DRV10964 5V、三相正弦无传感器 BLDC 电机驱动器

1 特性

- 专有的无传感器无窗口 180° 正弦控制方案
- 输入电压范围：2.1V 至 5.5V
- 500mA 输出电流
- 休眠模式下的静态电流低至 15μA（典型值）
- 驱动器高侧和低侧 (H+L) 总导通电阻 (Rdson) 小于 1.5Ω
- 电流限制和短路电流保护
- 锁定检测
- 电压浪涌保护 (AVS)
- 欠压闭锁 (UVLO)
- 热关断

2 应用范围

- 笔记本 CPU 风扇
- 游戏站 CPU 风扇
- ASIC 冷却风扇

3 说明

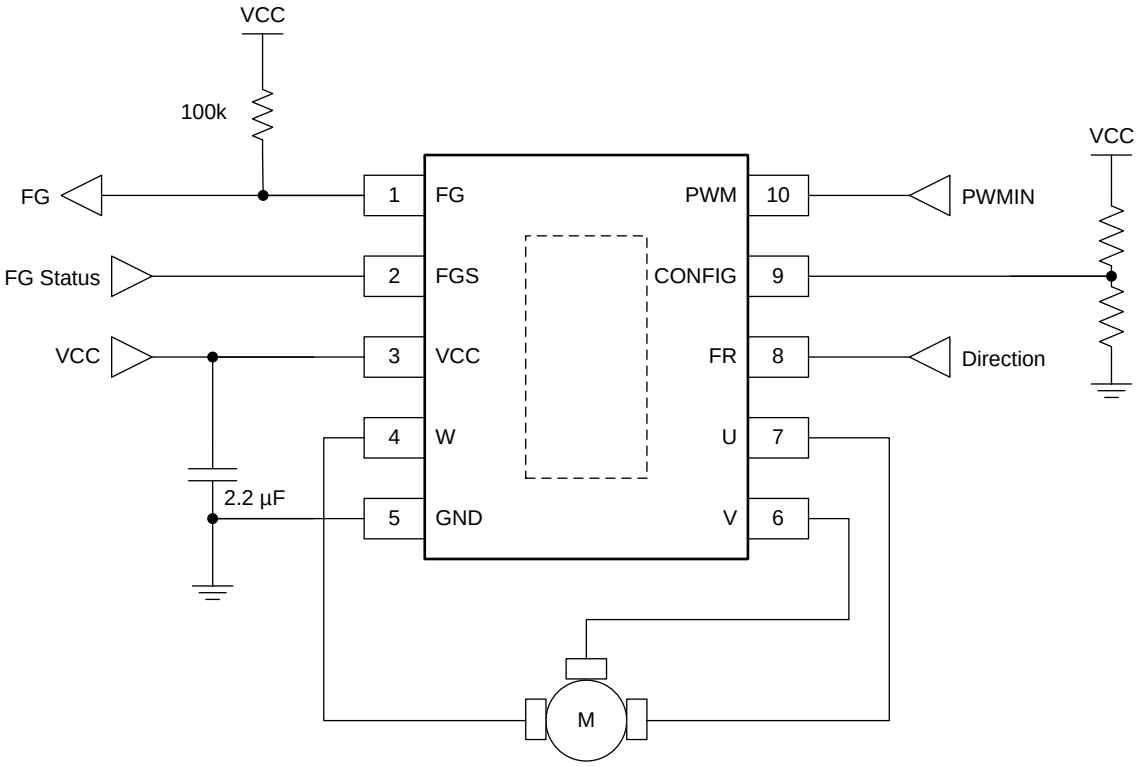
DRV10964 是一款带有集成功率金属氧化物半导体场效应晶体管 (MOSFET) 的三相无传感器电机驱动器。该器件专门针对高效、低噪声和低外部组件数的电机驱动应用而 设计。专有的无传感器无窗口 180° 正弦控制方案可提供超静音的电机驱动性能。DRV10964 具备智能锁定检测功能，与其他内部保护电路搭配使用以确保器件安全运行。DRV10964 采用带有外露散热焊盘的高效散热型 10 引脚超小外形尺寸无引线 (USON) 封装。

器件信息 (1)

部件号	封装	封装尺寸（标称值）
DRV10964	USON (10)	3.00mm x 3.00mm

(1) 要了解所有可用封装，请见数据表末尾的可订购产品附录。

简化电路原理图



An IMPORTANT NOTICE at the end of this data sheet addresses availability, warranty, changes, use in safety-critical applications, intellectual property matters and other important disclaimers. PRODUCTION DATA.

目录

1 特性 ... 1
2 应用范围 ... 1
3 说明 ... 1
4 修订历史记录 ... 2
5 **Pin Configuration and Functions** ... 3
6 **Specifications** ... 4
6.1 Absolute Maximum Ratings ... 4
6.2 ESD Ratings ... 4
6.3 Recommended Operating Conditions ... 4
6.4 Thermal Information ... 4
6.5 Electrical Characteristics ... 5
6.6 Typical Characteristics ... 6
7 **Detailed Description** ... 7
7.1 Overview ... 7
7.2 Functional Block Diagram ... 7
7.3 Feature Description ... 7
7.4 Device Functional Modes ... 14
8 **Application and Implementation** ... 17
8.1 Application Information ... 17
8.2 Typical Application ... 17
9 **Power Supply Recommendations** ... 19
10 **Layout** ... 19
10.1 Layout Guidelines ... 19
10.2 Layout Example ... 19
11 器件和文档支持 ... 20
11.1 社区资源 ... 20
11.2 商标 ... 20
11.3 静电放电警告 ... 20
11.4 Glossary ... 20
12 机械、封装和可订购信息 ... 20

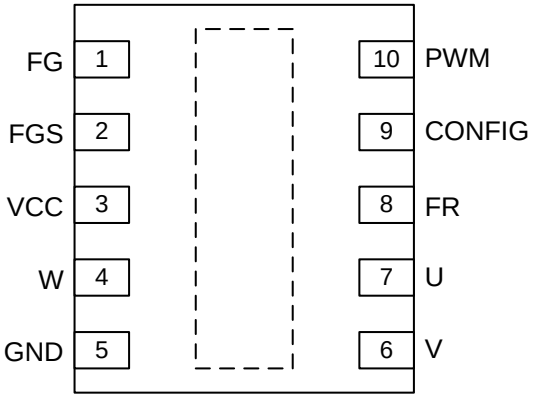
4 修订历史记录

日期	修订版本	注释
2016 年 2016	*	最初发布。

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5 Pin Configuration and Functions

DSN Package
10-Pin USON
Top View



Pin Functions

PIN		I/O	DESCRIPTION
NO.	NAME		
1	FG	Output	Motor speed indicator output (open drain).
2	FGS	Input	Motor speed indicator selector. The state of this pin is latched on power up and can not be changed dynamically.
3	VCC	Power	Input voltage for motor and chip supply.
4	W	IO	Motor Phase W
5	GND	Ground	Ground
6	V	IO	Motor Phase V
7	U	IO	Motor Phase U
8	FR	Input	Motor direction selector. This pin can be dynamically changed after power up.
9	CONFIG	Input	Resistor setting for configuring the handoff threshold. The state of this pin is latched on power up and can not be changed dynamically.
10	PWM	Input	Motor speed control input.
—	Thermal Pad	—	Connect to Ground for maximum thermal efficiency. Thermal pad is on the bottom of the package.

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6 Specifications

6.1 Absolute Maximum Ratings

over operating free-air temperature range (unless otherwise noted) (1) (2)

		MIN	MAX	UNIT
	VCC pin supply voltage	–0.3	6	V
	Motor phase pins (U, V, W)	–1	7.7	V
	Direction, speed indicator input, and speed input (FR, FGS, PWM, CONFIG)	–0.3	6	V
	Speed output (FG)	–0.3	7.7	V
T_J	Junction temperature	–40	150	°C
T_{SDR}	Maximum lead soldering temperature, 10 seconds		260	°C
T_{stg}	Storage temperature	–55	150	°C

(1) Stresses beyond those listed under *Absolute Maximum Ratings* may cause permanent damage to the device. These are stress ratings only, which do not imply functional operation of the device at these or any other conditions beyond those indicated under *Recommended Operating Conditions*. Exposure to absolute-maximum-rated conditions for extended periods may affect device reliability.
(2) All voltages are with respect to ground.

6.2 ESD Ratings

			VALUE	UNIT
$V_{(ESD)}$	Electrostatic discharge	Human-body model (HBM), per ANSI/ESDA/JEDEC JS-001 (1)	±2500	V
		Charged-device model (CDM), per JEDEC specification JESD22-C101 (2)	±1000	

(1) JEDEC document JEP155 states that 500-V HBM allows safe manufacturing with a standard ESD control process.
(2) JEDEC document JEP157 states that 250-V CDM allows safe manufacturing with a standard ESD control process.

6.3 Recommended Operating Conditions

over operating free-air temperature range (unless otherwise noted)

		MIN	MAX	UNIT
VCC	VCC pin supply voltage	2.1	5.5	V
U, V, W	Motor phase pins	–0.7	7	V
FR, FGS, PWM, CONFIG	Direction, speed indicator input, and speed input	–0.1	5.5	V
FG	Speed output	–0.1	7.5	V
T_J	Junction temperature	–40	125	°C

6.4 Thermal Information

THERMAL METRIC (1)		DRV10964 DSN (USON) 10 PINS	UNIT
$R_{\theta\ JA}$	Junction-to-ambient thermal resistance	40.9	°C/W
$R_{\theta\ JC(top)}$	Junction-to-case (top) thermal resistance	46.6	°C/W
$R_{\theta\ JB}$	Junction-to-board thermal resistance	15.8	°C/W
ψ_{JT}	Junction-to-top characterization parameter	0.5	°C/W
ψ_{JB}	Junction-to-board characterization parameter	16	°C/W
$R_{\theta\ JC(bot)}$	Junction-to-case (bottom) thermal resistance	2.9	°C/W

(1) For more information about traditional and new thermal metrics, see the *Semiconductor and IC Package Thermal Metrics* application report, SPRA953.

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6.5 Electrical Characteristics

(VCC = 5 V, T_A = 25°C unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
SUPPLY CURRENT						
I_{VCC}	Operating current	PWM = V_{CC}, no motor connected		6.5		mA
I_{VCC_SLEEP}	Sleep current	PWM = 0 V		15	20	µA
UVLO						
V_{UVLO_H}	Undervoltage threshold high			2	2.1	V
V_{UVLO_L}	Undervoltage threshold low		1.7	1.8		V
V_{UVLO_HYS}	Undervoltage threshold hysteresis		100	200	300	mV
INTEGRATED MOSFET						
R_{DSON}	Series resistance (H+L)	V_{CC} = 5 V; I_{OUT} = 0.5 A		1	1.5	Ω
PWM						
V_{IH_PWM}	Input high threshold		0.45 × VCC			V
V_{IL_PWM}	Input low threshold				0.15 × VCC	V
F_{PWM}	PWM input frequency	Duty cycle >0% and <100%	15		100	kHz
$R_{PU_PWM_VCC}$	PWM pin pullup resistor	Active mode		40		kΩ
		Standby mode		1.5		MΩ
t_{SLEEP}	Sleep entry time	PWM = 0 V and the motor speed less than 10 Hz		1		ms
FG						
I_{OL_FG}	FG sink current	V_{FG} = 0.3 V	5			mA
I_{SC_FG}	FG short circuit current	V_{FG} = 5 V		13	25	mA
FGS and FR						
V_{IH_FGS}	Input high threshold		0.45 × VCC			V
V_{IL_FGS}	Input low threshold				0.15 × VCC	V
V_{IH_FR}	Input high threshold		0.45 × VCC			V
V_{IL_FR}	Input low threshold				0.15 × VCC	V
$R_{PU_FGS_VCC}$	FGS pin pullup resistor	Active Mode		40		kΩ
		Standby Mode		1.5		MΩ
$R_{PU_FR_VCC}$	FR pin pullup resistor			425		kΩ
BEMF COMPARATOR						
V_{offset}	Input offset		-10		10	mV
V_{HYS}	Input hysteresis		14	21	28	mV
T_{delay_r}	Output delay rising	25-mV step			1.5	µs
T_{delay_f}	Output delay falling	25-mV step			1.5	µs
V_{com}	Common mode voltage		0.3		VCC – 0.7	V
RATE LIMITING						
t_{ARamp}	Ramp time for align (from 0 to 50% duty cycle)			300		ms

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Electrical Characteristics (continued)

(VCC = 5 V, T_A = 25°C unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
CONFIG						
$CONFIG_{trip}$	CONFIG pin trip points	Handoff speed threshold 87.5 Hz	0	3.1	5.4	% VCC
		Handoff speed threshold 12.5 Hz	7.3	9.4	11.7	% VCC
		Handoff speed threshold 25 Hz	13.5	15.6	17.9	% VCC
		Handoff speed threshold 37.5 Hz	19.8	21.8	24.1	% VCC
		Handoff speed threshold 50 Hz	26.0	28.1	30.4	% VCC
		Handoff speed threshold 62.5 Hz	32.2	34.4	36.6	% VCC
		Handoff speed threshold 75 Hz	38.5	40.6	42.9	% VCC
		Handoff speed threshold 87.5 Hz	44.7	46.8	48.9	% VCC
		Handoff speed threshold 100 Hz	50.7	53.1	55.1	% VCC
		Handoff speed threshold 112.5 Hz	57.0	59.3	61.3	% VCC
		Handoff speed threshold 125 Hz	63.2	65.6	67.6	% VCC
		Handoff speed threshold 137.5 Hz	69.5	71.9	73.8	% VCC
		Handoff speed threshold 150 Hz	75.6	78.1	80.1	% VCC
		Handoff speed threshold 162.5 Hz	81.9	84.4	86.3	% VCC
		Handoff speed threshold 175 Hz	88.2	90.6	92.6	% VCC
		Handoff speed threshold 187.5 Hz	94.5	96.9	100	% VCC
r_i	CONFIG pin input impedance			10		MΩ
LOCK PROTECTION						
t_{ON_LOCK}	Lock detect time	Abnormal Kt lock		0.3	0.33	s
t_{OFF_LOCK}	Lock release time			5	5.9	s
SHORT CIRCUIT CURRENT PROTECTION						
I_{SHT}	Short circuit current protection			1.8		A
THERMAL SHUTDOWN						
T_{SD}	Thermal shutdown temperature			160		°C
T_{SD_HYS}	Thermal shutdown hysteresis			10		°C

6.6 Typical Characteristics

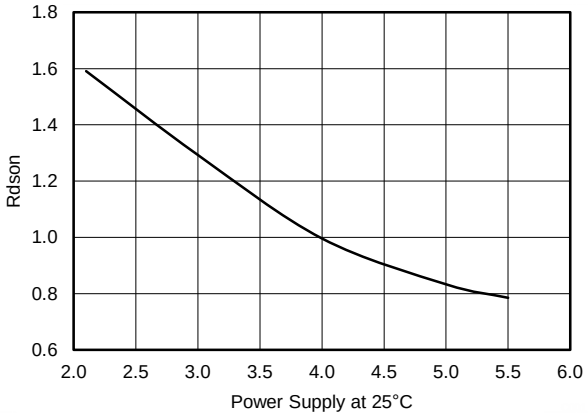


图 1. $R_{DS(ON)}$ vs Power Supply at 25°C

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7 Detailed Description

7.1 Overview

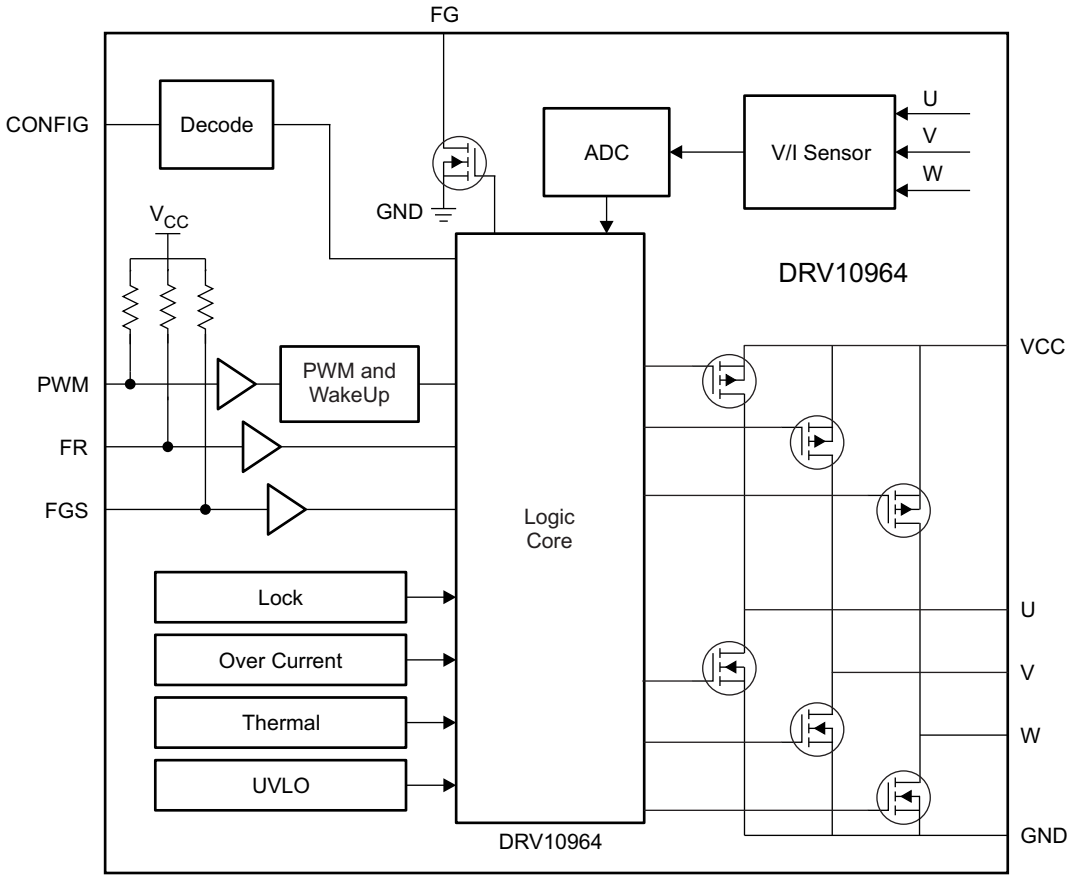
The DRV10964 device is a three phase sensorless motor driver with integrated power MOSFETs. It is specifically designed for high efficiency, low noise and low external component count motor drive applications. The proprietary sensorless windowless 180° sinusoidal control scheme provides ultra-quiet motor operation by keeping electrically induced torque ripple small.

Upon start-up, the DRV10964 device will spin the motor in the direction indicated by the FR input pin. The DRV10964 device will operate a three phase BLDC motor using a sinusoidal control scheme. The magnitude of the applied sinusoidal phase voltages is determined by the duty cycle of the PWM pin. As the motor spins, the DRV10964 device provides the speed information at the FG pin.

The DRV10964 device contains an intelligent lock detect function. In the case where the motor is stalled by an external force, the system will detect the lock condition and will take steps to protect itself as well as the motor. The operation of the lock detect circuit is described in detail in *Lock Detection* .

The DRV10964 device also contains several internal protection circuits such as overcurrent protection, overvoltage protection, undervoltage protection, and overtemperature protection.

7.2 Functional Block Diagram



7.3 Feature Description

7.3.1 Sleep Mode

When the PWM commanded duty cycle input is lower than 0.38%, but not 0%, the phase outputs will be put into a high impedance state. The device will stop driving the motor. The device logic is still active during standby mode and the DRV10964 device will consume current as specified by I_{VCC}.

Feature Description (接下页)

When the PWM commanded duty cycle input is driven to 0% (less than VIL_PWM for at least t_{SLEEP} time), the DRV10964 device will enter a low power sleep mode. In sleep mode, most of the circuitry in the device will be disabled to minimize the system current. The current consumption in this state is specified by I_{VCC_SLEEP}.

The device will remain in sleep mode until either the PWM commanded duty cycle input is driven to a logic high (higher than V_{IH_PWM}) or the PWM input pin is allowed to float. If the input is allowed to float an internal pullup resistor will raise the voltage to a logic high level.

Recovering from sleep mode is treated the same as power on condition as illustrated in 图 14.

As part of the device initialization the motor resistance value and the motor Kt value are measured during the initial motor spin up as shown in 图 14.

7.3.2 Speed Input and Control

The DRV10964 provides three-phase 25-kHz PWM outputs which have an average value of sinusoidal waveforms from phase to phase. When any phase is measured with reference to ground, the waveform observed will be a PWM encoded sinusoid coupled with third order harmonics as shown in 图 2. This encoding scheme simplifies the driver requirements because there will always be one phase output that is equal to zero.

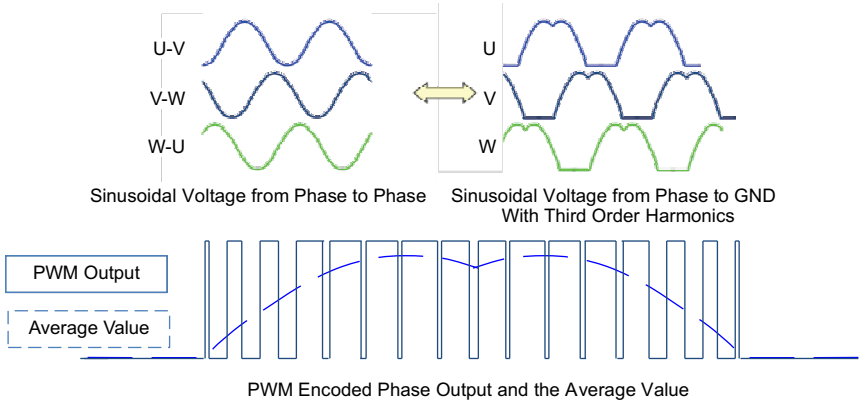


图 2. Sinusoidal Phase Encoding Used in DRV10964

The output amplitude is determined by the supply voltage (VCC) and the commanded PWM duty cycle (PWM) as described in 公式 1 and illustrated in 图 3. The maximum amplitude is applied when the commanded PWM duty cycle is 100%.

$$Vph_{pk} = PWMdc \times VCC \quad (1)$$

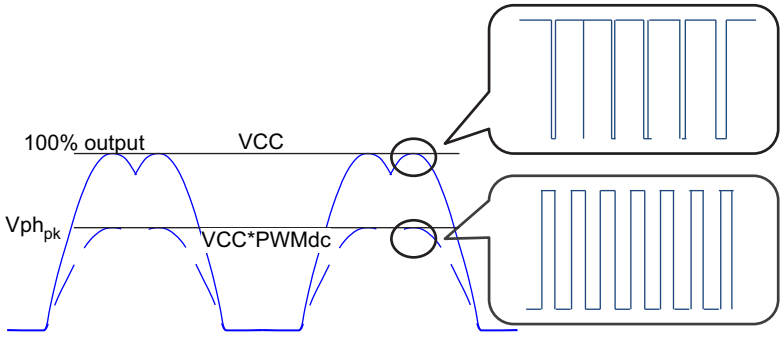


图 3. Output Voltage Amplitude Adjustment

The motor speed is controlled indirectly by using the PWM command to control the amplitude of the phase voltages which are applied to the motor.

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Feature Description (接下页)

The duty cycle of PWM input is converted into a 9-bit digital number (from 0 to 511). The control resolution is 1/512 ≈ 0.2%. The duty cycle analyzer implements a first order transfer function between the input duty cycle and the 9-bit digital number. This is illustrated in 图 4 and 图 5.

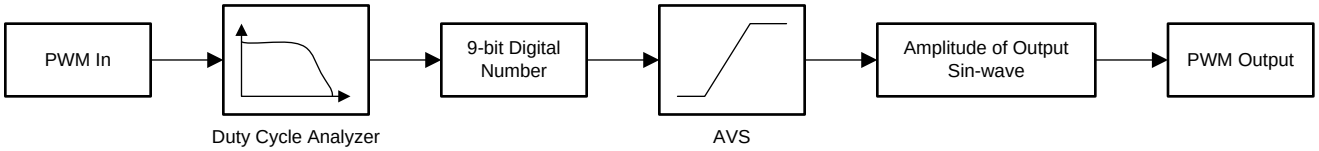


图 4. PWM Command Input Controls the Output Peak Amplitude

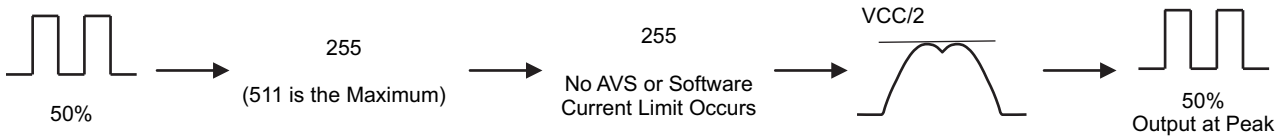


图 5. Example of PWM Command Input Controlling the Output

The transfer function between the PWM commanded duty cycle and the output peak amplitude is adjustable in the DRV10964 device. The output peak amplitude is described by 公式 1 when PWM_{dc} > minimum operation duty cycle. The minimum operation duty cycle is 10%. When the PWM commanded duty cycle is lower than minimum operation duty cycle and higher than 0.38%, the output will be controlled at the minimum operation duty cycle. When the input duty cycle is lower than 0.38%, the DRV10964 device will not drive the output, and enters the standby mode. This is illustrated in 图 6.

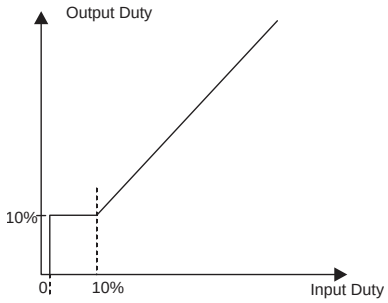


图 6. Speed Control Transfer Function

7.3.3 Motor Direction Change

The DRV10964 can be easily configured to drive the motor in either direction by setting the input on the FR (Forward Reverse) pin to a logic 1 or logic 0 state. The direction of commutation as described by the commutation sequence is illustrated in 表 1.

表 1. Motor Direction Phase Sequencing

	FR = 0	FR = 1
Motor direction	U->V->W	U->W->V

7.3.4 Motor Frequency Feedback (FG)

During operation of the DRV10964 device, the FG pin provides an indication of the speed of the motor. The output provided on this pin is configured by applying a logic signal to the FGS pin.

The formula to determine the speed of the motor is:

IF FGS = 0, RPM = (FREQFG × 60)/number of pole pairs (2)

IF FGS = 1, RPM = (FREQFG × 60 × 3)/number of pole pairs (3)

During Open Loop Acceleration the FG pin will provide an indication of the frequency of the signal which is driving the motor. The lock condition of the motor is not known during Open Loop Acceleration so it is possible that the FG could be toggling during this time even though the motor is not moving.

The FG pin has built in short circuit protection, which limits the current in the event that the pin is shorted to VCC. The current will be limited to I_{SC_FG}.

7.3.4.1 Tach Feedback During Spin Down

The DRV10964 will provide feedback on the FG pin during spin down of the motor. 图 7 illustrates the behavior of the FG output. When DRV10964 PWM input is at 0% DRV10964 will provide the output of the U phase comparator on the FG pin until the motor speed drops below 10 Hz. When the motor speed is below 10 Hz the device will enter into the Sleep state and the FG output will be held at a constant value based on the last BEMF zero cross detection.

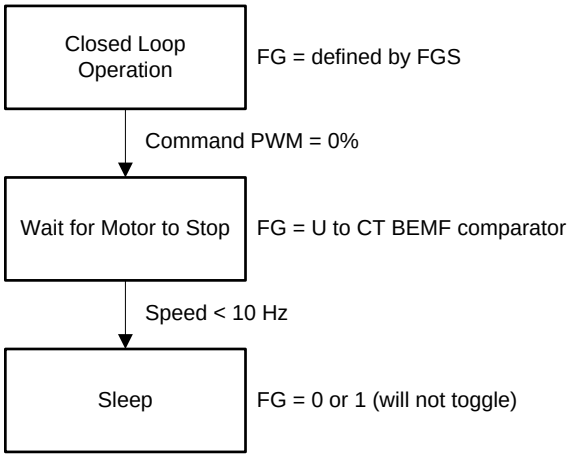


图 7. TACH Feedback on Spin Down

7.3.5 Lock Detection

When the motor is locked by some external condition the DRV10964 will detect the lock condition and will take action to protect the motor and the device. The lock condition must be properly detected whether it occurs as a result of a slowly increasing load or a sudden shock.

The DRV10964 reacts to lock conditions by stopping the motor drive. To stop driving the motor the phase outputs are placed into a high impedance state. To prevent the current which is flowing in the motor from being returned to the power supply (VCC) the DRV10964 uses an Ant-Voltage Surge feature. For more information on this feature, see *Anti-Voltage Surge (AVS)*. After successfully transitioning into a high impedance state as the result of a lock condition the DRV10964 will attempt to restart the motor after t_{OFF_LOCK} seconds.

The DRV10964 has a comprehensive lock detect function which includes 5 different lock detect schemes. Each of these schemes detects a particular condition of lock as illustrated in 图 8.

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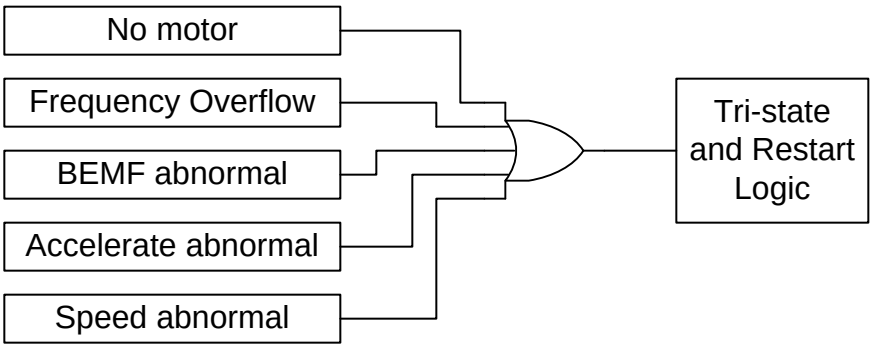


图 8. Lock Detect

The behavior of each lock detect scheme is described in the following sections.

7.3.5.1 Lock0: No Motor

The Phase U current is checked after transitioning from open loop to closed loop. If Phase U current is not greater than 50mA then the motor is not connected. This is reported as a locked condition.

7.3.5.2 Lock1: Frequency Overflow

For most applications the maximum electrical frequency of the motor will be less than 3 kHz. If the motor is stopped then the BEMF voltage will be zero. Under this condition, when the DRV10964 device is in the closed loop mode, the sensor less control algorithm will continue to accelerate the electrical commutation rate even though the motor is not spinning. A lock condition is triggered if the electrical frequency exceeds 3 kHz.

7.3.5.3 Lock2: BEMF Abnormal

For any specific motor, the integrated value of BEMF during half of an electrical cycle will be a constant as illustrated by the shaded green area in 图 9. This is true regardless of whether the motor runs fast or slow. The DRV10964 monitors this value and uses it as a criterion to determine if the motor is in a lock condition.

The DRV10964 uses the integrated BEMF to determine the Kt value of the motor during the initial motor start. Based on this measurement a range of acceptable Kt values is established. This range is between 1/2 x Kt and 4 x Kt During closed loop motor operation the Ktc value is continuously updated. If the calculated Ktc goes beyond the acceptable range a lock condition is triggered. This is illustrated in 图 10.

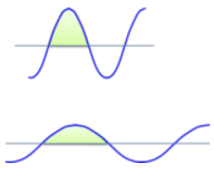


图 9. BEMF Integration

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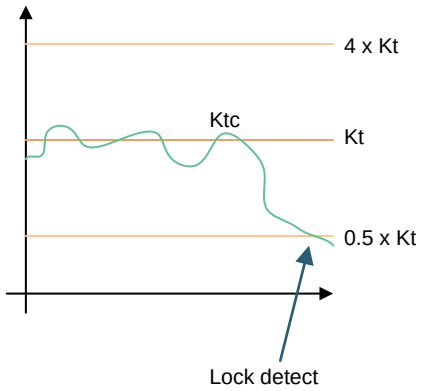


图 10. Abnormal Kt Lock Detect

7.3.5.3.1 Lock 3: Accelerate Abnormal

This lock condition is active when the DRV10964 device is operating in the closed loop mode. When the closed loop commutation rate becomes lower than 1/2 of the previous commutation period then this is an indication that the motor is not moving. Under this condition the accelerate abnormal condition will be triggered.

7.3.5.4 Lock4: Speed Abnormal

If the motor is in normal operation the motor BEMF will always be less than the voltage applied to the phase. The DRV10964 sensorless control algorithm is continuously updating the value of the motor BEMF based on the speed of the motor and the motor Kt as shown in 图 11. If the calculated value for motor BEMF is higher than the applied voltage (U) for a certain period of time (t_{ON_LOCK}) then there is an error in the system. The calculated value for motor BEMF is wrong or the motor is out of phase with the commutation logic. When this condition is detected a lock detect is triggered.

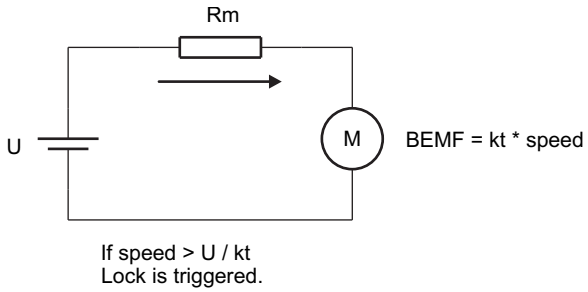


图 11. BEMF Monitoring

7.3.6 Short Circuit Current Protection

The short circuit current protection function shuts off drive to the motor by placing the motor phases into a high impedance state if the current in any motor phase exceeds the short circuit protection limit I_{SHT}. The DRV10964 device will go through the initialization sequence and will attempt to restart the motor after the short circuit condition is removed. This function is intended to protect the device and the motor from catastrophic failure when subjected to a short circuit condition.

7.3.7 Anti-Voltage Surge (AVS)

Under normal operation the DRV10964 acts to transfer energy from the power supply to the motor to generate torque, which results in angular rotation of the motor. Under certain conditions, however, energy which is stored in the motor in the form of inductive energy or angular momentum (mechanical energy) can be returned to the power supply. This can happen whenever the output voltage is quickly interrupted or whenever the voltage applied to the motor becomes less than the BEMF voltage generated by the motor. The energy which is returned to the supply can cause the supply voltage to increase. This condition is referred to as voltage surge.

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The DRV10964 includes an anti-voltage-surge (AVS) feature which prevents energy from being transferred from the motor to the power supply. This feature helps to protect the DRV10964 as well as any other components that are connected to the power supply (VCC).

7.3.7.1 Protecting Against the Return of Mechanical Energy

Mechanical energy is typically returned to the power supply when the speed command is abruptly decreased. If the voltage applied to the phase becomes less than the BEMF voltage then the motor will work as a generator and current will flow from the motor back to VCC. This is illustrated in 图 12. To prevent this from happening, the DRV10964 buffers the speed command value and limits the rate at which it is able to change. The AVS function acts to ensure that the effective output amplitude (U) is maintained to be larger than the BEMF voltage. This prevents current from becoming less than zero. The value of BEMF used to perform this function is calculated by the motor Kt and the motor speed.

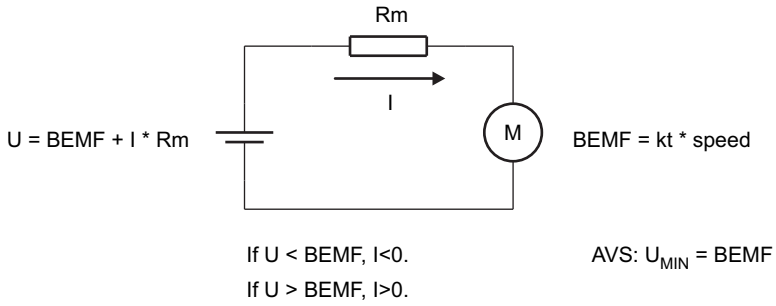


图 12. Mechanical AVS

7.3.7.2 Protecting Against the Return of Inductive Energy

When the DRV10964 suddenly stops driving the motor, the current which is flowing in the motor's inductance will continue to flow. It flows through the intrinsic body diodes in the mosfets and charges VCC. An example of this behavior is illustrated by the two pictures in the top half of 图 13. When the driver is active, the current flows from S1 to the motor and then to S6 and is returned to ground. When the driver is placed into a high impedance (tri-state) mode, the current goes flows from ground through the body diode of S2 to the motor and then through the body diode of S5 to VCC. The current will continue to flow through the motor's inductance in this direction until the inductive energy is dissipated.

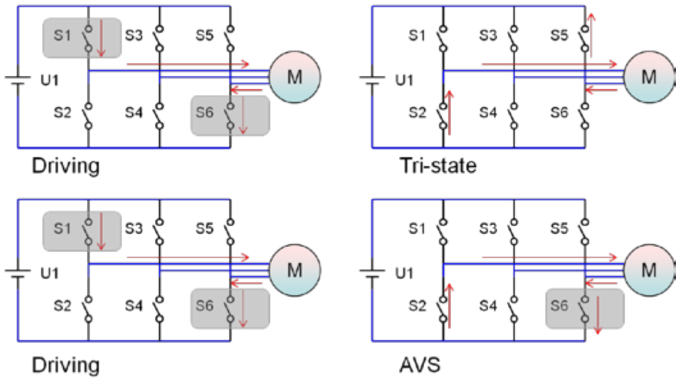


图 13. Inductive AVS

The lower two pictures in 图 13 illustrate how the AVS circuit in the DRV10964 device prevents this energy from being returned to the supply. When the AVS condition is detected the DRV10964 device will act to turn on the low side device designated as S6. This allows the current flowing in the motor inductance to be returned to ground instead of being directed to the VCC supply voltage.

7.3.8 Overtemperature Protection

The DRV10964 contains a thermal shut down function which disables motor operation when the device junction temperature has exceeded T_{SD}. Motor operation will resume when the junction temperature becomes lower than T_{SD} - T_{SD_HYS}.

7.3.9 Undervoltage Protection

The DRV10964 contains an undervoltage lockout feature, which prevents motor operation whenever the supply voltage (VCC) becomes too low. Upon power up, the DRV10964 will operate once VCC rises above V_{UVLO_H}. The DRV10964 will continue to operate until VCC falls below V_{UVLO_L}.

7.3.10 CONFIG Configuration

The CONFIG pin provides an option for selecting the open loop to closed loop threshold. This is accomplished with the selection of a resistor divider between VCC and GND which is connected to the CONFIG pin. See *Electrical Characteristics*.

7.4 Device Functional Modes

7.4.1 Spin up Settings

7.4.1.1 Motor Kt and Rm

DRV10964 utilizes information about the motor's torque constant and resistance to control motor timing. These parameters are measured during the initial motor spin up as shown in 图 14.

7.4.1.2 Motor Start

DRV10964 will start the motor using a procedure which is illustrated in 图 14.

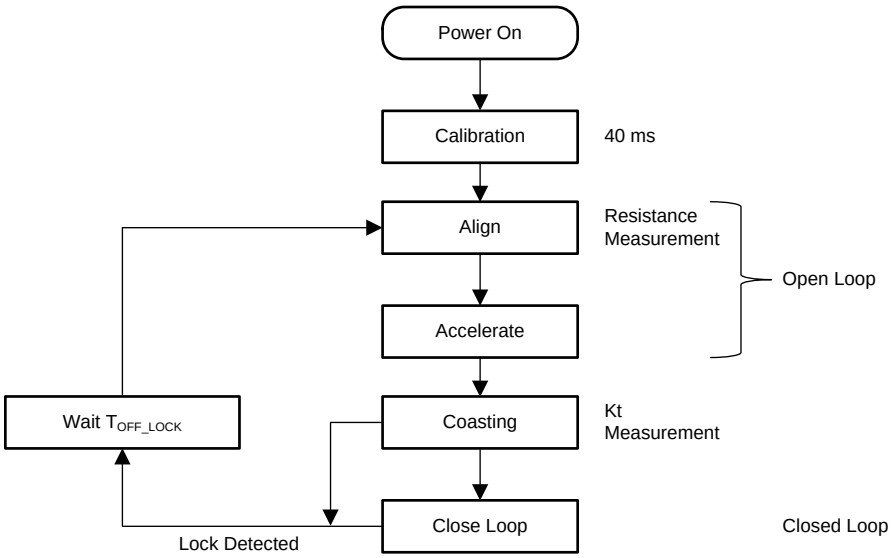


图 14. DRV10964 Initialization and Motor Start-up Sequence

7.4.1.3 Initial Speed Detect (ISD)

The ISD function is used to identify the initial condition of the motor.

Phase-to-phase comparators are used to detect the zero crossings of the motor's BEMF voltage while it is coasting (motor phase outputs are in high-impedance state). 图 15 shows the configuration of the comparators.

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Device Functional Modes (接下页)

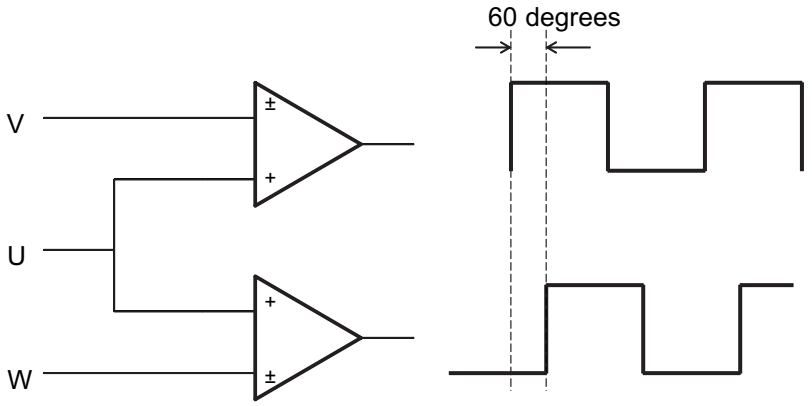


图 15. Initial Speed Detect Function

The motor speed is determined by measuring the time between two rising edges of either of the comparators.

If neither of the comparator outputs toggle for a given amount of time (80 ms), the condition is defined as stationary and the Align state will begin. If the comparators are toggling at a speed that is greater than this threshold then the DRV10964 will wait for the motor to slow down until the toggling is less than the threshold and it can be treated as stationary.

7.4.1.4 Align

To align the rotor to the commutation logic the DRV10964 applies a 50% duty cycle on phases V and W while holding phase U at GND. This condition is maintained for 0.64 seconds. In order to avoid a sudden change in current that could result in undesirable acoustics the 50% duty cycle is applied gradually to the motor over 0.3 seconds.

7.4.1.5 Handoff and Closed Loop

When the motor accelerates to the velocity defined by the voltage applied to the CONFIG pin, commutation control transitions from open loop mode to closed loop mode. The commutation drive sequence and timing is determined by the internal control algorithm and the applied voltage is determined by the PWM commanded duty cycle input.

The selection of handoff threshold can be determined by experimental testing. The goal is to choose a handoff threshold that is as low as possible and allows the motor to smoothly and reliably transition between the open loop acceleration and the closed loop acceleration. Normally higher speed motors (maximum speed) require a higher handoff threshold because higher speed motors have lower Kt and as a result lower BEMF. 表 2 shows the configurable settings for the handoff threshold. Maximum speed in electrical hertz are shown as a guide to assist in identifying the appropriate handoff speed for a particular application.

表 2. Motor Handoff Speed Threshold Options

MAXIMUM SPEED (Hz)	Hand Off Frequency (Hz)	CONFIG[3:0]
350 to approximately 400	87.5	0x0
<100	12.5	0x1
100 to approximately 150	25	0x2
150 to approximately 200	37.5	0x3
200 to approximately 250	50	0x4
250 to approximately 300	62.5	0x5
300 to approximately 350	75	0x6
350 to approximately 400	87.5	0x7
400 to approximately 450	100	0x8
450 to approximately 500	112.5	0x9

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Device Functional Modes (接下页)

表 2. Motor Handoff Speed Threshold Options (接下页)

MAXIMUM SPEED (Hz)	Hand Off Frequency (Hz)	CONFIG[3:0]
500 to approximately 560	125	0xA
560 to approximately 620	137.5	0xB
620 to approximately 700	150	0xC
700 to approximately 800	162.5	0xD
800 to approximately 900	175	0xE
>900	187.5	0xF

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8 Application and Implementation

注

Information in the following applications sections is not part of the TI component specification, and TI does not warrant its accuracy or completeness. TI's customers are responsible for determining suitability of components for their purposes. Customers should validate and test their design implementation to confirm system functionality.

8.1 Application Information

DRV10964 is used in sensorless three-phase BLDC motor control. The driver provides a high performance, high reliability, flexible and simple solution for compute fan applications. The following design shows a common application of the DRV10964.

8.2 Typical Application

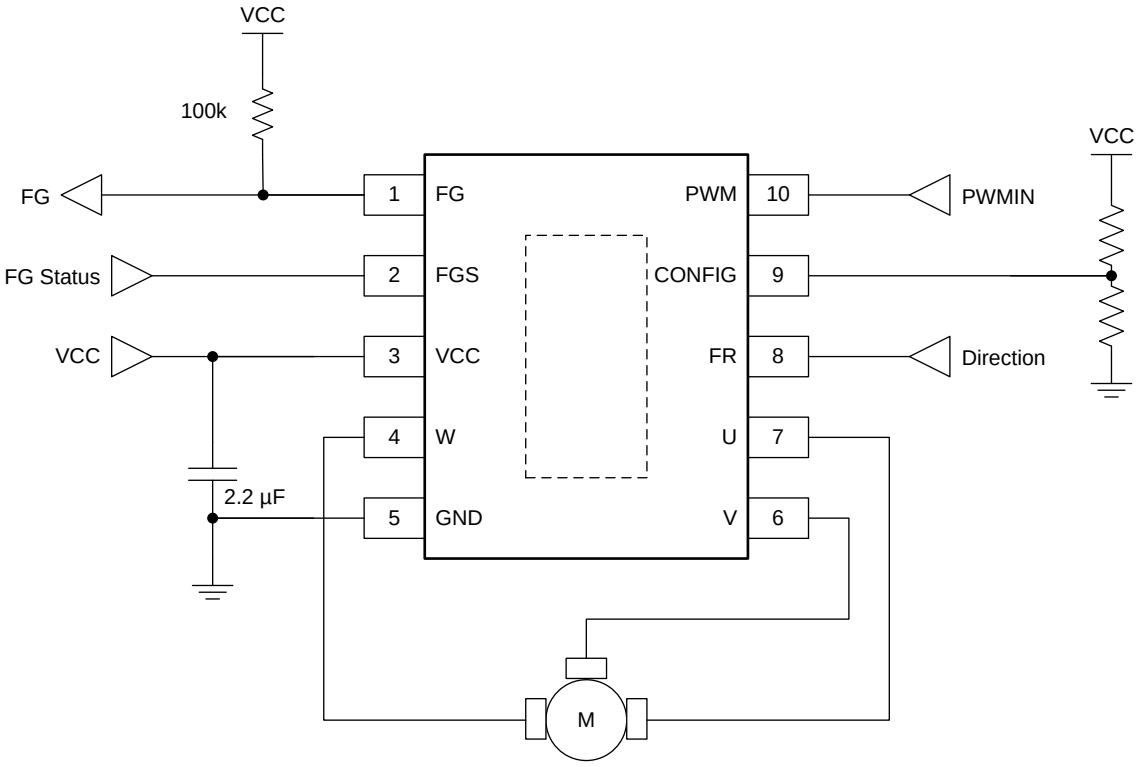


图 16. Typical Application Schematic

8.2.1 Design Requirements

表 3 lists several key motor characteristics and recommended ranges which the DRV10964 is capable of driving. However, that does not necessarily mean motors outside these boundaries cannot be driven by DRV10964.

Recommended ranges listed in 表 3 can serve as a general guideline to quickly decide whether DRV10964 is a good fit for an application. Motor performance is not ensured for all uses.

表 3. Key Motor Characteristics and Recommended Ranges

	Rm (Ω)	Lm (µH)	Kt (mV/Hz)	f_{FG_max} (Hz)
Recommended Value	2.5 ~ 10	50 ~ 1000	1 ~ 100	1300

Rm - Motor phase resistance between phase to phase;

Lm - Motor phase to phase inductance between phase to phase;

Kt - Motor BEMF constant from phase to center tape;

f_{FG_max} - Maximum electrical frequency. Maximum motor speed can be calculated from:

- If FGS = 1, RPM = (f_{FG_max} × 3 x 60)/ number of pole pairs
- If FGS = 0, RPM = (f_{FG_max} × 120)/ number of pole pairs

8.2.2 Detailed Design Procedure

1. Refer to *Design Requirements* and make sure your system meets the recommended application range.

2. Refer to the DRV10964 Tuning Guide and measure the motor parameters.

3. Refer to the DRV10964 Tuning Guide. Configure the parameters using DRV10964 GUI, and optimize the motor operation. The Tuning Guide takes the user through all the configurations step by step, including: start-up operation, closed-loop operation, current control, initial positioning, lock detection, and anti-voltage surge.

4. Build your hardware based on Layout Guidelines.

5. Connect the device into system and validate your system solution

8.2.3 Application Curves

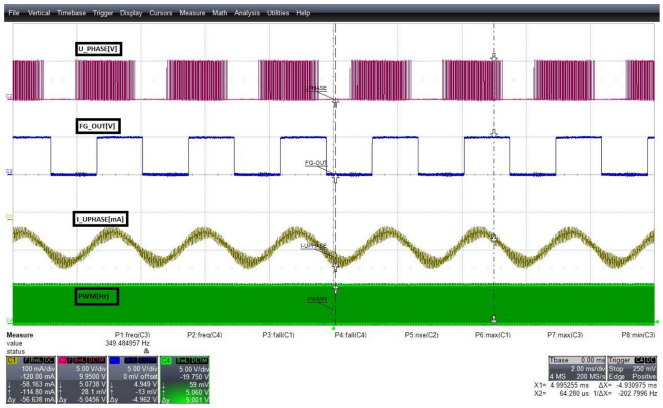
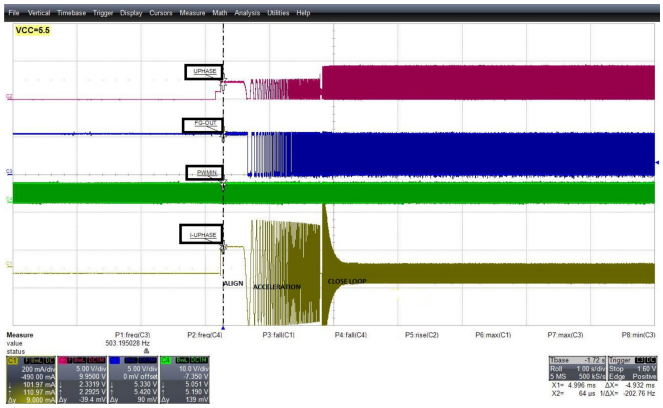


图 17. Reference PCB Sinusoidal Current Profile



NOTE: FG_OUT Signal Being Held HIGH During Locked Rotor Condition (Stall)

图 18. Reference PCB Start-Up (Align-Acceleration) Profile

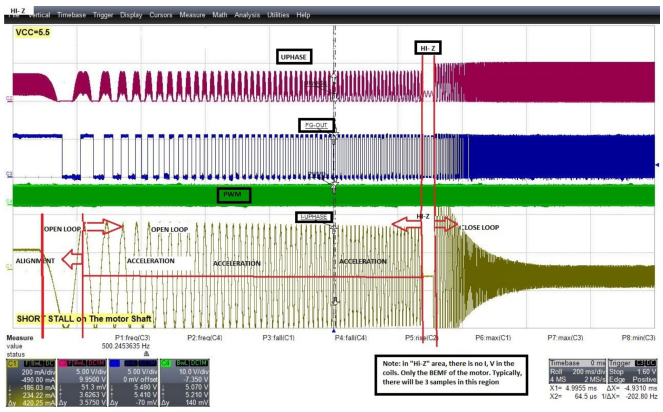


图 19. Reference PCB Open Loop and Close Loop

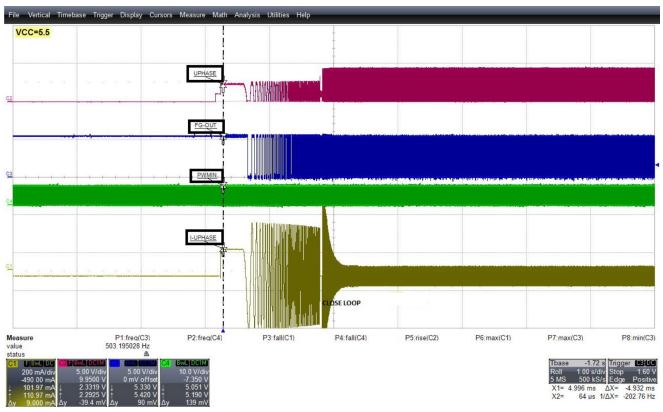


图 20. Reference PCB Closed Loop

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9 Power Supply Recommendations

The DRV10964 is designed to operate from an input voltage supply, V(VCC), range from 2.1 and 5.5 V. The user must place a 2.2-µF ceramic capacitor rated for VCC as close as possible to the VCC and GND pin.

10 Layout

10.1 Layout Guidelines

The package uses an exposed pad to remove heat from the device. For proper operation, this pad must be thermally connected to copper on the PCB to dissipate heat. On a multi-layer PCB with a ground plane, this can be accomplished by adding a number of vias to connect the thermal pad to the ground plane. On PCBs without internal planes, copper area can be added on either side of the PCB to dissipate heat. If the copper area is on the opposite side of the PCB from the device, thermal vias are used to transfer the heat between top and bottom layers.

For details about how to design the PCB, refer to TI application report, *PowerPAD™ Thermally Enhanced Package* (SLMA002), and TI application brief, *PowerPAD™ Made Easy* (SLMA004), available at www.ti.com. In general, the more copper area that can be provided, the more power can be dissipated.

10.2 Layout Example

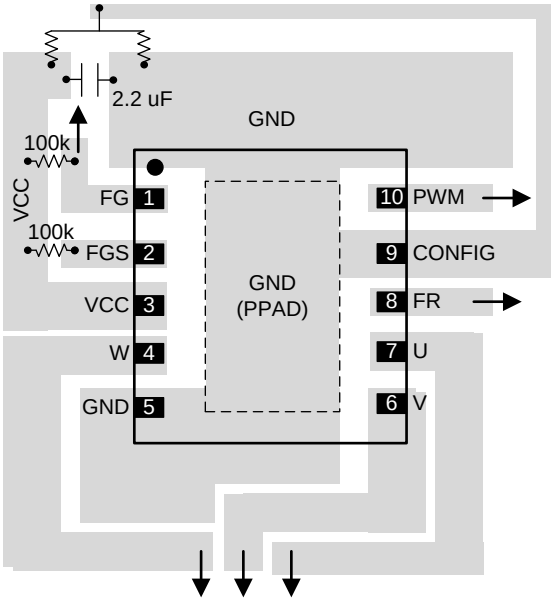


图 21. DRV10964 Layout Example

11 器件和文档支持

11.1 社区资源

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11.4 Glossary

SLYZ022 — *TI Glossary*.

This glossary lists and explains terms, acronyms, and definitions.

12 机械、封装和可订购信息

以下页中包括机械、封装和可订购信息。这些信息是针对指定器件可提供的最新数据。这些数据会在无通知且不对本文档进行修订的情况下发生改变。欲获得该数据表的浏览器版本，请查阅左侧的导航栏。

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PACKAGING INFORMATION

Orderable Device	Status (1)	Package Type	Package Drawing	Pins	Package Qty	Eco Plan (2)	Lead/Ball Finish (6)	MSL Peak Temp (3)	Op Temp (°C)	Device Marking (4/5)	Samples
DRV10964FFDSNR	ACTIVE	SON	DSN	10	3000	Green (RoHS & no Sb/Br)	CU NIPDAU	Level-2-260C-1 YEAR	-40 to 125	964FF1	Samples
DRV10964FFDSNT	ACTIVE	SON	DSN	10	250	Green (RoHS & no Sb/Br)	CU NIPDAU	Level-2-260C-1 YEAR	-40 to 125	964FF1	Samples

(1) The marketing status values are defined as follows:
ACTIVE: Product device recommended for new designs.
LIFEBUY: TI has announced that the device will be discontinued, and a lifetime-buy period is in effect.
NRND: Not recommended for new designs. Device is in production to support existing customers, but TI does not recommend using this part in a new design.
PREVIEW: Device has been announced but is not in production. Samples may or may not be available.
OBSOLETE: TI has discontinued the production of the device.

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RoHS Exempt: TI defines "RoHS Exempt" to mean products that contain lead but are compliant with EU RoHS pursuant to a specific EU RoHS exemption.
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(3) MSL, Peak Temp. - The Moisture Sensitivity Level rating according to the JEDEC industry standard classifications, and peak solder temperature.

(4) There may be additional marking, which relates to the logo, the lot trace code information, or the environmental category on the device.

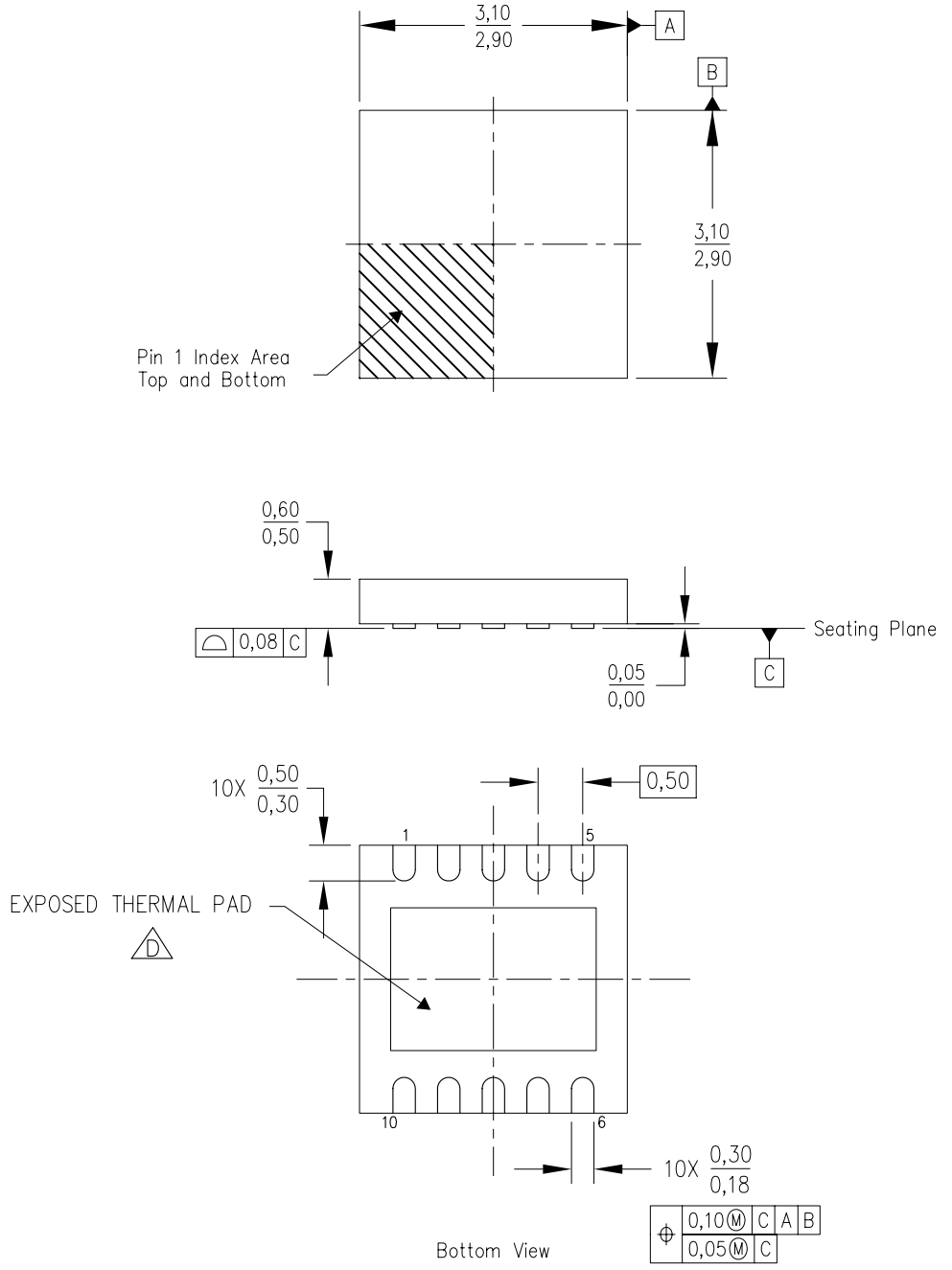
(5) Multiple Device Markings will be inside parentheses. Only one Device Marking contained in parentheses and separated by a "~" will appear on a device. If a line is indented then it is a continuation of the previous line and the two combined represent the entire Device Marking for that device.

(6) Lead/Ball Finish - Orderable Devices may have multiple material finish options. Finish options are separated by a vertical ruled line. Lead/Ball Finish values may wrap to two lines if the finish value exceeds the maximum column width.

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DSN (S–PUSON–N10) PLASTIC QUAD FLATPACK NO–LEAD



4209052/B 11/10

NOTES:
A. All linear dimensions are in millimeters. Dimensioning and tolerancing per ASME Y14.5–1994.
B. This drawing is subject to change without notice.
C. QFN (Quad Flatpack No–Lead) package configuration.
D. The package thermal pad must be soldered to the board for thermal and mechanical performance. See the Product Data Sheet for details regarding the exposed thermal pad dimensions.

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