Board thickness is 1.46 mm (FR4 PCB material)
- The layer has a thickness of 70 μm copper with an area of 5500 mm^2 copper and 20% conductivity

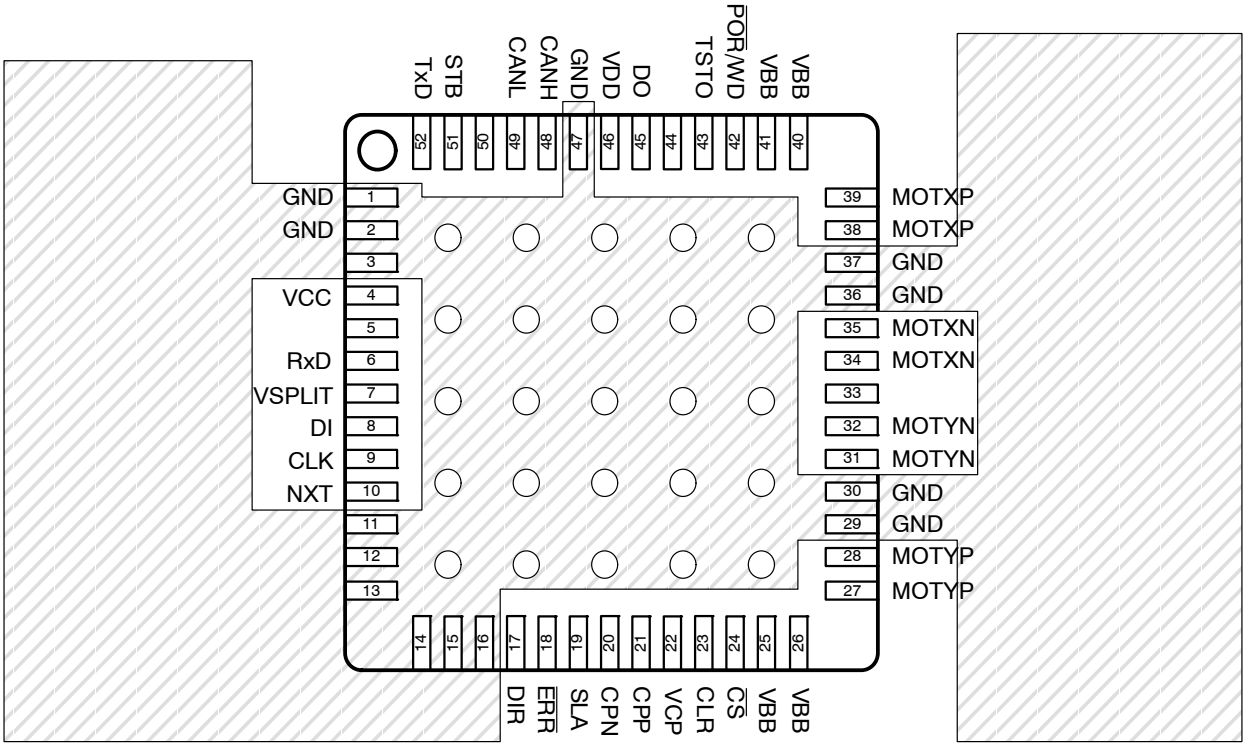


Figure 4. Example of QFN−52 PCB Ground Plane Layout in Top View (preferred layout at top and bottom)

ELECTRICAL SPECIFICATION

Recommend Operation Conditions

Operating ranges define the limits for functional operation and parametric characteristics of the device. Note that the functionality of the chip outside these operating ranges is not guaranteed. Operating outside the recommended operating ranges for extended periods of time may affect device reliability.

Table 4. OPERATING RANGES

Symbol	Parameter	Min	Max	Unit
V_{BB}	Motor Driver Analog DC supply	6	30	V
V_{CC}	CAN transceiver DC supply	4.75	5.25	V
T_J	Junction temperature (Note 8)	−40	+172	°C

8. No more than 100 cumulative hours in life time above T_{tw}.

Table 5. DC PARAMETERS MOTOR DRIVER

(The DC Parameters are Given for V_{BB} and Temperature in Their Operating Ranges Unless Otherwise Specified)
Convention: Currents Flowing in the Circuit are Defined as Positive.

Symbol	Pin(s)	Parameter	Remark/ Test Conditions	Min	Typ	Max	Unit
SUPPLY AND VOLTAGE REGULATOR							
V_{BB}	VBB	Nominal operating supply range		6		30	V
I_{BB}		Total internal current consumption	Unloaded outputs			8	mA
I_{BBS}		Sleep current in V_{BB} (Note 9)	Unloaded outputs			100	μA
V_{DD}	VDD	Regulated Output Voltage		4.50	5	5.50	V
I_{INT}		Internal load current	Unloaded outputs			8	mA
I_{LOAD}		Max. Output Current (external and internal loads)	6 V ≤ V_{BB} < 8 V	15			mA
			8 V ≤ V_{BB} v 30 V	40			mA
I_{DDLIM}		Current limitation	Pin shorted to ground			200	mA
I_{LOAD_PD}		Output current in Power Down		1			mA
POWER ON RESET (POR)							
V_{DDH}	VDD	Internal POR comparator threshold	VDD rising	3.9	4.15	4.4	V
V_{DDL}		Internal POR comparator threshold	VDD falling		3.80		V
V_{DDHYS}		Hysteresis between V_{DDH} and V_{DDL}		0.1	0.35	0.6	V
MOTORDRIVER							
$I_{MDmax,Peak}$	MOTXP MOTXN MOTYP MOTYN	Max current through motor coil in normal operation			1600		mA
$I_{Mdmax,RMS}$		Max RMS current through coil in normal operation			800		mA
I_{Mdabs}		Absolute error on coil current		−10		10	%
I_{Mdrel}		Error on current ratio I_{coilx} / I_{coily}		−7		7	%
I_{SET_TC1}		Temperature coefficient of coil current set−level, CUR[4:0] = 0 ... 27 (Note 10)	−40 °C ≤ T_J ≤ 160°C		−240		ppm/K
I_{SET_TC2}		Temperature coefficient of coil current set−level, CUR[4:0] = 28 ... 31 (Note 10)	−40 °C ≤ T_J ≤ 160°C		−490		ppm/K
R_{HS}		On−resistance high−side driver, CUR[4:0] = 0 ... 31	V_{BB} = 12 V, T_J = 27°C		0.45	0.56	Ω
			V_{BB} = 12 V, T_J = 160°C		0.94	1.25	Ω
R_{LS3}		On−resistance low−side driver, CUR[4:0] = 23 ... 31	V_{BB} = 12 V, T_J = 27°C		0.45	0.56	Ω
			V_{BB} = 12 V, T_J = 160°C		0.94	1.25	Ω
R_{LS2}		On−resistance low−side driver, CUR[4:0] = 16 ... 22	V_{BB} = 12 V, T_J = 27°C		0.90	1.2	Ω
			V_{BB} = 12 V, T_J = 160°C		1.9	2.5	Ω
R_{LS1}		On−resistance low−side driver, CUR[4:0] = 9 ... 15	V_{BB} = 12 V, T_J = 27°C		1.8	2.3	Ω
			V_{BB} = 12 V, T_J = 160°C		3.8	5.0	Ω
R_{LS0}		On−resistance low−side driver, CUR[4:0] = 0 ... 8	V_{BB} = 12 V, T_J = 27°C		3.6	4.5	Ω
			V_{BB} = 12 V, T_J = 160°C		7.5	10	Ω
I_{Mpd}		Pull down current motor pins	HiZ mode		1		mA

9. Characterization Data Only, not tested in production
10. The coil current at a given junction temperature is calculated as: I_{coil} @ T_J = I_{coil} [1 + (T_J − 125) x I_{SET_TCi} x 10^{-6}]. See also paragraph Programmable Peak Current.
11. Not valid for pins with internal Pull Down resistor.
12. No more than 100 cumulated hours in life time above T_{tw}.
13. Thermal shutdown is derived from Thermal Warning.

Table 5. DC PARAMETERS MOTOR DRIVER

(The DC Parameters are Given for V_{BB} and Temperature in Their Operating Ranges Unless Otherwise Specified)
Convention: Currents Flowing in the Circuit are Defined as Positive.

Symbol	Pin(s)	Parameter	Remark/ Test Conditions	Min	Typ	Max	Unit
DIGITAL INPUTS							
I_{leak}	DI, CLK NXT, DIR CLR, CSB	Input Leakage (Note 11)	T_J = 160°C			1	μA
V_{IL}		Logic Low Threshold		0		0.65	V
V_{IH}		Logic High Threshold		2.20		V_{DD}	V
R_{pd_CLR}	CLR	Internal Pull Down Resistor		120		300	kΩ
R_{pd_TST}	TST0	Internal Pull Down Resistor		3		9	kΩ
DIGITAL OUTPUTS							
V_{OL}	DO, ERRB, PORB/ WD	Logic Low level open drain	I_{OL} = 5 mA			0.3	V
THERMAL WARNING & SHUTDOWN							
T_{tw}		Thermal Warning		138	145	152	°C
T_{tsd}		Thermal shutdown (Notes 12 and 13)			T_{tw} + 20		°C
CHARGE PUMP							
V_{opCP}	VCP	Output voltage	6 V< V_{BB} < 15 V		2 * V_{BB} − 2		V
			15 V < V_{BB} < 30 V	V_{BB} + 9	V_{BB} + 11.5	V_{BB} + 16	V
PACKAGE THERMAL RESISTANCE VALUE							
Rth_{J-A}	QFN package	Thermal Resistance Junction−to−Ambient	Simulated Conform JEDEC JESD−51, (2S2P)		30		K/W
Rth_{J-EP}		Thermal Resistance Junction−to−Exposed Pad			0.95		K/W
SPEED AND LOAD ANGLE OUTPUT							
V_{out}	SLA	Output Voltage Range		0.2		V_{DD} − 0.2	V
V_{off}		Output Offset SLA pin		−50		50	mV
G_{sla}		Gain of SLA Pin = V_{BEMF} / V_{COIL}	SLAG = 0		0.5		
			SLAG = 1		0.25		
R_{out}		Output Resistance SLA pin	(Note 9)		0.23	1	kΩ
C_{load}		Load Capacitance SLA pin	(Note 9)			50	pF

9. Characterization Data Only, not tested in production
10. The coil current at a given junction temperature is calculated as: I_{coil} @ T_J = I_{coil} [1 + (T_J − 125) x I_{SET_TCi} x 10^{-6}]. See also paragraph Programmable Peak Current.
11. Not valid for pins with internal Pull Down resistor.
12. No more than 100 cumulated hours in life time above T_{tw}.
13. Thermal shutdown is derived from Thermal Warning.

Table 6. AC PARAMETERS MOTOR DRIVER (The AC Parameters are Given for V_{BB} and Temperature in Their Operating Ranges)

Symbol	Pin(s)	Parameter	Remark/ Test Conditions	Min	Typ	Max	Unit
INTERNAL OSCILLATOR							
f_{osc}		Frequency of internal oscillator		3.6	4	4.4	MHz
MOTOR DRIVER							
f_{PWM}	MOTxx	PWM frequency	Frequency depends only on internal oscillator	20.8	22.8	24.8	kHz
		Double PWM frequency		41.6	45.6	49.6	kHz
f_d		PWM jitter Depth (Note 14)			10		% f_{PWM}
tb_{rise}	MOTxx	Turn−on voltage slope, 10% to 90%	EMC[1:0] = 00		150		V/μs
			EMC[1:0] = 01		100		V/μs
			EMC[1:0] = 10		50		V/μs
			EMC[1:0] = 11		25		V/μs
tb_{fall}	MOTxx	Turn−off voltage slope, 90% to 10%	EMC[1:0] = 00		150		V/μs
			EMC[1:0] = 01		100		V/μs
			EMC[1:0] = 10		50		V/μs
			EMC[1:0] = 11		25		V/μs
DIGITAL OUTPUTS							
t_{H2L}	DO ERRB	Output fall−time from V_{inH} to V_{inL} (Note 14)	Capacitive load 400 pF and pull−up resistor of 1.5 kΩ			50	ns
CHARGE PUMP							
f_{CP}	CPN CPP	Charge pump frequency			250		kHz
t_{CPU}	MOTxx	Start−up time of charge pump (Note 14)	Spec external components See Table 10			5	ms
CLR FUNCTION							
t_{CLR}	CLR	Hard reset duration time		100			μs
POWER−UP							
t_{PU}	PORB/ WD	Power−up time	V_{BB} = 12 V, I_{LOAD} = 50 mA, C_{LOAD} = 220 nF			110	μs
t_{POR}		Reset duration	See Figure 22			100	ms
t_{RF}		Reset filter time	See Figure 22	1			μs
WATCHDOG							
t_{WDTO}	PORB/ WD	Watchdog time out interval	See Figure 23	32		512	ms
t_{WDPR}		Prohibited watchdog acknowledge delay	See Figure 23		2		ms
NXT FUNCTION							
t_{NXT_HI}	NXT	NXT Minimum, High Pulse Width	See Figure 5	2			μs
t_{NXT_HI}		NXT Minimum, Low Pulse Width	See Figure 5	2			μs
t_{DIR_SET}		NXT Hold Time, Following Change of DIR	See Figure 5		2		μs
t_{DIR_HOLD}		NXT Hold Time, Before Change of DIR	See Figure 5		2		μs

14. Characterization Data Only, not tested in production.

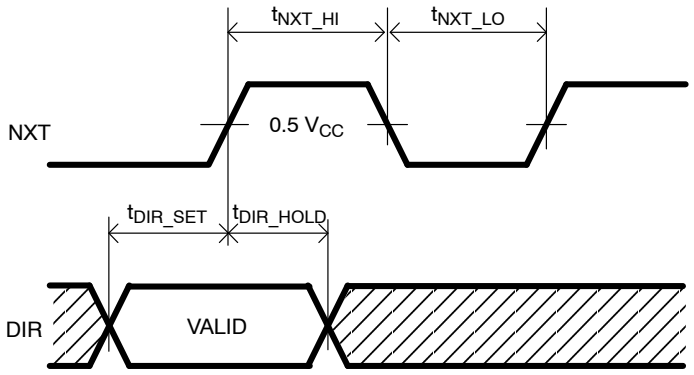


Figure 5. NXT−Input Timing Diagram

Table 7. SPI TIMING PARAMETERS

Symbol	Parameter	Min	Typ	Max	Unit
t_{CLK}	SPI clock period	1			μs
t_{CLK_HIGH}	SPI clock high time	100			ns
t_{CLK_LOW}	SPI clock low time	100			ns
t_{SET_DI}	DI set up time, valid data before rising edge of CLK	50			ns
t_{HOLD_DI}	DI hold time, hold data after rising edge of CLK	50			ns
t_{CSB_HIGH}	CSB high time	2.5			μs
t_{SET_CSB}	CSB set up time, CSB low before rising edge of CLK	100			ns
t_{SET_CLK}	CLK set up time, CLK low before rising edge of CSB	100			ns

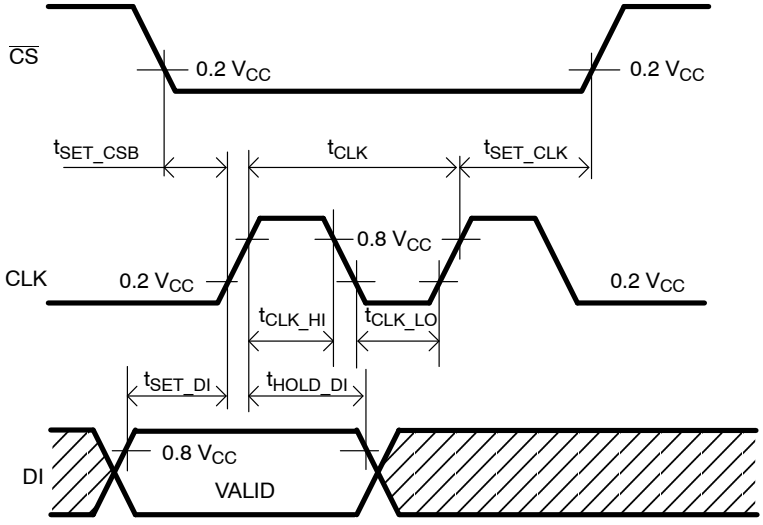


Figure 6. SPI Timing

Table 8. DC PARAMETERS CAN TRANSCEIVER

(The DC parameters are given for V_{CC} and temperature in its operating range; T_J = −40 to +150°C; R_{LT} = 60 Ω unless otherwise specified) Convention: currents flowing in the circuit are defined as positive.

Symbol	Pin(s)	Parameter	Remark / Test Conditions	Min	Typ	Max	Unit
SUPPLY							
I_{CC}	VCC	Supply current	Dominant; V_{TxD} = 0 V Recessive; V_{TxD} = V_{CC}		45	65	mA
I_{CCS}		Supply current in standby mode	$T_{J,max}$ = 100°C		4	8	mA
TRANSMITTER DATA INPUT							
V_{iH}	TXD	High−level input voltage	CAN bus output recessive	2.0	−	V_{CC} + 0.3	V
V_{iL}		Low−level input voltage	CAN bus output dominant	−0.3	−	+0.8	V
I_{iH}		High−level input current	V_{TxD} = V_{CC}	−5	0	+5	μA
I_{iL}		Low−level input current	V_{TxD} = 0 V	−75	−200	−350	μA
C_i		Input capacitance	(Note 15)	−	5	10	pF
TRANSMITTER MODE SELECT							
V_{iH}	TXD	High−level input voltage	Standby mode	2.0	−	V_{CC} + 0.3	V
V_{iL}		Low−level input voltage	Normal mode	−0.3	−	+0.8	V
I_{iH}		High−level input current	V_{STB} = V_{CC}	−5	0	+5	μA
I_{iL}		Low−level input current	V_{STB} = 0 V	−1	−4	−10	μA
C_i		Input capacitance	(Note 15)	−	5	10	pF
RECEIVER DATA OUTPUT							
V_{OH}	RXD	High−level output voltage	I_{RXD} = −10 mA	0.6 x V_{CC}		0.75 x V_{CC}	V
V_{OL}		Low−level output voltage	I_{RXD} = 5 mA		0.25	0.45	V
I_{oh}		High−level output current	V_o = 0.7 x V_{CC}	−5	−10	−15	mA
I_{ol}		Low−level output current	V_o = 0.3 x V_{CC}	5	10	15	mA
C_i		Input capacitance	(Note 15)	−	5	10	pF

15. Characterization Data Only, not tested in production.

Table 8. DC PARAMETERS CAN TRANSCEIVER

(The DC parameters are given for V_{CC} and temperature in its operating range; T_J = −40 to +150°C; R_{LT} = 60 Ω unless otherwise specified) Convention: currents flowing in the circuit are defined as positive.

Symbol	Pin(s)	Parameter	Remark / Test Conditions	Min	Typ	Max	Unit
BUS LINES							
$V_{o(reces)}$ (norm)	CANH CANL	Recessive bus voltage	V_{TxD} = V_{CC}; no load normal mode	2.0	2.5	3.0	V
$V_{o(reces)}$ (stby)		Recessive bus voltage	V_{TxD} = V_{CC}; no load standby mode	−100	0	100	mV
$I_{o(reces)}$ (CANH)		Recessive output current at pin CANH	−35 V < V_{CANH}< +35 V; 0 V < V_{CC} < 5.25 V	−2.5	−	+2.5	mA
$I_{o(reces)}$ (CANL)		Recessive output current at pin CANL	−35 V <V_{CANL} < +35 V; 0 V <V_{CC} < 5.25 V	−2.5	−	+2.5	mA
$V_{o(dom)}$ (CANH)		Dominant output voltage at pin CANH	V_{TxD} = 0 V	3.0	3.6	4.25	V
$V_{o(dom)}$ (CANL)		Dominant output voltage at pin CANL	V_{TxD} = 0 V	0. 5	1.4	1.75	V
$V_{o(dif)}$ (bus_dom)		Differential bus output voltage (V_{CANH} − V_{CANL})	V_{TxD} = 0 V; dominant; 42.5 Ω < R_{LT} < 60 Ω	1.5	2.25	3.0	V
$V_{o(dif)}$ (bus_rec)		Differential bus output voltage (V_{CANH} − V_{CANL})	V_{TxD} = V_{CC}; recessive; no load	−120	0	+50	mV
$I_{o(sc)}$ (CANH)		Short circuit output current at pin CANH	V_{CANH} = 0 V; V_{TxD} = 0 V	−45	−70	−120	mA
$I_{o(sc)}$ (CANL)		Short circuit output current at pin CANL	V_{CANL} = 36 V; V_{TxD} = 0 V	45	70	120	mA
$V_{i(dif)}$ (th)		Differential receiver threshold voltage (see Figure 8)	−5 V < V_{CANL} < +12 V; −5 V < V_{CANH} < +12 V;	0.5	0.7	0.9	V
$V_{ihcm(dif)}$ (th)		Differential receiver threshold voltage for high common−mode (see Figure 8))	−35 V < V_{CANL} < +35 V; −35 V < V_{CANH} < +35 V;	0.40	0.7	1.00	V
$V_{i(dif)}$ (hys)		Differential receiver input voltage hysteresis (see Figure 8)	−35 V < V_{CANL} < +35 V; −35 V < V_{CANH} < +35 V;	50	70	100	mV
$R_{i(cm)}$ (CANH)		Common−mode input resistance at pin CANH		15	26	37	kΩ
$R_{i(cm)}$ (CANL)		Common−mode input resistance at pin CANL		15	26	37	kΩ
$R_{i(cm)}$ (m)		Matching between pin CANH and pin CANL common mode input resistance	V_{CANH} = V_{CANL}	−3	0	+3	%
$R_{i(dif)}$		Differential input resistance		25	50	75	kΩ
$C_{i(CANH)}$	CANH CANL	Input capacitance at pin CANH	V_{TxD} = V_{CC}; (Note 15)		7.5	20	pF
$C_{i(CANL)}$		Input capacitance at pin CANL	V_{TxD} = V_{CC}; (Note 15)		7.5	20	pF
$C_{i(dif)}$		Differential input capacitance	V_{TxD} = V_{CC}; (Note 15)		3.75	10	pF
COMMON−MODE STABILIZATION							
V_{SPLIT}	VSPLIT	Reference output voltage at pin V_{SPLIT}	Normal mode; −500 μA < I_{SPLIT} < 500 μA	0.3 x V_{CC}	−	0.7 x V_{CC}	
$I_{SPLIT(i)}$		V_{SPLIT} leakage current	Stand−by mode	−5		+5	μA
$I_{SPLIT(lim)}$		V_{SPLIT} limitation current	Normal mode	−3		+3	mA
POWER ON RESET (POR)							
PORL		POR level	CANH, CANL, V_{ref} in tri−state below POR level	2.2	3.5	4.7	V

15. Characterization Data Only, not tested in production.

Table 9. AC PARAMETER CAN TRANSCEIVER

The AC parameters are given for V_{CC} and temperature in its operating range; T_J = −40 to +150°C; R_{LT} = 60 Ω unless otherwise specified

Symbol	Pin(s)	Parameter	Remark / Test Conditions	Min	Typ	Max	Unit
TIMING CHARACTERISTICS							
$t_{d(TxD-BUSon)}$		Delay TXD to bus active	C_l = 100 pF between CANH to CANL	40	85	105	ns
$t_{d(TxD-BUSoff)}$		Delay TXD to bus inactive	C_l = 100 pF between CANH to CANL	30	60	105	ns
$t_{d(BUSon-RXD)}$		Delay bus active to RXD	C_{rxd} = 15 pF	25	55	105	ns
$t_{d(BUSoff-RXD)}$		Delay bus inactive to RXD	C_{rxd} = 15 pF	40	100	105	ns
$t_{pd(rec-dom)}$		Propagation delay TXD to RXD from recessive to dominant	C_l = 100 pF between CANH to CANL	90		230	ns
$t_{d(dom-rec)}$		Propagation delay TXD to RXD from dominant to recessive	C_l = 100 pF between CANH to CANL	90		245	ns
$t_{d(stb-nm)}$		Delay standby mode to normal mode		5	7.5	10	μs
t_{dbus}		Dominant time for wake−up via bus		0.75	2.5	5	μs

16. Characterization Data Only, not tested in production

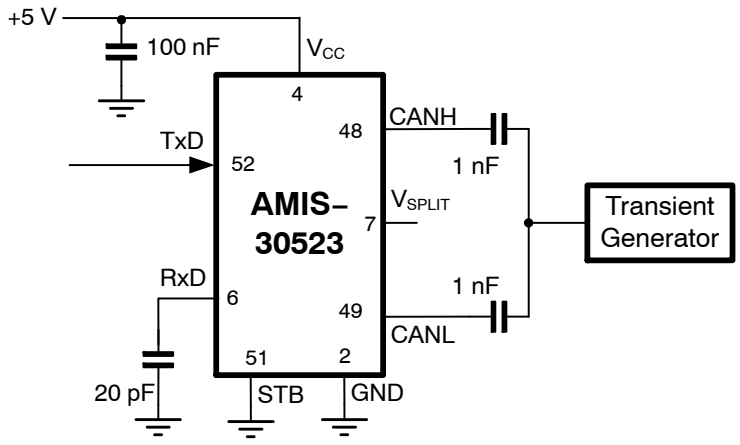


Figure 7. Test Circuit for Transients

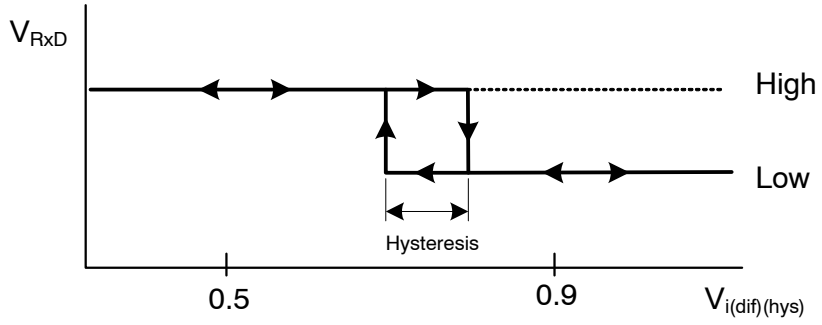


Figure 8. Hysteresis of the Receiver

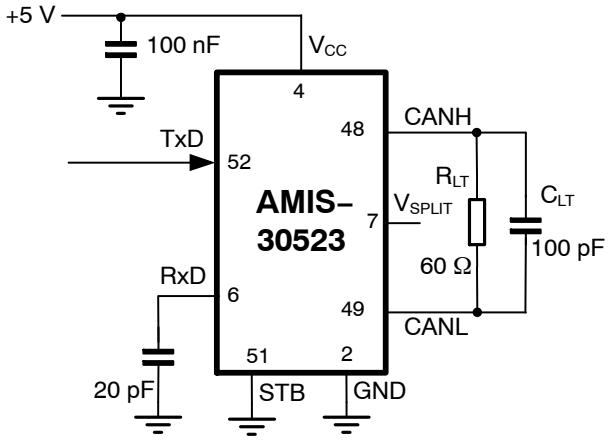


Figure 9. Test Circuit for Timing Characteristics

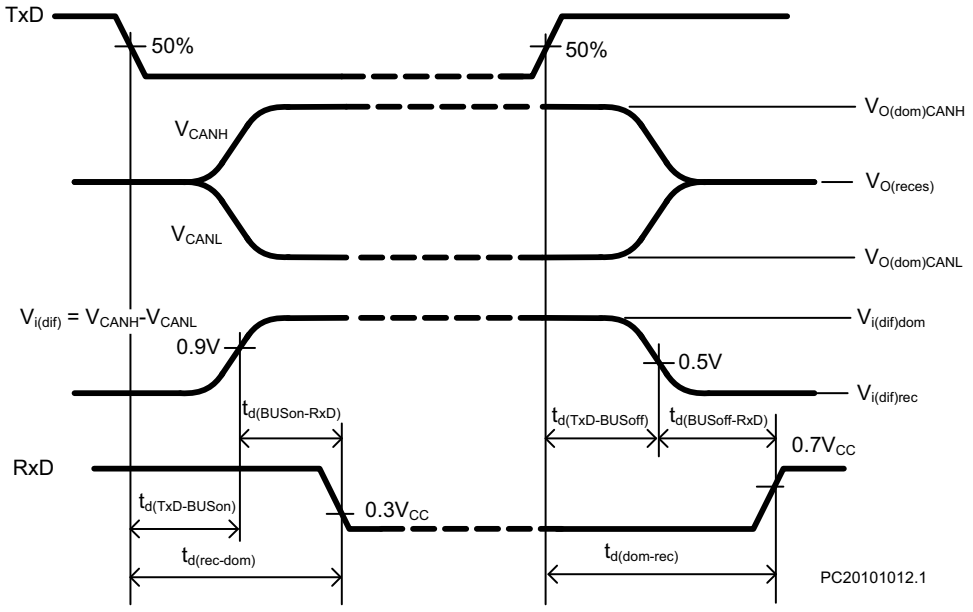


Figure 10. Timing Diagram for AC Characteristics

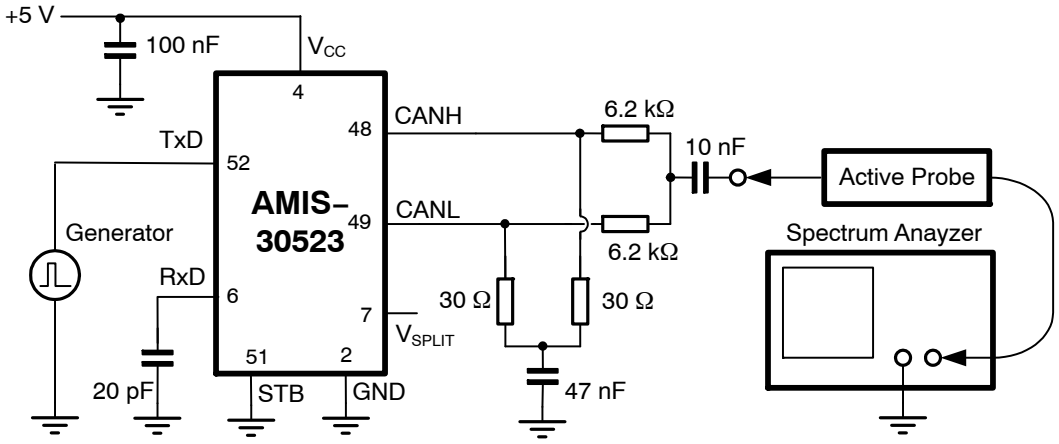


Figure 11. Basic Test Set−up for EME

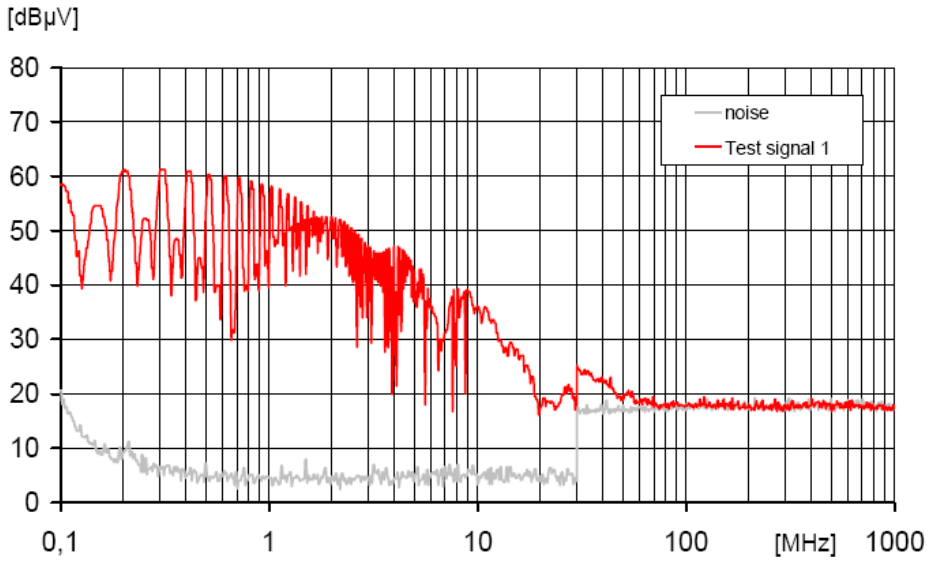


Figure 12. EME Measurements

TYPICAL APPLICATION SCHEMATIC

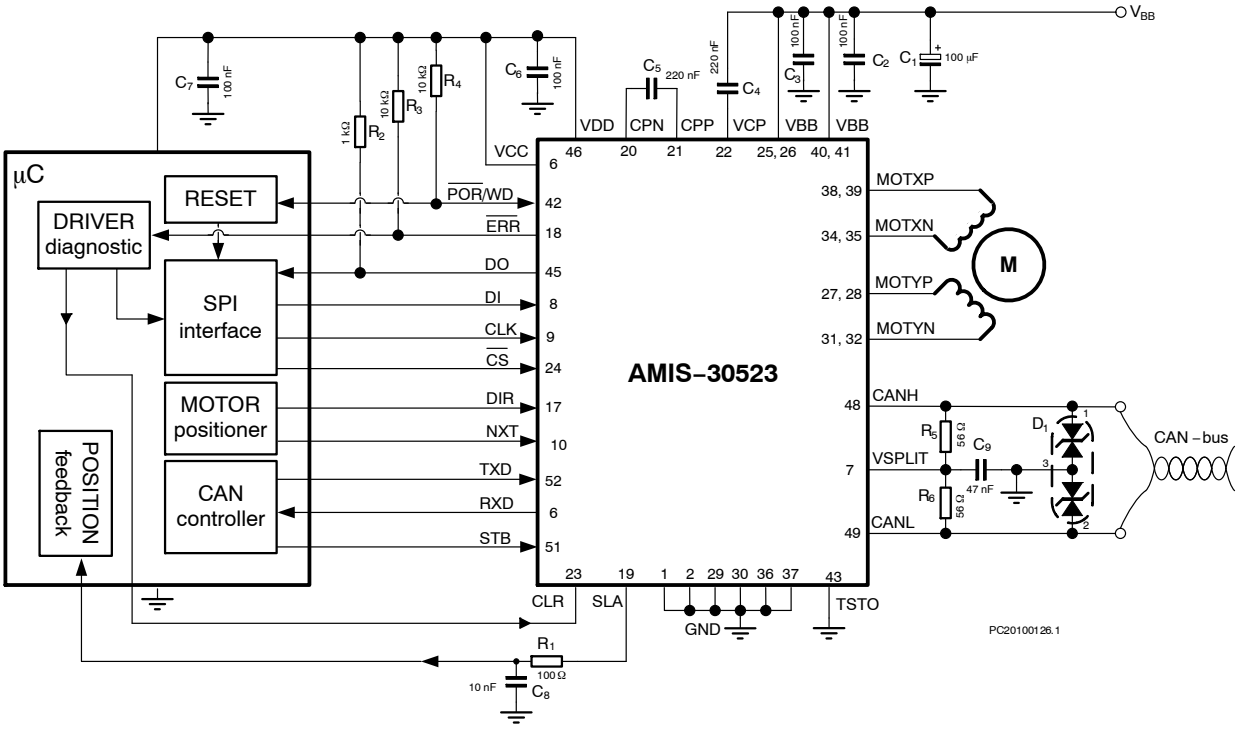


Figure 13. Typical Application Schematic AMIS−30523

Table 10. EXTERNAL COMPONENTS LIST AND DESCRIPTION

Component	Function	Typ Value	Tolerance	Unit
C_1	V_{BB} buffer capacitor (Note 17)	100	−20 +80%	μF
C_2, C_3	V_{BB} decoupling block capacitor	100	−20 +80%	nF
C_4	Charge−pump pumping capacitor	220	±20%	nF
C_5	Charge−pump buffer capacitor	220	±20%	nF
C_6, C_7	V_{DD} buffer capacitor	100	±20 %	nF
C_8	Low pass filter SLA	10	±20%	nF
C_9	VSPLIT decoupling capacitor	47	±20%	nF
R_1	Low pass filter SLA	100	±1%	Ω
R_2	Pull up resistor open drain DO output	1	±1%	kΩ
R_3, R_4	Pull up resistor open drain output	10	±1%	kΩ
R_5, R_6	CAN termination resistors	56	±1%	Ω
D_1	CAN protection diode	NUP2105		

17. Low ESR < 1 Ω.

FUNCTIONAL DESCRIPTION MOTOR DRIVER

Introduction

The AMIS−30523 is a micro−stepping stepper motor driver for bipolar stepper motors embedded with an integrated CAN transceiver.

The motor driver is connected through I/O pins and a SPI interface with an external microcontroller. It has an on−chip voltage regulator, reset−output and watchdog reset, able to supply peripheral devices. It contains a current−translation table and takes the next micro−step depending on the clock signal on the “NXT” input pin and the status of the “DIR” (=direction) register or input pin. A proprietary PWM algorithm is used for reliable current control. The motor driver provides a so−called “speed and load angle” output. This allows the creation of stall detection algorithms and control loops based on load−angle to adjust torque and speed.

H−Bridge Drivers

A full H−bridge is integrated for each of the two stator windings. Each H−bridge consists of two low−side and two high−side N−type MOSFET switches. Writing logic ‘0’ in bit <MOTEN> disables all drivers (high−impedance). Writing logic ‘1’ in this bit enables both bridges and current can flow in the motor stator windings.

In order to avoid large currents through the H−bridge switches, it is guaranteed that the top− and bottom−switches of the same half−bridge are never conductive simultaneously (interlock delay).

A two−stage protection against shorts on motor lines is implemented. In a first stage, the current in the driver is limited. Secondly, when excessive voltage is sensed across the transistor, the transistor is switched off.

In order to reduce the radiated/conducted emission, voltage slope control is implemented in the output switches. The output slope is defined by the gate−drain capacitance of output transistor and the (limited) current that drives the gate. There are two trimming bits for slope control (see Table 15 SPI Control Parameter Overview EMC[1:0]).

The power transistors are equipped with so−called “active diodes”: when a current is forced trough the transistor switch in the reverse direction, i.e. from source to drain, then the transistor is switched on. This ensures that most of the current flows through the channel of the transistor instead of through the inherent parasitic drain−bulk diode of the transistor.

Depending on the desired current range and the micro−step position at hand, the $R_{DS(on)}$ of the low−side transistors will be adapted such that excellent current−sense accuracy is maintained. The $R_{DS(on)}$ of the high−side transistors remain unchanged; see Table 5 DC Parameters Motor driver, for more details.

PWM Current Control

A PWM comparator compares continuously the actual winding current with the requested current and feeds back the information to a digital regulation loop. This loop then generates a PWM signal, which turns on/off the H−bridge switches. The switching points of the PWM duty−cycle are synchronized to the on−chip PWM clock. The frequency of the PWM controller can be doubled and an artificial jitter can be added (see Table 15 SPI Control Parameter Overview PWMJ). The PWM frequency will not vary with changes in the supply voltage. Also variations in motor−speed or load−conditions of the motor have no effect. There are no external components required to adjust the PWM frequency.

Automatic Forward and Slow−Fast Decay

The PWM generation is in steady−state using a combination of forward and slow−decay. The absence of fast−decay in this mode, guarantees the lowest possible current−ripple “by design”. For transients to lower current levels, fast−decay is automatically activated to allow high−speed response. The selection of fast or slow decay is completely transparent for the user and no additional parameters are required for operation.

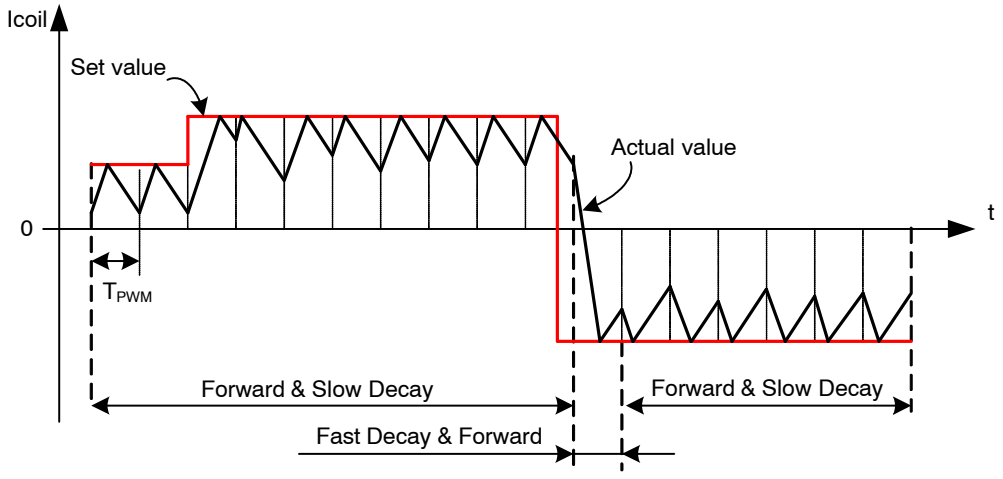


Figure 14. Forward and Slow/Fast Decay PWM

Automatic Duty Cycle Adaptation

In case the supply voltage is lower than 2 * Bemf, then the duty cycle of the PWM is adapted automatically to >50% to maintain the requested average current in the coils. This process is completely automatic and requires no additional parameters for operation. The over−all current−ripple is divided by two if PWM frequency is doubled (see Table 15 SPI Control Parameter Overview PWMF)

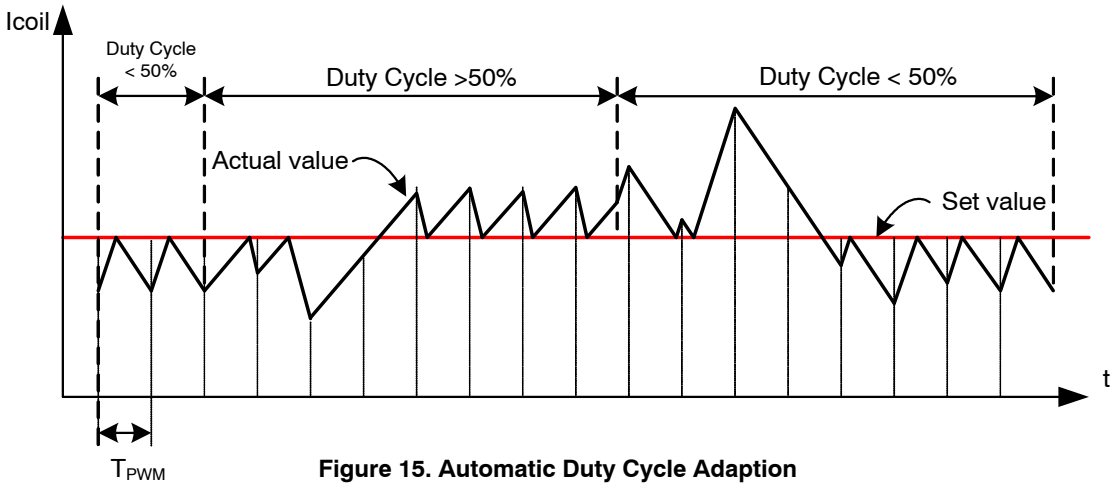


Figure 15. Automatic Duty Cycle Adaption

Step Translator and Step Mode

The step translator provides the control of the motor by means of SPI register Stepmode: SM[2:0], SPI register DIRCNTRL and input pins DIR and NXT. It is translating consecutive steps in corresponding currents in both motor coils for a given step mode.

One out of seven possible stepping modes can be selected through SPI−bits SM[2:0] (see Table 15 SPI Control Parameter Overview) After power−on or hard reset, the coil−current translator is set to the default 1/32 micro−stepping at position ‘0’. Upon changing the step mode, the translator jumps to position 0* of the corresponding stepping mode. When remaining in the same step mode, subsequent translator positions are all in the same column and increased or decreased with 1. Table 12 lists the output current vs. the translator position.

As shown in Figure 16 the output current−pairs can be projected approximately on a circle in the (I_x,I_y) plane. There are, however, two exceptions: uncompensated half step and full step. In these step modes the currents are not regulated to a fraction of I_{max} but are in all intermediate steps regulated at 100%. In the (I_x,I_y) plane the current−pairs are projected on a square. Table 11 lists the output current vs. the translator position for these cases.

Table 11. SQUARE TRANSLATOR TABLE FOR FULL STEP AND UNCOMPENSATED HALF STEP

	Stepmode (SM[2:0])		% of Imax	
	101	110		
MSP[6:0]	Uncompensated Half−Step	Full Step	Coil x	Coil y
000 0000	**0**	–	0	100
001 0000	1	1	100	100
010 0000	2	–	100	0
011 0000	3	2	100	−100
100 0000	4	–	0	−100
101 0000	5	3	−100	−100
110 0000	6	–	−100	0
111 0000	7	0	−100	100

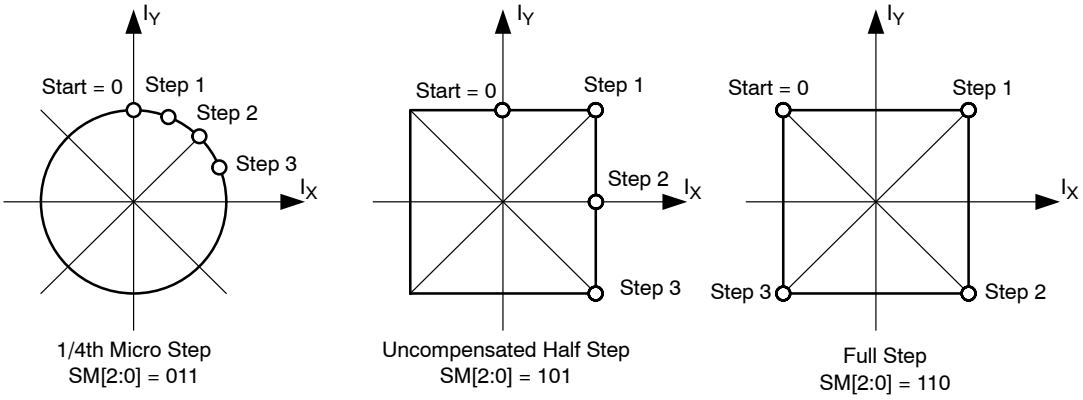


Figure 16. Translator Table: Circular and Square

Table 12. CIRCULAR TRANSLATOR TABLE

	Stepmode (SM[2:0])					% of I_{max}	
	000	001	010	011	100		
MSP[6:0]	1/32	1/16	1/8	1/4	1/2	Coil x	Coil y
000 0000	'0'	0*	0*	0*	0*	0	100
000 0001	1	–	–	–	–	3.5	98.8
000 0010	2	1	–	–	–	8.1	97.7
000 0011	3	–	–	–	–	12.7	96.5
000 0100	4	2	1	–	–	17.4	95.3
000 0101	5	–	–	–	–	22.1	94.1
000 0110	6	3	–	–	–	26.7	93
000 0111	7	–	–	–	–	31.4	91.8
000 1000	8	4	2	1	–	34.9	89.5
000 1001	9	–	–	–	–	38.3	87.2
000 1010	10	5	–	–	–	43	84.9
000 1011	11	–	–	–	–	46.5	82.6
000 1100	12	6	3	–	–	50	79
000 1101	13	–	–	–	–	54.6	75.5
000 1110	14	7	–	–	–	58.1	72.1
000 1111	15	–	–	–	–	61.6	68.6
001 0000	16	8	4	2	1	65.1	65.1
001 0001	17	–	–	–	–	68.6	61.6
001 0010	18	9	–	–	–	72.1	58.1
001 0011	19	–	–	–	–	75.5	54.6
001 0100	20	10	5	–	–	79	50
001 0101	21	–	–	–	–	82.6	46.5
001 0110	22	11	–	–	–	84.9	43
001 0111	23	–	–	–	–	87.2	38.3
001 1000	24	12	6	3	–	89.5	34.9
001 1001	25	–	–	–	–	91.8	31.4
001 1010	26	13	–	–	–	93	26.7
001 1011	27	–	–	–	–	94.1	22.1
001 1100	28	14	7	–	–	95.3	17.4
001 1101	29	–	–	–	–	96.5	12.7
001 1110	30	15	–	–	–	97.7	8.1
001 1111	31	–	–	–	–	98.8	3.5
010 0000	32	16	8	4	2	100	0
010 0001	33	–	–	–	–	98.8	−3.5
010 0010	34	17	–	–	–	97.7	−8.1
010 0011	35	–	–	–	–	96.5	−12.7
010 0100	36	18	9	–	–	95.3	−17.4
010 0101	37	–	–	–	–	94.1	−22.1
010 0110	38	19	–	–	–	93	−26.7
010 0111	39	–	–	–	–	91.8	−31.4
010 1000	40	20	10	5	–	89.5	−34.9
010 1001	41	–	–	–	–	87.2	−38.3
010 1010	42	21	–	–	–	84.9	−43
010 1011	43	–	–	–	–	82.6	−46.5
010 1100	44	22	11	–	–	79	−50
010 1101	45	–	–	–	–	75.5	−54.6
010 1110	46	23	–	–	–	72.1	−58.1
010 1111	47	–	–	–	–	68.6	−61.6
011 0000	48	24	12	6	3	65.1	−65.1
011 0001	49	–	–	–	–	61.6	−68.6
011 0010	50	25	–	–	–	58.1	−72.1
011 0011	51	–	–	–	–	54.6	−75.5
011 0100	52	26	13	–	–	50	−79
011 0101	53	–	–	–	–	46.5	−82.6
011 0110	54	27	–	–	–	43	−84.9
011 0111	55	–	–	–	–	38.3	−87.2
011 1000	56	28	14	7	–	34.9	−89.5
011 1001	57	–	–	–	–	31.4	−91.8
011 1010	58	29	–	–	–	26.7	−93
011 1011	59	–	–	–	–	22.1	−94.1
011 1100	60	30	15	–	–	17.4	−95.3
011 1101	61	–	–	–	–	12.7	−96.5
011 1110	62	31	–	–	–	8.1	−97.7
011 1111	63	–	–	–	–	3.5	−98.8

Table 12. CIRCULAR TRANSLATOR TABLE

	Stepmode (SM[2:0])					% of Imax	
	000	001	010	011	100		
MSP[6:0]	1/32	1/16	1/8	1/4	1/2	Coil x	Coil y
100 0000	64	32	16	8	4	0	−100
100 0001	65	–	–	–	–	−3.5	−98.8
100 0010	66	33	–	–	–	−8.1	−97.7
100 0011	67	–	–	–	–	−12.7	−96.5
100 0100	68	34	17	–	–	−17.4	−95.3
100 0101	69	–	–	–	–	−22.1	−94.1
100 0110	70	35	–	–	–	−26.7	−93
100 0111	71	–	–	–	–	−31.4	−91.8
100 1000	72	36	18	9	–	−34.9	−89.5
100 1001	73	–	–	–	–	−38.3	−87.2
100 1010	74	37	–	–	–	−43	−84.9
100 1011	75	–	–	–	–	−46.5	−82.6
100 1100	76	38	19	–	–	−50	−79
100 1101	77	–	–	–	–	−54.6	−75.5
100 1110	78	39	–	–	–	−58.1	−72.1
100 1111	79	–	–	–	–	−61.6	−68.6
101 0000	80	40	20	10	5	−65.1	−65.1
101 0001	81	–	–	–	–	−68.6	−61.6
101 0010	82	41	–	–	–	−72.1	−58.1
101 0011	83	–	–	–	–	−75.5	−54.6
101 0100	84	42	21	–	–	−79	−50
101 0101	85	–	–	–	–	−82.6	−46.5
101 0110	86	43	–	–	–	−84.9	−43
101 0111	87	–	–	–	–	−87.2	−38.3
101 1000	88	44	22	11	–	−89.5	−34.9
101 1001	89	–	–	–	–	−91.8	−31.4
101 1010	90	45	–	–	–	−93	−26.7
101 1011	91	–	–	–	–	−94.1	−22.1
101 1100	92	46	23	–	–	−95.3	−17.4
101 1101	93	–	–	–	–	−96.5	−12.7
101 1110	94	47	–	–	–	−97.7	−8.1
101 1111	95	–	–	–	–	−98.8	−3.5
110 0000	96	48	24	12	6	−100	0
110 0001	97	–	–	–	–	−98.8	3.5
110 0010	98	49	–	–	–	−97.7	8.1
110 0011	99	–	–	–	–	−96.5	12.7
110 0100	100	50	25	–	–	−95.3	17.4
110 0101	101	–	–	–	–	−94.1	22.1
110 0110	102	51	–	–	–	−93	26.7
110 0111	103	–	–	–	–	−91.8	31.4
110 1000	104	52	26	13	–	−89.5	34.9
110 1001	105	–	–	–	–	−87.2	38.3
110 1010	106	53	–	–	–	−84.9	43
110 1011	107	–	–	–	–	−82.6	46.5
110 1100	108	54	27	–	–	−79	50
110 1101	109	–	–	–	–	−75.5	54.6
110 1110	110	55	–	–	–	−72.1	58.1
110 1111	111	–	–	–	–	−68.6	61.6
111 0000	112	56	28	14	7	−65.1	65.1
111 0001	113	–	–	–	–	−61.6	68.6
111 0010	114	57	–	–	–	−58.1	72.1
111 0011	115	–	–	–	–	−54.6	75.5
111 0100	116	58	29	–	–	−50	79
111 0101	117	–	–	–	–	−46.5	82.6
111 0110	118	59	–	–	–	−43	84.9
111 0111	119	–	–	–	–	−38.3	87.2
111 1000	120	60	30	15	–	−34.9	89.5
111 1001	121	–	–	–	–	−31.4	91.8
111 1010	122	61	–	–	–	−26.7	93
111 1011	123	–	–	–	–	−22.1	94.1
111 1100	124	62	31	–	–	−17.4	95.3
111 1101	125	–	–	–	–	−12.7	96.5
111 1110	126	63	–	–	–	−8.1	97.7
111 1111	127	–	–	–	–	−3.5	98.8

Direction

The direction of rotation is selected by means of following combination of the DIR input pin and the SPI−controlled direction bit <DIRCTRL>. (see Table 15 SPI Control Parameter Overview)

NXT input

Changes on the NXT input will move the motor current one step up/down in the translator table (even when the motor is disabled). Depending on the NXT−polarity bit <NXTP> (see Table 15 SPI Control Parameter Overview), the next step is initiated either on the rising edge or the falling edge of the NXT input.

Translator Position

The translator position MSP[6:0] can be read in SPI Status Register 3 (See Table 18 SPI Status Registers). This is a 7−bit number equivalent to the 1/32th micro−step from Table 12 “Circular Translator Table”. The translator position is updated immediately following a NXT trigger.

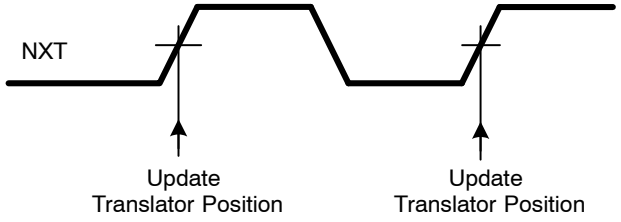


Figure 17. Translator Position Timing Diagram

Synchronization of Step Mode and NXT Input

When step mode is re−programmed to another resolution (Figure 18), then this is put in effect immediately upon the first arriving “NXT” input. If the micro−stepping resolution is increased, the coil currents will be regulated to the nearest micro−step, according to the fixed grid of the increased resolution. If however the micro−stepping resolution is decreased, then it is possible to introduce an offset (or phase shift) in the micro−step translator table.

If the step resolution is decreased at a translator table position that is shared both by the old and new resolution setting, then the offset is zero and micro−stepping is proceeds according to the translator table.

If the translator position is **not** shared both by the old and new resolution setting, then the micro−stepping proceeds with an offset relative to the translator table (See Figure 18 right hand side).

More information can be found in application note AND8399/D.

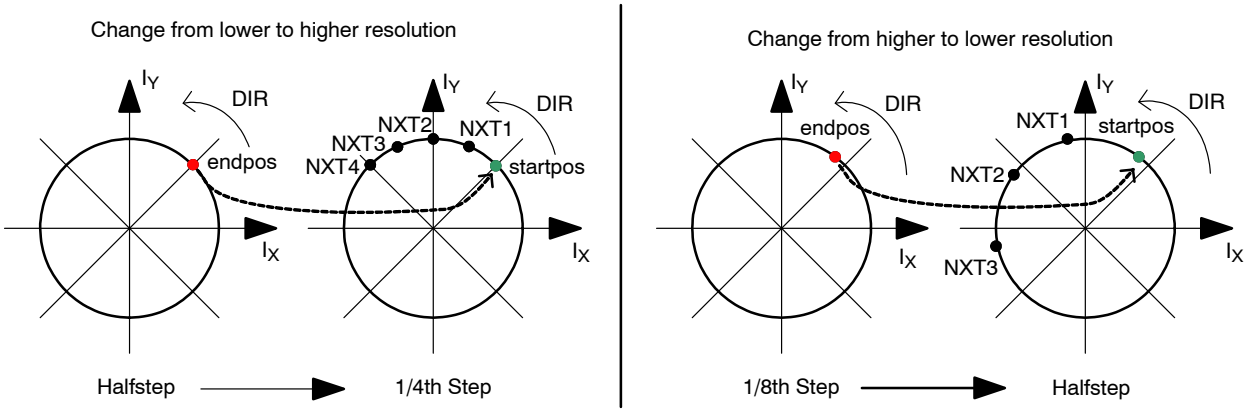


Figure 18. NXT−Step−Mode Synchronization

Left: change from lower to higher resolution. The left−hand side depicts the ending half−step position during which a new step mode resolution was programmed. The right−hand side diagram shows the effect of subsequent NXT commands on the micro−step position.

Right: change from higher to lower resolution. The left−hand side depicts the ending micro−step position during which a new step mode resolution was programmed. The right−hand side diagram shows the effect of subsequent NXT commands on the half−step position.

NOTE: It is advised to reduce the micro−stepping resolution only at micro−step positions that overlap with desired micro−step positions of the new resolution.

Programmable Peak−Current

The amplitude of the current waveform in the motor coils (coil peak current = I_{max}) is adjusted by means of an SPI parameter “CUR[4:0]” (see Table 15 SPI Control Parameter Overview). Whenever this parameter is changed, the coil−currents will be updated immediately at the next PWM period. Figure 19 presents the Peak−Current and Current Ratings in conjunction to the Current setting CUR[4:0].

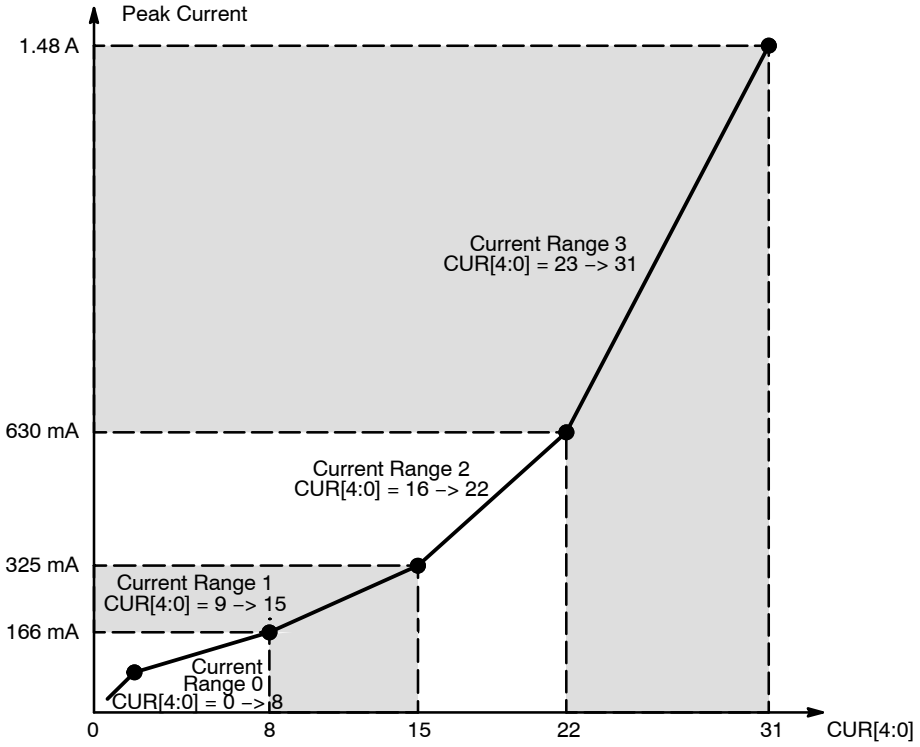


Figure 19. Programmable Peak−Current Overview

Speed and Load Angle Output

The SLA−pin provides an output voltage that indicates the level of the Back−e.m.f. voltage of the motor. This Back−e.m.f. voltage is sampled during every so−called ”coil current zero crossings”. Per coil, two zero−current positions exist per electrical period, yielding in total four zero−current observation points per electrical period.

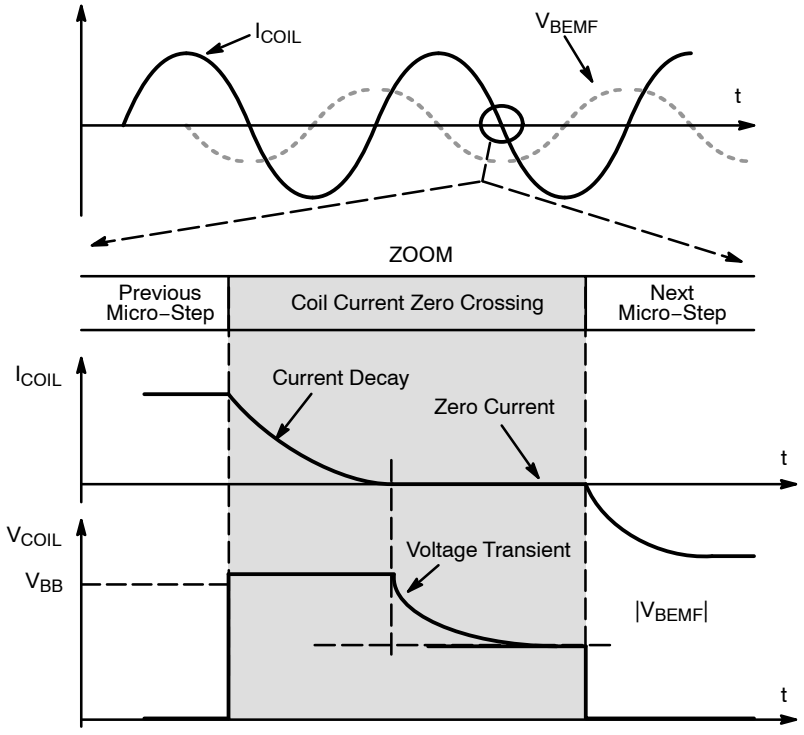


Figure 20. Principle of Bemf Measurement

Because of the relatively high recirculation currents in the coil during current decay, the coil voltage V_{COIL} shows a transient behavior. As this transient is not always desired in application software, two operating modes can be selected by means of the bit <SLAT> (see “SLA−transparency” in Table 15 SPI Control Parameter Overview). The SLA pin shows in “transparent mode” full visibility of the voltage transient behavior. This allows a sanity−check of the speed−setting versus motor operation and characteristics and supply voltage levels. If the bit “SLAT” is cleared, then only the voltage samples at the end of each coil current zero crossing are visible on the SLA−pin. Because the transient behavior of the coil voltage is not visible anymore, this mode generates smoother Back e.m.f. input for post−processing, e.g. by software.

In order to bring the sampled Back e.m.f. to a descent output level (0 to 5 V), the sampled coil voltage V_{COIL} is divided by 2 or by 4. This divider is set through an SPI bit <SLAG> (see Table 15 SPI Control Parameter Overview).

The following drawing illustrates the operation of the SLA−pin and the transparency−bit. “PWMsh” and “$I_{coil} = 0$” are internal signals that define together with SLAT the sampling and hold moments of the coil voltage.

More information can be found in application note AND8399/D.

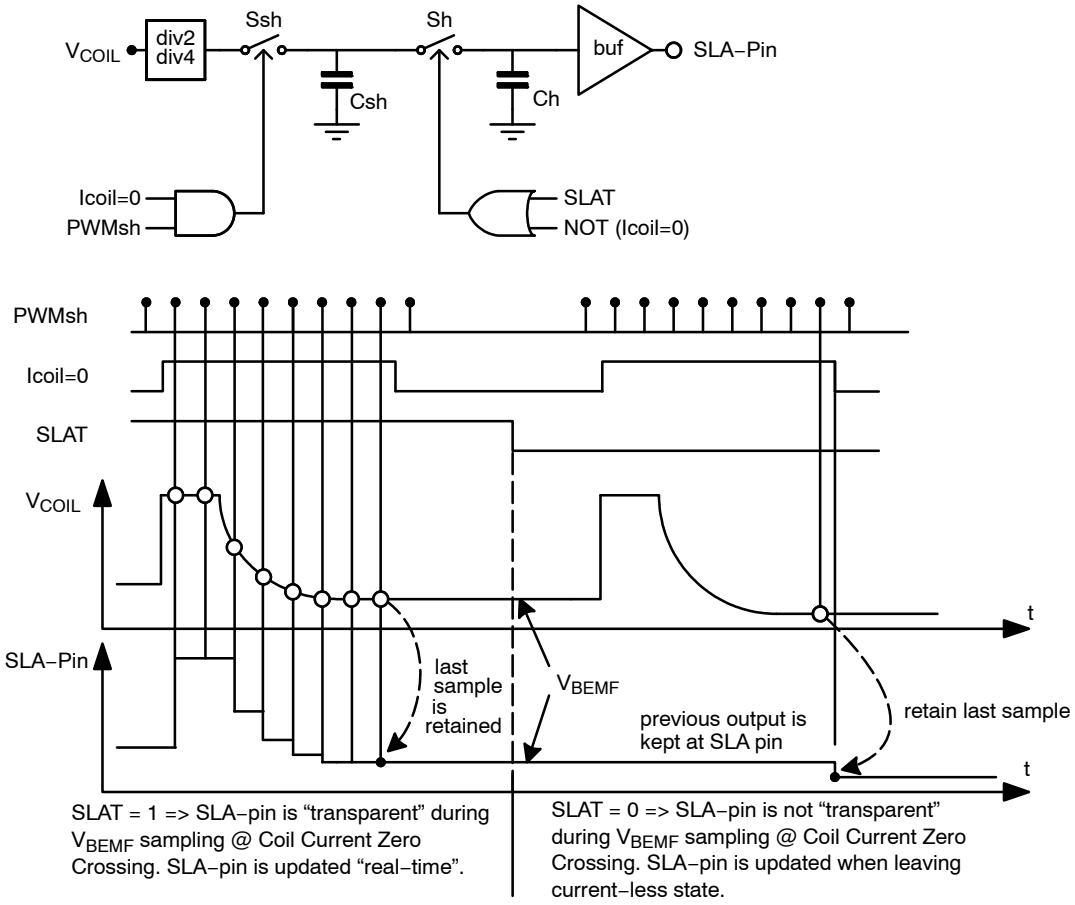


Figure 21. Timing Diagram of SLA−Pin

Warning, Error Detection and Diagnostics Feedback

Thermal Warning and Shutdown

When junction temperature rises above T_{TW}, the thermal warning bit <TW> is set (Table 17 SPI Status registers Address SR0). If junction temperature increases above thermal shutdown level, then the circuit goes in “Thermal Shutdown” mode (<TSD>) and all driver transistors are disabled (high impedance) (see Table 17 SPI Status registers Address SR2). The conditions to reset flag <TSD> is to be at a temperature lower than T_{TW} and to clear the <TSD> flag reading out Status Register 2.

Over−Current Detection

The over−current detection circuit monitors the load current in each activated output stage. If the load current exceeds the over−current detection threshold, then the over−current flag is set and the drivers are switched off to reduce the power dissipation and to protect the integrated circuit. Each driver transistor has an individual detection bit in (see Table 17 SPI Status registers Address SR1 and SR2: <OVCXij> and <OVCYij>). Error condition is latched and the microcontroller needs to clear the status bits (by reading Status Register 1 or 2) to reactivate the drivers.

Note: Successive reading the SPI StatusRegisters 1 and 2 in case of a short circuit condition, may lead to damage to the drivers

Open Coil/Current Not Reached Detection

Open coil detection is based on the observation of 100% duty cycle of the PWM regulator. If in a coil 100% duty cycle is detected for longer than 200 ms then the related driver transistors are disabled (high−impedance) and an appropriate bit in the SPI status register is set (<OPENX> or <OPENY>). (Table 17 SPI Status Register Address SR0)

When the resistance of a motor coil is very large and the supply voltage is low, it can happen that the motor driver is not able to deliver the requested current to the motor. Under these conditions the PWM controller duty cycle will be 100% and after 200 ms the error pin and <OPENX>, <OPENY> will flag this situation (motor current is kept alive). This feature can be used to test if the operating conditions (supply voltage, motor coil resistance) still allow reaching the requested coil−current or else the coil current should be reduced.

Charge Pump Failure

The charge pump is an important circuit that guarantees low $R_{DS(on)}$ for all drivers, especially for low supply voltages. If supply voltage is too low or external components are not properly connected to guarantee $R_{DS(on)}$ of the drivers, then the bit <CPFAIL> is set in Table 17. Also after POR the charge pump voltage will need some time to exceed the required threshold. During that time t_{CPU} <CPFAIL> will be set to “1”.

Error Output

This is a digital output to flag a problem to the external microcontroller. The signal on this output is active low and the logic combination of:

NOT(ERRB) = <TW> OR <TSD> OR <OVCXij> OR < OVCYij> OR <OPENi> OR <CPFAIL>

This open drain output can be wired OR−ed with error outputs other motor drivers.

Logic Supply Regulator

AMIS−30523 has an on−chip 5 V low−drop regulator with external capacitor to supply the digital part of the chip, some low−voltage analog blocks and external circuitry. The voltage level is derived from an internal bandgap reference. To calculate the available drive−current for external circuitry, the specified I_{load} should be reduced with the consumption of internal circuitry (unloaded outputs) and the loads connected to logic outputs. See Table 5 DC parameters Motor Driver.

Power−On Reset (POR) Function

The open drain output pin PORB/WD provides an “active low” reset for external purposes. At power−up of AMIS−30523, this pin will be kept low for some time to reset for example an external microcontroller. A small analogue filter avoids resetting due to spikes or noise on the V_{DD} supply.

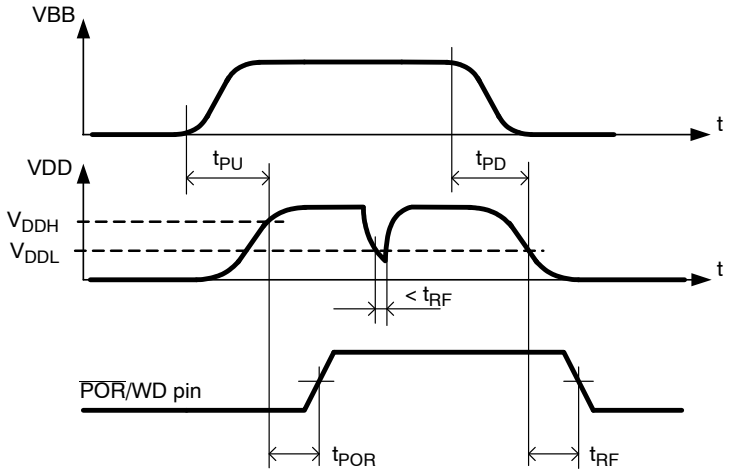


Figure 22. Power−on−Reset Timing Diagram

Watchdog Function

The watchdog function is enabled/disabled through <WDEN> bit (See Table 15 SPI Control Registers address 00h). Once this bit has been set to “1” (watchdog enable), the microcontroller needs to re−write this bit to clear an internal timer before the watchdog timeout interval expires. In case the timer is activated and WDEN is acknowledged too early (before t_{WDPR}) or not within the interval (after t_{WDTO}), then a reset of the microcontroller will occur through PORB/WD pin. In addition, a warm/cold boot bit <WD> is available in Table 17 for further processing when the external microcontroller is alive again. See Figure 23.

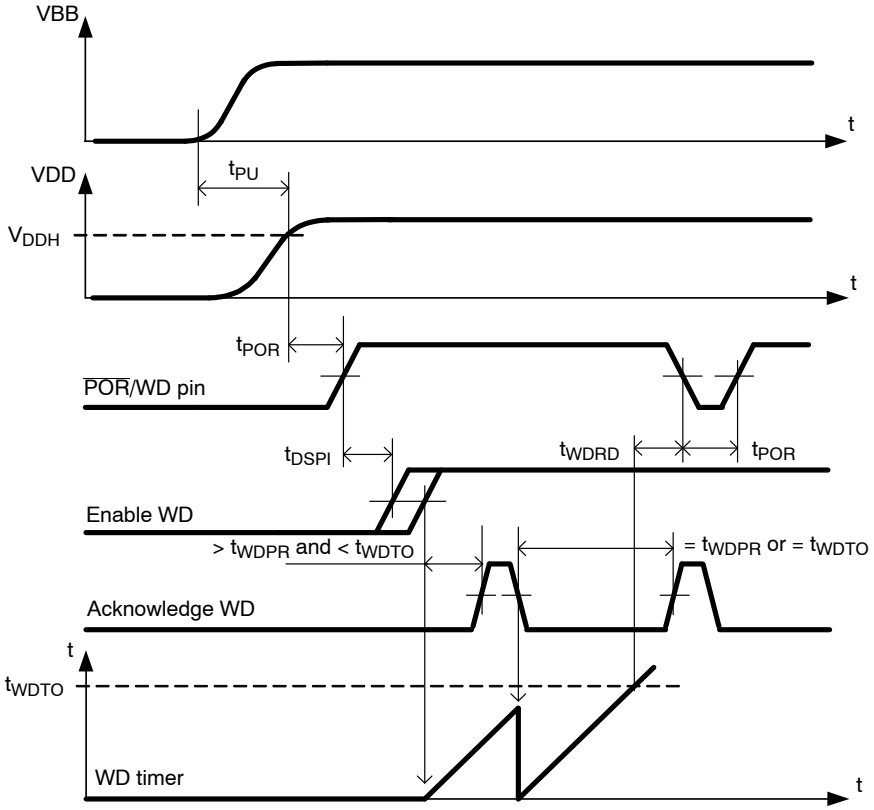


Figure 23. Watchdog Timing Diagram

NOTE: t_{DSPI} is the time needed by the external microcontroller to shift−in the <WDEN> bit after a power−up.

The duration of the watchdog timeout interval is programmable through the WDT[3:0] bits (See Table 14 SPI Control Registers address 00h). The timing is given in Table 13 below.

Table 13. WATCHDOG TIMEOUT INTERVAL AS FUNCTION OF WDT[3.0]

Index	WDT[3:0]				t_{WDTO} (ms)
0	0	0	0	0	32
1	0	0	0	1	64
2	0	0	1	0	96
3	0	0	1	1	128
4	0	1	0	0	160
5	0	1	0	1	192
6	0	1	1	0	224
7	0	1	1	1	256
8	1	0	0	0	288
9	1	0	0	1	320
A	1	0	1	0	352
B	1	0	1	1	384
C	1	1	0	0	416
D	1	1	0	1	448
E	1	1	1	0	480
F	1	1	1	1	512

CLR Pin (= Hard Reset)

Logic 0 on CLR pin allows normal operation of the chip. To reset the complete digital inside AMIS−30523, the input CLR needs to be pulled to logic 1 during minimum time given by t_{CLR}. (See Table 6 AC Parameters Motor Driver). This reset function clears all internal registers without the need of a power−cycle, except in sleep mode. The operation of all analog circuits is depending on the reset state of the digital, charge pump remains active. Logic 0 on CLR pin resumes normal operation again.

The voltage regulator remains functional during and after the reset and the PORB/WD pin is not activated. Watchdog function is reset completely.

Sleep Mode

The bit <SLP> in SPI Control Register 2 (See Table 14 SPI Control Registers address 03h) is provided to enter a so−called “sleep mode”. This mode allows reduction of current−consumption when the motor is not in operation. The effect of sleep mode is as follows:

- The drivers are put in HiZ
- All analog circuits are disabled and in low−power mode
- All internal registers are maintaining their logic content
- NXT and DIR inputs are forbidden
- SPI communication remains possible (slight current increase during SPI communication)
- Oscillator and digital clocks are silent, except during SPI communication

The voltage regulator remains active but with reduced current−output capability ($I_{LOADSLP}$). The watchdog timer stops running and it’s value is kept in the counter. Upon leaving sleep mode, this timer continues from the value it had before entering sleep mode.

Normal operation is resumed after writing logic ‘0’ to bit <SLP>. A start−up time is needed for the charge pump to stabilize. After this time, (tcpu) NXT commands can be issued.

SPI INTERFACE

The serial peripheral interface (SPI) allows an external microcontroller (Master) to communicate with AMIS−30523. The implemented SPI block is designed to interface directly with numerous micro−controllers from several manufacturers. AMIS−30523 acts always as a Slave and can't initiate any transmission. The operation of the device is configured and controlled by means of SPI registers which are observable for read and/or write from the Master.

SPI Transfer Format and Pin Signals

During a SPI transfer, data is simultaneously transmitted (shifted out serially) and received (shifted in serially). A serial clock line (CLK) synchronizes shifting and sampling of the information on the two serial data lines (DO and DI). DO signal is the output from the Slave (AMIS−30523), and DI signal is the output from the Master. A chip select line (CSB) allows individual selection of a Slave SPI device in a multiple−slave system. The CSB line is active low. If AMIS−30523 is not selected, DO is pulled up with the external pull up resistor. Since AMIS−30523 operates as a Slave in MODE 0 (CPOL = 0; CPHA = 0) it always clocks data out on the falling edge and samples data in on rising edge of clock. The Master SPI port must be configured in MODE 0 too, to match this operation. The SPI clock idles low between the transferred bytes.

The diagram below is both a Master and a Slave timing diagram since CLK, DO and DI pins are directly connected between the Master and the Slave.

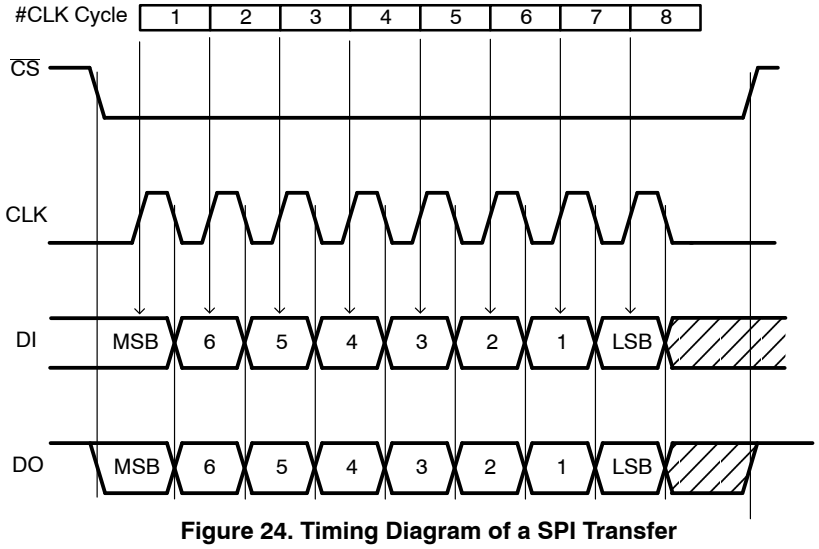


Figure 24. Timing Diagram of a SPI Transfer

NOTE: At the falling edge of the eighth clock pulse the data−out shift register is updated with the content of the addressed internal SPI register. The internal SPI registers are updated at the first rising edge of the AMIS−30523 system clock when $\overline{CS}$ = High.

Transfer Packet:

Serial data transfer is assumed to follow MSB first rule. The transfer packet contains one or more bytes.

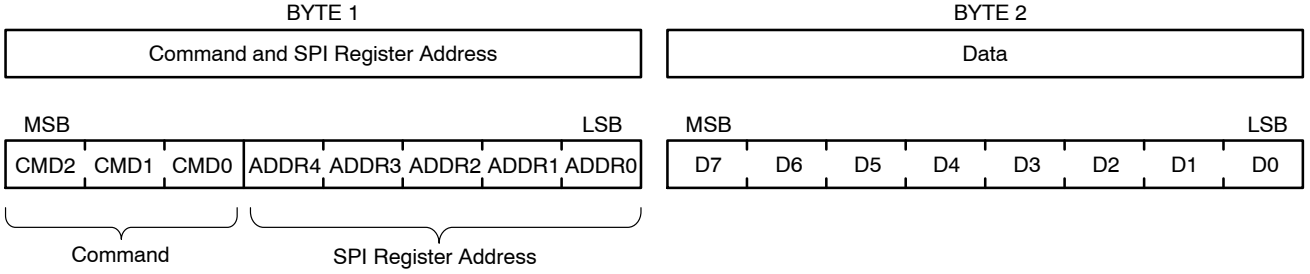


Figure 25. SPI Transfer Packet

Byte 1 contains the Command and the SPI Register Address and indicates to AMIS−30523 the chosen type of operation and addressed register. Byte 2 contains data, or sent from the Master in a WRITE operation, or received from AMIS−30523 in a READ operation.

Two command types can be distinguished in the communication between master and AMIS−30523:

- READ **from** SPI Register with address ADDR[4:0]: **CMD2** = "0"

- WRITE **to** SPI Register with address ADDR[4:0]: **CMD2** = “1”

READ Operation

If the Master wants to read data from Status or Control Registers, it initiates the communication by sending a READ command. This READ command contains the address of the SPI register to be read out. At the falling edge of the eight clock pulse the data−out shift register is updated with the content of the corresponding internal SPI register. In the next 8−bit clock pulse train this data is shifted out via DO pin. At the same time the data shifted in from DI (Master) should be interpreted as the following successive command or dummy data.

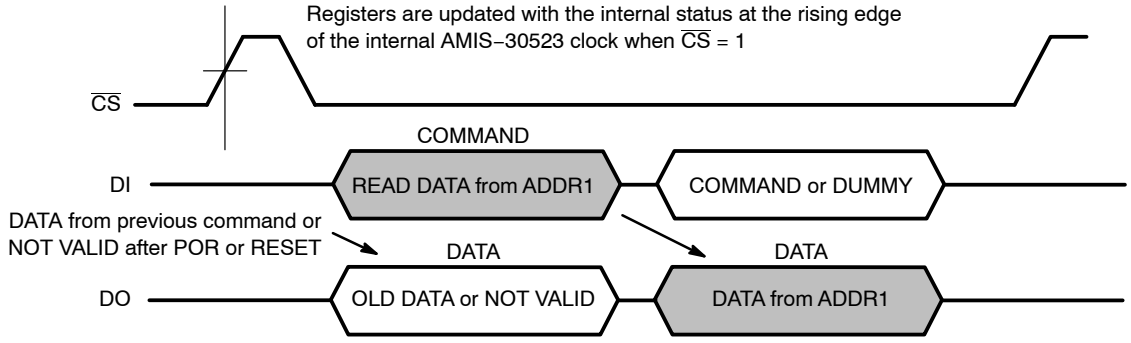


Figure 26. Single READ Operation where DATA from SPI Register with Address 1 is Read by the Master

All 4 Status Registers (see Table 17 SPI Registers) contain 7 data bits and a parity check bit The most significant bit (D7) represents a parity of D[6:0]. If the number of logical ones in D[6:0] is odd, the parity bit D7 equals “1”. If the number of logical ones in D[6:0] is even then the parity bit D7 equals “0”. This simple mechanism protects against noise and increases the consistency of the transmitted data. If a parity check error occurs it is recommended to initiate an additional READ command to obtain the status again.

Also the Control Registers can be read out following the same routine. Control Registers don’t have a parity check.

The CSB line is active low and may remain low between successive READ commands as illustrated in Figure 28. There is however one exception. In case an error condition is latched in one of Status Registers (see Table 17 SPI Registers) the ERRB pin is activated. (See the Error Output section). This signal flags a problem to the external microcontroller. By reading the Status Registers information about the root cause of the problem can be determined. After this READ operation the Status Registers are cleared. Because the Status Registers and ERRB pin (see SPI Registers) are only updated by the internal system clock when the CSB line is high, the Master should force CSB high immediately after the READ operation. For the same reason it is recommended to keep the CSB line high always when the SPI bus is idle.

WRITE Operation

If the Master wants to write data to a Control Register it initiates the communication by sending a WRITE command. This contains the address of the SPI register to write to. The command is followed with a data byte. This incoming data will be stored in the corresponding Control Register after CSB goes from low to high! AMIS−30523 responds on every incoming byte by shifting out via DO the data stored in the last received address.

It is important that the writing action (command – address and data) to the Control Register is exactly 16 bits long. If more or less bits are transmitted the complete transfer packet is ignored (with the exception of preceding read commands (see Figure 28)).

A WRITE command executed for a read−only register (e.g. Status Registers) will not affect the addressed register and the device operation.

Because after a power−on−reset the initial address is unknown the data shifted out via DO is not valid.

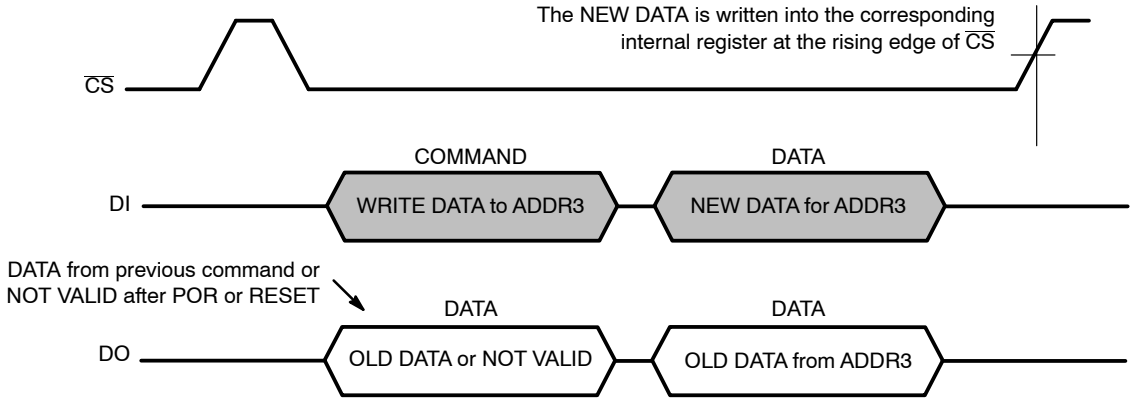


Figure 27. Single WRITE Operation where DATA from the Master is Written in SPI Register with Address 3

Examples of Combined READ and WRITE Operations

In the following examples successive READ and WRITE operations are combined. In Figure 28 the Master first reads the status from Register at ADDR4 and at ADDR5 followed by writing a control byte in Control Register at ADDR2. Note that during the write command the old data of the pointed register is returned at the moment the new data is shifted in

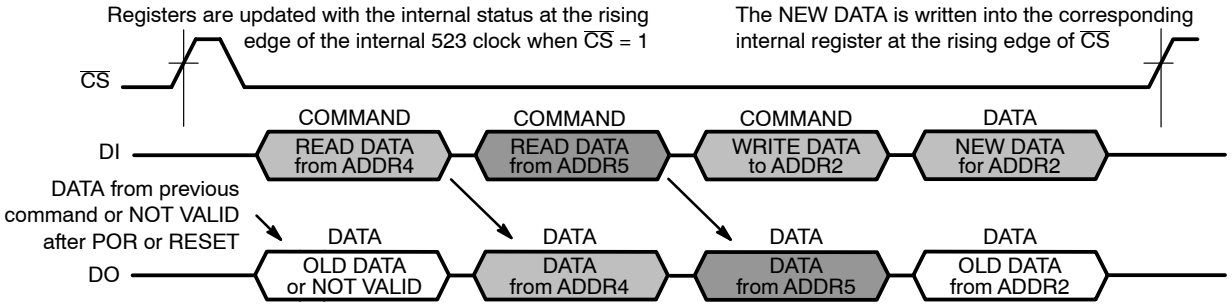


Figure 28. Two Successive READ Commands Followed by a WRITE Command

After the write operation the Master could initiate a read back command in order to verify the data correctly written as illustrated in Figure 29. During reception of the READ command the old data is returned for a second time. Only after receiving the READ command the new data is transmitted. This rule also applies when the master device wants to initiate an SPI transfer to read the Status Registers. Because the internal system clock updates the Status Registers only when CSB line is high, the first read out byte might represent old status information.

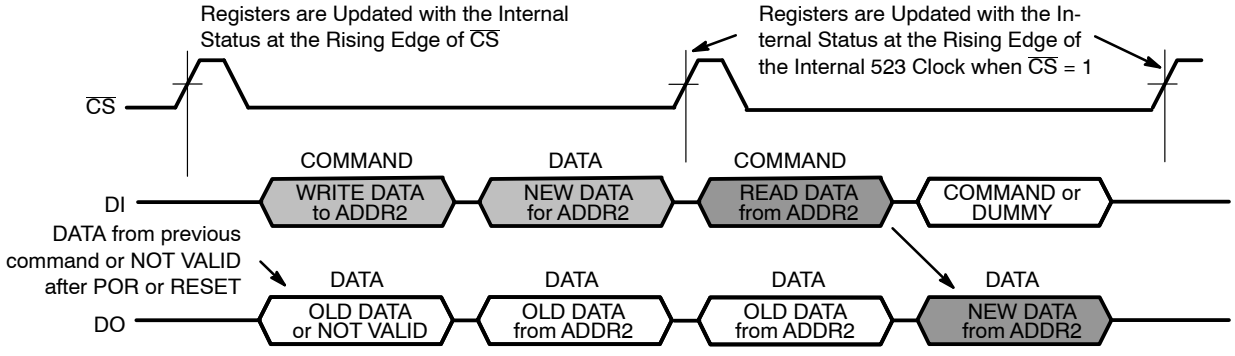


Figure 29. A WRITE Operation where DATA from the Master is Written in SPI Register with Address 2 Followed by a READ Back Operation to Verify a Correct WRITE Operation

NOTE: The internal data−out shift buffer of the AMIS−30523 is updated with the content of the selected SPI register only at the last (every eighth) falling edge of the CLK signal (see SPI Transfer Format and Pin Signals). As a result, new data for transmission cannot be written to the shift buffer at the beginning of the transfer packet and the first byte shifted out might represent old data.

Table 14. SPI CONTROL REGISTERS (All SPI control registers have Read/Write Access and default to ”0” after power−on or hard reset.)

		Structure							
	Content	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
	Access	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Address	Reset	0	0	0	0	0	0	0	0
WR (00h)	Data	WDEN	WDT[3:0]				–	–	–
CR0 (01h)	Data	SM[2:0]			CUR[4:0]				
CR1 (02h)	Data	DIRCTRL	NXTP	–	–	PWMF	PWMJ	EMC[1:0]	
CR2 (03h)	Data	MOTEN	SLP	SLAG	SLAT	–	–	–	–

Where:
R/W Read and Write access
Reset: Status after power−On or hard reset

Table 15. SPI CONTROL PARAMETER OVERVIEW

Symbol	Description	Status		Value
DIRCTRL	Controls the direction of rotation (in combination with logic level on input DIR)	<DIR> = 0	<DIRCTRL> = 0	CW motion
			<DIRCTRL> = 1	CCW motion
		<DIR> = 1	<DIRCTRL> = 0	CCW motion
			<DIRCTRL> = 1	CW motion
NXTP	Selects if NXT triggers on rising or falling edge	<NXTP> = 0	Trigger on rising edge	
		<NXTP> = 1	Trigger on falling edge	
EMC[1:0]	Turn On − Turn−off Slopes of motor driver (Note 18)	00	Very Fast	
		01	Fast	
		10	Slow	
		11	Very Slow	
SLAT	Speed load angle transparency bit	<SLAT> = 0	SLA is transparent	
		<SLAT> = 1	SLA is NOT transparent	
SLAG	Speed load angle gain setting	<SLAG> = 0	Gain = 0.5	
		<SLAG> = 1	Gain = 0.25	
PWMF	Enables doubling of the PWM frequency (Note 18)	<PWMF> = 0	Default Frequency	
		<PWMF> = 1	Double Frequency	
PWMJ	Enables jittery PWM	<PWMJ> = 0	Jitter disabled	
		<PWMJ> = 1	Jitter enabled	
SM[2:0]	Stepmode	000	1/32 Micro − Step	
		001	1/16 Micro − Step	
		010	1/8 Micro − Step	
		011	1/4 Micro − Step	
		100	Compensated Half Step	
		101	Uncompensated Half Step	
		110	Full Step	
		111	n.a.	
SLP	Enables sleep mode	<SLP> = 0	Active mode	
		<SLP> = 1	Sleep mode	
MOTEN	Activates the motor driver outputs	<MOTEN> = 0	Drivers disabled	
		<MOTEN> = 1	Drivers enabled	

18. The typical values can be found in Table 5: DC Parameters Motor Driver and in Table 6: AC parameters Motor Driver

CUR[4:0] Selects IMCmax peak. This is the peak or amplitude of the regulated current waveform in the motor coils.

Table 16. SPI CONTROL PARAMETER OVERVIEW CUR[4:0]

Current Range (Note 20)	Index CUR[4:0]	Current (mA) (Note 19)	Current Range (Note 20)	Index CUR[4:0]	Current (mA) (Note 19)
0	0 00000	33	2	16 10000	365
	1 00001	64		17 10001	400
	2 00010	95		18 10010	440
	3 00011	104		19 10011	485
	4 00100	115		20 10100	530
	5 00101	126		21 10101	585
	6 00110	138		22 10110	630
	7 00111	153	3	23 10111	750
	8 01000	166		24 11000	825
1	9 01001	190		25 11001	895
	10 01010	205		26 11010	975
	11 01011	230		27 11011	1065
	12 01100	250		28 11100	1155
	13 01101	275		29 11101	1245
	14 01110	300		30 11110	1365
	15 01111	325		31 11111	1480

19. Typical current amplitude at T_J = 125°C
20. Reducing the current over different current ranges might trigger overcurrent detection. See application note AND8372/D for solutions.

SPI Status Register Description

All 4 SPI status registers have Read Access and are default to “0” after power−on or hard reset.

Table 17. SPI STATUS REGISTERS

		Structure							
	Content	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
	Access	R	R	R	R	R	R	R	R
Address	Reset	0	0	0	0	0	0	0	0
SR0 (04h)	Data is not latched	PAR	TW	CPfail	WD	OPENX	OPENY	–	–
SR1 (05h)	Data is latched	PAR	OVCXPT	OVCXPB	OVCXNT	OVCXNB	–	–	–
SR2 (06h)	Data is latched	PAR	OVCYPT	OVCYPB	OVCYYNT	OVCYNB	TSD	–	–
SR3 (07h)	Data is not latched	PAR	MSP[6:0]						

Where:

R	Read only mode access
Reset	Status after power−on or hard reset
PAR	Parity check

Table 18. SPI STATUS FLAGS OVERVIEW

Mnemonic	Flag	Length (bit)	Related SPI Register	Comment	Reset State
CPFail	Charge pump failure	1	Status Register 0	‘0’ = no failure ‘1’ = failure: indicates that the charge pump does not reach the required voltage level.	‘0’
MSP[6:0]	Micro−step position	7	Status Register 3	Translator micro step position	‘0000000’
OPENX	OPEN Coil X	1	Status Register 0	‘1’ = Open coil detected	‘0’
OPENY	OPEN Coil Y	1	Status Register 0	‘1’ = Open coil detected	‘0’
OVCXNB	**OV**er **C**urrent on X H−bridge; MOT**XN** terminal; **B**ottom tran.	1	Status Register 1	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at bottom transistor XN−terminal	‘0’
OVCXNT	**OV**er **C**urrent on X H−bridge; MOT**XN** terminal; **T**op transist.	1	Status Register 1	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at top transistor XN−terminal	‘0’
OVCXPB	**OV**er **C**urrent on X H−bridge; MOTXP terminal; **B**ottom transist.	1	Status Register 1	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at bottom transistor XP−terminal	‘0’
OVCXPT	**OV**er **C**urrent on X H−bridge; MOT**XP** terminal; **T**op transist.	1	Status Register 1	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at top transistor XP−terminal	‘0’
OVCYNB	**OV**er **C**urrent on Y H−bridge; MOT**YN** terminal; **B**ottom transist.	1	Status Register 2	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at bottom transistor YN−terminal	‘0’
OVCYNT	**OV**er **C**urrent on Y H−bridge; MOT**YN** terminal; **T**op transist.	1	Status Register 2	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at top transistor YN−terminal	‘0’
OVCYPB	**OV**er **C**urrent on Y H−bridge; MOT**YP** terminal; **B**ottom transist.	1	Status Register 2	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at bottom transistor YP−terminal	‘0’
OVCYPT	**OV**er Current on Y H−bridge; MOT**YP** terminal; **T**op transist.	1	Status Register 2	‘0’ = no failure ‘1’ = failure: indicates that over current is detected at top transistor YP−terminal	‘0’
TSD	Thermal shutdown	1	Status Register 2		‘0’
TW	Thermal warning	1	Status Register 0		‘0’
WD	Watchdog event (Note 21)	1	Status Register 0	‘1’ = watchdog reset after time−out	‘0’

21. WD − This bit indicates that the watchdog timer has not been cleared properly. If the master reads that WD is set to “1” after reset, it means that a watchdog reset occurred (warm boot) instead of POR (cold boot). WD bit will be cleared only when the master writes “0” to WDEN bit.

FUNCTIONAL DESCRIPTION CAN TRANSCEIVER

Introduction

The CAN transceiver is the interface between a (CAN) protocol controller and the physical bus. It provides differential transmit capability to the bus and differential receive capability to the CAN controller. Due to the wide common−mode voltage range of the receiver inputs, it is able to reach outstanding levels of electro−magnetic susceptibility (EMS). Similarly, extremely low electromagnetic emission (EME) is achieved by the excellent matching of the output signals.

Additional features are the ideal passive behavior when the supply voltage is removed; a wake−up over bus and the extreme low current in stand−by mode.

To cope with the long bus delay the communication speed needs to be low. The integrated transceiver allows low transmit data rates down 10 kbit/s or lower.

Operating Modes

The CAN transceiver provides two modes of operation as illustrated in Table 19. These modes are selectable through pin STB

Table 19. OPERATING MODES

Mode	STB	RXD	
		Low	High
Normal	Low	Bus dominant	Bus recessive
Standby	High	Wake−up request detected	No wake−up request detected

In the normal mode, the transceiver is able to communicate via the bus lines. The signals are transmitted and received to the CAN controller via the pins TxD and RxD. The slopes on the bus lines outputs are optimized to give extremely low EME.

In stand−by mode both the transmitter and receiver are disabled and a very low−power differential receiver monitors the bus lines for CAN bus activity. The bus lines are terminated to ground and supply current is reduced to a minimum, typically 10 μA. When a wake−up request is detected by the low−power differential receiver, the signal is first filtered and then verified as a valid wake signal after a time period of t_{BUS}, the RxD pin is driven low by the transceiver to inform the controller of the wake−up request.

Split Circuit

The VSPLIT pin is operational only in normal mode. In standby mode this pin is floating. The V_{SPLIT} is connected as shown in Figure 13 and its purpose is to provide a stabilized DC voltage of 0.5 x V_{CC} to the bus avoiding possible steps in the common−mode signal therefore reducing EME. These unwanted steps could be caused by an un−powered node on the network with excessive leakage current from the bus that shifts the recessive voltage from its nominal 0.5 x V_{CC} voltage.

Wake−up

Once a valid wake−up (dominant state longer than t_{BUS}) has been received during the standby mode the RxD pin is driven low

Over−Temperature Detection

A thermal protection circuit protects the IC from damage by switching off the transmitter if the junction temperature exceeds a value of approximately 160°C. Because the transmitter dissipates most of the power, the power dissipation and temperature of the IC is reduced. All other IC functions continue to operate. The transmitter off−state resets when pin TxD goes high. The thermal protection circuit is particularly needed when a bus line short circuits.

High Communication Speed Range

The transceiver is primarily intended for industrial applications. It allows very low baud rates needed for long bus length applications. But also high speed communication is possible up to 1 Mbit/s.

Fail Safe Features

A current−limiting circuit protects the transmitter output stage from damage caused by accidental short circuit to either positive or negative supply voltage, although power dissipation increases during this fault condition.

The pins CANH and CANL are protected from automotive electrical transients (according to ISO 7637; see Figure 7). Pins TxD and STB are pulled high internally should the input become disconnected. Pins TxD, STB and RxD will be floating, preventing reverse supply should the V_{CC} supply be removed.

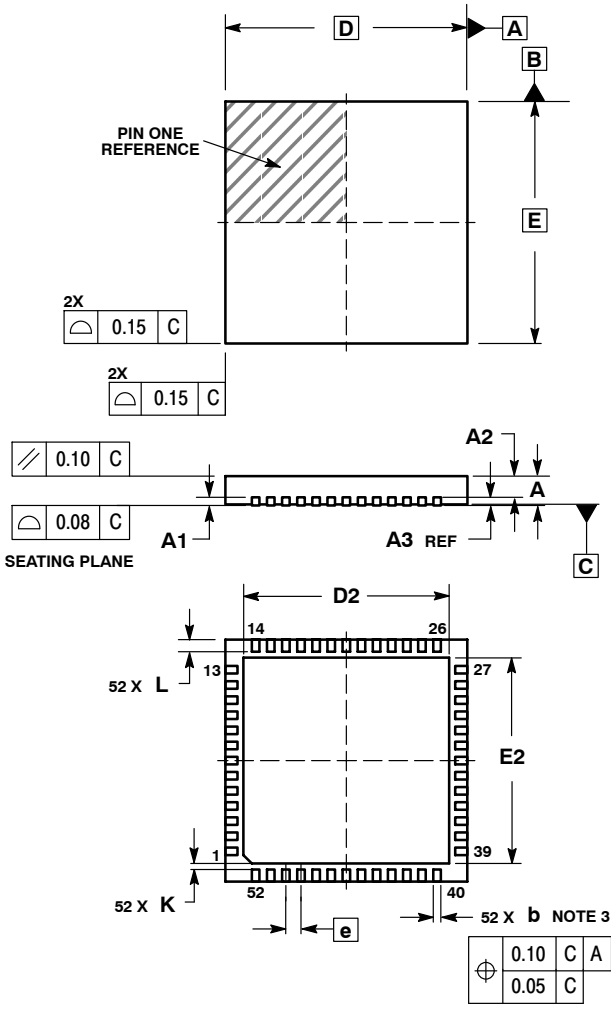
DEVICE ORDERING INFORMATION

Part Number	Temperature Range	Peak Current	Package Type	Shipping†
AMIS30523C5231RG	−40°C – 125°C	1600 mA	QFN−52 (Pb−Free)	Tape & Reel
AMIS30523C5231G	−40°C – 125°C	1600 mA	QFN−52 (Pb−Free)	Tube

†For information on tape and reel specifications, including part orientation and tape sizes, please refer to our Tape and Reel Packaging Specifications Brochure, BRD8011/D.

PACKAGE DIMENSIONS

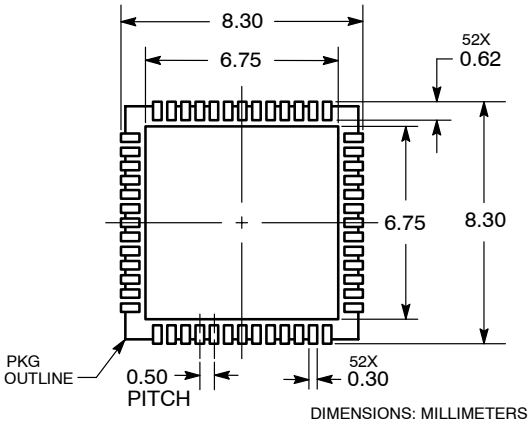
QFN52 8x8, 0.5P
CASE 485M−01
ISSUE C



NOTES:
1. DIMENSIONING AND TOLERANCING PER ASME Y14.5M, 1994.
2. CONTROLLING DIMENSION: MILLIMETERS
3. DIMENSION b APPLIES TO PLATED TERMINAL AND IS MEASURED BETWEEN 0.25 AND 0.30 MM FROM TERMINAL.
4. COPLANARITY APPLIES TO THE EXPOSED PAD AS WELL AS THE TERMINALS.

	MILLIMETERS	
DIM	MIN	MAX
A	0.80	1.00
A1	0.00	0.05
A2	0.60	0.80
A3	0.20 REF	
b	0.18	0.30
D	8.00 BSC	
D2	6.50	6.80
E	8.00 BSC	
E2	6.50	6.80
e	0.50 BSC	
K	0.20	---
L	0.30	0.50

RECOMMENDED SOLDERING FOOTPRINT



DIMENSIONS: MILLIMETERS

*For additional information on our Pb−Free strategy and soldering details, please download the ON Semiconductor Soldering and Mounting Techniques Reference Manual, SOLDERRM/D.

PUBLICATION ORDERING INFORMATION

LITERATURE FULFILLMENT:
Literature Distribution Center for ON Semiconductor
P.O. Box 5163, Denver, Colorado 80217 USA
Phone: 303−675−2175 or 800−344−3860 Toll Free USA/Canada
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Email: orderlit@onsemi.com

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ON Semiconductor Website: **www.onsemi.com**

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pubnumber/D

Компания «ЭлектроПласт» предлагает заключение долгосрочных отношений при поставках импортных электронных компонентов на взаимовыгодных условиях!

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- Поставка более 17-ти миллионов наименований электронных компонентов;
- Поставка сложных, дефицитных, либо снятых с производства позиций;
- Оперативные сроки поставки под заказ (от 5 рабочих дней);
- Экспресс доставка в любую точку России;
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- Лицензия ФСБ на осуществление работ с использованием сведений, составляющих государственную тайну;
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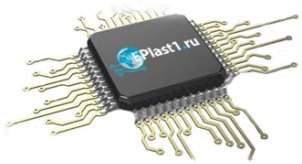
- Подбор аналогов;
- Консультации по применению компонента;
- Поставка образцов и прототипов;
- Техническая поддержка проекта;
- Защита от снятия компонента с производства.



Как с нами связаться

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