

# iMOTION™ IMC100

## High performance motor control IC series

IMC100

Quality Requirement Category: Industry

### Feature list

- Motion Control Engine (MCE) as ready-to-use solution for variable speed drives
- Field oriented control (FOC) for permanent magnet synchronous motor (PMSM)
- Space vector PWM with sinusoidal commutation and integrated protection features
- Current sensing via single or leg shunt
- Sensorless operation
- Optional support for hall sensors (analog or digital)
- Optional boost or totem pole PFC control integrated
- Flexible host interface options for motor control commands: UART, PWM or analog input signal
- Support for IEC/UL 60335 ('Class B')
- Integrated scripting engine for application flexibility
- Multiple package options

### Applications

- Refrigerators
- Home appliances
- Pumps, fans
- ...any other PMSM drive

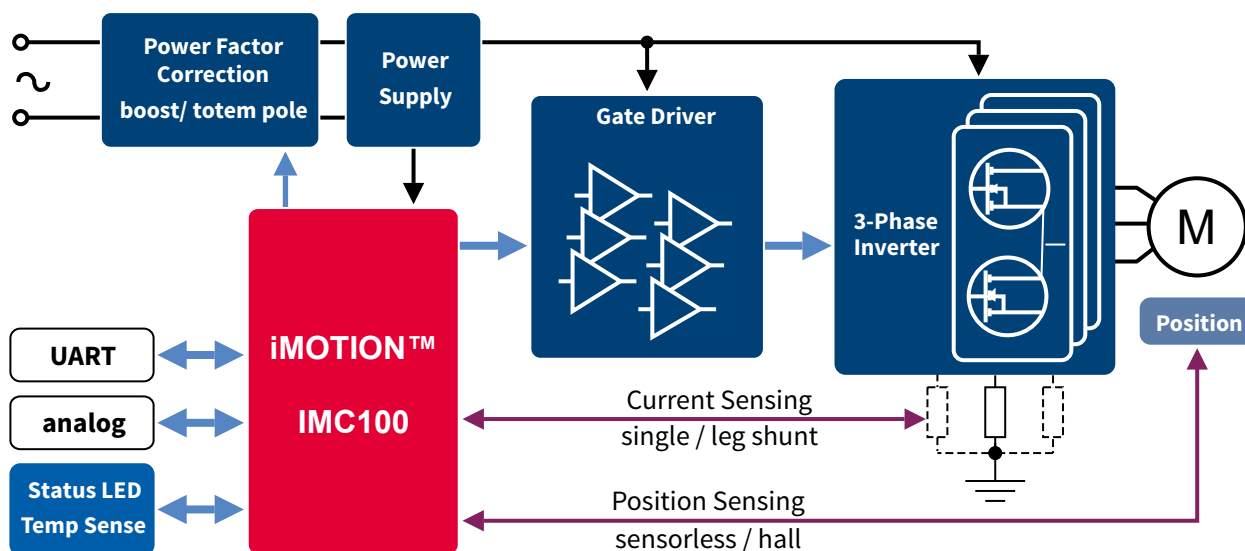
### Ordering Information

Product Type	Application	Package
IMC099T-T038	single motor, no scripting, no class B	TSSOP-38
IMC101T-T038	single motor	TSSOP-38
IMC101T-Q048		QFN-48
IMC101T-F048		LQFP-48
IMC101T-F064		LQFP-64
IMC102T-F048	single motor + PFC (boost, totem pole)	LQFP-48
IMC102T-F064		LQFP-64

**Description**

**Description**

iMOTION™ IMC100 is a family of highly integrated ICs for the control of variable speed drives. By integrating both the required hardware and software to perform control of a permanent magnet synchronous motor (PMSM) they provide the shortest time to market for any motor system at the lowest system and development cost. The integrated script engine allows to add application flexibility without interfering with the motor and PFC control algorithm.



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**About this document**

**Scope and purpose**

This Datasheet describes the mechanical, electrical and functional characteristics of the iMOTION™ IMC100 series of motor control ICs. If no specific device is given the characteristics are valid for all devices within the iMOTION™ IMC100 series.

For a detailed description of the functionality and configuration options please refer to the reference manual of the Motion Control Engine.

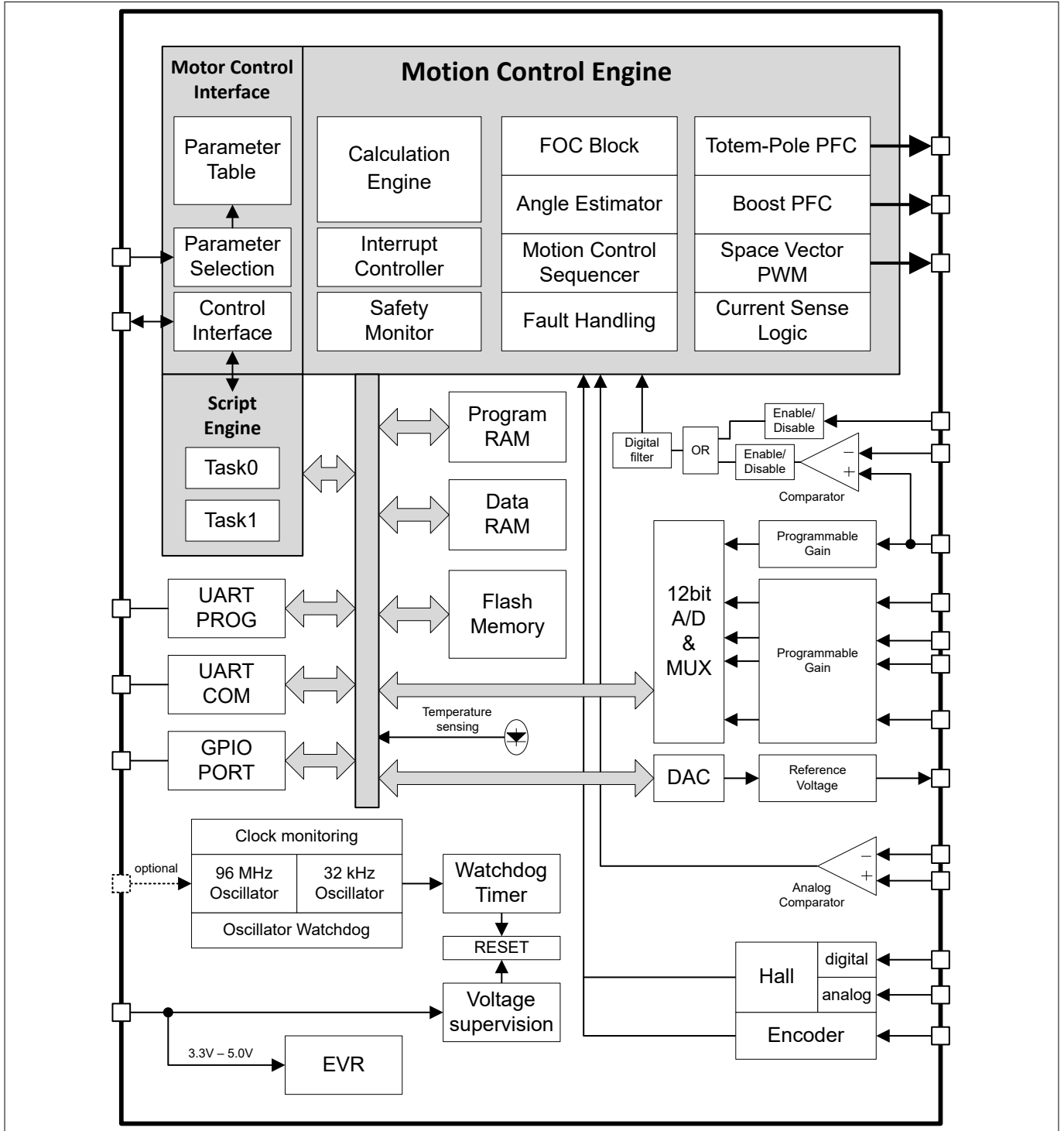
**Intended audience**

The Datasheet is targeting developers implementing a variable speed drive.

**Block Diagram Reference**

**1 Block Diagram Reference**

The block diagram below gives an overview on the available functional units in the iMOTION™ IMC100 family. Not all units are required in all applications and some modules might share pins in smaller packages. Please refer to the pin configuration for the individual packages and the application schematic examples given.



**Figure 1 Block diagram**

**Pin Configuration**

## 2 Pin Configuration

The following tables give the pin configurations of the individual devices of the IMC100 series in the available packages.

The pin type is specified as follows:

- I - digital input
- O - digital output
- AIN - analog input

The pin function given below refers to the standard software configuration. Different software might configure pins differently. Some of the input pins can be configured to have pull up or pull down resistor and some output pins can be configured to push-pull or open drain. This is described in the reference manual of the respective software.

Pins can serve multiple functions and have to be configured accordingly. Please also refer to the respective pin configuration drawings in this data sheet and the description in the MCE software manual.

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

*Note: All required reference voltages are generated by an internal DAC, therefore the pins like REFU, REFV, REFW and PFCREF only require a blocking capacitor.*

### 2.1 Pin Configuration IMC099T/ IMC101T

*Note: IMC099T-T038 does not support scripting. Therefore the scripting pins given below for the TSSOP-38 package only apply to the IMC101T-T038.*

**Table 1 Pin list**

Signal	Type	LQFP-64	VQFN-48	LQFP-48	TSSOP-38	Description
Supply						
VDD	Power	2, 24, 25, 35, 50	18, 19, 27, 38	21, 28, 38	10, 26	Supply Voltage
VSS	Power	1, 23, 49	17, 37	20, 37	9, 25	Ground
Motor control						
PWMUL	O	29	21	22	11	PWM output phase U low side
PWMUH	O	30	22	23	12	PWM output phase U high side
PWMVL	O	31	23	24	13	PWM output phase V low side
PWMVH	O	32	24	25	14	PWM output phase V high side
PWMWL	O	33	25	26	15	PWM output phase W low side
PWMWH	O	34	26	27	16	PWM output phase W high side
GK	I	36	28	29	18	Motor gate kill input
VDC	AIN	14	8	11	2	DC bus sensing input
ISS/IU	AIN	18	12	15	6	Current sense input single shunt / phase U
IV	AIN	15	9	12	3	Current sense input phase V / analog input

**(table continues...)**

**Pin Configuration**

**Table 1** (continued) Pin list

Signal	Type	LQFP-64	VQFN-48	LQFP-48	TSSOP-38	Description
IW	AIN	11	5	8	37	Current sense input phase W / analog input
REFU	AIN	17	11	14	5	Itrip phase U reference / analog input
REFV	AIN	16	10	13	4	Itrip phase V reference / analog input
REFW	AIN	10	4	7	36	Itrip phase W reference / analog input
Hall sensor inputs						
AHALL1+	AIN	10	4	7	36	Analog hall 1 positive input
AHALL1-	AIN	11	5	8	37	Analog hall 1 negative input
AHALL2+	AIN	16	10	13	4	Analog hall 2 positive input
AHALL2-	AIN	15	9	12	3	Analog hall 2 negative input
HALL1	I	26	44	47	1	Digital hall input 1
HALL2	I	27	45	48	38	Digital hall input 2
HALL3	I	28	46	1	8	Digital hall input 3
Interface						
DIR	I	52	40	40	28	Direction input
DUTYFREQ <sup>1)</sup>	I	55	43	43	31	Duty/Frequency input
VSP	AIN	9	3	6	35	Analog speed reference input
PGOUT	O	42	30	34	21	Pulse output
PARAM	AIN	20	14	17	8	Parameter table selection, analog
PAR0	I	3	33	2	22	Parameter page select 0
PAR1	I	4	34	3	23	Parameter page select 1
PAR2	I	5	35	4	24	Parameter page select 2
PAR3	I	6	36	5	27	Parameter page select 3
NTC	AIN	13	7	10	7	External thermistor input
LED	O	41	29	35	17	Status LED
Communication						
RX0	I	57	45	45	33	Serial port 0, device programming, receive input
TX0	O	58	46	46	34	Serial port 0, device programming, transmit output
RX1	I	63	47	30	20	Serial port 1, user communication, receive input
TX1	O	64	48	31	19	Serial port 1, user communication, transmit output
Scripting						
AIN0	AIN	9	3	6	35	Analog input 0

**(table continues...)**

<sup>1</sup> Function not available when used with Hall sensor mode (i.e. AHALL1+/- and AHALL2+/- or HALL1/2/3 are used)

**Pin Configuration**

**Table 1** (continued) Pin list

Signal	Type	LQFP-64	VQFN-48	LQFP-48	TSSOP-38	Description
AIN1	AIN	10	4	7	36	Analog input 1
AIN2	AIN	11	5	8	37	Analog input 2
AIN3	AIN	12	6	9	38	Analog input 3
AIN4	AIN	13	7	10	1	Analog input 4
AIN7	AIN	16	10	13	4	Analog input 7
AIN8	AIN	17	11	14	5	Analog input 8
AIN10	AIN	19	13	16	7	Analog input 5
AIN11	AIN	20	14	17	8	Analog input 6
GPIO2	IO	3	33	2	22	Digital input/output 2
GPIO3	IO	4	34	3	23	Digital input/output 3
GPIO4	IO	5	35	4	24	Digital input/output 4
GPIO5	IO	6	36	5	27	Digital input/output 5
GPIO6	IO	52	40	40	28	Digital input/output 6
GPIO7	IO	7	1	1	29	Digital input/output 7
GPIO8	IO	8	2	32	30	Digital input/output 8
GPIO9	IO	26	20	33	32	Digital input/output 9
GPIO10	IO	27	31	36		Digital input/output 10
GPIO11	IO	28	32	39		Digital input/output 11
GPIO12	IO	37	39	41		Digital input/output 12
GPIO13	IO	38	41	42		Digital input/output 13
GPIO14	IO	39	42	44		Digital input/output 14
GPIO15	IO	40	44	47		Digital input/output 15
GPIO16	IO	43	15	48		Digital input/output 16
GPIO17	IO	44	16	18		Digital input/output 17
GPIO18	IO	45		19		Digital input/output 18
GPIO19	IO	46				Digital input/output 19
GPIO20	IO	47				Digital input/output 20
GPIO21	IO	48				Digital input/output 21
GPIO22	IO	51				Digital input/output 22
GPIO23	IO	53				Digital input/output 23
GPIO24	IO	54				Digital input/output 24
GPIO25	IO	56				Digital input/output 25
GPIO26	IO	59				Digital input/output 26
GPIO27	IO	60				Digital input/output 27
GPIO28	IO	61				Digital input/output 28
GPIO29	IO	62				Digital input/output 29

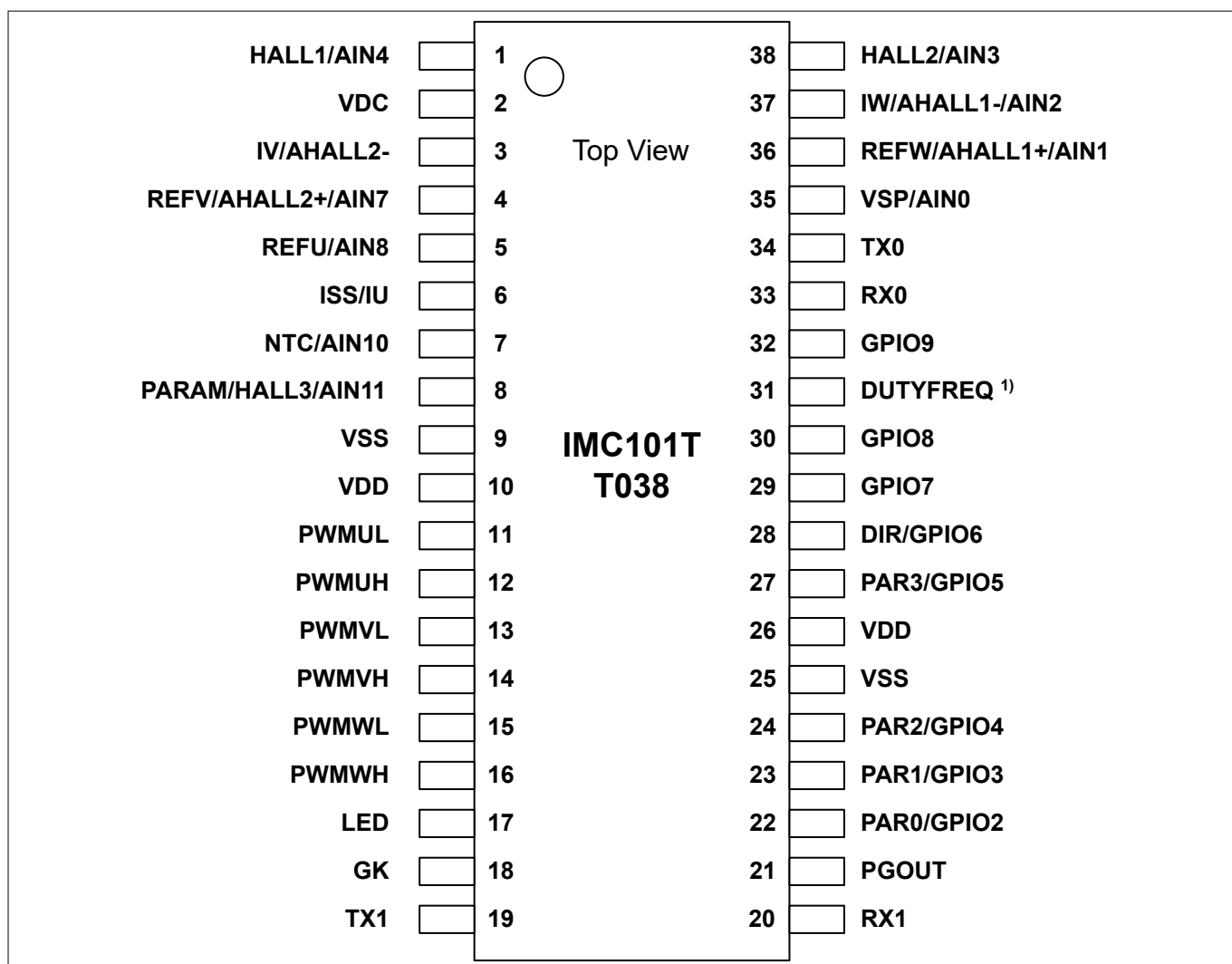


**Pin Configuration**

**2.2 Pin Configuration Drawing IMC099T/ IMC101T**

The following drawings give the position of the functional pins for the available packages.

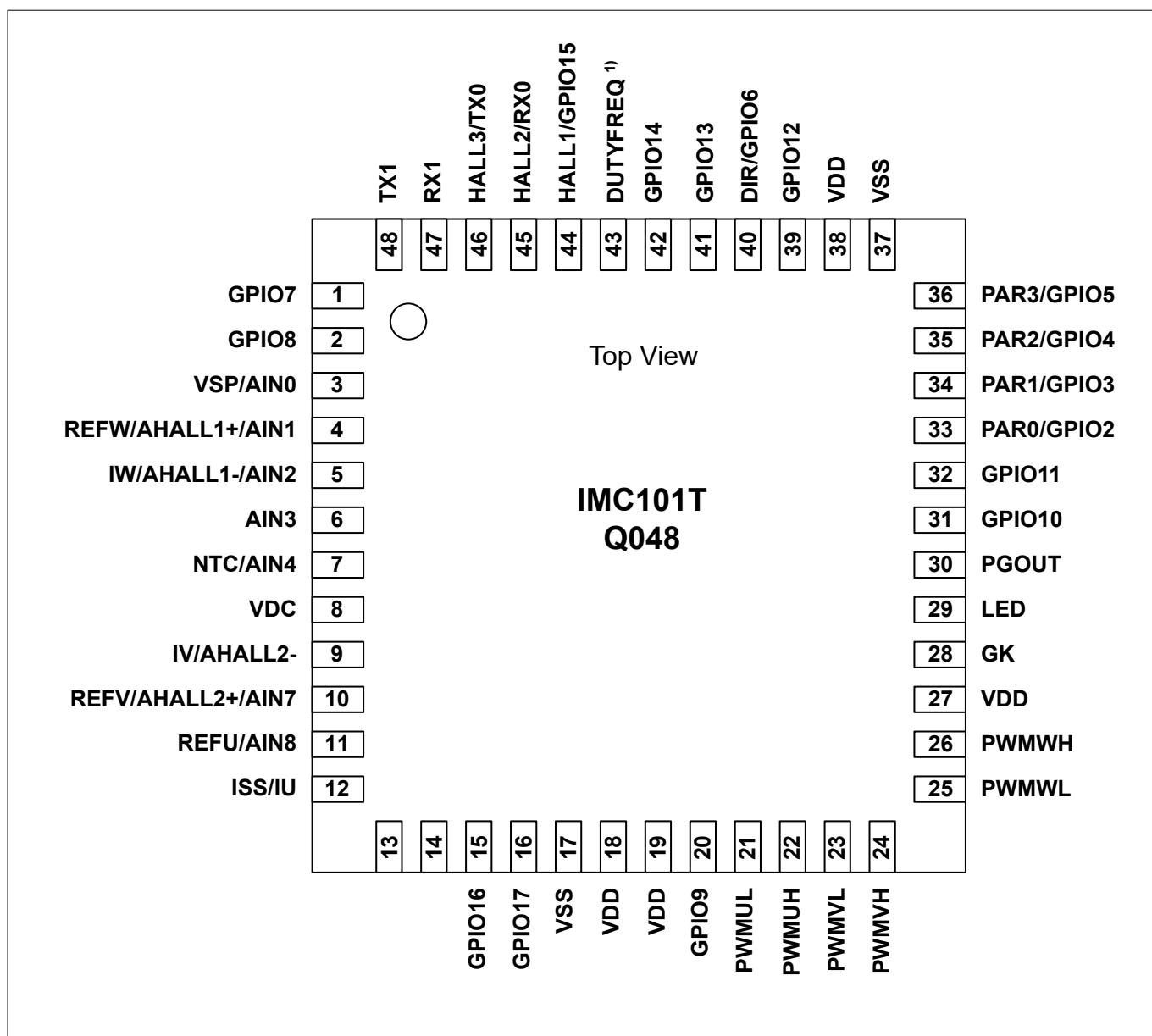
*Note: IMC099T-T038 does not support scripting. Therefore the scripting pins given in the drawing below for the TSSOP-38 package only apply to the IMC101T-T038.*



**Figure 2 IMC099T-T038, IMC101T-T038**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

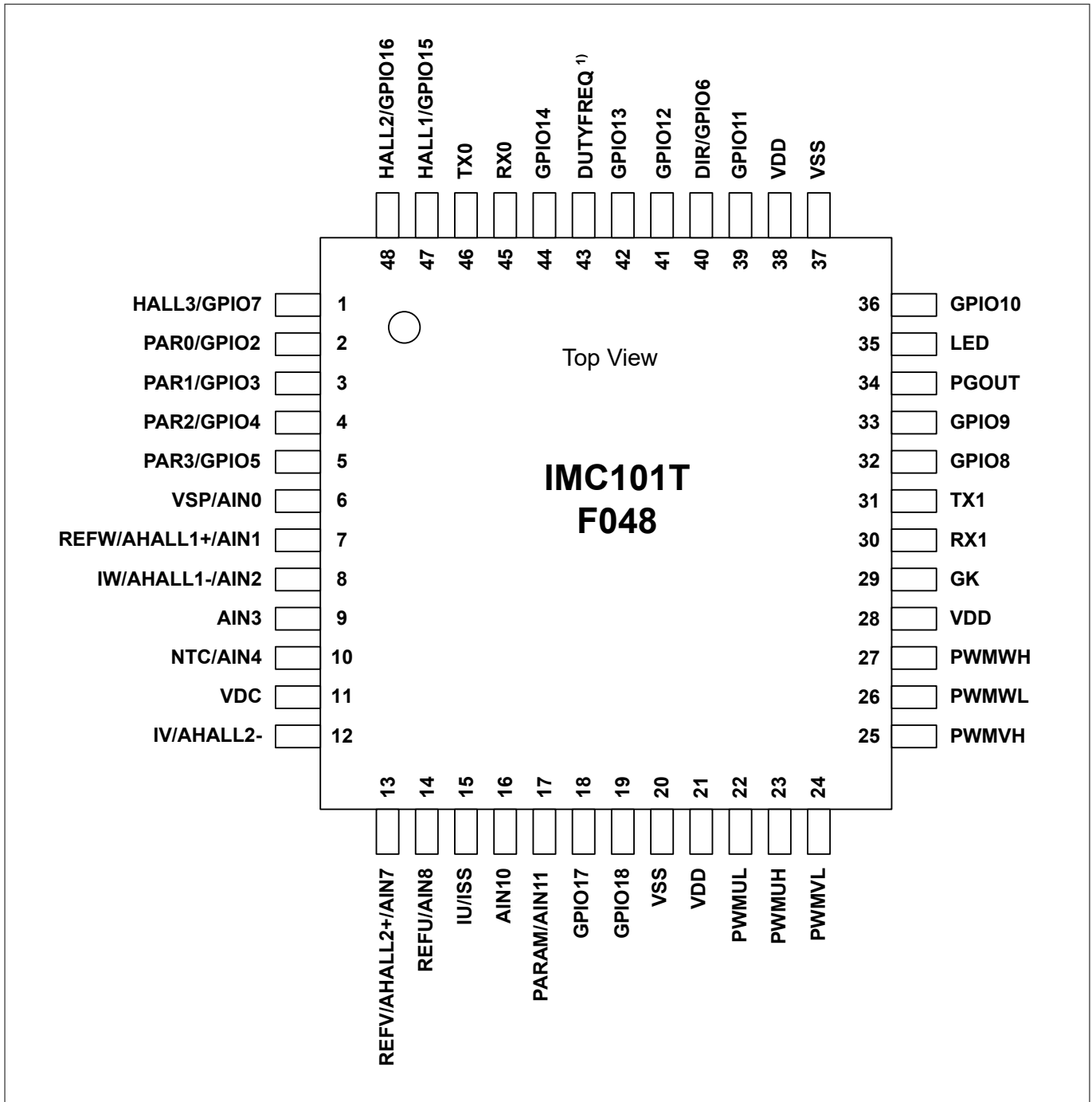
**Pin Configuration**



**Figure 3 IMC101T-Q048**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

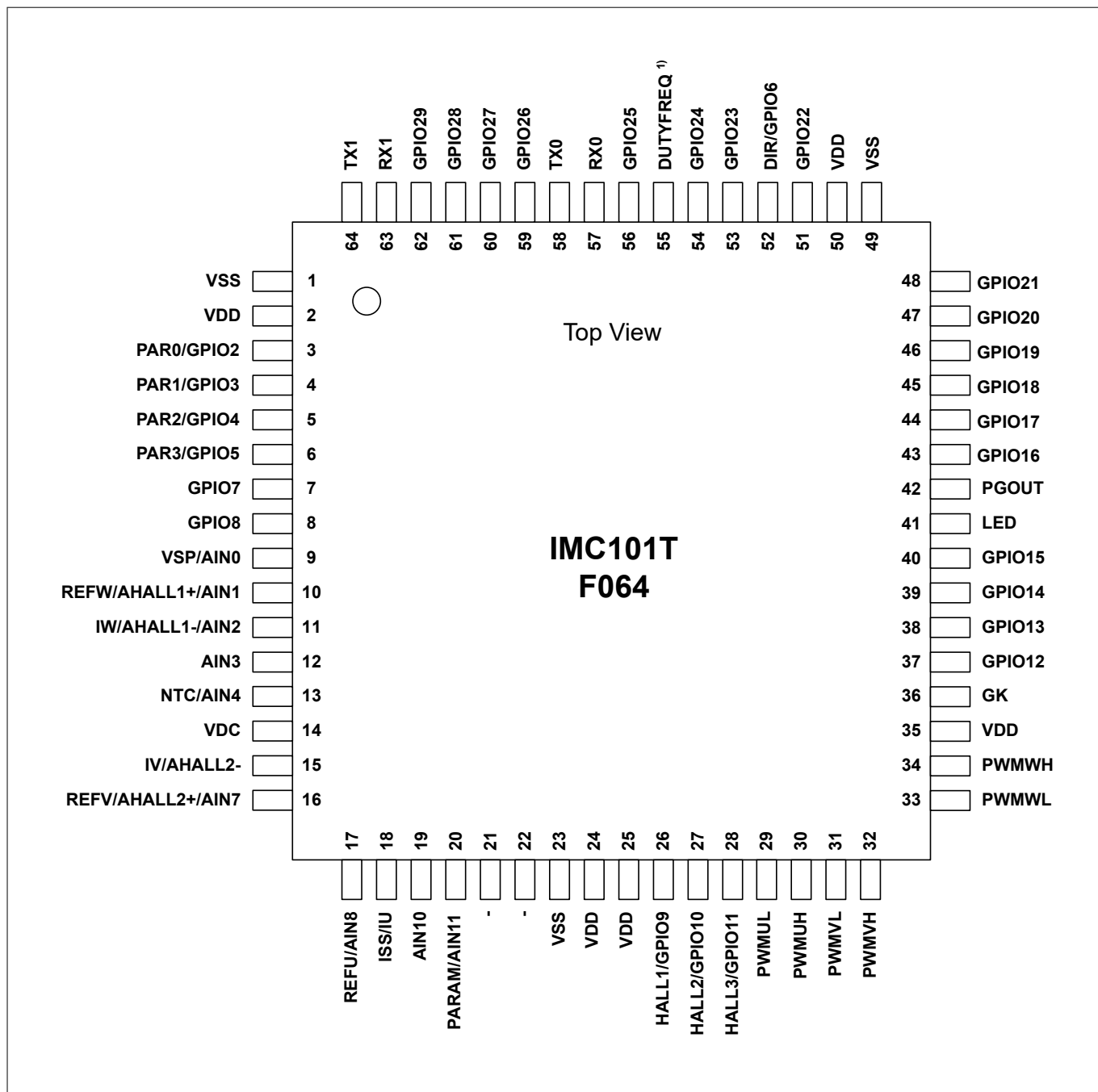
**Pin Configuration**



**Figure 4 IMC101T-F048**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

**Pin Configuration**



**Figure 5 IMC101T-F064**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

**Pin Configuration**

**2.3 Pin Configuration IMC102T**

**Table 2 Pin list Motion Control Engine**

Signal	Type	LQFP-64	LQFP-48	Description
<b>Supply</b>				
VDD	Power	2, 24, 25, 35, 50	21, 28, 38	Supply Voltage
VSS	Power	1, 23, 49	20, 37	Ground
<b>Motor control</b>				
PWMUL	O	29	22	PWM output phase U low side
PWMUH	O	30	23	PWM output phase U high side
PWMVL	O	31	24	PWM output phase V low side
PWMVH	O	32	25	PWM output phase V high side
PWMWL	O	33	26	PWM output phase W low side
PWMWH	O	34	27	PWM output phase W high side
GK	I	36	29	Motor gate kill input
VDC	AIN	14	11	DC bus sensing input
ISS/IU	AIN	18	15	Current sense input single shunt / phase U
IV	AIN	15	12	Current sense input phase V / analog input
IW	AIN	11	8	Current sense input phase W / analog input
REFU	AIN	17	14	Itrip phase U reference / analog input
REFV	AIN	16	13	Itrip phase V reference / analog input
REFW	AIN	10	7	Itrip phase W reference / analog input
<b>Hall sensor inputs</b>				
AHALL1+	AIN	10	7	Analog hall 1 positive input
AHALL1-	AIN	11	8	Analog hall 1 negative input
AHALL2+	AIN	16	13	Analog hall 2 positive input
AHALL2-	AIN	15	12	Analog hall 2 negative input
HALL1	I	26	47	Digital hall input 1
HALL2	I	27	48	Digital hall input 2
HALL3	I	28	1	Digital hall input 3
<b>Power factor correction</b>				
PFCG0	O	44	33	PFC gate drive 0
PFCG1	O	43	32	PFC gate drive 1 (totem pole only - high side switch)
PFCI	AIN	12	9	PFC current sensing
PFCREF	AIN	21	18	Itrip PFC reference input
PFCITRIP	AIN	22	19	Itrip PFC input
VAC1	AIN	20	17	VAC sense input line 1
VAC2	AIN	19	16	VAC sense input line 2

**(table continues...)**

**Pin Configuration**

**Table 2 (continued) Pin list Motion Control Engine**

Signal	Type	LQFP-64	LQFP-48	Description
Interface				
DIR	I	52	40	Direction input
DUTYFREQ <sup>2)</sup>	I	55	43	Duty/Frequency input
VSP	AIN	9	6	Analog speed reference input
PGOUT	O	42	34	Pulse output
PAR0	I	3	2	Parameter page select 0
PAR1	I	4	3	Parameter page select 1
PAR2	I	5	4	Parameter page select 2
PAR3	I	6	5	Parameter page select 3
NTC	AIN	13	10	External thermistor input
LED	O	41	35	Status LED
Communication				
RX0	I	57	45	Serial port 0, device programming, receive input
TX0	O	58	46	Serial port 0, device programming, transmit output
RX1	I	63	30	Serial port 1, user communication, receive input
TX1	O	64	31	Serial port 1, user communication, transmit output
Scripting pins				
AIN0	AIN	9	6	Analog input 0
AIN1	AIN	10	7	Analog input 1
AIN2	AIN	11	8	Analog input 2
AIN4	AIN	13	10	Analog input 4
AIN7	AIN	16	13	Analog input 7
AIN8	AIN	17	14	Analog input 8
GPI02	IO	3	2	Digital input/output 2
GPI03	IO	4	3	Digital input/output 3
GPI04	IO	5	4	Digital input/output 4
GPI05	IO	6	5	Digital input/output 5
GPI06	IO	52	-	Digital input/output 6
GPI07	IO	7	1	Digital input/output 7
GPI08	IO	8	-	Digital input/output 8
GPI09	IO	26	-	Digital input/output 9
GPI010	IO	27	36	Digital input/output 10
GPI011	IO	28	39	Digital input/output 11
GPI012	IO	37	41	Digital input/output 12
GPI013	IO	38	42	Digital input/output 13

**(table continues...)**

<sup>2</sup> Function not available when used with Hall sensor mode (i.e. AHALL1+/- and AHALL2+/- or HALL1/2/3 are used)

**Pin Configuration**

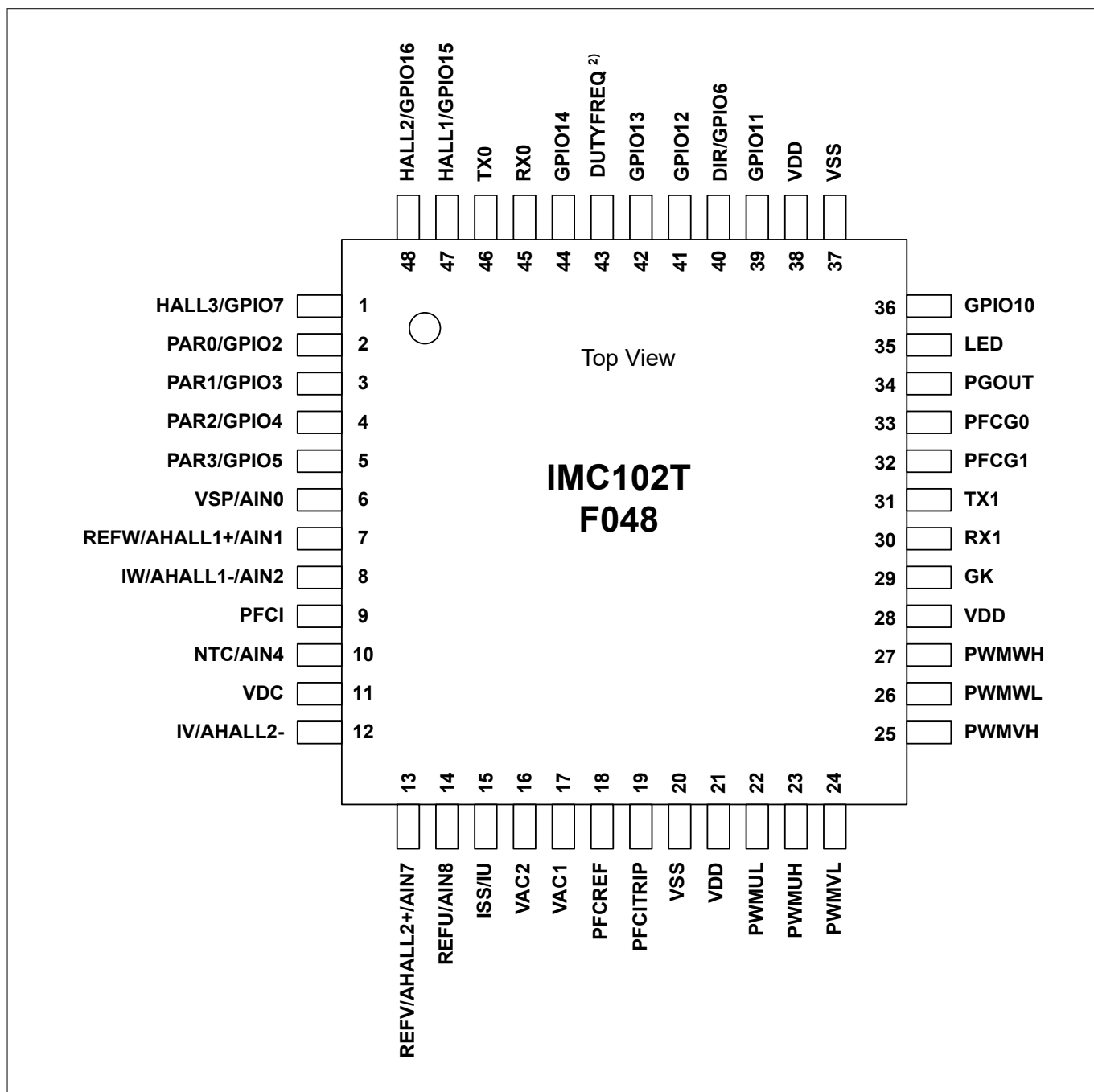
**Table 2 (continued) Pin list Motion Control Engine**

<b>Signal</b>	<b>Type</b>	<b>LQFP-64</b>	<b>LQFP-48</b>	<b>Description</b>
GPIO14	IO	39	44	Digital input/output 14
GPIO15	IO	40	47	Digital input/output 15
GPIO18	IO	45	48	Digital input/output 18
GPIO19	IO	46		Digital input/output 19
GPIO20	IO	47		Digital input/output 20
GPIO21	IO	48		Digital input/output 21
GPIO22	IO	51		Digital input/output 22
GPIO23	IO	53		Digital input/output 23
GPIO24	IO	54		Digital input/output 24
GPIO25	IO	56		Digital input/output 25
GPIO26	IO	59		Digital input/output 26
GPIO27	IO	60		Digital input/output 27
GPIO28	IO	61		Digital input/output 28
GPIO29	IO	62		Digital input/output 29

**Pin Configuration**

**2.4 Pin Configuration Drawing IMC102T**

The following drawings give the position of the functional pins for the available packages.

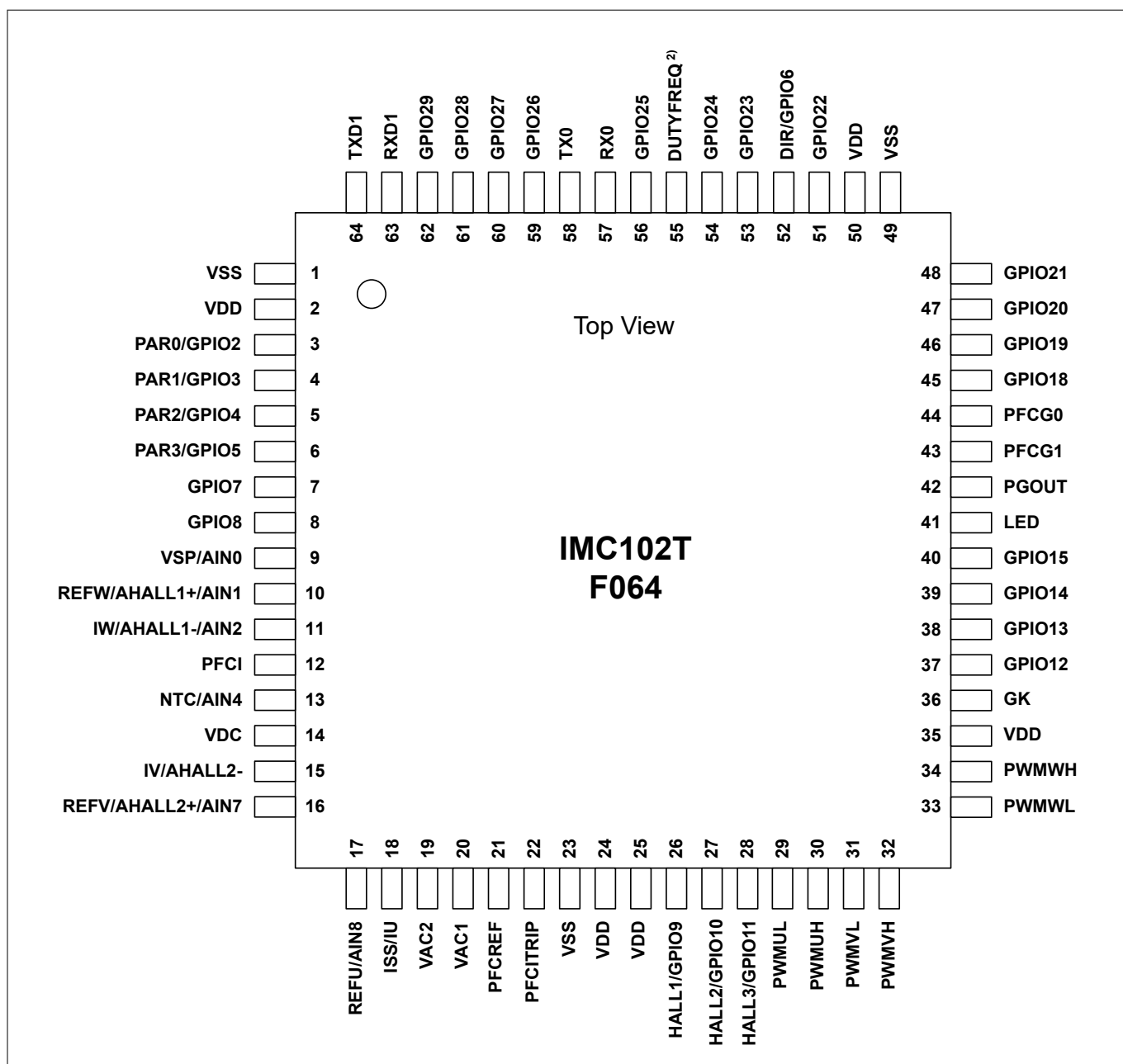


**Figure 6 IMC102T-F048**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.



**Pin Configuration**



**Figure 7 IMC102T-F064**

Pins that do not have any signal assigned are reserved for future use. These pins should be left unconnected and neither be connected to ground nor to the positive supply.

### **3 Functional description**

iMOTION™ IMC100 is a series of highly integrated ICs for the control of a Permanent Magnet Synchronous Motor (PMSM). IMC101 devices provide control of a single motor while the IMC102 devices control the motor and additionally a boost or totem pole power factor correction (PFC).

The IMC100 series is based on Infineon's Motion Control Engine (MCE) and integrate all hardware and software functions required to implement a closed loop sensorless or optionally sensor based control algorithm for permanent magnet motors. IMC100 devices do not require any software programming and can be configured for a wide range of motor control inverters.

The IMC100 series takes advantage of a new hardware platform that is based on a comprehensive set of innovative analog and motor control peripherals. The high level of integration both in terms of hardware modules and software algorithms results in a minimum number of external components required for the implementation of the inverter control.

Infineon's patented and field proven Motion Control Engine (MCE) implements field oriented control (FOC) using single or leg shunt current feedback and uses space vector pulse width modulation (PWM) with sinusoidal signals to achieve highest energy efficiency. In addition to the motor control algorithm it also integrates multiple configurable protection features like over- and under-voltage, over current, rotor lock etc. to protect both the power stage as well as the motor during application tuning or in case of malfunction.

The second generation of the MCE further improves the performance of the sensorless control algorithm and adds functionality like optional sensor support for applications that require accurate rotor positioning, two types of ready-to-use PFC algorithms as well as more and flexible and faster host interface options.

The IMC100 series is offered in several device and package variants for applications from single motor control to motor control plus PFC. All devices can be used in applications requiring functional safety according to IEC 60335 ('Class B').

There are multiple versions of the MCE software offered by Infineon and made available for download from the Infineon web site.

By using a special secure boot loader algorithm in combination with type specific chip IDs it is assured that these MCE software versions can only be installed onto the matching hardware derivatives, i.e. IMC100 variants for which the software has been tested and released for. Infineon as well as third parties provides tools to program these software images. For details please refer to the iMOTION™ programming manual.

The MCE integrates a script engine providing additional flexibility. The script engine can make use of analog and digital IOs for reading sensors or driving signals. The respective IOs are given in the pin lists referencing the name in the script to the physical pin of the package.

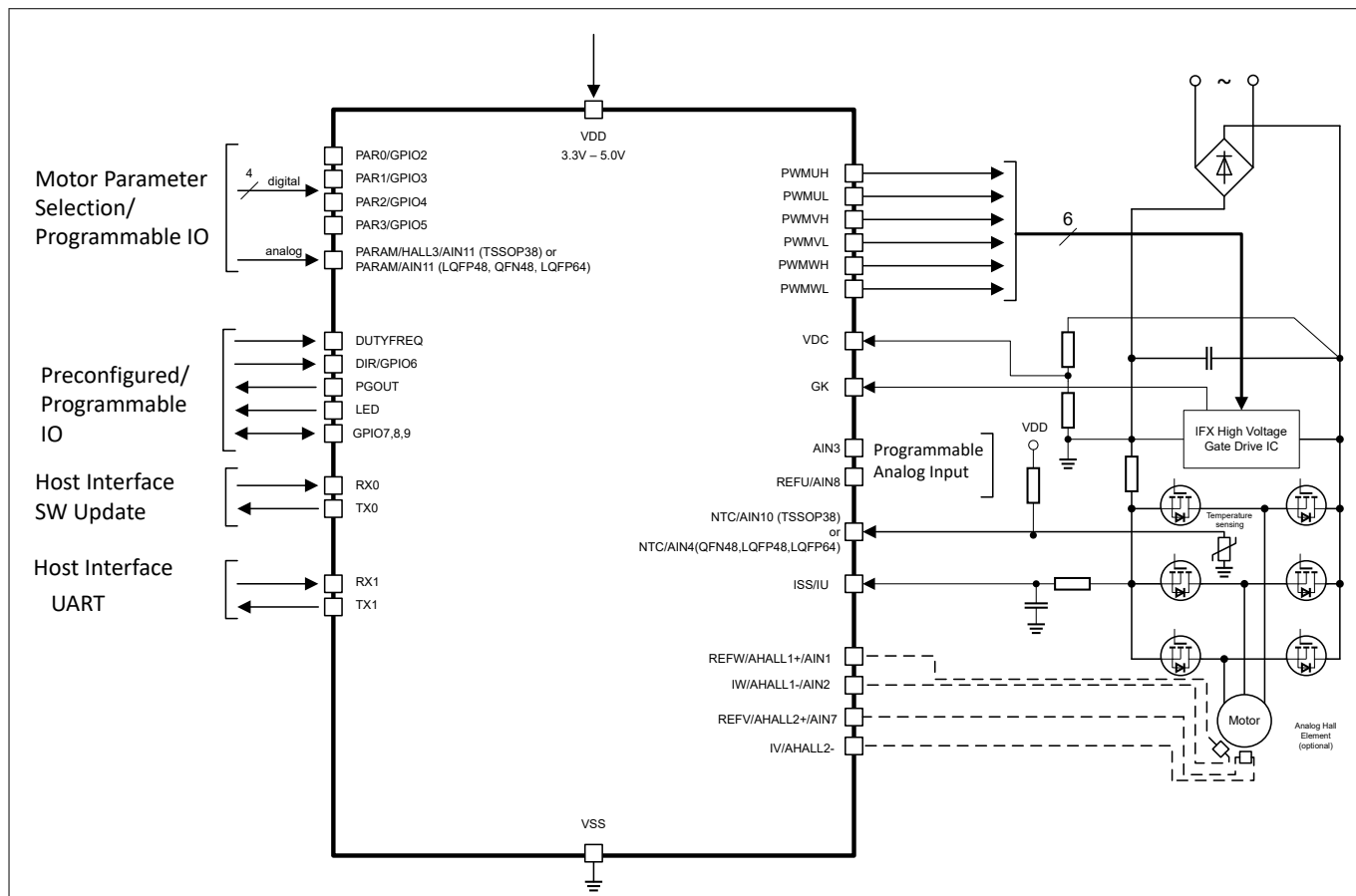
This data sheet provides all electrical, mechanical, thermal and quality parameters. A detailed description of the features, functionality and configuration of the Motion Control Engine (MCE) including scripting can be found in the respective reference manual of the MCE.

The application schematics in the following chapters show some examples of different use cases for the IMC100 devices. The combination of the different configuration options like leg vs. single shunt, sensorless or sensed operation, boost or totem pole PFC etc. is not limited to the examples shown here but can be chosen according to the individual application requirements.

**Functional description**

**3.1 Application schematic motor control single shunt**

Figure 8 gives the schematic diagram for a motor control system using the IMC101 in sensorless operation and single shunt mode. As an option analog hall elements can be used to improve low speed performance.

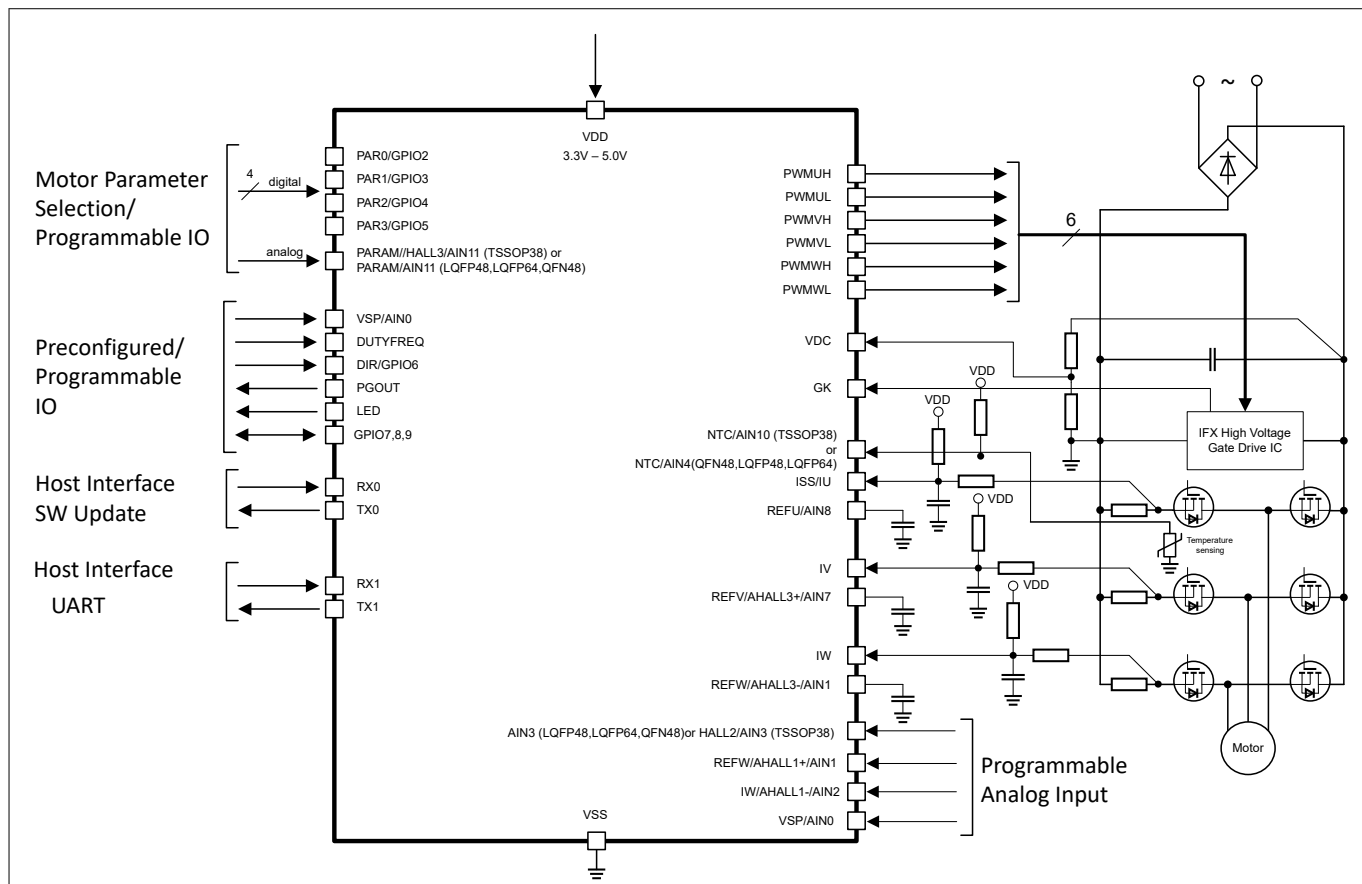


**Figure 8 IMC101 in single shunt configuration**

**Functional description**

**3.2 Application schematic motor control leg shunt**

Figure 9 gives the schematic diagram for a motor control system using the IMC101 in sensorless operation and leg shunt mode. An NTC can be used for temperature sensing at the power stage.

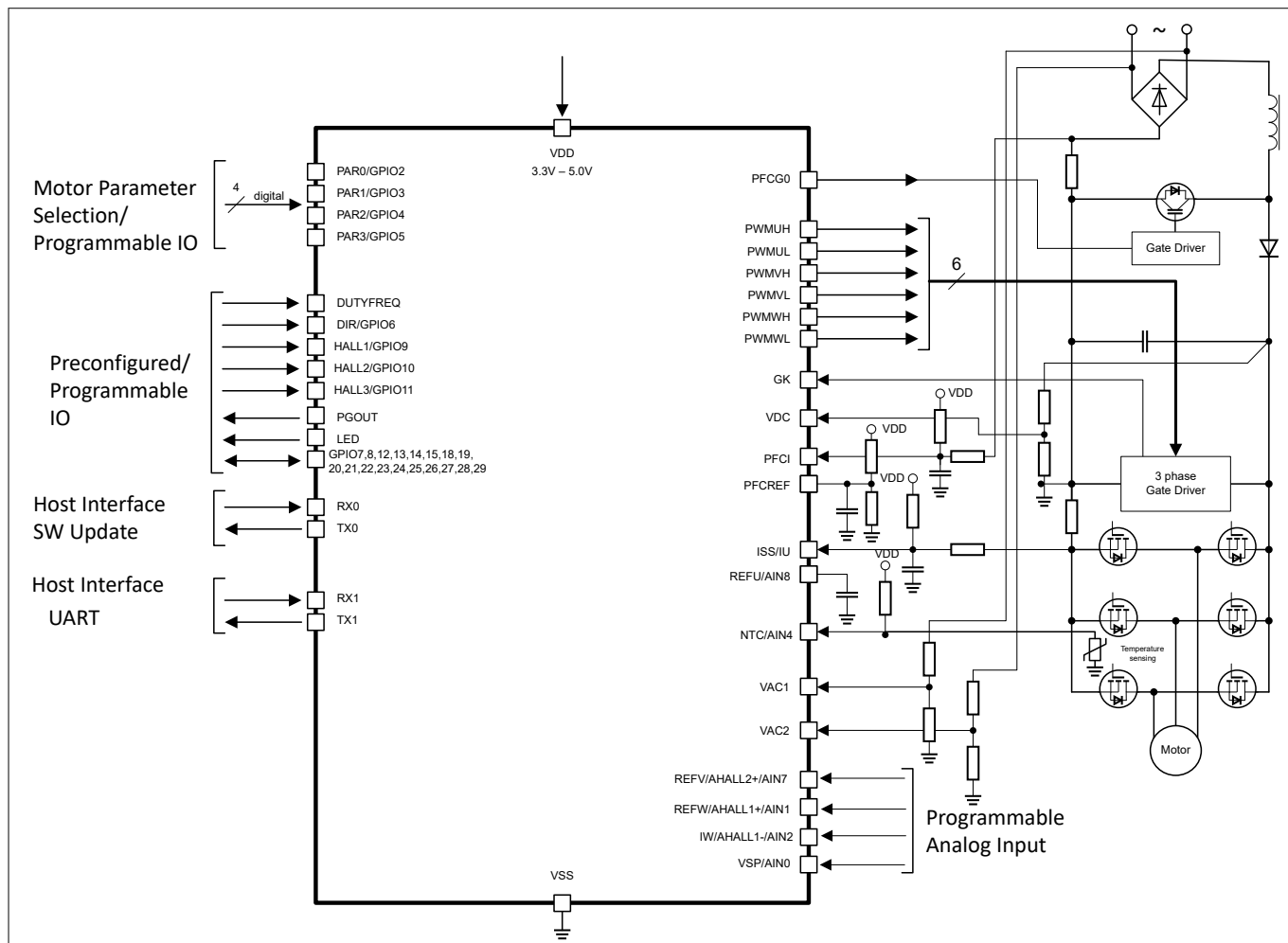


**Figure 9 IMC101 in leg shunt configuration**

**Functional description**

**3.3 Application schematic motor control plus boost PFC**

Figure 10 gives the schematic diagram for a motor control system with boost PFC using the IMC102 in sensorless operation and single shunt mode. An NTC can be used for temperature sensing at the power stage.

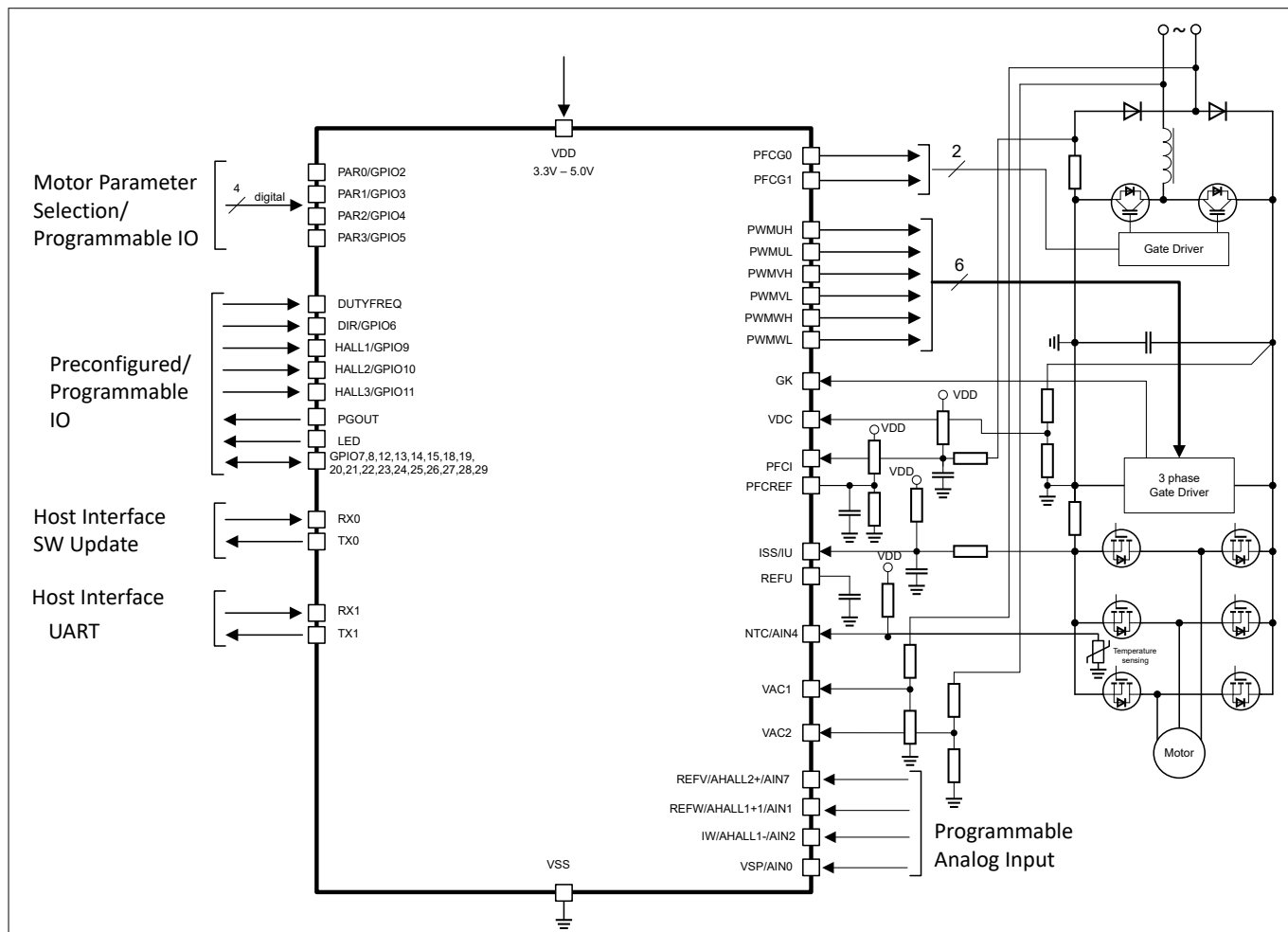


**Figure 10 IMC102 in single shunt configuration with boost PFC control**

**Functional description**

**3.4 Application schematic motor control plus totem pole PFC**

Figure 11 gives the schematic diagram for a motor control system with totem pole PFC using the IMC102 in sensorless operation and single shunt mode.



**Figure 11 IMC102 in single shunt configuration with totem pole PFC**

## 4 Electrical characteristics and parameters

### 4.1 General Parameters

#### 4.1.1 Parameter Interpretation

The parameters listed in this section represent partly the characteristics of the IMC100 and partly its requirements on the system. To aid interpreting the parameters easily when evaluating them for a design, they are indicated by the abbreviations in the “Symbol” column:

- **CC**  
 Such parameters indicate **C**ontroller **C**haracteristics, which are distinctive feature of the IMC100 and must be regarded for a system design.
- **SR**  
 Such parameters indicate **S**ystem **R**equirements, which must be provided by the application system in which the IMC100 is designed in.

#### 4.1.2 Absolute Maximum Ratings

Stresses above the values listed under “Absolute Maximum Ratings” may cause permanent damage to the device. This is a stress rating only and functional operation of the device at these or any other conditions above those indicated in the operational sections of this specification is not implied. Exposure to absolute maximum rating conditions may affect device reliability.

**Table 3 Absolute Maximum Rating Parameters**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Ambient temperature	$T_A$ SR	-40	–	105	°C	–
Junction temperature	$T_J$ SR	-40	–	115	°C	–
Storage temperature	$T_{ST}$ SR	-55	–	125	°C	–
Voltage on power supply pin with respect to $V_{SS}$	$V_{DD}$ SR	-0.3	–	6	V	–
Voltage on pins with respect to $V_{SS}$	$V_{IN}$ SR	-0.3	–	$V_{DD} + 0.3$	V	–
Input current on any pin during overload condition	$I_{IN}$ SR	-10	–	10	mA	–
Absolute maximum sum of all input currents during overload condition	$\Sigma I_{IN}$ SR	-50	–	+50	mA	–

**Electrical characteristics and parameters**

**4.1.3 Pin Reliability in Overload**

When receiving signals from higher voltage devices, low-voltage devices experience overload currents and voltages that go beyond their own IO power supplies specification.

Table 4 defines overload conditions that will not cause any negative reliability impact if all the following conditions are met:

- full operation life-time is not exceeded
- **Operating Conditions** are met for
  - pad supply levels ( $V_{DD}$ )
  - temperature

If a pin current is outside of the **Operating Conditions** but within the overload conditions, then the parameters of this pin as stated in the Operating Conditions can no longer be guaranteed. Operation is still possible in most cases but with relaxed parameters.

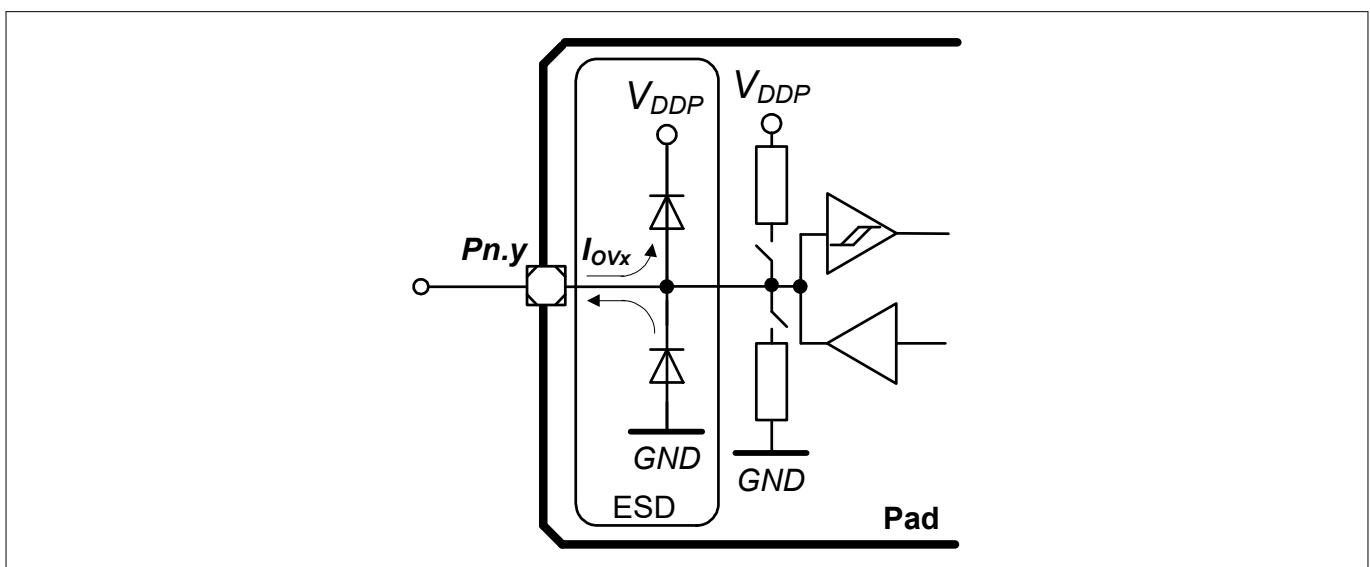
*Note:* An overload condition on one or more pins does not require a reset.

*Note:* A series resistor at the pin to limit the current to the maximum permitted overload current is sufficient to handle failure situations like short to battery.

**Table 4 Overload Parameters**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Input current on analog port pins during overload condition	$I_{OVA}$ SR	-3	-	3	mA	
Input current on any port pin during overload condition	$I_{OV}$ SR	-5	-	5	mA	
Absolute sum of all input currents during overload condition	$I_{OVS}$ SR	-	-	25	mA	

Figure 12 shows the path of the input currents during overload via the ESD protection structures. The diodes against  $V_{DD}$  and ground are a simplified representation of these ESD protection structures.



**Figure 12 Input Overload Current via ESD structures**



**Electrical characteristics and parameters**

Table 5 and Table 6 list input voltages that can be reached under overload conditions. Note that the absolute maximum input voltages as defined in the [Absolute Maximum Ratings](#) must not be exceeded during overload.

**Table 5 PN-Junction Characteristics for positive Overload**

<b>Pad Type</b>	<b><math>I_{OV} = 5 \text{ mA}</math></b>
Standard, High-current, AN/DIG_IN	$V_{IN} = V_{DD} + (0.3 \dots 0.5) \text{ V}$ $V_{AIN} = V_{DD} + 0.5 \text{ V}$ $V_{AREF} = V_{DD} + 0.5 \text{ V}$

**Table 6 PN-Junction Characteristics for negative Overload**

<b>Pad Type</b>	<b><math>I_{OV} = 5 \text{ mA}</math></b>
Standard, High-current, AN/DIG_IN	$V_{IN} = V_{SS} - (0.3 \dots 0.5) \text{ V}$ $V_{AIN} = V_{SS} - 0.5 \text{ V}$ $V_{AREF} = V_{SS} - 0.5 \text{ V}$

#### 4.1.4 Operating Conditions

The following operating conditions must not be exceeded in order to ensure correct operation and reliability of the IMC100. All parameters specified in the following tables refer to these operating conditions, unless noted otherwise.

**Table 7 Recommended Operating Conditions**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Ambient Temperature	$T_A$ SR	-40	-	105	°C	
Junction temperature	$T_J$ SR	-40	-	115	°C	
Positive DC Bus Input Voltage	$V_{DCP}$ SR	12	-	400	V	
Digital supply voltage <sup>3)</sup>	$V_{DD}$ SR	3.0	3.3	5.5	V	

<sup>3)</sup> See also the Supply Monitoring thresholds [Power-Up and Supply Threshold Characteristics](#).

**Electrical characteristics and parameters**

**4.2 DC Parameters**

**4.2.1 Input/Output Characteristics**

The table below provides the characteristics of the input/output pins of the controller.

*Note: These parameters are not subject to production test, but verified by design and/or characterization.*

*Note: Unless otherwise stated, input DC and AC characteristics, including peripheral timings, assume that the input pads operate with the standard hysteresis.*

**Table 8 Input/Output Characteristics (Operating Conditions apply)**

Parameter	Symbol		Limit Values		Unit	Test Conditions
			Min.	Max.		
Input low voltage on port pins (Standard Hysteresis)	$V_{ILPS}$	SR	–	$0.19 \times V_{DD}$	V	CMOS Mode
Input high voltage on port pins (Standard Hysteresis)	$V_{IHPS}$	SR	$0.7 \times V_{DD}$	–	V	CMOS Mode
Input low voltage on port pins (Large Hysteresis, scripting pins only)	$V_{ILPL}$	SR	–	$0.08 \times V_{DD}$	V	CMOS Mode
Input high voltage on port pins (Large Hysteresis, scripting pins only)	$V_{IHPL}$	SR	$0.85 \times V_{DD}$	–	V	CMOS Mode
Output low voltage on port pins	$V_{OLP}$	CC	–	1.0	V	$I_{OL} = 11 \text{ mA ( 5 V)}$ $I_{OL} = 7 \text{ mA (3.3 V)}$
			–	0.4	V	$I_{OL} = 5 \text{ mA (5 V)}$ $I_{OL} = 3.5 \text{ mA (3.3 V)}$
Output low voltage on PWM outputs	$V_{OLP1}$	CC	–	1.0	V	$I_{OL} = 50 \text{ mA (5 V)}$ $I_{OL} = 25 \text{ mA (3.3 V)}$
			–	0.32	V	$I_{OL} = 10 \text{ mA (5 V)}$
			–	0.4	V	$I_{OL} = 5 \text{ mA (3.3 V)}$
Output high voltage on port pins	$V_{OHP}$	CC	$V_{DD} - 1.0$	–	V	$I_{OH} = -10 \text{ mA (5 V)}$ $I_{OH} = -7 \text{ mA (3.3 V)}$
			$V_{DD} - 0.4$	–	V	$I_{OH} = -4.5 \text{ mA (5 V)}$ $I_{OH} = -2.5 \text{ mA (3.3 V)}$
Output high voltage on PWM outputs	$V_{OHP1}$	CC	$V_{DD} - 0.32$	–	V	$I_{OH} = -6 \text{ mA (5 V)}$
			$V_{DD} - 1.0$	–	V	$I_{OH} = -8 \text{ mA (3.3 V)}$
			$V_{DD} - 0.4$	–	V	$I_{OH} = -4 \text{ mA (3.3 V)}$
Rise/fall time on PWM outputs <sup>4)</sup>	$t_{HCPR}$	CC	–	9	ns	50 pF @ 5 V

**(table continues...)**

<sup>4</sup> Rise/Fall time parameters are taken with 10% - 90% of supply.

**Electrical characteristics and parameters**

**Table 8 (continued) Input/Output Characteristics (Operating Conditions apply)**

Parameter	Symbol		Limit Values		Unit	Test Conditions
			Min.	Max.		
	$t_{HCPF}$		–	12	ns	50 pF @ 3.3 V
Rise/fall time on standard pad	$t_R, t_F$	CC	–	12	ns	50 pF @ 5 V
			–	15	ns	50 pF @ 3.3 V.
Pin capacitance (digital inputs/outputs)	$C_{IO}$	CC	–	10	pF	
Pull-up/-down resistor on port pins (if enabled in software)	$R_{PUP}$	CC	20	50	kΩ	$V_{IN} = V_{SS}$
Input leakage current <sup>5)</sup>	$I_{OZP}$	CC	-1	1	μA	$0 < V_{IN} < V_{DD}$ , $T_A 105^\circ\text{C}$
Maximum current per pin standard pin	$I_{MP}$	SR	-10	11	mA	–
Maximum current per PWM outputs pins	$I_{MP1A}$	SR	-10	50	mA	–
Maximum current into $V_{DD}$ / out of $V_{SS}$	$I_{MVDD} / I_{MVSS}$	SR	–	260	mA	

<sup>5)</sup> An additional error current ( $I_{INJ}$ ) will flow if an overload current flows through an adjacent pin.

**Electrical characteristics and parameters**

**4.2.2 Analog to Digital Converter (ADC)**

The following table shows the Analog to Digital Converter (ADC) characteristics. This specification applies to all analog input including the analog Hall sensor interface input (AHALLx+/AHALLx-, where x=1,2) as given in the pin configuration list.

*Note: These parameters are not subject to production test, but verified by design and/or characterization.*

**Table 9 ADC Characteristics (Operating Conditions apply)<sup>6)</sup>**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Supply voltage range	$V_{DD}$ SR	3.0	–	5.5	V	
Analog input voltage range	$V_{AIN}$ SR	$V_{SS}-0.05$	–	$V_{DD}+0.05$	V	
Conversion time	$t_{C12}$ CC	–	1.0	1.6	μs	
Total capacitance of an analog input	$C_{AINT}$ CC	–	–	10	pF	
Total capacitance of the reference input	$C_{AREFT}$ CC	–	–	10	pF	
Sample time	$t_{sample}$ CC	–	200	–	ns	
RMS noise	$EN_{RMS}$ CC	–	1.5	–	LSB12	
DNL error	$EA_{DNL}$ CC	–	±2.0	–	LSB12	
INL error	$EA_{INL}$ CC	–	±4.0	–	LSB12	
Gain error	$EA_{GAIN}$ CC	–	±0.5	–	%	$V_{DD} = 3.3V$
Offset error	$EA_{OFF}$ CC	–	±8.0	–	mV	

<sup>6)</sup> All parameters are defined for the full supply range if not stated otherwise.

**Electrical characteristics and parameters**

**4.2.3 Power Supply Current**

The total power supply current defined below consists of a leakage and a switching component. Application relevant values are typically lower than those given in the following tables, and depend on the customer's system operating conditions (e.g. thermal connection or used application configurations).

*Note: These parameters are not subject to production test, but verified by design and/or characterization.*

**Table 10 Power Supply parameter table;  $V_{DDP} = 5V$**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Active mode current motor control only	$I_{DDP_{PWM}} CC$	–	10	20	mA	
Active mode current motor control plus PFC	$I_{DDP_{PFC}} CC$	–	14	20	mA	product with PFC only
Deep Sleep mode current <sup>7)</sup>	$I_{DDP_{DS}} CC$	–	0.27	–	mA	
Wake-up time from Sleep to Active mode	$t_{SSA} CC$	–	6	–	cycles	
Wake-up time from Deep Sleep to Active mode	$t_{DSA} CC$	–	290	–	μsec	

**4.2.4 Flash Memory Parameters**

*Note: These parameters are not subject to production test, but verified by design and/or characterization.*

**Table 11 Flash Memory Parameters**

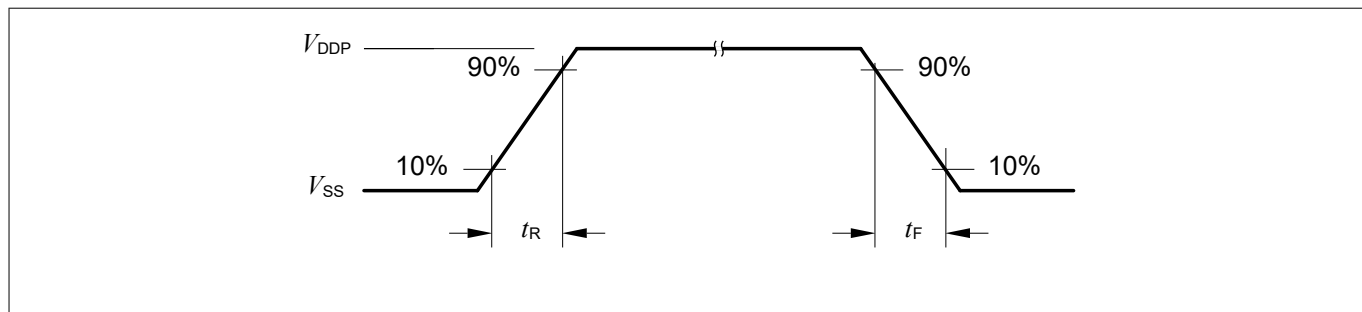
Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Data Retention Time	$t_{RET} CC$	10			years	Max. 100 erase / program cycles
Erase Cycles <sup>8)</sup>	$N_{E_{CYC}} CC$			$5 \cdot 10^4$	cycles	Sum of page and sector erase cycles
Total Erase Cycles	$N_{TE_{CYC}} CC$			$2 \cdot 10^6$	cycles	

<sup>7</sup> CPU in sleep, peripherals clock disabled, Flash is powered down and code executed from RAM after wake-up.

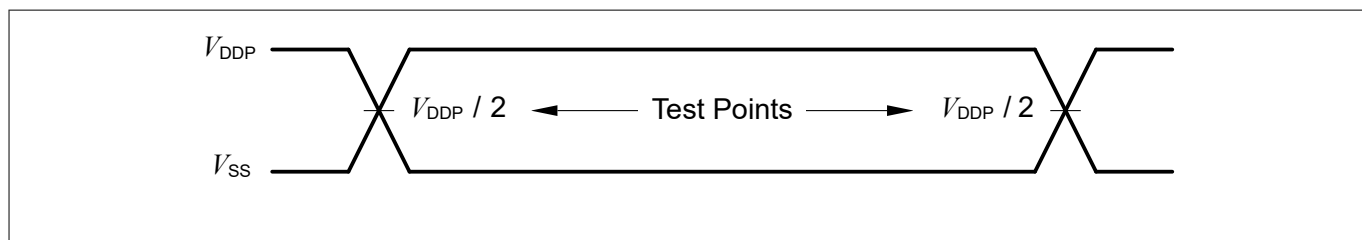
<sup>8</sup> Sum of page erase and sector erase cycles a page sees.

### 4.3 AC Parameters

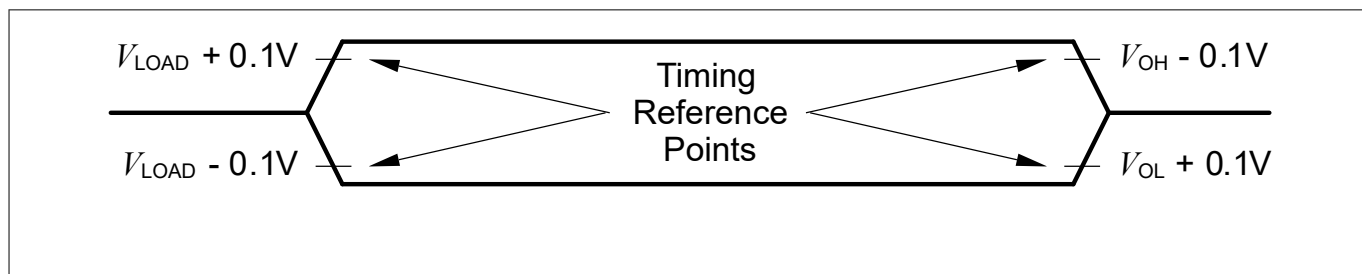
#### 4.3.1 Testing Waveforms



**Figure 13 Rise/Fall Time Parameters**



**Figure 14 Testing Waveform, Output Delay**



**Figure 15 Testing Waveform, Output High Impedance**

**Electrical characteristics and parameters**

**4.3.2 Power-Up and Supply Threshold Characteristics**

This chapter provides the characteristics of the supply threshold for the controller.

The guard band between the lowest valid operating voltage and the brownout reset threshold provides a margin for noise immunity and hysteresis. The electrical parameters may be violated while  $V_{DD}$  is outside its operating range.

The brownout detection triggers a reset within the defined range. The prewarning detection can be used to trigger an early warning and issue corrective and/or fail-safe actions in case of a critical supply voltage drop.

*Note: These parameters are not subject to production test, but verified by design and/or characterization.*

*Note: Operating Conditions apply.*

**Table 12 Power-Up and Supply Threshold Parameters**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
$V_{DD}$ ramp-up time	$t_{RAMPUP}$ SR	$V_{DD}/S_{VDDrise}$	–	$10^7$	$\mu s$	
$V_{DD}$ slew rate	$S_{VDDOP}$ SR	0	–	0.1	$V/\mu s$	Slope during normal operation
	$S_{VDD10}$ SR	0	–	10	$V/\mu s$	Slope during fast transient within +/-10% of $V_{DD}$
	$S_{VDDrise}$ SR	0	–	10	$V/\mu s$	Slope during power-on or restart after brownout event
	$S_{VDDfall}^{9)}$ SR	0	–	0.25	$V/\mu s$	Slope during supply falling out of the +/-10% limits <sup>10)</sup>
$V_{DD}$ prewarning voltage	$V_{DDPW}$ CC	2.1	2.25	2.4	V	ANAVDEL.VDEL_SELECT = 00 <sub>B</sub>
		2.85	3	3.15	V	ANAVDEL.VDEL_SELECT = 01 <sub>B</sub>
		4.2	4.4	4.6	V	ANAVDEL.VDEL_SELECT = 10 <sub>B</sub>
$V_{DD}$ brownout reset voltage	$V_{DDBO}$ CC	1.55	1.62	1.75	V	calibrated, before user code starts running
$V_{DD}$ voltage to ensure defined pad states	$V_{DDA}$ CC	–	1.0	–	V	

**(table continues...)**

<sup>9</sup> A capacitor of at least 100 nF has to be added between VDD and VSS to fulfill the requirement as stated for this parameter.

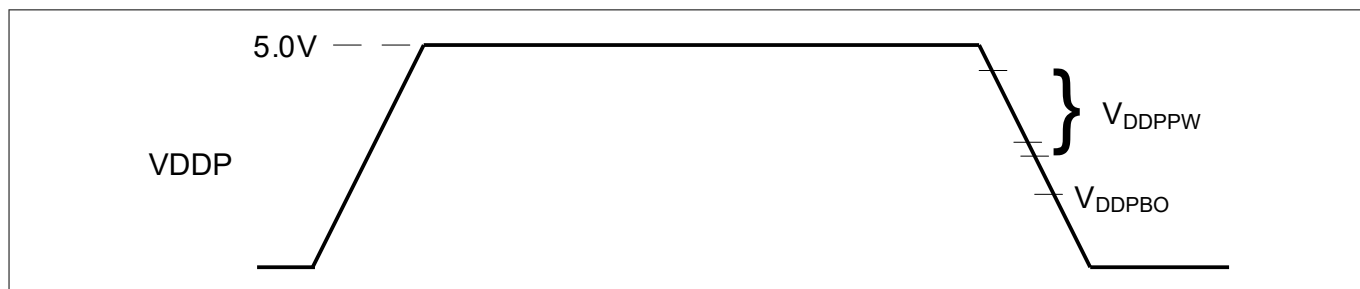
<sup>10</sup> Valid for a 100 nF buffer capacitor connected to supply pin where current from capacitor is forwarded only to the chip. A larger capacitor value has to be chosen if the power source sink a current.



**Electrical characteristics and parameters**

**Table 12 (continued) Power-Up and Supply Threshold Parameters**

Parameter	Symbol	Values			Unit	Note or Test Condition
		Min.	Typ.	Max.		
Start-up time from power-on reset	$t_{SSW\ CC}$	-	260	-	$\mu s$	Time to the first user code instruction <sup>11)</sup>
Start-up time to PWM on	$t_{PWMON\ CC}$	5.2	-	360	ms	Time to PWM enabled



**Figure 16 Supply Threshold Parameters**

<sup>11</sup> This values does not include the ramp-up time. During startup firmware execution, MCLK is running at 48 MHz and the clocks to peripheral as specified in register CGATSTAT0 are gated.

**Electrical characteristics and parameters**

**4.3.3 On-Chip Oscillator Characteristics**

Table 13 provides the characteristics of the 96 MHz digital controlled oscillator DCO1. The DCO1 is used as the time base during normal operation.

Note: These parameters are not subject to production test, but verified by design and/or characterization.

**Table 13 96 MHz DCO1 Characteristics**

Parameter	Symbol	Limit Values			Unit	Test Conditions
		Min.	Typ.	Max.		
Nominal frequency	$f_{\text{NOM CC}}$	-	96	-	MHz	under nominal conditions after trimming
Accuracy with adjustment based on XTAL as reference	$\Delta f_{\text{LTX CC}}$	-0.3	-	+0.3	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from -40 °C to 105 °C
Accuracy with adjustment algorithm <sup>12)</sup> based on temperature sensor	$\Delta f_{\text{LTS CC}}$	-0.6	-	+0.6	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from 0 °C to 105 °C
		-1.9	-	+1.0	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from -25 °C to 105 °C
		-2.6	-	+1.3	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from -40 °C to 105 °C
Accuracy	$\Delta f_{\text{LT CC}}$	-1.7	-	+3.4	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from 0 °C to 85 °C
		-3.9	-	+4.0	%	with respect to $f_{\text{NOM}}(\text{typ})$ , $T_A$ from -40 °C to 105 °C

Table 14 provides the characteristics of the 32 kHz digital controlled oscillator DCO2. The DCO2 is only used internally as a secondary clock source for the internal watchdog and as a fallback in case of failure of DCO1.

**Table 14 32 kHz DCO2 Characteristics**

Parameter	Symbol	Limit Values			Unit	Test Conditions
		Min.	Typ.	Max.		
Nominal frequency	$f_{\text{NOM CC}}$	32.5	32.75	33	kHz	under nominal conditions <sup>13)</sup> after trimming
Short term frequency deviation (over $V_{\text{DCC}}$ )	$\Delta f_{\text{ST CC}}$	-1	-	+1	%	with respect to $f_{\text{NOM}}(\text{typ})$ , at 25 °C

**(table continues...)**

<sup>12</sup> MCE version newer or equal to V1.03.00, clock adjustment algorithm for improved accuracy enabled

<sup>13</sup> The deviation is relative to the factory trimmed frequency at nominal  $V_{\text{DCC}}$  and  $T_A = +25^\circ\text{C}$ .

**Electrical characteristics and parameters**

**Table 14 (continued) 32 kHz DCO2 Characteristics**

Parameter	Symbol	Limit Values			Unit	Test Conditions
		Min.	Typ.	Max.		
Accuracy	$\Delta f_{LT\ CC}$	-1.7	–	+3.4	%	with respect to $f_{NOM}(typ)$ , $T_A$ from 0 °C to 85 °C
		-3.9	–	+4.0	%	with respect to $f_{NOM}(typ)$ , $T_A$ from -40° C to 105 °C

**Electrical characteristics and parameters**

**4.4 Motor Control Parameters**

The following parameters are defined in the iMOTION™ Motion Control Engine (MCE) software.

**4.4.1 PWM Characteristics**

**Table 15 Electrical characteristics**

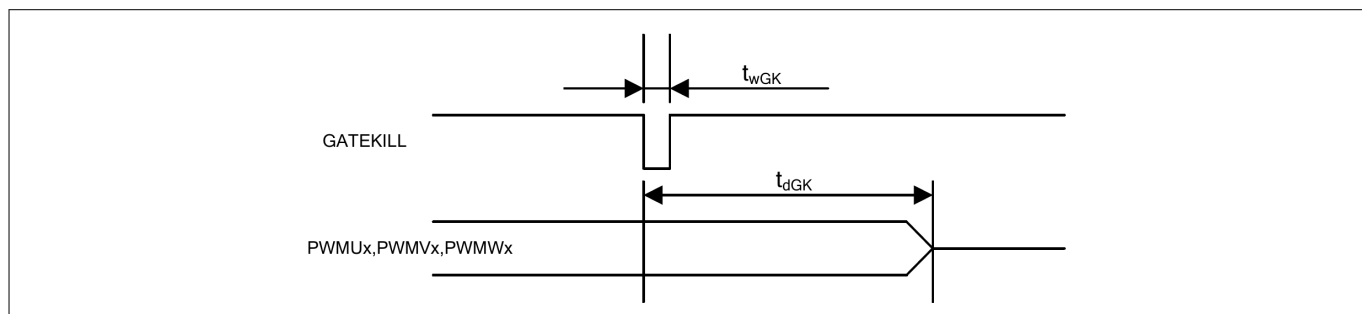
Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Motor PWM Frequency	$f_{PWM}$	5	16	40	kHz	

**4.4.2 Current Sensing**

**Table 16 Motor Current Sensing**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Input range	$I_{PWM}$	$V_{SS}-0.05$	-	$V_{DD}+0.05$	V	
Configurable analog gain		-	1/ 3/ 6/ 12	-		
Itrip input range	$I_{PWMTRIP}$	$V_{SS}-0.05$	-	$V_{DD}+0.05$	V	
Itrip offset		-	$\pm 8$	-	mV	
Input capacitance	$C_{REF}$	-	-	10	pF	REFU, REFV, REFW capacitor

### 4.4.3 Fault Timing



**Figure 17** Fault timing

**Table 17** Gatekill timing

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
GK pulse width	$t_{wGK}$	1	-	-	$\mu\text{s}$	
GK input to PWM shutoff	$t_{dGK}$	-	1.3	-	$\mu\text{s}$	
Motor Fault reset timing	$t_{\text{RESET}}$	-	1.84	-	ms	fault reset command via UART to PWM reactivation
Itrip to PWM shutoff	$t_{\text{PWMOFF}}$	-	1.0	-	$\mu\text{s}$	single shunt
Itrip to PWM shutoff	$t_{\text{PWMOFF}}$	-	1.0	-	$\mu\text{s}$	leg shunt

**Electrical characteristics and parameters**

**4.5 Power Factor Correction (PFC) parameters**

The parameters specified for the power factor correction only refer to products with integrated PFC control algorithms.

**4.5.1 Boost PFC characteristics**

**Table 18 Electrical characteristics**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
PFC frequency	$f_{PFC}$	-	20	50	kHz	Motor PWM frequency within specified range

**4.5.2 Totem Pole PFC characteristics**

**Table 19 Electrical characteristics**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
PFC frequency	$f_{PFC}$	-	20	50	kHz	Motor PWM frequency within specified range

**4.5.3 PFC Current Sensing**

The current sensing specification applies to both PFC algorithms, boost mode and totem pole.

**Table 20 PFC Current Sensing**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Input range	$I_{PFC}$	$V_{SS} - 0.05$	-	$V_{DD} + 0.05$	V	$V_{DD} = 3.3$ or $5.0$ V
Configurable analog gain		-	1/ 3/ 6/ 12	-		
PFC Itrip input range	$I_{PFCTRIP}$	$V_{SS} - 0.05$	-	$V_{DD} + 0.05$	V	$V_{DD} = 3.3$ or $5.0$ V
Itrip offset		-	$\pm 3$	-	mV	Input voltage difference > 200mV
Input capacitance	$C_{REF}$	-	-	10	pF	PFCREF capacitor

#### 4.5.4 PFC Fault Timing

**Table 21 PFC Fault timing**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Itrip to PFC PWM shutoff	t <sub>PFCOFF</sub>	-	1.18	-	μs	
PFC fault reset timing	t <sub>RESET</sub>	-	1.0	-	ms	fault reset command via UART to PWM reactivation

**Electrical characteristics and parameters**

**4.6 Control Interface Parameters**

The following tables specify the interfaces that can be used to control the motor drive in the application.

**4.6.1 Serial Interface Parameters**

The IMC100 series provides the following communication interfaces.

*Note:* These parameters are not subject to production test, but verified by design and/or characterization.

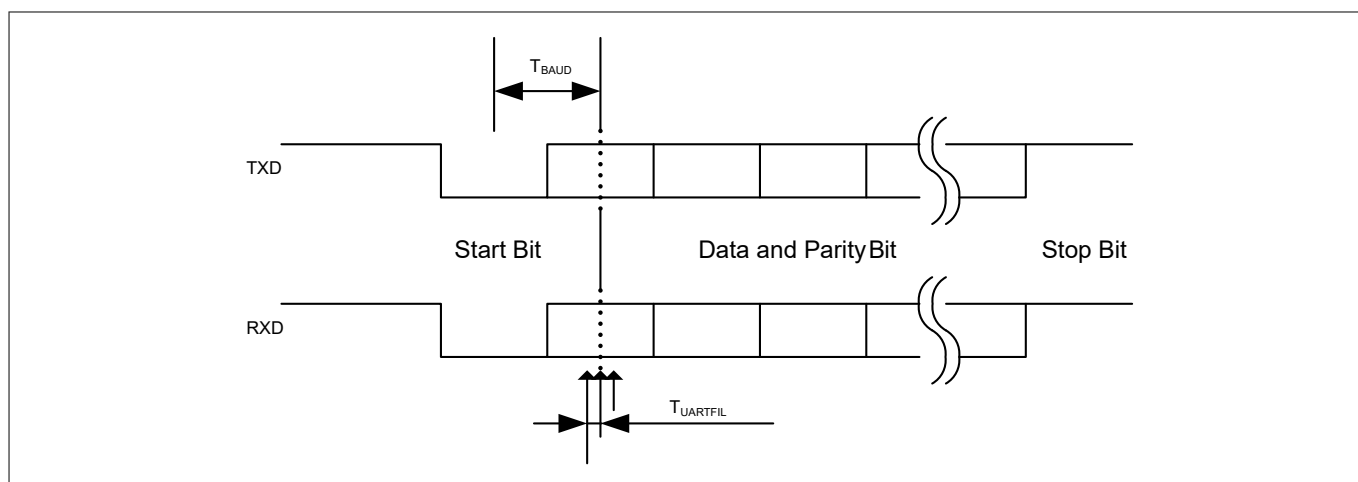
**4.6.1.1 UART Interface**

The UART interface is configured as given below.

*Note:* Operating Conditions apply.

**Table 22 Electrical characteristics**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
UART baud rate		1200	57600	-	Bps	
UART mode		-	8-N-1	-		data-parity-stop bit
UART sampling filter period <sup>14)</sup>	$T_{UARTFIL}$	-	1/16	-	$T_{BAUD}$	



**Figure 18 UART timing**

<sup>14</sup> Each bit including start and stop bit is sampled three times at center of a bit at an interval of  $1/16 T_{BAUD}$ . If three sampled values do not agree, then UART noise error is generated.



### 4.6.2 Analog Speed Input

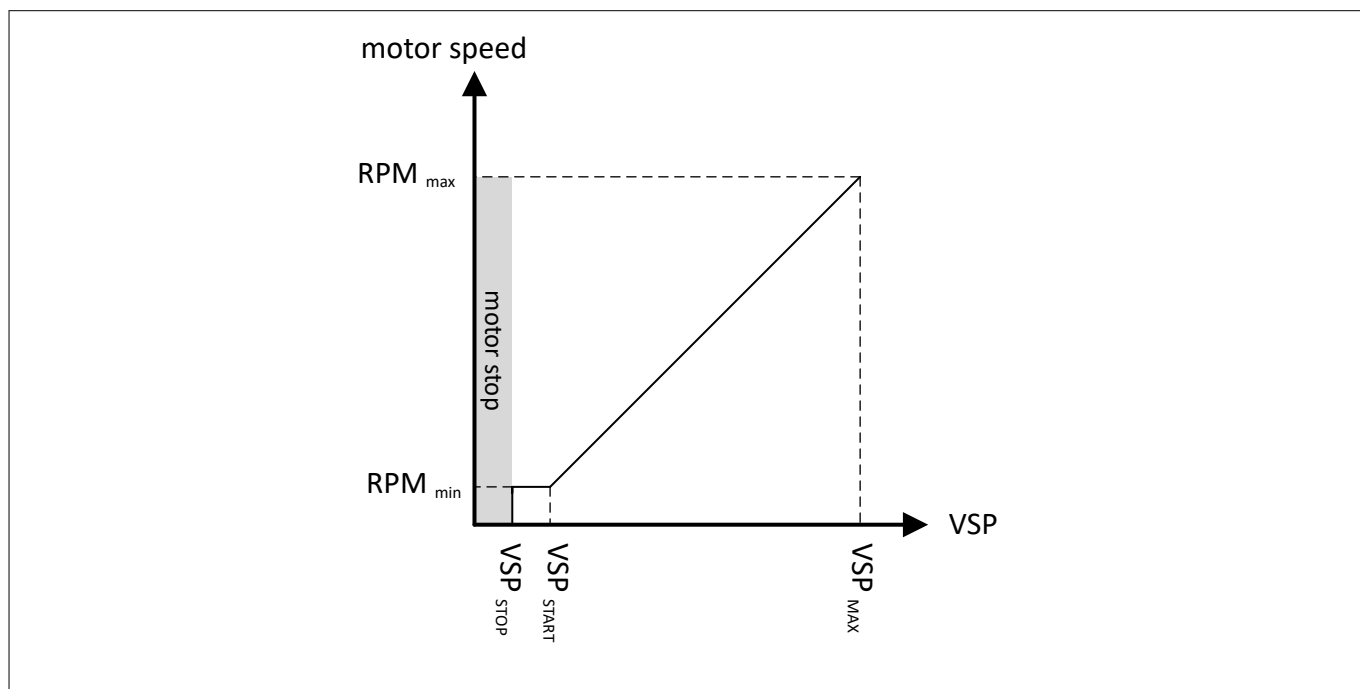


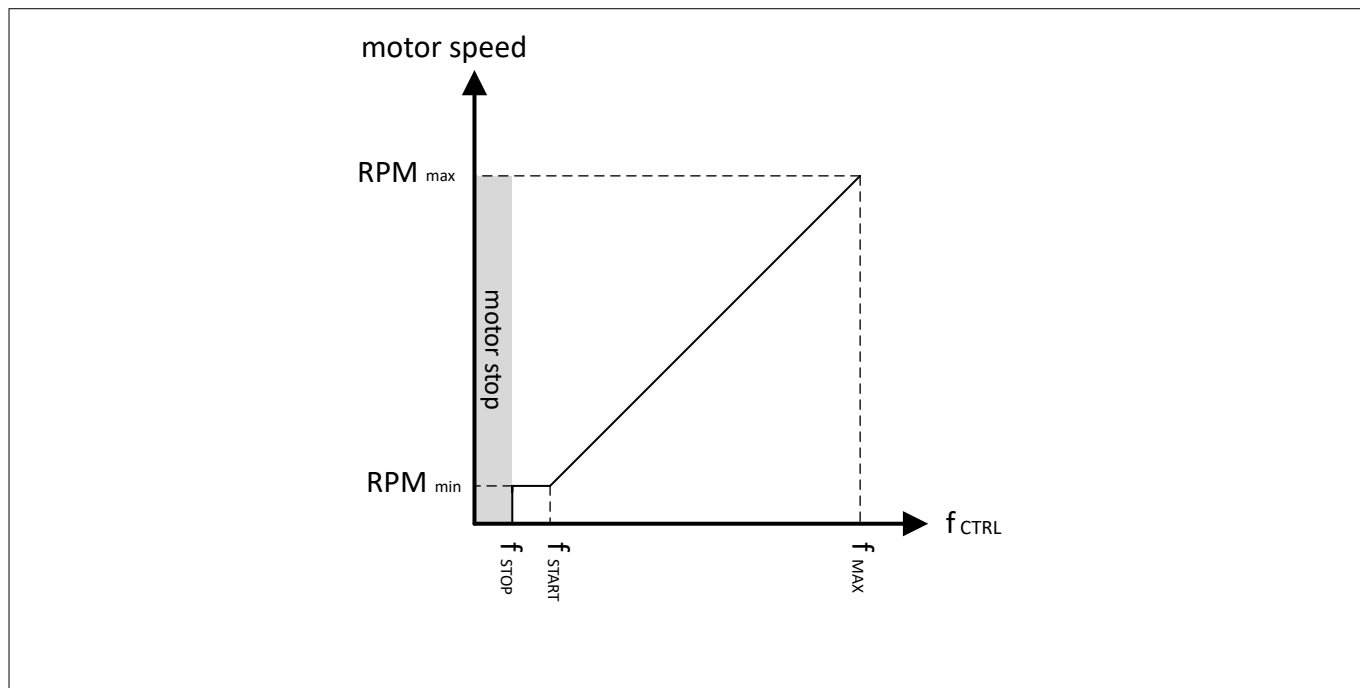
Figure 19 VSP analog control mode

Table 23 Analog Speed Control Voltage (VSP)

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Motor start voltage	$VSP_{START}$	-	1.2	-	V	Configured $VSP_{START}=1.0V$
Motor stop voltage	$VSP_{STOP}$	-	1.0	-	V	Configured $VSP_{STOP}=1.0V$
Motor max voltage	$VSP_{MAX}$	-	4.9	4.95	V	$V_{DD}=5.0V$
VSP active to PWM start	$t_{START}$	-	44	-	ms	
VSP inactive to PWM stop	$t_{STOP}$	-	16	-	ms	

### 4.6.3 Frequency Input

In frequency input control mode, the motor operations like motor start, motor stop and speed change are controlled by applying a square wave frequency signal on a digital input pin.



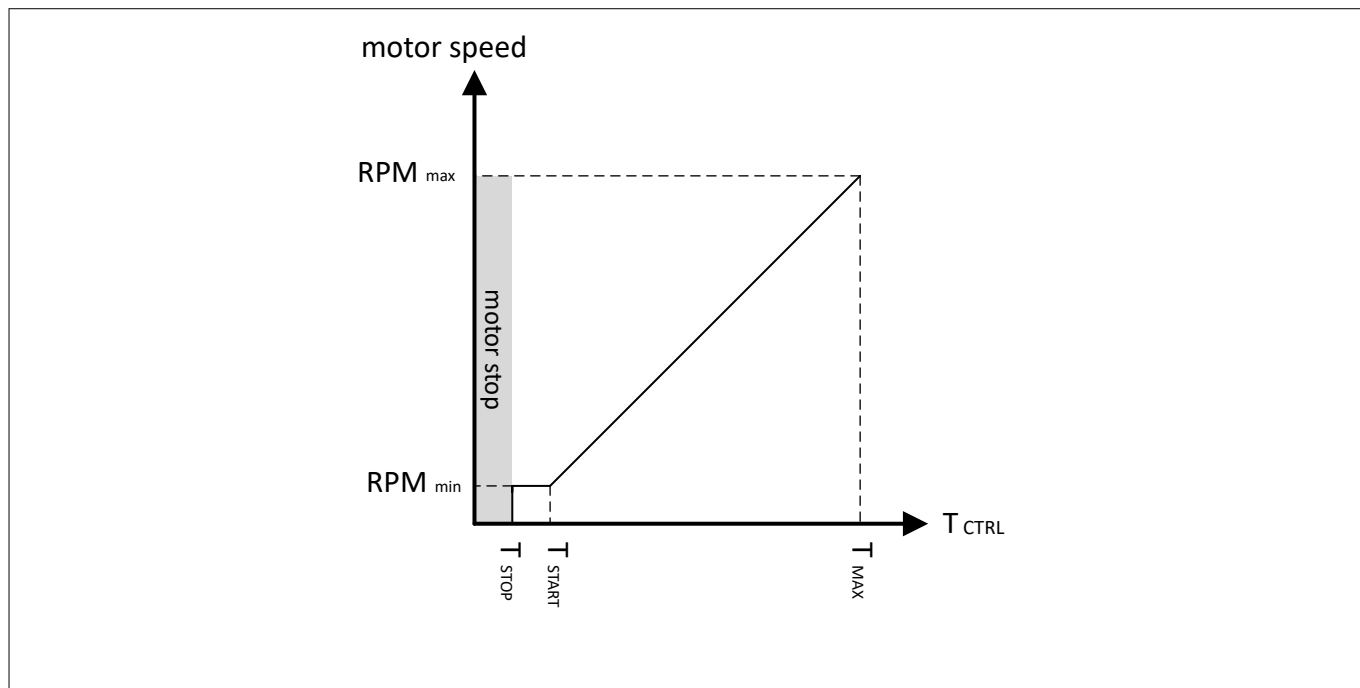
**Figure 20** Frequency input control mode

**Table 24** Frequency Control Mode

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Motor start frequency	$f_{START}$	-	100	360	Hz	$f_{START} > f_{STOP}$
Motor stop frequency	$f_{STOP}$	-	50	-	Hz	
Motor max speed frequency	$f_{MAX}$	-	-	1000	Hz	
Frequency input duty cycle	$T_{DUTY}$	10	-	90	%	

### 4.6.4 Duty Cycle Input

In duty cycle input control mode, the motor operations like motor start, stop and speed change are controlled by varying the duty cycle of a rectangular wave signal on a digital input pin.



**Figure 21** Duty cycle input control mode

**Table 25** Duty Cycle Control Mode

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Input signal frequency	$f_{DUTY}$	5	1000	20000	Hz	
Motor start duty cycle	$T_{START}$	-	10	-	%	$T_{START} > T_{STOP}$
Motor stop duty cycle	$T_{STOP}$	-	5	-	%	
Motor max duty cycle	$T_{MAX}$	-	95	-	%	

**Electrical characteristics and parameters**

### 4.6.5 Over Temperature Input

The over temperature input can be used to continuously monitor an external temperature sensor like an NTC.

**Table 26 Over Temperature Input**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Over Temperature Input Threshold	$V_{OT}$	0.1	1.0	3.0	V	$V_{DD}=3.3V$ , Configurable parameter e.g. via MCEDesigner, default=1.0V
Over Temperature to PWM shutdown	$t_{OT}$		1.0	2.1	ms	

### 4.6.6 Pulse Output

The IMC100 series can generate a square wave pulse output in sync with the motor rotation which can be used to monitor the motor speed. The number of pulses to be generated for a full rotation can be configured.

**Table 27 Pulse Output**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Pulses per Rotation	$PPR$	4	-	24		
Pulse duty cycle	$t_{PPR}$	-	50	-	%	

### 4.6.7 LED Output

The IMC100 series provides an output that can be connected to an LED to give a visual indication of the status of the motor drive.

**Table 28 LED Output**

Parameter	Symbol	Values			Unit	Note or test condition
		Min.	Typ.	Max.		
Fault to LED delay	$t_{LEDFault}$	-	53	-	ms	
Fault reset to LED delay	$t_{LEDRESET}$	-	1.84	-	ms	
LED blinking frequency	$f_{LED}$	1		1000	Hz	
LED blinking duty cycle	$t_{LED}$	5		95	%	

## 4.7 Quality declaration

**Table 29 Quality Parameters**

Parameter	Symbol	Limit Values		Unit	Notes
		Min.	Max.		
ESD susceptibility according to Human Body Model (HBM)	$V_{\text{HBM}}$ SR	–	2000	V	Conforming to ANSI/ESDA/JEDEC JS-001
ESD susceptibility according to Charged Device Model (CDM) pins	$V_{\text{CDM}}$ SR	–	500	V	Conforming to ANSI/ESDA/JEDEC JS-002
Moisture sensitivity level	MSL CC	–	3	–	JEDEC J-STD-020D
Soldering temperature	$T_{\text{SDR}}$ SR	–	260	°C	Profile according to JEDEC J-STD-020D

## **5 Device and Package specification**

### **5.1 SBSL and Chip-IDs**

The table below gives the IDs for the individual devices in the IMC100 family. Depending upon the mode either the SBSL-ID (secure boot loader) or the Chip-ID should be used to identify the device. For details refer to the Reference Manual or the iMOTION™ Programming Manual.

**Table 30 SBSL-IDs and Chip-IDs**

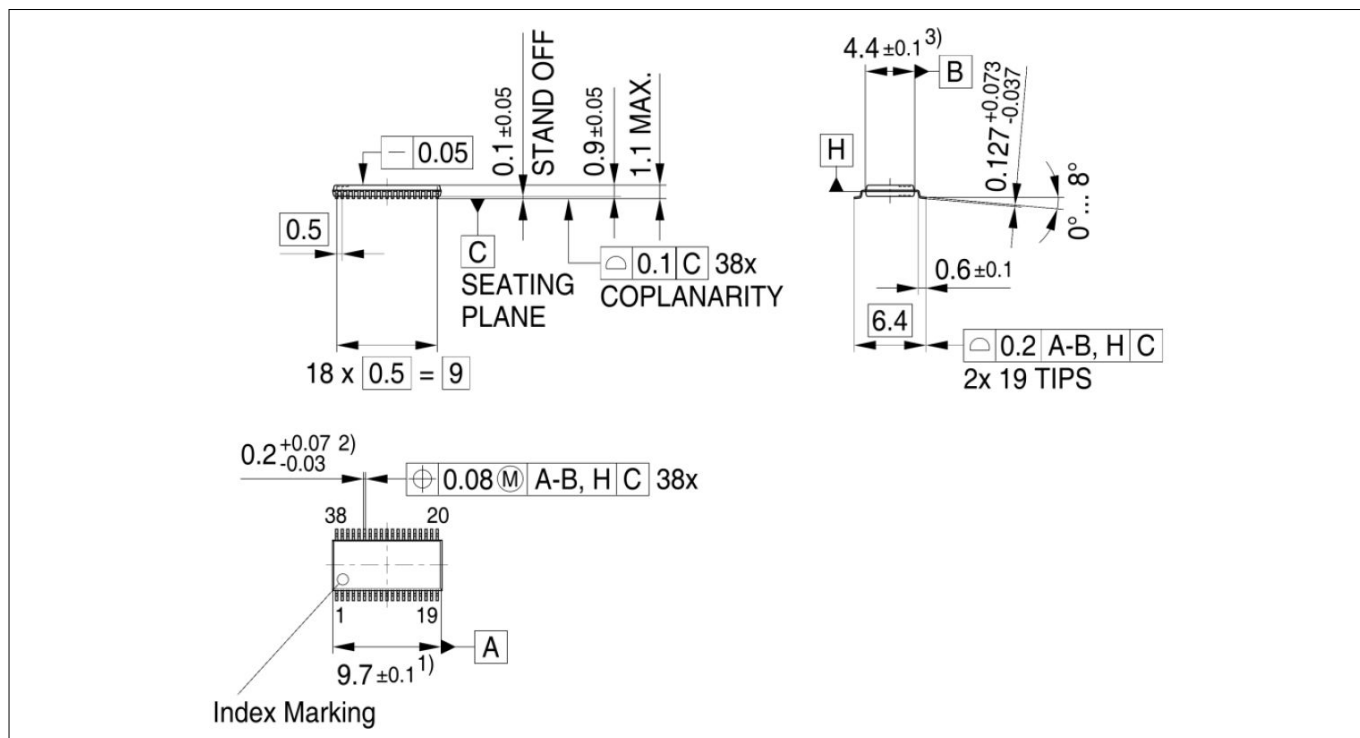
<b>Product Type</b>	<b>Package</b>	<b>Chip-ID</b>	<b>SBSL-ID</b>
IMC099T-T038	TSSOP-38	0x10990005	02af86dbe4df1c3471cd41bfae101928
IMC101T-T038	TSSOP-38	0x11010005	02270f1fccdf57c333d31abd78f960b0
IMC101T-Q048	QFN-48	0x11010008	0244e4486f613c04e6539585aec5d311
IMC101T-F048	LQFP-48	0x11010006	023443609d83afdd5bbda261eb9469b4
IMC101T-F064	LQFP-64	0x1101000B	02a5cdc6d93bbfba0e3617fd7be5df07
IMC102T-F048	LQFP-48	0x11020006	02fc84949a9e41a3043571111137bffb
IMC102T-F064	LQFP-64	0x1102000B	0289426daa14293ab31828d8341ad4ef

## 5.2 Package Outlines

All dimensions in mm.

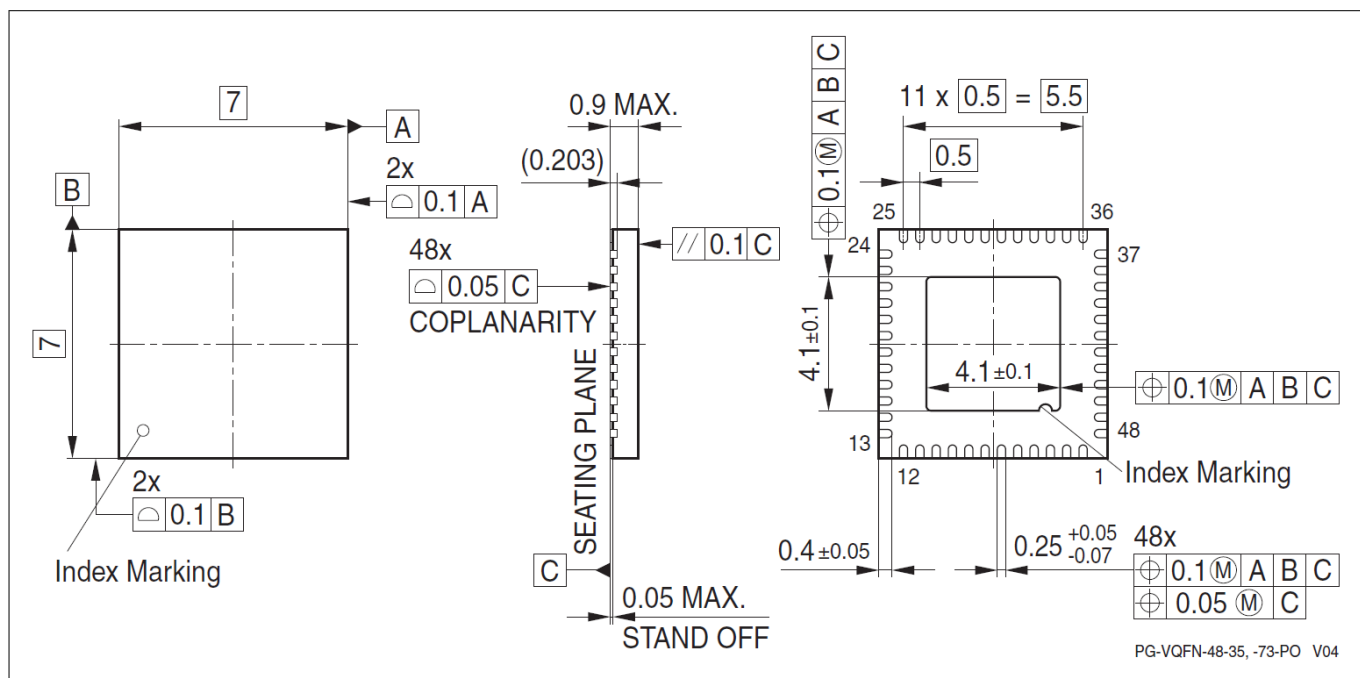
You can find complete information about Infineon packages, packing and marking in our Infineon Internet Page "Packages": [www.infineon.com/packages](http://www.infineon.com/packages)

### 5.2.1 Package Outline PG-TSSOP-38-9



**Figure 22 PG-TSSOP-38-9**

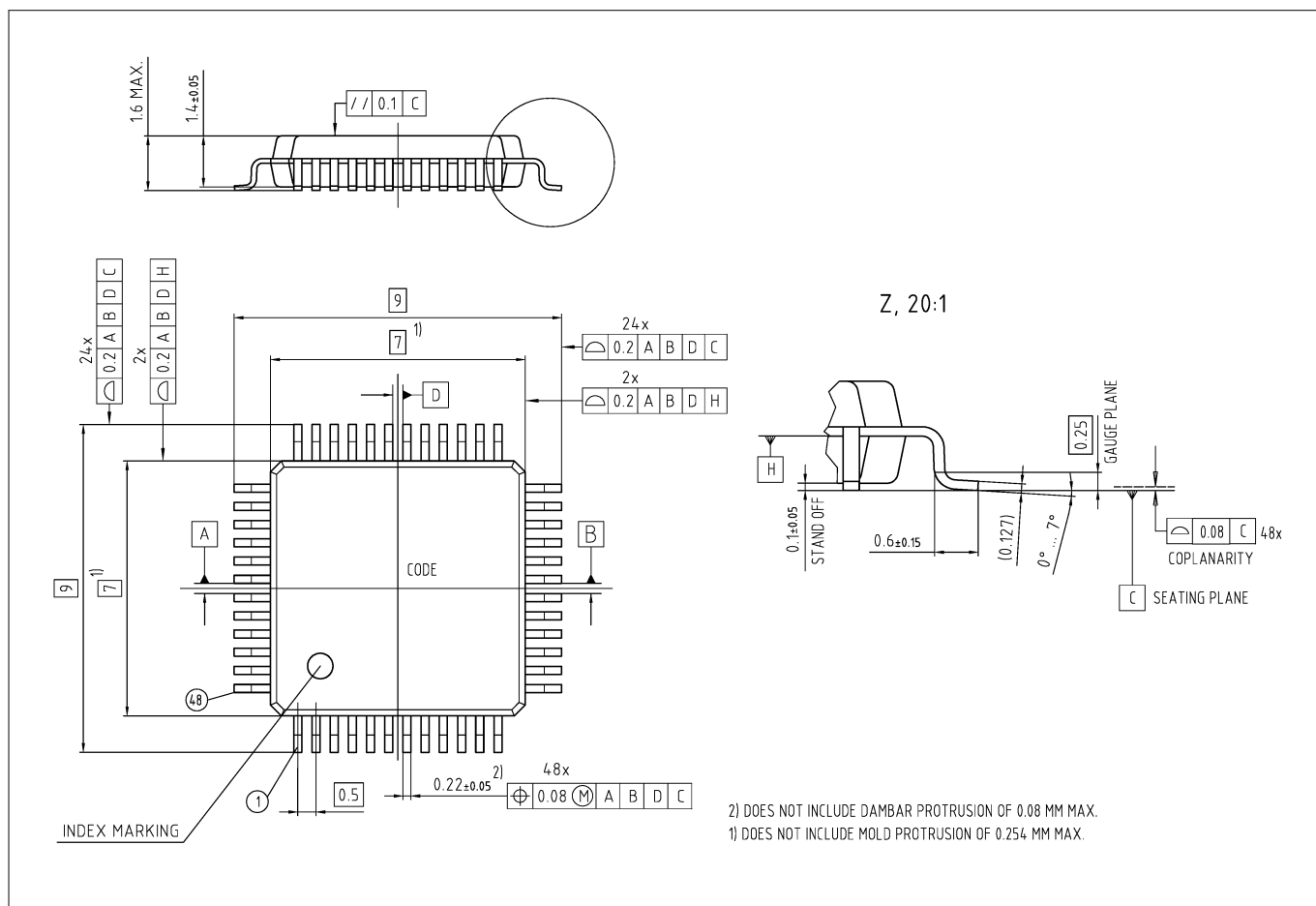
**5.2.2 Package Outline PG-VQFN-48-73**



**Figure 23 PG-VQFN-48-73**



**5.2.3 Package Outline PG-LQFP-48-10**



**Figure 24 PG-LQFP-48-10**

5.2.4 Package Outline PG-LQFP-64-26

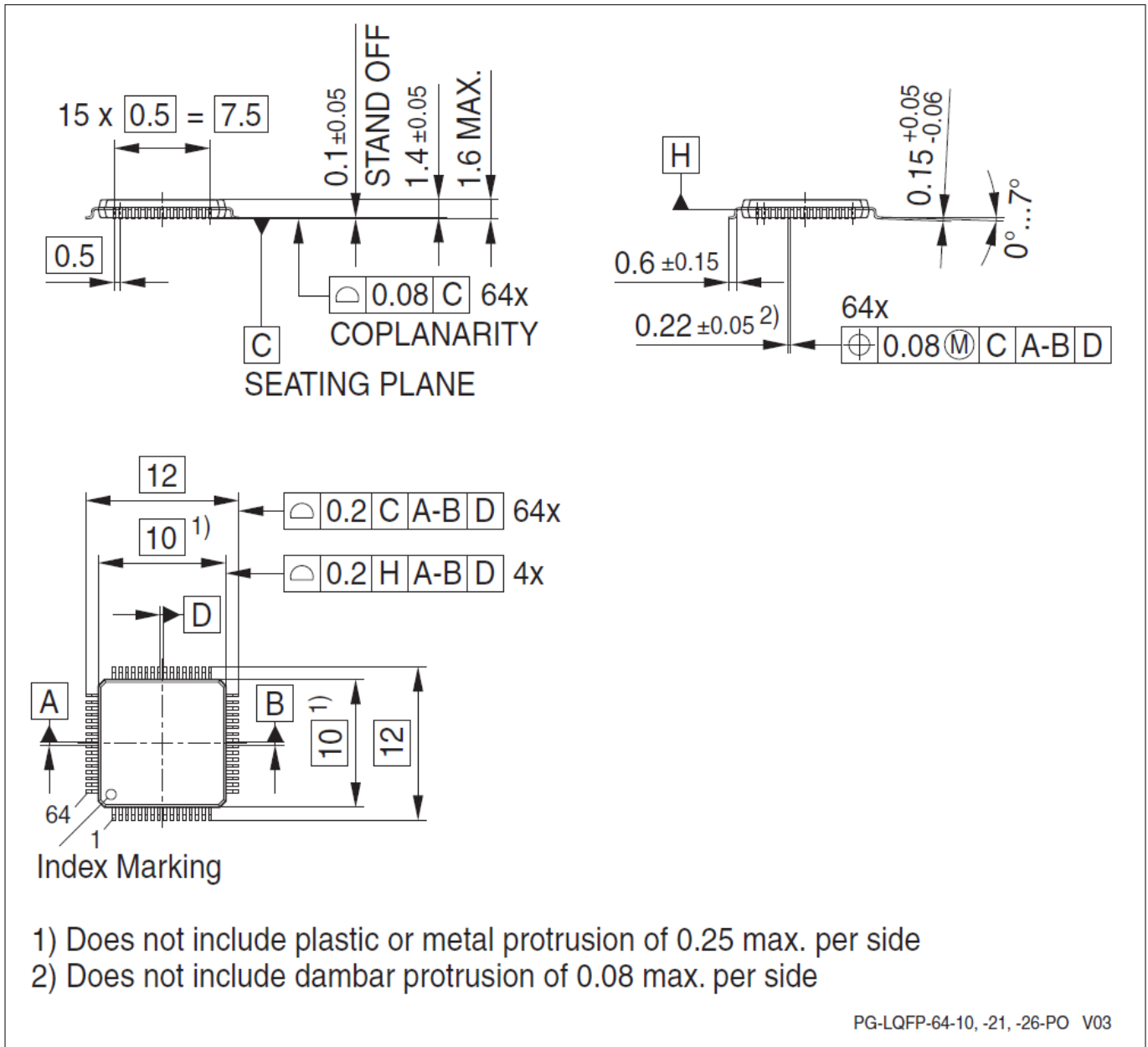


Figure 25 PG-LQFP-64-26

### 5.3 Thermal Considerations

**Table 31 Thermal Characteristics of the Packages**

Parameter	Symbol	Limit Values		Unit	Package Types
		Min.	Max.		
Exposed Die Pad Dimensions	Ex × Ey CC	-	4.2 × 4.2	mm	PG-VQFN-48-73
Thermal resistance Junction-Ambient <sup>15)</sup>	R <sub>ΘJA</sub> CC	-	86.0	K/W	PG-TSSOP-38-9
		-	44.9	K/W	PG-VQFN-48-73
		-	t.b.d.	K/W	PG-LQFP-48-10
		-	66.7	K/W	PG-LQFP-64-26

*Note:* For electrical reasons, it is required to connect the exposed pad to the board ground V<sub>SSP</sub>, independent of EMC and thermal requirements.

When operating the IMC100 in a system, the total heat generated in the chip must be dissipated to the ambient environment to prevent overheating and the resulting thermal damage.

The maximum heat that can be dissipated depends on the package and its integration into the target board. The “Thermal resistance R<sub>ΘJA</sub>” quantifies these parameters. The power dissipation must be limited so that the average junction temperature does not exceed 115°C.

The difference between junction temperature and ambient temperature is determined by

$$\Delta T = (P_{INT} + P_{IOSTAT} + P_{IODYN}) \times R_{\Theta JA}$$

The internal power consumption is defined as

$$P_{INT} = V_{DD} \times I_{DDP} \text{ (switching current and leakage current).}$$

The static external power consumption caused by the output drivers is defined as

$$P_{IOSTAT} = \Sigma((V_{DD} - V_{OH}) \times I_{OH}) + \Sigma(V_{OL} I_{OL})$$

The dynamic external power consumption caused by the output drivers (P<sub>IODYN</sub>) depends on the capacitive load connected to the respective pins and their switching frequencies.

If the total power dissipation for a given system configuration exceeds the defined limit, countermeasures must be taken to ensure proper system operation:

- Reduce V<sub>DD</sub>, if possible in the system
- Reduce the system frequency
- Reduce the number of output pins
- Reduce the load on active output drivers

<sup>15</sup> Device mounted on a 4-layer JEDEC board (JESD 51-5); exposed pad of VQFN soldered.

## 5.4 Part marking

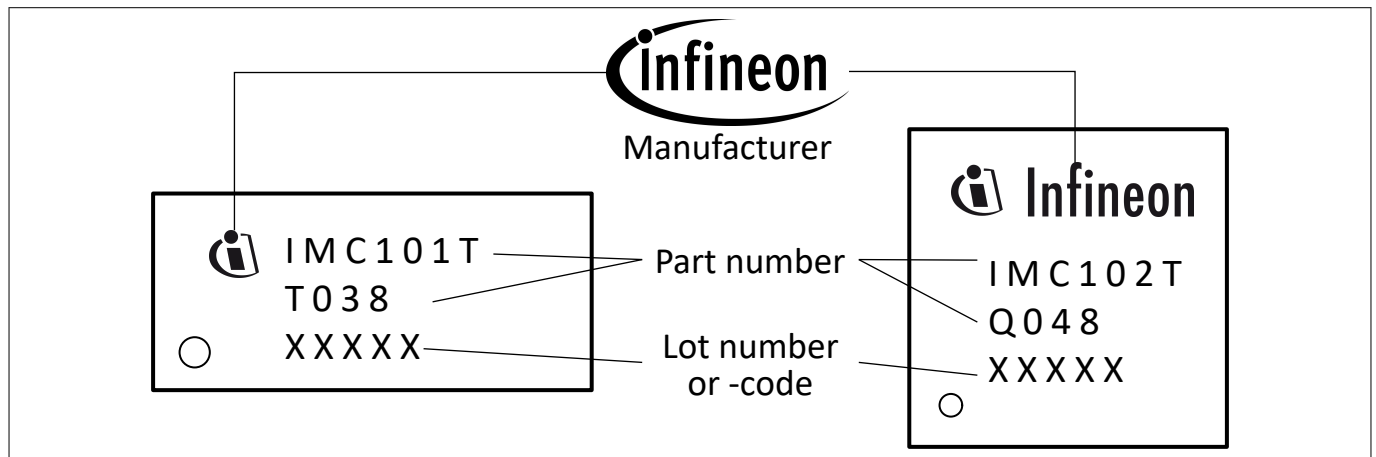


Figure 26 Part marking

## 6 References

### Revision history

Document version	Date of release	Description of changes
1.0	2018-02-09	<ul style="list-style-type: none"><li>Initial version</li></ul>
1.1	2018-02-20	<ul style="list-style-type: none"><li>Corrected RX1, TX1 in QFN-48, QFP-48 and LQFP-64</li></ul>
1.2	2018-07-24	<ul style="list-style-type: none"><li>Added pins for scripting engine</li><li>Added SBSL-IDs and Chip-IDs</li><li>Added input voltage specification</li><li>Several minor corrections</li></ul>
1.3	2019-02-14	<ul style="list-style-type: none"><li>Added the IMC099T-T038</li></ul>
1.4	2019-07-09	<ul style="list-style-type: none"><li>Added IMC102T-F048, IMC102T-F048</li><li>Corrected position of hall pins</li><li>Corrected min/max pin input voltage</li><li>Added GPIO16/GPIO17/GPIO18 to QFN-48 and QFP-48</li></ul>
1.5	2020-04-15	<ul style="list-style-type: none"><li>Added clarification on DUTYFREQ vs. Hall sensor availability</li><li>Added DCO accuracy with calibration</li><li>Increased max motor PWM to 40 kHz</li></ul>
1.6	2020-06-18	<ul style="list-style-type: none"><li>Added GPIO6, GPIO7 to pin table for LQFP-48</li><li>Corrected pin drawing for IMC101F-F048</li></ul>
1.7	2022-09-06	<ul style="list-style-type: none"><li>Removed operating conditions for gate driver</li></ul>

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