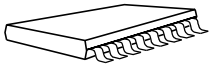
TMC 428 – DATA SHEET

Intelligent Triple Stepper Motor Controller with Serial Peripheral Interfaces



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Features

The TMC428 is a miniaturized high performance stepper motor controller. It controls up to three 2-phase stepper motors. All motors can operate independently. The TMC428 allows up to 6 bit micro step resolution– which is up to 64 micro steps per full step –individually selectable for each motor. Once initialized, it performs all real time critical tasks autonomously based on target positions and velocities, which may be altered on-the-fly. So, an inexpensive micro controller together with the TMC428 forms a complete motion control system. The micro controller is free to do application specific interfacing and high level control functions. Both, the communication with the micro controller and with one to three daisy chained stepper motor drivers take place via two separate 4 wire serial peripheral interfaces. The TMC428 directly connects to SPI™* smart power stepper motor drivers.

- Controls up to three 2-phase stepper motors
- Serial 4-wire interface for µC with easy-to-use protocol
- Configurable interface for SPI™ motor drivers
- Different types of SPI™ stepper motor driver chips may by mixed within a single daisy chain
- Communication on demand minimizes traffic to the SPI™ stepper motor drivers chain
- Programmable SPI™ data rates up to 1 Mbit/s
- Wide range for clock frequency – can use CPU clock up to 16 MHz
- Internal 24 bit wide position counters
- Full step frequencies up to 20 kHz
- Read-out facility for actual motion parameters (position, velocity, acceleration) and driver status
- Individual micro step resolution of {64, 32, 16, 8, 4, 2, 1} micro steps via built-in sequencer
- Programmable 6 bit micro step table with up to 64 entries for a quarter sine wave period
- Built-in ramp generators for autonomous positioning and speed control
- On-the-fly alteration of target motion parameters (like position, velocity, acceleration)
- Automatic acceleration dependent current control (power boost)
- Power down mode (100 µA) with transparent wake-up for normal operation (typical 5 mA @ 16 MHz)
- 3.3V or 5V operation with CMOS / TTL compatible IOs (all inputs Schmitt-Trigger)
- Ultra small 16 pin SSOP package (optional 24 pin SOIC24 package)
- Integrated power-on-reset

* *SPI is Trademark of Motorola, Inc.*

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General Description

The TMC428 is a miniaturized high performance stepper motor controller with a low price for high volume automotive and industrial motion control applications as well. Once initialized, the TMC428 controls up to three independent 2-phase stepper motors from each other. The low price makes it attractive also for those applications, where only one or two stepper motors have to be controlled simultaneously.

The TMC428 performs all real time critical tasks autonomously. Thus a low cost micro controller is sufficient to perform the tasks of initialization, application specific interfacing, and to specify target positions and velocities. The TMC428 allows on-the-fly alteration of all target parameters. Read-back option for all internal registers simplifies programming. The TMC428 can perform up to 2^{23} steps respectively micro steps fully independent from the micro controller with its internal position counters. The step resolution– individually programmable for each stepper motor –ranges from full step, half step, up to 6 bit micro stepping (64 micro steps / full step) for precise positioning and noiseless stepper motor rotation. Optionally, the micro step table– common for all motors –can be adapted to motor characteristics to further enhance smooth, low toque ripple application.

The TMC428 uses serial interfaces for communication with the micro controller and for the stepper motor drivers. The serial interface for the micro controller uses a fixed length of 32 bits with a simple protocol, directly connecting to SPI™ interfaces. The serial interface to the stepper motor drivers is flexible configurable for different types– even from different vendors –with up to 64 bit length for the SPI daisy chain. Our own smart power stepper motor drivers TMC288 and TMC289 perfectly fit to the TMC428. Without additional hardware, drivers with same serial interface polarities of chip select and clock signals may be mixed in a single chain. To mix drivers with different serial interface polarities, additional inverters (e.g. 74HC04, 74HC14) are required. For those driver chips without serial data send back option, the variant of the TMC428 with two additional chip select outputs is proposed. The TMC428 sends data to the driver chain on demand only, which minimizes the interface traffic and reduces the power consumption.

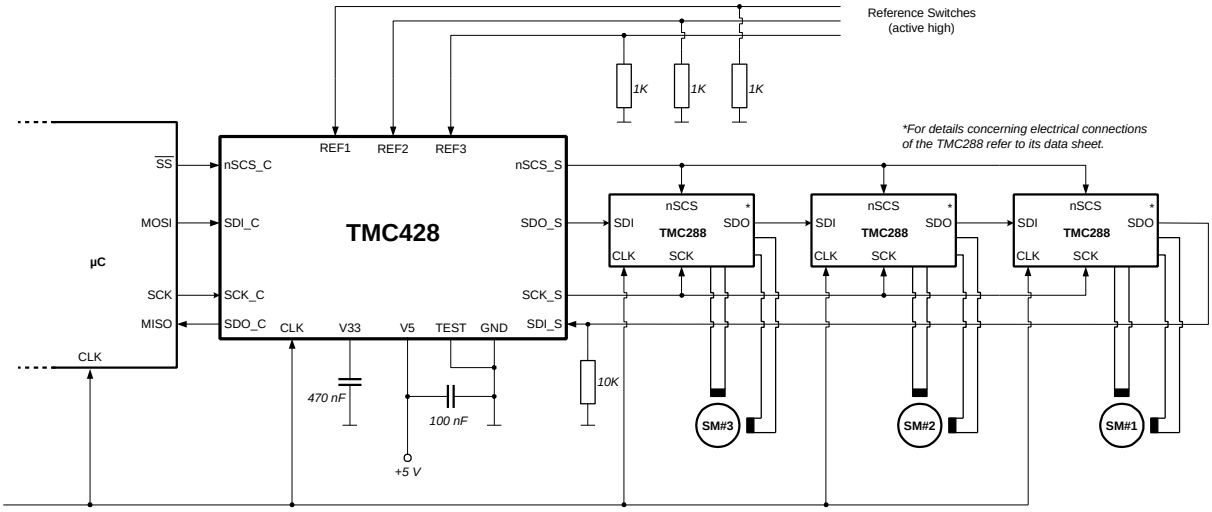

Figure 1: TMC428 application environment with TMC428 in SSOP16 Package

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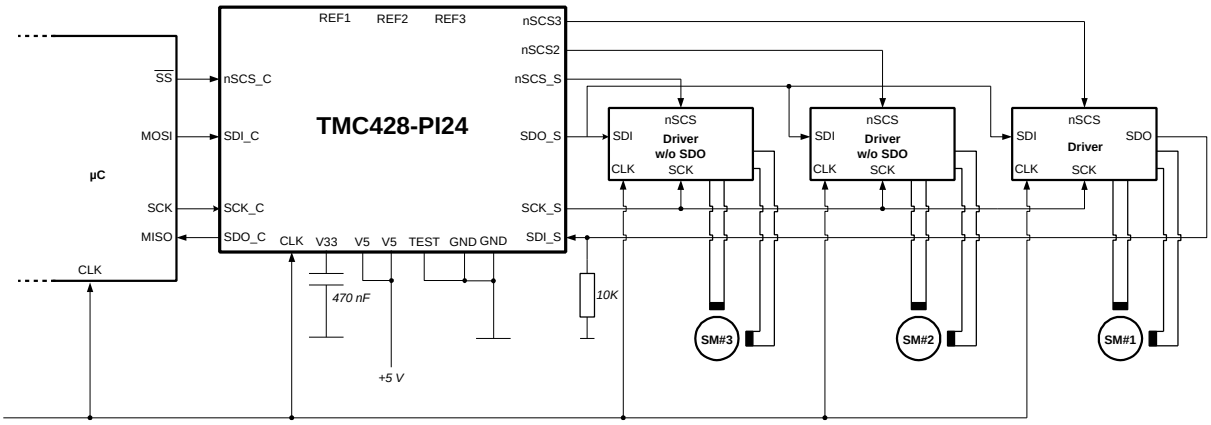

Figure 2 – Usage of Drivers without Serial Data Output (SDO) with TMC428 in SOIC24 Package

The maximum SPI™ data rate is the clock frequency divided by 16. The maximum step frequency depends on the total length of the datagrams send to the SPI™ stepper motor driver chain. At a clock frequency of 16 MHz, with a daisy chain of three SPI™ stepper motor drivers of 16 bit datagram length each, the maximum *full step* frequency is 16 MHz / 16 / (3 * 16) which is approximately 20 kHz. But, the micro step rate may be higher, even if the stepper motor driver loses micro steps due to SPI™ data rate limit, as long as the number of skipped micro steps is less then a full step. In this respect, one should remember, that at high step rates– respectively pulse rates –the differences between micro stepping and full step excitation vanishes.

The TMC428 has four different modes of motion, programmable individually for each stepper motor, named RAMPMODE, SOFTMODE, VELOCITYMODE, and HOLDMODE. For positioning applications the RAMPMODE is most suitable, whereas for constant velocity applications the VELOCITYMODE is. In RAMPMODE, the user just sets the position and the TMC428 calculates a trapezoid velocity profile and drives autonomously to the target position. During motion, the position may be altered arbitrarily. The SOFTMODE is similar to the RAMPMODE, but the decrease of the amount of velocity during deceleration is done with a soft, exponentially shaped velocity profile. In VELOCITYMODE, a target velocity is set by the user and the TMC428 takes into account user defined limits of velocity and acceleration. In HOLDMODE, the user sets target velocities, but the TMC428 ignores any limits of velocity and acceleration, to realize arbitrary velocity profiles, controlled completely by the user.

The TMC428 has capabilities to generate interrupts depending on different stepper motor conditions chosen by an interrupt mask. However, status bits send back automatically to the micro controller each time it sends data to the TMC428 are sufficient for polling techniques. Error condition handling of stepper motor drivers can be handled by read out option of data bits– up to 48 bits, which is sufficient for most stepper motor drivers – send back from the drivers to the TMC428.

Without any additional logic, in the default reference switch mode, the three reference switch inputs are defined as left side reference switches, one for each stepper motor. In another mode, the 1st reference input is defined as left reference switch input of motor number one, the 2nd reference input is defined as left reference switch input of motor number two, and the 3rd reference input is defined as right reference switch of stepper motor number one. In that mode, there is no reference switch input available for stepper motor three. With an external multiplexer 74HC157 any stepper motor may have a left and a right reference switch.

Serial stepper motor drivers provide different status bits (driver active, in-active, ...) and error bits (short to ground, wire open, ...). To have access to those error bits, datagrams with a total length up to 48 bits

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send back from the stepper motor driver chain to the TMC428 are buffered within two 24 bit wide registers. The micro controller has direct access to these registers. Although, the TMC428 provides datagrams with up to 64 bits, only the last 48 bits send back from the driver chain are buffered for read out by the micro controller. This is because buffering of 3 time 16 bits is sufficient for a chain of three TMC288 stepper motor drivers (see Figure 1) and most other drivers– also from other vendors –sending back up to 16 bits.

From the user's point of view, the TMC428 consists of a set of registers, accessed by an micro controller (µC) via a serial interface in an uniform way. Each time, a µC sends a datagram to the TMC428, it simultaneously receives a datagram from the TMC428. Each datagram contains all necessary information to address and to select between read and write for both, the registers and the on-chip memory. This simplifies the communication with the TMC428 and makes the programming easy. Some micro controllers have a SPI™ hardware interface, which directly connects to the serial four wire micro controller interface of the TMC428. For micro controllers without SPI™ hardware interface one just has to write a subroutine sending a 32 bit vector via a serial four wire interface if called, returning that 32 bit vector received from the TMC428.

Notation of Number Systems

Decimal numbers are used as usual without additional identification. Binary numbers are identified by a prefixed % character. Hexadecimal numbers are identified by a prefixed $ character. So, for example the decimal number 42 in the decimal system is written as %101010 in the binary number system, and it is written as $2A in the hexadecimal number system.

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Pinning

There are two package variants of the TMC428 available. The smaller SSOP16 package is sufficient for our TMC288 SPI™ stepper motor drivers with up to three drivers in a chain and for most SPI™ stepper motor drivers from other vendors. Some SPI™ stepper motor drivers from other vendors have no serial data output and can not simply be arranged in a daisy chain to drive more than one motor. So, the bigger SOIC24 package is provided for those stepper motor drivers from other vendors only. All inputs are Schmitt-Trigger. Possibly unused inputs (**REF1**, **REF2**, **REF3**, **SDI_S**) need to be connected to ground.

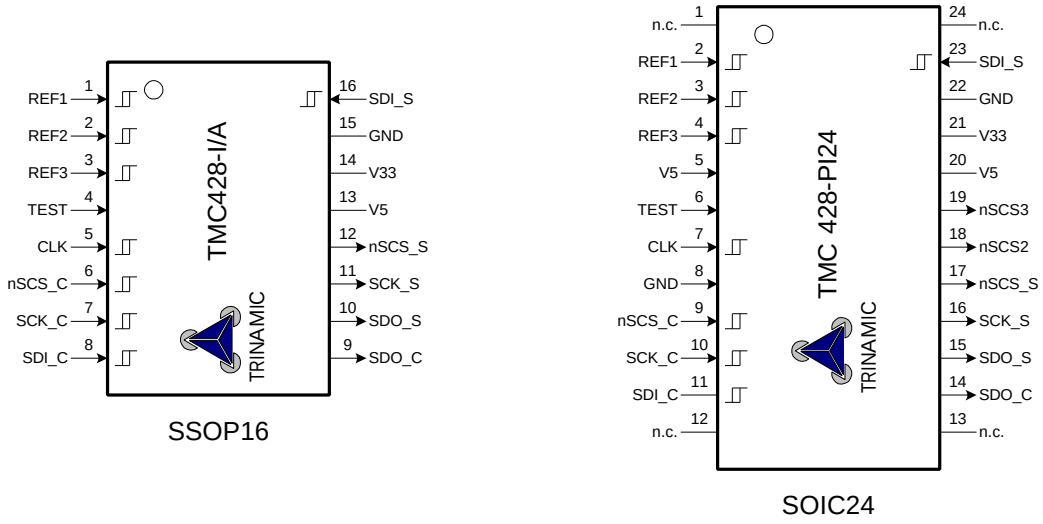

Figure 3: TMC428 pin out

Pin	SSOP16	SOIC24	In/Out	Description
Reset	-	-	-	internal power-on reset
CLK	5	7	I	clock input
nSCS_C	6	9	I	low active SPI chip select input driven from µC
SCK_C	7	10	I	serial data clock input driven from µC
SDI_C	8	11	I	serial data input driven from µC
SDO_C	9	14	O	serial data output to µC input
nSCS_S	12	17	O	SPI chip select signal to stepper motor driving chain
nSCS2	-	18	O	SPI chip select signal (SOIC24 package only)
nSCS3	-	19	O	SPI chip select signal (SOIC24 package only)
SCK_S	11	16	O	serial data clock output to SPI stepper motor driver chain
SDO_S	10	15	O	serial data output to SPI stepper motor driver chain
SDI_S	16	23	I	serial data input from SPI stepper motor driver chain
REF1	1	2	I	reference switch input 1
REF2	2	3	I	reference switch input 2
REF3	3	4	I	reference switch input 3
V5	13	5,20		+5V supply / +3.3V supply
V33	14	21		470 nF ceramic capacitor pin / +3.3V supply
GND	15	8, 22		ground
TEST	4	6	I	must be connected to ground
n.c.	-	1, 12, 13, 24	-	not connected

Table 1 - TMC428 pin out

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Functional Description and Block Diagram

From the user's point of view, the TMC428 consists of a set of registers of different units and on-chip RAM (see. Figure 4), accessed via the serial µC interface in an uniform way. The serial interface to the micro controller is easy to use. It uses just a simple protocol with fixed length datagrams for read and write access. The serial interface to the stepper motor driver chain has to be configured by an initialization sequence which writes the configuration into the on-chip RAM. Once configured the serial driver interface works autonomously. The internal multiple port RAM controller of the TMC428 autonomously takes care of access scheduling. So, the user may read and write both, registers and on-chip RAM at any time. The registers hold global configuration parameters and the motion parameters. The on-chip RAM stores the configuration of the serial driver interface and the micro step table.

The ramp generator monitors the motion parameters stored in its registers. If required, it generates step pulses automatically taking user defined motion parameter limits into account. The serial driver interface automatically sends datagrams to the stepper motor driver chain on demand. The ramp generator calculates velocity profiles controlling the pulse generator. The micro step unit (including sequencer) processes step pulses from the pulse generator– representing micro steps, half steps, or full steps depending on the selected step resolution –and makes the results available to the serial driver interface. The ramp generator also interfaces the reference switch inputs. Unused reference switches have to be connected to ground. A pull-down resistor is necessary at the SDI_S input of the TMC428 for those serial peripheral interface stepper motor drivers that set their serial data output to high impedance 'Z' while inactive.

The interrupt controller continuously watches reference switches and ramp generator conditions and generates an interrupt if required. To save pins, the interrupt signal is multiplexed to the SDO_C signal. This signal becomes the low active interrupt signal called nINT while nSCS_C is high (see Figure 5). So, if the micro controller disables the interrupt during access to the TMC428 and enables the interrupt otherwise, the multiplexed interrupt output of the TMC428 behaves like a dedicated interrupt output. For polling, the TMC428 sends the status of the interrupt signal to the micro controller with each datagram.

To drive a stepper motor to a new target position, the user just overwrites the target position of that stepper motor by sending a datagram to the TMC428. To run a stepper motor with a target velocity, the user just writes it into a register assigned to a stepper motor.

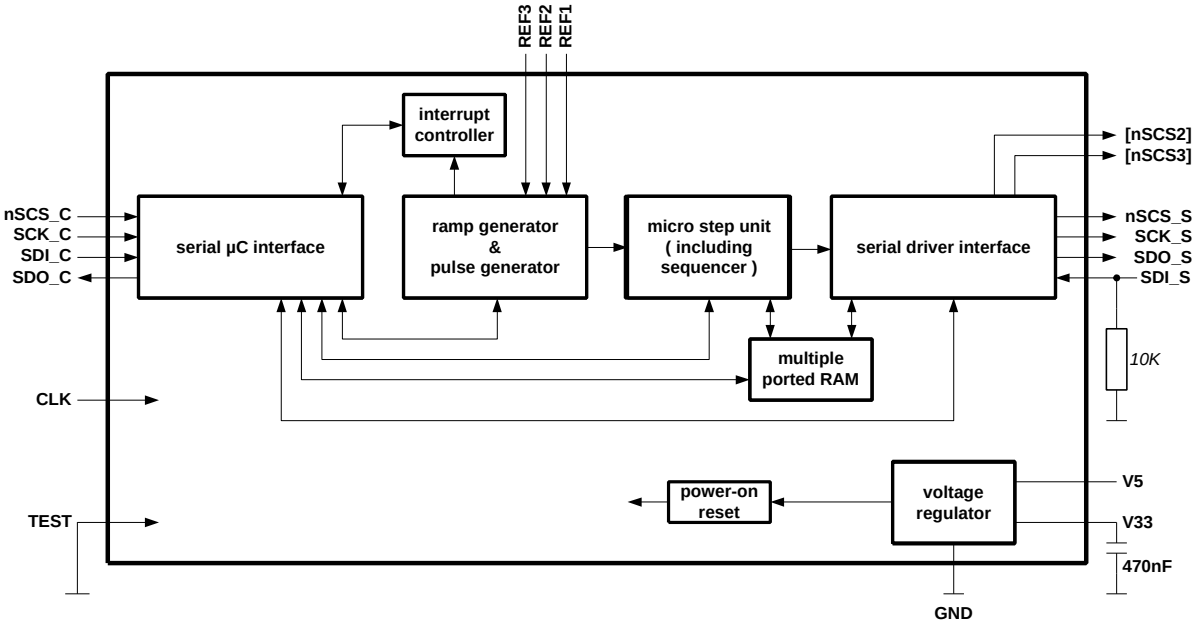

Figure 4: TMC428 functional block diagram

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Serial Peripheral Interfaces

The four pins named SCS_C, SCK_C, SDI_C, SDO_C form the serial micro controller interface of the TMC428. The communication between the micro controller and the TMC428 takes place via 32 bit datagrams of fixed length. Concerning communication, the µC is the master and the TMC428 is the slave, with the TMC428 in turn being the master for the stepper motor driver daisy chain. Similar to the micro controller interface, the TMC428 uses a four wire serial interface for communication with the stepper motor driver daisy chain. The four pins named SCS_S, SCK_S, SDO_S, SDI_S form the serial stepper motor driver interface. Stepper motor drivers with parallel inputs can be used in connection with the TMC428 with some additional glue logic.

Serial Peripheral Interface for µC

The serial micro controller interface of the TMC428 behaves as a simple 32 bit shift register shifting serial data SDI_C in with the rising edge of the clock signal SCK_C and copying the content of the 32 shift register with the rising edge of the selection signal nSCS_C into a buffer register of 32 bit length. The serial interface of the TMC428 sends back data read from registers or read from internal RAM back immediately via the signal SDO_C. It processes serial data synchronously to the clock signal CLK.

Because of the on-the-fly processing of the input data stream, the serial micro controller interface of the TMC428 accepts the serial data clock signal SCK_C with at least a duration (tSCKCL + tSCKCH = 3*tCLK + 3 * tCLK) of a total number of six clock cycles of CLK as outlined in the timing diagram Figure 5. The data signal from the micro controller changes with the falling level of the serial data clock input SCK_C. The maximum duration (tSCKCL + tSCKCH) of the serial data clock signal SCK_C is unlimited. But three clock cycles is the lower limit for the low level (tSCKCL ≥ 3 * tCLK) of the serial data clock SCK_C and for the high level (tSCKCH ≥ 3 * tCLK) it.

A complete serial datagram frame has a fixed length of 32 bit. While the data transmission from the micro controller to the TMC428 is idle, the low active serial chip select input nSCS_C and also the serial data clock signal SCK_C are set to high. While the signal nSCS_C is high, the TMC428 assigns the status of the internal low active interrupt signal named nINT to the serial data output SDO_C (Figure 5). The serial data input SDI_C of the TMC428 has to be driven by the micro controller. In contrast to other SPI™ compatible devices, the SDO_C signal of the TMC428 is always driven. It will never be in high impedance 'Z'.

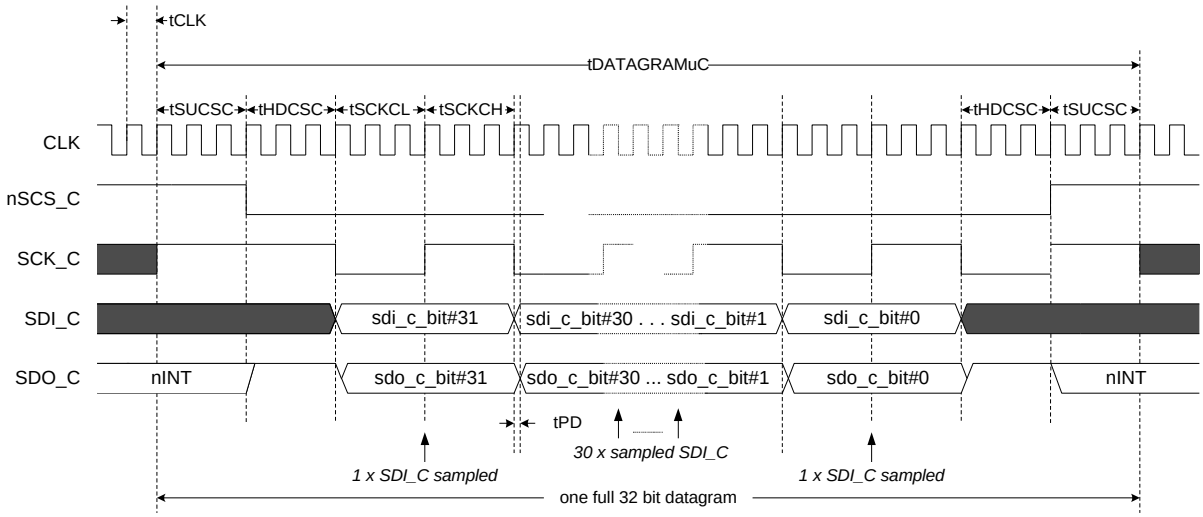

Figure 5 - Timing diagram of the serial µC interface

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The signal nSCS_C has to be assigned at least three clock cycles (tSUCSC) high before sending a 32 bit datagram. To initiate a transmission, the signal nSCS_C has to be set to low. Three clock cycles later (tHDCSC) the serial data clock may go low. The most significant bit (MSB) of a 32 bit wide datagram comes first and the least significant bit (LSB) is transmitted as the last one. To complete the data transmission the serial data clock SCK_C has to set to high first and at least three clock cycles later, the signal nSCS_C has to be assigned to high. So, nSCS_C and SCK_C change in opposite order from low to high at the end of a transmission as these signals change from high to low at the beginning.

Automatic Power-On Reset

The TMC428 performs an automatic power-on reset (see). To be sure, that the power-on reset has been completed before starting communication with the TMC428, one should wait at least for 10 µs before sending the first datagram, which is approximately one datagram at 16 MHz clock frequency (tDATAGRAM16MHzMin = (1+32+1) * 6 / 16 MHz = 12.75 µs).

Serial Peripheral Interface to Stepper Motor Driver Chain

The timing of the serial stepper motor interface is similar to that of the micro controller interface. It directly connects to SPI™ smart power stepper motor drivers. The bit mapping is configurable individually for each stepper motor driver chip of the daisy chain. From the micro controllers point of view, it simply sends a fixed sequence of datagrams to the TMC428 to initialize it after power-up. Once initialized by the micro controller, the TMC428 autonomously generates the datagrams for the stepper motor driver daisy chain without any additional interventions of the micro controller.

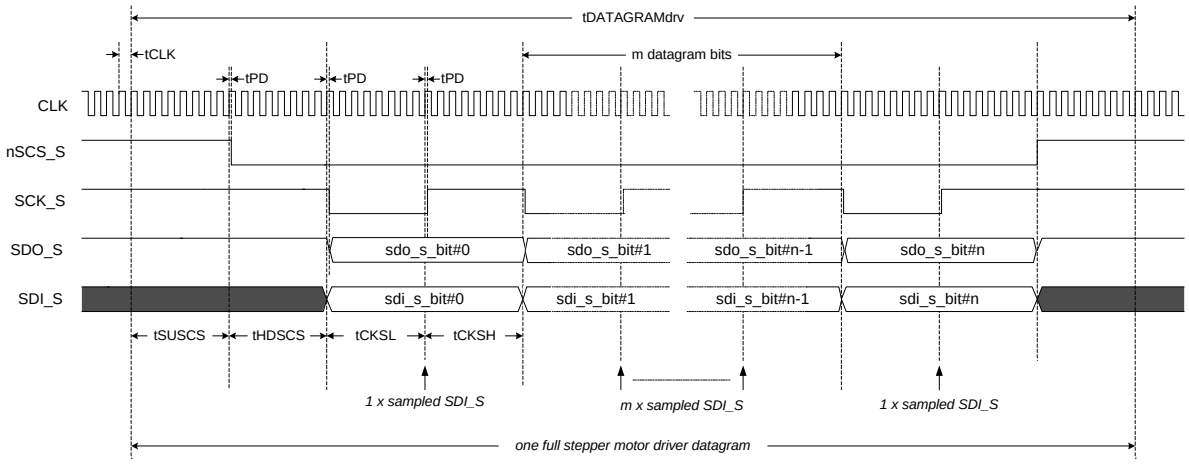

Figure 6: Timing diagram of the serial stepper motor driver interface

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The bit mapping for each stepper motor driver is composed of so called *primary signal bits* provided by the micro step unit of the TMC428 individually for each stepper motor. Each primary signal bit is represented by a five bit code word called *primary signal code*. The order of primary signal bits to be send to the stepper motor driver daisy chain is defined by the order of primary signal code words in the configuration RAM area. To distinguish different stepper motor drivers, an additional bit called *next motor bit* (NxM-Bit) is prefixed to the five bit wide primary signal code words. So, the total data word width is six bit. Each NxM-Bit effects an incrementation of an internal stepper motor address until processing– sending serially datagram bits –of the last stepper motor is completed. For this, a parameter called LSMD (last stepper motor driver) has to be programmed during initialization after power up. So, the codes written into the serial interface configuration RAM area represent the mapping of control signals provided by the micro step units to control bits of the drivers. It might be noted here, that configuring the serial driver interface is much easier as it might seem here. It is explained in detail, illustrated by examples below.

The timing of the serial driver interface is programmable in a wide range. The clock divider provides 16 up to 512 clock cycles (tCLK) for a serial driver interface data clock period. The default duration of a clock period (tSCKCL+tSCKCH) of the signal nSCS_S is 16+16=32 clock periods of the clock signal CLK. The minimal duration of a serial interface clock period (tSCKCL+tSCKCH) is 8+8=16 clock cycles of signal CLK as outlined in Figure 6. Also, the polarities of the signals nSCS_S and SCK_S are programmable to use driver chips from other vendors with inverted polarities without additional glue logic.

The input SDI_S of the serial driver interface must always be driven to a defined level. So, to avoid high impedance ('Z') at that input pin, a pull-up resistor or a pull-down resistor of 10 KΩ is necessary at that input, if the stepper motor driver chain is idle.

Symbol	Parameter	Min	Typ	Max	Unit
tSUCSC	Setup Clocks for nSCS_C	3		∞	CLK periods
tHDCSC	Hold Clocks for nSCS_C	3		∞	CLK periods
tSCKCL	Serial Clock Low	3		∞	CLK periods
tSCKCH	Serial Clock High	3		∞	CLK periods
tDAMAGRAMuC	Datagram Length	3+3 + 32*6 + 3+3 = 204		∞	CLK periods
tDAMAGRAMuC	Datagram Length	12.75		∞	µs
fCLK	Clock Frequency	0		16	MHz
tCLK	Clock Period tCLK = 1 / fCLK	62.5		∞	ns
tPD	CLK-rising-edge-to-Output Propagation Delay		5		ns

Table 2 - Timing Characteristics of the Serial Microcontroller Interface

Symbol	Parameter	Min	Typ	Max	Unit
tSUSCS		8	16	256	CLK periods
tHDSCS		8	16	256	CLK periods
tCKSL		8	16	256	CLK periods
tCKSH		8	16	256	CLK periods
tDAMAGRAMdrv	Datagram Length	8+8+1*16+8+8=48		512+64*512+512= 33792	CLK periods
tDAMAGRAMdrv	Datagram Length	3		2112	µs
fCLK	Clock Frequency	0		16	MHz
tCLK	Clock Period tCLK = 1 / fCLK	62.5		∞	ns
tPD	CLK-rising-edge to Outputs Delay		5		ns

Table 3 - Timing Characteristics of the Serial Stepper Motor Driver Interface

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Datagram Structure

The micro controller (µC) communicates with the TMC428 via the four wire (nSCS_C, SCK_C, SDI_C, SDO_C) serial interface. Each datagram send to the TMC428 via the pin SDI_C and each datagram received from the TMC428 via the pin SDO_C is 32 bit long. The first bit send is the MSB (most significant bit named sdi_c_bit#31 at Figure 5). The last bit send is the LSB (least significant bit named sdi_c_bit#0 at Figure 5). During reception of a datagram, the TMC428 immediately sends back a datagram of the same length to the micro controller. That datagram send back is the result of the request given by the datagram from the micro controller.

A request to read out one register of the TMC428 immediately turns back a datagram with the contents of that register addressed by the datagram send from the micro controller. In case of writing data into registers, the TMC428 sends back 8 status bits and 24 data bits set to '0'. Datagrams send from the micro controller to the TMC428 have the form:

32 bit DATAGRAM send from a µC to the TMC428 via pin SDI_C

31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
RRS	**ADDRESS**						**RW**	**DATA**																							

The 32 bit wide datagrams send to the TMC428 are assorted in four groups of bits: **RRS** (register RAM select) selecting either registers or on-chip RAM; **ADDRESS** bits addressing memory within the register set or within the RAM area; **RW** (read write) bit distinguishing between read access and write access; **DATA** bits for write access– for read access these bits are *don't care* and should be set to '0'. Different internal registers of the TMC428 have different lengths. So, for some registers only a subset of these 24 data bit is really necessary, and unnecessary data bits should be set to '0'. Some addresses access more than a single register simultaneously. In that cases, unnecessary data bits should also be set to '0'.

The 32 bit wide datagrams received by the µC from the TMC428 are assorted in two groups of bits: **STATUS BITS** and **DATA BITS**. The status bits, send back with each datagram, carry the most important information about internal states of the TMC428 and the settings of the reference switches. These datagrams have the form:

32 bit DATAGRAM send back from the TMC428 to a µC via pin SDO_C

31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
STATUS BITS								**DATA BITS**																							
nINT	**CDGW**	**SM3**		**SM2**		**SM1**																									
		RS3	**xEQt3**	**RS2**	**xEQt2**	**RS1**	**xEQt1**																								

The status bit **nINT** is the internal low active interrupt controller output signal. Handling of interrupt conditions without using interrupt techniques is possible by polling this status bit. The interrupt signal is also directly available at the SDO_C pin of the TMC428 if nSCS_C is high. The pin SDO_C may directly be connected to an interrupt input of the micro controller. Because the SDO_C / nINT output is multiplexed,

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the micro controller has to disable its interrupt input while it sends a datagram to the TMC428, because SDO_C signal– driven by the TMC428 –alternates during datagram transmission.

For initialization purposes, the TMC428 enables direct communication between the micro controller and the stepper motor driver chain by sending a so called *cover datagram*. The position **cover_position** and actual length **cover_len** of a cover datagram is specified by writing them into a common register. Writing an up to 24 bit wide cover datagram to the register **cover_datagram** will fade in that cover datagram into the next datagram send to the stepper motor driver chain. As a default setting, the TMC428 only sends datagrams on demand. Optionally, continuous update – periodic sending of datagrams to the stepper motor driver chain – is also possible. So, the status bit named **CDGW** (cover datagram waiting) is a handshake signal for the micro controller in regard to the datagram covering mechanism. This feature is necessary to enable direct data transmission from a micro controller to the stepper motor driver chips for initialization purposes.

The status bits **RS3, RS2, RS1** represent the settings of the reference switches. But, the reference switch inputs REF3, REF2, REF1 are not mapped directly to these status bits. Rather, the reference switch inputs may have different functions, depending on programming (see page 20). The three status bits **xEQt3, xEQt2, xEQt1** indicate individually for each stepper motor, if it has reached its target position. The status bits **RS3, RS2, RS1** and bits **xEQt3, xEQt2, xEQt1** can trigger an interrupt or enable simple polling techniques.

Simple Datagram Examples

The % prefix– normally indicating binary representation in this data sheet –is omitted for the following datagram examples. Assuming, one would like to write (rw=**0**) to a register (rrs=*0*) at the address %001101 the following data word %0000 0000 0000 0001 0010 0011, one would have to send the following 32 bit datagram

*0*110011**0**00000000000000000100100011

to the TMC428. With inactive interrupt (nINT=1), no cover datagram waiting (CDGW=0), all reference switches inactive (RS3=0, RS2=0, RS1=0), and all stepper motors at target position (xEQt3=1, xEQt2=1, xEQt1=1) the status bits would be %*10010101* the TMC428 would send back the 32 bit datagram:

*10010101*00000000000000000000000

To read (rw=**1**) back that register write before, one would have to send the 32 bit datagram

*0*110011**1**00000000000000000000000

to the TMC428 and would get back from it the datagram

*10010101*00000000000000000100100011.

Write (rw=**0**) access to on-chip RAM (rrs=**1**) to an address %111111 occurs similar to register access, but with rrs=1. To write two 6 bit data words %100001 and %100011 to successive pair-wise RAM addresses %1111110 and %1111111 (%100001 to %1111110 and %100011 to %1111111) which are commonly addressed by one datagram (see pages 13 and 29), one would have to send the datagram

*1*111111**0**00000000010001100100001.

To read (rw=**1**) from that on-chip memory address, one would have to send the datagram
*1*111111**1**00000000000000000000000.

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Address Space Partitions

The address space is partitioned in different ranges. Each of the up to three stepper motors has a set of registers individually assigned to it, arranged within a contiguous address space. An additional set of registers within the address space holds some global parameters common for all stepper motors. One dedicated global parameter register is essential for the configuration of the serial four wire stepper motor driver interface. One half of the on-chip RAM address space holds the configuration parameters for the stepper motor driver chain. The other half of the on-chip RAM address space is provided to store a micro step table if required. The first seven datagram bits (*sdi_c_bit#31* and *sdi_c_bit#30* ... *sdi_c_bit#25*, respectively *RRS* and *ADDRESS*) address the whole address space of the TMC428.

address ranges (incl. RRS)			assignment	
%000 0000	. . .	%000 1111	16 registers for stepper motor #1	registers with up to 24 bits
%001 0000	. . .	%001 1111	16 registers for stepper motor #2	
%010 0000	. . .	%010 1111	16 registers for stepper motor #3	
%011 0000	. . .	%011 1110	15 common registers	
		%011 1111	1 global parameter register	
%100 0000	. . .	%101 1111	32 addresses of 2x6 bit for driver chain configuration	RAM 128x6 bit
%110 0000	. . .	%111 1111	32 addresses of 2x6 bit for micro step table	

Table 4 - TMC428 address space partitions

The stepper motors are controlled directly by writing motion parameters into associated registers. Only one register write access is necessary to change a target motion parameter. E.g. to change the target position of one stepper motor, a micro controller has to send only one 32 bit datagram to the TMC428. The same is true for changing a target velocity. Some parameters are composed as a single data word at a single address. Those parameters– initialized once and unchanged during operation –have to be changed commonly. Access to on-chip RAM addresses takes always place to two successive RAM addresses. So, always two data words are modified with each write access to the on-chip RAM. Once initialized after power-up, the content of the RAM is usually left unchanged.

Read and Write

Read and write access is selected by the RW bit (sdi_c_bit#24) of the datagram send from the µC to the TMC428. The on-chip configuration RAM and the registers are writeable with read-back option. Some addresses are read-only. Write access (**RW**=0) to some of those read-only registers triggers initialization.

Register Set

The register address mapping is given in Table 5 on page 14. These registers are initialized internally during power-up. During power-up initialization, the TMC428 sends no datagrams to the stepper motor driver chain. *Please note*: Before writing target parameters to the register set, the RAM has to be initialized first.

RAM Area

The RAM address mapping is given in Table 12 page 30. The on-chip RAM is *NOT* initialized internally during power-up. The RAM has to be initialized by the micro controller first after power-up.

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32 bit DATAGRAM send from a µC to the TMC428 via pin SDI_C

31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
RRS	ADDRESS						RW	DATA																							

	smda		IDX				
0	0	0	0	0	0	0	x_target
			0	0	0	1	x_actual
			0	0	1	0	v_min
			0	0	1	1	v_max
			0	1	0	0	v_target
			0	1	0	1	v_actual
			0	1	1	0	a_max
			0	1	1	1	a_actual
			1	0	0	0	is_agtat, is_aleat, is_v0, a_threshold
			1	0	0	1	1, pmul, pdiv
			1	0	1	0	lp, ref_conf, rm
			1	0	1	1	interrupt_mask, interrupt_flags
			1	1	0	0	pulse_div, ramp_div, usrs
			1	1	0	1	dx_ref_tolerance
			1	1	1	0	x_latched
			1	1	1	1	

	JDX						common registers (SMDA=11)
0	1	1	0	0	0	0	datagram_low_word
			0	0	0	1	datagram_high_word
			0	0	1	0	cover_position, cover_len
			0	0	1	1	cover_datagram
			0	1	0	0	
			0	1	0	1	
			0	1	1	0	
			0	1	1	1	
			1	0	0	0	power-down
			1	0	0	1	
			1	0	1	0	
			1	0	1	1	
			1	1	0	0	
			1	1	0	1	
			1	1	1	0	l3, r3, l2, r2, l2, r1
1	1	1	1	1	1	1	mot1r, refmux, cont_update, clk2_div, cs_ComInd, polarities (DAC_AB, FD_AB, PH_AB, SCK_S, nSCS_S), LSDM

Table 5 - TMC428 register address mapping

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Register Description

The registers contain binary coded numbers. Some are unsigned, positive numbers, some are signed numbers in two's complement, and some are just bit vectors or bit vectors of single flags.

x_target (IDX=%0000)

This register holds the current target position in units of full steps respectively micro steps. The unit of the target position depends on the setting of the associated micro step resolution register **usrs**. If the difference **x_target - x_actual** is not zero then the TMC428 moves the stepper motor that the difference becomes zero. Both, target position **x_target** and current position **x_actual** (usually not necessary) may be altered on the fly. To move from one position to another, the ramp generator of TMC428 automatically generates ramp profiles (step pulses with defined frequencies) in consideration of velocity limits **v_min** and **v_max** and acceleration limit **a_max**.

Note: The registers **x_target, x_actual, v_min, v_max, and a_max** are initialized with zero after power up. Thus, no step pulses are generated because motion is prohibited. Setting **a_max** to zero during motion of the stepper motor results in the inability of the stepper motor to stop, because it cannot change its velocity.

x_actual (IDX=%0001)

The current position of each stepper motor is available by read out of the registers called **x_actual**. The actual position can be over written by the micro controller. This feature is for reference switch calibration under control of the micro controller. If a reference switch position has been determined, the actual position is set to zero at the reference switch position.

v_min (IDX=%0010)

This register holds the absolute value of the velocity where the stepper motor can be stopped abruptly. It should be set greater than zero. This value allows to reach the target position faster because the stepper motor is not slowed down below **v_min** before the target is reached. Also consider, that due to the finite numerical representation of integral relations, the target position can not be reached exactly, if the calculated velocity is less than one. So, setting **v_min** to one assures reaching each target position exactly. The unit of velocity parameters (**v_max**, **v_target**, and **v_actual**) is steps per time unit. The time unit is defined by the parameter **pulse_div**. The pulse frequencies in unit steps per second depends on the clock frequency of the clock signal at pin CLK of the TMC428.

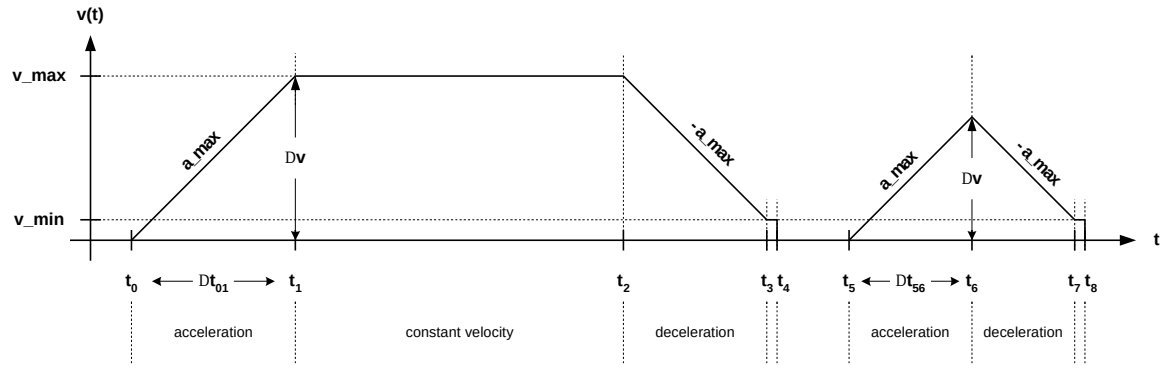

Figure 7 - Velocity ramp parameters and velocity profiles

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v_max (IDX=%0011)

This is the limit of the velocity. The absolute value of velocity– which may be positive or negative –will not exceed this limit, except the limit is changed during motion to a value below the current velocity. Note: To set target position **x_target** and current position **x_actual** to an equivalent value (e.g. to set both to zero at a reference point), the assigned stepper motor should be stopped first, and the parameter **v_max** should be set to zero to hold the assigned stepper motor at rest before writing into the register **x_target** and **x_actual**.

v_target (IDX=%0100)

In modes RAMP_MODE and SOFT_MODE this register holds the current target velocity calculated internally by the ramp generator. In mode VELOCITY_MODE a target velocity can be written into this register. Then the associated stepper motor accelerates until it reaches the target velocity specified. Changing velocity occurs in consideration of motion parameter limits in VELOCITY_MODE. In HOLD_MODE the register can be overwritten but it is ignored.

v_actual (IDX=%0101)

This read only register holds the current velocity of the associated stepper motor. Internally, the ramp generator of the TMC428 processes with 20 bits while only 12 bits can be read out as **v_actual**. So, an actual velocity of zero *read out* by the micro controller means that the current velocity is in an interval between zero and one. Because of this, the actual velocity should not be used to detect a stop of a stepper motor. For stop detection there is a dedicated bit within the interrupt register, which can simply be read out by the micro processor or generate an interrupt. But, if one writes zero to register **v_actual**, which is possible in HOLD_MODE only, the associated stepper motor stops immediately, because hidden bits are set to zero with each write access to the register **v_actual**. In HOLD_MODE only, this register is a read-write register. In HOLD_MODE, motion parameters are ignored and the micro controller has the full control to generate a ramp. In that mode, the TMC428 only handles the micro stepping and datagram generation for the associated stepper motor of the daisy chain.

a_max (IDX=%0110)

The maximum acceleration is defined by this register. The unit of the acceleration parameters (**a_max**, **a_actual, a_threshold**) is change of velocity per time unit divided by 256. Note: In contrast to the time unit of the velocity parameters defined by **pulse_div**, the time unit of the acceleration parameters is defined by the parameter **ramp_div** (see page 22). The change of pulse frequencies expressed as *change of velocity per second* also depends on the frequency of the clock signal at pin CLK of the TMC428.

a_actual (IDX=%0111)

The actual acceleration, which the TMC428 actually applies to a stepper motor can be read out by the micro controller from this register for monitoring purposes. Internally, it is updated with each clock. The actual acceleration is used to select scale factors for the coil currents. The returned value **a_actual** is the smoothed internal acceleration. This smoothing avoids oscillations of the readout value. Thus the returned **a_actual** values should not be used directly for high precision applications.

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is_agtat & is_aleat & is_v0 & a_threshold (IDX=%1000)

These parameters represent current scaling values I_s and are applied to the motor depending on the ramp phase: The parameter **is_agtat** is applied if the acceleration (a) it greater than (gt) a threshold acceleration (a_t). This is to increase current during strong acceleration. The parameter **is_aleat** is applied if the acceleration is lower equal (le) than the threshold acceleration. This is the nominal motor current. The third parameter **is_v0** is applied if the stepper motor is at rest, to save power, to keep it cool, and to avoid noise probably caused by chopper drivers. The parameter **a_threshold** is the threshold used to compare with the current acceleration to select the current scale factor. The three parameters **is_agtat, is_aleat**, and **is_v0** are bit vectors of three bit width. One of these is selected conditionally and assigned to an interim bit vector **i_scale**. The current scaling factor I_s is defined in Table 6.

i_scale			I_s
0	0	0	1
0	0	1	1 / 8
0	1	0	2 / 8
0	1	1	3 / 8
1	0	0	4 / 8
1	0	1	5 / 8
1	1	0	5 / 8
1	1	1	7 / 8

Table 6 - Current Scale Factors

One of the three scale factors **is_agtat, is_aleat**, and **is_v0** is selected according to Table 7. If the velocity is zero, the parameter **is_v0** is used for scaling. If the velocity is not zero, either **is_aleat** or **is_agtat** is used for scaling, depending on the absolute value of the acceleration and the acceleration threshold **a_threshold**.

v = 0		**I_s := is_v0**
v ? 0	**$\lvert a \rvert = a_{threshold}$**	**I_s := is_aleat**
	$\lvert a \rvert > a_{threshold}$	**I_s := is_agtat**

Table 7 - Current Scale Selection Scheme

The automatic motion dependent current scale feature of the TMC428 is provided primarily for micro step operational mode. But it may also be applied for full step or half step drivers, if those provide current control bits. For those drivers, one could initialize the micro step tabular with a constant function, square function or sine wave using the two most significant DAC bits.

pmul & pdiv (IDX=%1001)

The stepper motors are driven with a trapezoidal velocity profile, which may become triangular if the maximum velocity is not reached (see Figure 7, 15). Depending on the difference between the target position **x_target** and the actual position **x_actual**, the ramp generator continuously calculates target velocities **v_target** for the pulse generator (see **Figure 8**, page 18). The pulse generator then generates (micro) step pulses taking into account the motion parameter limits (**v_min**, **v_max**, **a_max**). With a target velocity proportional to the difference of target position **x_target** and current position **x_actual**,

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the stepper motor approaches the target position. This also works, if the target position is changed during motion. The stepper motor moves to a target position until the difference between the target position **x_target** and the current position **x_actual** vanishes.

With the right proportionality factor **p**, target positions are reached fast, without overshooting them. The proportionality factor primarily depends on the acceleration limit **a_max** and on the two clock divider parameters **pulse_div** and **ramp_div**. These two separate clock divider parameters– set to the same value for most applications –give an extreme wide dynamic range concerning acceleration and velocity. These two *separate* parameters allow to reach very high velocities with very low acceleration.

If the proportionality factor **p** is set to small, this results in a slow approach to the target position. If set too large, it causes overshooting and even oscillations around the target position. The calculation of the proportionality factor is simple:

The representation of the proportionality factor **p** by the two parameters **p_mul** and **p_div** is some kind of a fixed point representation. It is

p = p_mul / p_div

with

p_mul = {128, 128+1, 128+2, 128+3, ..., 128+127}

and

p_div = {2^3, 2^4, 2^5, ..., 2^{14}, 2^{15}, 2^{16}}.

Instead of direct storage of the parameters **p_mul** and **p_div**, the TMC428 stores two parameters called **pmul** and **pdiv**, with

p_mul = 128 + pmul and **p_div = 2^{3+pdiv}= 2^(3+pdiv)**

where

pmul = {0, 1, 2, 3, ..., 127} and **pdiv = {0, 1, 2, 3, 4, 5, 6, 7, 8, 9, 10, 11, 12, 13}**.

The reason why **p_mul** ranges from 128 to 255 is, that **p** is divided by **p_div** which is a power of two ranging from 8 to 65536. So, values of **p** less than 128 can be achieved by increasing **p_div**.

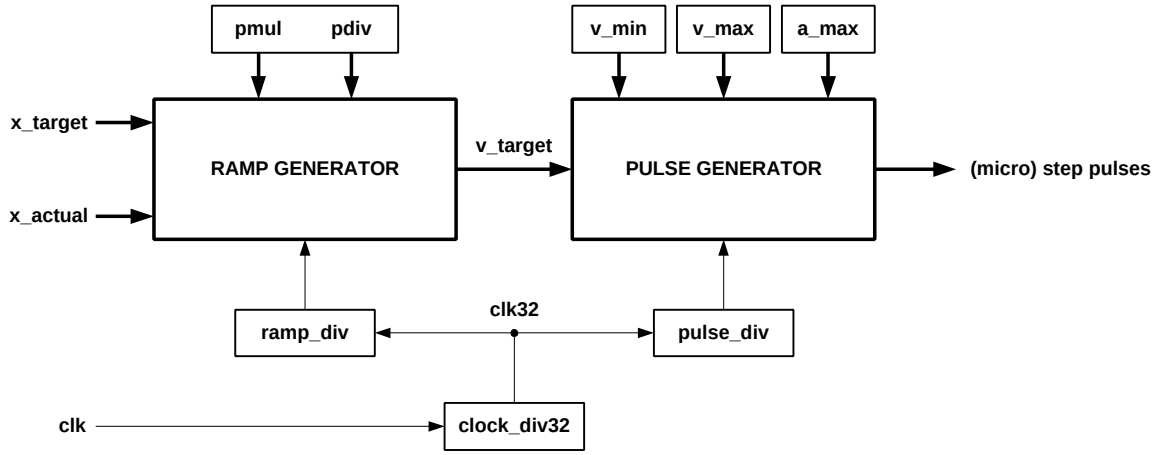

Figure 8 - Ramp Generator and Pulse Generator

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The parameter **p** has to be calculated for a given acceleration. This calculation is not done by the TMC428 itself, because this task has to be done only once for a given acceleration limit. The acceleration limit is a stepper motor parameter, which is usually fixed in most applications. If the acceleration limit has to be changed nevertheless, the micro controller could do this task or one could provide a pair of **p_mul** and **p_div** in a memory for each acceleration limit **a_max** required.

How to Calculate p_mul and p_div respectively pmul and pdiv

The proportionality factor **p = p_mul / p_div** depends on the acceleration limit **a_max**. So, a pair of **p_mul / p_div** has to be calculated once for each proposed acceleration limit **a_max**. There may exist more than one valid pair of **p_mul** and **p_div** for a given **a_max**.

To accelerate, the ramp generator with each time step accumulates the acceleration value to the actual velocity. Internally, the absolute value of the velocity is represented by 11+8 = 19 bits, while only the most significant 11 bits and the sign are used as input for the pulse generator. So, there are 2^{11} = 2048 values possible to specify a velocity, ranging from 0 to 2047. The ramp generator accumulates **a_max** divided by 2^8 = 256 at each time step to the velocity during acceleration phases. So, the acceleration from velocity = 0 to maximum velocity = 2047 spans over 2048* 256 / **a_max** pulse generator clock pulses. Within that acceleration phase, the pulse generator generates S = ½ * 2048* 256 / **a_max** * T steps for its (micro) step unit. The parameter T is the clock divider ratio T = $2^{rampdiv}$ / $2^{pulsdiv}$ = $2^{rampdiv-pulsdiv}$= 2^(ramp_div-pulse_div). During acceleration, the velocity has to be increased until the velocity limit **v_max** is reached or deceleration is required to reach the target position exactly (see Figure 7). The TMC428 automatically decelerates, if required using the difference between current position and target position and the proportionality parameter **p**, which has to be **p** = 2048 / S. With this, one gets p = 2048 / ((½ * 2048* 256 / **a_max**) * 2^(ramp_div-pulse_div)) . This expression can be simplified to

p = a_max / (128 * 2^(ramp_div-pulse_div)).

To avoid overshooting, the parameter **p_mul** should be made approximately up to 10% smaller than calculated. If the proportionality parameter **p** is too small, the target position will be reached slower, because the slow down ramp starts earlier. The target position is approached with minimal velocity **v_min**, whenever the internally calculated target velocity becomes less than **v_min**. With a good parameter **p** the minimal velocity **v_min** is reached a couple of steps before the target position. With parameter **p** set a little bit to large and small **v_min** overshooting of one step respectively one micro step may occur. Decrementation of the parameter **pmul** avoids such one-step overshooting.

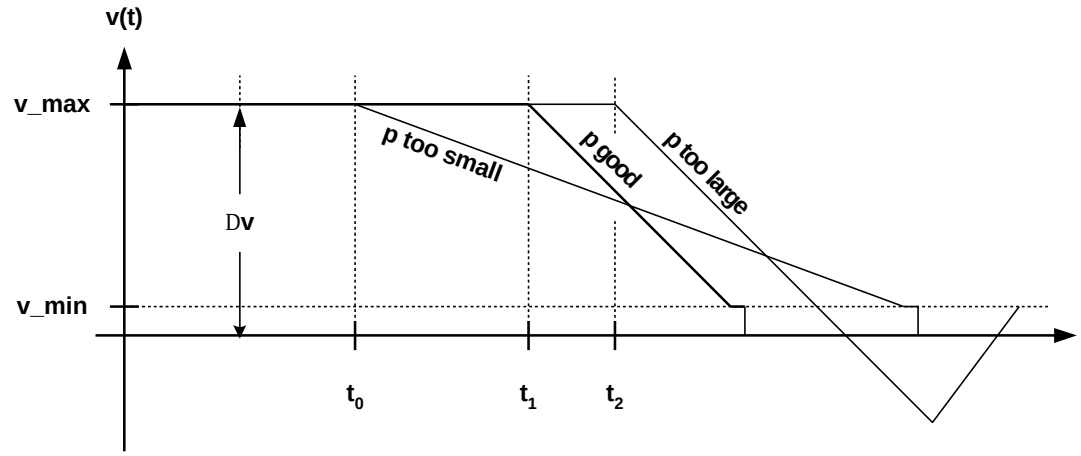

Figure 9 - Proportionality Parameter p and Outline of Velocity Profile(s)

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To represent the parameter **p = p_mul / p_div = (128+pmul) / 2^(3+pdiv)** one just has to find a pair of **pmul** and **pdiv** that approximates **p**, with **pmul** in range **0 ... 127** and **pdiv** one of **{8, 16 , 32 ,64 ,128 , 256, 512, 1024, 2048, 4096, 8192, 16384, 32786, 65536}**. There are only 128 * 14 = 1792 pairs of **(pmul, pdiv)**. So, one can simply try all possible pairs **(pmul, pdiv)** with a program and choose one pair. To find one pair, one has to calculate

p = a_max / (128 * 2^(ramp_div-pulse_div))

and

p' = p_mul / p_div = (128+pmul) / 2^(3+pdiv)

and

q = p / p'

for each pair **(pmul , pdiv)** and select one pair for that **1.0 < q < 0.95** is valid. So, the value **q** interpreted as a function **q(a_max, ramp_div, pulse_div, pmul, pdiv)** gives the quality criterion required. Although **q = 1.0** indicates that **(pmul , pdiv)** perfectly represents the desired **p** for a given **a_max**, this could cause overshooting because of finite numerical precision. In case of high resolution micro stepping, overshooting of one micro step is negligible, if it is below the micro step resolution of a stepper motor. To avoid overshooting, one can use **pmul-1** instead of the selected **pmul**. An example program in C language can be found on page 47.

lp & ref_conf & ramp_mode (rm) (IDX=%1010)

The bit vectors **ref_conf** and **ramp_mode** are accessed via a common address, because these parameters normally are initialized only once. The bit called **lp** (latched position) is a read only status bit. The TMC428 has three reference switch inputs. Without additional hardware, three reference switches are available. Per default, each reference switch input is assigned individually to each stepper motor as a left reference switch. The reference switch input REF3 can alternatively be assigned as the right reference switch of stepper motor number one. In that configuration *a left and a right reference switch* is assigned to stepper motor one, a left reference switch is assigned to stepper motor two, and no reference switch is assigned to stepper motor three. The bit named **mot1r** in the stepper motor global parameter register (rrs=1 & address=111111) selects one of these configurations. With additional hardware, up to six reference switches– a left and a right one assigned to each stepper motor –are supported (see Figure 11). The additional hardware is just a 74HC157, where three of four 2-to-1-multiplexers are used. The feature of multiplexing is controlled by the bit named **refmux** in the stepper motor global parameter register (rrs=1 & address=111111).

The two least significant bits on this address named **ramp_mode (rm)** select one of the four possible stepping modes:

00 : RAMP_MODE
01 : SOFT_MODE
10 : VELOCITY_MODE
11 : HOLD_MODE

The mode called **RAMP_MODE** is proposed as the default mode for positioning tasks, where the **VELOCITY_MODE** is the default for applications, where stepper motors have to be driven precisely with constant velocity. The **SOFT_MODE** is similar to the standard **RAMP_MODE** except that the target position is approached quite slowly, but this feature could be useful for those applications where vibrations at the target positions have to be minimized. The **HOLD_MODE** is proposed for motion control applications, where the ramp generation is completely controlled by the micro controller.

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The bits contained in **ref_conf** control the semantic and the actions of the reference/stop switch modes concerning interrupt generation as explained later. A stepper motor stops if the reference/stop switch, which corresponds to the actual driving direction, becomes active. The configuration bits named **DISABLE_STOP_L** respectively **DISABLE_STOP_R** disable these automatic stop functions. If the bit **SOFT_STOP** is set, motor stop forced by a reference switch is done within motion parameter limits while otherwise stopping is abruptly.

The bit **REF_RnL** (reference switch Right not Left) defines which switch is the reference switch: If set to '1', the right, else (set to '0') the left one is the reference switch. Note: Definition of the reference switch by the configuration bit **REF_RnL** has no effect concerning stopping using reference switches as stop switches if **DISABLE_STOP_L='0'** respectively **DISABLE_STOP_R='0'**.

32 bit DATAGRAM send from a µC to the TMC428																															
31	30	29	28	27	26	25	**24**	23	22	21	20	19	18	17	16	15	14	13	***12***	**11**	**10**	**9**	**8**	7	6	5	4	3	2	**1**	**0**
RRS	**ADDRESS**						**RW**	**DATA**																							
0	**smda**		**1**	**0**	**1**	**0**													***lp***	**ref_conf**										**rm**
0																			***latched position (waiting)***	**REF_RnL**	**SOFT_STOP**	**DISABLE_STOP_R**	**DISABLE_STOP_L**							**00 : RAMP, 01 : SOFT, 10 : VELOCITY, 11 : HOLD**

Table 8 - lp & ref_conf & ramp_mode (rm)

A reference switch indicates a reference position within a given tolerance. The tolerance can be programmed in units of steps respectively micro steps. When a reference switch is reached, the actual position can be stored automatically. The read-only status bit **lp** (latch position waiting) indicates the status of this automatic storage of the current position triggered by a reference switch tagged event.

interrupt_mask & interrupt_flags (IDX=%1011)

The TMC428 provides one interrupt register of eight flags for each stepper motor. Each interrupt bit can be disabled individually. The interrupt status **nINT** is low active. So, if an interrupt condition of one stepper motor becomes active, **nINT** is set to low ('0') and it remains low until all interrupt bits– selected by interrupt masks –of all stepper motors become inactive. If the interrupt status is inactive, **nINT** is high ('1'). The interrupt status is mapped to the most significant bit (31) of each datagram send back to the µC (see page 10) and it is available at the **SDO_C** pin of the TMC428 if the pin **nSCS_C** is low.

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Demultiplexing of the multiplexed interrupt status signal at the pin **SDO_C** could be done using additional hardware. But it is not necessary if the micro controller always disables its interrupt when it sends a datagram to the TMC428 and enables its interrupt input when sending of the datagram is completed.

32 bit DATAGRAM send from a µC to the TMC428																															
31	**30**	**29**	**28**	**27**	**26**	**25**	**24**	**23**	**22**	**21**	**20**	**19**	**18**	**17**	**16**	**15**	**14**	**13**	**12**	**11**	**10**	**9**	**8**	**7**	**6**	**5**	**4**	**3**	**2**	**1**	**0**
RRS	**ADDRESS**						**RW**	**DATA**																							
0	**smda**		**1**	**0**	**1**	**1**										**interrupt mask**								**interrupt flags**							
																MASK_STOP_RIGHT_HIGH	**MASK_STOP_LEFT_HIGH**	**MASK_STOP_RIGHT_LOW**	**MASK_STOP_LEFT_LOW**	**MASK_STOP**	**MASK_REF_MISS**	**MASK_REF_WRONG**	**MASK_POS_END**	**INT_STOP_RIGHT_HIGH**	**INT_STOP_LEFT_HIGH**	**INT_STOP_RIGHT_LOW**	**INT_STOP_LEFT_LOW**	**INT_STOP**	**INT_REF_MISS**	**INT_REF_WRONG**	**INT_POS_END**

Table 9 - interrupt register & interrupt mask

An interrupt flag is set to '1' if its assigned interrupt condition occurs and the corresponding interrupt mask is set ('1'). Interrupt flags are reset to '0' by a write access (RW='0') to the interrupt register address (IDX=%1010) with a '1' at the position of the bit to be cleared. A '0' at the corresponding position within the datagram used to reset interrupt flags leaves the corresponding interrupt flag untouched.

If an end position is reached and the interrupt mask **MASK_POS_END** is '1' the bit named **INT_POS_END** is set to one. If the reference switch becomes active out of the reference switch tolerance range– defined by the **dx_ref_tolerance** register –the interrupt flag **INT_REF_WRONG** is set if its interrupt mask bit **MASK_REF_WRONG** is set. The interrupt flag **INT_REF_MISS** is set if the reference switch is inactive at the 0 position and the mask **MASK_REF_MISS** is enabled. The **INT_STOP** flag is set, if the reference switch has forced a stop and if the interrupt mask **MASK_STOP** is set. The **INT_STOP_LEFT_LOW** flag is set if the reference switch changes from high to low and if the interrupt mask bit **MASK_STOP_LEFT_LOW** is set. The interrupt flag **INT_STOP_RIGHT_LOW** similar to **INT_STOP_LEFT_LOW** but for the right reference switch. The **INT_STOP_LEFT_HIGH** indicates that the left reference switch input changes from low to high if the mask **MASK_STOP_LEFT_HIGH** is set. The **INT_STOP_RIGHT_HIGH** indicates it for the right reference switch if the mask **MASK_STOP_LEFT_HIGH** is set.

pulse_div & ramp_div & usrs (IDX=%1100)

The frequency of the external clock signal (see Figure 3, **CLK**) is divided by 32 (see Figure 8, **clk_div32**). This clock drives two programmable clock dividers for the ramp generator and for the pulse generator. The pulse generator clock– defining the maximum step pulse rate –is determined by the parameter **pulse_div**. The pulse rate **R** (step frequency respectively micro step frequency) is given by

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R[Hz] = f_clk[Hz] * velocity / (2^pulse_div * 2048 * 32)

where **f_clk[Hz]** is the frequency of the external clock signal. The parameter velocity is in range 0 to 2047. The pulse generator of the TMC428 generates one step pulse with each pulse generator clock pulse if the velocity is set to 2047. The change D**R** in the pulse rate per time unit (step frequency change per second – the acceleration) is given by

D**R[Hz/s] = f_clk[Hz] * a_max / 256 / (2^ramp_div * 2048 * 32).**

The parameter a_max is in range 0 to 2047. So, the parameter **ramp_div** scales the acceleration parameter **a_max**, where the parameter **pulse_div** scales the velocity parameters.

usrs			[micro steps / full step]	significant DAC bits (controlling current amplitude)	comment
0	0	0	1	-	full step (constant current amplitude)
0	0	1	2	5 (MSB)	half step
0	1	0	4	5 (MSB), 4	micro stepping
0	1	1	8	5 (MSB), 4, 3	
1	0	0	16	5 (MSB), 4, 3, 2	
1	0	1	32	5 (MSB), 4, 3, 2, 1	
1	1	0	64	5 (MSB), 4, 3, 2, 1, 0 (LSB)	
1	1	1	64	5 (MSB), 4, 3, 2, 1, 0 (LSB)	

Table 10 – micro step resolution selection (usrs) parameter

The three bit wide parameter **usrs** (**µ s**tep **r**esolution **s**election**)** determines the micro step resolution for its associated stepper motor according to Table 10. There is a individual set of 6 DAC bits proposed for each of the two phases (coils) for current control to provide up to 64 micro steps per full step. Depending on the micro step resolution, a sub set of 6 DAC bits are significant. Using full stepping, the current amplitude is constant for both phases (coils) of a stepper motor and the polarity of one phase (coil) changes with each full step. The micro step counters are initialized by 0 during power-on reset. With each micro step an associated counter accumulates the programmed micro step resolution value **usrs**.

dx_ref_tolerance (IDX=%1101)

To allow the motor to drive near the reference point, it is possible to exclude a range of steps from the stop switch function. This parameter is important to disable stopping forced by reference switches during reference position search. The parameter affects interrupt conditions as described before.

x_latched (IDX=%1110)

This read-only register stores the actual position if a change of the reference switch is detected. The reference switch is defined by the bit REF_RnL of the configuration register lp & ref_conf & ramp_mode (IDX=%1010). To initialize this position storage mechanism one simply has to write to the (read-only) register. Then the actual position is saved in the register with the next change of the reference switch status. The bit lp signals if latching of the position is pending.

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Unused Address (IDX=%1111)

This register address (idx=1111) within each stepper motor register block {smda=00, 01, 10} is unused. Writing to this register has no effect. Reading this register gives back the actual status bits and 24 data bits set to '0'.

Global Parameter Registers

The registers addressed by **RRS=0** with **SMDA=%11** are global parameter registers. To emphasize this difference, the **JDX** is used as index name instead of **IDX**.

datagram_low_word (JDX=%0000) & datagram_high_word (JDX=%0001)

The TMC428 stores datagrams send back from the stepper motor driver chain with a total length of up to 48 bits. The register **datagram_low_word** holds the lower 24 bits of this 48 bits and the register **datagram_high_word** holds the higher 24 bits of the 48 bits. These both registers together form a 48 bit shift register, where the data from pin **SDI_S** are shifted left into it with each datagram bit send to the stepper motor driver chain via the signal **SDO_S**. A write to one of these read-only register addresses initializes these registers, to update its contents with the next received datagram from the drivers chain.

cover_pos & cover_len (JDX=%0010)

The TMC428 provides direct sending of datagrams from the micro controller to the stepper motor drivers. This may be necessary for initialization of different driver chips and useful for reconfiguration purposes. A datagram with up to 24 bits can be transferred to the stepper motor driver by covering one datagram sent to the drivers chain. The parameter **cover_pos** defines the position of the first datagram bit to be covered by the **cover_datagram (JDX=%0011)** of length **cover_len**. In contrast to the datagram numbering order of bits the position count for the cover datagram starts with 0. The **cover_datagram** bits indexed from cover_len-1 to 0 cover the datagram sent to the drivers chain.

Important: *A step bit used to control stepper motor drivers must not be covered.*

This is because the coverage of a step bit would cause losing that associated step if the step bit is active. The TMC428 stores **cover_pos+1** instead of **cover_pos** due to internal requirements. So, one writes **cover_pos** but reads back **cover_pos+1**.

cover_datagram (JDX=%0011)

This register holds up to 24 bit of a cover datagram. A cover datagram covers the next datagram sent to the stepper motor driver chain. If no datagrams are sent to the drivers chain, the cover datagram is sent immediately. The status of the cover datagram is mapped to the status bits sent back with each datagram (see page 10, **CDGW**). This status bit is also available for readout of **cover_pos & cover_len (JDX=%0010)**, where **CDGW** the most significant data bit (23). An example for the cover datagram is given in Figure 10. In that example 7 bits cover 7 bits of a 48 bit datagram from bit number 39 to bit number 46.

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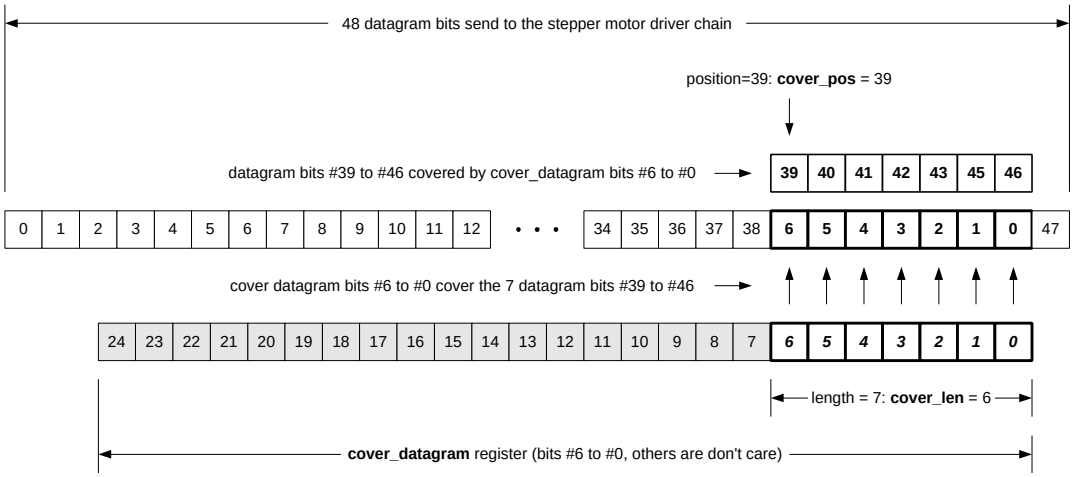

Figure 10: Cover Datagram Example

Unused Addresses (JDX={%0011, %0100, %0101, %0110, %0111})

There are unused addresses before the **power_down** address within the address space of the global parameter registers.

power_down (JDX=%1000)

A write to the register address named **power_down** sets the TMC428 into the power down mode until it detects a falling edge at the pin **nSCS_C**.

Unused Addresses (JDX={%1001, %1010, %1011, %1100, %1101})

There are also unused addresses after the power_down address within the address space of the global parameter registers.

Reference Switches l3 & r3 & l2 & r2 & l2 & r1 (JDX=%1110)

The current state of all reference switches– demultiplexed internally by the TMC428 if left and right reference switches are used –can be read from this read-only register. The bit named **continuous_update** of the **Stepper Motor Global Parameter Register (JDX=%1111)** is important for reading out of reference switches as explained below.

Stepper Motor Global Parameter Register (JDX=%1111)

Last but not least, this register holds different configuration bits for the stepper motor drivers chain. The absolute address (RRS & ADDRESS) of the stepper motor global parameter register is %0111111 0 ($7E). The stepper motor global parameter register holds different configuration bits together (see Table 11). For the datagram configuration the number of stepper motor drivers is important. It is represented by the

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parameter **lsmd** (**l**ast **s**tepper **m**otor **d**river). The two bit wide parameter **lsmd** has to be set to %00 for one stepper motor driver, %01 for two stepper motor drivers, and %10 for three stepper motor drivers.
Five bits are proposed to change polarities to opposite polarity. The selection signal for the stepper motor driver chain named **nSCS_S** is controlled by the polarity bit named **polarity_nscs_s.** The **nSCS_S** signal is low active if this bit is set to '0' it is high active if this bit is set to '1'. The polarity of the stepper motor driver chain clock signal **SCK_S** is defined by the bit **polarity_sck_s**. If this bit is '0' the clock polarity is according to Figure 6 on page 3. The clock signal **SCK_S** is inverted If it is set to '1'. The bit **polarity_PH_AB** defines the polarity of the phase bits for the stepper motor. Inverting this bit changes the rotation direction of the associated stepper motor. The bit **polarity_FD** defines the polarity of the fast decay controlling bit. If it is '0' fast decay is high active and if it is '1' fast decay is low active. The bit named **polarity_DAC_AB** defines the polarity of the DAC bit vectors. If it is '0' the DAC bits are high active and if it is '1' the DAC bits are inverted – low active.

The bit named **csCommonIndividual** defines either a single chip select signal **nSCS_S** is used common for all stepper motor driver chips (resp. **TMC288** / **TMC289**) or three chip select signals **nSCS_S**, **nCS2**, **nCS3** are use to select the stepper motor driver chips individually. This feature is available only for the TMC428 within the larger SOIC24 package (**TMC428-PI24**) where the two additional chip select signals **nCS2**, **nCS3** are available (see Figure 2). The one common chip select signal **nSCS_S** is used if the bit named **csCommonIndividual is** '0'.

32 bit DATAGRAM send from a µC to the TMC428																															
31	**30**	**29**	**28**	**27**	**26**	**25**	**24**	**23**	**22**	**21**	**20**	**19**	**18**	**17**	**16**	**15**	**14**	**13**	**12**	**11**	**10**	**9**	**8**	**7**	**6**	**5**	**4**	**3**	**2**	**1**	**0**
RRS	**ADDRESS**						**RW**	**DATA**																							
0	**1**	**1**	**1**	**1**	**1**	**1**										**clk2_div**									**polarities**					**lsmd**	
0										**mot1r**	**refmux**				**continuous_update**								**csCommonIndividual**	**polarity_DAC_AB**	**polarity_FD**	**polarity_PH_AB**	**polarity_sck_s**	**polarity_nscs_s**	**last stepper motor driver**	

Table 11 - Stepper Motor Global Parameter Register

The seven bits named **clk2_div** determine the clock frequency of the stepper motor driver chain clock signal **SCK_S**. The frequency **f_sck_s[Hz]** of the stepper motor driver chain clock signal **SCK_S** is **f_sck_s[Hz] = f_clk[Hz] / (2 * (clk2_div+1))**. A value of **127 (%1111111, $7F)** is the upper limit for the parameter **clk2_div**. With **clk2_div = 127** the clock frequency of **SCK_S** is at minimum. Due to internal processing, a value of **7 (%0000111, $07)** is the lower limit for the clock divider parameter **clk2_div**. With **clk2_div = 7** the clock frequency of **SCK_S** is at maximum. Due to internal processing, the frequency of **SCK_S** does not become higher for **clk2_div < 7**, but the signal **SCK_S** becomes asymmetric with respect to it's duty cycle. An asymmetric duty cycle may cause male function of stepper motor drivers, where stepper motor driver chips may work correctly in particular at low clock frequencies of **CLK**.

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So, the range of **clk2_div** is **{7, 8, 9, . . ., 125, 126, 127}**. The default value after power-on reset is **clk2_div = 15**. The clock frequency of **SCK_S** should be set as high as possible by choice of the parameter **clk2_div** in consideration of the data clock frequency limit defined by the slowest stepper motor driver chip of the daisy chain. If step frequencies reach the order of magnitude of the maximum datagram frequency– determined by the clock frequency of **SCK_S** and by the datagram length –the step frequencies may vary, which is an inherent property of that serial communication. Either if variations of step frequencies are acceptable or not depends on the application. Using high resolution micro stepping driver chips– as provided by TMC289 / TMC288 driver chips –avoids this problem.

The TMC428 sends datagrams to the stepper motor driver chain on demand if **continuous_update** is '0'. This reduces the communication traffic. The reference switches are processed while datagrams are send to the stepper motor driver chain only. If reference switches are configured to stop associated stepper motors automatically, the configuration bit **continuous_update** must be set to '1' to force periodic sending of datagrams to the stepper motor driver chain and to sample the reference switches periodically, also if all stepper motors are at rest. With this, a stepper motor restarts if its associated reference switch becomes inactive. Without continuous update, a stepper motor stopped automatically by a reference switch would stay at rest until a datagram is send to the stepper motor driver chain, also if its reference switch becomes inactive. Than, the relevant stepper motor can be moved in the opposite direction of the reference switch or in can be moved in both directions by disabling the automatic stop function.

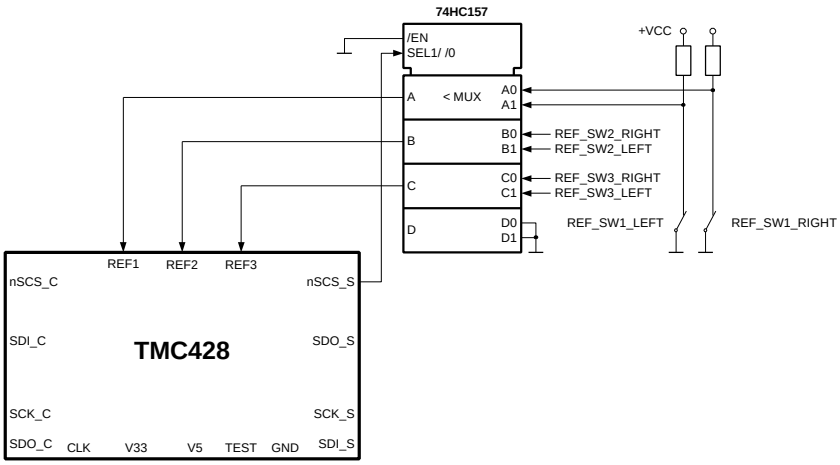

Figure 11 - Reference Switch Multiplexing with 74HC157 (refmux=1)

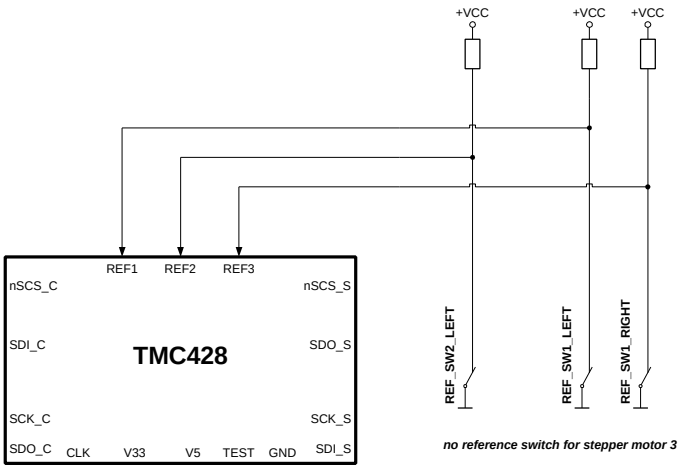

Figure 12 – Two-One-Null Reference Switch Configuration for mot1r=1 (and refmux=0)

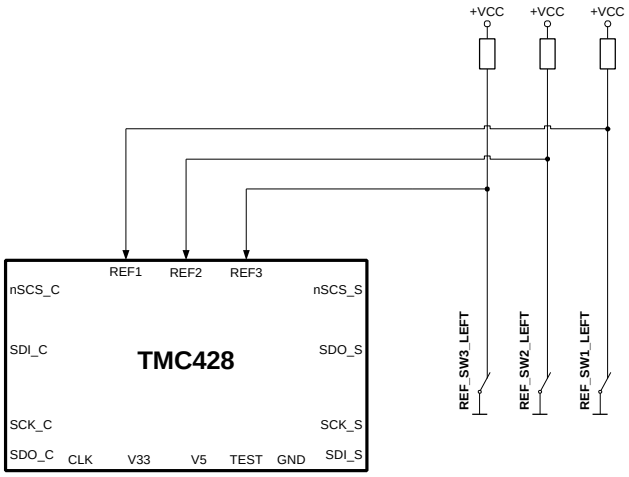

Figure 13 - Left-Side-Only Reference Switch Configuration for mot1r=0 (and refmux=0)

If **continuous_update** is '1', internal status bits are updated periodically also if all stepper motors are at rest. Additionally, the chip select signal **nSCS_S** for the stepper motor driver chain is also the control signal for a multiplexer in case of using the reference switch multiplexing option (see Figure 11). So, the **continuous_update** must be set to '1' if automatic stop by reference switches is enabled, if six multiplexed reference switches are used, and to get the states of reference switches while all stepper motors are at rest.

The bit named **refmux** must be set to '1' to enable reference switch multiplexing (see Figure 11). If reference switch multiplexing is enabled, and the **mot1r** is ignored. The default value after power-on reset of **refmux** is '0'. If **refmux** is '0', the association of the reference switch inputs REF1, REF2, REF3 depends on the setting of the configuration bit **mot1r**. The power-on default value of **mot1r** is '0'. With that default value, **REF1** is associated to the left reference switch of stepper motor #1, **REF2** is associated to the left reference switch of stepper motor #2, and **REF3** is associated to the left reference switch of stepper motor #3.

If **mot1r** is set to '1' the input **REF1** is also associated to the left reference switch of stepper motor #1. **REF2** is also associated to the left reference switch of stepper motor #2. But, the input **REF3** is associated to the *right reference switch* of stepper *motor #1* and no reference switch input is associated to stepper motor number#3 (see Figure 12).

After power-on-reset, per default **refmux=0** and **mot1r=0** selects the single reference switch configuration outlined in Figure 13, where each reference switch input (**REF1**, **REF2**, **REF3**) is assigned individually to one each stepper motor as the left reference switch.

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Simultanous Start of up to Three Stepper Motors

Starting stepper motors simultanously can be achifed by sending successive datagrams starting the stepper motors. If the delay between those datagrams is of the magnitude of some micro seconds, the stepper motors can be considered as started simultanously. Feedding the reference switch signals through the microcontoller (Figure 14) allows exact simultanous start of the stepper motors under software control.

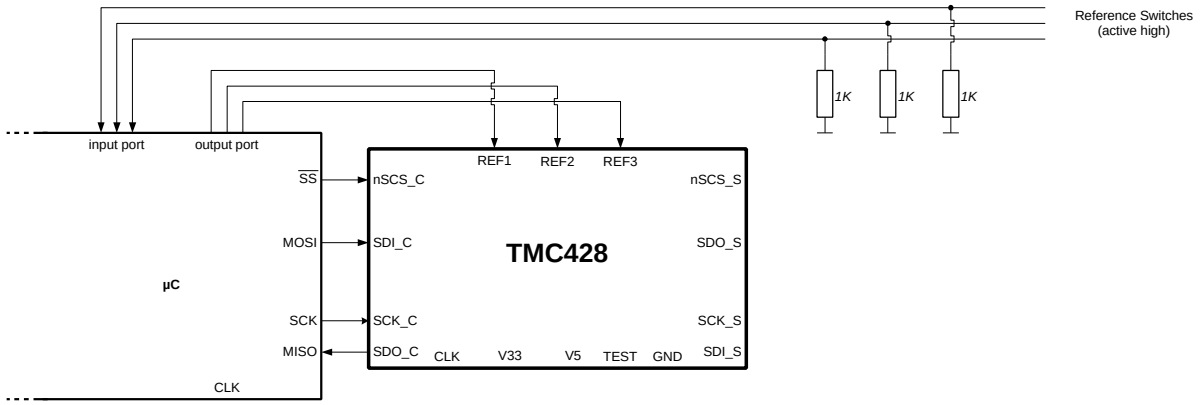

Figure 14 - Reference Switch Soft Control for Exact Simultanous Stepper Motor Start

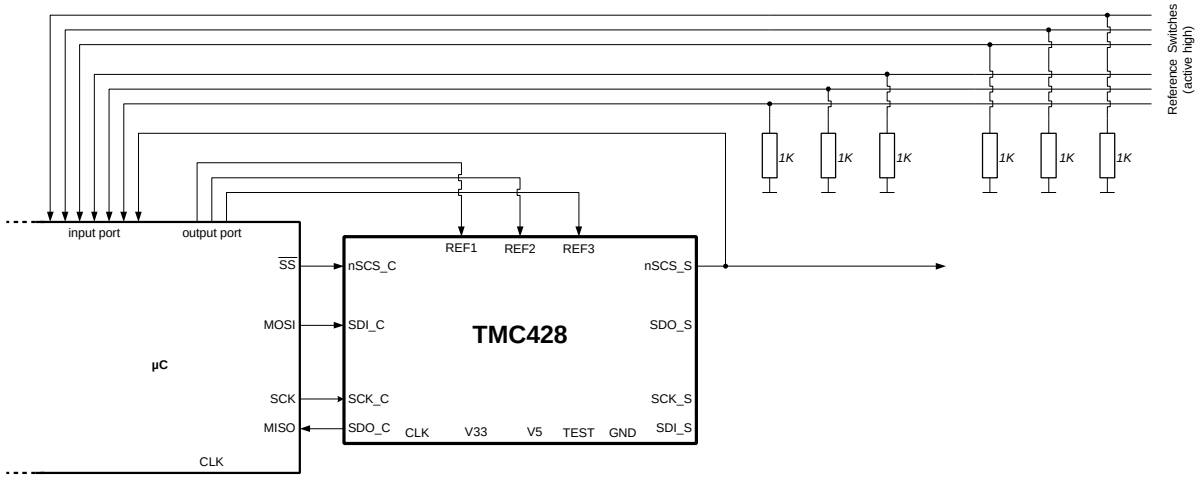

Figure 15 - Reference Switch Soft De-Multiplexing and Soft Control for six Reference Switches

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RAM Address Partitioning and Data Organization

The on-chip RAM capacity is 128 x 6 bit. These 128 on-chip RAM cells of 6 bit width are addressed via 64 addresses of 2 x 6 bit (see Table 12). So, from the point of view of addressing the on-chip RAM via datagrams, the address space enfolds 64 addresses of 24 bit wide data, where only 2 x 6 = 12 bits are relevant. These 64 addresses are partitioned– selected by the **RRS** (Register RAM Select, datagram bit 31)– into two address ranges of 32 addresses. The registers of the TMC428 are addressed with RRS='0'. The on-chip RAM is addressed with RRS='1'. The 64 on-chip RAM addresses are partitioned into two separated ranges by the most significant address bit of the datagram (bit 30).

The first 32 addresses are proposed for the configuration of the serial stepper motor driver chain. Each of these 32 addresses stores two configuration words, composed of the so called NxM (**N**e**x**t **M**otor) bit together with the 5 bit wide primary signal code. While sending a datagram, the primary signal code words are read internally beginning with the first address of the driver chain datagram configuration memory range. Each primary signal code word selects a signal proposed by the micro step unit. If the NxM bit is '1' an internal stepper motor addressing counter is incremented. If this internal counter is equivalent to the lsmd (last stepper motor driver) parameter, the datagram transmission is finished and the counter is preset to %00 for the next datagram transmission to the stepper motor driver chain.

The second 32 addresses are proposed to store the micro step table, which might be a quarter sine wave period as a basic approach or the quarter period of an periodic function optimized for micro stepping of a given stepper motor type. Different stepper motors may step with different micro step resolutions, but the micro step look up table (LUT) is the same for all stepper motors controlled by one TMC428. Any quarter wave period stored in the micro step table is expanded automatically to a full period wave together with its 90° phase shifted wave.

32 bit DATAGRAM send from a µC to the TMC428 via pin SDI_C																															
31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
RRS	**ADDRESS**						**RW**	**DATA**																							
																		data @ odd RAM addresses								**data @ even RAM addresses**					
1	**0**	**32 x (2x6 bit) driver chain datagram configuration range**																NxM_1	signal_codes							NxM_0	signal_codes				
1	**1**	**32 x (2x6 bit) quarter period sine wave LUT range**																quarter sine wave values (amplitude)								quarter sine wave values (amplitude)					

Table 12 - Partitioning of the On-Chip RAM address space

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Stepper Motor Driver Datagram Configuration

Different control signals are required to drive 2-phase stepper motors. What kind of signals are required, depends on the choice of stepping mode– full step, half step, micro step – and on additional options proposed by the used stepper motor driver chips. So, the TMC428 primarily provides a full set of control signals individually for each of the up to three stepper 2-phase stepper motors respectively stepper motor driver chips of the daisy chain. Mnemonics for primary signal codes are given in Table 13.

The control signals for each of the two coils of a 2-phase stepper motor are 6 bits for a DAC controlling the current of a coil, a phase polarity bit, and a fast decay bit for those stepper motor driver chips with a fast decay feature for the coil current. These signals are available individually for each coil (COIL A and COIL B). Fixed configuration bits– for example to select a current range of a driver –are proposed (named Zero and One). Additionally, step and direction bits are provided. One unique 5 bit code word– named primary signal code –is assigned to each primary control signal (see Table 13).

MNEMONIC	PRIMARY SIGNAL CODE		FUNCTION	
	hex	bin		
DAC_A_0	$00	%00000	DAC A, bit 0 (LSB)	COIL A
DAC_A_1	$01	%00001	DAC A, bit 1	
DAC_A_2	$02	%00010	DAC A, bit 2	
DAC_A_3	$03	%00011	DAC A, bit 3	
DAC_A_4	$04	%00100	DAC A, bit 4	
DAC_A_5	$05	%00101	DAC A, bit 5 (MSB)	
PH_A	$06	%00110	phase polarity bit A	
FD_A	$07	%00111	fast decay bit A	
DAC_B_0	$08	%01000	DAC B, bit 0 (LSB)	COIL B
DAC_B_1	$09	%01001	DAC B, bit 1	
DAC_B_2	$0A	%01010	DAC B, bit 2	
DAC_B_3	$0B	%01011	DAC B, bit 3	
DAC_B_4	$0C	%01100	DAC B, bit 4	
DAC_B_5	$0D	%01101	DAC B, bit 5 (MSB)	
PH_B	$0E	%01110	phase polarity bit B	
FD_B	$0F	%01111	fast decay bit B	
Zero	$10	%10000	constant '0'	
One	$11	%10001	constant '1'	
Direction	$12	%10010	0 : up / 1 : down resp. counter clockwise / clockwise	
Step	$13	%10011	step bit for step/direction control of drivers	
UNUSED (these codes may be used for future devices)	$14	%10100	'1' for TMC428-I, TMC428-A, TMC428-PI24	
	$15	%10101		
	$16	%10110		
	$17	%10111		
	$18	%11000		
	$19	%11001		
	$1A	%11010		
	$1B	%11011		
	$1C	%11100		
	$1D	%11101		
	$1E	%11110		
	$1F	%11111		

Table 13 - Primary Signal Codes

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The micro step unit (including sequencer) provides the full set of control signals for three stepper motor driver chips. A subset out of these control signals is selected by the stepper motor driver datagram configuration, which is stored within the first 32 addresses– but up to 64 values –of the on-chip RAM (see Table 12, page 30). The stepper motor drivers are organized in a daisy chain. So the addressing of the stepper motor driver chips within the daisy chain is by its position.

As mentioned before, the TMC428 sends datagrams to the stepper motor driver chain on demand. To guarantee the integrity of each datagram send to the stepper motor driver chain, the status of all primary control signals are buffered internally before sending. Afterwards, the transmission starts with selection of the buffered primary control signals of the first motor (**smda**=%00) by reading the first primary signal code word (even data word at on-chip RAM address %00000) from on-chip configuration RAM area. The primary signal codes select the primary signals provided for the first stepper motor. The first stepper motor is addressed until the **NxM** (next motor) bit is read from on-chip configuration RAM. The stepper motor driver address is incremented with each **NxM='1'** if the current stepper motor driver address is below the parameter **lsmd** (last stepper motor driver). If the stepper motor driver address is equivalent to the lsmd parameter, a NxM='1' indicates the completion of the transmission. With that, the stepper motor driver address counter of the serial interface is reinitialized to %00 and the unit waits for the next transmission request.

So, the order of primary signal codes in the on-chip RAM configuration area determines the order of datagram bits for the stepper motor driver chain, whereas the prefixed NxM bit determines the stepper motor driver positions. If no NxM bit with a value of '1' is stored within the on-chip RAM, the TMC428 will send endless. So, the on-chip RAM has to be configured first. After power-on reset, the registers of the TMC428 are initialized, so that no transmission of datagrams to the stepper motor driver chain is required. Access to on-chip RAM is always possible, also during transmission of datagrams to the driver chain.

Initialization of on-chip-RAM by µC after power-on

All registers are initialized by the automatic power-on reset. The registers are initialized, that stepper motors are at rest. The on-chip RAM is not initialized by the power-on reset. Writing to registers may involve action of the stepper motor units initiated by the TMC428 resulting in sending datagrams to the stepper motor driver chain. Those datagrams have a random power-on configuration of the on-chip-RAM. So, before writing any motion control register– respectively position or velocity –the on-chip RAM must be initialized first.

An Example of a Stepper Motor Driver Datagram Configuration

The following example demonstrates, how to configure the datagram and shows what has to be stored within the on-chip RAM to represent the desired configuration. In the example a driver chain of three stepper motor drivers is proposed. The first stepper motor driver has a serial interface of 12 bits length, the second driver has a length of 8 bits, and the last driver has a length of 10 bits (see Table 14). The corresponding content of the configuration on-chip RAM is outlined in Table 15. The datagrams, to be send from the micro controller to the TMC428, to store that configuration are outlined in Table 16.

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	example datagram configuration for sending from TMC428 to stepper motor driver daisy chain																													
position within datagram	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29
driver	driver # 1 (SMDA=%00)												driver # 2 (SMDA=%01)								driver #3 (SMDA=%10)									
NxM	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0	0	0	1
mnemonic of primary signal	PH_B	DAC_B_4	DAC_B_3	DAC_B_2	DAC_B_1	DAC_B_0	PH_A	DAC_A_4	DAC_A_3	DAC_A_2	DAC_A_1	DAC_A_0	Zero	Zero	Zero	One	One	One	Step	Direction	FD_B	FD_A	PH_B	DAC_B_2	DAC_B_1	DAC_B_0	PH_A	DAC_A_2	DAC_A_1	DAC_A_0

Table 14 - Datagram Example

on-chip RAM configuration for the example						
address	data	NxM & signal code word		mnemonic	position	
		NxM	signal code word			
$00	$0E	0	$0E	**PH_B**	0	**driver#1**
$01	$0C	0	$0C	**DAC_B_4**	1	
$02	$0B	0	$0B	**DAC_B_3**	2	
$03	$0A	0	$0A	**DAC_B_2**	3	
$04	$09	0	$09	**DAC_B_1**	4	
$05	$08	0	$08	**DAC_B_0**	5	
$06	$06	0	$06	**PH_A**	6	
$07	$04	0	$04	**DAC_A_4**	7	
$08	$03	0	$03	**DAC_A_3**	8	
$09	$02	0	$02	**DAC_A_2**	9	
$0A	$01	0	$01	**DAC_A_1**	10	
$0B	$**2**0	**1**	$00	**DAC_A_0**	11	
$0C	$10	0	$10	**Zero**	12	**driver#2**
$0D	$10	0	$10	**Zero**	13	
$0E	$10	0	$10	**Zero**	14	
$0F	$11	0	$11	**One**	15	
$10	$11	0	$11	**One**	16	
$11	$11	0	$11	**One**	17	
$12	$13	0	$13	**Step**	18	
$13	$**3**2	**1**	$12	**Direction**	19	
$14	$0F	0	$0F	**FD_B**	20	**driver#3**
$15	$07	0	$07	**FD_A**	21	
$16	$0E	0	$0E	**PH_B**	22	
$17	$0A	0	$0A	**DAC_B_2**	23	
$18	$09	0	$09	**DAC_B_1**	24	
$19	$08	0	$08	**DAC_B_0**	25	
$1A	$06	0	$06	**PH_A**	26	
$1B	$02	0	$02	**DAC_A_2**	27	
$1C	$01	0	$01	**DAC_A_1**	28	
$**1D**	$**2**0	**1**	$00	**DAC_A_0**	29	
With **lsmd** = %10 the (third) NxM bit at address $**1D** (position 29) finishes the datagram transmission						

Table 15 - RAM Contents for the Datagram Example

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```
binary datagram specification    : hexadecimal datagram

10000000----------001100--001110 : 80000c0e
10000010----------001010--001011 : 82000a0b
10000100----------001000--001001 : 84000809
10000110----------000100--n00110 : 86000406
10001000----------000010--000011 : 88000203
10001010----------100000--000001 : 8a002001
10001100----------010000--010000 : 8c001010
10001110----------010001--010000 : 8e001110
10010000----------010001--010001 : 90001111
10010010----------110010--010011 : 92003213
10010100----------000111--001111 : 9400070f
10010110----------001010--001110 : 96000a0e
10011000----------001000--001001 : 98000809
10011010----------000010--000110 : 9a000206
10011100----------100000--000001 : 9c002001
```

Table 16 – Configuration Datagram Sequence Specification for the Datagram Example

```
% binary datagram representation          $ hexadecimal datagram

% 10 00000 0 000000 00 001100 00 001110   $ 80 00 0c 0e
% 10 00001 0 000000 00 001010 00 001011   $ 82 00 0a 0b
% 10 00010 0 000000 00 001000 00 001001   $ 84 00 08 09
% 10 00011 0 000000 00 000100 00 000110   $ 86 00 04 06
% 10 00100 0 000000 00 000010 00 000011   $ 88 00 02 03
% 10 00101 0 000000 00 100000 00 000001   $ 8a 00 20 01
% 10 00110 0 000000 00 010000 00 010000   $ 8c 00 10 10
% 10 00111 0 000000 00 010001 00 010000   $ 8e 00 11 10
% 10 01000 0 000000 00 010001 00 010001   $ 90 00 11 11
% 10 01001 0 000000 00 110010 00 010011   $ 92 00 32 13
% 10 01010 0 000000 00 000111 00 001111   $ 94 00 07 0f
% 10 01011 0 000000 00 001010 00 001110   $ 96 00 0a 0e
% 10 01100 0 000000 00 001000 00 001001   $ 98 00 08 09
% 10 01101 0 000000 00 000010 00 000110   $ 9a 00 02 06
% 10 01110 0 000000 00 100000 00 000001   $ 9c 00 20 01
```

Table 17 - Datagrams Specified in Table 16 (with '-' (don't cares) replaced by '0')

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Initialization of the Micro Step Look-Up-Table

The TMC428 provides a look-up-table (LUT) of 64 values of 6 bit for micro stepping. The micro step LUT can be adapted by storing an arbitrary quarter period of a periodic function to individual stepper motor characteristics. It is common to uses one period of a sine wave function for micro stepping. With that function, the current of one phase is controlled with the sine function where the other phase is controlled with the cosine function.

To initialize the LUT for micro stepping one simply has to load a quarter sine wave period into the micro step LUT within the on-chip RAM area. Two successive values of the sine wave function are included in one datagram similar to the primary signal code words for the stepper motor driver chain configuration. The TMC428 automatically expands the quarter sine wave period to a full sine and cosine function. The necessary data values y(i) to represent a ¼ sine wave period for the micro step LUT are defined by

$$y(i) = \text{int}[\ ½ + 64 * \sin(¼ * 2 * \pi * i / 64)\ ] \qquad \text{with} \qquad i = \{\ 0, 1, 2, 3, ..., 60, 61, 62, 63\ \},$$

where the conditional replacement y(i) := 63 for y(i) > 63 has to be done. With this, one gets the following 64 values y(i) = { 0, 2, 3, 5, 6, 8, 9, 11, 12, 14, 16, 17, 19, 20, 22, 23, 24, 26, 27, 29, 30, 32, 33, 34, 36, 37, 38, 39, 41, 42, 43, 44, 45, 46, 47, 48, 49, 50, 51, 52, 53, 54, 55, 56, 56, 57, 58, 59, 59, 60, 60, 61, 61, 62, 62, 62, 63, 63, 63, *64*, *64*, *64*, *64*, *64* }.

32 bit DATAGRAM send from a µC to the TMC428 via pin SDI_C																															
31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
RRS	**ADDRESS**						**RW**	**DATA**																							
									$(x)_{10}$	**data @ odd RAM addresses**							$(x)_{10}$	**data @ even RAM addresses**											
1	1	0	0	0	0	0	0		2	0	0	0	0	1	0		0	0	0	0	0	0	0			0	0	0	0	0	0
		0	0	0	0	1			5	0	0	0	1	0	1		3	0	0	0	0	1	1			0	0	0	0	1	1
		0	0	0	1	0			8	0	0	1	0	0	0		6	0	0	0	1	1	0			0	0	0	1	1	0
		0	0	0	1	1			11	0	0	1	0	1	1		9	0	0	1	0	0	1			0	0	1	0	0	1
		0	0	1	0	0			14	0	0	1	1	1	0		12	0	0	1	1	0	0			0	0	1	1	0	0
		⋮	⋮	⋮	⋮	⋮				⋮	⋮	⋮	⋮	⋮	⋮											⋮	⋮	⋮	⋮	⋮	⋮
		1	1	0	1	1			62	1	1	1	1	1	0		62	1	1	1	1	1	0			1	1	1	1	1	0
		1	1	1	0	0			63	1	1	1	1	1	1		63	1	1	1	1	1	1			1	1	1	1	1	1
		1	1	1	0	1			*63*	1	1	1	1	1	1		63	1	1	1	1	1	1			1	1	1	1	1	1
		1	1	1	1	0			*63*	1	1	1	1	1	1		*63*	1	1	1	1	1	1			1	1	1	1	1	1
		1	1	1	1	1			*63*	1	1	1	1	1	1		*63*	1	1	1	1	1	1			1	1	1	1	1	1

Table 18 - scheme of ¼ sine wave period with 6 bit resolution and 64 (32 x 2) values

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The last five values (which are calculated to be 64) have to be replaced by 63. With this replacement one finally gets **y(i) = { 0, 2, 3, 5, 6, 8, 9, 11, 12, 14, 16, 17, 19, 20, 22, 23, 24, 26, 27, 29, 30, 32, 33, 34, 36, 37, 38, 39, 41, 42, 43, 44, 45, 46, 47, 48, 49, 50, 51, 52, 53, 54, 55, 56, 56, 57, 58, 59, 59, 60, 60, 61, 61, 62, 62, 62, 63, 63, 63, *63*, *63*, *63*, *63*, *63* }**. These 64 values– representing a quarter sine period in the interval [0 ... π/4 [which is expanded automatically by the TMC428 to a full sine cosine period –have to be send to the on-chip RAM of the TMC428 by 32 datagrams:

% binary representation of the datagram	: decimal represented pair of values (separated by & character)	: $ hexadecimal representation
% 11 00000 0 00000000 00 **000010** 00 **000000**	: **2** & **0**	: $ C0 00 02 00
% 11 00001 0 00000000 00 **000101** 00 **000011**	: **5** & **3**	: $ C2 00 05 03
% 11 00010 0 00000000 00 **001000** 00 **000110**	: **8** & **6**	: $ C4 00 08 06
% 11 00011 0 00000000 00 **001011** 00 **001001**	: **11** & **9**	: $ C6 00 0B 09
% 11 00100 0 00000000 00 **001110** 00 **001100**	: **14** & **12**	: $ C8 00 0E 0C
% 11 00101 0 00000000 00 **010001** 00 **010000**	: **17** & **16**	: $ CA 00 11 10
% 11 00110 0 00000000 00 **010100** 00 **010011**	: **20** & **19**	: $ CC 00 14 13
% 11 00111 0 00000000 00 **010111** 00 **010110**	: **23** & **22**	: $ CE 00 17 16
% 11 01000 0 00000000 00 **011010** 00 **011000**	: **26** & **24**	: $ D0 00 1A 18
% 11 01001 0 00000000 00 **011101** 00 **011011**	: **29** & **27**	: $ D2 00 1D 1B
% 11 01010 0 00000000 00 **100000** 00 **011110**	: **32** & **30**	: $ D4 00 20 1E
% 11 01011 0 00000000 00 **100010** 00 **100001**	: **34** & **33**	: $ D6 00 22 21
% 11 01100 0 00000000 00 **100101** 00 **100100**	: **37** & **36**	: $ D8 00 25 24
% 11 01101 0 00000000 00 **100111** 00 **100110**	: **39** & **38**	: $ DA 00 27 26
% 11 01110 0 00000000 00 **101010** 00 **101001**	: **42** & **41**	: $ DC 00 2A 29
% 11 01111 0 00000000 00 **101100** 00 **101011**	: **44** & **43**	: $ DE 00 1C 1B
% 11 10000 0 00000000 00 **101110** 00 **101101**	: **46** & **45**	: $ E0 00 2E 2D
% 11 10001 0 00000000 00 **110000** 00 **101111**	: **48** & **47**	: $ E2 00 30 2F
% 11 10010 0 00000000 00 **110010** 00 **110001**	: **50** & **49**	: $ E4 00 32 31
% 11 10011 0 00000000 00 **110100** 00 **110011**	: **52** & **51**	: $ E6 00 34 33
% 11 10100 0 00000000 00 **110110** 00 **110101**	: **54** & **53**	: $ E8 00 36 35
% 11 10101 0 00000000 00 **111000** 00 **110111**	: **56** & **55**	: $ EA 00 38 37
% 11 10110 0 00000000 00 **111001** 00 **111000**	: **57** & **56**	: $ EC 00 39 38
% 11 10111 0 00000000 00 **111011** 00 **111010**	: **59** & **58**	: $ EE 00 3B 3A
% 11 11000 0 00000000 00 **111100** 00 **111011**	: **60** & **59**	: $ F0 00 3C 3B
% 11 11001 0 00000000 00 **111101** 00 **111100**	: **61** & **60**	: $ F2 00 3D 3C
% 11 11010 0 00000000 00 **111110** 00 **111101**	: **62** & **61**	: $ F4 00 3E 3D
% 11 11011 0 00000000 00 **111110** 00 **111110**	: **62** & **62**	: $ F6 00 3E 3E
% 11 11100 0 00000000 00 **111111** 00 **111111**	: **63** & **63**	: $ F8 00 3F 3F
% 11 11101 0 00000000 00 **111111** 00 **111111**	: ***63*** & **63**	: $ FA 00 3F 3F
% 11 11110 0 00000000 00 **111111** 00 **111111**	: ***63*** & ***63***	: $ FC 00 3F 3F
% 11 11111 0 00000000 00 **111111** 00 **111111**	: ***63*** & ***63***	: $ FE 00 3F 3F

Table 19 - Datagrams for Initialization of a Quarter Sine Wave Period Micro Step Look-Up-Table

These 32 datagrams (Table 19) are sufficient for all programmable micro step resolutions. If micro stepping is proposed for at least one stepper motor, these 32 datagrams have to be send once to the TMC428 for initialization of the micro step table after power-on reset. The initialization of the micro step look-up-table is not necessary, if full stepping is used for *all* stepper motors. The On-Chip RAM is not initialized during power-on reset. So, the full initialization of the whole micro step look-up-table is recommended to avoid trouble caused by missing look-up table entries. Additionally, a fully initialized micro step look-up-table allows the selection of individual micro step resolutions for different stepper motors.

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TRINAMIC MICROCHIPS

Micro Step Enhancement

Sine cosine micro stepping is not sufficient for all types of real stepper motors not even for those stepper motors labeled as optimized for micro stepping operation. A periodic trapezoidal or triangular function similar to a sine function or a superposition of these function as a replacement of the pure sine wave function (Figure 16) is a better choice for different types of stepper motors. Taking the physics of stepper motors into account, the choice of the function for micro stepping can be simply determined by a single shape parameter s as explained below. The programmability of the micro step look-up table of the TMC428 also during operation– on-the-fly alteration of parameters –provides a simple and effective facility to attune micro stepping to a given type of two-phase stepper motor. Enhanced micro stepping requires accurate current control. So, stepper motor driver chips with enabled and well tuned fast decay operational mode– as our TMC288 / TMC289 smart power drivers provide –are necessary to be used.

Non-Linearities resulting from magnetic field configuration determined by shapes of pole shoes, ferromagnetic characteristics, and other stepper motor characteristics effect non-linearity in micro stepping of real stepper motors. The non-linearity of micro stepping causes micro step positioning displacements, vibrations and noise, which can be reduced dramatically with an adapted micro step table.

Nevertheless sine cosine micro stepping is a good first order approach for microstepping. The micro step enhancement possible with the TMC428 bases on replacement of the look-up table initialization function $\sin(j)$ used for sine cosine micro stepping by a function with the shape parameter s. A quarter sine wave period is the basic approach for initialization of the micro step look up table . A quarter of a trapezoidal function or a quarter of a triangular function is chosen depending on the shape parameter s for a given stepper motor type.

$$f_s(j) = \begin{cases} f_{box\_circle}(j) & for \quad s > 0 \\ f_{circle}(j) & for \quad s = 0 \\ f_{circle\_rhomb}(j) & for \quad s < 0 \end{cases} \qquad with \qquad -1.0 \le s \le +1.0 \qquad and \qquad 0 \le j < \frac{p}{2}.$$

The look-up table ($f(j)$) of the TMC428 enfolds a quarter period ($0 = j < p/2$) only. This quarter period is expanded to a full period ($0 = j < 2p$) and the phase shifted companion function value ($f(j - p/2)$) is added automatically by the TMC428 during operation. So, for reach function value ($f(j)$) one automatically gets a pair of function values {$f(j)$; $f(j - p/2)$} respectively {$\sin(j)$; $\cos(j)$}. This automatic expansion of the TMC428– primary proposed for sine cosine microstepping ($f(j) = \sin(j)$) –also works fine with other micro step controlling functions f_s.

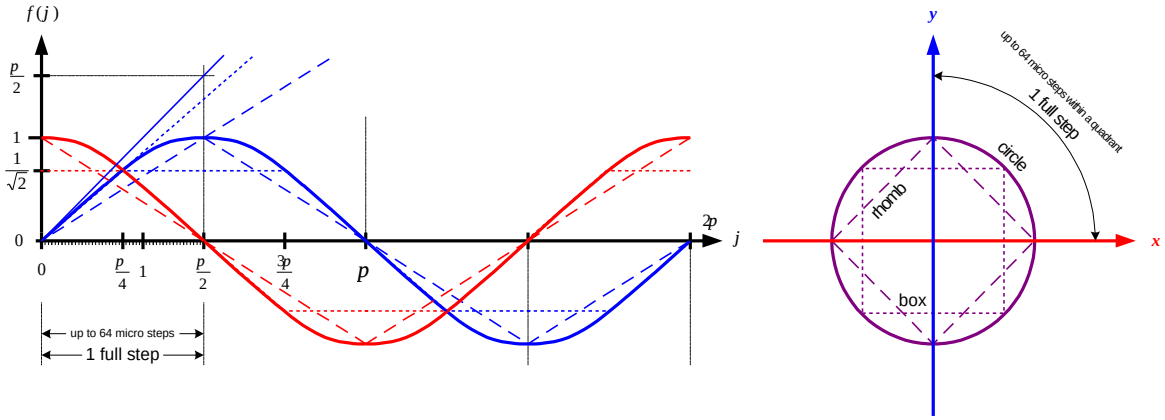

Figure 16 - micro step enhancemant by introduction of a shape function $f_s(j)$

The shape parameter s selects one of three functions $f_{box}(f)$, $f_{circle}(f)$, $f_{rhomb}(f)$ respectively a superposition of two of them. The shape parameter $s = 0$ selects the function $f_{circle}(f)$ which is the sine function $\sin(j)$ as used for sine cosine micro stepping. With this, one gets the unit circle (r=1.0) by transformation to cartesian coordinates {$y = \sin(j)$; $x = \cos(j)$} as outlined in Figure 16, a shape parameter s = +1.0 results in a box, and a shape parameter s = -1.0 results in a rhomb. Other values except those, result in something between box and circle respectively something between circle an rhomb.

The data values y(i) of the look-up table range from 0 to 63 and the argument i ranges also from 0 to 63. In the following, natural angles (radians) ranging from ($0 = j < 2p$) are used for the description. The three functions for superposition controlled by the shape parameter s are

$$f_{box}(j) = \begin{cases} \frac{4}{p \cdot \sqrt{2}} \cdot j & if \quad 0 \le j < \frac{p}{4} \\ \frac{1}{\sqrt{2}} & if \quad j \ge \frac{p}{4} \end{cases}$$

$$f_{circle}(j) = \sin(j)$$

$$f_{rhomb}(j) = \frac{2}{p} \cdot j$$

All together, these three functions are combined to form the function

$$f_s(j) = \begin{cases} f_{circle}(j) + s \cdot [f_{box}(j) - f_{circle}(j)] & for \quad s > 0 \\ f_{circle}(j) & for \quad s = 0 \\ f_{circle}(j) + s \cdot [f_{circle}(j) - f_{rhomb}(j)] & for \quad s < 0 \end{cases}$$

So, the shape parameter s selects the type of function and it also provides a continuous transition between circle and box respectively circle and rhomb. To estimate, what function would be best for a given type of stepper motor, one can try micro stepping based on different shape parameters s by downloading different micro step tables on-the-fly into the TMC428 during motion of a stepper motor. For calculation of data for the micro step look-up table of the TMC428, one has to replace $j \rightarrow j_i$ *ranging from 0 to p* /2 for the quarter period by

$$j_i = \frac{p}{2} \cdot \frac{i}{64} \quad with \quad i = \{0,1,2,3,...,63\} .$$

The amplitude of the shape function f_s (f_i) has to be limited to the range of 0.0 to 1.0 respectively to the range of 0 to 63 for the on-chip RAM as described in the beginning of the micro stepping section.

Partial look-up table initialization option

A partially initialized micro step table may be sufficient, if all stepper motors– except those driven in full step mode –are proposed to use the same micro step resolution constantly before a single micro step is processed. But with a partial initialized micro step look-up table, the micro step resolution *must not be changed* anyway. So, a partially initialized look-up table should be taken into account only, if it is a must because of small memory of proposed used micro controller. Instead of partial initialization of the look-up table of the TMC428, initialization the look-up table with a triangular function $f_{rhomb}(j)$ would be a much better choice.

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Package Outlines and Dimensions

Shrink Small Outline Package with 16 Pins (SSOP16, 150 MIL) of TMC428-I and TMC428-A

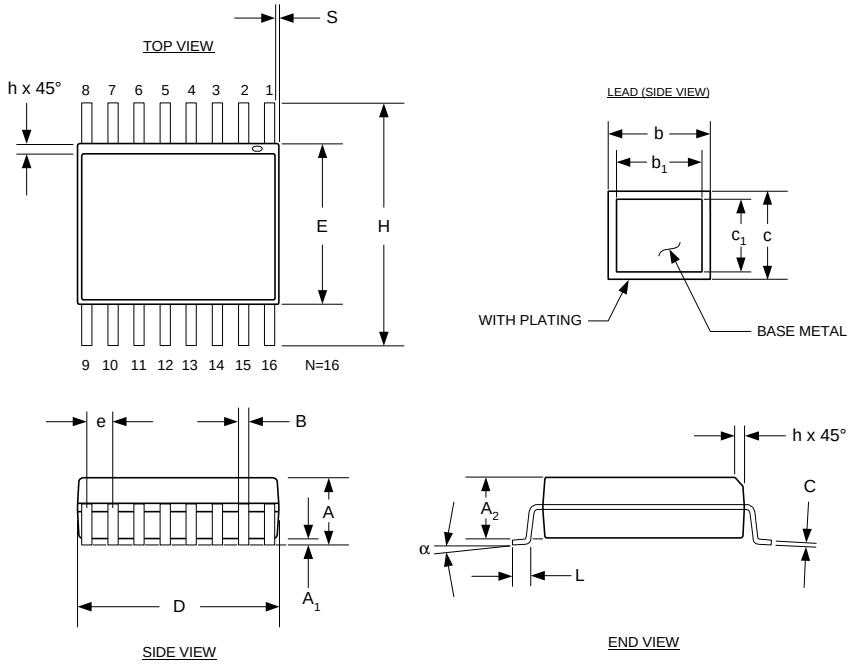

Figure 17 – Package Outline Drawing SSOP16, 150 MILS

Symbol	Dimensions in MILLIMETERS			*Dimensions in INCHES*		
	Min	**Typ**	**Max**	***Min***	***Typ***	***Max***
A	1.55	1.63	1.73	*0.061*	*0.064*	*0.068*
A1	0.10	0.15	0.25	*0.004*	*0.006*	*0.0098*
A2	1.40	1.47	1.55	*0.055*	*0.058*	*0.061*
b	0.20		0.30	*0.008*		*0.012*
b1	0.20	0.25	0.28	*0.008*	*0.010*	*0.011*
c	0.18		0.25	*0.007*		*0.010*
c1	0.18	0.20	0.23	*0.007*	*0.008*	*0.009*
B	0.20	0.25	0.31	*0.008*	*0.010*	*0.012*
C	0.19	0.20	0.25	*0.0075*	*0.008*	*0.0098*
D	4.80	4.93	4.98	*0.189*	*0.194*	*0.196*
E	3.91 BSC			*0.154 BSC*		
e	0.635 BSC			*0.025 BSC*		
H	6.02 BSC			*0.237 BSC*		
h	0.25	0.33	0.41	*0.010*	*0.013*	*0.016*
L	0.41	0.635	0.89	*0.016*	*0.025*	*0.035*
N	**16**			**16**		
S	0.051	0.114	0.178	*0.0020*	*0.0045*	*0.0070*
a	0°	5°	8°	0°	5°	8°

Table 20 - Dimensions of Package SSOP16, 150 MILS (Note: BSC » Best Case)

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Small Outline Package with 24 Pins (SOIC24) for TMC428-PI24

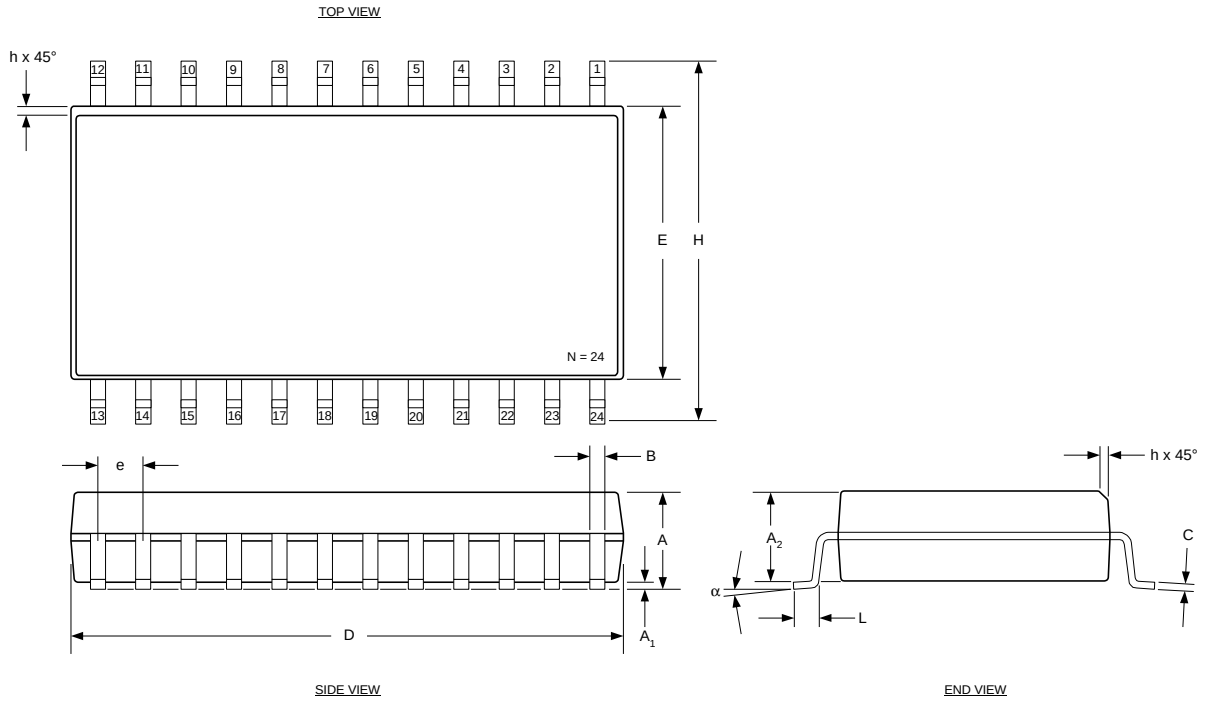

Figure 18 - Package Outline Drawing SOIC24, 300 MILS

Symbol	Dimensions in MILLIMETERS			*Dimensions in INCHES*		
	Min	**Typ**	**Max**	*Min*	*Typ*	***Max***
A	2.35		2.65	*0.0926*		*0.1043*
A1	0.1		0.3	*0.004*		*0.0118*
A2						
B	0.33		0.51	*0.013*		*0.02*
C	0.23		0.32	*0.0091*		*0.0125*
D	15.2		15.6	*0.5985*		*0.6141*
E	7.4		7.6	*0.2914*		*0.2992*
e	1.27 BSC			*0.05 BSC*		
H	10		10.65	*0.394*		*0.419*
h	0.25		0.75	*0.01*		*0.029*
L	0.4		1.27	*0.016*		*0.05*
N	**24**			**24**		
a	0°		8°	0°		8°

Table 21 - Dimensions of Package SOIC24, 300 MILS (Note: BSC » Best Case)

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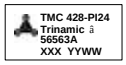
Marking

Product Name	TMC428-I
Product ID (at top and bottom)	56563A
Package Name	SSOP16 – 150 MILS
Internal Package Name	SSOP16_A
Date Code	YYWW (year YY and week WW)
Lot Number (at bottom only)	XXX
Logo	No
Real Size (see note below)	
Zoomed Size	**TMC428-I** **Trinamic** **56563A**

Product Name	**TMC428-A**
Product ID (at top and bottom)	56563A
Package Name	SSOP16 – 150 MILS
Internal Package Name	SSOP16_A
Date Code	YYWW (year YY and week WW)
Lot Number (at bottom only)	XXX
Logo	No
Real Size (see note below)	
Zoomed Size	**TMC428-A** **Trinamic** **56563A**

Product Name	TMC424-PI24
Product ID	56563A
Package Name	SOIC 24 – 300 MILS
Internal Package Name	SO024_B
Date Code	YYWW (year YY and week WW)
Lot Number	XXX
Logo	Yes
Real Size (see note below)	
Zoomed Size	

Note: Proposed to be of ''Real Size'' if printed with scale of 100% on paper of DIN-A4 format – but the printed size may differ depending on the printer.

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Characteristics

Symbol	Parameter	Conditions	Min	Max	Unit
VDD3	DC Supply Voltage	Voltage at Pin V33 in 3.3V mode	-0.3	3.6	V
VI3	DC Input Voltage, 3.3 V I/Os		-0.3	VDD3 + 0.3	V
VO3	DC Output Voltage, 3.3 V I/Os		-0.3	VDD3 + 0.3	V
VDD5	DC Supply Voltage	Voltage at Pin V5	-0.3	5.5	V
VI5	DC Input Voltage, 5V I/Os	Continuous DC Voltage	-0.3	VDD5 + 0.3, 5.5 max	V
VO5	DC Output Voltage, 5V I/Os	Continuous DC Voltage	-0.3	VDD5 + 0.3, 5.5 max	V
VESD	ESD Voltage at any I/O Pin	Human Body Model according to MIL-STD-883, with R_C = 1 - 10 MΩ, R_D = 1.5 KΩ, and C_s = 100 pF.		±2000	V
VESD5	ESD Voltage at Pin V5				V
VESD33	ESD Voltage at Pin V33				V
IMAXIO	Maximum Current into any Input or Output Terminal	One pin at a time		10	mA
TEMPIND	Operating Free Air Temperature Range	Industrial	-40	+85	°C
TEMPAUT	Operating Free Air Temperature Range	Automotive	-40	+125	°C
TSG	Storage Temperature		-60	+150	°C

Table 22 - Absolute Maximum Ratings

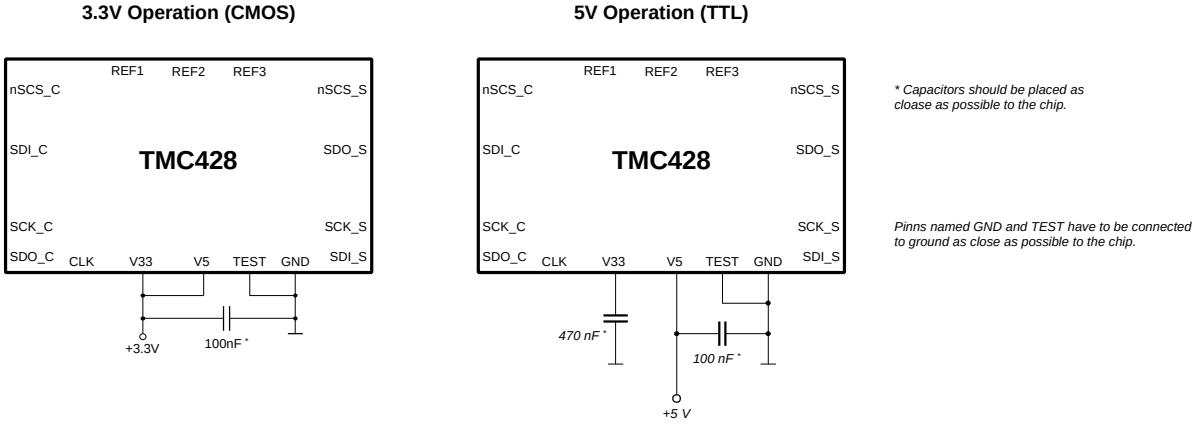

Figure 19 - 3.3V Operation (CMOS) vs. 5V Operation (TTL)

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Symbol	Parameter	Conditions	Min	Typ	Max	Unit
ILC	Input Leakage Current				10	µA
CIN	Input Capacitance			7		pF

Table 23 – Characteristics

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
VDD3	DC Supply Voltage		3.0	3.3	3.6	V
VI3	DC Input Voltage		0		VDD3	V
VIL3	Low Level Input Voltage	Pin TEST only	0		0.3 x VDD3	V
VIH3	High Level Input Voltage	Pin TEST only	0.7 x VDD3		VDD3 + 0.3	V
VLTH3	Low Level Input Voltage Threshold	All Inputs except TEST	1.025		1.126	V
VHTH3	High Level Input Voltage Threshold	All Inputs except TEST	1.675		1.725	V
VHYS3	Schmitt-Trigger Hysteresis		0.550		0.700	V
VOL3	Low Level Output Voltage	IOL = 0.3 mA			0.1	V
VOH3	High Level Output Voltage	IOH = 0.3 mA	VDD3 – 0.1			V
VOL3	Low Level Output Voltage	IOL = 2 mA			0.4	
VOH3	High Level Output Voltage	IOH = 2 mA	VDD3 – 0.4			V

Table 24 - DC Characteristics – 3.3V Supply Mode

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
VDD5	DC Supply Voltage		4.5	5	5.5	V
VI5	DC Input Voltage		0		VDD5	V
VIL5	Low Level Input Voltage	Pin TEST only	0		0.3 x VDD5	V
VIH5	High Level Input Voltage	Pin TEST only	0.7 x VDD5		VDD5 + 0.3	V
VLTH5	Low Level Input Voltage Threshold	All Inputs except TEST	1.025		1.126	V
VHTH5	High Level Input Voltage Threshold	All Inputs except TEST	1.675		1.725	V
VHYS5	Schmitt-Trigger Hysteresis		0.550		0.700	V
VOL5	Low Level Output Voltage	IOL = 0.3 mA			0.1	V
VOH5	High Level Output Voltage	IOH = 0.3 mA	VDD5 – 0.1			V
VOL5	Low Level Output Voltage	IOL = 4 mA			0.4	
VOH5	High Level Output Voltage	IOH = 4 mA	VDD5 – 0.4			V

Table 25 - DC Characteristics – 5V Supply Mode

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Symbol	Parameter	Conditions	Min	Typ	Max	Unit
ISC16MHZ	Supply Current	f = 16 MHz at Tc=25°C				mA
ISC4MHZ	Supply Current	f = 4 MHz at Tc=25°C		1,25		mA
ICS0MHZ	Supply Current	f = 0 MHz at Tc=25°C				µA
IPDN25C	Power Down Current	Power Down Mode at Tc=25°C, 5V Supply		70		µA
IPDN85C	Power Down Current	Power Down Mode at Tc=85°C, 5V Supply				µA
IPDN125C	Power Down Current	Power Down Mode at Tc=125°C, 5V Supply				µA

Table 26 - Power Dissipation

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
fCLK	Operation Frequency	fCLK = 1 / tCLK	0	4	16	MHz
tCLK	Clock Period	Raising Edge to Raising Edge of CLK	62,5		∞	ns
tCLK_L	Clock Time Low		25		∞	ns
tCLK_H	Clock Time High		25		∞	ns
tRISE_I	Input Signal Rise Time	10% to 90% except TEST pin			∞	ns
tFALL_I	Input Signal Fall Time	90% to 10% except TEST pin			∞	ns
tRISE_O	Output Signal Rise Time	10% to 90%		2		ns
tFALL_O	Output Signal Fall Time	90% to 10%		4		ns
tSU	Setup Time	relative to falling clock edge at CLK	1			ns
tHD	Hold Time	relative to falling clock edge at CLK	1			ns
tPD	Propagation Delay Time	50% of rising edge of the clock CLK to the 50% of the output	1	5		ns

Table 27 - General Timing Parameters

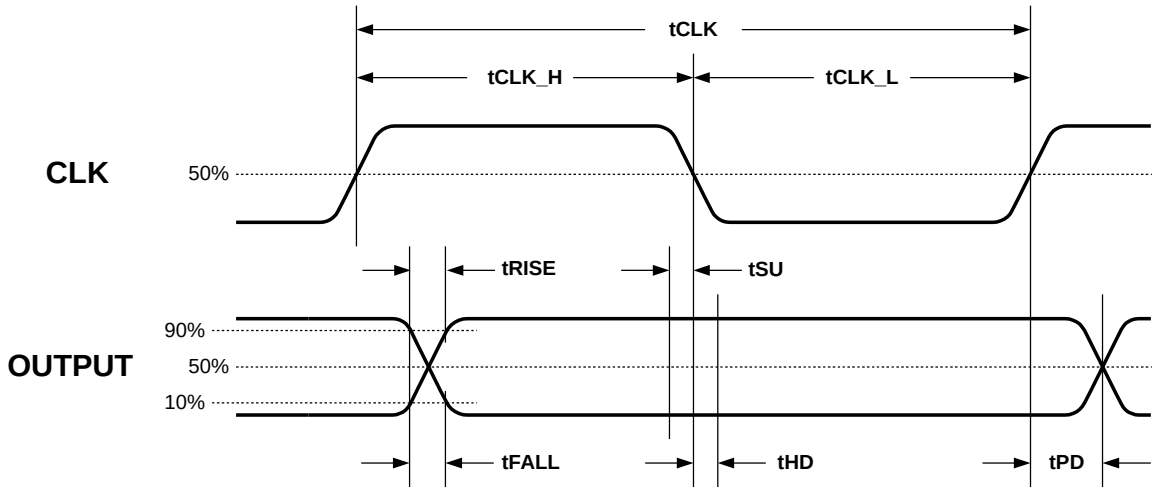

Figure 20 - General Timing Parameters

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On-Chip Voltage Regulator

The on-chip voltage regulator delivers a 3.3V supply for the core under a 30 mA load with a 4.5 minimum input voltage. An external 470 nF ceramic capacitor has to be connected between the V33 pin (see Figure 19, page 42) and ground, with connections as short as possible. The regulator is internally stable. The output capacitor is only needed for power supply filtering, not for feedback loop stabilization. The ripple voltage VRIPPLE on pin V33 is approximately

$$VRIPPLE \approx I\_average * tCLK / C\_load$$

where I_average is the average current, tCLK is the clock period, C_load is capacity of the capacitor. A capacity between 33 nF to 470 nF (perhaps 100 nF) are sufficient, depending on the ripple requirements. The technology is more important: x7r ceramic capacitors shall be preferred, in parallel with 470 pF to 1 pF c0g. Tantalum capacitors should be avoided, because of their poor high frequency behavior.

Additionally, an external 100 nF ceramic capacitor (CBLOCK) has to be connected between pin V5 and ground– with connections as short as possible –in 5V operational mode. In 3.3V operational mode an external 100 nF ceramic capacitor (see Figure 19) is necessary only between pin V33 and ground, with connections as short as possible.

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
TRANGEREG	Temperature range	Industrial	-40		85	°C
VDD5REG	Supply voltage vdd5	5 V Operational Mode	4.5	5	5.5	V
CBLOCK	Block capacitor	5 V Operational Mode, x7r ceramic capacitor		100		nF
VDD3REG	Supply voltage vdd3	3.3 V Operational Mode	2.9	3.3	3.6	V
ICCNLREG	Current consumption	no load		50	100	µA
IREG	Output current on vdd3	max. 10 mA internal load by core			20	mA
tSREG	Startup time	no external capacitor connected			20	µs
tSREGC	Startup time	C_load = 470 nF			150	µs
TDRFT	Temperature drift				300	ppm / °C
VRIPPLE	Ripple on vdd3	C_load = 470 nF, I_load = 10mA + 20 mA		100		mV
CREG	External capacitor	On V33 pin, x7r ceramic		470		nF
CREG_RANGE	External capacitor range	On V33 pin, x7r ceramic, necessary capacity depending on required VRIPPLE	33	470		nF
COPTIONAL	Optional capacitor	Additional Parallel Capacitor, c0g ceramic	1		470	pF
PSRRDC	power supply ripple rejection	DC		50		dB

Table 28 - Characteristics of the on-chip Voltage Regulator

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Power-On-Reset

The TMC428 is equipped with a static and dynamic reset with internal hysteresis (see Figure 21). So, it performs an automatic reset during power-on. If the power supply voltage goes below a threshold, an automatic power on reset is performed also.

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
VDD	Power supply range		3.0	3.3	3.6	V
Temp	Temperature		-40	25	85	°C
Vop	Reset on/off				0.59	V
Voff	Reset off		1,58	2,13	2,85	V
Von	Reset on		1.49	1.98	2.70	V
tRESPOR	Reset time of on-chip power-on-reset		2.14	3.31	5.52	µs
Pd	Power dissipation after Tres		22.2	33	55.6	µA
Vop125C	Reset on/off	T = -40°C				V
Voff125C	Reset off	T = -40°C				V
Von125C	Reset on	T = -40°C				V
tRESPOR125C	Reset time of on-chip power-on-reset	T = -40°C				µs
Pd125C	Power dissipation after Tres	T = -40°C				µA
Vop125C	Reset on/off	T = 125°C				V
Voff125C	Reset off	T = 125°C				V
Von125C	Reset on	T = 125°C				V
tRESPOR125C	Reset time of on-chip power-on-reset	T = 125°C				µs
Pd125C	Power dissipation after Tres	T = 125°C				µA

Table 29 - Characteristics of the on-chip Power-On-Reset

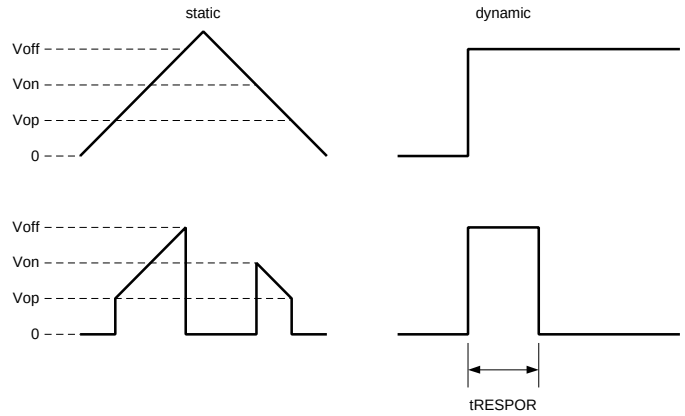

Figure 21 - Operating Principle of the power-on-reset

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Example for Calculation of p_mul and p_div for the TMC428

```
/* PROGRAM EXAMPLE 'pmulpdiv.c' : How to Calculate p_mul & p_div for the TMC428 */

#include <math.h>
#include <stdio.h>
#include <stdlib.h>
#include <string.h>

void CalcPMulPDiv(int a_max, int ramp_div, int pulse_div,
                  int *p_mul, int *p_div, double *PIdeal, double *PBest)
{
  int   d, d_best, m, m_best;
  double q_ideal, q_best, q;

  q_ideal = a_max /  (pow(2, ramp_div-pulse_div)*128.0);
  q_best  =  -1;
  d_best  =   0;
  m_best  = 128;

  for(d=0; d<=13; d++)
  {
    m = (int) (q_ideal*pow(2, d+3));

    if(m>127 && m<256)
    {
      q = m / pow(2, d+3);

      if(fabs(q-q_best) < fabs(q_ideal-q_best) || q_best<0)
      {
        q_best = q;
        d_best = d;
        m_best = m;
      }
    }
  }

  *p_mul = m_best;
  *p_div = d_best;

  *PIdeal = q_ideal;
  *PBest = q_best;
}

int main(int argc, char **argv)
{
    int a_max=0, ramp_div=0, pulse_div=0, p_mul, p_div;
    double pideal, pbest;
    char **argp;

    if (argc>1)
    {
      while (argv++, argc--)
      {
        argp = argv + 1;   if (*argp==NULL) break;

        if ( (!strcmp(*argv,"-a")) ) sscanf(*argp,"%d",&a_max);
        else if ( (!strcmp(*argv,"-r"))) sscanf(*argp,"%d",&ramp_div);
        else if ( (!strcmp(*argv,"-p"))) sscanf(*argp,"%d",&pulse_div);
      }
    }
    else
    {
      fprintf(stderr,"\n  USAGE : pmulpdiv -a <a_max> -r <ramp_div> -p <pulse_div>}\n"

                     "  EXAMPLE : pmulpdiv -a 865 -r 9 -p 7}\n");
      return 1;
    }

    printf("a_max=%d\tramp_div=%d\tpulse_div=%d\n\n", a_max, ramp_div, pulse_div);

    CalcPMulPDiv(a_max, ramp_div, pulse_div, &p_mul, &p_div, &pideal, &pbest);

    printf("p_mul = %3.3d\np_div = %3d\n\np_ideal = %.15f\np_best = %.15f\n",
            p_mul, p_div, pideal, pbest);

    return 0;
}

/* ---------------------------------------------------------------------- */
```

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