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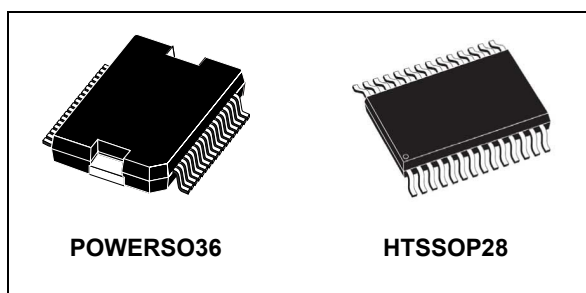
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# Fully integrated microstepping motor driver with motion engine and SPI

Datasheet - production data



## Features

- Operating voltage: 8 - 45 V
- 7.0 A out peak current (3.0 A<sub>r.m.s.</sub>)
- Low R<sub>DS(on)</sub> Power MOSFETs
- Programmable speed profile and positioning
- Programmable power MOS slew rate
- Up to 1/128 microstepping
- Sensorless stall detection
- SPI interface
- Low quiescent and standby currents
- Programmable non-dissipative overcurrent protection on high and low-side
- Two-levels of overtemperature protection

## Applications

- Bipolar stepper motors

## Description

The L6470 device, realized in analog mixed signal technology, is an advanced fully integrated solution suitable for driving two-phase bipolar stepper motors with microstepping. It integrates a dual low R<sub>DS(on)</sub> DMOS full bridge with all of the power switches equipped with an accurate on-chip current sensing circuitry suitable for non-dissipative current control and overcurrent protection. Thanks to a unique control system, a true 1/128 steps resolution is achieved. The digital control core can generate user defined motion profiles with acceleration, deceleration, speed or target position, easily programmed through a dedicated registers set. All commands and data registers, including those used to set analogue values (i.e. current control value, current protection trip point, deadtime, PWM frequency, etc.) are sent through a standard 5-Mbit/s SPI. A very rich set of protections (thermal, low bus voltage, overcurrent, motor stall) allows the design of a fully protected application, as required by the most demanding motor control applications.

**Table 1. Device summary**

Order codes	Package	Packaging
L6470H	HTSSOP28	Tube
L6470HTR	HTSSOP28	Tape and reel
L6470PD	POWERSO36	Tube
L6470PDTR	POWERSO36	Tape and reel

# Contents

- 1      Block diagram ..... 8**
- 2      Electrical data ..... 9**
  - 2.1 Absolute maximum ratings ..... 9
  - 2.2 Recommended operating conditions ..... 10
  - 2.3 Thermal data ..... 10
- 3      Electrical characteristics ..... 11**
- 4      Pin connection ..... 16**
  - Pin list ..... 17
- 5      Typical applications ..... 19**
- 6      Functional description ..... 21**
  - 6.1 Device power-up ..... 21
  - 6.2 Logic I/O ..... 21
  - 6.3 Charge pump ..... 21
  - 6.4 Microstepping ..... 22
    - Automatic full-step mode ..... 23
  - 6.5 Absolute position counter ..... 23
  - 6.6 Programmable speed profiles ..... 23
  - 6.7 Motor control commands ..... 24
    - 6.7.1 Constant speed commands ..... 24
    - 6.7.2 Positioning commands ..... 24
    - 6.7.3 Motion commands ..... 25
    - 6.7.4 Stop commands ..... 25
    - 6.7.5 Step-clock mode ..... 26
    - 6.7.6 GoUntil and ReleaseSW commands ..... 27
  - 6.8 Internal oscillator and oscillator driver ..... 27
    - 6.8.1 Internal oscillator ..... 28
    - 6.8.2 External clock source ..... 28
  - 6.9 Overcurrent detection ..... 29

6.10	Undervoltage lockout (UVLO)	30
6.11	Thermal warning and thermal shutdown	30
6.12	Reset and standby	30
6.13	External switch (SW pin)	31
6.14	Programmable DMOS slew rate, deadtime and blanking time	31
6.15	Integrated analog-to-digital converter	32
6.16	Internal voltage regulator	32
6.17	BUSY\SYNC pin	32
6.17.1	BUSY operation mode	33
6.17.2	SYNC operation mode	33
6.18	FLAG pin	33
<b>7</b>	<b>Phase current control</b>	<b>34</b>
7.1	PWM sinewave generators	34
7.2	Sensorless stall detection	35
7.3	Low speed optimization	35
7.4	BEMF compensation	36
7.5	Motor supply voltage compensation	36
7.6	Winding resistance thermal drift compensation	37
<b>8</b>	<b>Serial interface</b>	<b>38</b>
<b>9</b>	<b>Programming manual</b>	<b>40</b>
9.1	Registers and flags description	40
9.1.1	ABS_POS	41
9.1.2	EL_POS	41
9.1.3	MARK	42
9.1.4	SPEED	42
9.1.5	ACC	42
9.1.6	DEC	43
9.1.7	MAX_SPEED	43
9.1.8	MIN_SPEED	43
9.1.9	FS_SPD	44
9.1.10	KVAL_HOLD, KVAL_RUN, KVAL_ACC and KVAL_DEC	44
9.1.11	INT_SPEED	45
9.1.12	ST_SLP	45

9.1.13	FN_SLP_ACC	45
9.1.14	FN_SLP_DEC	45
9.1.15	K_THERM	46
9.1.16	ADC_OUT	46
9.1.17	OCD_TH	47
9.1.18	STALL_TH	47
9.1.19	STEP_MODE	47
9.1.20	ALARM_EN	49
9.1.21	CONFIG	49
9.1.22	STATUS	55
<b>9.2</b>	<b>Application commands</b>	<b>56</b>
9.2.1	Command management	58
9.2.2	Nop	58
9.2.3	SetParam (PARAM, VALUE)	59
9.2.4	GetParam (PARAM)	59
9.2.5	Run (DIR, SPD)	60
9.2.6	StepClock (DIR)	60
9.2.7	Move (DIR, N_STEP)	61
9.2.8	GoTo (ABS_POS)	61
9.2.9	GoTo_DIR (DIR, ABS_POS)	62
9.2.10	GoUntil (ACT, DIR, SPD)	62
9.2.11	ReleaseSW (ACT, DIR)	63
9.2.12	GoHome	63
9.2.13	GoMark	63
9.2.14	ResetPos	64
9.2.15	ResetDevice	64
9.2.16	SoftStop	64
9.2.17	HardStop	65
9.2.18	SoftHiZ	65
9.2.19	HardHiZ	65
9.2.20	GetStatus	66
<b>10</b>	<b>Package information</b>	<b>67</b>
10.1	HTSSOP28 package information	68
10.2	POWERSO36 package information	70
<b>11</b>	<b>Revision history</b>	<b>72</b>

## List of tables

Table 1.	Device summary . . . . .	1
Table 2.	Absolute maximum ratings . . . . .	9
Table 3.	Recommended operating conditions . . . . .	10
Table 4.	Thermal data . . . . .	10
Table 5.	Electrical characteristics . . . . .	11
Table 6.	Pin description . . . . .	17
Table 7.	Typical application values . . . . .	19
Table 8.	CL values according to external oscillator frequency . . . . .	28
Table 9.	Register map . . . . .	40
Table 10.	EL_POS register . . . . .	41
Table 11.	MIN_SPEED register . . . . .	43
Table 12.	Voltage amplitude regulation registers . . . . .	44
Table 13.	Winding resistance thermal drift compensation coefficient . . . . .	46
Table 14.	ADC_OUT value and motor supply voltage compensation feature . . . . .	46
Table 15.	Overcurrent detection threshold . . . . .	47
Table 16.	Stall detection threshold . . . . .	47
Table 17.	STEP_MODE register . . . . .	47
Table 18.	Step mode selection . . . . .	48
Table 19.	SYNC output frequency . . . . .	48
Table 20.	SYNC signal source . . . . .	49
Table 21.	ALARM_EN register . . . . .	49
Table 22.	CONFIG register . . . . .	49
Table 23.	Oscillator management . . . . .	50
Table 24.	External switch hard stop interrupt mode . . . . .	51
Table 25.	Overcurrent event . . . . .	51
Table 26.	Programmable power bridge output slew rate values . . . . .	51
Table 27.	Motor supply voltage compensation enable . . . . .	51
Table 28.	PWM frequency: integer division factor . . . . .	52
Table 29.	PWM frequency: multiplication factor . . . . .	52
Table 30.	Available PWM frequencies [kHz]: 8-MHz oscillator frequency . . . . .	53
Table 31.	Available PWM frequencies [kHz]: 16-MHz oscillator frequency . . . . .	53
Table 32.	Available PWM frequencies [kHz]: 24-MHz oscillator frequency . . . . .	54
Table 33.	Available PWM frequencies [kHz]: 32-MHz oscillator frequency . . . . .	54
Table 34.	STATUS register . . . . .	55
Table 35.	STATUS register DIR bit . . . . .	55
Table 36.	STATUS register MOT_STATUS bits . . . . .	56
Table 37.	Application commands . . . . .	56
Table 38.	Nop command structure . . . . .	58
Table 39.	SetParam command structure . . . . .	59
Table 40.	GetParam command structure . . . . .	59
Table 41.	Run command structure . . . . .	60
Table 42.	Stepclock command structure . . . . .	60
Table 43.	Move command structure . . . . .	61
Table 44.	GoTo command structure . . . . .	61
Table 45.	GoTo_DIR command structure . . . . .	62
Table 46.	GoUntil command structure . . . . .	62
Table 47.	ReleaseSW command structure . . . . .	63
Table 48.	GoHome command structure . . . . .	63

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Table 49.	GoMark command structure . . . . .	63
Table 50.	ResetPos command structure . . . . .	64
Table 51.	ResetDevice command structure . . . . .	64
Table 52.	SoftStop command structure . . . . .	64
Table 53.	HardStop command structure . . . . .	65
Table 54.	SoftHiZ command structure . . . . .	65
Table 55.	HardHiZ command structure . . . . .	65
Table 56.	GetStatus command structure . . . . .	66
Table 57.	HTSSOP28 package mechanical data . . . . .	69
Table 58.	POWERSO36 package mechanical data . . . . .	71
Table 59.	Revision history . . . . .	72

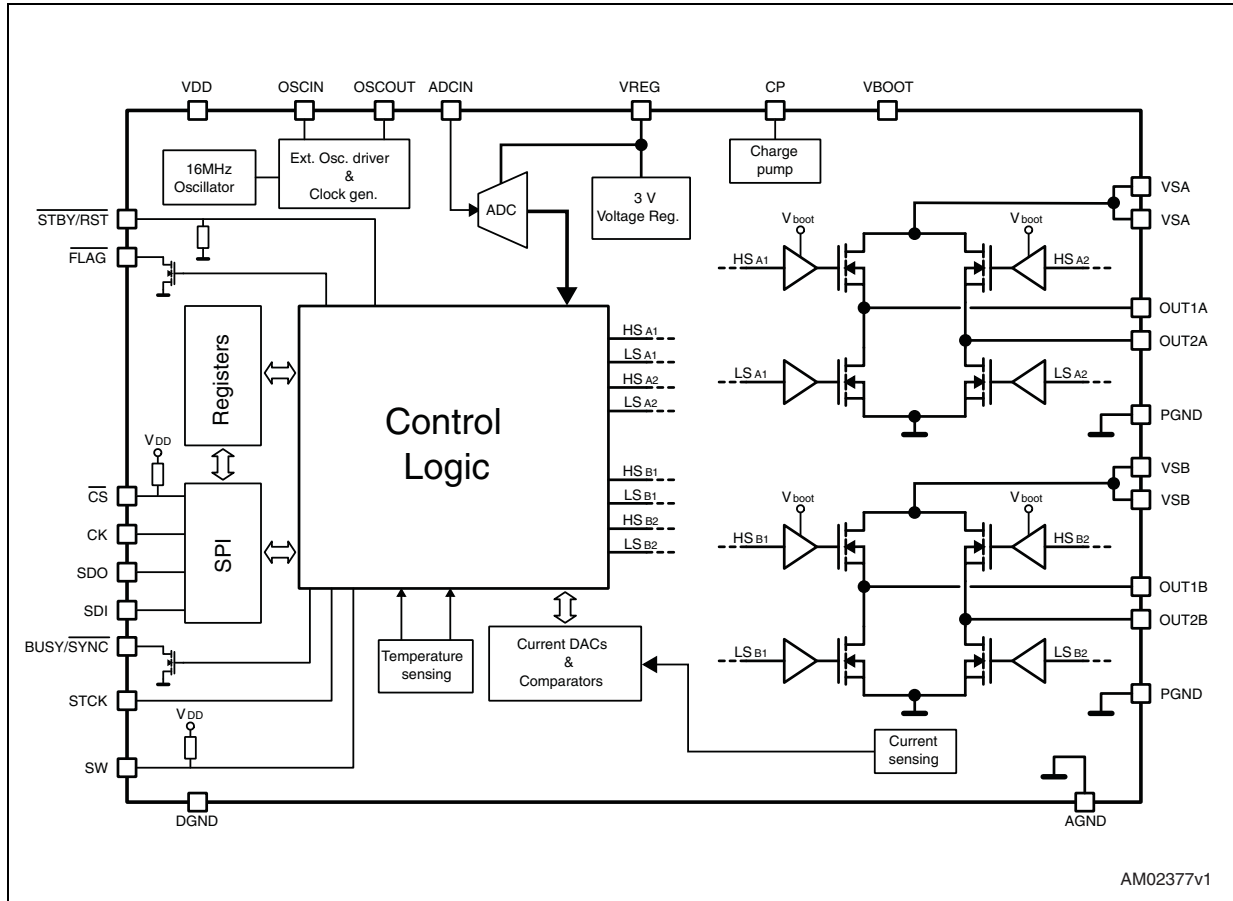
## List of figures

Figure 1.	Block diagram . . . . .	8
Figure 2.	HTSSOP28 pin connection (top view) . . . . .	16
Figure 3.	POWERSO36 pin connection (top view) . . . . .	16
Figure 4.	Bipolar stepper motor control application using L6470 . . . . .	20
Figure 5.	Charge pump circuitry . . . . .	22
Figure 6.	Normal mode and microstepping (128 microsteps) . . . . .	22
Figure 7.	Automatic full-step switching . . . . .	23
Figure 8.	Constant speed command examples . . . . .	24
Figure 9.	Positioning command examples . . . . .	25
Figure 10.	Motion command examples . . . . .	25
Figure 11.	OSCIN and OSCOUT pin configuration . . . . .	29
Figure 12.	External switch connection . . . . .	31
Figure 13.	Internal 3 V linear regulator . . . . .	32
Figure 14.	Current distortion and compensation . . . . .	35
Figure 15.	BEMF compensation curve . . . . .	36
Figure 16.	Motor supply voltage compensation circuit . . . . .	37
Figure 17.	SPI timings diagram . . . . .	38
Figure 18.	Daisy chain configuration . . . . .	39
Figure 19.	Command with 3-byte argument . . . . .	58
Figure 20.	Command with 3-byte response . . . . .	58
Figure 21.	Command response aborted . . . . .	58
Figure 22.	HTSSOP28 package outline . . . . .	68
Figure 23.	POWERSO36 package outline . . . . .	70



# 1 Block diagram

Figure 1. Block diagram



## 2 Electrical data

### 2.1 Absolute maximum ratings

Table 2. Absolute maximum ratings

Symbol	Parameter	Test condition	Value	Unit
$V_{DD}$	Logic interface supply voltage		5.5	V
$V_S$	Motor supply voltage	$V_{SA} = V_{SB} = V_S$	48	V
$V_{GND, diff}$	Differential voltage between AGND, PGND and DGND		$\pm 0.3$	V
$V_{boot}$	Bootstrap peak voltage		55	V
$V_{REG}$	Internal voltage regulator output pin and logic supply voltage		3.6	V
$V_{ADCIN}$	Integrated ADC input voltage range (ADCIN pin)		-0.3 to +3.6	V
$V_{OSC}$	OSCIN and OSCOUT pin voltage range		-0.3 to +3.6	V
$V_{out, diff}$	Differential voltage between $V_{SA}$ , OUT1 <sub>A</sub> , OUT2 <sub>A</sub> , PGND and $V_{SB}$ , OUT1 <sub>B</sub> , OUT2 <sub>B</sub> , PGND pins	$V_{SA} = V_{SB} = V_S$	48	V
$V_{LOGIC}$	Logic inputs voltage range		-0.3 to +5.5	V
$I_{out}^{(1)}$	R.m.s. output current		3	A
$I_{out, peak}^{(1)}$	Pulsed output current	$T_{PULSE} < 1 \text{ ms}$	7	A
$T_{OP}$	Operating junction temperature		-40 to 150	°C
$T_S$	Storage temperature range		-55 to 150	°C
$P_{tot}$	Total power dissipation ( $T_A = 25 \text{ °C}$ ) <sup>(2)</sup>		5	W

1. Maximum output current limit is related to metal connection and bonding characteristics. Actual limit must satisfy maximum thermal dissipation constraints.

2. HTSSOP28 mounted on EVAL6470H.

## 2.2 Recommended operating conditions

**Table 3. Recommended operating conditions**

Symbol	Parameter	Test condition	Value			Unit
$V_{DD}$	Logic interface supply voltage	3.3 V logic outputs		3.3		V
		5 V logic outputs		5		
$V_S$	Motor supply voltage	$V_{SA} = V_{SB} = V_S$	8		45	V
$V_{out\_diff}$	Differential voltage between $V_{SA}$ , OUT1 <sub>A</sub> , OUT2 <sub>A</sub> , PGND and $V_{SB}$ , OUT1 <sub>B</sub> , OUT2 <sub>B</sub> , PGND pins	$V_{SA} = V_{SB} = V_S$			45	V
$V_{REG,in}$	Logic supply voltage	$V_{REG}$ voltage imposed by external source	3.2	3.3		V
$V_{ADC}$	Integrated ADC input voltage (ADCIN pin)		0		$V_{REG}$	V

## 2.3 Thermal data

**Table 4. Thermal data**

Symbol	Parameter	Package	Typ.	Unit
$R_{thJA}$	Thermal resistance junction ambient	HTSSOP28 <sup>(1)</sup>	22	°C/W
		POWERSO36 <sup>(2)</sup>	12	

1. HTSSOP28 mounted on the EVAL6470H rev 1.0 board: a four-layer FR4 PCB with a dissipating copper surface of about 40 cm<sup>2</sup> on each layer and 15 via holes below the IC.
2. POWERSO36 mounted on the EVAL6470PD rev 1.0 board: a four-layer FR4 PCB with a dissipating copper surface of about 40 cm<sup>2</sup> on each layer and 22 via holes below the IC.

### 3 Electrical characteristics

$V_{SA} = V_{SB} = 36\text{ V}$ ;  $V_{DD} = 3.3\text{ V}$ ; internal 3 V regulator;  $T_J = 25\text{ °C}$ , unless otherwise specified.

**Table 5. Electrical characteristics**

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
<b>General</b>						
$V_{SthOn}$	$V_S$ UVLO turn-on threshold		7.5	8.2	8.9	V
$V_{SthOff}$	$V_S$ UVLO turn-off threshold		6.6	7.2	7.8	V
$V_{SthHyst}$	$V_S$ UVLO threshold hysteresis		0.7	1	1.3	V
$I_q$	Quiescent motor supply current	Internal oscillator selected; VREG = 3.3 V ext.; CP floating		0.5	0.65	mA
$T_{j(WRN)}$	Thermal warning temperature			130		°C
$T_{j(SD)}$	Thermal shutdown temperature			160		°C
<b>Charge pump</b>						
$V_{pump}$	Voltage swing for charge pump oscillator			10		V
$f_{pump,min}$	Minimum charge pump oscillator frequency <sup>(1)</sup>			660		kHz
$f_{pump,max}$	Maximum charge pump oscillator frequency <sup>(1)</sup>			800		kHz
$I_{boot}$	Average boot current	$f_{sw,A} = f_{sw,B} = 15.6\text{ kHz}$ POW_SR = '10'		1.1	1.4	mA
<b>Output DMOS transistor</b>						
$R_{DS(on)}$	High-side switch on-resistance	$T_J = 25\text{ °C}$ , $I_{out} = 3\text{ A}$		0.37		Ω
		$T_J = 125\text{ °C}$ , <sup>(2)</sup> $I_{out} = 3\text{ A}$		0.51		
$R_{DS(on)}$	Low-side switch on-resistance	$T_J = 25\text{ °C}$ , $I_{out} = 3\text{ A}$		0.18		
		$T_J = 125\text{ °C}$ , <sup>(2)</sup> $I_{out} = 3\text{ A}$		0.23		
$I_{DSS}$	Leakage current	OUT = $V_S$			3.1	mA
		OUT = GND	-0.3			
$t_r$	Rise time <sup>(3)</sup>	POW_SR = '00', $I_{out} = +1\text{ A}$		100		ns
		POW_SR = '00', $I_{out} = -1\text{ A}$		80		
		POW_SR = '11', $I_{out} = \pm 1\text{ A}$		100		
		POW_SR = '10', $I_{out} = \pm 1\text{ A}$		200		
		POW_SR = '01', $I_{out} = \pm 1\text{ A}$		300		

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
t <sub>f</sub>	Fall time <sup>(3)</sup>	POW_SR = '00'; I <sub>out</sub> = +1 A		90		ns
		POW_SR = '00'; I <sub>out</sub> = -1 A		110		
		POW_SR = '11', I <sub>out</sub> = ±1 A		110		
		POW_SR = '10', I <sub>out</sub> = ±1 A		260		
		POW_SR = '01', I <sub>load</sub> = ±1 A		375		
SR <sub>out_r</sub>	Output rising slew rate	POW_SR = '00', I <sub>out</sub> = +1 A		285		V/μs
		POW_SR = '00', I <sub>out</sub> = -1 A		360		
		POW_SR = '11', I <sub>out</sub> = ±1 A		285		
		POW_SR = '10', I <sub>out</sub> = ±1 A		150		
		POW_SR = '01', I <sub>out</sub> = ±1 A		95		
SR <sub>out_f</sub>	Output falling slew rate	POW_SR = '00', I <sub>out</sub> = +1 A		320		V/μs
		POW_SR = '00', I <sub>out</sub> = -1 A		260		
		POW_SR = '11', I <sub>out</sub> = ±1 A		260		
		POW_SR = '10', I <sub>out</sub> = ±1 A		110		
		POW_SR = '01', I <sub>out</sub> = ±1 A		75		
<b>Deadtime and blanking</b>						
t <sub>DT</sub>	Deadtime <sup>(1)</sup>	POW_SR = '00'		250		ns
		POW_SR = '11', f <sub>OSC</sub> = 16 MHz		375		
		POW_SR = '10', f <sub>OSC</sub> = 16 MHz		625		
		POW_SR = '01', f <sub>OSC</sub> = 16 MHz		875		
t <sub>blank</sub>	Blanking time <sup>(1)</sup>	POW_SR = '00'		250		ns
		POW_SR = '11', f <sub>OSC</sub> = 16 MHz		375		
		POW_SR = '10', f <sub>OSC</sub> = 16 MHz		625		
		POW_SR = '01', f <sub>OSC</sub> = 16 MHz		875		
<b>Source-drain diodes</b>						
V <sub>SD,HS</sub>	High-side diode forward ON voltage	I <sub>out</sub> = 1 A		1	1.1	V
V <sub>SD,LS</sub>	Low-side diode forward ON voltage	I <sub>out</sub> = 1 A		1	1.1	V
t <sub>rrHS</sub>	High-side diode reverse recovery time	I <sub>out</sub> = 1 A		30		ns
t <sub>rrLS</sub>	Low-side diode reverse recovery time	I <sub>out</sub> = 1 A		100		ns
<b>Logic inputs and outputs</b>						
V <sub>IL</sub>	Low logic level input voltage				0.8	V
V <sub>IH</sub>	High logic level input voltage		2			V
I <sub>IH</sub>	High logic level input current <sup>(4)</sup>	V <sub>IN</sub> = 5 V			1	μA
I <sub>IL</sub>	Low logic level input current <sup>(5)</sup>	V <sub>IN</sub> = 0 V	-1			μA

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
V <sub>OL</sub>	Low logic level output voltage <sup>(6)</sup>	V <sub>DD</sub> = 3.3 V, I <sub>OL</sub> = 4 mA			0.3	V
		V <sub>DD</sub> = 5 V, I <sub>OL</sub> = 4 mA			0.3	
V <sub>OH</sub>	High logic level output voltage	V <sub>DD</sub> = 3.3 V, I <sub>OH</sub> = 4 mA	2.4			V
		V <sub>DD</sub> = 5 V, I <sub>OH</sub> = 4 mA	4.7			
R <sub>PU</sub> R <sub>PD</sub>	CS pull-up and STBY pull-down resistors	$\overline{\text{CS}} = \text{GND};$ STBY/RST = 5 V	335	430	565	k $\Omega$
I <sub>logic</sub>	Internal logic supply current	3.3 V V <sub>REG</sub> externally supplied, internal oscillator		3.7	4.3	mA
I <sub>logic,STBY</sub>	Standby mode internal logic supply current	3.3 V V <sub>REG</sub> externally supplied		2	2.5	$\mu\text{A}$
f <sub>STCK</sub>	Step-clock input frequency				2	MHz
<b>Internal oscillator and external oscillator driver</b>						
f <sub>osc,i</sub>	Internal oscillator frequency	T <sub>j</sub> = 25 °C, V <sub>REG</sub> = 3.3 V	-3%	16	+3%	MHz
f <sub>osc,e</sub>	Programmable external oscillator frequency		8		32	MHz
V <sub>OSCOUTH</sub>	OSCOUT clock source high level voltage	Internal oscillator 3.3 V V <sub>REG</sub> externally supplied; I <sub>OSCOUT</sub> = 4 mA	2.4			V
V <sub>OSCOU<sub>L</sub></sub>	OSCOUT clock source low level voltage	Internal oscillator 3.3 V V <sub>REG</sub> externally supplied; I <sub>OSCOUT</sub> = 4 mA			0.3	V
t <sub>rOSCOUT</sub> t <sub>fOSCOUT</sub>	OSCOUT clock source rise and fall time	Internal oscillator			20	ns
t <sub>extosc</sub>	Internal to external oscillator switching delay			3		ms
t <sub>intosc</sub>	External to internal oscillator switching delay			1.5		$\mu\text{s}$
<b>SPI</b>						
f <sub>CK,MAX</sub>	Maximum SPI clock frequency <sup>(7)</sup>		5			MHz
t <sub>rCK</sub> t <sub>fCK</sub>	SPI clock rise and fall time <sup>(7)</sup>	C <sub>L</sub> = 30 pF			25	ns
t <sub>hCK</sub> t <sub>lCK</sub>	SPI clock high and low time <sup>(7)</sup>		75			ns
t <sub>setCS</sub>	Chip select setup time <sup>(7)</sup>		350			ns
t <sub>holCS</sub>	Chip select hold time <sup>(7)</sup>		10			ns
t <sub>disCS</sub>	Deselect time <sup>(7)</sup>		800			ns
t <sub>setSDI</sub>	Data input setup time <sup>(7)</sup>		25			ns
t <sub>holSDI</sub>	Data input hold time <sup>(7)</sup>		20			ns

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
$t_{enSDO}$	Data output enable time <sup>(7)</sup>				38	ns
$t_{disSDO}$	Data output disable time <sup>(7)</sup>				47	ns
$t_{vSDO}$	Data output valid time <sup>(7)</sup>				57	ns
$t_{holSDO}$	Data output hold time <sup>(7)</sup>		37			ns
<b>Switch input (SW)</b>						
$R_{PUSW}$	SW input pull-up resistance	SW = GND	60	85	110	k $\Omega$
<b>PWM modulators</b>						
$f_{PWM}$	Programmable PWM frequency <sup>(1)</sup>	$f_{osc} = 16$ MHz	2.8		62.5	kHz
		$f_{osc} = 32$ MHz	5.6		125	
$N_{PWM}$	PWM resolution			8		bit
<b>Stall detection</b>						
$I_{STALL,MAX}$	Maximum programmable stall threshold	STALL_TH = '1111111'		4		A
$I_{STALL,MIN}$	Minimum programmable stall threshold	STALL_TH = '0000000'		31.2 5		mA
$I_{STALL,RES}$	Programmable stall threshold resolution			31.2 5		mA
<b>Overcurrent protection</b>						
$I_{OCD,MAX}$	Maximum programmable overcurrent detection threshold	OCD_TH = '1111'		6		A
$I_{OCD,MIN}$	Minimum programmable overcurrent detection threshold	OCD_TH = '0000'		0.37 5		A
$I_{OCD,RES}$	Programmable overcurrent detection threshold resolution			0.37 5		A
$t_{OCD,Flag}$	OCD to flag signal delay time	$dl_{out}/dt = 350$ A/ $\mu$ s		650	1000	ns
$t_{OCD,SD}$	OCD to shutdown delay time	$dl_{out}/dt = 350$ A/ $\mu$ s POW_SR = '10'		600		ns
<b>Standby</b>						
$I_{qSTBY}$	Quiescent motor supply current in standby conditions	$V_S = 8$ V		26	34	$\mu$ A
		$V_S = 36$ V		30	36	
$t_{STBY,min}$	Minimum standby time			10		$\mu$ s
$t_{logicwu}$	Logic power-on and wake-up time			38	45	$\mu$ s
$t_{cpwu}$	Charge pump power-on and wake-up time	Power bridges disabled, $C_p = 10$ nF, $C_{boot} = 220$ nF		650		$\mu$ s
<b>Internal voltage regulator</b>						
$V_{REG}$	Voltage regulator output voltage		2.9	3	3.2	V
$I_{REG}$	Voltage regulator output current				40	mA

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
$V_{REG, drop}$	Voltage regulator output voltage drop	$I_{REG} = 40 \text{ mA}$		50		mV
$I_{REG, STBY}$	Voltage regulator standby output current				10	mA
<b>Integrated analog-to-digital converter</b>						
$N_{ADC}$	Analog-to-digital converter resolution			5		bit
$V_{ADC, ref}$	Analog-to-digital converter reference voltage			$V_{REG}$		V
$f_S$	Analog-to-digital converter sampling frequency			$f_{PWM}$		kHz

1. Accuracy depends on oscillator frequency accuracy.
2. Tested at 25 °C in a restricted range and guaranteed by characterization.
3. Rise and fall time depends on motor supply voltage value. Refer to  $SR_{out}$  values in order to evaluate the actual rise and fall time.
4. Not valid for  $\overline{STBY/RST}$  pin which has internal pull-down resistor.
5. Not valid for SW and CS pins which have internal pull-up resistors.
6.  $\overline{FLAG}$ ,  $\overline{BUSY}$  and SYNC open drain outputs included.
7. See [Figure 17 on page 38](#) – SPI timings diagram for details.



# 4 Pin connection

Figure 2. HTSSOP28 pin connection (top view)

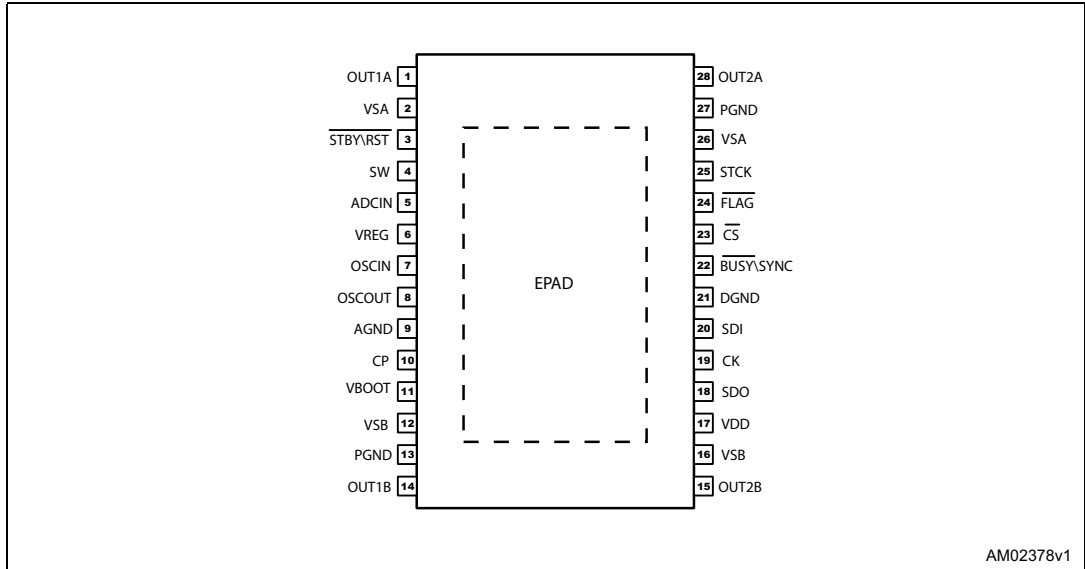
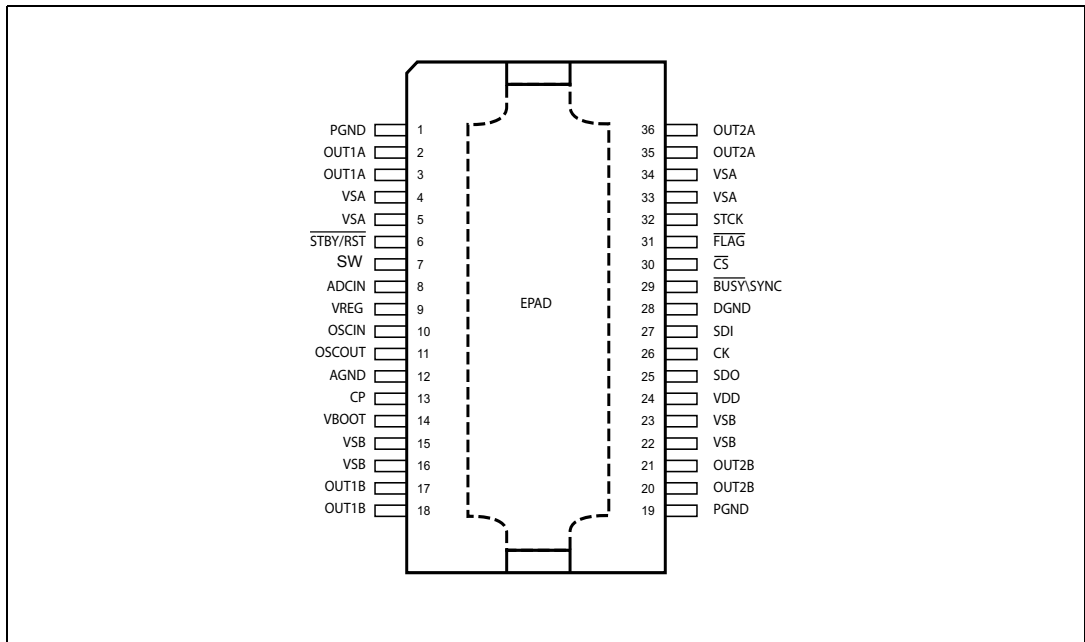


Figure 3. POWERSO36 pin connection (top view)



## Pin list

Table 6. Pin description

No.		Name	Type	Function
HTSSOP	POWERSO			
17	24	VDD	Power	Logic outputs supply voltage (pull-up reference)
6	9	VREG	Power	Internal 3 V voltage regulator output and 3.3 V external logic supply
7	10	OSCIN	Analog input	Oscillator pin 1. To connect an external oscillator or clock source. If this pin is unused, it should be left floating.
8	11	OSCOU	Analog output	Oscillator pin 2. To connect an external oscillator. When the internal oscillator is used this pin can supply 2/4/8/16 MHz. If this pin is unused, it should be left floating.
10	13	CP	Output	Charge pump oscillator output
11	14	VBOOT	Supply voltage	Bootstrap voltage needed for driving the high-side power DMOS of both bridges (A and B)
5	8	ADCIN	Analog input	Internal analog-to-digital converter input
2, 26	4, 5, 33, 34	VSA	Power supply	Full bridge A power supply pin. It must be connected to VSB.
12, 16	15, 16, 22, 23	VSB	Power supply	Full bridge B power supply pin. It must be connected to VSA.
27, 13	1, 19	PGND	Ground	Power ground pin
1	2, 3	OUT1A	Power output	Full bridge A output 1
28	35, 36	OUT2A	Power output	Full bridge A output 2
14	17, 18	OUT1B	Power output	Full bridge B output 1
15	20, 21	OUT2B	Power output	Full bridge B output 2
9	12	AGND	Ground	Analog ground.
4	7	SW	Logical input	External switch input pin. If not used the pin should be connected to VDD.
21	28	DGND	Ground	Digital ground
22	29	$\overline{\text{BUSY}}/\text{SYNC}$	Open drain output	By default, this BUSY pin is forced low when the device is performing a command. Otherwise the pin can be configured to generate a synchronization signal.
18	25	SDO	Logic output	Data output pin for serial interface
20	27	SDI	Logic input	Data input pin for serial interface
19	26	CK	Logic input	Serial interface clock
23	30	$\overline{\text{CS}}$	Logic input	Chip select input pin for serial interface

Table 6. Pin description (continued)

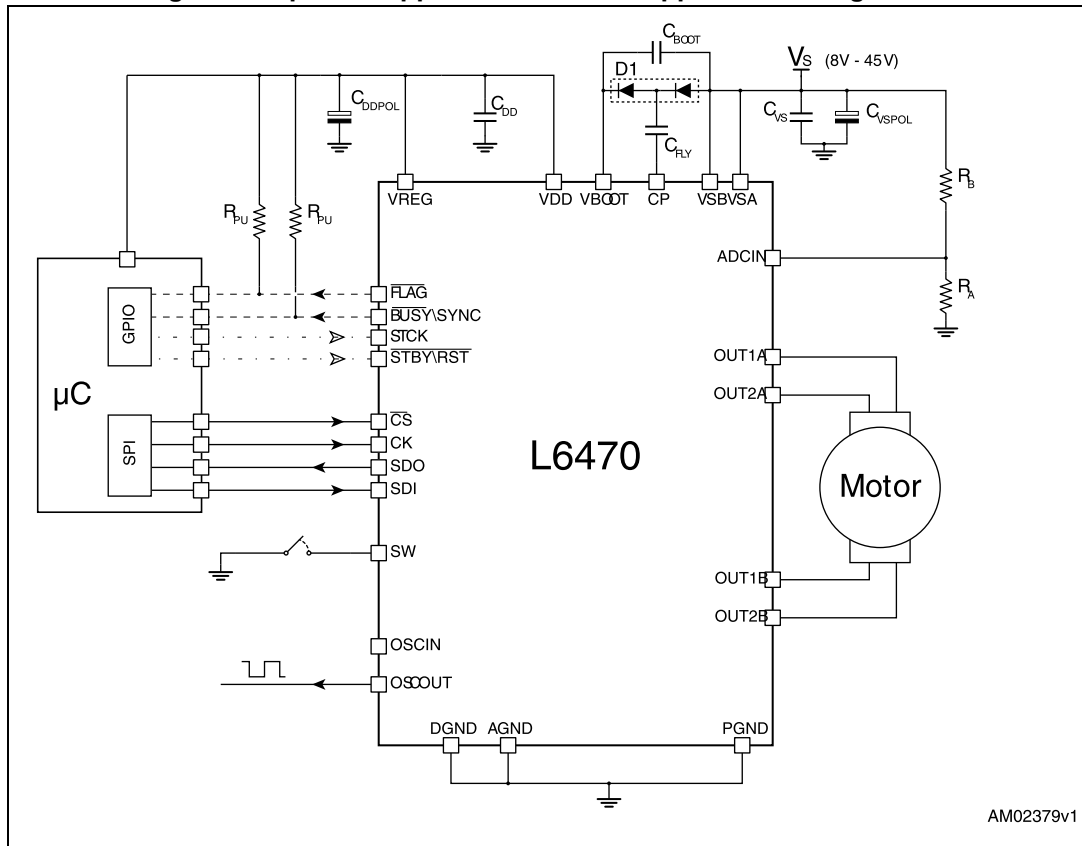
No.		Name	Type	Function
HTSSOP	POWERSO			
24	31	$\overline{\text{FLAG}}$	Open drain output	Status flag pin. An internal open drain transistor can pull the pin to GND when a programmed alarm condition occurs (step loss, OCD, thermal pre-warning or shutdown, UVLO, wrong command, non-performable command)
3	6	$\overline{\text{STBY}}\overline{\text{RST}}$	Logic input	Standby and reset pin. LOW logic level resets the logic and puts the device into Standby mode. If not used, it should be connected to VDD.
25	32	STCK	Logic input	Step-clock input
EPAD	EPAD	Exposed pad	Ground	Internally connected to PGND, AGND and DGND pins

## 5 Typical applications

Table 7. Typical application values

Name	Value
$C_{VS}$	220 nF
$C_{VSPOL}$	100 $\mu$ F
$C_{REG}$	100 nF
$C_{REGPOL}$	47 $\mu$ F
$C_{DD}$	100 nF
$C_{DDPOL}$	10 $\mu$ F
D1	Charge pump diodes
$C_{BOOT}$	220 nF
$C_{FLY}$	10 nF
$R_{PU}$	39 k $\Omega$
$R_{SW}$	100 $\Omega$
$C_{SW}$	10 nF
$R_A$	2.7 k $\Omega$ ( $V_S = 36$ V)
$R_B$	62 k $\Omega$ ( $V_S = 36$ V)

Figure 4. Bipolar stepper motor control application using L6470



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## 6 Functional description

### 6.1 Device power-up

At power-up end, the device state is the following:

- Registers are set to default
- Internal logic is driven by internal oscillator and a 2 MHz clock is provided by the OSCOUT pin
- Bridges are disabled (High Z)
- UVLO bit in the STATUS register is forced low (fail condition)
- FLAG output is forced low.

During power-up, the device is under reset (all logic IOs disabled and power bridges in high impedance state) until the following conditions are satisfied:

- $V_S$  is greater than  $V_{SthOn}$
- $V_{REG}$  is greater than  $V_{REGth} = 2.8$  V typical
- Internal oscillator is operative.

Any motion command makes the device exit from High Z state (HardStop and SoftStop included).

### 6.2 Logic I/O

Pins  $\overline{CS}$ , CK, SDI, STCK, SW and  $\overline{STBY}\overline{RST}$  are TTL/CMOS 3.3 V - 5 V compatible logic inputs.

Pin SDO is a TTL/CMOS compatible logic output. VDD pin voltage sets the logic output pin voltage range; when it is connected to VREG or 3.3 V external supply voltage, the output is 3.3 V compatible. When VDD is connected to a 5 V supply voltage, SDO is 5 V compatible.

VDD is not internally connected to  $V_{REG}$ , an external connection is always needed.

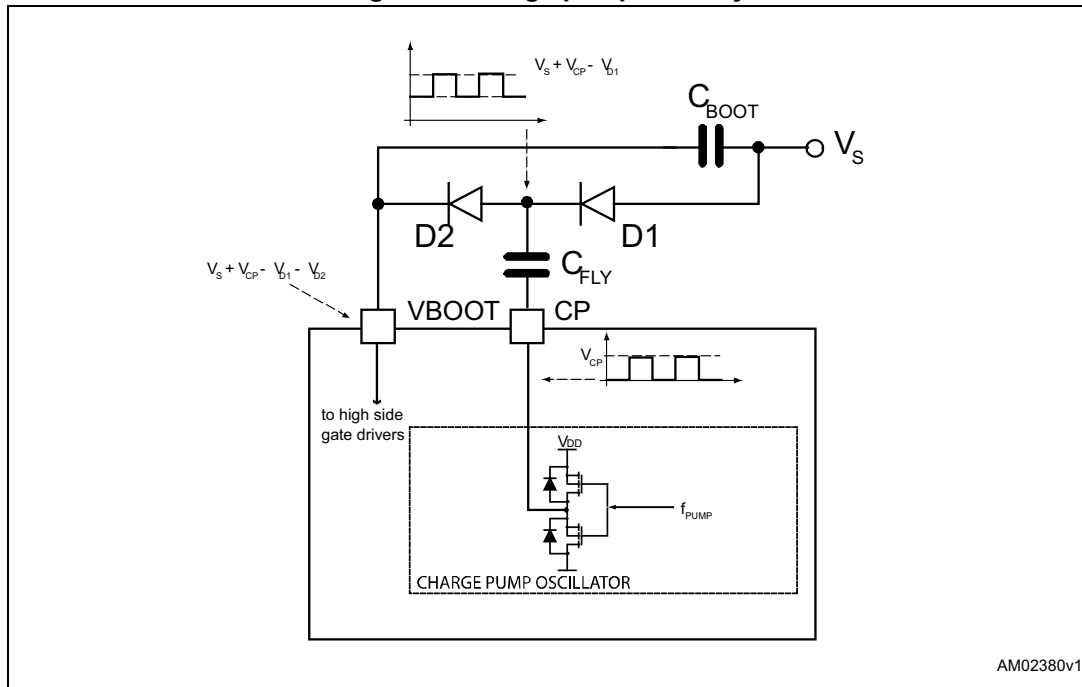
A 10  $\mu$ F capacitor should be connected to the VDD pin in order to obtain a proper operation.

Pins  $\overline{FLAG}$  and  $\overline{BUSY}\overline{SYNC}$  are open drain outputs.

### 6.3 Charge pump

To ensure the correct driving of the high-side integrated MOSFETs, a voltage higher than the motor power supply voltage needs to be applied to the VBOOT pin. The high-side gate driver supply voltage,  $V_{boot}$ , is obtained through an oscillator and a few external components realizing a charge pump (see [Figure 5](#)).

Figure 5. Charge pump circuitry



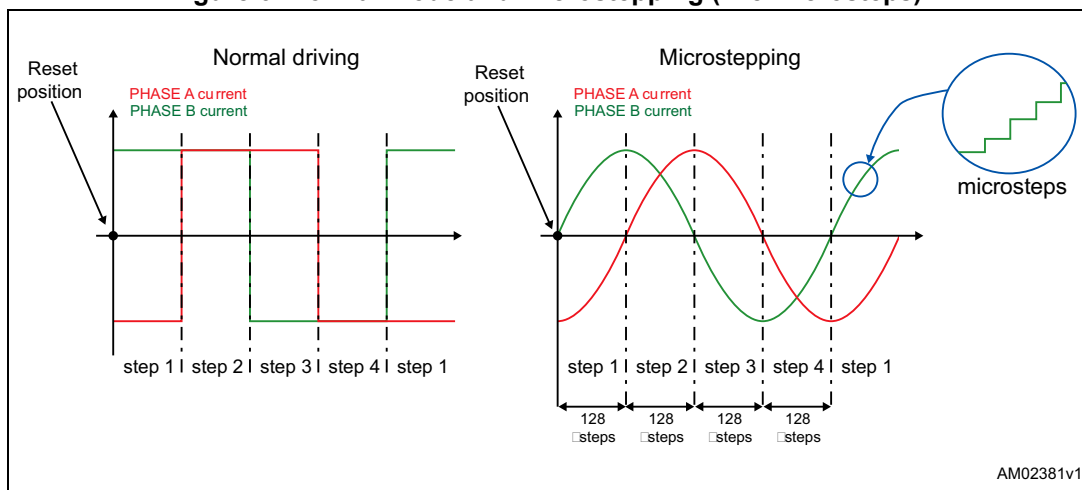
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### 6.4 Microstepping

The driver is able to divide the single step into up to 128 microsteps. Stepping mode can be programmed by the STEP\_SEL parameter in the STEP\_MODE register (see [Table 18 on page 48](#)).

Step mode can only be changed when bridges are disabled. Every time the step mode is changed the electrical position (i.e. the point of microstepping sinewave that is generated) is reset to zero and the absolute position counter value (see [Section 6.5](#)) becomes meaningless.

Figure 6. Normal mode and microstepping (128 microsteps)

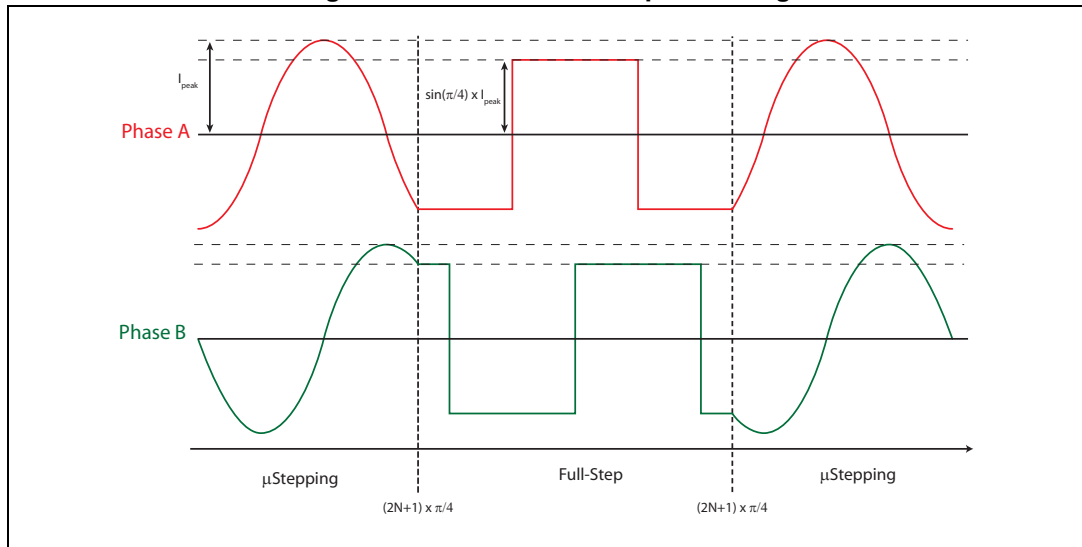


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## Automatic full-step mode

When motor speed is greater than a programmable full-step speed threshold, the L6470 device switches automatically to Full-step mode (see [Figure 7](#)); the driving mode returns to microstepping when motor speed decreases below the full-step speed threshold. The full-step speed threshold is set through the FS\_SPD register (see [Section 9.1.9 on page 44](#)).

**Figure 7. Automatic full-step switching**



## 6.5 Absolute position counter

An internal 22-bit register (ABS\_POS) records the motor motion according to the selected step mode; the stored value unit is equal to the selected step mode (full, half, quarter, etc.). The position range is from  $-2^{21}$  to  $+2^{21}-1$  ( $\mu$ steps (see [Section 9.1.1 on page 41](#))).

## 6.6 Programmable speed profiles

The user can easily program a customized speed profile defining independently acceleration, deceleration, maximum and minimum speed values by the ACC, DEC, MAX\_SPEED and MIN\_SPEED registers respectively (see [Section 9.1.5 on page 42](#), [Section 9.1.6 on page 43](#), [Section 9.1.7 on page 43](#) and [Section 9.1.8 on page 43](#)).

When a command is sent to the device, the integrated logic generates the microstep frequency profile that performs a motor motion compliant to speed profile boundaries.

All acceleration parameters are expressed in  $\text{step}/\text{tick}^2$  and all speed parameters are expressed in  $\text{step}/\text{tick}$ ; the unit of measurement does not depend on the selected step mode. Acceleration and deceleration parameters range from  $2^{-40}$  to  $(2^{12}-2) \cdot 2^{-40}$   $\text{step}/\text{tick}^2$  (equivalent to 14.55 to 59590  $\text{step}/\text{s}^2$ ).

The minimum speed parameter ranges from 0 to  $(2^{12}-1) \cdot 2^{-24}$   $\text{step}/\text{tick}$  (equivalent to 0 to 976.3  $\text{step}/\text{s}$ ).

The maximum speed parameter ranges from  $2^{-18}$  to  $(2^{10}-1) \cdot 2^{-18}$   $\text{step}/\text{tick}$  (equivalent to 15.25 to 15610  $\text{step}/\text{s}$ ).



## 6.7 Motor control commands

The L6470 device can accept different types of commands:

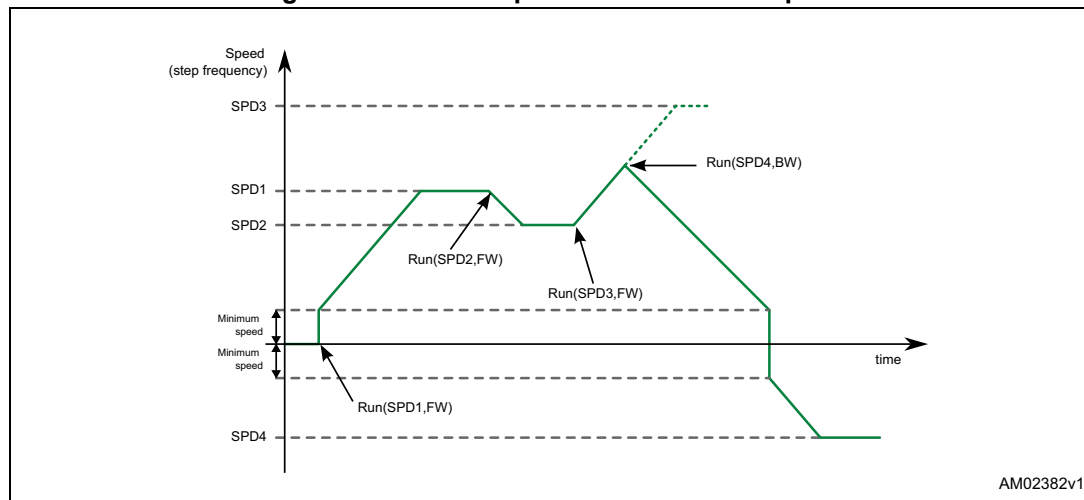
- constant speed commands (Run, GoUntil, ReleaseSW)
- absolute positioning commands (GoTo, GoTo\_DIR, GoHome, GoMark)
- motion commands (Move)
- stop commands (SoftStop, HardStop, SoftHiz, HardHiz).

For detailed command descriptions refer to [Section 9.2 on page 56](#).

### 6.7.1 Constant speed commands

A constant speed command produces a motion in order to reach and maintain a user-defined target speed starting from the programmed minimum speed (set in the MIN\_SPEED register) and with the programmed acceleration/deceleration value (set in the ACC and DEC registers). A new constant speed command can be requested anytime.

**Figure 8. Constant speed command examples**



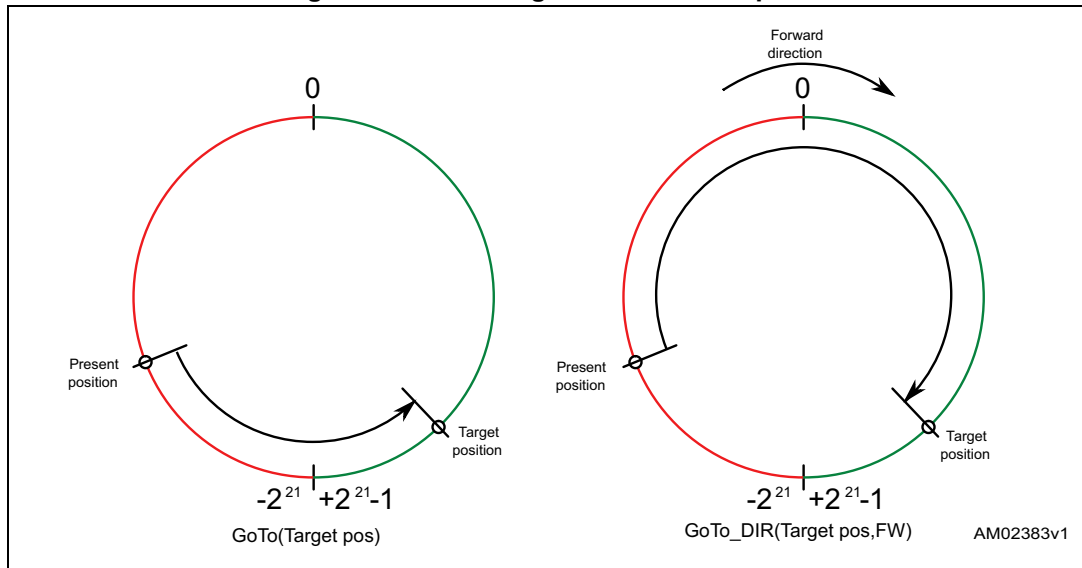
### 6.7.2 Positioning commands

An absolute positioning command produces a motion in order to reach a user-defined position that is sent to the device together with the command. The position can be reached performing the minimum path (minimum physical distance) or forcing a direction (see [Figure 9](#)).

The performed motor motion is compliant to programmed speed profile boundaries (acceleration, deceleration, minimum and maximum speed).

Note that with some speed profiles or positioning commands, the deceleration phase can start before the maximum speed is reached.

Figure 9. Positioning command examples



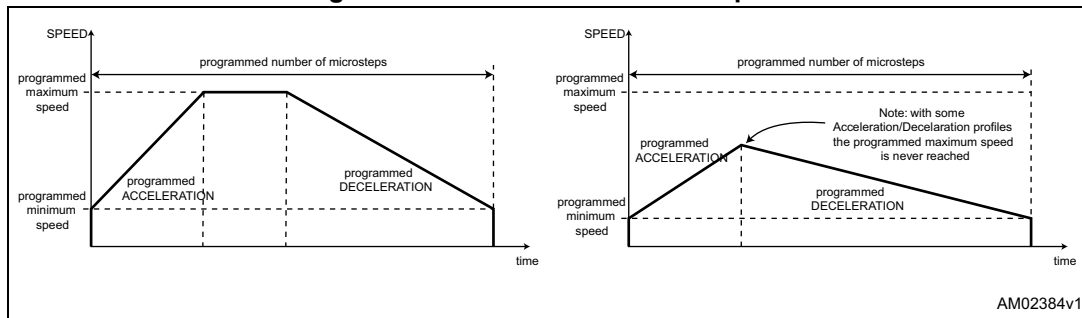
6.7.3 Motion commands

Motion commands produce a motion in order to perform a user-defined number of microsteps in a user-defined direction that are sent to the device together with the command (see Figure 10).

The performed motor motion is compliant to programmed speed profile boundaries (acceleration, deceleration, minimum and maximum speed).

Note that with some speed profiles or motion commands, the deceleration phase can start before the maximum speed is reached.

Figure 10. Motion command examples



6.7.4 Stop commands

A stop command forces the motor to stop. Stop commands can be sent anytime.

The SoftStop command causes the motor to decelerate with programmed deceleration value until the MIN\_SPEED value is reached and then stops the motor keeping the rotor position (a holding torque is applied).

The HardStop command stops the motor instantly, ignoring deceleration constraints and keeping the rotor position (a holding torque is applied).