

BA6476AFP-Y

3-phase, full-wave, pseudo-linear motor driver

The BA6476AFP-Y is an IC that can be used to control and drive floppy disk drive spindle motors. This IC uses a 3-phase, full-wave pseudo-linear drive system.

With a built-in digital servo and power saving function, this device has a high performance and can reduce the number of components required in the floppy drive.

Features

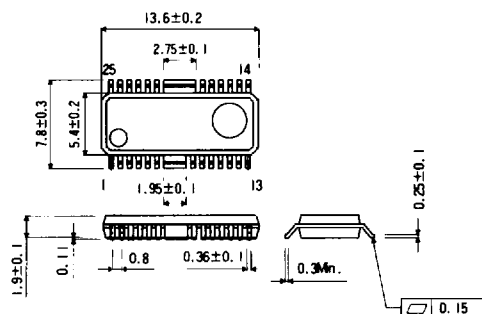
- available in HSOP25 package
- oscillator frequency is 1000.8 kHz
- switchable between 300 and 360 rpm
- low output saturation voltage
- built-in high performance digital servo circuit
- built-in Hall-effect power switch
- built-in current limiter and thermal shutdown

Applications

- floppy disk drive

Dimensions (Units : mm)

BA6476AFP-Y (HSOP25)



BA6476AFP-Y Floppy disk drives: Spindle motor driver

Block diagram

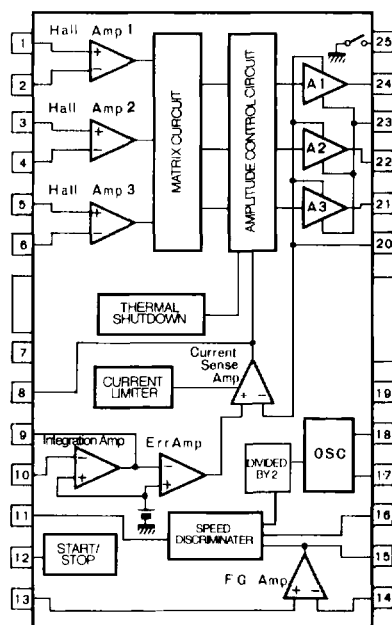


Table 1 Pin description (Sheet 1 of 2)

| Pin no. | Pin name | Function |
|---------|-----------------|--|
| 1 | H1+ | Hall input amplifier 1+ input |
| 2 | H1- | Hall input amplifier 1- input |
| 3 | H2+ | Hall input amplifier 2+ input |
| 4 | H2- | Hall input amplifier 2- input |
| 5 | H3+ | Hall input amplifier 3+ input |
| 6 | H3- | Hall input amplifier 3- input |
| 7 | S-GND | Signal ground |
| 8 | C _{NF} | Connection point for error amplifier output phase compensation capacitor |
| 9 | Err in | Error amplifier input (integration amplifier output). |
| 10 | F in | Integration amplifier positive input |
| 11 | SD out | Speed discriminator output |
| 12 | ST / SP | Start/stop pin |
| 13 | FGin+ | FG amplifier positive input |

Table 1 Pin description (Sheet 2 of 2)

| Pin no. | Pin name | Function |
|---------|-----------------|---|
| 14 | FGin- | FG amplifier inverted input |
| 15 | FGout | FG amplifier output |
| 16 | SC | Speed control input |
| 17 | OSC1 | Oscillator output |
| 18 | OSC2 | Oscillator input |
| 19 | V _{CC} | Power supply |
| 20 | R _{NF} | Driver voltage supply (current sense pin) |
| 21 | A3 | Motor output 3 |
| 22 | A2 | Motor output 2 |
| 23 | P-GND | Driver ground |
| 24 | A1 | Motor output 1 |
| 25 | H-GND | Hall bias switch (ground) |

Absolute maximum ratings (T_a = 25°C)

| Parameter | Symbol | Limits | Unit | Conditions |
|-----------------------|-------------------|------------|------|--|
| Power supply voltage | V _{CC} | 7 | V | |
| Power dissipation | P _d | 1450 | mW | Mounted on 90 am× 50 mm × 1.6 mm glass-epoxy PCB. Reduce power by 11.6 mW/°C for each degree above 25°C. |
| Output current | I _{Omax} | 1000 | mA | |
| Operating temperature | T _{opr} | -25 ~ +75 | °C | |
| Storage temperature | T _{stg} | -55 ~ +150 | °C | |

Recommended operating conditions (T_a = 25°C)

| Parameter | Symbol | Min | Typical | Max | Unit |
|-------------------|-----------------|-----|---------|-----|------|
| Operating voltage | V _{CC} | 4.2 | | 6.5 | V |

BA6476AFP-Y Floppy disk drives: Spindle motor driver**Electrical characteristics (unless otherwise noted, $T_a = 25^\circ\text{C}$, $V_{CC} = 5\text{ V}$)**

| Parameter | Symbol | Min | Typical | Max | Unit | Conditions |
|---------------------------------------|------------------|------|---------|------|---------------------|--|
| Supply current | I_{CC} | 13 | 20 | 28 | mA | |
| Stand-by current | I_{st} | | | 3.0 | μA | Pin 12 = 5 V |
| Hall in-phase input current | V_{HB} | 1.5 | | 4.5 | V | |
| Hall amplifier input sensitivity | V_{Hin} | 60 | | | mV _{pk-pk} | Minimum differential input |
| Output saturation voltage | V_{sat} | | 0.95 | 1.2 | V | V_{sat} at $I_{OUT} = 350\text{ mA}$ total, sum of high and low ends |
| Speed discriminator HIGH output level | V_{DH} | 4.7 | 4.9 | | V | $I = 500\text{ }\mu\text{A}$ (source) |
| Speed discriminator LOW output level | V_{DL} | | 0.1 | 0.25 | V | $I = 500\text{ }\mu\text{A}$ (sink) |
| Integration amp output H | V_{EinH} | 2.8 | 3.0 | 3.2 | V | Pin 10 = 2.0 V |
| Integration amp output L | V_{EinL} | 1.3 | 1.5 | 1.7 | V | Pin 10 = 3.0 V |
| FG amp gain | G_{FG} | 38.5 | 42 | 44.5 | dB | $f = 300\text{ Hz}$ |
| Speed discriminator minimum input | V_{FGmin} | 2.0 | | | mV _{pk-pk} | In terms of FG amplifier input |
| Speed discriminator noise margin | V_{FGnm} | | | 0.5 | mV _{pk-pk} | In terms of FG amplifier input |
| Error amplifier reference potential | V_{Err} | 2.47 | 2.57 | 2.67 | V | Pin 9 potential |
| Control input gain | G_{Err} | -14 | -11 | -7.5 | dB | V_{RNF} with respect to $V_{pin\ 9}$, $R_{NF} = 0.56\text{ }\Omega$. |
| Oscillator frequency | f_{osc} | | 1000.8 | 1100 | kHz | |
| Oscillation frequency accuracy | Δf_{osc} | -0.2 | | +0.2 | % | $f_{osc} = 1000.8\text{ kHz}$ |
| Current limiter voltage | V_{cl} | 175 | 205 | 235 | mV | Measured from pin 20 to V_{CC} . $R_{NF} = 0.56\text{ }\Omega$ |
| Pin 12 HIGH | V_{12H} | 3.0 | | 5.0 | V | Standby state |
| Pin 12 LOW | V_{12L} | 0.0 | | 1.5 | V | Operating state |
| Pin 16 HIGH | V_{16H} | 1.5 | | 5.0 | V | $f_{FG} = 360\text{ Hz}$ (phase locked) |
| Pin 17 LOW | V_{16L} | 0.0 | | 1.0 | V | $f_{FG} = 300\text{ Hz}$ (phase locked) |
| Pin 25 | V_{25} | | 0.8 | 1.0 | V | Pin 25 current = 10 mA (sink) |

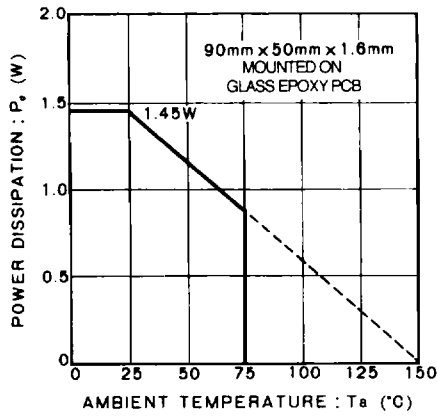


Figure 1

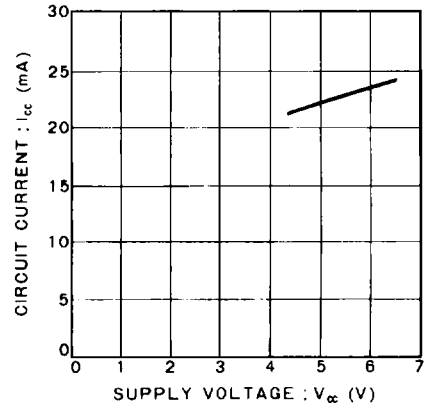


Figure 2

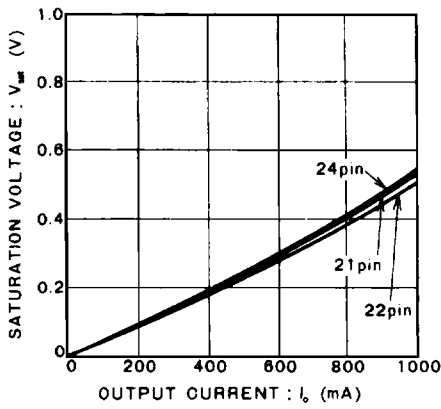


Figure 3

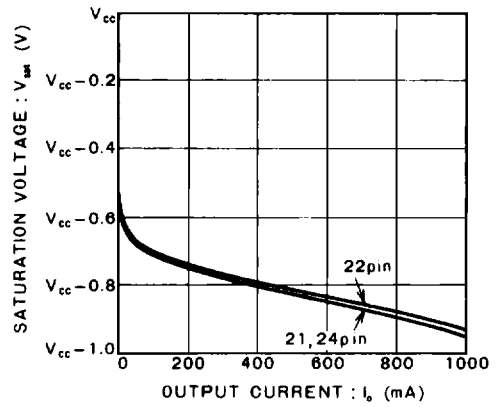


Figure 4

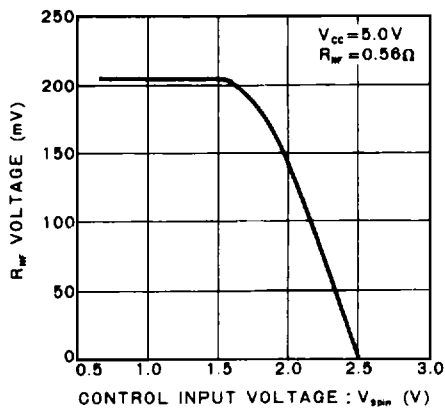


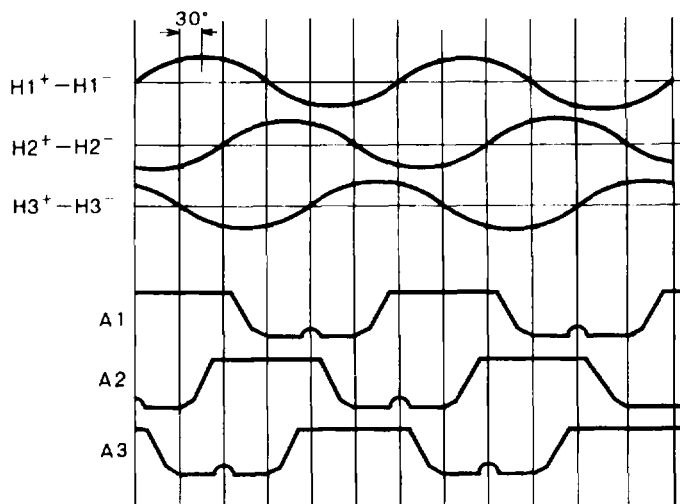
Figure 5

Operation

[Refer to Figure 17]

Hall inputs to driver outputs

Three Hall signals (for the three phases of the motor) are amplified in Hall amplifiers 1, 2, and 3, and applied to a matrix section, where they are further amplified and combined. After voltage-to-current conversion in the amplitude control circuit, the signals are fed to output drivers, which supply drive currents to the motor windings. Figure 6 shows the phase relationships between the Hall signal inputs and the current and voltage waveforms at the outputs of the drivers.

Figure 6 Hall input phase relationships**Error amplifier (pin 9) - current feedback amplifier (pins 8 and 20)**

A control voltage from the integrator circuit is applied to the input of the error amplifier (pin 9). The output of the error amplifier is fed through a current feedback amplifier to the input of the amplitude control circuit, where it acts to control the output current. Pin 20 is the inverting input of the current feedback amplifier.

The external resistor (R_{NF}) is connected between pin 20 and V_{CC} to sense the current flowing in the motor windings. The voltage (across R_{NF}) is provided as feedback. The output current is limited by a current limiter circuit. The output current limit (I_{max}) is determined by the small resistance (R_{NF}) connected between pin 20 and V_{CC} as follows:

$$I_{max}(\text{typical}) = \frac{205 \text{ mV}(\text{typical})}{R_{NF}}$$

Pin 8 is the current feedback amplifier output. To prevent amplifier oscillation, connect the capacitor C_{NF} between this pin and V_{CC} .

Start/stop (pin 12)

The ST/SP pin controls switching between the run and standby states. In the run state, motor power is supplied. In the standby mode, all transistors are off and no motor drive current is supplied, I_{CC} is zero.

Oscillator (pins 17 and 18)

The oscillator generates the master clock for the logic circuits. You can either connect a ceramic resonator and capacitors, as shown in Figure 17, or provide an external clock signal, inputting it directly to pin 18. The maximum operating frequency is 1100 kHz.

Speed selection (Pin 16)

The voltage level at pin 16 determines the modulus of an internal clock divider, which controls the motor speed. The selectable motor speeds are 300 and 360 rpm.

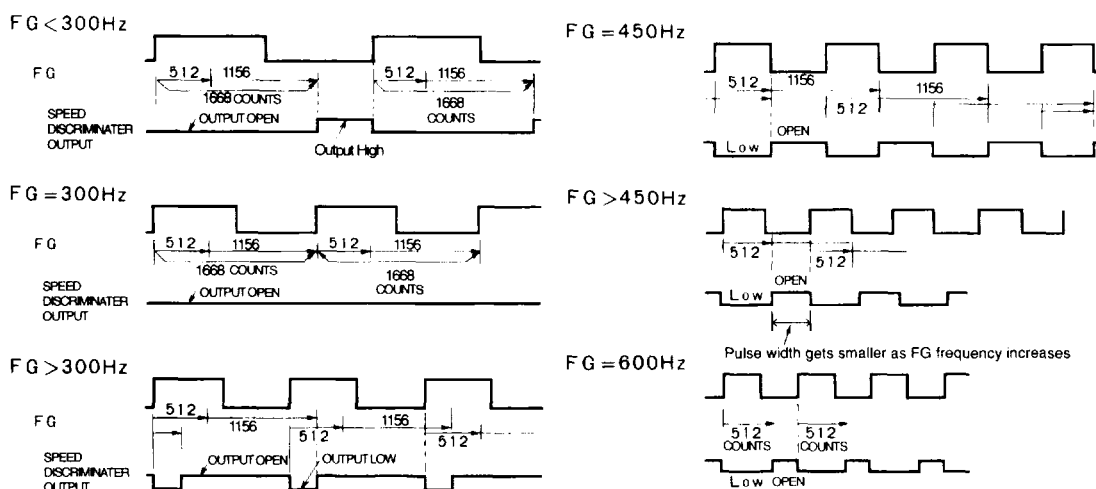
FG amplifier (pins 13, 14 and 15)

The FG amplifier amplifies the FG signal from the motor. The gain is internally set at 42 dB (typical). Following amplification, the FG signal is passed through a Schmitt (hysteresis) circuit and applied as an input to the motor speed logic.

Speed discriminator (pin 11)

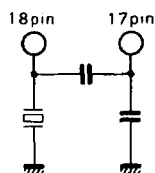
The speed discriminator compares the frequency of the FG signal to that of a reference signal derived by dividing the clock. It then outputs, at pin 11, a PWM signal corresponding to the difference between the FG and the reference signals. (See Figure 7.)

Figure 7 Pin 16 is LOW



Precautions for use**Ceramic resonator external circuit constants**

The proper values for externally-connected circuit constants depend on the ceramic resonator used. The circuit constants should be decided only after you have determined which manufacturer's resonator you will be using, and have studied the resonator. The circuit is shown in Figure 8. The decision as to which capacitors to use should be largely based on the precision and temperature characteristics of the capacitors.

Figure 8 Ceramic resonator external circuit**Oscillator frequency vs. motor speed**

Even if the oscillator frequency, as determined by a ceramic oscillator or external oscillator, is at the specified value, the speed of rotation of the motor (FG amp output, at pin 15) may vary due to variances in integrator circuit constants and the performance characteristics of the motor. You can correct the motor speed to compensate for these variances by adjusting the oscillator frequency. If you are using a ceramic capacitor, the frequency can be finely adjusted by changing the values of the external capacitors. For detailed information on how to do this, consult the ceramic resonator manufacturer.

Thermal shutdown (TSD)

At a temperature of typically 170°C, the TSD circuit opens the A1, A2, and A3 outputs and the motor shuts down. The TSD circuit resets when the temperature falls below 145°C (typically).

Hall element input levels

Excessively large signals on the Hall inputs can cause switching noise. The differential input amplitude should be kept to about 100 mV_{pk-pk} to minimize this effect.

Hall element connection methods

Hall elements can be connected in series or parallel. If the elements are connected in series, however, care must be taken not to allow the Hall element output to exceed the Hall in-phase input range (V_{HB}), as listed in the "Electrical characteristics" table.

Driver section ground pin (pin 23)

Pin 23, the motor current ground, is not connected to the signal ground on pin 7. This pin is in the motor current path, and the conductor trace must be wide enough to carry the motor current.

Cooling fin and pin 7

The cooling fin must be connected to the IC substrate. Pin 7 is the signal ground. Both the cooling fin and pin 7 must be connected to the ground trace of the PCB.

Input and output equivalent circuits

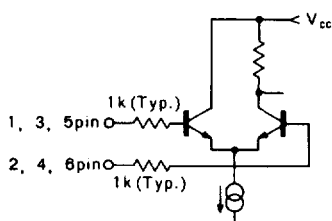


Figure 9 Hall inputs (pins 1 ~ 6)

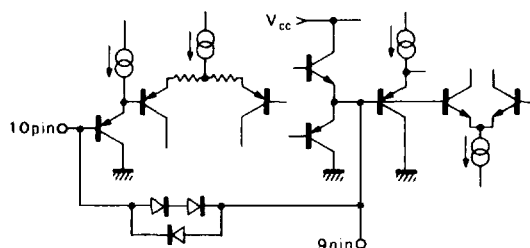


Figure 10 Error amplifier (pins 9, 10)

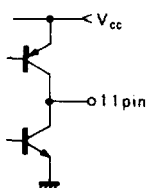


Figure 11 Speed discriminator (pin 11)

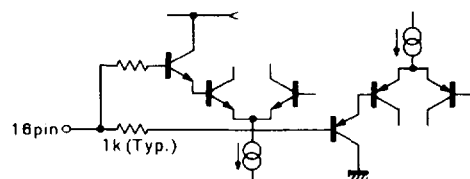


Figure 12 Speed controller (pin 16)

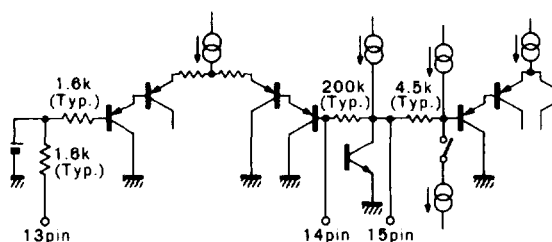


Figure 13 FG control amplifier (pins 13 ~ 15)

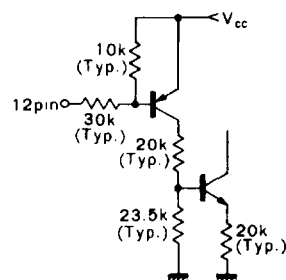


Figure 14 Start/stop circuit (pin 12)

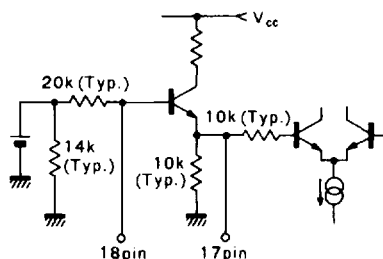


Figure 15 Oscillator (pins 17 and 18)

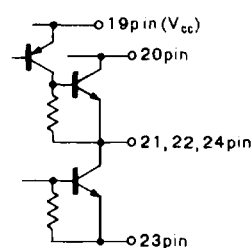


Figure 16 Motor output (pins 19 ~ 24)

Figure 17 Application example

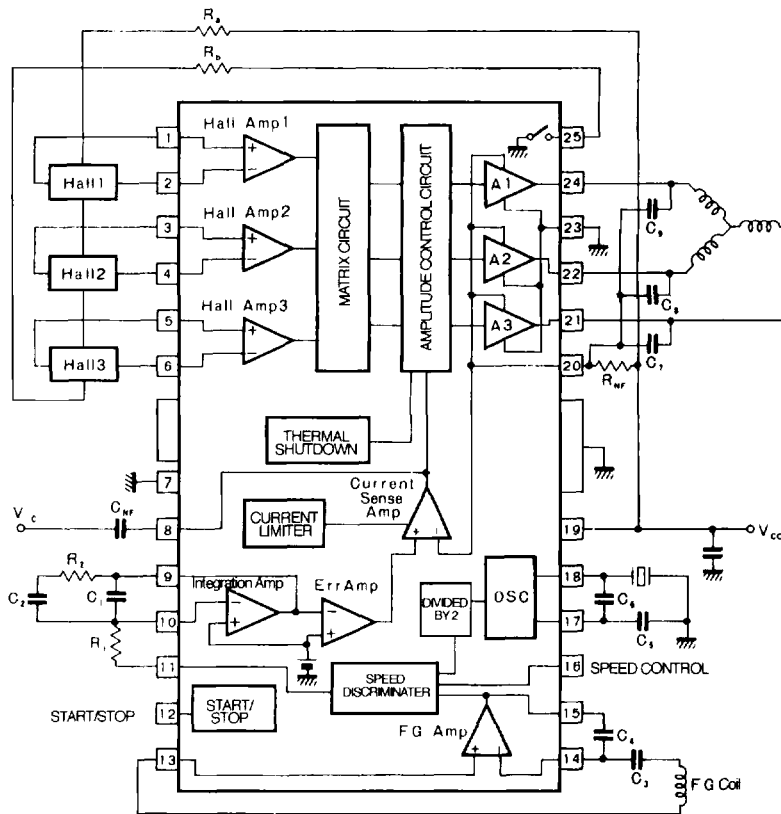


Table 2 External component function

| Component | Function |
|-----------------|--|
| R_a, R_b | Determine Hall element current, output bias |
| C_{NF} | Output current phase compensation capacitors |
| C_1 | Integration circuit constant |
| R_1 | Integration circuit constant |
| C_2 | Integration circuit constant |
| R_2 | Integration circuit constant |
| C_3 | Integration circuit constant |
| C_4 | FG amp high frequency cut-off constant |
| C_5, C_6 | Oscillator capacitors |
| C_7, C_8, C_9 | For output waveform stabilization |