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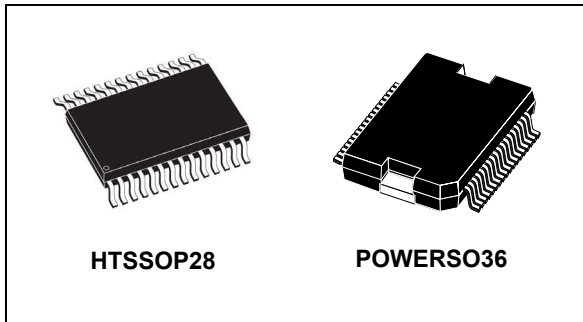
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Fully integrated microstepping motor driver

Datasheet - production data



Applications

- Bipolar stepper motor

Description

The L6472 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 $R_{DS(on)}$ 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 new current control, a 1/16 microstepping is achieved through an adaptive decay mode which outperforms traditional implementations. The digital control core can generate user defined motion profiles with acceleration, deceleration, speed or target position, easily programmed through a dedicated register set.

All application commands and data registers, including those used to set analog values (i.e.: current control value, current protection trip point, deadtime, etc.) are sent through a standard 5-Mbit/s SPI.

A very rich set of protections (thermal, low bus voltage, overcurrent) makes the L6472 device “bullet proof”, as required by the most demanding motor control applications.

Features

- Operating voltage: 8 - 45 V
- 7.0 A output peak current (3.0 A _{r.m.s.})
- Low $R_{DS(on)}$ power MOSFETs
- Programmable speed profile
- Programmable power MOSFET slew rate
- Up to 1/16 microstepping
- Predictive current control with adaptive decay
- Non dissipative current sensing
- SPI interface
- Low quiescent and standby currents
- Programmable non dissipative overcurrent protection on all power MOSFETs
- Two levels of overtemperature protection

Table 1. Device summary

Order codes	Package	Packing
L6472H	HTSSOP28	Tube
L6472HTR	HTSSOP28	Tape and reel
L6472PD	POWERSO36	Tube
L6472PDTR	POWERSO36	Tape and reel

Contents

- 1 Block diagram 8**
- 2 Electrical data 9**
 - 2.1 Absolute maximum ratings 9
 - 2.2 Recommended operating conditions 9
 - 2.3 Thermal data 10
- 3 Electrical characteristics 11**
- 4 Pin connection 16**
 - Pin list 17
- 5 Typical applications 19**
- 6 Functional description 20**
 - 6.1 Device power-up 20
 - 6.2 Logic I/O 20
 - 6.3 Charge pump 20
 - 6.4 Microstepping 21
 - Automatic full-step mode 22
 - 6.5 Absolute position counter 23
 - 6.6 Programmable speed profiles 23
 - 6.7 Motor control commands 23
 - 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 26
 - 6.8 Internal oscillator and oscillator driver 27
 - 6.8.1 Internal oscillator 27
 - 6.8.2 External clock source 27
 - 6.9 Overcurrent detection 28

6.10	Undervoltage lockout (UVLO)	29
6.11	Thermal warning and thermal shutdown	29
6.12	Reset and standby	29
6.13	External switch (SW pin)	30
6.14	Programmable DMOS slew rate, deadtime and blanking time	30
6.15	Integrated analog-to-digital converter	31
6.16	Internal voltage regulator	31
6.17	BUSY\SYNC pin	32
6.17.1	BUSY operation mode	32
6.17.2	SYNC operation mode	32
6.18	FLAG pin	32
7	Phase current control	33
7.1	Predictive current control	33
7.2	Auto-adjusted decay mode	34
7.3	Auto-adjusted fast decay during the falling steps	36
7.4	Torque regulation (output current amplitude regulation)	37
8	Serial interface	38
9	Programming manual	40
9.1	Register and flag 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	42
9.1.7	MAX_SPEED	43
9.1.8	MIN_SPEED	43
9.1.9	FS_SPD	44
9.1.10	TVAL_HOLD, TVAL_RUN, TVAL_ACC and TVAL_DEC	44
9.1.11	T_FAST	45
9.1.12	TON_MIN	45
9.1.13	TOFF_MIN	46
9.1.14	ADC_OUT	46

- 9.1.15 OCD_TH 47
- 9.1.16 STEP_MODE 47
- 9.1.17 ALARM_EN 49
- 9.1.18 CONFIG 49
- 9.1.19 STATUS 52
- 9.2 Application commands 54
 - 9.2.1 Command management 55
 - 9.2.2 NOP 56
 - 9.2.3 SetParam (PARAM, VALUE) 56
 - 9.2.4 GetParam (PARAM) 56
 - 9.2.5 Run (DIR, SPD) 57
 - 9.2.6 StepClock (DIR) 57
 - 9.2.7 Move (DIR, N_STEP) 58
 - 9.2.8 GoTo (ABS_POS) 58
 - 9.2.9 GoTo_DIR (DIR, ABS_POS) 59
 - 9.2.10 GoUntil (ACT, DIR, SPD) 59
 - 9.2.11 ReleaseSW (ACT, DIR) 60
 - 9.2.12 GoHome 60
 - 9.2.13 GoMark 61
 - 9.2.14 ResetPos 61
 - 9.2.15 ResetDevice 61
 - 9.2.16 SoftStop 62
 - 9.2.17 HardStop 62
 - 9.2.18 SoftHiZ 62
 - 9.2.19 HardHiZ 63
 - 9.2.20 GetStatus 63
- 10 Package information 64**
 - 10.1 HTSSOP28 package information 65
 - 10.2 POWERSO36 package information 67
- 11 Revision history 69**

List of tables

Table 1.	Device summary	1
Table 2.	Absolute maximum ratings	9
Table 3.	Recommended operating conditions	9
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	27
Table 9.	Register map	40
Table 10.	EL_POS register	41
Table 11.	MIN_SPEED register	43
Table 12.	Torque regulation by TVAL_HOLD, TVAL_ACC, TVAL_DEC and TVAL_RUN registers	44
Table 13.	T_FAST register	45
Table 14.	Maximum fast decay times	45
Table 15.	Minimum ON time	45
Table 16.	Minimum OFF time	46
Table 17.	ADC_OUT value and torque regulation feature	46
Table 18.	Overcurrent detection threshold	47
Table 19.	STEP_MODE register	47
Table 20.	Step mode selection	47
Table 21.	SYNC output frequency	48
Table 22.	SYNC signal source	48
Table 23.	ALARM_EN register	49
Table 24.	CONFIG register	49
Table 25.	Oscillator management	50
Table 26.	External switch hard stop interrupt mode	50
Table 27.	Overcurrent event	51
Table 28.	Programmable power bridge output slew rate values	51
Table 29.	External torque regulation enable	51
Table 30.	Switching period	51
Table 31.	STATUS register	52
Table 32.	STATUS register DIR bit	52
Table 33.	STATUS register MOT_STATUS bits	53
Table 34.	Application commands	54
Table 35.	NOP command structure	56
Table 36.	SetParam command structure	56
Table 37.	GetParam command structure	56
Table 38.	Run command structure	57
Table 39.	StepClock command structure	57
Table 40.	Move command structure	58
Table 41.	GoTo command structure	58
Table 42.	GoTo_DIR command structure	59
Table 43.	GoUntil command structure	59
Table 44.	ReleaseSW command structure	60
Table 45.	GoHome command structure	60
Table 46.	GoMark command structure	61
Table 47.	ResetPos command structure	61

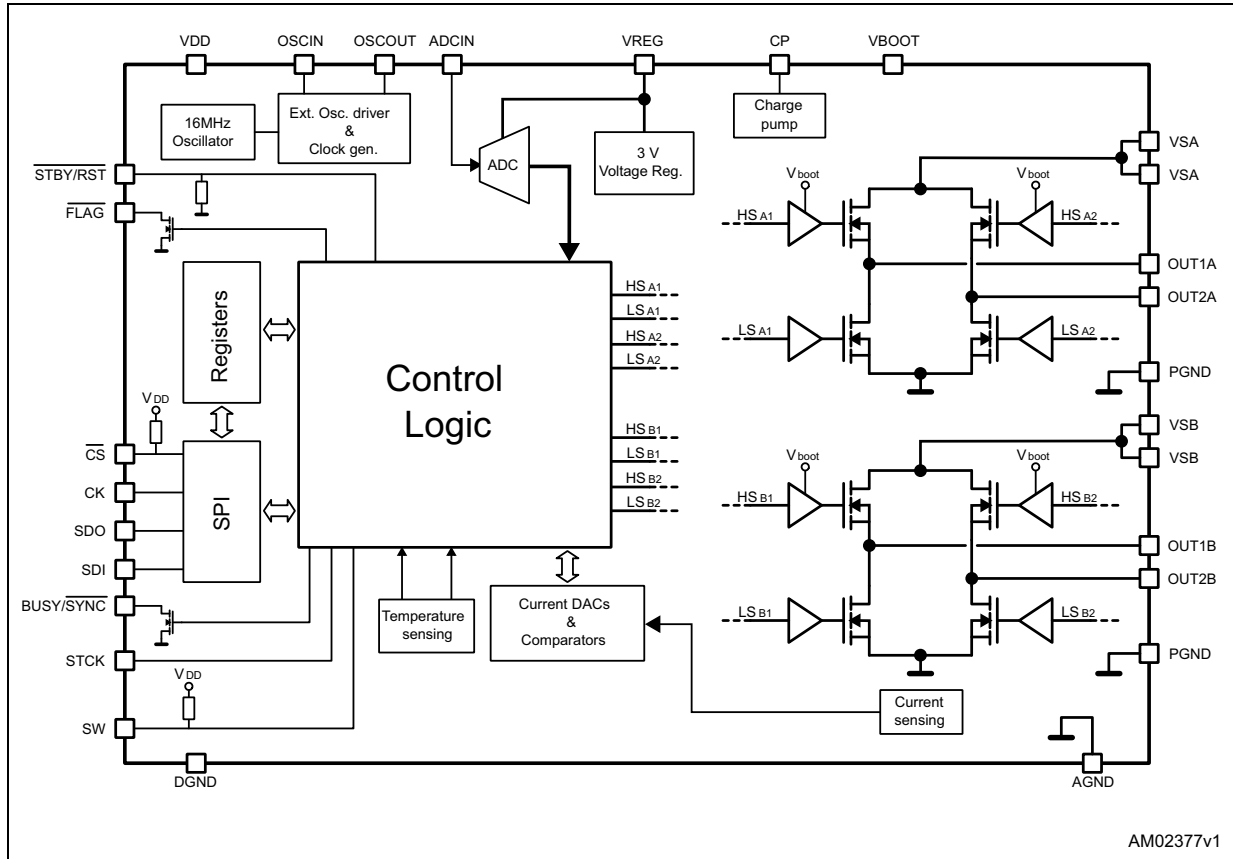
Table 48.	ResetDevice command structure	61
Table 49.	SoftStop command structure	62
Table 50.	HardStop command structure	62
Table 51.	SoftHiZ command structure	62
Table 52.	HardHiZ command structure	63
Table 53.	GetStatus command structure	63
Table 54.	HTSSOP28 package mechanical data	66
Table 55.	POWERSO36 package mechanical data	68
Table 56.	Document revision history	69

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 the L6472	19
Figure 5.	Charge pump circuitry	21
Figure 6.	Normal mode and microstepping (16 microsteps)	22
Figure 7.	Automatic full-step switching	22
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 configurations	28
Figure 12.	External switch connection	30
Figure 13.	Internal 3 V linear regulator	31
Figure 14.	Predictive current control	33
Figure 15.	Non-predictive current control	34
Figure 16.	Adaptive decay - fast decay tuning	35
Figure 17.	Adaptive decay switch from normal to slow + fast decay mode and vice-versa	36
Figure 18.	Fast decay tuning during the falling steps	37
Figure 19.	SPI timings diagram	38
Figure 20.	Daisy chain configuration	39
Figure 21.	Command with 3-byte argument	55
Figure 22.	Command with 3-byte response	55
Figure 23.	Command response aborted	55
Figure 24.	HTSSOP28 package outline	65
Figure 25.	POWERSO36 package outline	67

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		± 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 _A , OUT2 _A , PGND and V_{SB} , OUT1 _B , OUT2 _B , 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 ($T_A = 25 \text{ °C}$)	(2)	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 the EVAL6472H.

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 _A , OUT2 _A , PGND and V_{SB} , OUT1 _B , OUT2 _B , 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 ⁽¹⁾	22	°C/W
		POWERSO36 ⁽²⁾	12	

1. HTSSOP28 mounted on the EVAL6472H Rev 1.0 board: four-layer FR4 PCB with a dissipating copper surface of about 40 cm² on each layer and 15 via holes below the IC.
2. POWERSO36 mounted on the EVAL6472PD Rev 1.0 board: four-layer FR4 PCB with a dissipating copper surface of about 40 cm² 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
General						
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; $V_{REG} = 3.3\text{ V ext}$; CP floating		0.5	0.65	mA
$T_{j(WRN)}$	Thermal warning temperature			130		°C
$T_{j(SD)}$	Thermal shutdown temperature			160		°C
Charge pump						
V_{pump}	Voltage swing for charge pump oscillator			10		V
$f_{pump,min}$	Minimum charge pump oscillator frequency ⁽¹⁾			660		kHz
$f_{pump,max}$	Maximum charge pump oscillator frequency ⁽¹⁾			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
Output DMOS transistor						
$R_{DS(on)}$	High-side switch on-resistance	$T_J = 25\text{ °C}$, $I_{out} = 3\text{ A}$		0.37		Ω
		$T_J = 125\text{ °C}$, ⁽²⁾ $I_{out} = 3\text{ A}$		0.51		
	Low-side switch on-resistance	$T_J = 25\text{ °C}$, $I_{out} = 3\text{ A}$		0.18		
		$T_J = 125\text{ °C}$, ⁽²⁾ $I_{out} = 3\text{ A}$		0.23		
I_{DSS}	Leakage current	OUT = V_S			3.1	mA
		OUT = GND	-0.3			
t_r	Rise time ⁽³⁾	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 _f	Fall time ⁽³⁾	POW_SR = '00', I _{out} = +1 A		90		ns
		POW_SR = '00', I _{out} = -1 A		110		
		POW_SR = '11', I _{out} = ±1 A		110		
		POW_SR = '10', I _{out} = ±1 A		260		
		POW_SR = '01', I _{load} = ±1 A		375		
SR _{out_r}	Output rising slew rate	POW_SR = '00', I _{out} = +1 A		285		V/μs
		POW_SR = '00', I _{out} = -1 A		360		
		POW_SR = '11', I _{out} = ±1 A		285		
		POW_SR = '10', I _{out} = ±1 A		150		
		POW_SR = '01', I _{out} = ±1 A		95		
SR _{out_f}	Output falling slew rate	POW_SR = '00', I _{out} = +1 A		320		V/μs
		POW_SR = '00', I _{out} = -1 A		260		
		POW_SR = '11', I _{out} = ±1 A		260		
		POW_SR = '10', I _{out} = ±1 A		110		
		POW_SR = '01', I _{out} = ±1 A		75		
Deadtime and blanking						
t _{DT}	Deadtime ⁽¹⁾	POW_SR = '00'		250		ns
		POW_SR = '11', f _{OSC} = 16 MHz		375		
		POW_SR = '10', f _{OSC} = 16 MHz		625		
		POW_SR = '01', f _{OSC} = 16 MHz		875		
t _{blank}	Blanking time ⁽¹⁾	POW_SR = '00'		250		ns
		POW_SR = '11', f _{OSC} = 16 MHz		375		
		POW_SR = '10', f _{OSC} = 16 MHz		625		
		POW_SR = '01', f _{OSC} = 16 MHz		875		
Source-drain diodes						
V _{SD,HS}	High-side diode forward ON voltage	I _{out} = 1 A		1	1.1	V
V _{SD,LS}	Low-side diode forward ON voltage	I _{out} = 1 A		1	1.1	V
t _{rrHS}	High-side diode reverse recovery time	I _{out} = 1 A		30		ns
t _{rrLS}	Low-side diode reverse recovery time	I _{out} = 1 A		100		ns
Logic inputs and outputs						
V _{IL}	Low logic level input voltage				0.8	V
V _{IH}	High logic level input voltage		2			V
I _{IH}	High logic level input current ⁽⁴⁾	V _{IN} = 5 V			1	μA

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
I_{IL}	Low logic level input current ⁽⁵⁾	$V_{IN} = 0\text{ V}$	-1			μA
V_{OL}	Low logic level output voltage ⁽⁶⁾	$V_{DD} = 3.3\text{ V}, I_{OL} = 4\text{ mA}$			0.3	V
		$V_{DD} = 5\text{ V}, I_{OL} = 4\text{ mA}$			0.3	
V_{OH}	High logic level output voltage	$V_{DD} = 3.3\text{ V}, I_{OH} = 4\text{ mA}$	2.4			V
		$V_{DD} = 5\text{ V}, I_{OH} = 4\text{ mA}$	4.7			
$R_{PU} R_{PD}$	CS pull-up and STBY pull-down resistors	$\overline{CS} = \text{GND}; \overline{STBY/RST} = 5\text{ V}$	335	430	565	$k\Omega$
I_{logic}	Internal logic supply current	3.3 V V_{REG} externally supplied, internal oscillator		3.7	4.3	mA
$I_{logic,STBY}$	Standby mode internal logic supply current	3.3 V V_{REG} externally supplied		2	2.5	μA
f_{STCK}	Step-clock input frequency				2	MHz
Internal oscillator and external oscillator driver						
$f_{osc,i}$	Internal oscillator frequency	$T_j = 25\text{ }^\circ\text{C}, V_{REG} = 3.3\text{ V}$	-3%	16	+3%	MHz
$f_{osc,e}$	Programmable external oscillator frequency		8		32	MHz
$V_{OSCOUTH}$	OSCOUT clock source high level voltage	Internal oscillator 3.3 V V_{REG} externally supplied; $I_{OSCOUT} = 4\text{ mA}$	2.4			V
$V_{OSCOUTL}$	OSCOUT clock source low level voltage	Internal oscillator 3.3 V V_{REG} externally supplied; $I_{OSCOUT} = 4\text{ mA}$			0.3	V
$t_{rOSCOUT}$ $t_{fOSCOUT}$	OSCOUT clock source rise and fall time	Internal oscillator			20	ns
t_{extosc}	Internal to external oscillator switching delay			3		ms
t_{intosc}	External to internal oscillator switching delay			1.5		μs
SPI						
$f_{CK,MAX}$	Maximum SPI clock frequency ⁽⁷⁾		5			MHz
t_{rCK} t_{fCK}	SPI clock rise and fall time ⁽⁷⁾	$C_L = 30\text{ pF}$			25	ns
t_{hCK} t_{lCK}	SPI clock high and low time ⁽⁷⁾		75			ns
t_{setCS}	Chip select setup time ⁽⁷⁾		350			ns
t_{hoICS}	Chip select hold time ⁽⁷⁾		10			ns
t_{disCS}	De-select time ⁽⁷⁾		800			ns
t_{setSDI}	Data input setup time ⁽⁷⁾		25			ns
t_{hoSDI}	Data input hold time ⁽⁷⁾		20			ns
t_{enSDO}	Data output enable time ⁽⁷⁾				38	ns

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
t_{disSDO}	Data output disable time ⁽⁷⁾				47	ns
t_{vSDO}	Data output valid time ⁽⁷⁾				57	ns
t_{holSDO}	Data output hold time ⁽⁷⁾		37			ns
Switch input (SW)						
R_{PUSW}	SW input pull-up resistance	SW = GND	60	85	110	k Ω
Current control						
$I_{STEP,max}$	Max. programmable reference current			4		A
$I_{STEP,min}$	Min. programmable reference current			31		mA
Overcurrent protection						
$I_{OCD,MAX}$	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	$di_{out}/dt = 350 \text{ A}/\mu\text{s}$		650	1000	ns
$t_{OCD,SD}$	OCD to shutdown delay time	$di_{out}/dt = 350 \text{ A}/\mu\text{s}$ POW_SR = '10'		600		μs
Standby						
I_{qSTBY}	Quiescent motor supply current in standby conditions	$V_S = 8 \text{ V}$		26	34	μA
		$V_S = 36 \text{ V}$		30	36	
$t_{STBY,min}$	Minimum standby time			10		μs
$t_{logicwu}$	Logic power-on and wake-up time			38	45	μs
t_{cpwu}	Charge pump power-on and wake-up time	Power bridges disabled, $C_p = 10 \text{ nF}$, $C_{boot} = 220 \text{ nF}$		650		μs
Internal voltage regulator						
V_{REG}	Voltage regulator output voltage		2.9	3	3.2	V
I_{REG}	Voltage regulator output current				40	mA
$V_{REG,drop}$	Voltage regulator output voltage drop	$I_{REG} = 40 \text{ mA}$		50		mV
$I_{REG,STBY}$	Voltage regulator standby output current				10	mA

Table 5. Electrical characteristics (continued)

Symbol	Parameter	Test condition	Min.	Typ.	Max.	Unit
Integrated analog-to-digital converter						
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			$f_{OSC}/512$		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 the $\overline{STBY/RST}$ pin which has an internal pull-down resistor.
5. Not valid for the SW and CS pins which have an internal pull-up resistor.
6. \overline{FLAG} , \overline{BUSY} and SYNC open drain outputs included.
7. See [Figure 19: SPI timings diagram on page 38](#) for details.

4 Pin connection

Figure 2. HTSSOP28 pin connection (top view)

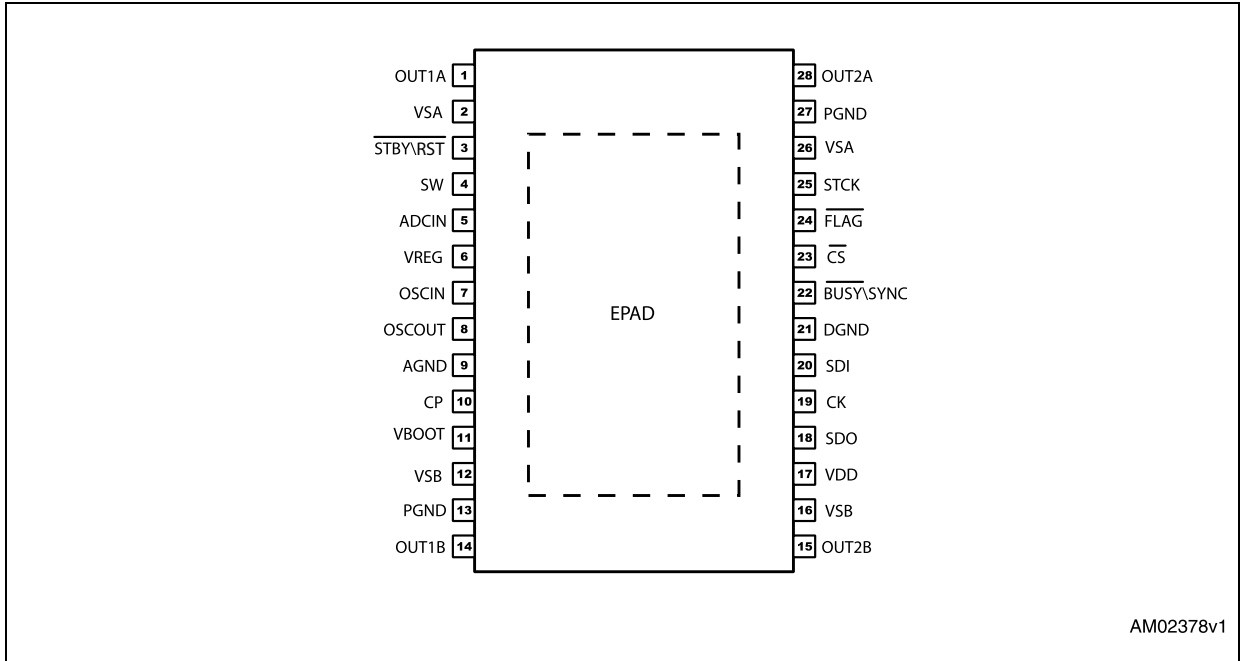
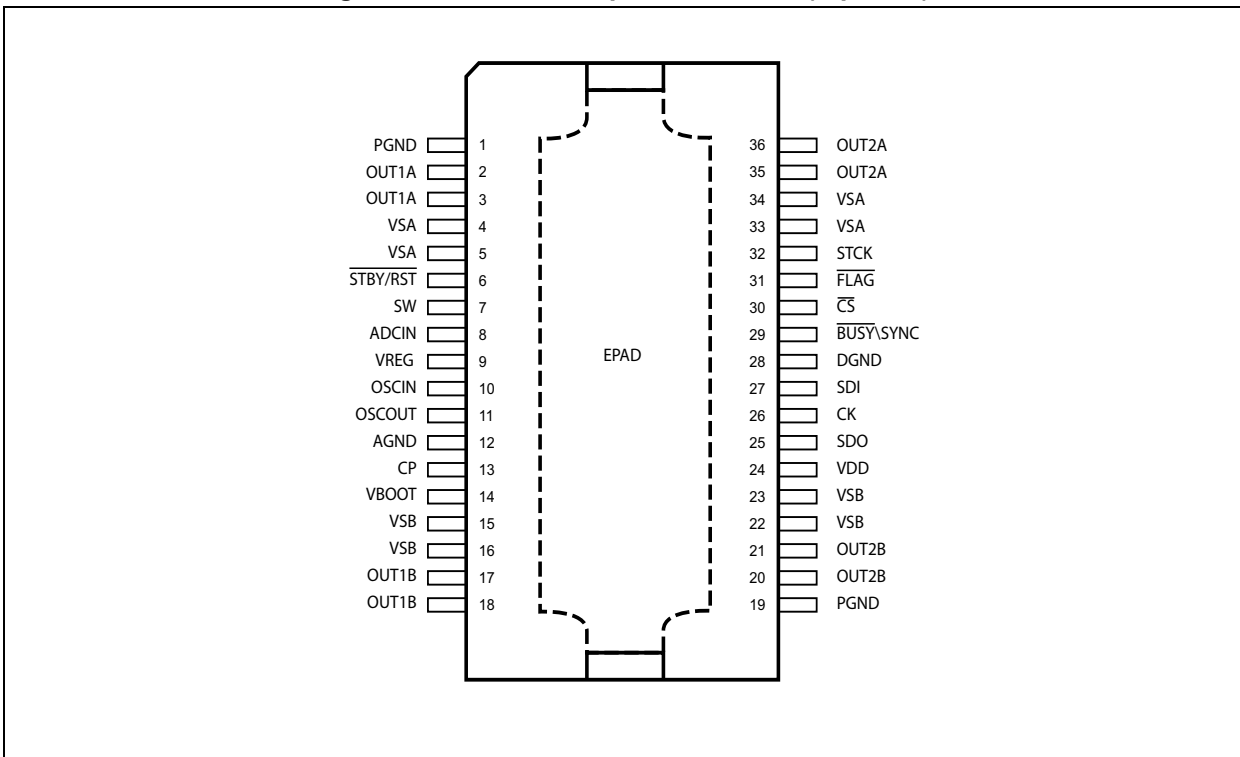


Figure 3. POWERSO36 pin connection (top view)



Pin list

Table 6. Pin description

Number		Name	Type	Function
POWERSO	HTSSOP			
24	17	VDD	Power	Logic output supply voltage (pull-up reference)
9	6	VREG	Power	Internal 3 V voltage regulator output and 3.3 V external logic supply
10	7	OSCIN	Analog input	Oscillator pin 1. To connect an external oscillator or clock source. If this pin is unused, it should be left floating.
11	8	OSCOUT	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.
13	10	CP	Output	Charge pump oscillator output
14	11	Vboot	Supply voltage	Bootstrap voltage needed for driving the high-side power DMOS of both bridges (A and B).
8	5	ADCIN	Analog input	Internal analog-to-digital converter input
4, 5	2	VSA	Power supply	Full bridge A power supply pin. It must be connected to VSB.
33, 34	26			
15, 16	12	VSB	Power supply	Full bridge B power supply pin. It must be connected to VSA.
22, 23	16			
1	27	PGND	Ground	Power ground pin
19	13			
2, 3	1	OUT1A	Power output	Full bridge A output 1
35, 36	28	OUT2A	Power output	Full bridge A output 2
17, 18	14	OUT1B	Power output	Full bridge B output 1
20, 21	15	OUT2B	Power output	Full bridge B output 2
12	9	AGND	Ground	Analog ground.
7	4	SW	Logical input	External switch input pin. If not used the pin should be connected to VDD.
28	21	DGND	Ground	Digital ground
29	22	$\overline{\text{BUSY}}/\text{SYNC}$	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.
25	18	SDO	Logic output	Data output pin for serial interface
27	20	SDI	Logic input	Data input pin for serial interface
26	19	CK	Logic input	Serial interface clock
30	23	$\overline{\text{CS}}$	Logic input	Chip select input pin for serial interface

Table 6. Pin description (continued)

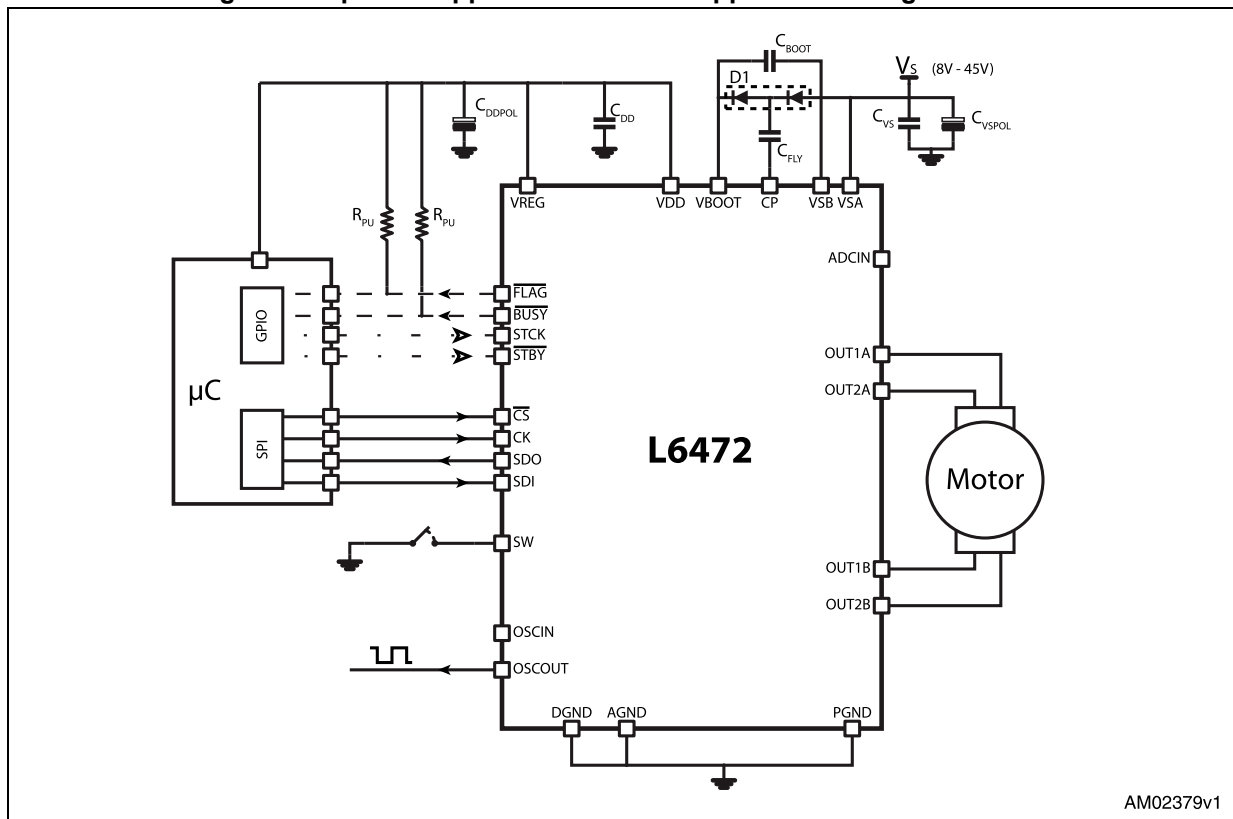
Number		Name	Type	Function
POWERSO	HTSSOP			
31	24	$\overline{\text{FLAG}}$	Open drain output	Status flag pin. An internal open drain transistor can pull the pin to GND when a programmed alarm condition occurs (step loss, OCD, thermal pre-warning or shutdown, UVLO, wrong command, non-performable command).
6	3	$\overline{\text{STBYRST}}$	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
32	25	STCK	Logic input	Step-clock input
	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 μ F
C_{REG}	100 nF
C_{REGPOL}	47 μ F
C_{DD}	100 nF
C_{DDPOL}	10 μ F
D1	Charge pump diodes
C_{BOOT}	220 nF
C_{FLY}	10 nF
R_{PU}	39 k Ω
R_{SW}	100 Ω
C_{SW}	10 nF

Figure 4. Bipolar stepper motor control application using the L6472



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6 Functional description

6.1 Device power-up

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

- Registers are set to default
- Internal logic is driven by the 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 IO 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 $V_{REGth} = 2.8\text{ V}$ (typ.)
- Internal oscillator is operative.

Any motion command causes the device to 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. The VDD pin voltage sets the logic output pin voltage range; when it is connected to VREG or a 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.

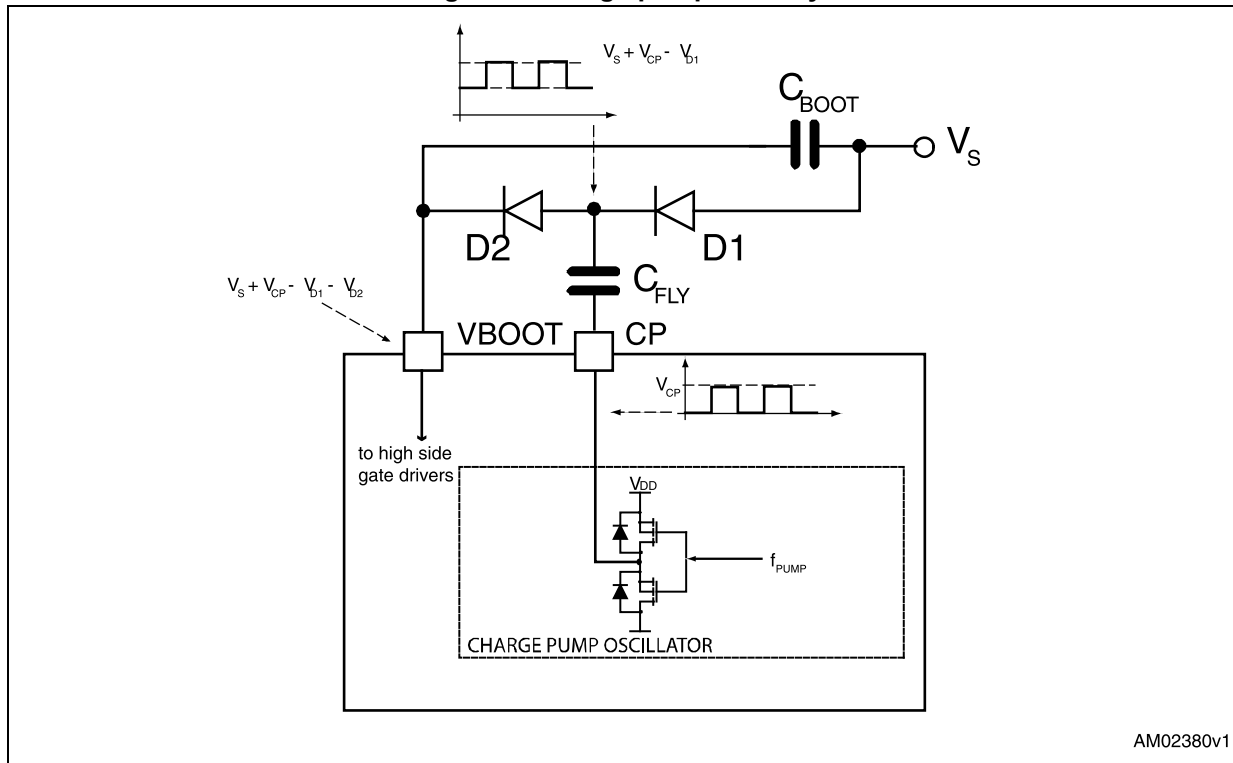
A 10 μF capacitor should be connected to the VDD pin in order to obtain a proper operation.

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 Vboot is obtained through an oscillator and a few external components realizing a charge pump (see [Figure 5](#)).

Figure 5. Charge pump circuitry



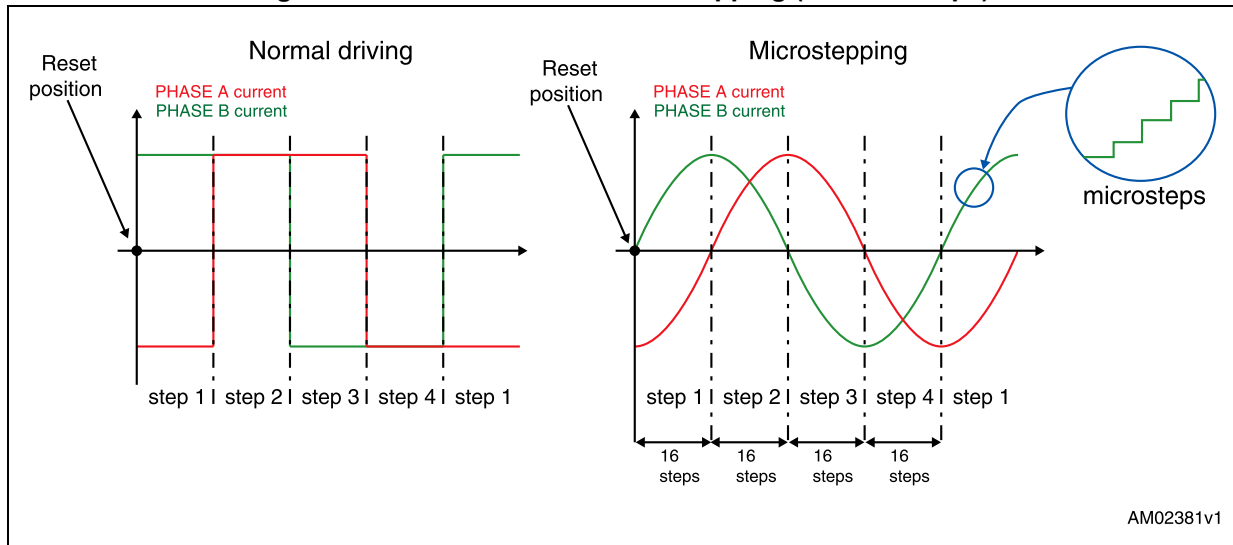
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6.4 Microstepping

The driver is able to divide the single step into up to 16 microsteps. Step mode can be programmed by the STEP_SEL parameter in the STEP_MODE register (see [Table 20 on page 47](#)).

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

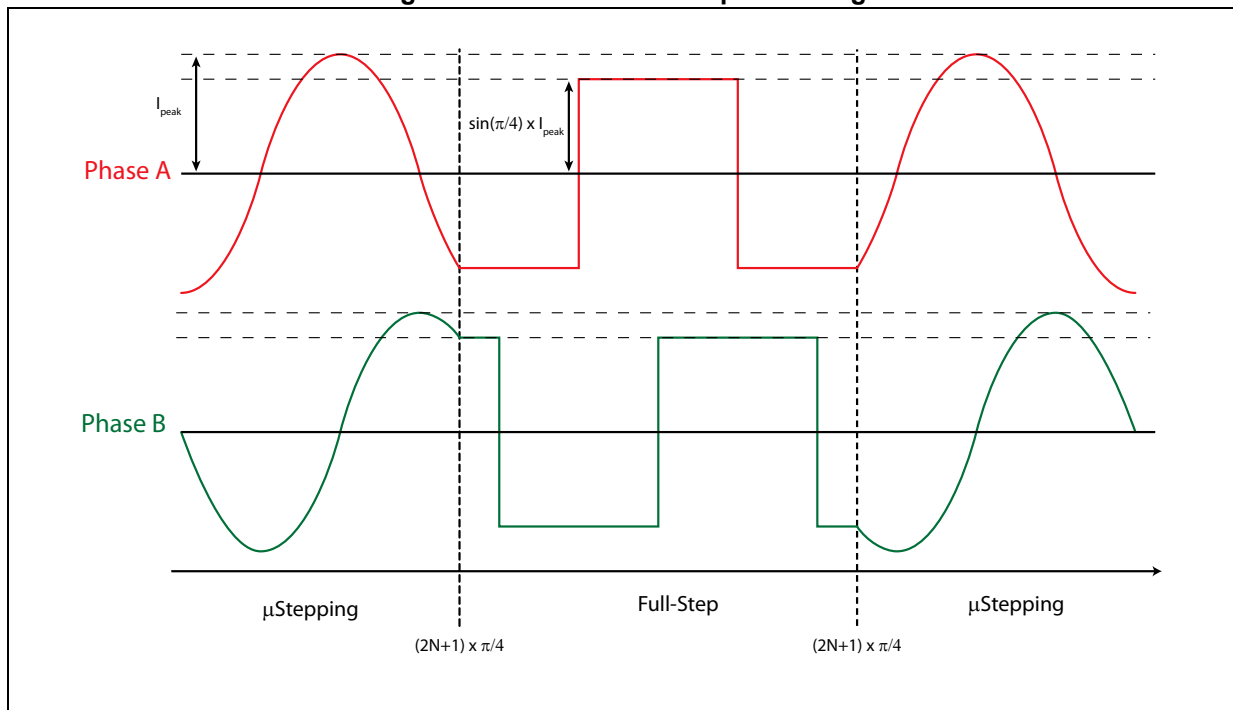
Figure 6. Normal mode and microstepping (16 microsteps)



Automatic full-step mode

When motor speed is greater than a programmable full-step speed threshold, the L6472 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) keeps track of 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 $+2^{21}-1$ (μ) steps (see [Section 9.1.1 on page 41](#)).

6.6 Programmable speed profiles

The user can easily program a customized speed profile, independently defining acceleration, deceleration, maximum and minimum speed values through the ACC, DEC, MAX_SPEED and MIN_SPEED registers respectively (see [Section 9.1.5 on page 42](#), [9.1.6 on page 42](#), [9.1.7 on page 43](#) and [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 step/tick² and all speed parameters are expressed in step/tick; the unit of measurement does not depend on selected step mode.

Acceleration and deceleration parameters range from 2^{-40} to $(2^{12}-2) \cdot 2^{-40}$ step/tick² (equivalent to 14.55 to 59590 step/s²).

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

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

6.7 Motor control commands

The L6472 can accept different types of commands:

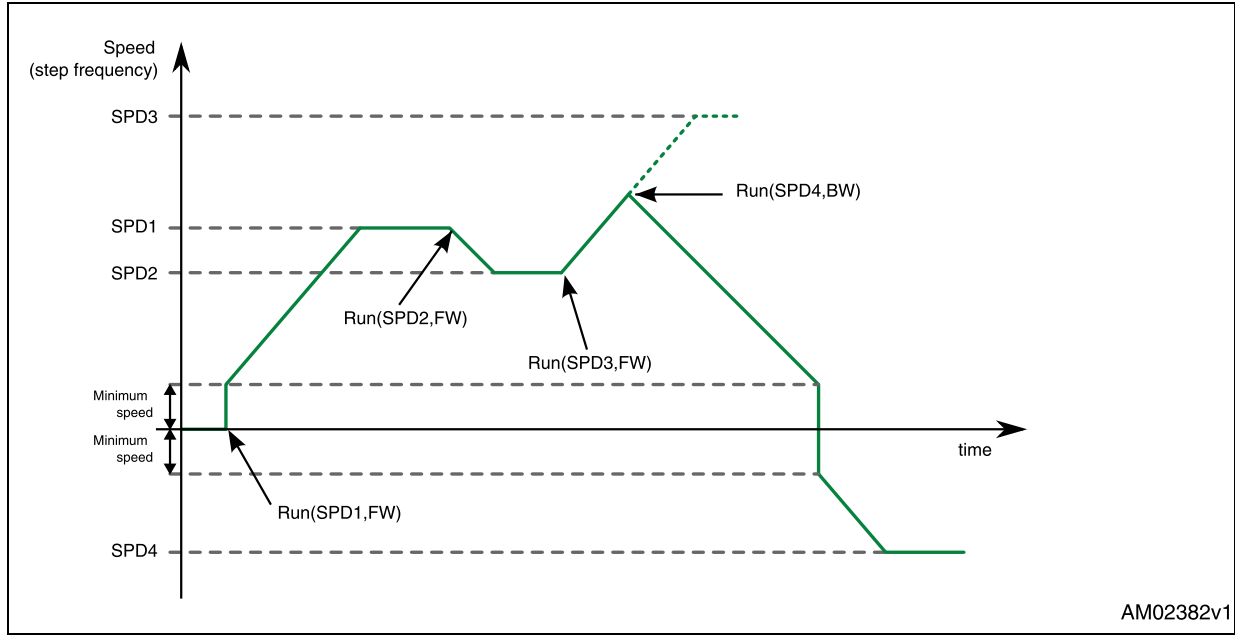
- constant speed commands (Run, GoUntil, ReleaseSW)
- absolute positioning commands (GoTo, GoTo_DIR, GoHome, GoMark)
- motion commands (Move)
- stop commands (SoftStop, HardStop, SoftHiz, HardHiz).

For detailed command descriptions refer to [Section 9.2 on page 54](#).

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



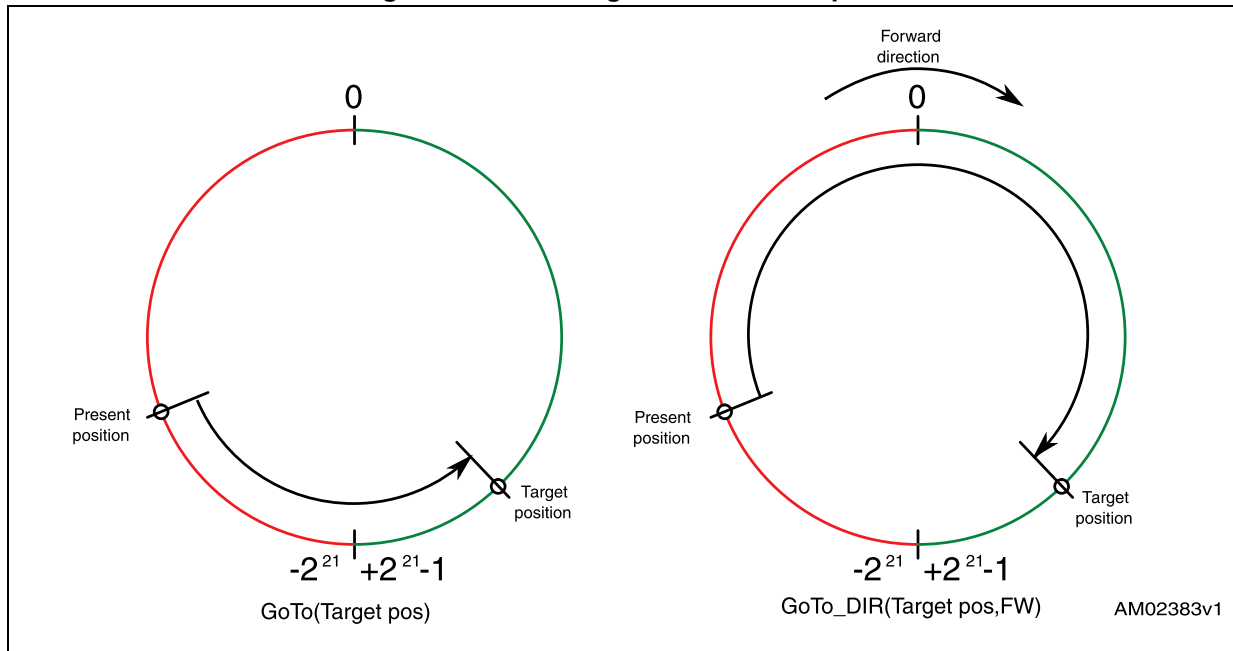
6.7.2 Positioning commands

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 by 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



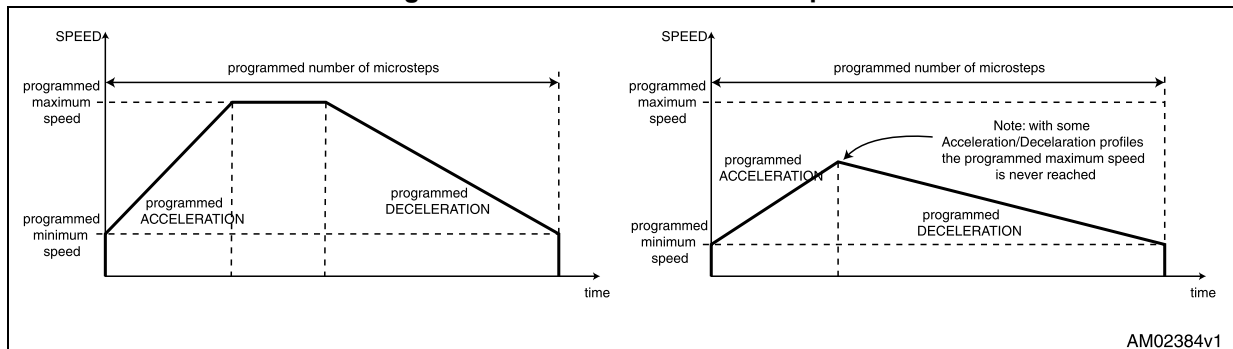
6.7.3 Motion commands

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 a programmed deceleration value until the MIN_SPEED value is reached and then stops the motor maintaining the rotor position (a holding torque is applied).