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World's First Wide-Range 6-Axis MEMS MotionTracking™ Device for Sports and High Impact Applications

GENERAL DESCRIPTION

Many of today's wearable and sports solutions, which analyze the motion of a user's golf or tennis swings, soccer ball kicks, or basketball activities, require higher than currently available ± 2000 dps (degrees per second) FSR for gyroscope and $\pm 16g$ FSR for accelerometer to better insure that critical data is not lost at the point of high impact or high speed rotation. The ICM-20649 6-axis inertial sensor offers the smallest size, lowest profile and lowest power in conjunction with industry leading high FSR.

With an extended FSR range of ± 4000 dps for gyroscope and $\pm 30g$ for accelerometer, the ICM-20649 enables precise analysis of contact sports applications providing continuous motion sensor data before, during and after impact providing more accurate feedback.

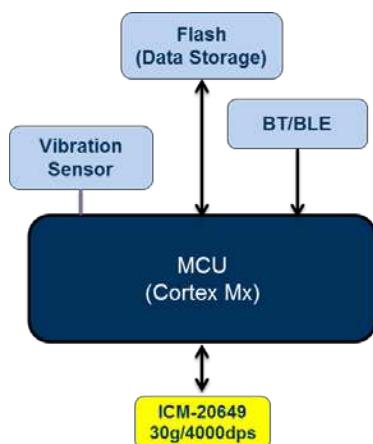
The ICM-20649 is the world's first wide-range 6-axis MotionTracking device for Sports and other High Impact applications. It is available in a 3x3x0.9 mm 24-pin QFN package.

ORDERING INFORMATION

PART	TEMP RANGE	PACKAGE
ICM-20649†	-40°C to +85°C	24-Pin QFN

†Denotes RoHS and Green-Compliant Package

BLOCK DIAGRAM



Motion Analysis Pod Architecture

APPLICATIONS

- Sports
- Wearable Sensors
- High Impact Applications

FEATURES

- 3-Axis gyroscope with programmable FSR of ± 500 dps, ± 100 dps, ± 2000 dps, and ± 4000 dps
- 3-Axis accelerometer with programmable FSR of $\pm 4g$, $\pm 8g$, $\pm 16g$, and $\pm 30g$
- User-programmable interrupts
- Wake-on-motion interrupt for low power operation of applications processor
- 512-byte FIFO buffer enables the applications processor to read the data in bursts
- On-Chip 16-bit ADCs and Programmable Filters
- DMP Enabled:
 - SMD, Step Count, Step Detect, Activity Classifier, RV, GRV
 - Calibration of accel/gyro/compass
- Host interface: 7 MHz SPI or 400 kHz I²C
- Digital-output temperature sensor
- VDD operating range of 1.71V to 3.6V
- MEMS structure hermetically sealed and bonded at wafer level
- RoHS and Green compliant

TYPICAL OPERATING CIRCUIT

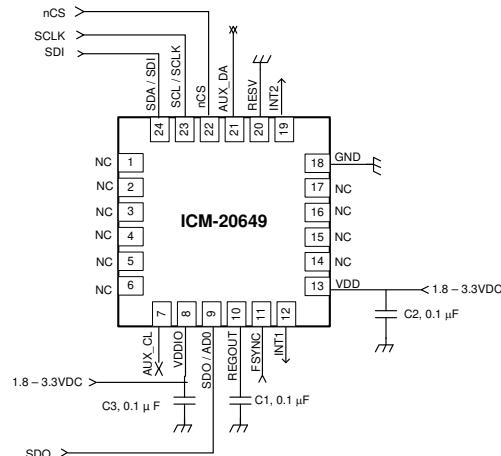


TABLE OF CONTENTS

GENERAL DESCRIPTION.....	1
ORDERING INFORMATION.....	1
APPLICATIONS.....	1
FEATURES.....	1
TYPICAL OPERATING CIRCUIT	1
1 Introduction.....	10
1.1 Purpose and Scope.....	10
1.2 Product Overview.....	10
2 Features	11
2.1 Gyroscope Features	11
2.2 Accelerometer Features.....	11
2.3 DMP Features.....	11
2.4 Additional Features.....	11
3 Electrical Characteristics.....	12
3.1 Gyroscope Specifications	12
3.2 Accelerometer Specifications.....	13
3.3 Electrical Specifications.....	14
3.3.1 D.C. Electrical Characteristics.....	14
3.3.2 A.C. Electrical Characteristics.....	15
3.3.3 Other Electrical Specifications	16
3.4 I ² C Timing Characterization.....	17
3.5 SPI Timing Characterization	18
3.6 Absolute Maximum Ratings	19
4 Applications Information	20
4.1 Pin Out Diagram and Signal Description	20
4.2 Typical Operating Circuit.....	21
4.3 Bill of Materials for External Components	21
4.4 Block Diagram	22
4.5 Overview	22
4.6 Three-Axis MEMS Gyroscope with 16-bit ADCs and Signal Conditioning	23
4.7 Three-Axis MEMS Accelerometer with 16-bit ADCs and Signal Conditioning.....	23
4.8 Digital Motion Processor.....	23
4.9 Primary I ² C and SPI Serial Communications Interfaces.....	23
4.9.1 ICM-20649 Solution Using I ² C Interface.....	23
4.9.2 ICM-20649 Solution Using SPI Interface	25
4.10 Auxiliary I ² C Serial Interface.....	26
4.11 Auxiliary I ² C Bus Modes of Operation:.....	26
4.12 Self-Test	26

4.13	Clocking.....	26
4.14	Sensor Data Registers	27
4.15	FIFO.....	27
4.16	FSYNC.....	27
4.17	Interrupts.....	27
4.18	Digital-Output Temperature Sensor	27
4.19	Bias and LDOs	27
4.20	Charge Pump	27
4.21	Power Modes.....	28
5	Programmable Interrupts	29
6	Digital Interface	30
6.1	I ² C and SPI Serial Interfaces	30
6.2	I ² C Interface.....	30
6.3	I ² C Communications Protocol	31
6.4	I ² C Terms	33
6.5	SPI Interface	33
7	Register Map.....	35
7.1	User Bank 0 Register Map:.....	35
7.2	User Bank 1 Register Map:.....	36
7.3	User Bank 2 Register Map:.....	36
7.4	User Bank 3 Register Map:.....	37
8	Register Descriptions	38
8.1	USR Bank 0 Register Map.....	38
8.1.1	WHO_AM_I	38
8.1.2	USER_CTRL	38
8.1.3	LP_CONFIG	39
8.1.4	PWR_MGMT_1.....	39
8.1.5	PWR_MGMT_2.....	40
8.1.6	INT_PIN_CFG	40
8.1.7	INT_ENABLE	41
8.1.8	INT_ENABLE_1	41
8.1.9	INT_ENABLE_2	41
8.1.10	INT_ENABLE_3	42
8.1.11	I2C_MST_STATUS	42
8.1.12	INT_STATUS	42
8.1.13	12.1.13 INT_STATUS_1	43
8.1.14	INT_STATUS_2	43
8.1.15	INT_STATUS_3	43
8.1.16	DELAY_TIMEH	43
8.1.17	DELAY_TIMEL.....	44

8.1.18	ACCEL_XOUT_H	44
8.1.19	ACCEL_XOUT_L	44
8.1.20	ACCEL_YOUT_H	44
8.1.21	ACCEL_YOUT_L	45
8.1.22	ACCEL_ZOUT_H	45
8.1.23	ACCEL_ZOUT_L	45
8.1.24	GYRO_XOUT_H	45
8.1.25	GYRO_XOUT_L	46
8.1.26	GYRO_YOUT_H	46
8.1.27	GYRO_YOUT_L	46
8.1.28	GYRO_ZOUT_H	46
8.1.29	GYRO_ZOUT_L	47
8.1.30	TEMP_OUT_H	47
8.1.31	TEMP_OUT_L	47
8.1.32	EXT_SLV_SENS_DATA_00	47
8.1.33	EXT_SLV_SENS_DATA_01	48
8.1.34	EXT_SLV_SENS_DATA_02	48
8.1.35	EXT_SLV_SENS_DATA_03	48
8.1.36	EXT_SLV_SENS_DATA_04	48
8.1.37	EXT_SLV_SENS_DATA_05	49
8.1.38	EXT_SLV_SENS_DATA_06	49
8.1.39	EXT_SLV_SENS_DATA_07	49
8.1.40	EXT_SLV_SENS_DATA_08	49
8.1.41	EXT_SLV_SENS_DATA_09	50
8.1.42	EXT_SLV_SENS_DATA_10	50
8.1.43	EXT_SLV_SENS_DATA_11	50
8.1.44	EXT_SLV_SENS_DATA_12	50
8.1.45	EXT_SLV_SENS_DATA_13	51
8.1.46	EXT_SLV_SENS_DATA_14	51
8.1.47	EXT_SLV_SENS_DATA_15	51
8.1.48	EXT_SLV_SENS_DATA_16	51
8.1.49	EXT_SLV_SENS_DATA_17	52
8.1.50	EXT_SLV_SENS_DATA_18	52
8.1.51	EXT_SLV_SENS_DATA_19	52
8.1.52	EXT_SLV_SENS_DATA_20	52
8.1.53	EXT_SLV_SENS_DATA_21	53
8.1.54	EXT_SLV_SENS_DATA_22	53
8.1.55	EXT_SLV_SENS_DATA_23	53
8.1.56	FIFO_EN_1	54
8.1.57	FIFO_EN_2	54

8.1.58	FIFO_RST	55
8.1.59	FIFO_MODE	55
8.1.60	FIFO_COUNTH.....	55
8.1.61	FIFO_COUNTL	55
8.1.62	FIFO_R_W	56
8.1.63	DATA_RDY_STATUS	56
8.1.64	FIFO_CFG	56
8.1.65	REG_BANK_SEL.....	56
8.2	USR Bank 1 Register Map	57
8.2.1	SELF_TEST_X_GYRO	57
8.2.2	SELF_TEST_Y_GYRO	57
8.2.3	SELF_TEST_Z_GYRO.....	57
8.2.4	SELF_TEST_X_ACCEL	57
8.2.5	SELF_TEST_Y_ACCEL.....	58
8.2.6	SELF_TEST_Z_ACCEL.....	58
8.2.7	XA_OFFS_H.....	58
8.2.8	XA_OFFS_L	58
8.2.9	YA_OFFS_H.....	58
8.2.10	YA_OFFS_L	59
8.2.11	ZA_OFFS_H	59
8.2.12	ZA_OFFS_L	59
8.2.13	TIMEBASE_CORRECTION_PLL	59
8.2.14	REG_BANK_SEL.....	60
8.3	USR Bank 2 Register Map	61
8.3.1	GYRO_SMPLRT_DIV.....	61
8.3.2	GYRO_CONFIG_1.....	61
8.3.3	GYRO_CONFIG_2.....	62
8.3.4	XG_OFFS_USRH.....	63
8.3.5	XG_OFFS_USRL.....	64
8.3.6	YG_OFFS_USRH.....	64
8.3.7	YG_OFFS_USRL.....	64
8.3.8	ZG_OFFS_USRH	64
8.3.9	ZG_OFFS_USRL	64
8.3.10	ODR_ALIGN_EN	65
8.3.11	ACCEL_SMPLRT_DIV_1	65
8.3.12	ACCEL_SMPLRT_DIV_2	65
8.3.13	ACCEL_INTEL_CTRL	65
8.3.14	ACCEL_WOM_THR	66
8.3.15	ACCEL_CONFIG	66
8.3.16	ACCEL_CONFIG_2	67

8.3.17	FSYNC_CONFIG	69
8.3.18	TEMP_CONFIG	69
8.3.19	MOD_CTRLUSR	70
8.3.20	REG_BANK_SEL	70
8.4	USR Bank 3 Register Map	71
8.4.1	I2C_MST_ODR_CONFIG	71
8.4.2	I2C_MST_CTRL	71
8.4.3	I2C_MST_DELAY_CTRL	71
8.4.4	I2C_SLV0_ADDR	72
8.4.5	I2C_SLV0_REG	72
8.4.6	I2C_SLV0_CTRL	72
8.4.7	I2C_SLV0_DO	73
8.4.8	I2C_SLV1_ADDR	73
8.4.9	I2C_SLV1_REG	73
8.4.10	I2C_SLV1_CTRL	74
8.4.11	SLV1_DO	74
8.4.12	I2C_SLV2_ADDR	75
8.4.13	I2C_SLV2_REG	75
8.4.14	I2C_SLV2_CTRL	75
8.4.15	I2C_SLV2_DO	76
8.4.16	I2C_SLV3_ADDR	76
8.4.17	I2C_SLV3_REG	76
8.4.18	I2C_SLV3_CTRL	77
8.4.19	I2C_SLV3_DO	77
8.4.20	I2C_SLV4_ADDR	78
8.4.21	I2C_SLV4_REG	78
8.4.22	I2C_SLV4_CTRL	78
8.4.23	I2C_SLV4_DO	78
8.4.24	I2C_SLV4_DI	79
8.4.25	REG_BANK_SEL	79
9	Use Notes	80
9.1	Gyroscope Mode Transition	80
9.2	Power Management 1 Register Setting	80
9.3	DMP Memory Access	80
9.4	Time Base Correction	80
9.5	I ² C Master Clock Frequency	81
9.6	Clocking	81
9.7	LP_EN Bit-Field Usage	82
9.8	Register Access Using SPI Interface	82
10	Orientation of Axes	83

11	Package Dimensions	84
12	Part Number Part Markings.....	86
13	References	87
14	Revision History	88

LIST OF FIGURES

Figure 1. I ² C Bus Timing Diagram	17
Figure 2. SPI Bus Timing Diagram.....	18
Figure 3. Pin out Diagram for ICM-20649 3.0x3.0x0.9 mm QFN.....	20
Figure 4. ICM-20649 Application Schematic (a) I ² C operation (b) SPI operation.....	21
Figure 5. ICM-20649 Block Diagram.....	22
Figure 6. ICM-20649 Solution Using I ² C Interface.....	24
Figure 7. ICM-20649 Solution Using SPI Interface	25
Figure 8. START and STOP Conditions.....	31
Figure 9. Acknowledge on the I ² C Bus	31
Figure 10. Complete I ² C Data Transfer.....	32
Figure 11. Typical SPI Master / Slave Configuration	34
Figure 12. Orientation of Axes of Sensitivity and Polarity of Rotation	83
Figure 13. Package Dimensions.....	84
Figure 14. Part Number Package Markings.....	86

LIST OF TABLES

Table 1. Gyroscope Specifications	12
Table 2. Accelerometer Specifications.....	13
Table 3. D.C. Electrical Characteristics	14
Table 4. A.C. Electrical Characteristics	16
Table 5. Other Electrical Specifications.....	16
Table 6. I ² C Timing Characteristics	17
Table 7. SPI Timing Characteristics (7 MHz).....	18
Table 8. Absolute Maximum Ratings	19
Table 9. Signal Descriptions	20
Table 10. Bill of Materials	21
Table 11. Power Modes for ICM-20649	28
Table 12. Table of Interrupt Sources.....	29
Table 13. Serial Interface	30
Table 14. I ² C Terms	33
Table 15. Configuration.....	62
Table 16. Gyroscope Filter Bandwidths (Low-Power Mode)	63
Table 17. Accelerometer Configuration	67
Table 18. Accelerometer Configuration 2	68
Table 19. I ² C Master Clock Frequency	81
Table 20. Package Dimensions.....	85
Table 21. Part Number Package Markings	86

1 INTRODUCTION

1.1 PURPOSE AND SCOPE

This document is a preliminary product specification, providing a description, specifications, and design related information on the ICM-20649 MotionTracking device.

Final specifications are available via our sales contacts. For references to register map and descriptions of individual registers, please refer to the ICM-20649 Register Map and Register Descriptions sections.

1.2 PRODUCT OVERVIEW

The ICM-20649 is a MotionTracking device that combines a 3-axis gyroscope, 3-axis accelerometer, and a Digital Motion Processor™ (DMP) all in a small 3.0x3.0x0.9mm QFN package. The device supports the following features:

- Android Lollipop support
- FIFO of size 512 bytes (FIFO size will vary depending on DMP feature-set)
- Runtime Calibration
- Enhanced FSYNC functionality to improve timing for applications like EIS

ICM-20649 devices, with their 6-axis integration, on-chip DMP, and run-time calibration firmware, enable manufacturers to eliminate the costly and complex selection, qualification, and system level integration of discrete devices, guaranteeing optimal motion performance for consumers.

The gyroscope has a programmable full-scale range up to ± 4000 dps. The accelerometer has a user-programmable accelerometer full-scale range up to $\pm 30g$. Factory-calibrated initial sensitivity of both sensors reduces production-line calibration requirements.

Other key features include on-chip 16-bit ADCs, programmable digital filters, an embedded temperature sensor, and programmable interrupts. The device features I²C and SPI serial interfaces, a VDD operating range of 1.71V to 3.6V, and a separate digital IO supply, VDDIO from 1.71V to 3.6V.

Communication with all registers of the device is performed using I²C at up to 100 kHz (standard-mode) or up to 400 kHz (fast-mode), or SPI at up to 7 MHz.

By leveraging its patented and volume-proven CMOS-MEMS fabrication platform, which integrates MEMS wafers with companion CMOS electronics through wafer-level bonding, InvenSense has driven the package size down to a footprint and thickness of 3.0x3.0x0.9 mm (24-pin QFN), to provide a very small yet high-performance, low-cost package. The device provides high robustness by supporting 10,000g shock reliability.

2 FEATURES

2.1 GYROSCOPE FEATURES

The triple-axis MEMS gyroscope in the ICM-20649 includes the following features:

- Digital-output X-, Y-, and Z-axis angular rate sensors (gyroscopes) with a user-programmable full-scale range of ± 500 dps, ± 1000 dps, ± 2000 dps, and ± 4000 dps and integrated 16-bit ADCs
- Digitally-programmable low-pass filter
- Factory calibrated sensitivity scale factor
- Self-test

2.2 ACCELEROMETER FEATURES

The triple-axis MEMS accelerometer in ICM-20649 includes the following features:

- Digital-output X-, Y-, and Z-axis accelerometer with a programmable full scale range of $\pm 4g$, $\pm 8g$, $\pm 16g$, and $\pm 30g$ and integrated 16-bit ADCs
- User-programmable interrupts
- Wake-on-motion interrupt for low power operation of applications processor
- Self-test

2.3 DMP FEATURES

The DMP in ICM-20649 includes the following capabilities:

- Offloads computation of motion processing algorithms from the host processor. The DMP can be used to minimize power, simplify timing, simplify the software architecture, and save valuable MIPS on the host processor for use in applications.
- Optimized for Android Lollipop for low power features (AP suspended) including SMD, Step Count, Step Detect, Activity Classification, Rotation Vector, and Gaming Rotation Vector
- Optimized for Android Lollipop batching, both while the AP is active and suspended. The DMP will also batch data from externally connected sensors such as a compass, or pressure sensor.
- The DMP enables ultra-low power run-time and background calibration of the accelerometer, gyroscope, and compass, maintaining optimal performance of the sensor data for both physical and virtual sensors generated through sensor fusion. This enables the best user experience for all sensor enabled applications for the lifetime of the device.
- DMP features simplify the software architecture resulting in quicker time to market.
- DMP features are OS, Platform, and Architecture independent, supporting virtually any AP, MCU, or other embedded architecture.

2.4 ADDITIONAL FEATURES

The ICM-20649 includes the following additional features:

- I²C at up to 100 kHz (standard-mode) or up to 400 kHz (fast-mode) or SPI at up to 7 MHz for communication with registers
- Auxiliary master I²C bus for reading data from external sensors (e.g. magnetometer)
- Digital-output temperature sensor
- 10,000g shock tolerant
- MEMS structure hermetically sealed and bonded at wafer level
- RoHS and Green compliant

3 ELECTRICAL CHARACTERISTICS

3.1 GYROSCOPE SPECIFICATIONS

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

Note: All specifications apply to Standard (Duty-Cycled) Mode and Low-Noise Mode, unless noted otherwise.

PARAMETER	CONDITIONS	MIN	TYP	MAX	UNITS	NOTES
GYROSCOPE SENSITIVITY						
Full-Scale Range	GYRO_FS_SEL = 0		±500		dps	1
	GYRO_FS_SEL = 1		±1000		dps	1
	GYRO_FS_SEL = 2		±2000		dps	1
	GYRO_FS_SEL = 3		±4000		dps	1
Gyroscope ADC Word Length		16			bits	1
Sensitivity Scale Factor	GYRO_FS_SEL = 0	65.5			LSB/(dps)	1
	GYRO_FS_SEL = 1	32.8			LSB/(dps)	1
	GYRO_FS_SEL = 2	16.4			LSB/(dps)	1
	GYRO_FS_SEL = 3	8.2			LSB/(dps)	1
Sensitivity Scale Factor Tolerance	25°C		±0.5		%	3
Sensitivity Scale Factor Variation Over Temperature	-40°C to +85°C		±2		%	2
Nonlinearity	Best fit straight line; 25°C		±0.1		%	2, 4
Cross-Axis Sensitivity			±2		%	2, 4
ZERO-RATE OUTPUT (ZRO)						
Initial ZRO Tolerance	25°C (Component-level)		±5		dps	3
ZRO Variation Over Temperature	-40°C to +85°C		±0.05		dps/°C	2
GYROSCOPE NOISE PERFORMANCE (GYRO_FS_SEL=0)						
Noise Spectral Density	Based on Noise Bandwidth = 10 Hz		0.0175		dps/VHz	3
GYROSCOPE MECHANICAL FREQUENCIES						
LOW PASS FILTER RESPONSE	Programmable Range	25	27	29	kHz	3
GYROSCOPE START-UP TIME	From Full-Chip Sleep mode		5.7		Hz	1, 4
OUTPUT DATA RATE	From Full-Chip Sleep mode		35		ms	2, 4
	Standard (duty-cycled) Mode	4.4		562.5	Hz	1
	Low-Noise Mode GYRO_FCHOICE = 1; GYRO_DLPFCFG = x		4.4		1.125k	
	Low-Noise Mode GYRO_FCHOICE = 0; GYRO_DLPFCFG = x			9k	Hz	

Table 1. Gyroscope Specifications

Notes:

1. Guaranteed by design.
2. Derived from validation or characterization of parts, not guaranteed in production.
3. Tested in production.
4. Low-noise mode specification.

3.2 ACCELEROMETER SPECIFICATIONS

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

Note: All specifications apply to Standard (Duty-Cycled) Mode and Low-Noise Mode, unless noted otherwise.

PARAMETER	CONDITIONS	MIN	TYP	MAX	UNITS	NOTES
ACCELEROMETER SENSITIVITY						
Full-Scale Range	ACCEL_FS = 0		±4		g	1
	ACCEL_FS = 1		±8		g	1
	ACCEL_FS = 2		±16		g	1
	ACCEL_FS = 3		±30		g	1
ADC Word Length	Output in two's complement format	16			bits	1
Sensitivity Scale Factor	ACCEL_FS = 0	8,192			LSB/g	1
	ACCEL_FS = 1	4,096			LSB/g	1
	ACCEL_FS = 2	2,048			LSB/g	1
	ACCEL_FS = 3	1,024			LSB/g	1
Initial Tolerance	Component-level	±0.5			%	3
Sensitivity Change vs. Temperature	-40°C to +85°C ACCEL_FS=0	±0.026			%/°C	2
Nonlinearity	Best Fit Straight Line	±0.5			%	2, 4
Cross-Axis Sensitivity		±2			%	2, 4
Initial Tolerance	Component-level, all axes	±65			mg	3
Zero-G Level Change vs. Temperature	0°C to +85°C	±0.80			mg/°C	2
ACCELEROMETER NOISE PERFORMANCE						
Noise Spectral Density	Based on Noise Bandwidth = 10 Hz		285		µg/√Hz	3
LOW PASS FILTER RESPONSE	Programmable Range	5.7		246	Hz	1, 4
INTELLIGENCE FUNCTION INCREMENT			32		mg/LSB	1
ACCELEROMETER STARTUP TIME	From Sleep mode		20		ms	2, 4
	From Cold Start, 1ms V _{DD} ramp		30		ms	2, 4
OUTPUT DATA RATE	Low-Power Mode	0.27		562.5	Hz	1
	Low-Noise Mode ACCEL_FCHOICE = 1; ACCEL_DLPFCFG = x		4.5		1.125k	
	Low-Noise Mode ACCEL_FCHOICE = 0; ACCEL_DLPFCFG = x				4.5k	

Table 2. Accelerometer Specifications

Notes:

1. Guaranteed by design.
2. Derived from validation or characterization of parts, not guaranteed in production.
3. Tested in production.
4. Low-noise mode specification.

3.3 ELECTRICAL SPECIFICATIONS

3.3.1 D.C. Electrical Characteristics

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

PARAMETER	CONDITIONS	MIN	TYP	MAX	UNITS	NOTES
SUPPLY VOLTAGES						
VDD		1.71	1.8	3.6	V	1
VDDIO		1.71	1.8	3.6	V	1
SUPPLY CURRENTS						
Gyroscope Only (DMP & Accelerometer disabled)	Low-Noise Mode		2.67		mA	2
Accelerometer Only (DMP & Gyroscope disabled)	Low-Noise Mode		760		µA	2
Gyroscope + Accelerometer (DMP disabled)	Low-Noise Mode		3.21		mA	2
Gyroscope Only (DMP & Accelerometer disabled)	Low-Power Mode, 102.3 Hz update rate, 1x averaging filter		1.23		mA	2, 3
Accelerometer Only (DMP & Gyroscope disabled)	Low-Power Mode, 102.3 Hz update rate, 1x averaging filter		68.9		µA	2, 3
Gyroscope + Accelerometer (DMP disabled)	Low-Power Mode, 102.3 Hz update rate, 1x averaging filter		1.27		mA	2, 3
Full-Chip Sleep Mode			8		µA	2
TEMPERATURE RANGE						
Specified Temperature Range	Performance parameters are not applicable beyond Specified Temperature Range	-40		+85	°C	1

Table 3. D.C. Electrical Characteristics

Notes:

1. Guaranteed by design.
2. Derived from validation or characterization of parts, not guaranteed in production.
3. The 102.3 Hz ODR value shown here is an example; please see the section below for the full list of ODRs supported and corresponding current values.

3.3.2 A.C. Electrical Characteristics

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

PARAMETER	CONDITIONS	MIN	TYP	MAX	UNITS	NOTES
SUPPLIES						
Supply Ramp Time (T _{RAMP})	Monotonic ramp. Ramp rate is 10% to 90% of the final value.	0.01	20	100	ms	1
TEMPERATURE SENSOR						
Operating Range	Ambient	-40		85	°C	1
Sensitivity	Untrimmed		333.87		LSB/°C	
Room Temp Offset	21°C		0		LSB	
Power-On RESET						
Supply Ramp Time (T _{RAMP})	Valid power-on RESET	0.01	20	100	ms	1
Start-up time for register read/write	From power-up		11	100	ms	1
I²C ADDRESS						
	AD0 = 0		1101000			
	AD0 = 1		1101001			
DIGITAL INPUTS (FSYNC, AD0, SCLK, SDI, CS)						
V _{IH} , High Level Input Voltage		0.7*VDDIO			V	1
V _{IL} , Low Level Input Voltage				0.3*VDDIO	V	
C _i , Input Capacitance		< 10			pF	
DIGITAL OUTPUT (SDO, INT)						
V _{OH} , High Level Output Voltage	R _{LOAD} = 1 MΩ;	0.9*VDDIO			V	1
V _{OL1} , LOW-Level Output Voltage	R _{LOAD} = 1 MΩ;			0.1*VDDIO	V	
V _{OLINT1} , INT Low-Level Output Voltage	OPEN = 1, 0.3 mA sink Current			0.1	V	
Output Leakage Current	OPEN = 1		100		nA	
t _{INT} , INT Pulse Width	LATCH_INT_EN = 0		50		μs	
I²C I/O (SCL, SDA)						
V _{IL} , LOW Level Input Voltage		-0.5 V		0.3*VDDIO	V	1
V _{IH} , HIGH-Level Input Voltage		0.7*VDDIO		VDDIO + 0.5 V	V	
V _{hys} , Hysteresis			0.1*VDDIO		V	
V _{OL} , LOW-Level Output Voltage	3 mA sink current	0		0.4	V	
I _{OL} , LOW-Level Output Current	V _{OL} = 0.4 V V _{OL} = 0.6 V		3 6		mA mA	
Output Leakage Current			100		nA	
t _{of} , Output Fall Time from V _{IHmax} to V _{ILmax}	C _b bus capacitance in pF	20+0.1 C _b		250	ns	
AUXILIARY I/O (AUX_CL, AUX_DA)						
V _{IL} , LOW-Level Input Voltage		-0.5 V		0.3*VDDIO	V	1
V _{IH} , HIGH-Level Input Voltage		0.7* VDDIO		VDDIO + 0.5 V	V	
V _{hys} , Hysteresis			0.1* VDDIO		V	
V _{OL1} , LOW-Level Output Voltage	VDDIO > 2 V; 1 mA sink current	0		0.4	V	
V _{OL3} , LOW-Level Output Voltage	VDDIO < 2 V; 1 mA sink current	0		0.2* VDDIO	V	
I _{OL} , LOW-Level Output Current	V _{OL} = 0.4 V V _{OL} = 0.6 V		3 6		mA mA	
Output Leakage Current			100		nA	
t _{of} , Output Fall Time from V _{IHmax} to V _{ILmax}	C _b bus capacitance in pF	20+0.1C _b		250	ns	
INTERNAL CLOCK SOURCE						
Clock Frequency Initial Tolerance	Accelerometer Only Mode	-5		+5	%	1
	Gyroscope or 6-Axis Mode WITHOUT Timebase Correction	-9		+9	%	1
	Gyroscope or 6-Axis Mode WITH Timebase Correction	-1		+1		

PARAMETER	CONDITIONS	MIN	TYP	MAX	UNITS	NOTES
Frequency Variation over Temperature	Accelerometer Only Mode	-10		+10	%	1
	Gyroscope or 6-Axis Mode		±1		%	1

Table 4. A.C. Electrical Characteristics

Notes:

1. Derived from validation or characterization of parts, not guaranteed in production.

3.3.3 Other Electrical Specifications

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

PARAMETER	CONDITIONS	MIN	TYP	MAX	Units	Notes
SERIAL INTERFACE						
SPI Operating Frequency, All Registers Read/Write	Low Speed Characterization		100 ±10%		kHz	
	High Speed Characterization		7 ±10%		MHz	
I ² C Operating Frequency	All registers, Fast-mode			400	kHz	
	All registers, Standard-mode			100	kHz	

Table 5. Other Electrical Specifications

3.4 I²C TIMING CHARACTERIZATION

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, T_A = 25°C, unless otherwise noted.

PARAMETERS	CONDITIONS	MIN	TYPICAL	MAX	UNITS	NOTES
I ² C TIMING	I ² C FAST-MODE					
f _{SCL} , SCL Clock Frequency				400	kHz	1, 2
t _{HD.STA} , (Repeated) START Condition Hold Time		0.6			μs	1, 2
t _{LOW} , SCL Low Period		1.3			μs	1, 2
t _{HIGH} , SCL High Period		0.6			μs	1, 2
t _{SU.STA} , Repeated START Condition Setup Time		0.6			μs	1, 2
t _{HD.DAT} , SDA Data Hold Time		0			μs	1, 2
t _{SU.DAT} , SDA Data Setup Time		100			ns	1, 2
t _r , SDA and SCL Rise Time	C _b bus cap. from 10 to 400 pF	20+0.1C _b		300	ns	1, 2
t _f , SDA and SCL Fall Time	C _b bus cap. from 10 to 400 pF	20+0.1C _b		300	ns	1, 2
t _{SU.STO} , STOP Condition Setup Time		0.6			μs	1, 2
t _{BUF} , Bus Free Time Between STOP and START Condition		1.3			μs	1, 2
C _b , Capacitive Load for each Bus Line		< 400			pF	1, 2
t _{VD.DAT} , Data Valid Time				0.9	μs	1, 2
t _{VD.ACK} , Data Valid Acknowledge Time				0.9	μs	1, 2

Table 6. I²C Timing Characteristics

Notes:

1. Timing Characteristics apply to both Primary and Auxiliary I²C Bus.
2. Based on characterization of 5 parts over temperature and voltage as mounted on evaluation board or in sockets.

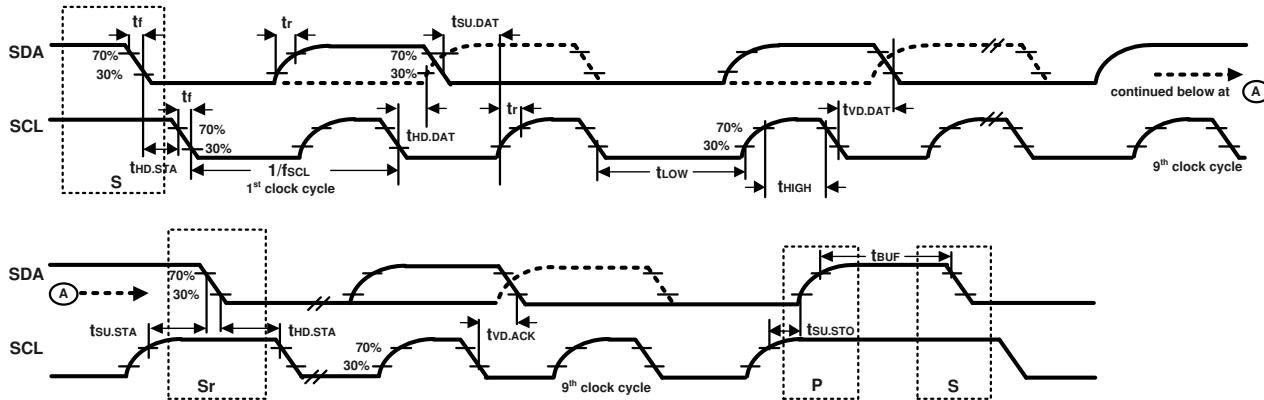


Figure 1. I²C Bus Timing Diagram

3.5 SPI TIMING CHARACTERIZATION

Typical Operating Circuit of section 4.2, VDD = 1.8 V, VDDIO = 1.8 V, TA = 25°C, unless otherwise noted.

Parameters	Conditions	Min	Typical	Max	Units	Notes
SPI TIMING						
f _{SCLK} , SCLK Clock Frequency				7	MHz	
t _{LOW} , SCLK Low Period		64			ns	
t _{HIGH} , SCLK High Period		64			ns	
t _{SU,CS} , CS Setup Time		8			ns	
t _{HD,CS} , CS Hold Time		500			ns	
t _{SU,SDI} , SDI Setup Time		5			ns	
t _{HD,SDI} , SDI Hold Time		7			ns	
t _{VD,SDO} , SDO Valid Time	C _{load} = 20 pF			59	ns	
t _{HD,SDO} , SDO Hold Time	C _{load} = 20 pF	6			ns	
t _{DIS,SDO} , SDO Output Disable Time				50	ns	

Table 7. SPI Timing Characteristics (7 MHz)

Note:

1. Based on characterization of 5 parts over temperature and voltage as mounted on evaluation board or in sockets.

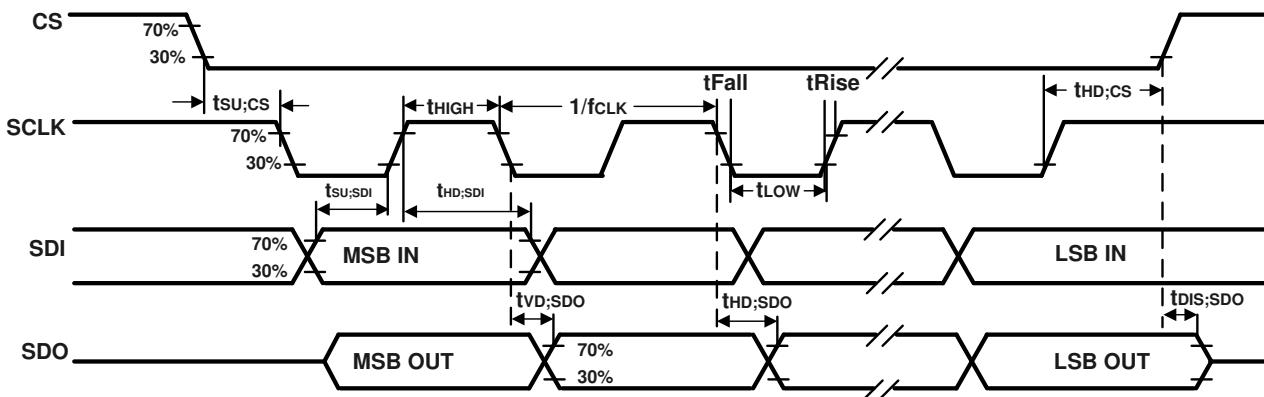


Figure 2. SPI Bus Timing Diagram

3.6 ABSOLUTE MAXIMUM RATINGS

Stress above those listed as “Absolute Maximum Ratings” may cause permanent damage to the device. These are stress ratings only and functional operation of the device at these conditions is not implied. Exposure to the absolute maximum ratings conditions for extended periods may affect device reliability.

Parameter	Rating
Supply Voltage, VDD	-0.5V to 4V
Supply Voltage, VDDIO	-0.5V to 4V
REGOUT	-0.5V to 2V
Input Voltage Level (AUX_DA, ADO, FSYNC, INT, SCL, SDA)	-0.5V to VDD + 0.5V
Acceleration (Any Axis, unpowered)	10,000g for 0.2 ms
Operating Temperature Range	-40°C to +105°C
Storage Temperature Range	-40°C to +125°C
Electrostatic Discharge (ESD) Protection	2 kV (HBM); 200V (MM)
Latch-up	JEDEC Class II (2), 125°C ±100 mA

Table 8. Absolute Maximum Ratings

4 APPLICATIONS INFORMATION

4.1 PIN OUT DIAGRAM AND SIGNAL DESCRIPTION

PIN NUMBER	PIN NAME	PIN DESCRIPTION
7	AUX_CL	I ² C Master serial clock, for connecting to external sensors.
8	VDDIO	Digital I/O supply voltage.
9	AD0 / SDO	I ² C Slave Address LSB (AD0); SPI serial data output (SDO).
10	REGOUT	Regulator filter capacitor connection.
11	FSYNC	Frame synchronization digital input. Connect to GND if unused.
12	INT1	Interrupt 1.
13	VDD	Power supply voltage.
18	GND	Power supply ground.
19	INT2	Interrupt 2.
20	RESV	Reserved. Connect to GND.
21	AUX_DA	I ² C master serial data, for connecting to external sensors.
22	nCS	Chip select (SPI mode only).
23	SCL / SCLK	I ² C serial clock (SCL); SPI serial clock (SCLK).
24	SDA / SDI	I ² C serial data (SDA); SPI serial data input (SDI).
1 – 6, 14 - 17	NC	No Connect pins. Do not connect.

Table 9. Signal Descriptions

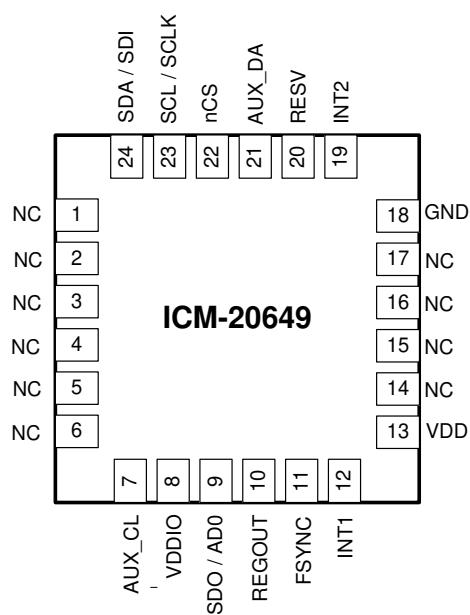


Figure 3. Pin out Diagram for ICM-20649 3.0x3.0x0.9 mm QFN

4.2 TYPICAL OPERATING CIRCUIT

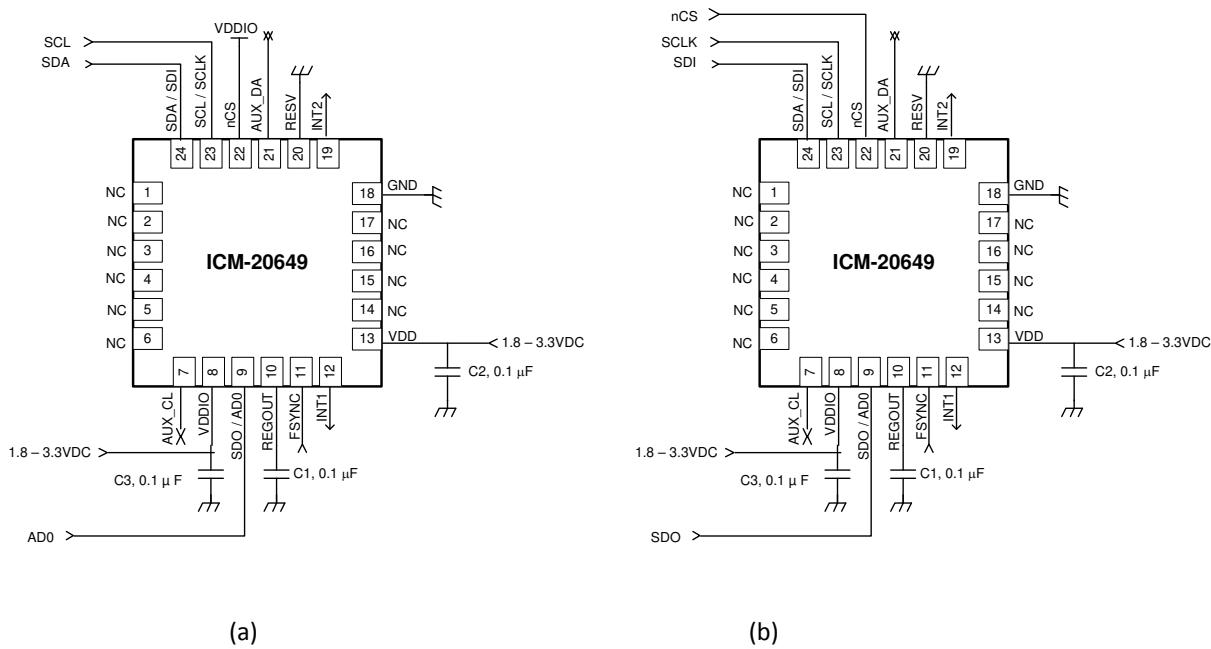


Figure 4. ICM-20649 Application Schematic (a) I²C operation (b) SPI operation

4.3 BILL OF MATERIALS FOR EXTERNAL COMPONENTS

Component	Label	Specification	Quantity
Regulator Filter Capacitor	C1	Ceramic, X7R, 0.1 µF ±10%	1
VDD Bypass Capacitor	C2	Ceramic, X7R, 0.1 µF ±10%	1
VDDIO Bypass Capacitor	C3	Ceramic, X7R, 0.1 µF ±10%	1

Table 10. Bill of Materials

4.4 BLOCK DIAGRAM

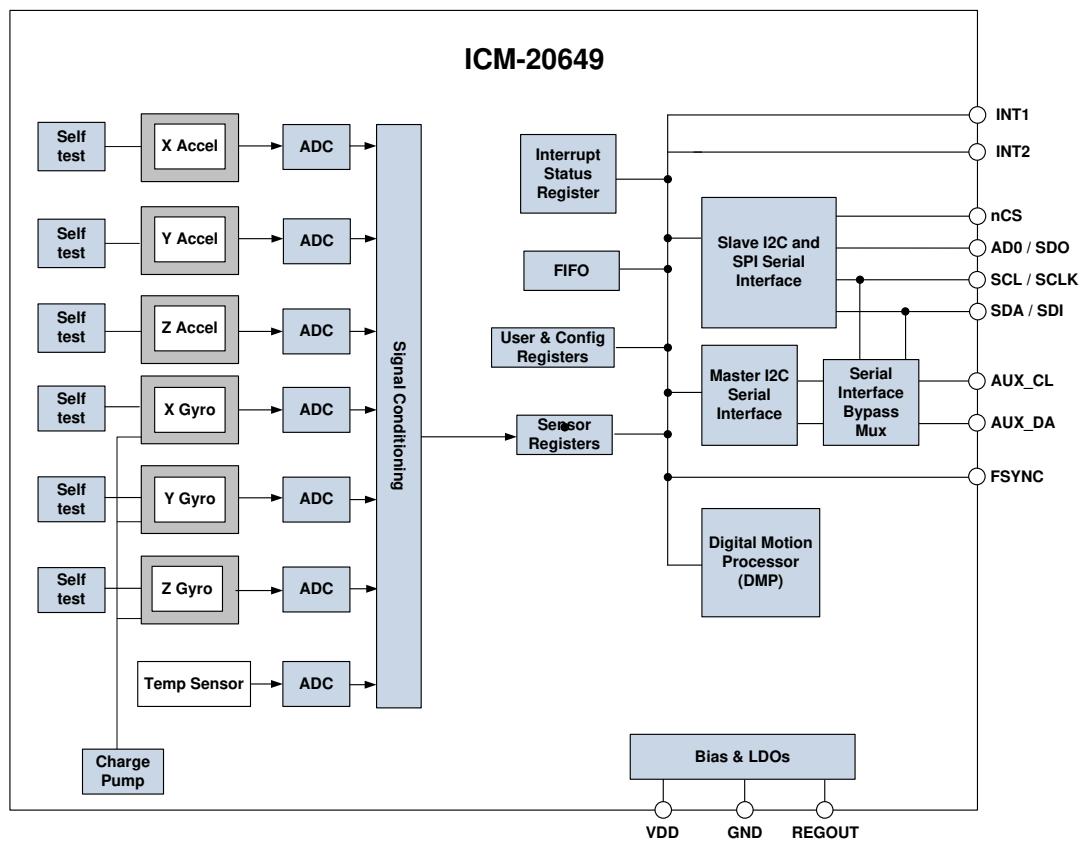


Figure 5. ICM-20649 Block Diagram

4.5 OVERVIEW

The ICM-20649 is comprised of the following key blocks and functions:

- Three-axis MEMS rate gyroscope sensor with 16-bit ADCs and signal conditioning
- Three-axis MEMS accelerometer sensor with 16-bit ADCs and signal conditioning
- Digital Motion Processor (DMP) engine
- Primary I²C and SPI serial communications interfaces
- Auxiliary I²C serial interface
- Self-Test
- Clocking
- Sensor Data Registers
- FIFO
- FSYNC
- Interrupts
- Digital-Output Temperature Sensor
- Bias and LDOs
- Charge Pump
- Power Modes

4.6 THREE-AXIS MEMS GYROSCOPE WITH 16-BIT ADCS AND SIGNAL CONDITIONING

The ICM-20649 consists of three independent vibratory MEMS rate gyroscopes, which detect rotation about the X-, Y-, and Z- Axes. When the gyros are rotated about any of the sense axes, the Coriolis Effect causes a vibration that is detected by a capacitive pickoff. The resulting signal is amplified, demodulated, and filtered to produce a voltage that is proportional to the angular rate. This voltage is digitized using individual on-chip 16-bit Analog-to-Digital Converters (ADCs) to sample each axis. The full-scale range of the gyro sensors may be digitally programmed to ± 500 , ± 1000 , ± 2000 , or ± 4000 degrees per second (dps).

4.7 THREE-AXIS MEMS ACCELEROMETER WITH 16-BIT ADCS AND SIGNAL CONDITIONING

The ICM-20649's 3-Axis accelerometer uses separate proof masses for each axis. Acceleration along a particular axis induces displacement on the corresponding proof mass, and capacitive sensors detect the displacement differentially. The ICM-20649's architecture reduces the accelerometers' susceptibility to fabrication variations as well as to thermal drift. When the device is placed on a flat surface, it will measure 0g on the X- and Y-axes and +1g on the Z-axis. The accelerometers' scale factor is calibrated at the factory and is nominally independent of supply voltage. Each sensor has a dedicated sigma-delta ADC for providing digital outputs. The full scale range of the digital output can be adjusted to $\pm 4g$, $\pm 8g$, $\pm 16g$, or $\pm 30g$.

4.8 DIGITAL MOTION PROCESSOR

The embedded Digital Motion Processor (DMP) within the ICM-20649 offloads computation of motion processing algorithms from the host processor. The DMP acquires data from accelerometers, gyroscopes, and additional third party sensors such as magnetometers, and processes the data. The resulting data can be read from the FIFO. The DMP has access to the external pins, which can be used for generating interrupts.

The purpose of the DMP is to offload both timing requirements and processing power from the host processor. Typically, motion processing algorithms should be run at a high rate, often around 200 Hz, in order to provide accurate results with low latency. This is required even if the application updates at a much lower rate; for example, a low power user interface may update as slowly as 5 Hz, but the motion processing should still run at 200 Hz. The DMP can be used to minimize power, simplify timing, simplify the software architecture, and save valuable MIPS on the host processor for use in applications.

The DMP is optimized for Android Lollipop support.

4.9 PRIMARY I²C AND SPI SERIAL COMMUNICATIONS INTERFACES

The ICM-20649 communicates to a system processor using either a SPI or an I²C serial interface. The ICM-20649 always acts as a slave when communicating to the system processor. The LSB of the I²C slave address is set by pin 1 (A0).

4.9.1 ICM-20649 Solution Using I²C Interface

In Figure 6, the system processor is an I²C master to the ICM-20649. In addition, the ICM-20649 is an I²C master to the optional external compass sensor. The ICM-20649 has limited capabilities as an I²C Master, and depends on the system processor to manage the initial configuration of any auxiliary sensors. The ICM-20649 has an interface bypass multiplexer, which connects the system processor I²C bus pins 23 and 24 (SCL and SDA) directly to the auxiliary sensor I²C bus pins 7 and 21 (AUX_CL and AUX_DA).

Once the auxiliary sensors have been configured by the system processor, the interface bypass multiplexer should be disabled so that the ICM-20649 auxiliary I²C master can take control of the sensor I²C bus and gather data from the auxiliary sensors.

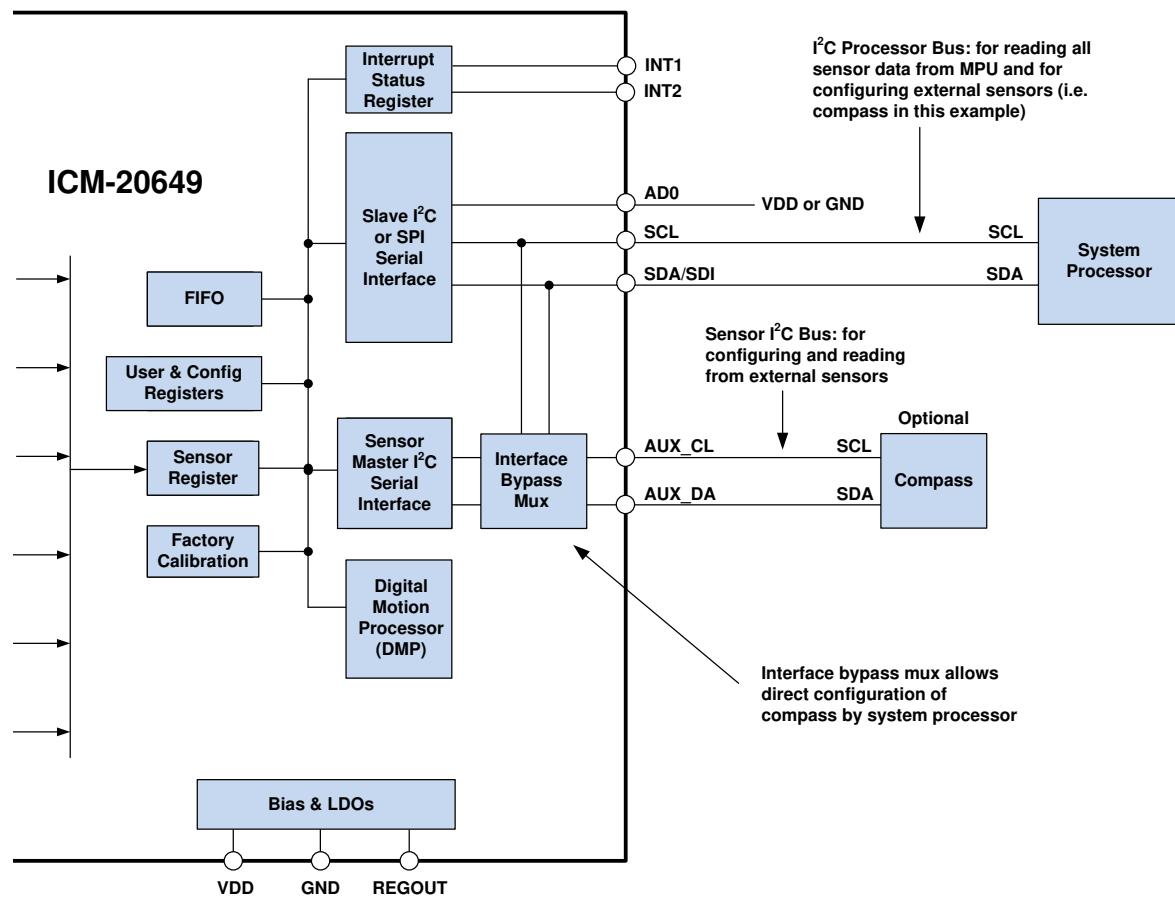


Figure 6. ICM-20649 Solution Using I²C Interface

4.9.2 ICM-20649 Solution Using SPI Interface

In Figure 7, the system processor is an SPI master to the ICM-20649. Pins 9, 22, 23, and 24 are used to support the SDO, nCS, SCLK, and SDI signals for SPI communications. Because these SPI pins are shared with the I²C slave pins (9, 23 and 24), the system processor cannot access the auxiliary I²C bus through the interface bypass multiplexer, which connects the processor I²C interface pins to the sensor I²C interface pins. Since the ICM-20649 has limited capabilities as an I²C Master, and depends on the system processor to manage the initial configuration of any auxiliary sensors, another method must be used for programming the sensors on the auxiliary sensor I²C bus pins 7 and 21 (AUX_CL and AUX_DA).

When using SPI communications between the ICM-20649 and the system processor, configuration of devices on the auxiliary I²C sensor bus can be achieved by using I²C Slaves 0-4 to perform read and write transactions on any device and register on the auxiliary I²C bus. The I²C Slave 4 interface can be used to perform only single byte read and write transactions. Once the external sensors have been configured, the ICM-20649 can perform single or multi-byte reads using the sensor I²C bus. The read results from the Slave 0-3 controllers can be written to the FIFO buffer as well as to the external sensor registers.

For more information regarding the control of the ICM-20649's auxiliary I²C interface, please refer to the ICM-20649 Register Map and Register Descriptions sections.

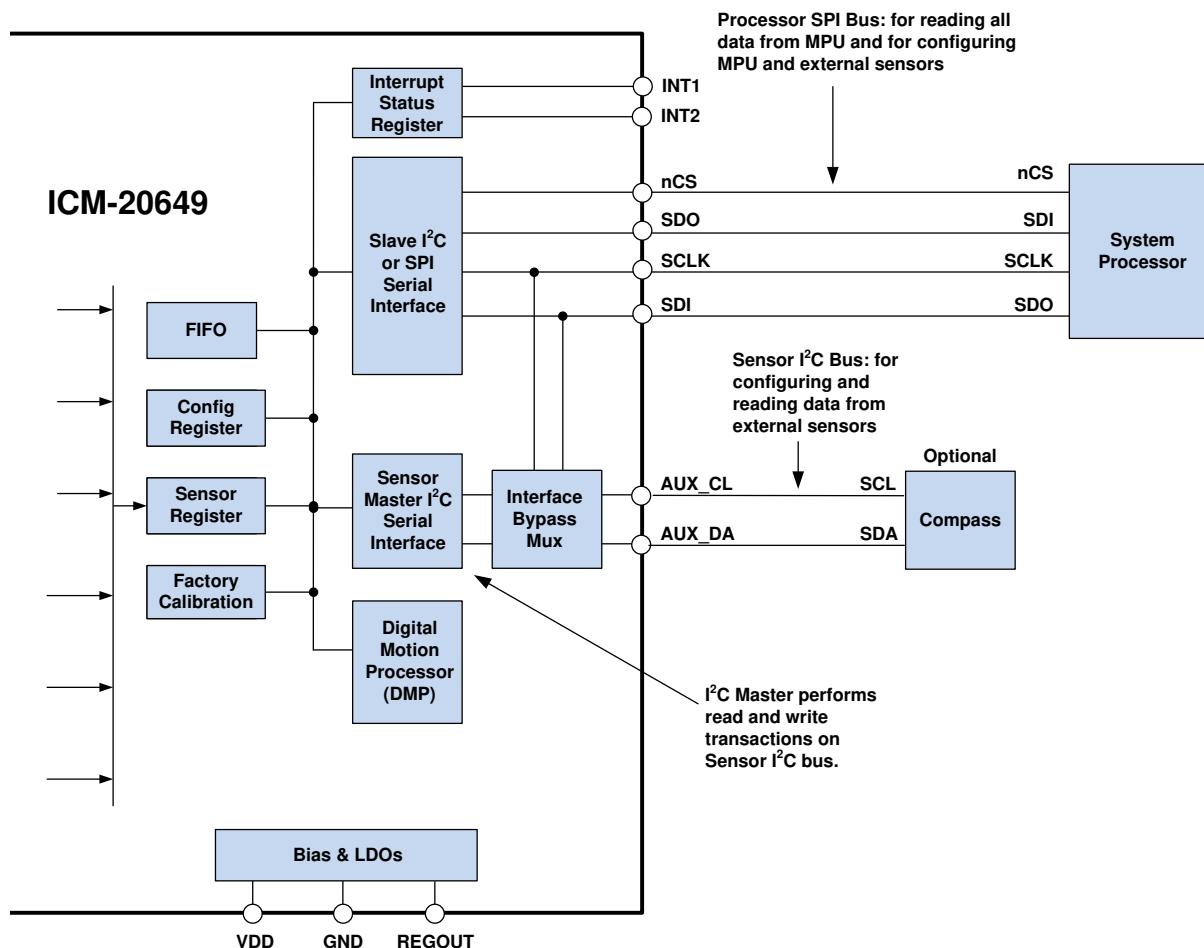


Figure 7. ICM-20649 Solution Using SPI Interface