

## 50 V Code-Free FOC BLDC Motor Controller

### FEATURES AND BENEFITS

- Code-free sensorless field-oriented control (FOC)
- Proprietary non-reverse fast startup
- Soft-On Soft-Off (SOSO) for quiet operation
- Analog / PWM / Clock mode speed control
- Closed-loop speed control
- Configurable current limit
- Windmill startup operation
- Lock detection
- Short-circuit protection (OCP)
- Brake and direction inputs

### APPLICATIONS

- Ceiling fans
- Pedestal fans
- Bathroom exhaust fans
- Home appliance fans and pumps



### DESCRIPTION

The AMT49406 is a 3-phase, sensorless, brushless DC (BLDC) motor driver (gate driver) which can operate from 5.5 to 50 V.

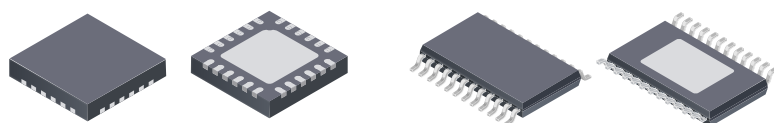
A field-oriented control (FOC) algorithm is fully integrated to achieve the best efficiency and acoustic noise performance. The device optimizes the motor startup performance in a stationary condition, a windmill condition, and even in a reverse windmill condition.

Motor speed is controlled through analog, PWM, or CLOCK input. Closed-loop speed control is optional, and RPM-to-clock frequency ratio is programmable.

A simple I<sup>2</sup>C interface is provided for setting motor-rated voltage, rated current, rated speed, resistance, and startup profiles.

The AMT49406 is available in a 24-contact 4 mm × 4 mm QFN with exposed thermal pad (suffix ES) and a 24-lead TSSOP with exposed thermal pad (suffix LP). These packages are lead (Pb) free, with 100% matte-tin leadframe plating.

### PACKAGES



24-contact QFN  
with exposed thermal pad  
4 mm × 4 mm × 0.75 mm  
(ES package)

24-lead TSSOP  
with exposed thermal pad  
(LP package)

*Not to scale*

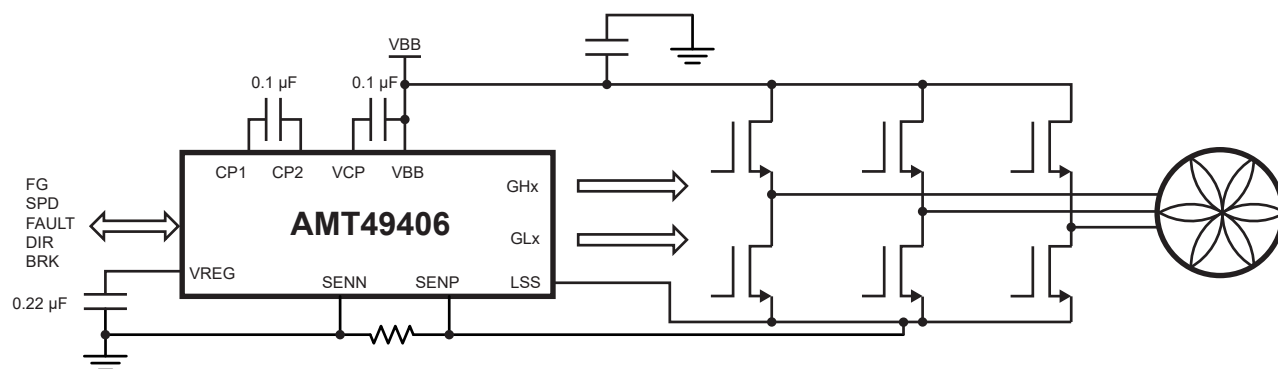


Figure 1: Typical Application

## SELECTION GUIDE

Part Number	Ambient Temperature Range ( $T_A$ ) (°C)	Packaging	Packing
AMT49406GESSR	–40 to 105	24-contact QFN with exposed thermal pad	6000 pieces per 13-inch reel
AMT49406GLPTR	–40 to 105	24-lead TSSOP with exposed thermal pad	4000 pieces per 13-inch reel



## ABSOLUTE MAXIMUM RATINGS

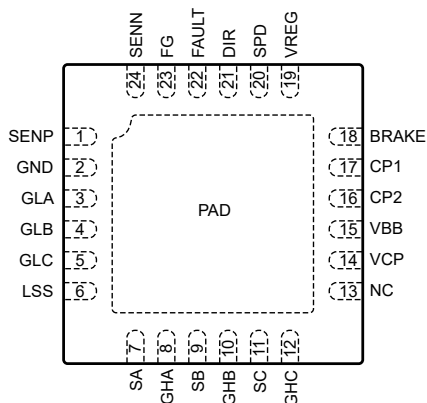
Characteristic	Symbol	Notes	Rating	Unit
Supply Voltage	$V_{BB}$		50	V
Logic Input Voltage Range	$V_{IN}$	SPD, BRAKE, DIR	–0.3 to 6	V
Logic Output	$V_O$	FG ( $I < 5$ mA)	6	V
LSS	$V_{LSS}$	DC	$\pm 500$	mV
		$t_W < 500$ ns	$\pm 4$	V
VREG	$V_{REG}$		0 to 4	V
SENN, SENP	$V_{SENN}, V_{SENP}$	DC	$\pm 500$	mV
		$t_W < 500$ ns	$\pm 4$	V
Output Voltage	$V_{OUT}$	SA, SB, SC	–2 to $V_{BB} + 2$	V
GHx	$V_{GHx}$		$V_{SX} - 0.3$ to $V_{CP} + 0.3$	V
GLx	$V_{GLx}$		$V_{LSS} - 0.3$ to 8.5	V
VCP	$V_{CP}$		$V_{BB} - 0.3$ to $V_{BB} + 8$	V
CP1	$V_{CP1}$		–0.3 to $V_{BB} + 0.3$	V
CP2	$V_{CP2}$		$V_{BB} - 0.3$ to $V_{CP} + 0.3$	V
Junction Temperature	$T_J$		150	°C
Storage Temperature Range	$T_{stg}$		–55 to 150	°C
Operating Temperature Range	$T_A$	Range G	–40 to 105	°C

## THERMAL CHARACTERISTICS

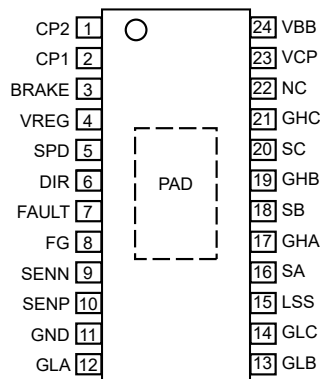
Characteristic	Symbol	Test Conditions*	Value	Unit
Package Thermal Resistance	$R_{\theta JA}$	24-contact QFN (package ES), on 2-sided PCB 1-in. <sup>2</sup> copper	45	°C/W
		24-lead TSSOP (package LP), on 2-sided PCB 1-in. <sup>2</sup> copper	36	°C/W

\*Additional thermal information available on the Allegro website.

## PINOUT DIAGRAMS AND TERMINAL LIST TABLE



ES Package Pinouts



LP Package Pinouts

Terminal List Table

Terminal Number		Name	Function
ES Package	LP Package		
16	1	CP2	Charge pump
17	2	CP1	Charge pump
18	3	BRAKE	Logic input
19	4	VREG	2.8 V regulator voltage
20	5	SPD	PWM or clock mode speed control
21	6	DIR	Direction control
22	7	FAULT	Fault indicator output
23	8	FG	Motor speed output
24	9	SENN	Current sense negative terminal
1	10	SENP	Current sense positive terminal
2	11	GND	Ground
3	12	GLA	Low-side gate drive output
4	13	GLB	Low-side gate drive output
5	14	GLC	Low-side gate drive output
6	15	LSS	Low-side source
7	16	SA	Motor output
8	17	GHA	High-side gate drive output
9	18	SB	Motor output
10	19	GHB	High-side gate drive output
11	20	SC	Motor output
12	21	GHC	High-side gate drive output
13	22	NC	No connect
14	23	VCP	Charge pump
15	24	VBB	Power supply
PAD	PAD	PAD	Exposed pad for enhanced thermal dissipation

**ELECTRICAL CHARACTERISTICS** [1]: Valid over operating ambient temperature range and operating voltage range, unless noted otherwise

Characteristics	Symbol	Test Conditions	Min.	Typ.	Max.	Unit
<b>GENERAL</b>						
Supply Voltage Range	$V_{BB}$	Driving	5.5	–	48	V
		Operating	5.5	–	50	V
VBB Supply Current	$I_{BB}$	$I_{VREG} = 0$ mA	–	8	12	mA
		Standby mode	–	10	20	μA
Reference Voltage	$V_{REG}$	$I_{OUT} = 10$ mA	2.7	2.86	2.95	V
<b>GATE DRIVE</b>						
High Side Gate Drive Output	$V_{GH}$	$V_{BB} = 8$ V	6.5	6.8	–	V
		$V_{BB} = 24$ V	6.5	6.8	–	V
Low Side Gate Drive Output	$V_{GL}$	$V_{BB} = 8$ V	6.5	7.3	–	V
		$V_{BB} = 24$ V	6.5	7.3	–	V
Gate Drive Source Current	$I_{SO}$		–	55	–	mA
Gate Drive Sink Current	$I_{SI}$		–	105	–	mA
<b>MOTOR DRIVE</b>						
PWM Duty On Threshold	$PWM_{ON}$	Relative to target	–0.5	–	0.5	%
PWM Duty Off Threshold	$PWM_{OFF}$	Relative to target	–0.5	–	0.5	%
PWM Input Frequency Range	$f_{PWM(MIN)}$	PWM input frequency setting = 0	2.5	–	100	kHz
		PWM input frequency setting = 1	80	–	3200	Hz
Clock Input Frequency Range	$f_{CLOCK}$	CLOCK mode	1	–	2000	Hz
SPD Standby Threshold (Analog Enter)	$V_{SPD(TH\_ENT)}$		50	100	150	mV
SPD Standby Threshold (Analog Exit)	$V_{SPD(TH\_EXIT)}$		0.4	0.75	1	V
SPD On Threshold	$V_{SPD(ON)}$	ON/OFF setting = 10%	210	250	290	mV
SPD Max	$V_{SPD(MAX)}$		–	2.5	–	V
SPD ADC Resolution	$V_{SPDADC(RES)}$		–	9.78	–	mV
SPD ADC Accuracy	$V_{SPDADC(ACC)}$	$V_{SPD} = 0.2$ to $2.5$ V	–40	–	40	mV
Speed Closed Loop Accuracy	$f_{SPD(ACC)}$	PWM mode or Analog mode	–5	–	5	%
		Clock mode	–0.1	–	0.1	rpm
Dead Time	$t_{DT}$	Code = 9	–	400	–	ns
Motor PWM Frequency	$f_{PWM}$	$T_A = 25^\circ\text{C}$	23.3	24.4	25.4	kHz
<b>PROTECTION</b>						
VBB UVLO	$V_{BB(UVLO)}$	$V_{BB}$ rising	–	4.75	4.95	V
VBB UVLO Hysteresis	$V_{BB(HYS)}$		200	300	450	mV
Thermal Shutdown Temperature	$T_{JTSD}$	Temperature increasing	–	165	–	°C
Thermal Shutdown Hysteresis	$\Delta T_J$	Recovery = $T_{JTSD} - \Delta T_J$	–	20	–	°C

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**ELECTRICAL CHARACTERISTICS** <sup>[1]</sup> (continued): Valid over operating ambient temperature range and operating voltage range, unless noted otherwise

Characteristics	Symbol	Test Conditions	Min.	Typ.	Max.	Unit
<b>LOGIC, IO, I<sup>2</sup>C</b>						
Input Current	$I_{IN}$	SPD, FG; $V_{IN} = 0$ to 5.5 V	-5	1	5	$\mu A$
		BRK, DIR; $V_{IN} = 5$ V	-	50	-	$\mu A$
Logic Input, Low Level	$V_{IL}$		0	-	0.8	V
Logic Input, High Level	$V_{IH}$		2	-	5.5	V
Logic Input Hysteresis	$V_{HYS}$		200	300	600	mV
FG Output Leakage	$I_{FG}$	$V = 5.5$ V	-	-	1	$\mu A$

<sup>[1]</sup> Specified limits are tested at 25°C and 125°C and statistically assured over operating temperature range by design and characterization.

## FUNCTIONAL DESCRIPTION

The AMT49406 is a three-phase BLDC controller with integrated gate driver. It operates from 5.5 to 50 V and targets pedestal fan, ceiling fan, and ventilation fan applications.

The integrated field-oriented control (FOC) algorithm achieves the best efficiency and dynamic response and minimizes acoustic noise. Allegro's proprietary non-reverse startup algorithm improves startup performance. The motor will start up towards the target direction after power-up without reverse shaking or vibration. The Soft-On Soft-Off (SOSO) feature gradually increases the current to the motor at "on" command (windmill condition), and gradually reduces the current from the motor at the "off" command, further reducing the acoustic noise and operating the motor smoothly.

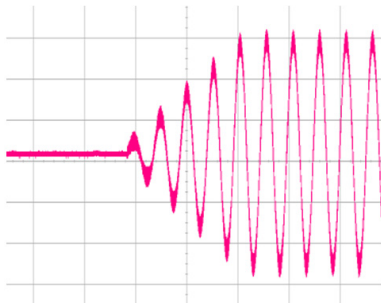


Figure 2: Current Waveform of Soft-On

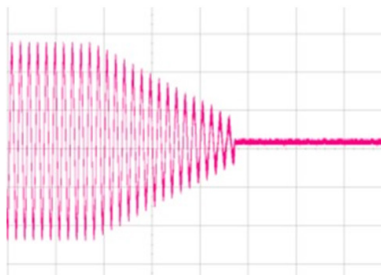


Figure 3: Current Waveform of Soft-Off

## Speed Control

Speed demand is provided via the SPD pin. Three speed control modes are selectable through the EEPROM. The AMT49406 also features a closed-loop speed function, which can be enabled or disabled via the EEPROM.

**PWM Mode:** The motor speed is controlled by the PWM duty cycle on the SPD pin, and higher duty cycle represents higher speed demand. If closed-loop speed is disabled, the output amplitude will be proportional to the PWM duty cycle. If closed-loop speed is enabled, the motor speed is proportional to the PWM duty cycle, and 100% duty represents the rated speed of the motor, which can be programmed in the EEPROM.

$$close\_loop\_speed = rated\_speed \times duty\_input$$

The SPD PWM frequency range is 80 Hz to 100 kHz. If it is higher than 2.8 kHz, set PWMfreq = 0; if it is lower than 2.8 kHz, set PWMfreq = 1.

**Analog Mode:** The motor speed is controlled by the analog voltage on the SPD pin, with higher voltage representing higher speed demand. If closed-loop speed is disabled, the output amplitude will be proportional to the analog voltage input. If closed-loop speed is enabled, the motor speed is as follows:

$$closed\_loop\_speed = rated\_speed \times analog\_input / SPD_{MAX}$$

**CLOCK Mode:** In the clock speed control mode, the closed-loop speed is always enabled. Higher frequency on the SPD pin will drive a higher motor speed as follows:

$$close\_loop\_speed (rpm) = clock\_input \times speed\_ctrl\_ratio,$$

where the speed\_ctrl\_ratio can be programmed in the EEPROM.

For example, if the ratio is 4 and the clock input frequency is 60 Hz, then the motor will operate at 240 rpm. Note the number of motor pole pairs must be set properly in the programming application for the rated speed (rpm) setting to be accurate.

If the clock frequency commands a speed that is higher than twice the rated speed, the AMT49406 treats it as a clock input error and stops the motor.

For all three speed control modes with closed-loop speed enabled, if the demand speed is higher than the maximum speed, the system can run at a certain supply voltage and load condition, and the AMT49406 will just provide the maximum output voltage (if current limit is not triggered) or the maximum output current (if current limit is triggered).

The SPD pin is also used as SCL in the I<sup>2</sup>C mode.

## Motor Stop and Standby Mode

If the speed demand is less than the programmed threshold, the motor will stop.

On/Off Setting	On Threshold	Off Threshold
6%	7.8%	5.9%
10%	11.7%	9.8%
15%	14.9%	12.9%
20%	21.5%	19.6%

For example, consider 10% is set as the threshold. If PWM duty is less than 9.8% (in PWM mode), or the analog voltage is less than 250 mV (in Analog mode), or the CLOCK input frequency is less than 9.8% of the “rated\_speed” (in CLOCK mode), the IC will stop the motor and enter the “idle” mode.

In order to enter standby, two conditions must be met: 1) the motor must be stationary, and 2) PWM or CLOCK signal must remain logic low (in PWM and CLOCK mode) or the analog voltage remains less than  $V_{SPD(TH\_ENT)}$  (in Analog mode) for longer than one second.

A rising edge on PWM or CLOCK will wake the IC in PWM and CLOCK mode, and in Analog mode, the SPD voltage must be higher than  $V_{SPD(TH\_EXIT)}$  to wake up the IC.

Standby Mode will turn off all circuitry including the charge pump and VREG.

After powering on, the device will always be in the active mode before entering standby mode.

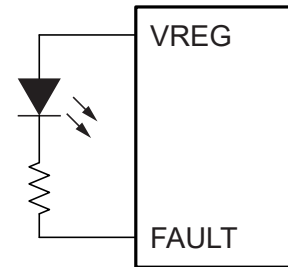
The standby mode can be disabled in the EEPROM.

**Direction Input:** Logic input to control motor direction. For logic high, the motor phases are ordered A→B→C. For logic low, the motor phases are ordered A→C→B. The AMT49406 supports changing the direction input while the motor is running. The direction can also be controlled through register.

**BRAKE:** Active-high signal turns on all low sides for braking function. The Brake function overrides speed control input. Care should be taken to avoid stress on the MOSFET when braking while the motor is running. With braking, the current will be limited only by  $V_{BEMF}/R_{MOTOR}$ . The AMT49406 includes an optional feature which holds off braking until the motor speed drops to a low enough (configurable) level so that the braking current will not damage the MOSFET.

**FAULT:** Open-drain output provides motor operation fault status. Default is high when there is no fault.

An LED and a serial resistor is recommended between the FAULT and VREG pins. The LED indicates fault information.



**Figure 4: AMT49406 with LED and Serial Resistor**

Fault Type	FAULT Pin	LED Pattern
Lock detected	low	constant on
OCP	0.67 seconds high 0.67 seconds low	slow flashing
OTP	0.67 seconds low 0.17 seconds high 0.08 seconds low 0.17 seconds high 0.08 seconds low 0.17 seconds high	long-short-short flashing
system error	0.08 seconds low 0.08 seconds high 0.08 seconds low 1.09 seconds high	double short flashing
OVP	0.17 seconds high 0.17 seconds low	fast flashing
zero speed demand	0.25 seconds high 0.08 seconds low 0.34 seconds high 0.67 seconds low	long-short flashing

**FG:** Open-drain output provides motor speed information to the system. The open-drain output can be pulled up to VREG or an external 3.3 or 5 V supply.

The FG pin is also used as SDA in I<sup>2</sup>C mode. The first I<sup>2</sup>C command can pass only when the FG is high (open drain off). After the first I<sup>2</sup>C command, the FG pin is no longer used for speed information, and the FG pin is dedicated as a data pin for the I<sup>2</sup>C interface.

FG is default high after power-on and exit from standby mode, and stays high for at least 9.8 ms. To ensure successful I<sup>2</sup>C communication, it is recommended to have the first I<sup>2</sup>C demand right after power-up or exit from standby mode within 9.8 ms.

**VREG:** Voltage reference (2.8 V) to power internal digital logic and analog circuitry. VREG can be used to power external circuitry with up to 10 mA bias current, if desired. A ceramic capacitor with 0.22  $\mu\text{F}$  or greater is required on the pin to stabilize the supply.

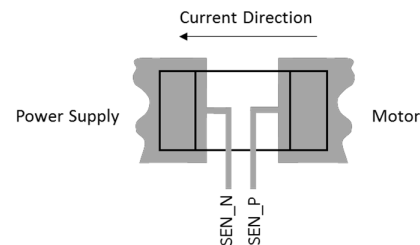
When VREG is loaded externally, the power consumption of the internal LDO is calculated by the equation:

$$P_{\text{LDO}} = (I_{\text{LOAD}} + I_{\text{INTERNAL}}) \times (V_{\text{BB}} - V_{\text{REG}}).$$

Ensure that the system has good power dissipation and the temperature is within the operating temperature range. The AMT49406 thermal shutdown function does not protect the LDO.

**Bus Current Sensing:** A single shunt-resistor connection between SENN and SENP is used to measure the bus current for the FOC algorithm and current limit. The resistor value is approximately tens of a milliohm, depends on the rated current of the system. The voltage difference between SENN and SENP should be less than 65 mV to prevent the signal saturation. For example, if the rated current is 4 A, it is recommend to use a 15 m $\Omega$  sensing resistor, so that 4 A  $\times$  15 m $\Omega$  is between 55 and 65 mV.

Use Kelvin sensing connection for the shunt resistor.



**Lock Detect:** A logic circuit monitors the motor position to determine if motor is running as expected. If a fault is detected, the motor drive will be disabled for the configurable  $t_{\text{LOCK}}$  time before an auto-restart is attempted. For additional information, refer to the configuration guide.

**Current Control:** The motor's rated current at rated speed and normal load must be programmed to the EEPROM for proper operation. The AMT49406 will limit the motor current (phase current peak value) to 1.3 times the programmed rated current during acceleration or increasing load, which protects the IC and the motor. The current profile during startup can also be programmed.

**Overcurrent Protection (short protection):** The  $V_{\text{DS}}$  voltages across each power MOSFET are monitored by the AMT49406. If a  $V_{\text{DS}}$  is higher than the threshold when that MOSFET enabled, an OCP fault is triggered and the IC will stop driving immediately.



## I<sup>2</sup>C OPERATION AND EEPROM MAP

The I<sup>2</sup>C interface allows the user to program the register and parameters into EEPROM. The AMT49406 7-bit slave address is 0x55.

After power-on, the default values in EEPROM will be loaded into the registers, which determines motor system operation. I<sup>2</sup>C can overwrite those values and change the motor system operation on the fly.

I<sup>2</sup>C can also be used to program the EEPROM, which is normally done in the production line.

The figures below shows the I<sup>2</sup>C interface timing.

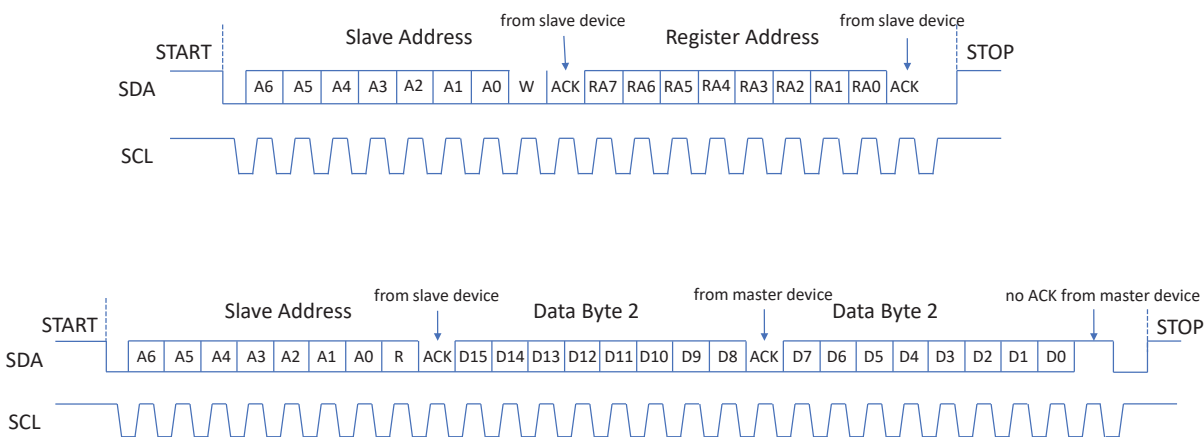
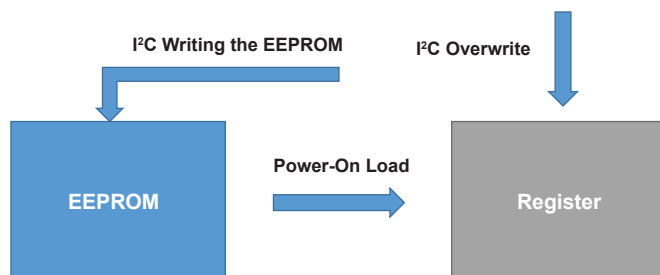


Figure 5: Read Command

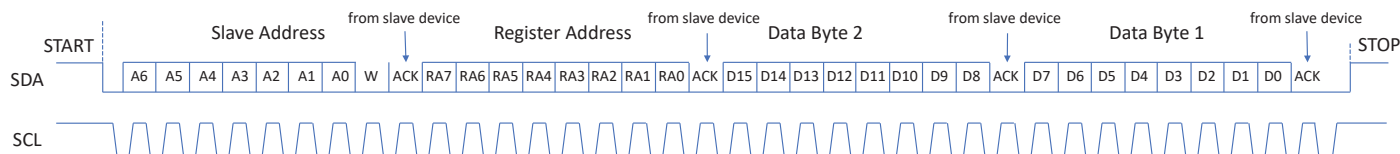


Figure 6: Write Command

## Register and EEPROM Map

Each register bit is associated with one EEPROM bit. The register address is the associated EEPROM bit address plus 64. For example, the rated speed is in EEPROM address 8, bit[10:0]; the associated register address is 72, bit[10:0].

In the following table, the bits shaded in gray should be kept at their default values. Changing these values may cause malfunction or damage to the part. If programming the EEPROM with

a custom programmer, it is recommended to use the AMT49406 application to determine the appropriate settings, save the settings file, and use the file contents to program to the EEPROM. The application's settings file contains one line for each EEPROM address, containing addresses 8 through 22 (15 lines/addresses).

Registers not shown in the table are not for users to access. Changing the value in undocumented registers may cause malfunction or damage to the part.

**Table 1: Register and EEPROM Map**

Address		AMT49406 Register Map			
0		Allegro internal information. No associated register for these EEPROM data			
1					
2					
3					
4					
5					
6		User-flexible code. No associated register for these EEPROM data. Provided to user. For example, tracking number of product, product revision info, etc.			
7					
8 / 72	3:0	Rated_speed [3:0]			
	7:4	Rated_speed [7:4]			
	11:8	speed_close_loop	Rated speed [10:8]		
	15:12	PWMin_range	Direction	Accelerate_range	Clock_PWM
9 / 73	3:0	Acceleration [3:0]			
	7:4	Acceleration [7:4]			
	11:8	Motor_Resistance [3:0]			
	15:12	Motor_Resistance [7:4]			
10 / 74	3:0	Rated Current [3:0]			
	7:4	Rated Current [7:4]			
	11:8	SPD mode	Rated Current [10:8]		
	15:12	Startup_Current [2:0]			
11 / 75	3:0	Open_Drive			
	7:4	Power_Ctl_En			open_ph_protect
	11:8	Startup_mode [1:0]			
	15:12				
12 / 76	3:0	PID_P [3:0]			
	7:4	PID_P [7:4]			
	11:8	Motor_Inductance [3:0]			
	15:12	Open_Window		over_Speed_Lock	Motor_Inductance [4]

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**Table 1: Register and EEPROM Map (continued)**

Address		AMT49406 Register Map			
13 / 77	3:0	PID_I [3:0]			
	7:4	PID_I [7:4]			
	11:8				
	15:12		delay_start		
14 / 78	3:0				
	7:4				
	11:8				
	15:12				
15 / 79	3:0	Angle_Error_Lock (startup)			
	7:4	soft_on	soft_off		
	11:8	Deadtime_setting [3:0]			
	15:12	Safe_Brake_thrd [1:0]			
16 / 80	3:0	OCP_reset_mode	OCP_Enable		
	7:4	First_cycle_speed [1:0]			
	11:8	Decelerate_buffer [1:0]		Accelerate_buffer [1:0]	
	15:12			BEMF_Lock_filter [1:0]	
17 / 81	8:0	Speed_demand [8:0]			
	9	i2c_speed_mode			
	15:10				
18 / 82	3:0				
	7:4				
	11:8	IPD_Current_Thr [3:0]			
	15:12			IPD_Current_Thr [5:4]	
19 / 83	7:0				
	15:8				
20 / 84	7:0	Rated_Voltage			
	15:8	Sense_Resistor			
21 / 85	3:0				
	7:4	slight_mv_demand [2:0]			
	11:8			speed_input_off_threshold [1:0]	
	15:12	standby_dis			
22 / 86	3:0	speed close loop parameter			
	7:4	Restart_attempt		speed close loop parameter	
	11:8	Lock_restart_set	vibration_lock		Brake_mode
	15:12				

**Table 2: Register and EEPROM Map Notes**

Parameter	Address	Notes
Rated_Voltage	20 [7:0]	Rated Voltage (V) = Rated_voltage_register_value / 5
Rated_Speed	8 [10:0]	Rated Speed (Hz) = Rated_speed_register_value × 0.530
Motor_Resistance	9 [15:8]	Motor Resistance ( $\Omega$ ) = Motor_resistance_register_value / [ (Rated_voltage_register_value × 4.096) / (Sense_resistor_register_value / 125) / (Rated_voltage_register_value / 10) ]
Rated_Current	10 [10:0]	Rated Current (mA) = Rated_current_register_value / (Sense_resistor_register_value / 125)
Startup_Current	10 [15:13]	0: NA. else Startup Current = Rated Current × 1/8 × (startup_current_register_value + 1)
Acceleration	9 [7:0]	Acceleration (Hz/s) = Acceleration_register_value × k if range = 0 then k = 0.05, else k = 3.2
Accelerate_range	8 [13]	
speed_close_loop	8 [11]	1: closed loop. 0: open loop.
Direction	8 [14]	1: A→B→C. 0: A→C→B.
SPD mode	10 [11]	1: analog 0: digital (PWM or Clock).
Clock_PWM	8 [12]	1: clock mode. 0: PWM mode.
PWMin_range	8 [15]	1: ≤ 2.8 kHz 0: > 2.8 kHz.
clock_speed_ratio	22 [5:0]	Ratio (rpm/Hz) = clock_speed_ratio_value × 0.25. clock_speed_ratio maximum value is 42.
Speed_input_off_threshold	21 [9:8]	00: 10%. 01: 6% 10: 15%. 11: 20%
Startup_mode	11 [11:10]	00: 6 pulse mode. 01: 2 pulse mode. 10: slight-move mode. 11: align & go.
IPD_current_thrd	18 [13:8]	IPD current threshold (A) = IPD_current_thrd_value × 0.086
Slight_mv_demand	21 [7:5]	Amplitude demand in slight move mode (%) = value × 3.2 + 2.4
PID_P	12 [7:0]	Position observer loop P gain.
PID_I	13 [7:0]	Position observer loop I gain.
Motor_Inductance	12 [12:8]	Refer to the configuration guide.
Sense_Resistor	20 [15:8]	Sense resistor value (m $\Omega$ ) = sense_resistor_value / 3.7
Open_drive	11 [3]	Refer to the configuration guild.
Power_Ctrl_En	11 [7]	1: enable the current limit.
Open_window	12 [15]	1: open window for inductance tuning. 0: normal
delay_start	13[13]	1: delayed start. 0: start right after windmill checking.
Soft_off	15 [6]	Refer to the functional description.
Soft_on	15 [7]	Refer to the functional description.
First_Cycle_Speed	16 [7:6]	00: 0.55 Hz. 01: 1.1 Hz. 10: 2.2 Hz. 11: 4.4 Hz
Accelerate_buffer	16 [9:8]	Refer to the configuration guide.
Decelerate_buffer	16 [11:10]	Refer to the configuration guide.
Deadtime_setting	15[11:8]	(n + 1) × 40 ns.
Standby_mode	21 [15]	0: enable. 1: disable.
Brake_mode	22 [8]	0: brake when safe. 1: 100% uncontrolled
Safe_brake_thrd	15 [15:14]	00: 1× rated current. 01: 2×. 10: 4×. 11: 8×.
OCP_reset_mode	16 [3]	0: upon motor restart. 1: after 5 seconds.

Continued on next page...

Table 2: Register and EEPROM Map Notes (continued)

Parameter	Address	Notes
OCP_Enable	16 [2:0]	100: 480 ns filter. 111: OCP disabled.
Angle_Error_Lock	15 [3:2]	Lock detect during startup. 00: disabled. 01: 5 degrees. 10: 9 degrees. 11: 13 degrees
BEMF_lock_filter	16 [13:12]	Refer to the configuration guide.
Open_ph_protect	11 [4]	Refer to the configuration guide.
Vibration_lock	22 [10]	Refer to the configuration guide.
Over_speed_lock	12 [13]	Refer to the configuration guide.
Restart_attempt	22 [7:6]	00: Always. 01: 3 times. 10: 5 times. 11: 10 times.
Lock_restart_set	22 [11]	0: 5 seconds. 1: 10 seconds.
i2c_spd_mode	17 [9]	0: controlled by SPD pin. 1: controlled by register value in 17 [8:0].
i2c_spd_demand	17 [8:0]	0~511 represents 0~100%
<b>READBACK</b>		
Motor speed	120	Motor Speed (Hz) = register_value × 0.530 Hz
Bus current	121	Bus current (mA) = register_value / (Sense_resistor_register_value / 125)
Q-axis current	122	Q-axis current (mA) = register_value / (Sense_resistor_register_value / 125)
V <sub>BB</sub>	123	V <sub>BB</sub> (V) = register_value / 5
Temperature	124	Temperature (°C) = register_value – 53
Control demand	125	0~511 represents 0~100%
Control command	126	0~511 represents 0~100%
Operation state	127 [15:12]	

Note: Refer to application note and user interface for additional detail.

## Programming EEPROM

The AMT49406 contains 24 words of EEPROM, each of 16 bit length. The EEPROM is controlled with the following I<sup>2</sup>C registers.

### EEPROM Control – Register 161: Used to control programming of EEPROM

Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
Name	0	0	0	0	0	0	0	0	0	0	0	0	RD	WR	ER	EN

Bit	Name	Description
0	EN	Set EEPROM voltage required for Writing or Erasing.
1	ER	Sets Mode to Erase.
2	WR	Sets Mode to Write.
3	RD	Sets Mode to Read.
15:4	n/a	Do not use; always set to zero (0) during programming process.

### EEPROM Address – Register 162: Used to set the EEPROM address to be altered

Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
Name	0	0	0	0	0	0	0	0	0	0	0	eeADDRESS				

Bit	Name	Description
0:4	eeADDRESS	Used to specify EEPROM address to be changed. There are 20 addresses. Do not change address 0 or 19 as these are factory-controlled.
15:5	n/a	Do not use; always set to zero (0) during programming process.

### EEPROM Data\_In – Register 163: Used to set the EEPROM new data to be programmed

Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
Name	eeDATAin															

Bit	Name	Description
15:0	eeDATAin	Used to specify the new EEPROM data to be changed.

## EEPROM Commands

There are three basic commands, Read, Erase, and Write. To change the contents of a memory location, the word must be first erased. The EEPROM programming process (writing or erasing) takes 10 ms per word.

Each word must be written individually. The following examples are shown in the following format:

I2C\_register\_address [data] ; comment

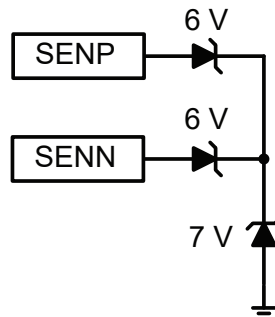
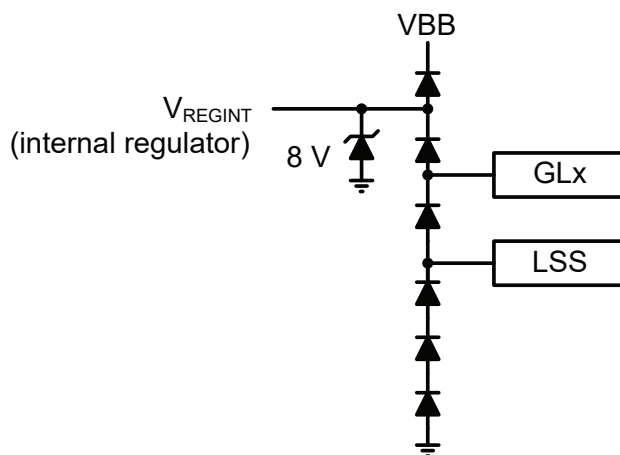
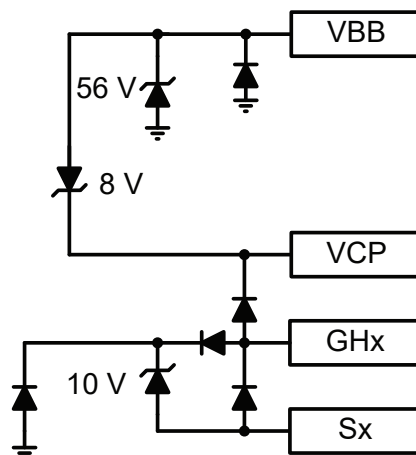
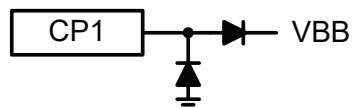
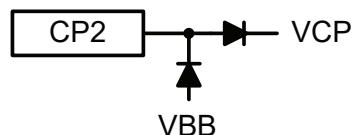
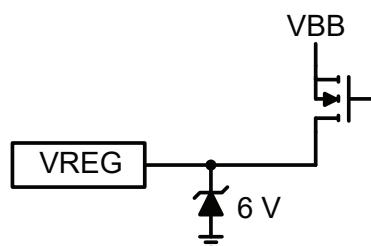
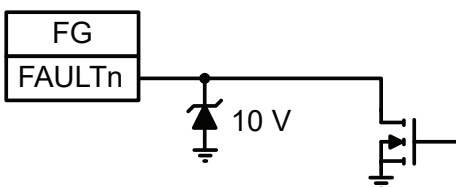
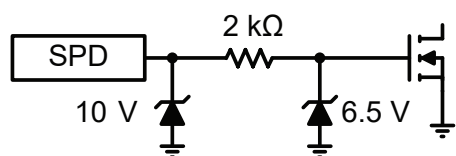
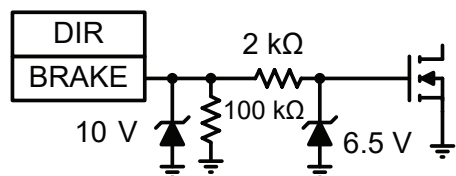
Example #1: Write EEPROM address 7 to 261 (hex = 0x0105)

1. Erase the existing data.
2. Write the new data.
  - A. 162 [7] ; set EEPROM address to write.
  - B. 163 [261] ; set Data\_In = 261.
  - C. 161 [5] ; set control to Write and Set Voltage High.
  - D. Wait 15 ms ; requires 15 ms High Voltage Pulse to Write.
  - E. 161 [0] ; clear Voltage.

Example #2: Read address 7 to confirm correct data properly programmed.

1. Read the word.
  - A. 7 [N/A for read] ; read register 7; this will be contents of EEPROM.

## PIN DIAGRAMS





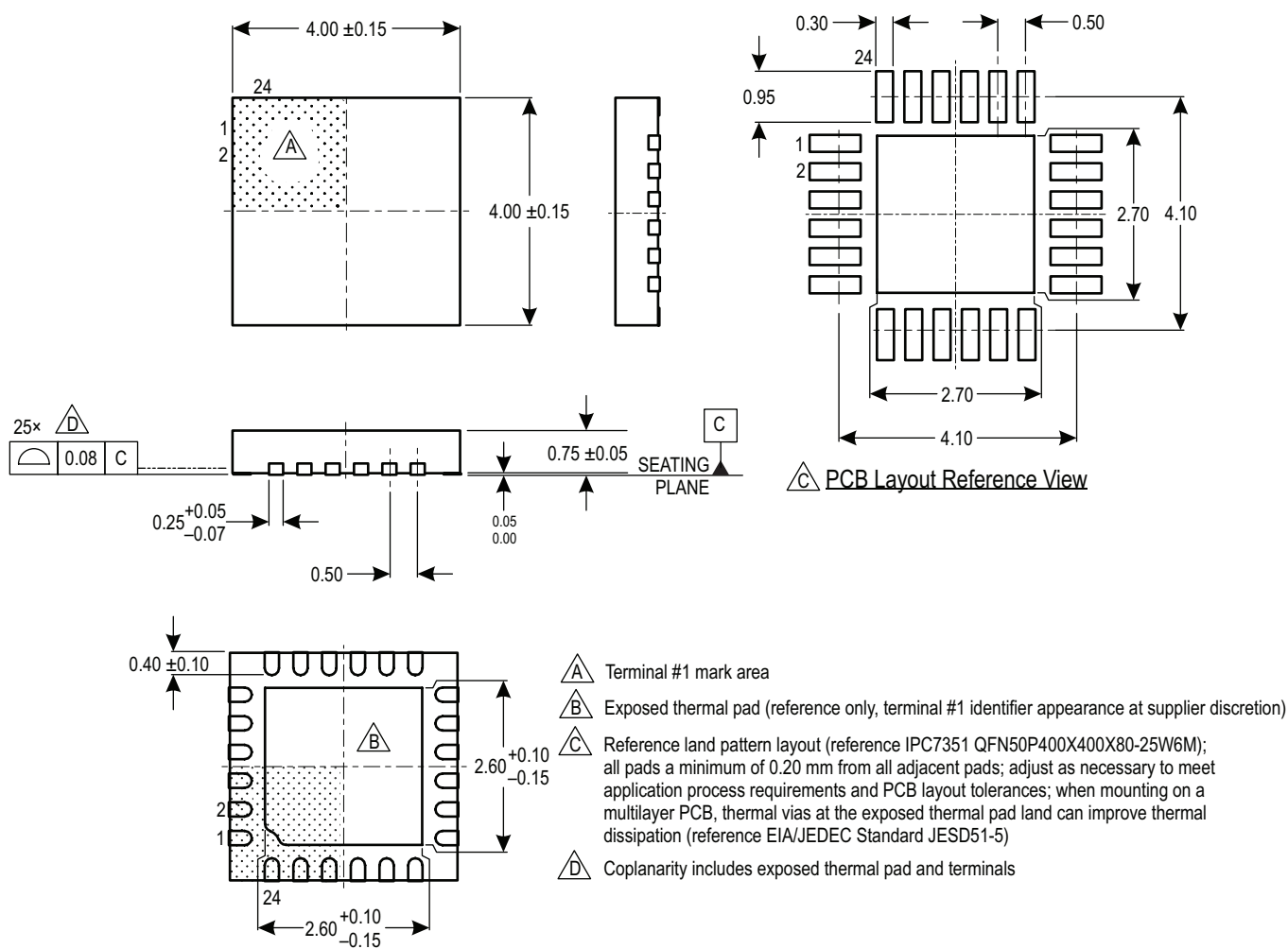
## PACKAGE OUTLINE DRAWING

**For Reference Only – Not for Tooling Use**

Reference Allegro DWG-2871 (Rev. A) or JEDEC MO-220WGGD-11.

Dimensions in millimeters – NOT TO SCALE.

Exact case and lead configuration at supplier discretion within limits shown.

**Figure 7: Package ES, 24-Contact QFN with Exposed Pad**

## For Reference Only – Not for Tooling Use

(Reference MO-153 ADT)

NOT TO SCALE

Dimensions in millimeters

Dimensions exclusive of mold flash, gate burrs, and dambar protrusions

Exact case and lead configuration at supplier discretion within limits shown

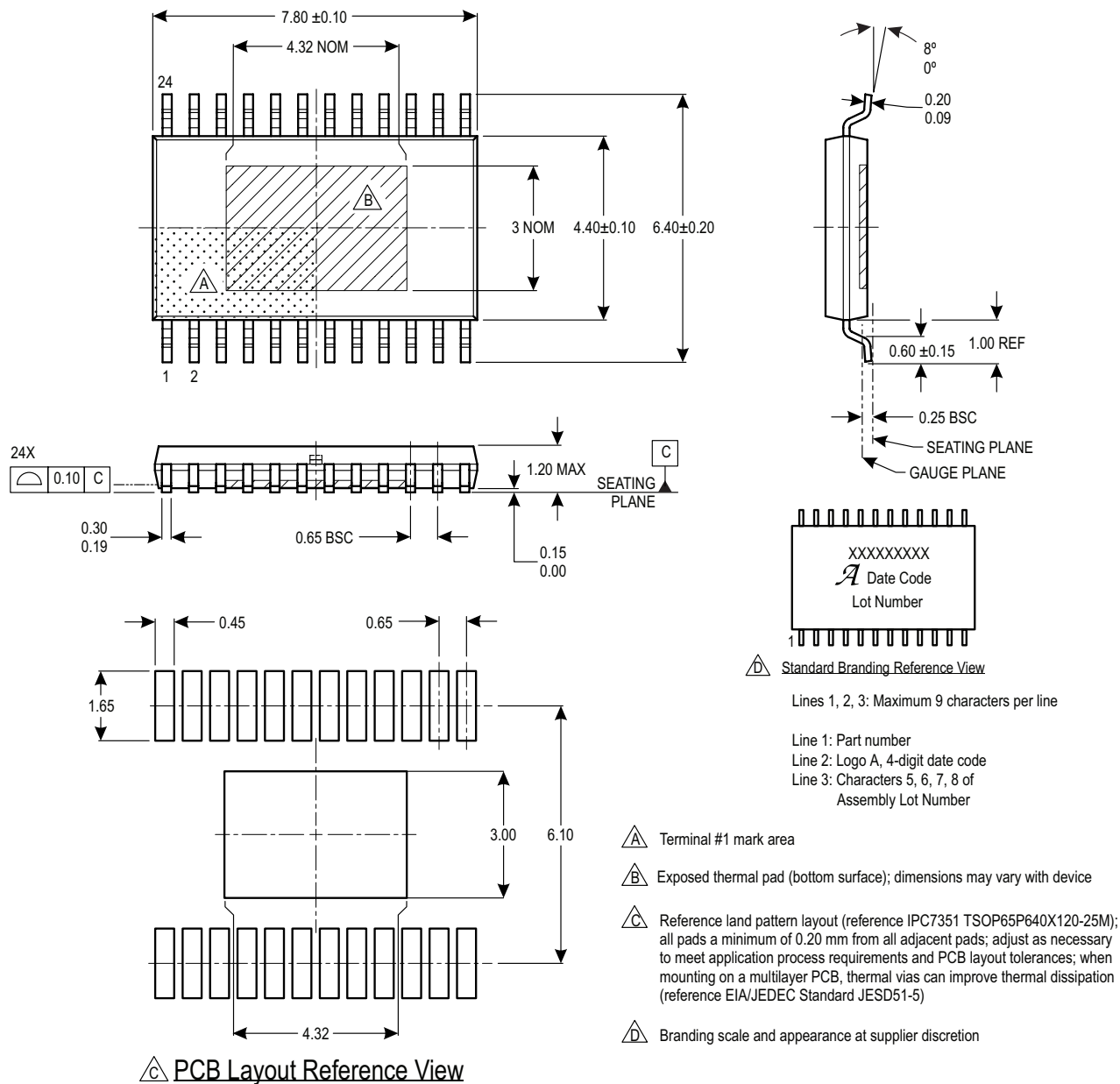


Figure 8: Package LP, 24-Lead TSSOP with Exposed Pad

**Revision History**

Number	Date	Description
–	December 13, 2018	Initial release
1	January 24, 2019	Updated Motor PWM Frequency (page 4)

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