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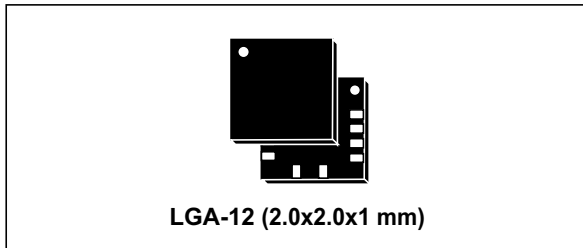
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## MEMS digital output motion sensor: ultra-low-power high-performance 3-axis "femto" accelerometer

Datasheet - production data



### Features

- Wide supply voltage, 1.71 V to 3.6 V
- Independent IO supply (1.8 V) and supply voltage compatible
- Ultra-low power consumption down to 2  $\mu$ A
- $\pm 2g/\pm 4g/\pm 8g/\pm 16g$  selectable full scales
- I<sup>2</sup>C/SPI digital output interface
- 8-bit data output
- 2 independent programmable interrupt generators for free-fall and motion detection
- 6D/4D orientation detection
- "Sleep-to-wake" and "return-to-sleep" functions
- Free-fall detection
- Motion detection
- Embedded temperature sensor
- Embedded FIFO
- ECOPACK<sup>®</sup>, RoHS and "Green" compliant

### Applications

- Motion-activated functions
- Display orientation
- Shake control
- Pedometer
- Gaming and virtual reality input devices
- Impact recognition and logging

### Description

The LIS2DE12 is an ultra-low-power high-performance three-axis linear accelerometer belonging to the "femto" family with digital I<sup>2</sup>C/SPI serial interface standard output.

The LIS2DE12 has user-selectable full scales of  $\pm 2g/\pm 4g/\pm 8g/\pm 16g$  and is capable of measuring accelerations with output data rates from 1 Hz to 5.3 kHz.

The self-test capability allows the user to check the functionality of the sensor in the final application.

The device may be configured to generate interrupt signals by detecting two independent inertial wake-up/free-fall events as well as by the position of the device itself.

The LIS2DE12 is available in a small thin plastic land grid array package (LGA) and is guaranteed to operate over an extended temperature range from -40 °C to +85 °C.

**Table 1. Device summary**

Order code	Temp. range [°C]	Package	Packaging
LIS2DE12TR	-40 to +85	LGA-12	Tape and reel

# Contents

- 1      Block diagram and pin description ..... 8**
  - 1.1    Block diagram ..... 8
  - 1.2    Pin description ..... 8
  
- 2      Mechanical and electrical specifications ..... 10**
  - 2.1    Mechanical characteristics ..... 10
  - 2.2    Temperature sensor characteristics ..... 11
  - 2.3    Electrical characteristics ..... 11
  - 2.4    Communication interface characteristics ..... 12
    - 2.4.1    SPI - serial peripheral interface ..... 12
    - 2.4.2    I<sup>2</sup>C - inter-IC control interface ..... 13
  - 2.5    Absolute maximum ratings ..... 14
  
- 3      Terminology and functionality ..... 15**
  - 3.1    Terminology ..... 15
    - 3.1.1    Sensitivity ..... 15
    - 3.1.2    Zero-g level ..... 15
  - 3.2    Functionality ..... 16
    - 3.2.1    Normal mode ..... 16
    - 3.2.2    Self-test ..... 16
    - 3.2.3    6D / 4D orientation detection ..... 16
    - 3.2.4    Sleep-to-wake and Return-to-sleep ..... 17
  - 3.3    Sensing element ..... 17
  - 3.4    IC interface ..... 17
  - 3.5    Factory calibration ..... 18
  - 3.6    FIFO ..... 18
  - 3.7    Temperature sensor ..... 18
  
- 4      Application hints ..... 19**
  - 4.1    Soldering information ..... 20
  
- 5      Digital main blocks ..... 21**
  - 5.1    FIFO ..... 21

5.1.1	Bypass mode .....	21
5.1.2	FIFO mode .....	21
5.1.3	Stream mode .....	22
5.1.4	Stream-to-FIFO mode .....	22
5.1.5	Retrieving data from FIFO .....	22
<b>6</b>	<b>Digital interfaces .....</b>	<b>23</b>
6.1	I <sup>2</sup> C serial interface .....	23
6.1.1	I <sup>2</sup> C operation .....	24
6.2	SPI bus interface .....	26
6.2.1	SPI read .....	27
6.2.2	SPI write .....	28
6.2.3	SPI read in 3-wire mode .....	29
<b>7</b>	<b>Register mapping .....</b>	<b>30</b>
<b>8</b>	<b>Register description .....</b>	<b>32</b>
8.1	STATUS_REG_AUX (07h) .....	32
8.2	OUT_TEMP_L (0Ch), OUT_TEMP_H (0Dh) .....	32
8.3	WHO_AM_I (0Fh) .....	32
8.4	CTRL_REG0 (1Eh) .....	32
8.5	TEMP_CFG_REG (1Fh) .....	33
8.6	CTRL_REG1 (20h) .....	33
8.7	CTRL_REG2 (21h) .....	34
8.8	CTRL_REG3 (22h) .....	35
8.9	CTRL_REG4 (23h) .....	35
8.10	CTRL_REG5 (24h) .....	36
8.11	CTRL_REG6 (25h) .....	36
8.12	REFERENCE (26h) .....	37
8.13	STATUS_REG (27h) .....	37
8.14	FIFO_READ_START (28h) .....	37
8.15	OUT_X_H (29h) .....	38
8.16	OUT_Y_H (2Bh) .....	38
8.17	OUT_Z_H (2Dh) .....	38
8.18	FIFO_CTRL_REG (2Eh) .....	38



8.19	FIFO_SRC_REG (2Fh)	39
8.20	INT1_CFG (30h)	39
8.21	INT1_SRC (31h)	40
8.22	INT1_THS (32h)	41
8.23	INT1_DURATION (33h)	41
8.24	INT2_CFG (34h)	42
8.25	INT2_SRC (35h)	43
8.26	INT2_THS (36h)	43
8.27	INT2_DURATION (37h)	44
8.28	CLICK_CFG (38h)	44
8.29	CLICK_SRC (39h)	45
8.30	CLICK_THS (3Ah)	45
8.31	TIME_LIMIT (3Bh)	45
8.32	TIME_LATENCY (3Ch)	46
8.33	TIME_WINDOW (3Dh)	46
8.34	ACT_THS (3Eh)	46
8.35	ACT_DUR (3Fh)	46
<b>9</b>	<b>Package information</b>	<b>47</b>
9.1	LGA-12 package information	47
9.2	LGA-12 packing information	48
<b>10</b>	<b>Revision history</b>	<b>50</b>

## List of tables

Table 1.	Device summary . . . . .	1
Table 2.	Pin description . . . . .	9
Table 3.	Internal pull-up values (typ.) for SDO/SA0 pin . . . . .	9
Table 4.	Mechanical characteristics . . . . .	10
Table 5.	Temperature sensor characteristics . . . . .	11
Table 6.	Electrical characteristics . . . . .	11
Table 7.	SPI slave timing values . . . . .	12
Table 8.	I <sup>2</sup> C slave timing values . . . . .	13
Table 9.	Absolute maximum ratings . . . . .	14
Table 10.	Normal mode . . . . .	16
Table 11.	Current consumption . . . . .	16
Table 12.	Internal pin status . . . . .	20
Table 13.	Serial interface pin description . . . . .	23
Table 14.	I <sup>2</sup> C terminology . . . . .	23
Table 15.	SAD+read/write patterns . . . . .	24
Table 16.	Transfer when master is writing one byte to slave . . . . .	24
Table 17.	Transfer when master is writing multiple bytes to slave . . . . .	25
Table 18.	Transfer when master is receiving (reading) one byte of data from slave . . . . .	25
Table 19.	Transfer when master is receiving (reading) multiple bytes of data from slave . . . . .	25
Table 20.	Register address map . . . . .	30
Table 21.	STATUS_REG_AUX register . . . . .	32
Table 22.	STATUS_REG_AUX description . . . . .	32
Table 23.	WHO_AM_I register . . . . .	32
Table 24.	CTRL_REG0 register . . . . .	32
Table 25.	CTRL_REG0 description . . . . .	32
Table 26.	TEMP_CFG_REG register . . . . .	33
Table 27.	TEMP_CFG_REG description . . . . .	33
Table 28.	CTRL_REG1 register . . . . .	33
Table 29.	CTRL_REG1 description . . . . .	33
Table 30.	Data rate configuration . . . . .	33
Table 31.	CTRL_REG2 register . . . . .	34
Table 32.	CTRL_REG2 description . . . . .	34
Table 33.	High-pass filter mode configuration . . . . .	34
Table 34.	Low-power mode - high-pass filter cutoff frequency [Hz] . . . . .	34
Table 35.	CTRL_REG3 register . . . . .	35
Table 36.	CTRL_REG3 description . . . . .	35
Table 37.	CTRL_REG4 register . . . . .	35
Table 38.	CTRL_REG4 description . . . . .	35
Table 39.	Self-test mode configuration . . . . .	35
Table 40.	CTRL_REG5 register . . . . .	36
Table 41.	CTRL_REG5 description . . . . .	36
Table 42.	CTRL_REG6 register . . . . .	36
Table 43.	CTRL_REG6 description . . . . .	36
Table 44.	REFERENCE register . . . . .	37
Table 45.	REFERENCE description . . . . .	37
Table 46.	STATUS_REG register . . . . .	37
Table 47.	STATUS_REG description . . . . .	37
Table 48.	FIFO_READ_START register . . . . .	37

Table 49.	FIFO_CTRL_REG register . . . . .	38
Table 50.	FIFO_CTRL_REG description . . . . .	38
Table 51.	FIFO mode configuration . . . . .	38
Table 52.	FIFO_SRC_REG register . . . . .	39
Table 53.	FIFO_SRC_REG description . . . . .	39
Table 54.	INT1_CFG register . . . . .	39
Table 55.	INT1_CFG description . . . . .	39
Table 56.	Interrupt mode . . . . .	40
Table 57.	INT1_SRC register . . . . .	40
Table 58.	INT1_SRC description . . . . .	40
Table 59.	INT1_THS register . . . . .	41
Table 60.	INT1_THS description. . . . .	41
Table 61.	INT1_DURATION register . . . . .	41
Table 62.	INT1_DURATION description. . . . .	41
Table 63.	INT2_CFG register . . . . .	42
Table 64.	INT2_CFG description . . . . .	42
Table 65.	Interrupt mode . . . . .	42
Table 66.	INT2_SRC register . . . . .	43
Table 67.	INT2_SRC description . . . . .	43
Table 68.	INT2_THS register . . . . .	43
Table 69.	INT2_THS description. . . . .	43
Table 70.	INT2_DURATION register . . . . .	44
Table 71.	INT2_DURATION description. . . . .	44
Table 72.	CLICK_CFG register. . . . .	44
Table 73.	CLICK_CFG description . . . . .	44
Table 74.	CLICK_SRC register. . . . .	45
Table 75.	CLICK_SRC description . . . . .	45
Table 76.	CLICK_THS register . . . . .	45
Table 77.	CLICK_THS register description. . . . .	45
Table 78.	TIME_LIMIT register . . . . .	45
Table 79.	TIME_LIMIT description . . . . .	45
Table 80.	TIME_LATENCY register . . . . .	46
Table 81.	TIME_LATENCY description . . . . .	46
Table 82.	TIME_WINDOW register. . . . .	46
Table 83.	TIME_WINDOW description. . . . .	46
Table 84.	ACT_THS register. . . . .	46
Table 85.	ACT_THS description . . . . .	46
Table 86.	ACT_DUR register . . . . .	46
Table 87.	ACT_DUR description. . . . .	46
Table 88.	Reel dimensions for carrier tape of LGA-12 package . . . . .	49
Table 89.	Document revision history. . . . .	50

## List of figures

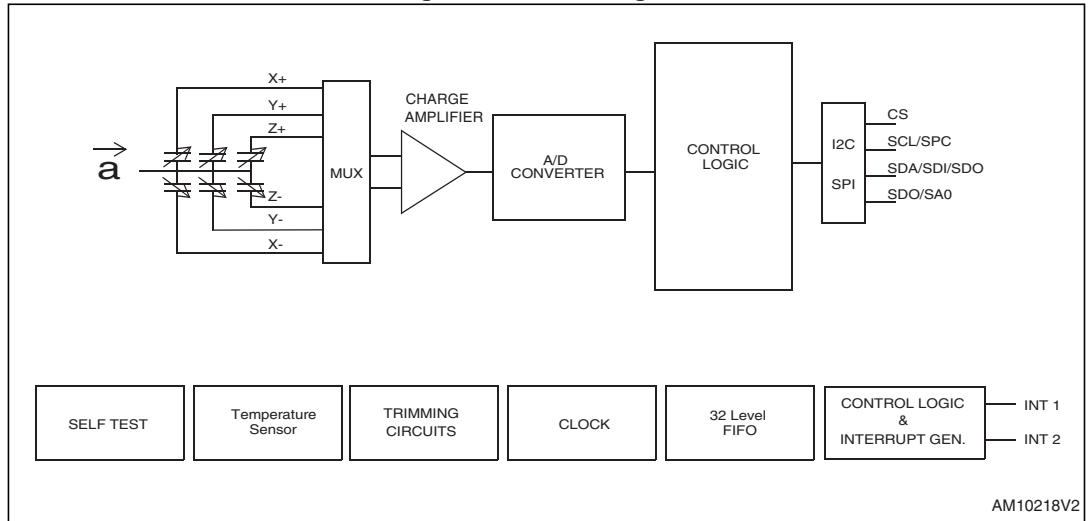
Figure 1.	Block diagram . . . . .	8
Figure 2.	Pin connections . . . . .	8
Figure 3.	SPI slave timing diagram . . . . .	12
Figure 4.	I <sup>2</sup> C slave timing diagram . . . . .	13
Figure 5.	LIS2DE12 electrical connections . . . . .	19
Figure 6.	Read and write protocol . . . . .	26
Figure 7.	SPI read protocol . . . . .	27
Figure 8.	Multiple byte SPI read protocol (2-byte example). . . . .	27
Figure 9.	SPI write protocol . . . . .	28
Figure 10.	Multiple byte SPI write protocol (2-byte example). . . . .	28
Figure 11.	SPI read protocol in 3-wire mode . . . . .	29
Figure 12.	LGA-12: package outline and mechanical data . . . . .	47
Figure 13.	Carrier tape information for LGA-12 package. . . . .	48
Figure 14.	LGA-12 package orientation in carrier tape . . . . .	48
Figure 15.	Reel information for carrier tape of LGA-12 package . . . . .	49



# 1 Block diagram and pin description

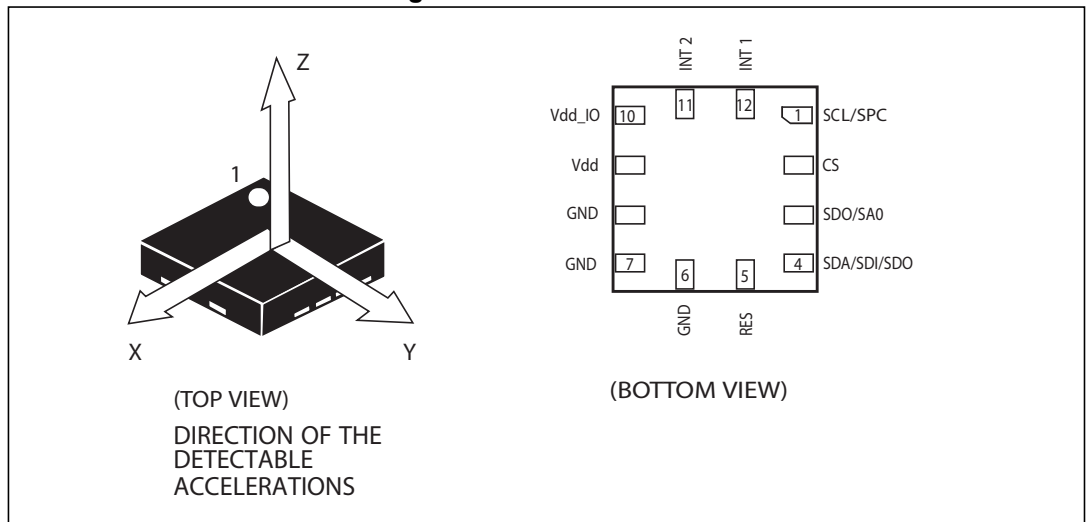
## 1.1 Block diagram

Figure 1. Block diagram



## 1.2 Pin description

Figure 2. Pin connections



**Table 2. Pin description**

Pin#	Name	Function
1	SCL SPC	I <sup>2</sup> C serial clock (SCL) SPI serial port clock (SPC)
2	CS	SPI enable I <sup>2</sup> C/SPI mode selection: 1: SPI idle mode / I <sup>2</sup> C communication enabled 0: SPI communication mode / I <sup>2</sup> C disabled
3 <sup>(1)</sup>	SDO SA0	SPI serial data output (SDO) I <sup>2</sup> C less significant bit of the device address (SA0)
4	SDA SDI SDO	I <sup>2</sup> C serial data (SDA) SPI serial data input (SDI) 3-wire interface serial data output (SDO)
5	Res	Connect to GND
6	GND	0 V supply
7	GND	0 V supply
8	GND	0 V supply
9	Vdd	Power supply
10	Vdd_IO	Power supply for I/O pins
11	INT2	Interrupt pin 2
12	INT1	Interrupt pin 1

1. SDO/SA0 pin is internally pulled up. Refer to [Table 3](#) for the internal pull-up values (typ).

**Table 3. Internal pull-up values (typ.) for SDO/SA0 pin**

Vdd_IO	Resistor value for SDO/SA0 pin
	Typ. (kΩ)
1.7 V	54.4
1.8 V	49.2
2.5 V	30.4
3.6 V	20.4

## 2 Mechanical and electrical specifications

### 2.1 Mechanical characteristics

@ Vdd = 2.5 V, T = 25 °C unless otherwise noted<sup>(a)</sup>

**Table 4. Mechanical characteristics**

Symbol	Parameter	Test conditions	Min.	Typ. <sup>(1)</sup>	Max.	Unit
FS	Measurement range <sup>(2)</sup>	FS bits set to 00		±2.0		g
		FS bits set to 01		±4.0		
		FS bits set to 10		±8.0		
		FS bits set to 11		±16.0		
So	Sensitivity	FS bits set to 00 Normal mode		15.6		mg/digit
		FS bits set to 01 Normal mode		31.2		
		FS bits set to 10 Normal mode		62.5		
		FS bits set to 11 Normal mode		187.5		
TCS <sub>o</sub>	Sensitivity change vs. temperature	FS bits set to 00		±0.05		%/°C
TyOff	Typical zero-g level offset accuracy <sup>(3)</sup>	FS bits set to 00		±100		mg
TCOff	Zero-g level change vs. temperature	Max delta from 25 °C		±0.5		mg/°C
Vst	Self-test output change <sup>(4) (5) (6)</sup>	FS bits set to 00 X-axis; Normal mode	4		90	LSb
		FS bits set to 00 Y-axis; Normal mode	4		90	LSb
		FS bits set to 00 Z-axis; Normal mode	4		90	LSb
Top	Operating temperature range		-40		+85	°C

1. Typical specifications are not guaranteed.
2. Verified by wafer level test and measurement of initial offset and sensitivity.
3. Typical zero-g level offset value after factory calibration test at socket level.
4. The sign of “Self-test output change” is defined by the ST bits in *CTRL\_REG4 (23h)*, for all axes.
5. “Self-test output change” is defined as the absolute value of:  
 $OUTPUT[LSb]_{(Self\ test\ enabled)} - OUTPUT[LSb]_{(Self\ test\ disabled)}$ . 1LSb = 15.6 g at 8-bit representation, ±2 g full scale
6. After enabling the ST bit, correct data is obtained after two samples, normal mode.

a. The product is factory calibrated at 2.5 V. The operational power supply range is from 1.71 V to 3.6 V.

## 2.2 Temperature sensor characteristics

@ Vdd = 2.5 V, T = 25 °C unless otherwise noted<sup>(b)</sup>

**Table 5. Temperature sensor characteristics**

Symbol	Parameter	Min.	Typ. <sup>(1)</sup>	Max.	Unit
TSDr	Temperature sensor output change vs. temperature		1		digit/°C <sup>(2)</sup>
TODR	Temperature refresh rate		ODR <sup>(3)</sup>		Hz
Top	Operating temperature range	-40		+85	°C

1. Typical specifications are not guaranteed.
2. 8-bit resolution.
3. Refer to [Table 30](#).

## 2.3 Electrical characteristics

@ Vdd = 2.5 V, T = 25 °C unless otherwise noted<sup>(c)</sup>

**Table 6. Electrical characteristics**

Symbol	Parameter	Test conditions	Min.	Typ. <sup>(1)</sup>	Max.	Unit
Vdd	Supply voltage		1.71	2.5	3.6	V
Vdd_IO	I/O pins supply voltage <sup>(2)</sup>		1.71		Vdd+0.1	V
IddLP	Current consumption in normal mode	50 Hz ODR		6		μA
IddPdn	Current consumption in power-down mode			0.5		μA
VIH	Digital high-level input voltage		0.8*Vdd_IO			V
VIL	Digital low-level input voltage				0.2*Vdd_IO	V
VOH	High-level output voltage		0.9*Vdd_IO			V
VOL	Low-level output voltage				0.1*Vdd_IO	V
Top	Operating temperature range		-40		+85	°C

1. Typical specification are not guaranteed.
2. It is possible to remove Vdd maintaining Vdd\_IO without blocking the communication busses, in this condition the measurement chain is powered off.

b. The product is factory calibrated at 2.5 V. Temperature sensor operation is guaranteed in the range 2 V - 3.6 V.

c. The product is factory calibrated at 2.5 V. The operational power supply range is from 1.71 V to 3.6 V.

## 2.4 Communication interface characteristics

### 2.4.1 SPI - serial peripheral interface

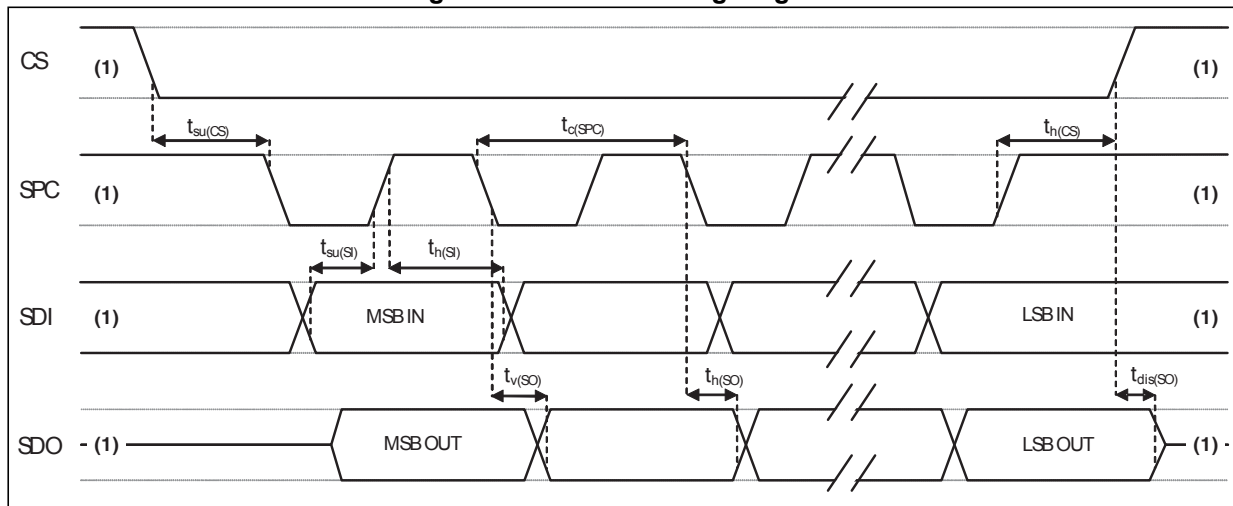
Subject to general operating conditions for Vdd and Top.

Table 7. SPI slave timing values

Symbol	Parameter	Value <sup>(1)</sup>		Unit
		Min	Max	
$t_{c(SPC)}$	SPI clock cycle	100		ns
$f_{c(SPC)}$	SPI clock frequency		10	MHz
$t_{su(CS)}$	CS setup time	5		ns
$t_{h(CS)}$	CS hold time	20		
$t_{su(SI)}$	SDI input setup time	5		
$t_{h(SI)}$	SDI input hold time	15		
$t_{v(SO)}$	SDO valid output time		50	
$t_{h(SO)}$	SDO output hold time	5		
$t_{dis(SO)}$	SDO output disable time		50	

1. Values are guaranteed at 10 MHz clock frequency for SPI with both 4 and 3 wires, based on characterization results, not tested in production.

Figure 3. SPI slave timing diagram



1. When no communication is ongoing, data on SDO is driven by internal pull-up resistors.

Note: Measurement points are done at 0.2·Vdd\_IO and 0.8·Vdd\_IO, for both input and output ports.

### 2.4.2 I<sup>2</sup>C - inter-IC control interface

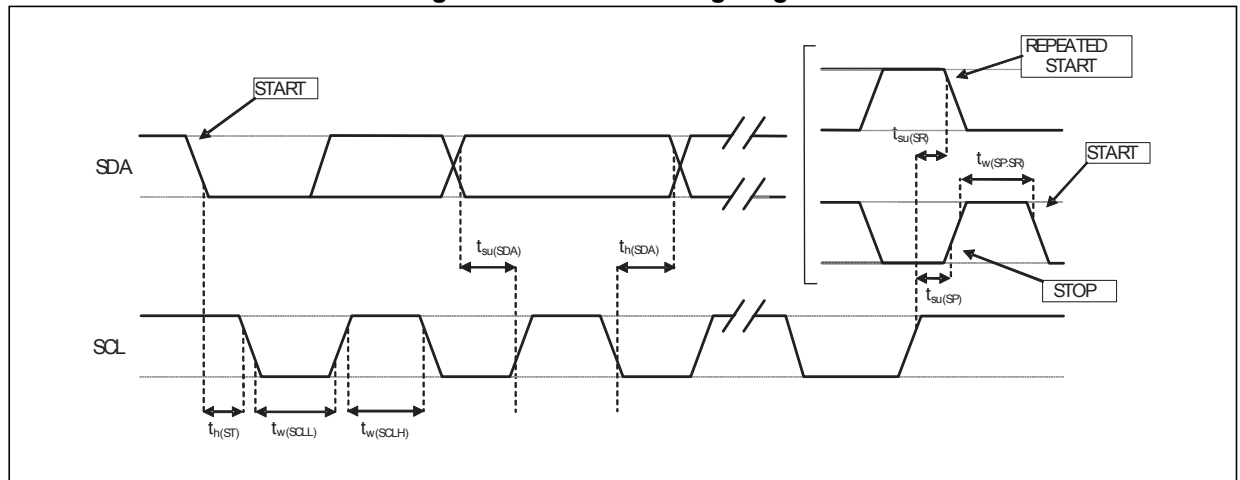
Subject to general operating conditions for Vdd and top.

**Table 8. I<sup>2</sup>C slave timing values**

Symbol	Parameter	I <sup>2</sup> C standard mode <sup>(1)</sup>		I <sup>2</sup> C fast mode <sup>(1)</sup>		Unit
		Min	Max	Min	Max	
f <sub>(SCL)</sub>	SCL clock frequency	0	100	0	400	kHz
t <sub>w(SCLL)</sub>	SCL clock low time	4.7		1.3		μs
t <sub>w(SCLH)</sub>	SCL clock high time	4.0		0.6		
t <sub>su(SDA)</sub>	SDA setup time	250		100		ns
t <sub>h(SDA)</sub>	SDA data hold time	0	3.45	0	0.9	μs
t <sub>h(ST)</sub>	START condition hold time	4		0.6		μs
t <sub>su(SR)</sub>	Repeated START condition setup time	4.7		0.6		
t <sub>su(SP)</sub>	STOP condition setup time	4		0.6		
t <sub>w(SP:SR)</sub>	Bus free time between STOP and START condition	4.7		1.3		

1. Data based on standard I<sup>2</sup>C protocol requirement, not tested in production.

**Figure 4. I<sup>2</sup>C slave timing diagram**



Note: Measurement points are done at 0.2·Vdd<sub>IO</sub> and 0.8·Vdd<sub>IO</sub>, for both ports.



## 2.5 Absolute maximum ratings

Stresses above those listed as “absolute maximum ratings” may cause permanent damage to the device. This is a stress rating only and functional operation of the device under these conditions is not implied. Exposure to maximum rating conditions for extended periods may affect device reliability.

**Table 9. Absolute maximum ratings**

Symbol	Ratings	Maximum value	Unit
V <sub>dd</sub>	Supply voltage	-0.3 to 4.8	V
V <sub>dd_IO</sub>	Supply voltage on I/O pins	-0.3 to 4.8	V
V <sub>in</sub>	Input voltage on any control pin (CS, SCL/SPC, SDA/SDI/SDO, SDO/SA0)	-0.3 to V <sub>dd_IO</sub> +0.3	V
A <sub>POW</sub>	Acceleration (any axis, powered, V <sub>dd</sub> = 2.5 V)	3000 g for 0.5 ms	
		10000 g for 0.2 ms	
A <sub>UNP</sub>	Acceleration (any axis, unpowered)	3000 g for 0.5 ms	
		10000 g for 0.2 ms	
T <sub>OP</sub>	Operating temperature range	-40 to +85	°C
T <sub>STG</sub>	Storage temperature range	-40 to +125	°C
ESD	Electrostatic discharge protection (HBM)	2	kV

*Note:* Supply voltage on any pin should never exceed 4.8 V.



This device is sensitive to mechanical shock, improper handling can cause permanent damage to the part.



This device is sensitive to electrostatic discharge (ESD), improper handling can cause permanent damage to the part.

## 3 Terminology and functionality

### 3.1 Terminology

#### 3.1.1 Sensitivity

Sensitivity describes the gain of the sensor and can be determined by applying 1 *g* acceleration to it. As the sensor can measure DC accelerations, this can be done easily by pointing the axis of interest towards the center of the Earth, noting the output value, rotating the sensor by 180 degrees (pointing to the sky) and noting the output value again. By doing so,  $\pm 1$  *g* acceleration is applied to the sensor. Subtracting the larger output value from the smaller one, and dividing the result by 2, leads to the actual sensitivity of the sensor. This value changes very little over temperature and time. The sensitivity tolerance describes the range of sensitivities of a large population of sensors.

#### 3.1.2 Zero-*g* level

The zero-*g* level offset (TyOff) describes the deviation of an actual output signal from the ideal output signal if no acceleration is present. A sensor in a steady state on a horizontal surface will measure 0 *g* for the X-axis and 0 *g* for the Y-axis whereas the Z-axis will measure 1 *g*. The output is ideally in the middle of the dynamic range of the sensor (content of OUT registers 00h, data expressed as two's complement number). A deviation from the ideal value in this case is called zero-*g* offset. Offset is to some extent a result of stress to the MEMS sensor and therefore the offset can slightly change after mounting the sensor on a printed circuit board or exposing it to extensive mechanical stress. Offset changes little over temperature, see [Table 4](#) "Zero-*g* level change vs. temperature" (TCOff). The zero-*g* level tolerance (TyOff) describes the standard deviation of the range of zero-*g* levels of a population of sensors.

## 3.2 Functionality

### 3.2.1 Normal mode

The LIS2DE12 provides a normal operating mode (see table below).

**Table 10. Normal mode**

Operating mode	BW [Hz]	Turn-on time [ms]	So @ ±2g [mg/digit]
Normal mode	ODR/2	1	16

**Table 11. Current consumption**

ODR [Hz]	Normal mode [µA]
1	2
10	3
25	4
50	6
100	10
200	18
400	36
1620	100
5376	185

### 3.2.2 Self-test

The self-test allows the user to check the sensor functionality without moving it. When the self-test is enabled, an actuation force is applied to the sensor, simulating a definite input acceleration. In this case the sensor outputs will exhibit a change in their DC levels which are related to the selected full scale through the device sensitivity. When the self-test is activated, the device output level is given by the algebraic sum of the signals produced by the acceleration acting on the sensor and by the electrostatic test-force. If the output signals change within the amplitude specified inside [Table 4](#), then the sensor is working properly and the parameters of the interface chip are within the defined specifications.

### 3.2.3 6D / 4D orientation detection

The LIS2DE12 provides the capability to detect the orientation of the device in space, enabling easy implementation of energy-saving procedures and automatic image rotation for mobile devices.

The 4D detection is a subset of the 6D function especially defined to be implemented in mobile devices for portrait and landscape computation. In 4D configuration, the Z-axis position detection is disabled.

### 3.2.4 Sleep-to-wake and Return-to-sleep

The LIS2DE12 can be programmed to automatically switch to low-ODR mode upon recognition of a determined event.

Once the event condition is over, the device returns back to the preset ODR.

To enable this function the desired threshold value must be stored inside the *ACT\_THS (3Eh)* register while the duration value is written inside the *ACT\_DUR (3Fh)* register.

When the acceleration falls below the threshold value for a period of time longer than the duration value, the device ODR automatically switches to 10 Hz ODR.

During this condition, the ODR[3:0] bits inside *CTRL\_REG1 (20h)* are not considered.

As soon as the acceleration rises above threshold, the module restores the operating mode and ODRs as determined by the *CTRL\_REG1 (20h)* register setting.

## 3.3 Sensing element

A proprietary process is used to create a surface micromachined accelerometer. The technology processes suspended silicon structures which are attached to the substrate in a few points called anchors and are free to move in the direction of the sensed acceleration. To be compatible with traditional packaging techniques, a cap is placed on top of the sensing element to avoid blocking the moving parts during the molding phase of the plastic encapsulation.

When an acceleration is applied to the sensor, the proof mass displaces from its nominal position, causing an imbalance in the capacitive half-bridge. This imbalance is measured using charge integration in response to a voltage pulse applied to the capacitor.

At steady state the nominal value of the capacitors are a few pF and when an acceleration is applied, the maximum variation of the capacitive load is in the fF range.

## 3.4 IC interface

The complete measurement chain is composed of a low-noise capacitive amplifier which converts the capacitive unbalance of the MEMS sensor into an analog voltage that will be available to the user through an analog-to-digital converter.

The acceleration data may be accessed through an I<sup>2</sup>C/SPI interface, thus making the device particularly suitable for direct interfacing with a microcontroller.

The LIS2DE12 features a data-ready signal (DRDY) which indicates when a new set of measured acceleration data is available, thus simplifying data synchronization in the digital system that uses the device.

The LIS2DE12 may also be configured to generate an inertial wake-up and free-fall interrupt signal according to a programmed acceleration event along the enabled axes. Both free-fall and wake-up can be available simultaneously on two different pins.

### 3.5 Factory calibration

The IC interface is factory calibrated for sensitivity (So) and zero-g level (TyOff).

The trim values are stored inside the device in non-volatile memory. Any time the device is turned on, these values are downloaded into the registers to be used during active operation. This allows using the device without further calibration.

### 3.6 FIFO

The LIS2DE12 contains a 10-bit, 32-level FIFO. Buffered output allows the following operation modes: FIFO, Stream, Stream-to-FIFO and FIFO bypass. When FIFO bypass mode is activated, FIFO is not operating and remains empty. In FIFO mode, measurement data from acceleration detection on the x, y, and z-axes are stored in the FIFO buffer.

### 3.7 Temperature sensor

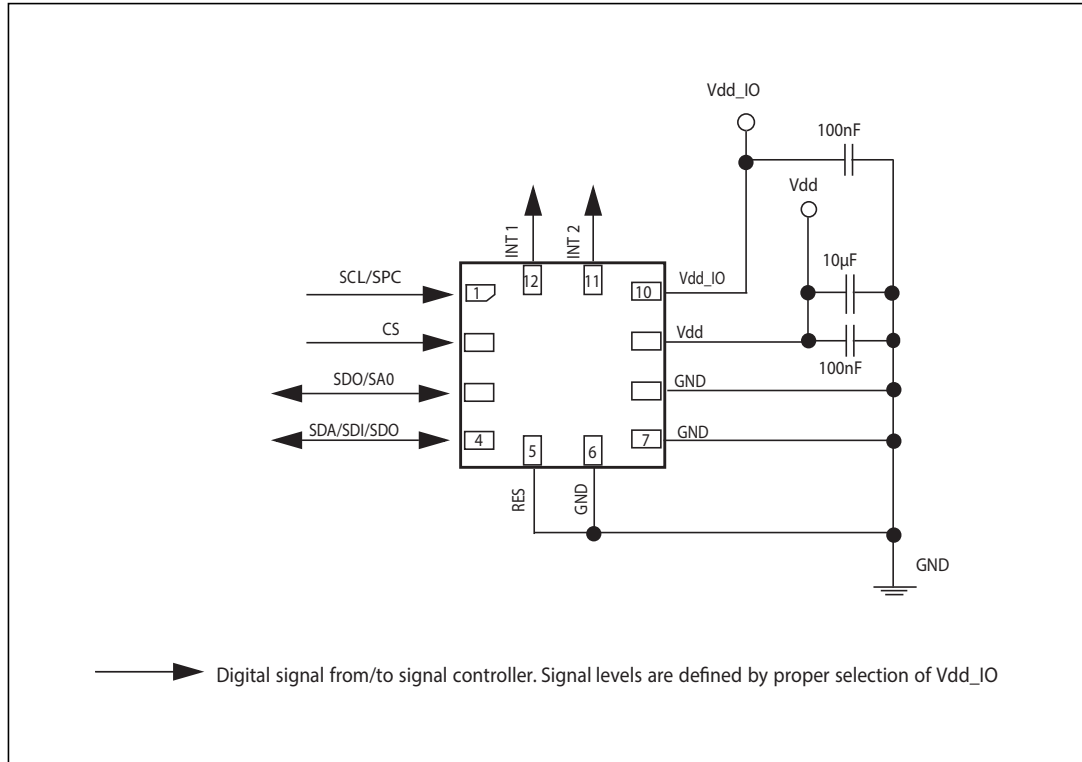
In order to enable the internal temperature sensor, bits TEMP\_EN[1:0] in register *TEMP\_CFG\_REG (1Fh)* and the BDU bit in *CTRL\_REG4 (23h)* have to be set.

The temperature is available in *OUT\_TEMP\_L (0Ch)*, *OUT\_TEMP\_H (0Dh)* stored as two's complement data, left-justified.

Refer to *Table 5: Temperature sensor characteristics* for the conversion factor.

## 4 Application hints

Figure 5. LIS2DE12 electrical connections



The device core is supplied through the Vdd line while the I/O pads are supplied through the Vdd\_IO line. Power supply decoupling capacitors (100 nF ceramic, 10 µF aluminum) should be placed as near as possible to pin 9 of the device (common design practice).

All the voltage and ground supplies must be present at the same time to have proper behavior of the IC (refer to [Figure 5](#)). It is possible to remove Vdd while maintaining Vdd\_IO without blocking the communication bus, in this condition the measurement chain is powered off.

The functionality of the device and the measured acceleration data is selectable and accessible through the I<sup>2</sup>C or SPI interfaces. When using the I<sup>2</sup>C, CS must be tied high.

The functions, the threshold and the timing of the two interrupt pins (INT1 and INT2) can be completely programmed by the user through the I<sup>2</sup>C/SPI interface.



Table 12. Internal pin status

Pin#	Name	Function	Pin status
1	SCL SPC	I <sup>2</sup> C serial clock (SCL) SPI serial port clock (SPC)	Default: input high impedance
2	CS	SPI enable I <sup>2</sup> C/SPI mode selection: 1: SPI idle mode / I <sup>2</sup> C communication enabled 0: SPI communication mode / I <sup>2</sup> C disabled	Default: input high impedance
3	SDO SA0	SPI serial data output (SDO) I <sup>2</sup> C less significant bit of the device address (SA0)	Default: input with internal pull-up <sup>(1)</sup>
4	SDA SDI SDO	I <sup>2</sup> C serial data (SDA) SPI serial data input (SDI) 3-wire interface serial data output (SDO)	Default: (SDA) input high impedance
5	Res	Connect to GND	
6	GND	0 V supply	
7	GND	0 V supply	
8	GND	0 V supply	
9	Vdd	Power supply	
10	Vdd_IO	Power supply for I/O pins	
11	INT2	Interrupt pin 2	Default: push-pull output forced to GND
12	INT1	Interrupt pin 1	Default: push-pull output forced to GND

1. In order to disable the internal pull-up on the SDO/SA0 pin, write 90h in [CTRL\\_REG0 \(1Eh\)](#).

## 4.1 Soldering information

The LGA package is compliant with the ECOPACK<sup>®</sup>, RoHS and “Green” standard. It is qualified for soldering heat resistance according to JEDEC J-STD-020.

Leave “Pin 1 Indicator” unconnected during soldering.

Land pattern and soldering recommendations are available at [www.st.com](http://www.st.com).

## 5 Digital main blocks

### 5.1 FIFO

The LIS2DE12 embeds a 32-level FIFO for each of the three output channels, X, Y and Z. This allows consistent power saving for the system, since the host processor does not need to continuously poll data from the sensor, but it can wake up only when needed and burst the significant data out from the FIFO.

In order to enable the FIFO buffer, the FIFO\_EN bit in *CTRL\_REG5 (24h)* must be set to '1'.

This buffer can work according to the following different modes: Bypass mode, FIFO mode, Stream mode and Stream-to-FIFO mode. Each mode is selected by the FM [1:0] bits in *FIFO\_CTRL\_REG (2Eh)*. Programmable FIFO watermark level, FIFO empty or FIFO overrun events can be enabled to generate dedicated interrupts on the INT1 pin (configuration through *CTRL\_REG3 (22h)*).

In the *FIFO\_SRC\_REG (2Fh)* register the EMPTY bit is equal to '1' when all FIFO samples are ready and FIFO is empty.

In the *FIFO\_SRC\_REG (2Fh)* register the WTM bit goes to '1' if new data is written in the buffer and *FIFO\_SRC\_REG (2Fh)* (FSS [4:0]) is greater than or equal to *FIFO\_CTRL\_REG (2Eh)* (FTH [4:0]). *FIFO\_SRC\_REG (2Fh)* (WTM) goes to '0' if reading an X, Y, Z data slot from FIFO and *FIFO\_SRC\_REG (2Fh)* (FSS [4:0]) is less than or equal to *FIFO\_CTRL\_REG (2Eh)* (FTH [4:0]).

In the *FIFO\_SRC\_REG (2Fh)* register the OVRN\_FIFO bit is equal to '1' if the FIFO slot is overwritten.

#### 5.1.1 Bypass mode

In Bypass mode the FIFO is not operational and for this reason it remains empty. For each channel only the first address is used. The remaining FIFO levels are empty.

Bypass mode must be used in order to reset the FIFO buffer when a different mode is operating (i.e. FIFO mode).

#### 5.1.2 FIFO mode

In FIFO mode, the buffer continues filling data from the X, Y and Z accelerometer channels until it is full (a set of 32 samples stored). When the FIFO is full, it stops collecting data from the input channels and the FIFO content remains unchanged.

An overrun interrupt can be enabled, I1\_OVERRUN = '1' in the *CTRL\_REG3 (22h)* register, in order to be raised when the FIFO stops collecting data. When the overrun interrupt occurs, the first data has been overwritten and the FIFO stops collecting data from the input channels.

After the last read it is necessary to transit from Bypass mode in order to reset the FIFO content. After this reset command, it is possible to restart FIFO mode just by selecting the FIFO mode configuration (FM[1:0] bits) in register *FIFO\_CTRL\_REG (2Eh)*.

### 5.1.3 Stream mode

In Stream mode the FIFO continues filling data from the X, Y, and Z accelerometer channels until the buffer is full (a set of 32 samples stored) at which point the FIFO buffer index restarts from the beginning and older data is replaced by the current data. The oldest values continue to be overwritten until a read operation frees the FIFO slots.

An overrun interrupt can be enabled, `I1_OVERRUN = '1'` in the [CTRL\\_REG3 \(22h\)](#) register, in order to read the entire contents of the FIFO at once. If, in the application, it is mandatory not to lose data and it is not possible to read at least one sample for each axis within one ODR period, a watermark interrupt can be enabled in order to read partially the FIFO and leave memory slots free for incoming data.

Setting the FTH [4:0] bit in the [FIFO\\_CTRL\\_REG \(2Eh\)](#) register to an N value, the number of X, Y and Z data samples that should be read at the rise of the watermark interrupt is up to (N+1).

### 5.1.4 Stream-to-FIFO mode

In Stream-to-FIFO mode, data from the X, Y and Z accelerometer channels are collected in a combination of Stream mode and FIFO mode. The FIFO buffer starts operating in Stream mode and switches to FIFO mode when the selected interrupt occurs.

The FIFO operating mode changes according to the INT1 pin value if the TR bit is set to '0' in the [FIFO\\_CTRL\\_REG \(2Eh\)](#) register or the INT2 pin value if the TR bit is set to '1' in the [FIFO\\_CTRL\\_REG \(2Eh\)](#) register.

When the interrupt pin is selected and the interrupt event is configured on the corresponding pin, the FIFO operates in Stream mode if the pin value is equal to '0' and it operates in FIFO mode if the pin value is equal to '1'. Switching modes is dynamically performed according to the pin value.

Stream-to-FIFO can be used in order to analyze the sampling history that generates an interrupt. The standard operation is to read the contents of FIFO when the FIFO mode is triggered and the FIFO buffer is full and stopped.

### 5.1.5 Retrieving data from FIFO

FIFO data is read from [OUT\\_X\\_H \(29h\)](#), [OUT\\_Y\\_H \(2Bh\)](#) and [OUT\\_Z\\_H \(2Dh\)](#). When the FIFO is in Stream, Stream-to-FIFO or FIFO mode, a read operation starts from [FIFO\\_READ\\_START \(28h\)](#), performs a 6-byte read and provides the data stored in the FIFO by reading [OUT\\_X\\_H \(29h\)](#), [OUT\\_Y\\_H \(2Bh\)](#) and [OUT\\_Z\\_H \(2Dh\)](#). Each time data is read from the FIFO, the oldest X, Y and Z data are placed in the [OUT\\_X\\_H \(29h\)](#), [OUT\\_Y\\_H \(2Bh\)](#) and [OUT\\_Z\\_H \(2Dh\)](#) registers and both single-read and read-burst operations can be used.

The address to be read is automatically updated by the device and it rolls back to 0x28 when register 0x2D is reached. In order to read all FIFO levels in a multiple byte read, 192 bytes (6 output registers of 32 levels) have to be read.

## 6 Digital interfaces

The registers embedded inside the LIS2DE12 may be accessed through both the I<sup>2</sup>C and SPI serial interfaces. The latter may be SW configured to operate either in 3-wire or 4-wire interface mode.

The serial interfaces are mapped to the same pads. To select/exploit the I<sup>2</sup>C interface, the CS line must be tied high (i.e. connected to Vdd\_IO).

**Table 13. Serial interface pin description**

Pin name	Pin description
CS	SPI enable I <sup>2</sup> C/SPI mode selection: 1: SPI idle mode / I <sup>2</sup> C communication enabled 0: SPI communication mode / I <sup>2</sup> C disabled
SCL SPC	I <sup>2</sup> C serial clock (SCL) SPI serial port clock (SPC)
SDA SDI SDO	I <sup>2</sup> C serial data (SDA) SPI serial data input (SDI) 3-wire interface serial data output (SDO)
SA0 SDO	I <sup>2</sup> C less significant bit of the device address (SA0) SPI serial data output (SDO)

### 6.1 I<sup>2</sup>C serial interface

The LIS2DE12 I<sup>2</sup>C is a bus slave. The I<sup>2</sup>C is employed to write data into registers whose content can also be read back.

The relevant I<sup>2</sup>C terminology is given in the table below.

**Table 14. I<sup>2</sup>C terminology**

Term	Description
Transmitter	The device which sends data to the bus
Receiver	The device which receives data from the bus
Master	The device which initiates a transfer, generates clock signals and terminates a transfer
Slave	The device addressed by the master

There are two signals associated with the I<sup>2</sup>C bus: the serial clock line (SCL) and the serial data line (SDA). The latter is a bidirectional line used for sending and receiving data to/from the interface. Both the lines must be connected to Vdd\_IO through an external pull-up resistor. When the bus is free, both the lines are high.

The I<sup>2</sup>C interface is compliant with fast mode (400 kHz) I<sup>2</sup>C standards as well as with normal mode.

### 6.1.1 I<sup>2</sup>C operation

The transaction on the bus is started through a START (ST) signal. A START condition is defined as a HIGH-to-LOW transition on the data line while the SCL line is held HIGH. After this has been transmitted by the master, the bus is considered busy. The next byte of data transmitted after the start condition contains the address of the slave in the first 7 bits and the eighth bit tells whether the master is receiving data from the slave or transmitting data to the slave. When an address is sent, each device in the system compares the first seven bits after a start condition with its address. If they match, the device considers itself addressed by the master.

The Slave Address (SAD) associated to the LIS2DE12 is 001100xb. The **SDO/SA0** pad can be used to modify the less significant bit of the device address. If the SA0 pad is connected to the voltage supply, LSb is '1' (address 0011001b), else if the SA0 pad is connected to ground, the LSb value is '0' (address 0011000b). This solution permits to connect and address two different accelerometers to the same I<sup>2</sup>C lines.

Data transfer with acknowledge is mandatory. The transmitter must release the SDA line during the acknowledge pulse. The receiver must then pull the data line LOW so that it remains stable low during the HIGH period of the acknowledge clock pulse. A receiver which has been addressed is obliged to generate an acknowledge after each byte of data received.

The I<sup>2</sup>C embedded inside the LIS2DE12 behaves like a slave device and the following protocol must be adhered to. After the start condition (ST) a slave address is sent, once a slave acknowledge (SAK) has been returned, an 8-bit sub-address (SUB) is transmitted: the 7 LSb represent the actual register address while the MSb enables address auto increment. If the MSb of the SUB field is '1', the SUB (register address) is automatically increased to allow multiple data read/writes.

The slave address is completed with a Read/Write bit. If the bit is '1' (Read), a repeated START (SR) condition must be issued after the two sub-address bytes; if the bit is '0' (Write) the master will transmit to the slave with direction unchanged. [Table 15](#) explains how the SAD+read/write bit pattern is composed, listing all the possible configurations.

**Table 15. SAD+read/write patterns**

Command	SAD[6:1]	SAD[0] = SA0	R/W	SAD+R/W
Read	001100	0	1	00110001 (31h)
Write	001100	0	0	00110000 (30h)
Read	001100	1	1	00110011 (33h)
Write	001100	1	0	00110010 (32h)

**Table 16. Transfer when master is writing one byte to slave**

Master	ST	SAD + W		SUB		DATA		SP
Slave			SAK		SAK		SAK	

**Table 17. Transfer when master is writing multiple bytes to slave**

Master	ST	SAD + W		SUB		DATA		DATA		SP
Slave			SAK		SAK		SAK		SAK	

**Table 18. Transfer when master is receiving (reading) one byte of data from slave**

Master	ST	SAD + W		SUB		SR	SAD + R			NMAK	SP
Slave			SAK		SAK			SAK	DATA		

**Table 19. Transfer when master is receiving (reading) multiple bytes of data from slave**

Master	ST	SAD+W		SUB		SR	SAD+R		MAK		MAK		NMAK	SP
Slave			SAK		SAK			SAK	DATA		DATA		DATA	

Data are transmitted in byte format (DATA). Each data transfer contains 8 bits. The number of bytes transferred per transfer is unlimited. Data is transferred with the Most Significant bit (MSb) first. If a receiver can't receive another complete byte of data until it has performed some other function, it can hold the clock line, SCL low to force the transmitter into a wait state. Data transfer only continues when the receiver is ready for another byte and releases the data line. If a slave receiver doesn't acknowledge the slave address (i.e. it is not able to receive because it is performing some real-time function) the data line must be left HIGH by the slave. The master can then abort the transfer. A low-to-high transition on the SDA line while the SCL line is HIGH is defined as a STOP condition. Each data transfer must be terminated by the generation of a STOP (SP) condition.

In order to read multiple bytes, it is necessary to assert the most significant bit of the sub-address field. In other words, SUB(7) must be equal to 1 while SUB(6-0) represents the address of the first register to be read.

In the presented communication format MAK is Master acknowledge and NMAK is No Master Acknowledge.