DRV10974 12V、三相无传感器 BLDC 电机驱动器

1 特性

- 输入电压范围：4.4 V 至 18 V
- 总驱动器 H + L $r_{DS(on)}$：750mΩ（典型值），T_A = 25°C 时
- 相位驱动电流：1A 连续（峰值 1.5A）
- 180° 正弦换向，可实现最优声学性能
- 可利用电阻器配置超前角
- 可利用电阻器配置电流限制
- 软启动和可通过电阻器配置的加速曲线
- 提供内置电流感应，无需使用外部电流感应电阻器
- 专有无传感器控制，无需电机中心抽头
- 简单的用户接口：
  - 用于启动的单引脚配置
  - PWM 输入指定施加到电机的电压幅度
  - 开漏 FG 输出提供速度反馈
  - 用于正向/反向控制的引脚
- 全方位保护：
  - 电机锁定检测和重启
  - 过流、短路、过热和欠压保护

2 应用

- 白色家电
- 风扇、风机和泵
- BLDC 电机模块

3 说明

DRV10974 器件是一款具有集成功率 MOSFET 的三相无传感器电机驱动器，可提供高达 1A (rms) 的持续驱动电流。该器件专为成本敏感型、低噪声和低外部组件数量的应用而设计。

DRV10974 器件使用一个专有无传感器控制方案提供可靠换向。180° 正弦换向显著减少了 120°（梯形）换向中较为典型的纯音。DRV10974 旋转使用一个外部低功耗电阻器进行配置。电流限制可使用外部低功耗电阻器进行设置。

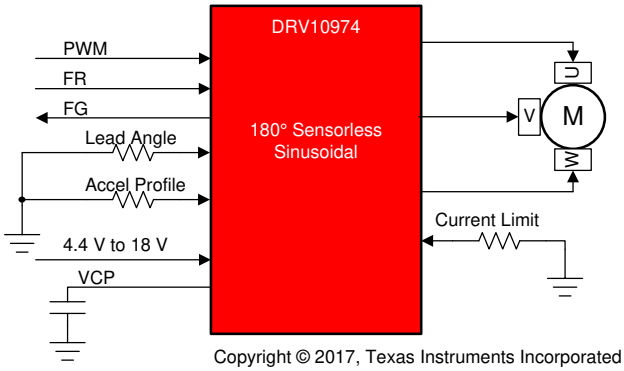
通过施加一个用于控制驱动电压幅度的 PWM 输入，或者使用模拟电压驱动 PWM 引脚，然后监控 FG 引脚上的速度反馈，DRV10974 器件可以轻松控制电机的转速。

DRV10974 器件包含许多可提高效率的特性。由于该器件支持借助电阻器配置超前角，因此用户可通过调整相电流和相 BEMF 来优化驱动器效率。此外，该器件使用的 MOSFET 的 $r_{DS(on)}$ 较低，有助于在驱动电机时节省电力。

器件信息(1)

器件型号	封装	封装尺寸（标称值）
DRV10974	HTSSOP (16)	5.00mm x 4.40mm
	WQFN (16	4.00mm × 4.00mm

(1) 如需了解所有可用封装，请参阅产品说明书末尾的可订购产品附录。



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应用原理图

本文档旨在为方便起见，提供有关 TI 产品中文版本的信息，以确认产品的概要。有关适用的官方英文版本的最新信息，请访问 www.ti.com，其内容始终优先。TI 不保证翻译的准确性和有效性。在实际设计之前，请务必参考最新版本的英文版本。

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4 Revision History

Changes from Revision D (June 2020) to Revision E (March 2021) — **Page**

- Updated Human-body model (HBM) 5

Changes from Revision B (June 2018) to Revision C (September 2018) — **Page**

- 将文档状态从“混合状态”更改为“量产数据” 1
- 删除了*器件信息*表 WQFN 条目中的“高级信息”标识 1
- Deleted the "Advance informatoin" note from the WQFN pinout drawing 3
- Deleted the "Advance Information" note from the *Thermal Information* table 5
- Added description of Analog Mode Speed Control 12
- Added Kt High and Kt Low descriptions in abnormal Kt lock detect figure 16
- Added layout example for QFN package type 27

Changes from Revision A (April 2018) to Revision B (June 2018) — **Page**

- 向*器件信息*表中添加了 WQFN 封装 1
- Added pinout drawing for the WQFN package 3
- Added a column to the *Pin Functions* table for the WQFN package, and added the TYPE column 3
- Added a column to the *Thermal Information* table for the VQFN package 5
- Changed $r_{DS(on)}$ vs. Temperature graph to include V_{CC} condition 10
- Changed Speed-Control Transfer Function figure to clearly show when the device enters and exits low power mode 12
- Updated Lock BEMF Abnormal text for clarity 16
- Changed *Detailed Design Procedure* to cover the high level tuning process of the RMP, ADV, and CS settings 25

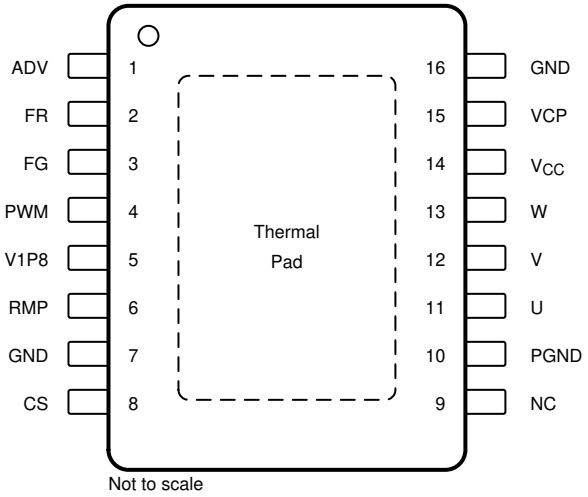
Changes from Revision * (January 2018) to Revision A (April 2018) — **Page**

- 添加或更改了*节 1* 列表中的项目 1
- 更改了*节 3* 部分第三段的内容 1
- Added parameter symbol (f_{PWM_OUT}) to the 25-kHz PWM signal 12
- Added parameter symbol (f_{PWM_OUT}) to the 25-kHz PWM signal 12
- Added parameter symbol (DC_{STEP}) for the control resolution 12

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- Added parameter symbol (DC_{ON_MIN}) for the minimum-operation duty cycle....12
- Changed "pulse durations" to "duty cycles"....12
- Changed PWM_{DC} to PWM_{dc}....12
- Added parameter symbol (f_{FG_MIN}) for the motor speed....15
- Changed the number of lock-detect schemes from five to six....15
- Added a table note stating the required resistor tolerance....18
- Added a new 节 *7.4.1.2* section....19
- Added a parameter symbol (t_{ALIGN}) in the 节 *7.4.1.3* section, and reworded the last sentence thereof....20
- Changed the column headings of the two rightmost columns in 表 7-2....20
- Added three table notes following 表 7-2....20
- Changed "programmed resistor" to "selected resistor"....21
- Added a table note stating the required resistor tolerance....21
- Added a table note stating the required resistor tolerance....22
- Added a ±30% tolerance to the V1P8 capacitor in 表 8-1....24
- Changed content of Row 4 in 表 8-2 to "Motor electrical constant"....25
- Deleted all previous content from the 节 *8.2.2* section and replaced it with a reference to the *DRV10974 Tuning Guide*....25
- Changed 图 8-3....25
- Added location information for the capacitor in the 节 *9* section....26

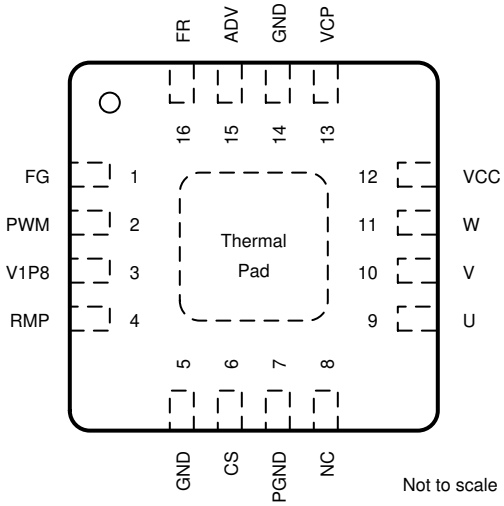
5 Pin Configuration and Functions



NC – No internal connection

图 5-1. PWP PowerPAD™ Package 16-Pin HTSSOP With Exposed Thermal Pad Top View

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NC – No internal connection

图 5-2. RUM Package 16-Pin WQFN With Exposed Thermal Pad Top View

表 5-1. Pin Functions

PIN			I/O	TYPE(1)	DESCRIPTION
NAME.	NO.				
	HTSSOP	WQFN			
ADV	1	15	I	D	Selects the applied lead angle by 1/8-W resistor; not to be driven externally with a source; leaving the pin open results in the longest lead angle; the lead angle is determined by the ADV pin voltage at power up.
CS	8	6	I	D	Selects current limit by 1/8-W resistor; not to be driven externally with a source; leaving the pin open results in the highest current limit; the current limit is determined by the CS pin voltage at power up.
FG	3	1	O	D	Provides motor speed feedback; open-drain output with internal pullup to V3P3; needs a pullup resistor to limit current if pullup voltage is higher than V3P3
FR	2	16	I	D	Direction control. FR = 0: U→V→W; FR = 1: U→W→V; value is determined by the FR pin state on exit of low-power mode; internal pulldown
GND	7, 16	5, 14	—	—	Digital and analog ground
NC	9	8	—	NC	No internal connection
PGND	10	7	—	P	Power ground connection for motor power
PWM	4	2	I	D	Motor speed-control input; auto detect for analog or digital mode; internal pullup to 2.2 V
RMP	6	4	I	D	Acceleration ramp-rate control; 1/8-W resistor to GND to set acceleration rate; leaving the pin open results in the slowest acceleration rate; the acceleration rate is determined by the RMP pin voltage at power up.
U	11	9	I/O	A	Motor phase U
V	12	10	I/O	A	Motor phase V
V1P8	5	3	O	P	LDO regulator for internal operation; 1-µF, 6.3-V ceramic capacitor tied to GND. Can supply a maximum of 3 mA to an extenal load.
V_{CC}	14	12	I	P	Power-supply connection; 10-µF, 25-V ceramic capacitor tied to GND
VCP	15	13	O	A	Charge-pump output; 100-nF, 10-V ceramic capacitor tied to V_{CC}
W	13	11	I/O	A	Motor phase W
Thermal pad	—	—	—	—	The exposed thermal pad must be electrically connected to the ground plane by soldering to the PCB for proper operation, and connected to the bottom side of the PCB through vias for better thermal spreading.

(1) I = Input, O = Output, I/O = Input/output, P = Power, D = Digital, A = Analog, NC = No connection

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6 Specifications

6.1 Absolute Maximum Ratings

over operating junction temperature range (unless otherwise noted)(1)

		MIN	MAX	UNIT
Pin voltage	V_{CC}	–0.3	20	V
	PWM, FR	–0.3	5.5	
	CS, RMP, ADV	–0.3	2	
	GND, PGND	–0.3	0.3	
	U, V, W	–1	20	
	V1P8	–0.3	2	
	FG	–0.3	20	
	VCP	–0.3	V_{CC} + 5.5	
Maximum junction temperature, $T_J$max		–40	150	°C
Storage temperature, T_{stg}		–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.

6.2 ESD Ratings

			VALUE	UNIT
$V_{(ESD)}$	Electrostatic discharge	Human-body model (HBM), per ANSI/ESDA/JEDEC JS-001(1)	±2000	V
		Charged-device model (CDM), per JEDEC specification JESD22-C101(2)	±500	

(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 junction temperature range (unless otherwise noted)

		MIN	NOM	MAX	UNIT
Supply voltage	V_{CC}	4.4		18	V
Voltage	U, V, W	–0.7		18	V
	PWM, FR	–0.1		5.5	
	FG	0.5		18	
	CS	–0.1		1.8	
	PGND, GND	–0.1		0.1	
	RMP, ADV	–0.1		1.8	
Current	V1P8 regulator-output current; external load	0		3	mA
Operating ambient temperature, T_A		–40		85	°C
Operating junction temperature, T_J		–40		125	°C

6.4 Thermal Information

THERMAL METRIC(1)		DRV10974		UNIT
		PWP (HTSSOP)	RUM (VQFN)	
		16 PINS	16 PINS	
$R_{\theta JA}$	Junction-to-ambient thermal resistance	37.8	34.5	°C/W
$R_{\theta JC(top)}$	Junction-to-case (top) thermal resistance	25.2	27	°C/W
$R_{\theta JB}$	Junction-to-board thermal resistance	20.7	13.3	°C/W

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THERMAL METRIC(1)		DRV10974		UNIT
		PWP (HTSSOP)	RUM (VQFN)	
		16 PINS	16 PINS	
ψ_{JT}	Junction-to-top characterization parameter	0.7	0.3	°C/W
ψ_{JB}	Junction-to-board characterization parameter	20.5	13.3	°C/W
$R_{\theta JC(bot)}$	Junction-to-case (bottom) thermal resistance	1.9	4	°C/W

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

6.5 Electrical Characteristics

over operating junction temperature range (unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
SUPPLY CURRENT						
I_{CC}	Supply current	T_A = 25°C, V_{CC} = 12 V, no motor load		5	7	mA
$I_{CC(LP)}$	Low power mode	T_A = 25°C, V_{CC} = 12 V		380		µA
UVLO						
$V_{(UVLO_F)}$	V_{CC} UVLO falling		4.2	4.3	4.4	V
$V_{(UVLO_R)}$	V_{CC} UVLO rising		4.5	4.7	4.85	V
$V_{hys(UVLO)}$	V_{CC} UVLO hysteresis			400		mV
$V_{VCP(UVLO_F)}$	Charge pump UVLO falling	V_{VCP} – V_{CC}	3.35	3.7	4.05	V
$V_{VCP(UVLO_R)}$	Charge pump UVLO rising	V_{VCP} – V_{CC}	3.65	4.0	4.37	V
$V_{hys(VCP)}$	Charge pump UVLO hysteresis			330		mV
$V_{(V1P8_F)}$	V1P8 UVLO falling		1.25	1.4	1.55	V
$V_{(V1P8_R)}$	V1P8 UVLO rising		1.35	1.5	1.65	V
$V_{hys(V1P8)}$	V1P8 UVLO hysteresis			100		mV
VOLTAGE REGULATORS						
V_{V1P8}	V1P8 voltage	T_A = 25°C, $C_{(V1P8)}$ = 1 µF	1.7	1.8	1.9	V
I_{V1P8}	Maximum external load from V1P8	T_A = 25°C, $C_{(V1P8)}$ = 1 µF			3	mA
INTEGRATED MOSFET						
$r_{ds(on)_HS}$	High-side FET on-resistance	T_A = 25°C, V_{CC} = 12 V, I_O = 100 mA		0.375	0.425	Ω
$r_{ds(on)_LS}$	Low-side FET on-resistance	T_A = 25°C, V_{CC} = 12 V, I_O = 100 mA		0.375	0.425	Ω
PHASE DRIVER						
SL_{PH_LH}	Phase slew rate switching low to high	SlewRate = 0; measure 20% to 80%; VCC = 12 V; phase current > 20 mA	70	120	170	V/µs
SL_{PH_HL}	Phase slew rate switching high to low	SlewRate = 0; measure 80% to 20%; VCC = 12 V; phase current > 20 mA	70	120	170	V/µs
f_{PWM_OUT}	Phase output PWM frequency			25		kHz
t_{dead_time}	Recommended dead time		440			ns
CHARGE PUMP						
V_{VCP}	VCP voltage	V_{CC} = 4.4 V to 18 V	V_{CC} + 4	V_{CC} + 5	V_{CC} + 5.5	V
CURRENT LIMIT						

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over operating junction temperature range (unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
I_{LIMIT}	Current-limit threshold	V_{CC} = 12 V, $R_{(CS)}$ = 7.32 kΩ ±1%		0.2		A
		V_{CC} = 12 V, $R_{(CS)}$ = 16.2 kΩ ±1%		0.4		
		V_{CC} = 12 V, $R_{(CS)}$ = 25.5 kΩ ±1%		0.6		
		V_{CC} = 12 V, $R_{(CS)}$ = 38.3 kΩ ±1%		0.8		
		V_{CC} = 12 V, $R_{(CS)}$ = 54.9 kΩ ±1%		1		
		V_{CC} = 12 V, $R_{(CS)}$ = 80.6 kΩ ±1%		1.2		
		V_{CC} = 12 V, $R_{(CS)}$ = 115 kΩ ±1%		1.4		
		V_{CC} = 12 V, $R_{(CS)}$ = 182 kΩ ±1%, open loop and closed loop current limit		1.6		
		V_{CC} = 12 V, $R_{(CS)}$ = 182 kΩ ±1%, align current limit		1.5		
RANGE OF MOTORS SUPPORTED						
R_m	Motor resistance measurement	Phase to center tap	1		20	Ω
K_t	Motor BEMF constant measurement	Phase to center tap	5		150	mV/Hz
t_{ALIGN}	Motor align time			0.67		s

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over operating junction temperature range (unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
PWM - DIGITAL MODE						
$V_{IH(DIG)}$	PWM input high voltage		2.2			V
$V_{IL(DIG)}$	PWM input low voltage				0.6	V
f_{PWM}	PWM input frequency		0.1		100	kHz
DC_{MAX}	Maximum output PWM duty cycle	V_{VCC} < 14 V		100 %		
		$V_{VCC} \geqslant$ 14 V		[(14 / V_{VCC}) × 100] %		
DC_{MIN}	Minimum output PWM duty cycle device needs to guarantee (irrespective of input PWM DC)	Lower duty cycle from 15% down		15%		
DC_{ON_MIN}	Minimum input duty cycle that device uses to drive motor			1.5 %		
DC_{STEP}	Duty cycle step size/resolution			0.2 %		
$V_{IH(AUTO)}$	PWM input high voltage for auto detection		1.62	1.695	1.77	V
$V_{IL(AUTO)}$	PWM input low voltage for exiting PWM mode		1.315	1.39	1.465	V
$R_{pu(PWM)}$	Internal PWM pullup resistor to V3P3			120		kΩ
LOW-POWER MODE						
$t_{(EX_LPM)}$	PWM pulse duration to exit low-power mode	PWM > $V_{IH(DIG)}$	1			µs
$V_{(EX_LPM)}$	PWM voltage to exit low-power mode		1.5			V
$t_{(EN_LPM)}$	PWM low time to enter low-power mode	PWM < $V_{IL(DIG)}$,motor stationary	25			ms
PWM - ANALOG MODE						
V_{ANA_FS}	Analog full-speed voltage			1.8		V
V_{ANA_ZS}	Analog zero-speed voltage		20			mV
$R_{out(PWM)}$	External analog driver output impedance				50	kΩ
t_{SAM}	Analog speed sample period			320		µs
V_{ANA_RES}	Analog voltage resolution			3.5		mV
DIGITAL I/O (FG OUTPUT, FR INPUT)						
f_{FG_MIN}	Minimum FG output frequency during coast			10		Hz
$V_{IH(FR)}$	Input high		2.2			V
$V_{IL(FR)}$	Input low				0.6	V
$I_{(FG_SINK)}$	Output sink current, FG	V_O = 0.3 V	5			mA
$R_{pu(FG)}$	Internal FG pullup resistor to 3.3V			20		kΩ
$R_{pd(FR)}$	Internal FR pulldown resistor to ground			100		kΩ
LOCK DETECTION RELEASE TIME						
$t_{(LOCK_OFF)}$	Lock release time			5		s
OVERCURRENT PROTECTION						
I_{OC_limit}	Overcurrent protection	T_A = 25°C	2.5			A
t_{OC_retry}	Overcurrent protection retry time			5		s
THERMAL SHUTDOWN						
T_{SD}	Shutdown temperature threshold		140	150		°C
$T_{SD(hys)}$	Shutdown temperature threshold hysteresis			15		°C

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over operating junction temperature range (unless otherwise noted)

PARAMETER		TEST CONDITIONS	MIN	TYP	MAX	UNIT
LEAD ANGLE						
ADV_{select}	Lead angle selection	V_{CC} = 12 V, $R_{(ADV)}$ = 10.7 kΩ ±1%		10		µs
		V_{CC} = 12 V, $R_{(ADV)}$ = 14.3 kΩ ±1%		25		
		V_{CC} = 12 V, $R_{(ADV)}$ = 17.8 kΩ ±1%		50		
		V_{CC} = 12 V, $R_{(ADV)}$ = 22.1 kΩ ±1%		100		
		V_{CC} = 12 V, $R_{(ADV)}$ = 28 kΩ ±1%		150		
		V_{CC} = 12 V, $R_{(ADV)}$ = 34 kΩ ±1%		200		
		V_{CC} = 12 V, $R_{(ADV)}$ = 41.2 kΩ ±1%		250		
		V_{CC} = 12 V, $R_{(ADV)}$ = 49.9 kΩ ±1%		300		
		V_{CC} = 12 V, $R_{(ADV)}$ = 59 kΩ ±1%		400		
		V_{CC} = 12 V, $R_{(ADV)}$ = 71.5 kΩ ±1%		500		
		V_{CC} = 12 V, $R_{(ADV)}$ = 86.6 kΩ ±1%		600		
		V_{CC} = 12 V, $R_{(ADV)}$ = 105 kΩ ±1%		700		
		V_{CC} = 12 V, $R_{(ADV)}$ = 124 kΩ ±1%		800		
		V_{CC} = 12 V, $R_{(ADV)}$ = 150 kΩ ±1%		900		
		V_{CC} = 12 V, $R_{(ADV)}$ = 182 kΩ ±1%		1000		
ACCELERATION RAMP RATE						
RMP_{select}	RMP selection for acceleration profile	V_{CC} = 12 V, $R_{(RMP)}$ = 7.32 kΩ ±1%		0		code
		V_{CC} = 12 V, $R_{(RMP)}$ = 10.7 kΩ ±1%		1		
		V_{CC} = 12 V, $R_{(RMP)}$ = 14.3 kΩ ±1%		2		
		V_{CC} = 12 V, $R_{(RMP)}$ = 17.8 kΩ ±1%		3		
		V_{CC} = 12 V, $R_{(RMP)}$ = 22.1 kΩ ±1%		4		
		V_{CC} = 12 V, $R_{(RMP)}$ = 28 kΩ ±1%		5		
		V_{CC} = 12 V, $R_{(RMP)}$ = 34 kΩ ±1%		6		
		V_{CC} = 12 V, $R_{(RMP)}$ = 41.2 kΩ ±1%		7		
		V_{CC} = 12 V, $R_{(RMP)}$ = 49.9 kΩ ±1%		8		
		V_{CC} = 12 V, $R_{(RMP)}$ = 59 kΩ ±1%		9		
		V_{CC} = 12 V, $R_{(RMP)}$ = 71.5 kΩ ±1%		10		
		V_{CC} = 12 V, $R_{(RMP)}$ = 86.6 kΩ ±1%		11		
		V_{CC} = 12 V, $R_{(RMP)}$ = 105 kΩ ±1%		12		
		V_{CC} = 12 V, $R_{(RMP)}$ = 124 kΩ ±1%		13		
		V_{CC} = 12 V, $R_{(RMP)}$ = 150 kΩ ±1%		14		
		V_{CC} = 12 V, $R_{(RMP)}$ = 182 kΩ ±1%		15		

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6.6 Typical Characteristics

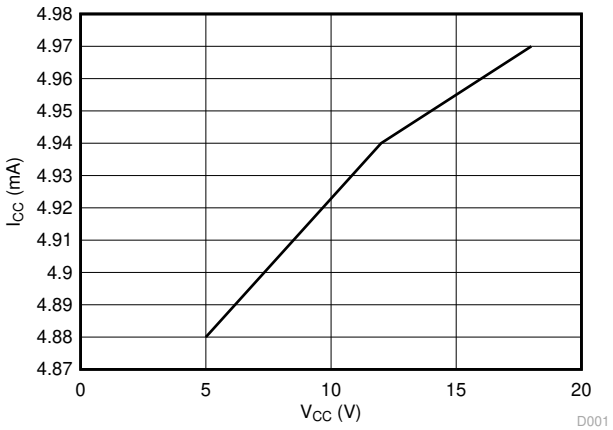
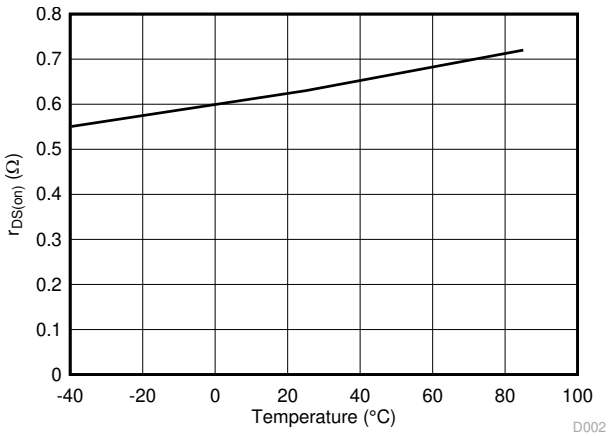


图 6-1. Supply Current vs Power Supply



V_{CC} = 12 V

图 6-2. $r_{DS(on)}$ vs Temperature When V_{CC} = 12 V

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7 Detailed Description

7.1 Overview

The DRV10974 device is a three-phase sensorless motor driver with integrated power MOSFETs, which provide drive-current capability up to 1 A continuous (rms). The device is specifically designed for low-noise, low external-component count, 12-V motor-drive applications. The 180° commutation requires no configuration beyond setting the peak current, the lead angle, and the acceleration profile, each of which is configured by an external resistor.

The 180° sensorless-control scheme provides sinusoidal output voltages to the motor phases as shown in 图 7-1.

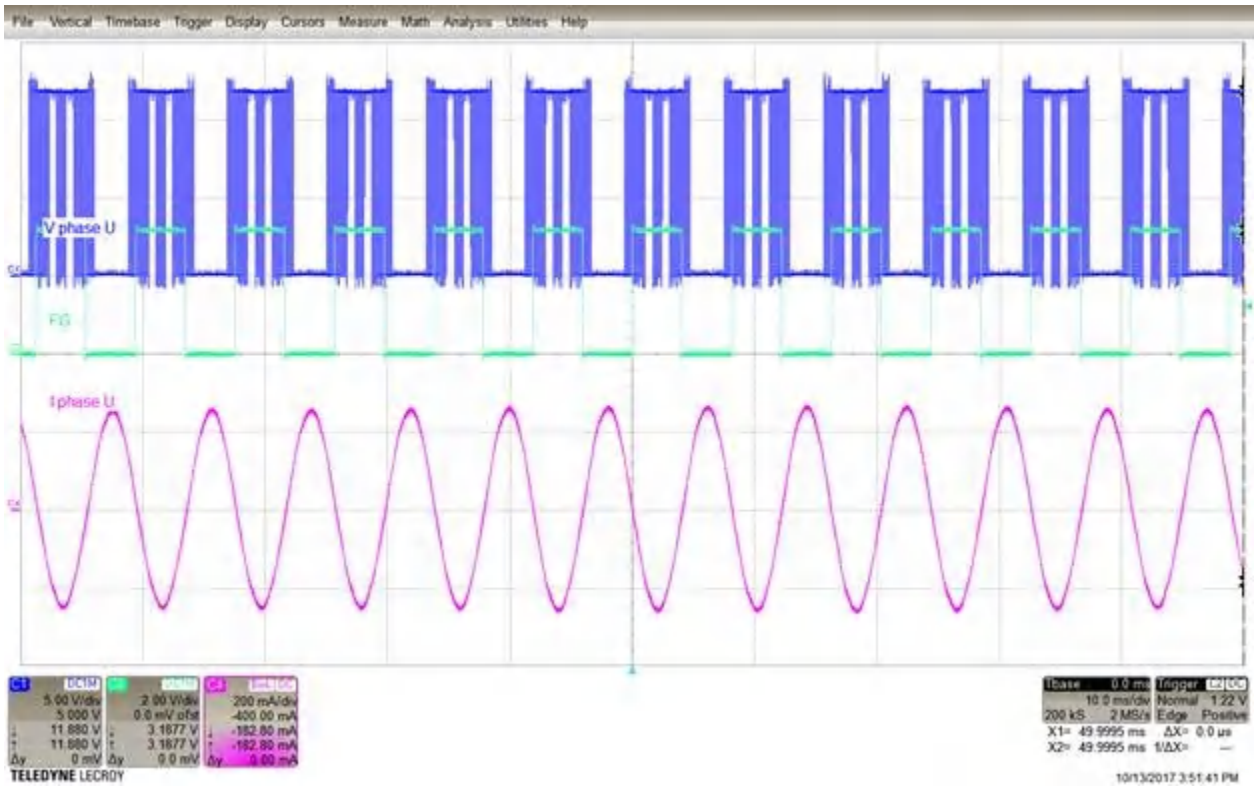


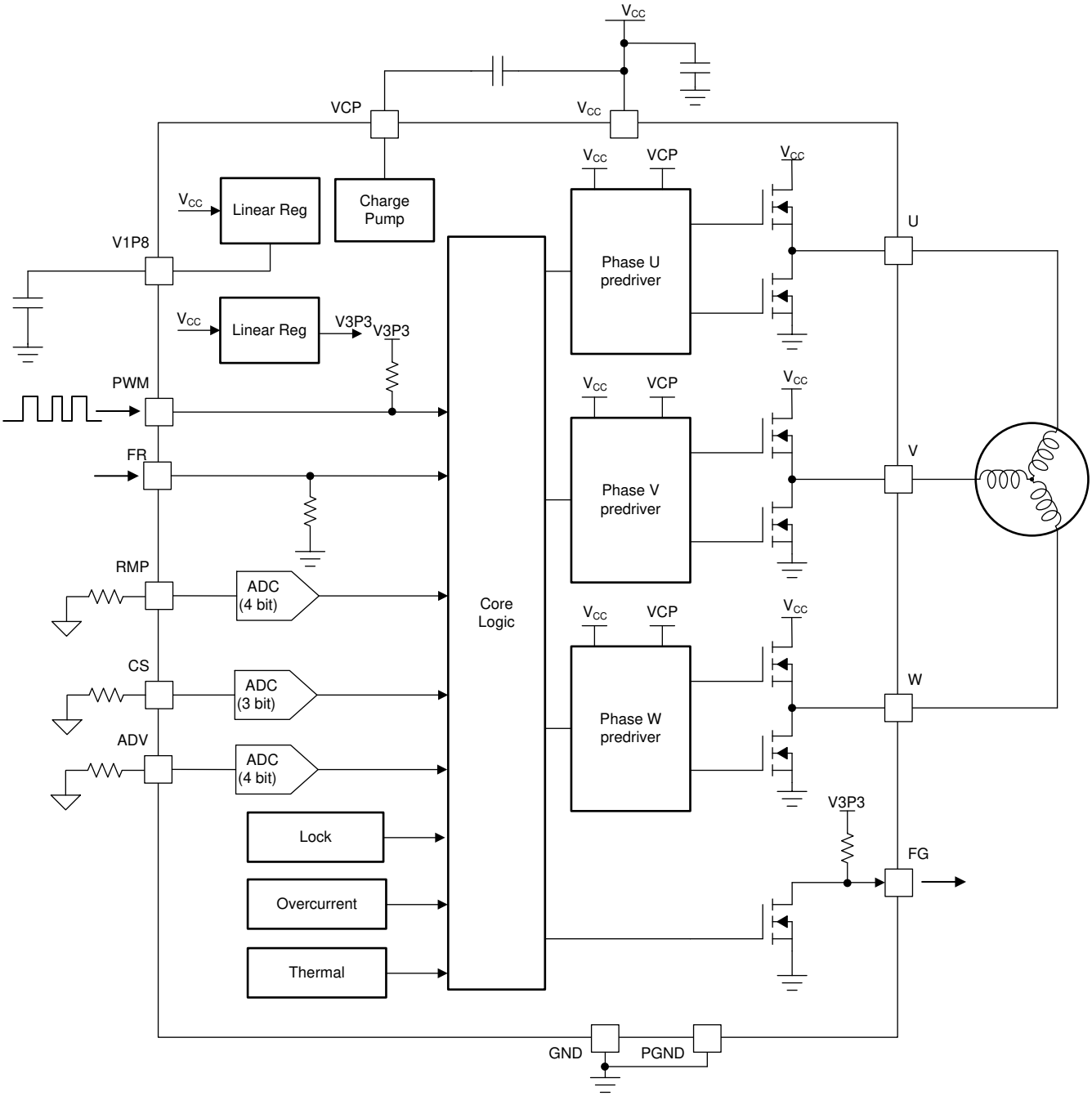
图 7-1. 180° Sensorless-Control Scheme

Interfacing to the DRV10974 device is simple and intuitive. The DRV10974 device receives a PWM input that it uses to control the speed of the motor. The duty cycle of the PWM input is used to determine the magnitude of the voltage applied to the motor. The resulting motor speed can be monitored on the FG pin. The FR pin is used to control the direction of rotation for the motor. The acceleration ramp rate is controlled by the RMP pin. The current limit is controlled by a resistor on the CS pin. The lead angle is controlled by a resistor on the ADV pin. When the motor is not spinning, a low-power mode turns off unused circuits to conserve power.

The DRV10974 device features extensive protection and fault-detect mechanisms to ensure reliable operation. The device provides overcurrent protection without the requirement for an external current-sense resistor. Rotor-lock detect uses several methods to reliably determine when the rotor stops spinning unexpectedly. The device provides additional protection for undervoltage lockout (UVLO), for thermal shutdown, and for phase short circuit (phase to phase, phase to ground, phase to supply).

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7.2 Functional Block Diagram



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7.3 Feature Description

7.3.1 Speed Input and Control

The DRV10974 device has a three-phase 25-kHz PWM (f_{PWM_OUT}) output that has an average value of sinusoidal waveforms from phase to phase as shown in 图 7-2. When any phase is measured with reference to ground, the waveform observed is a PWM-encoded sinusoid coupled with third-order harmonics as shown in 图 7-3. This encoding scheme simplifies the driver requirements because one phase output is always equal to zero.

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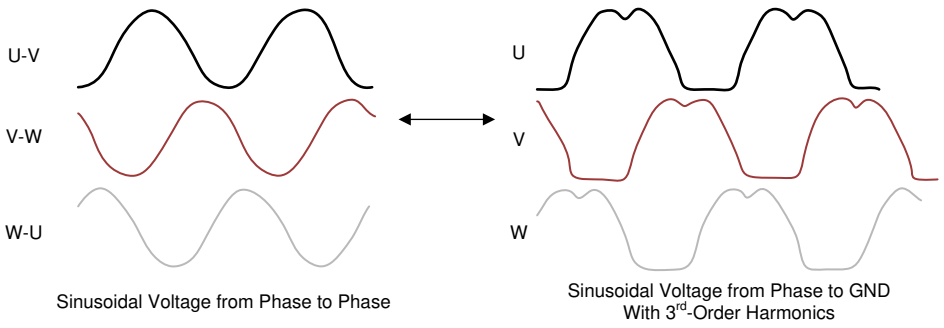


图 7-2. Sinusoidal Voltage

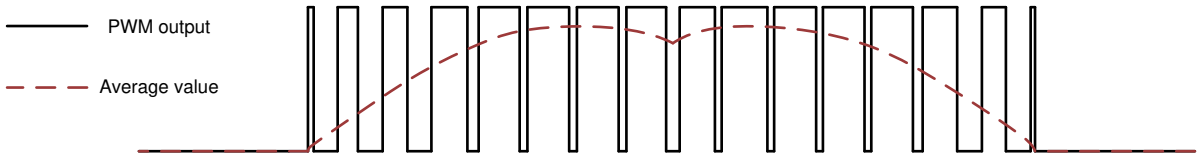


图 7-3. PWM Encoded Phase Output and the Average Value

The output amplitude is determined by the supply voltage (V_{CC}) and the PWM-commanded duty cycle (PWM) as calculated in 方程式 1 and shown in 图 7-4. The maximum amplitude is applied when the commanded PWM duty cycle is slightly less than 100% in order to keep the 25-kHz PWM rate (f_{PWM_OUT}).

$$V_{ph_{pk}} = PWM_{dc} \times V_{CC} \quad (1)$$

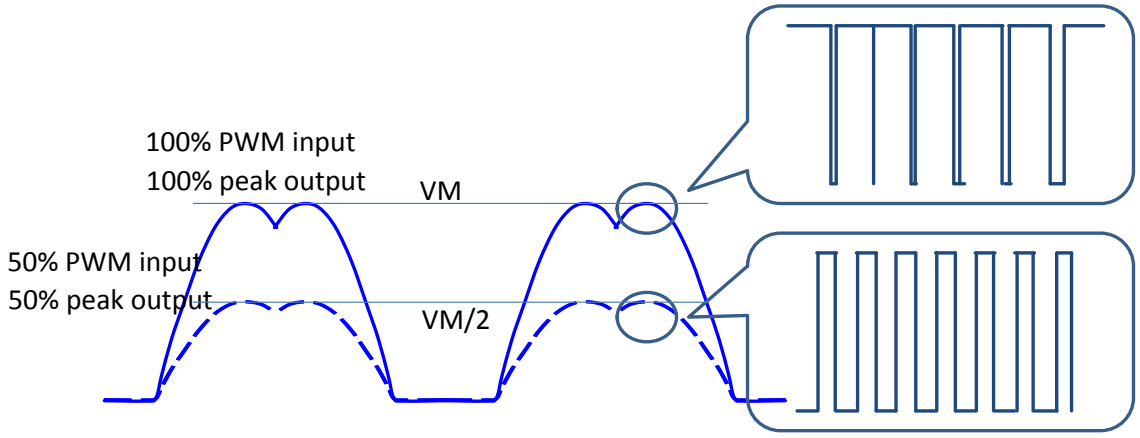


图 7-4. Output Voltage Amplitude Adjustment

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. The PWM pin can be driven by either a digital duty cycle or an analog voltage.

The duty cycle of the PWM input (PWM) is passed through a low-pass filter that ramps from 0% to 100% duty cycle in 120 ms. The control resolution is approximately 0.2% (DC_{STEP}). The signal path from PWM input to PWM motor is shown in 图 7-5.

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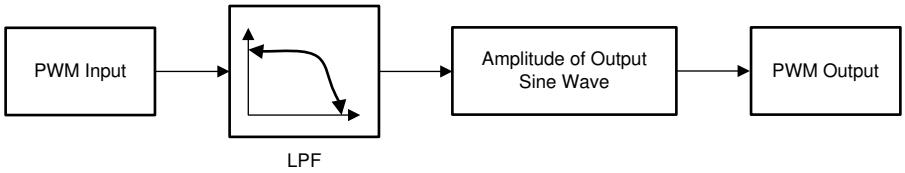


图 7-5. PWM Command Input Control Diagram

The output peak amplitude is described by 方程式 1 when PWM_{dc} > 15% (the minimum-operation duty cycle). When the PWM-commanded duty cycle is lower than the minimum-operation duty cycle and higher than 1.5% (DC_{ON_MIN}), the output is controlled the by the minimum-operation duty cycle (DC_{MIN}). This is shown in 图 7-6 for analog input, and for duty cycles greater than 1.5% (DC_{ON_MIN}) for digital input. If the supply voltage (V_{VCC}) > 14 V, the maximum PWM_{dc} is limited to 14 V / V_{VCC}.

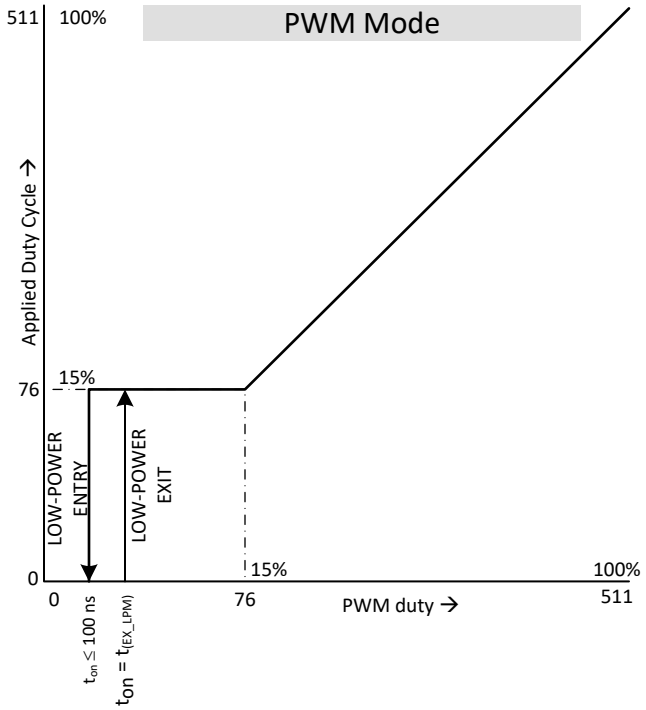


图 7-6. PWM-Mode Speed-Control Transfer Function

When the PWM pin is driven with an analog voltage, the output peak amplitude depends on the supply voltage, the analog voltage on the PWM pin (V_{ANA}), and the voltage of V1P8 (V_{V1P8}). This is shown in 方程式 2:

$$V_{ph_{pk}} = \frac{V_{ANA}}{V_{1P8}} \times V_{CC} \tag{2}$$

Note the output peak amplitude is described by 方程式 2 when the V_{ANA} > 0.27 V or 15% of 1.8 V. This is the equivalent of the minimum-operation duty cycle percentage of 15% (DC_{MIN}). When the analog voltage on the PWM pin is lower than the minimum-operation duty-cycle percentage but higher than the zero-speed analog voltage (V_{ANA_ZS}), the output is controlled by the minimum-operation duty cycle. When the analog voltage on the PWM pin is below zero-speed analog voltage, the DRV10974 enters low-power mode. This is shown in 图 7-7.

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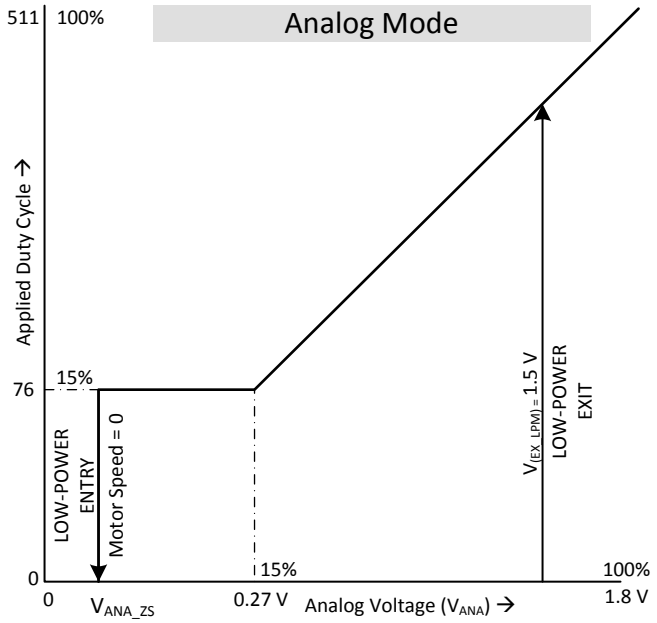


图 7-7. Analog-Mode Speed-Control Transfer Function

7.3.2 Motor Direction Change

The DRV10974 device 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 defined as follows:

FR = 0	U→V→W
FR = 1	U→W→V

7.3.3 Motor-Frequency Feedback (FG)

During operation of the DRV10974 device, the FG pin provides an indication of the speed of the motor. The FG pin toggles at a rate of one time during an electrical cycle. Using this information and the number of pole pairs in the motor, use 方程式 3 to calculate the mechanical speed of the motor.

$$RPM = \frac{f_{(FG)} \times 60}{pole_pairs} \tag{3}$$

During open-loop acceleration the FG pin indicates the frequency of the signal that is driving the motor. The lock condition of the motor is unknown during open-loop acceleration and therefore the FG pin could toggle during this time even though the motor is not moving.

During spin down, the DRV10974 device continues to provide speed feedback on the FG pin. The DRV10974 device provides the output of the U-phase comparator on the FG pin until the motor speed drops below 10 Hz (f_{FG_MIN}). When the motor speed falls below 10 Hz, the device enters into the low-power mode and the FG output is held at a logic high.

7.3.4 Lock Detection

When the motor is locked by some external condition, the DRV10974 device detects the lock condition and acts to protect the motor and the device. The lock condition must be properly detected whether the condition occurs as a result of a slowly increasing load or a sudden shock.

The DRV10974 device reacts to the lock condition by stopping the motor drive. To stop driving the motor, the phase outputs are placed into a high-impedance state. After successfully transitioning into a high-impedance

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state as the result of a lock condition, the DRV10974 device attempts to restart the motor after $t_{(LOCK_OFF)}$ seconds.

The DRV10974 device has a comprehensive lock-detect function that includes six different lock-detect schemes. Each of these schemes detects a particular condition of the lock as shown in 图 7-8.

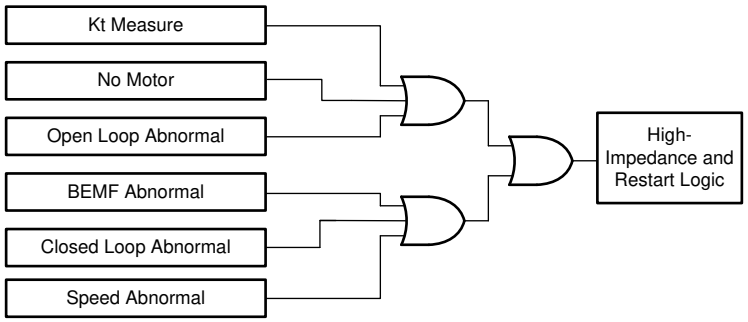


图 7-8. Lock Detect

The following sections describe each lock-detect scheme.

7.3.4.1 Lock Kt Measure

The DRV10974 device measures the actual Kt of the motor when transitioning from open-loop acceleration to closed-loop acceleration. If the measured Kt is less than 200 mV, the device indicates that the handoff Kt level was not properly reached and the lock is triggered.

7.3.4.2 Lock No Motor

The phase-U current is checked at the end of the align state. If the phase-U current is not greater than 50 mA, then the motor is not connected. This condition is reported as a lock condition.

7.3.4.3 Lock Open Loop Abnormal

Transition from open loop to closed loop is based on the estimated value of BEMF. If during open-loop acceleration the electrical commutation rate exceeds 200 Hz without reaching the handoff threshold, this lock is triggered.

7.3.4.4 Lock BEMF Abnormal

For any specific motor, the integrated value of BEMF during half of an electrical cycle is a constant as shown by the shaded gray area in 图 7-9. This value is constant regardless of whether the motor runs fast or slow. The DRV10974 device monitors this value and uses it as a criterion to determine if the motor is in a lock condition.

The DRV10974 device 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. Then, during closed-loop motor operation the Ktc (Kt calculated) value is continuously updated. Finally, the Ktc value is checked to see if it is within the range between ½ Kt and 2Kt. If the Ktc value goes beyond the acceptable range, a lock condition is triggered as shown in 图 7-10. Note, there is a blanking period of 0.3 s after the transition from open loop to closed loop where the abnormal BEMF lock is momentarily disabled. The device uses this time to finalize the Kt value that Ktc is compared against.

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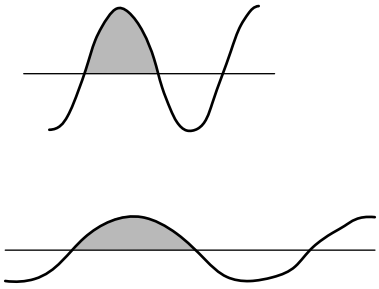


图 7-9. BEMF Integration

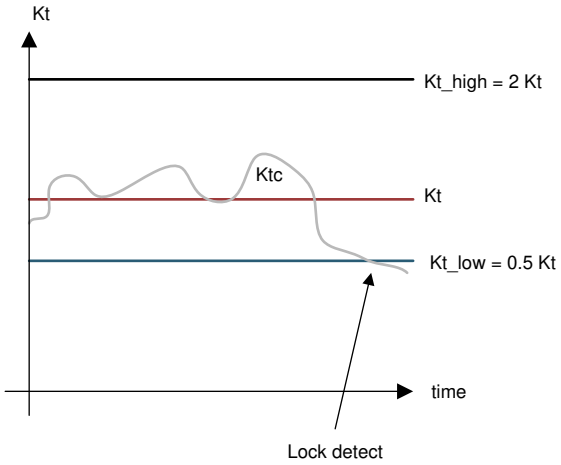


图 7-10. Abnormal Kt Lock Detect

7.3.4.5 Lock Closed Loop Abnormal

This lock condition is active when the DRV10974 device is operating in the closed-loop mode. The motor is indicated as not moving when the closed-loop commutation period becomes lower than half the previous commutation period. This condition triggers the closed-loop abnormal-lock condition.

7.3.4.6 Lock Speed Abnormal

If the motor is in normal operation, the motor BEMF is always less than the voltage applied to the phase. The sensorless-control algorithm of the DRV10974 device is continuously updating the value of the motor BEMF based on the speed of the motor and the motor Kt as shown in 图 7-11. If the calculated value for motor BEMF is 1.5 times higher than the applied voltage on phase U (V_U) for an electrical period then an error is present in the system, and 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 is triggered.

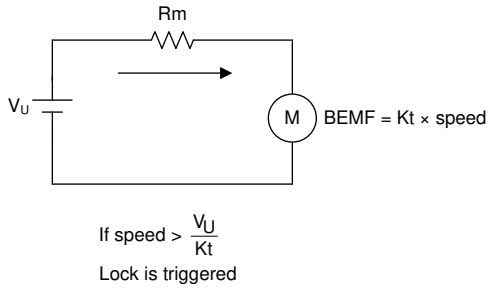


图 7-11. BEMF Monitoring

7.3.5 Soft Current-Limit

The current-limit function provides active protection for preventing damage as a result of high current. The soft current-limit does not use direct-current measurement for protection, but rather, uses the measured motor resistance (Rm) and motor velocity constant (Kt) to limit the voltage applied to the phase (U) such that the current does not exceed the limit value ($I_{(LIMIT)}$). The soft current-limit scheme is shown in 图 7-12 based on the calculation in 方程式 4.

The soft current-limit is only active when in normal closed-loop mode and does not result in a fault condition nor does it result in the motor being stopped. The soft current-limit is typically useful for limiting the current that results from heavy loading during motor acceleration. The $I_{(LIMIT)}$ current is configured by an external resistor ($R_{(CS)}$) as shown in 表 7-1.

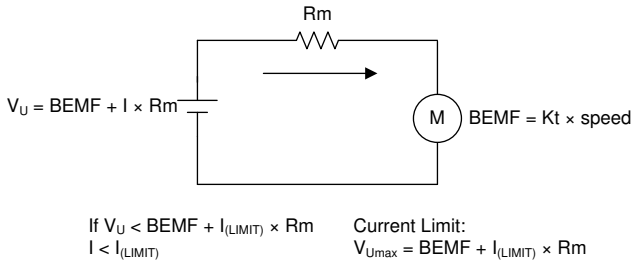


图 7-12. Current Limit

Use 方程式 4 to calculate the $I_{(LIMIT)}$ value.

$$I_{(LIMIT)} = \frac{V_{(U)LIMIT} - Speed \times Kt}{Rm} \tag{4}$$

表 7-1 can be used to determine the $I_{(LIMIT)}$ value.

表 7-1. Soft Current-Limit Selections

$R_{(CS)}$ [kΩ](1)	$I_{(LIMIT)}$ [mA]
7.32	200
16.2	400
25.5	600
38.3	800
54.9	1000
80.6	1200
115	1400
182	1600 (1500 during align)

(1) All resistors are ±1 %.

备注

The soft current-limit is not correct if the motor is out of phase with the commutation control logic (locked rotor). The soft current-limit is not effective under this condition.

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 $I_{(OC_LIMIT)}$. The DRV10974 device goes through the initialization sequence and attempts to restart the motor after the short-

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circuit condition is improved. This function is intended to protect the device and the motor from catastrophic failure when subjected to a short-circuit condition.

7.3.7 Overtemperature Protection

The DRV10974 device has a thermal shutdown function which disables the motor operation when the device junction temperature has exceeded the T_{SD} temperature. Motor operation resumes when the junction temperature becomes lower than T_{SD} – $T_{SD(hys)}$.

7.3.8 Undervoltage Protection

The DRV10974 device has an undervoltage lockout feature, which prevents motor operation whenever the supply voltage (V_{CC}) becomes too low. Upon power up, the DRV10974 device operates when V_{CC} rises above $V_{(UVLO_F)}$ + $V_{hys(UVLO)}$. The DRV10974 device continues to operate until V_{CC} falls below $V_{(UVLO_F)}$.

7.4 Device Functional Modes

7.4.1 Spin-Up Settings

7.4.1.1 Motor Start

The DRV10974 device starts the motor using a procedure which is shown in 图 7-13.

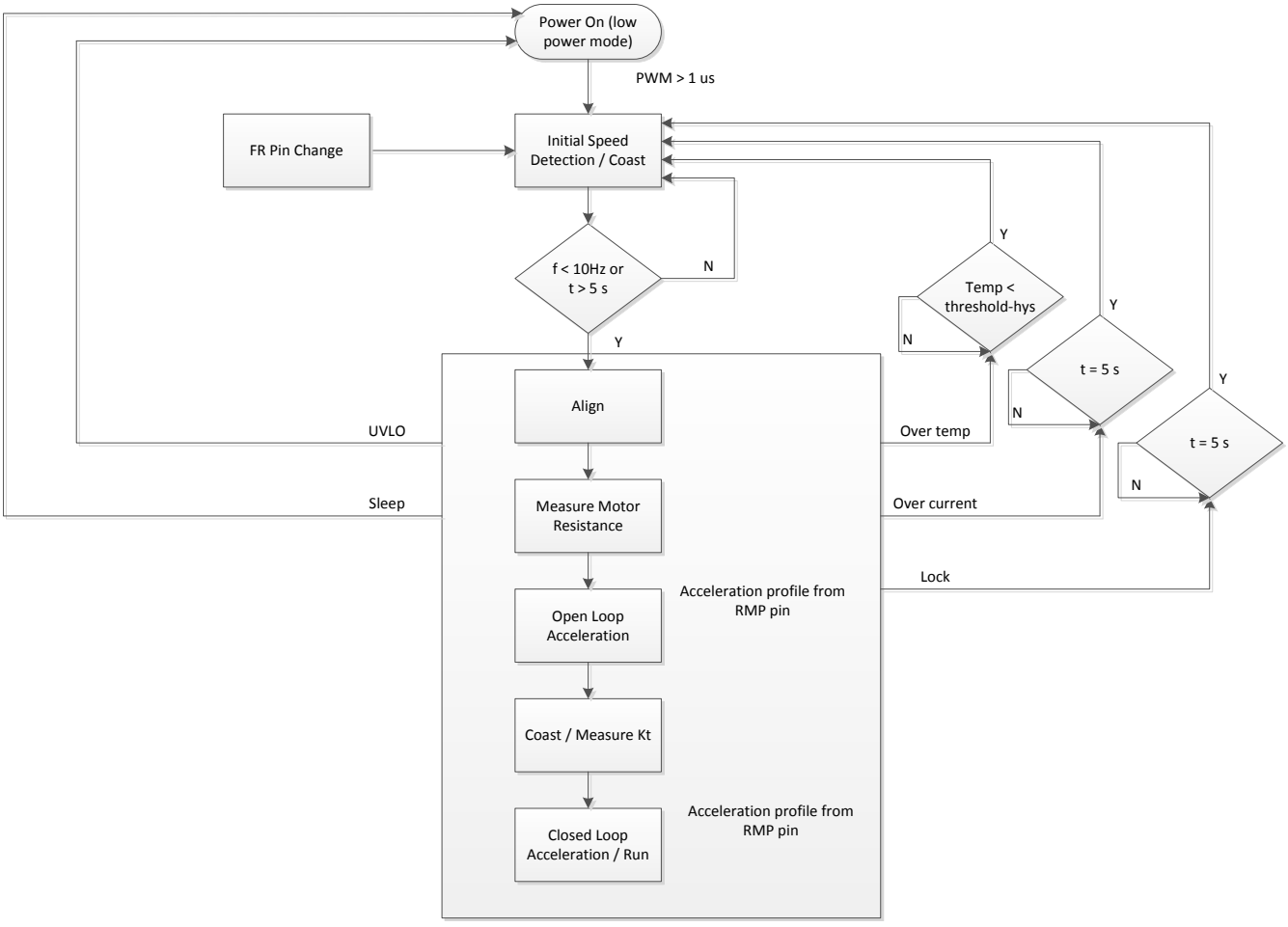


图 7-13. DRV10974 Initialization and Motor Start-Up Sequence

7.4.1.2 Initial Speed Detect

Every time the DRV10974 device exits low-power mode, it determines if the motor is spinning using a function called initial speed detect. If the frequency on the FG pin is less than 10 Hz, the motor is considered stationary. If

the frequency is greater than 10 Hz the motor is decelerated until it is below 10 Hz or a 5-second time-out has occurred.

7.4.1.3 Align

To align the rotor to the commutation logic, the DRV10974 device applies a current equivalent to the closed-loop run current to phase U by driving phases V and W equally. This condition is maintained for a maximum of 0.67 s (t_{ALIGN}). To avoid a sudden change in current that could result in undesirable acoustics, the voltage applied to the motor is changed gradually to obtain a current change of 12 A/s.

7.4.2 Open-Loop Acceleration

After the motor is confirmed to be stationary and after completing the motor initialization, the DRV10974 device begins to accelerate the motor. This acceleration is accomplished by applying a voltage to the motor at the appropriate drive state and increasing the rate of commutation without regard to the actual position of the motor (referred to as *open-loop operation*). The function of the open-loop operation is to drive the motor to a minimum speed so that the motor generates sufficient BEMF to allow the commutation control logic to drive the motor accurately.

The motor start-up profile can be configured using an external resistor to set the acceleration profile before transitioning to closed-loop operation. 图 7-14 shows this acceleration profile. During closed-loop operation the RMP pin controls the closed-loop acceleration and deceleration. 表 7-2 lists the selectable acceleration parameters.

表 7-2. Acceleration Profile Settings

RMP SELECTION	R_{RMP} [kΩ](1)	Accel2 [Hz/s^2]	Accel1 [Hz/s]	CLOSED-LOOP-ACCELERATION TRANSITION TIME [s](2)	CLOSED-LOOP-DECELERATION TRANSITION TIME [s](3)
0	7.32	0.22	4.6	2.7	44
1	10.7	1.65	9.2	2.7	22
2	14.3	1.65	15	1	22
3	17.8	3.3	25	1	11
4	22.1	7	25	0.2	44
5	28	7	35	0.2	22
6	34	14	50	0.2	22
7	41.2	27	75	0.2	11
8	49.9	27	75	5.4	11
9	59	14	50	8	22
10	71.5	7	35	11	22
11	86.6	7	25	22	44
12	105	3.3	25	5.4	11
13	124	1.65	15	8	22
14	150	1.65	9.2	11	22
15	182	0.22	4.6	22	44

(1) All resistors are ±1%
(2) Time to transition from 0 to 100% duty cycle.
(3) Time to transition from 100% to 0% duty cycle.

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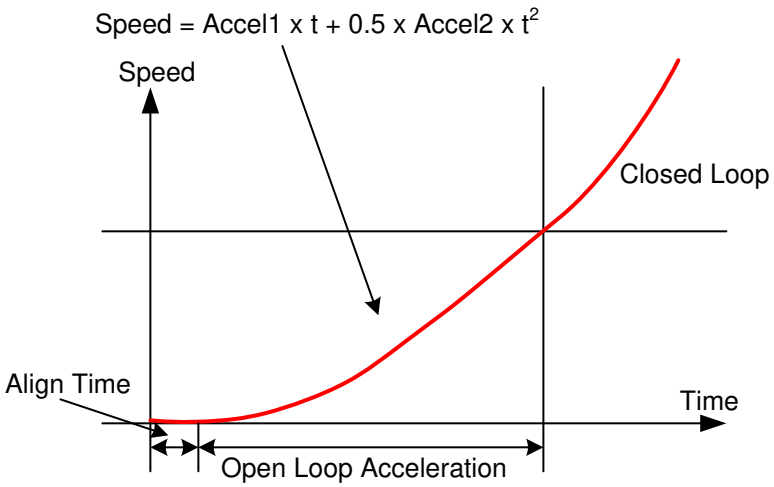


图 7-14. Start-Up Profile

7.4.3 Start-Up Current Sensing

The start-up peak current is controlled by the current-sense limit resistor, $R_{(CS)}$. The start current is set by selecting the $R_{(CS)}$ resistor based on 表 7-3. The current should be selected to allow the motor to accelerate reliably to the handoff threshold. Heavier loads may require a higher current setting, but the rate of acceleration is limited by the selected resistor, $R_{(RMP)}$.

表 7-3. Start-Up Current Limit

$R_{(CS)}$ [kΩ](1)	$I_{(LIMIT)}$ [mA]
7.32	200
16.2	400
25.5	600
38.3	800
54.9	1000
80.6	1200
115	1400
182	1600 (1500 for align)

(1) All resistors are ±1%.

7.4.4 Closed Loop

When the motor accelerates to the target BEMF threshold, commutation control transitions from open-loop mode to closed-loop mode. During this transition, the motor is allowed to coast for one electrical cycle to measure Kt. The commutation drive sequence and timing are determined by the internal control algorithm, and the applied voltage is determined by the PWM-commanded duty-cycle input. The closed-loop acceleration and deceleration values are provided in 表 7-2.

7.4.5 Control Advance Angle

To achieve the best efficiency, the drive state of the motor must be controlled such that the current is aligned with the BEMF voltage of the motor. 图 7-15 illustrates the operation when the drive angle has been optimized. For complete flexibility, the DRV10974 device offers a wide range of fixed lead times. The options for lead time are controlled by a resistor on the ADV pin. The values available are shown in 表 7-4.

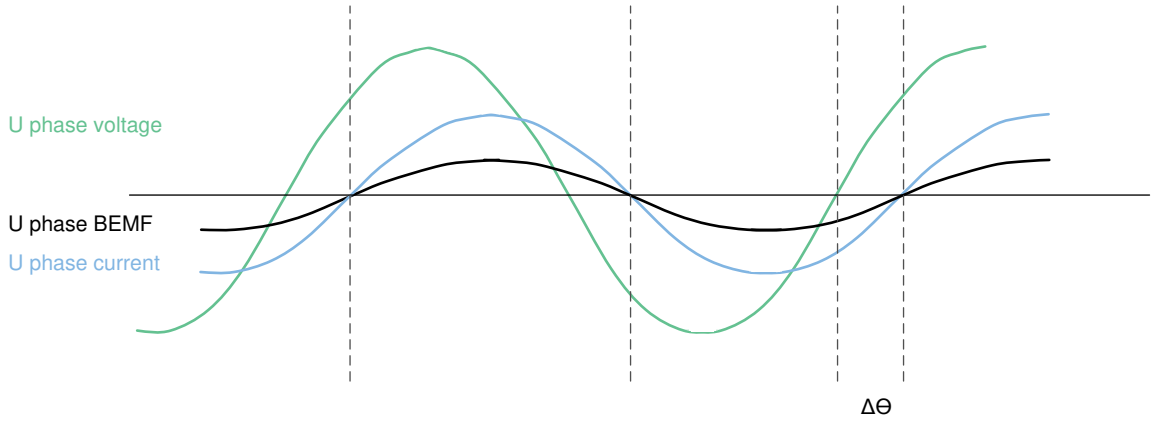


图 7-15. Drive Angle Adjustment

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表 7-4. Lead Time Selection

R_{ADV} [kΩ](1)	LEAD TIME [µs]
10.7	10
14.3	25
17.8	50
22.1	100
28	150
34	200
41.2	250
49.9	300
59	400
71.5	500
86.6	600
105	700
124	800
150	900
182	1000

(1) All resistors are ±1%.

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8 Application and Implementation

备注

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

The DRV10974 device is used in sensorless 3-phase BLDC motor control. The driver provides a high-performance, high-reliability, flexible, and simple solution for appliance fan, pump, and blower applications. The following design shows a common application of the DRV10974 device.

8.2 Typical Application

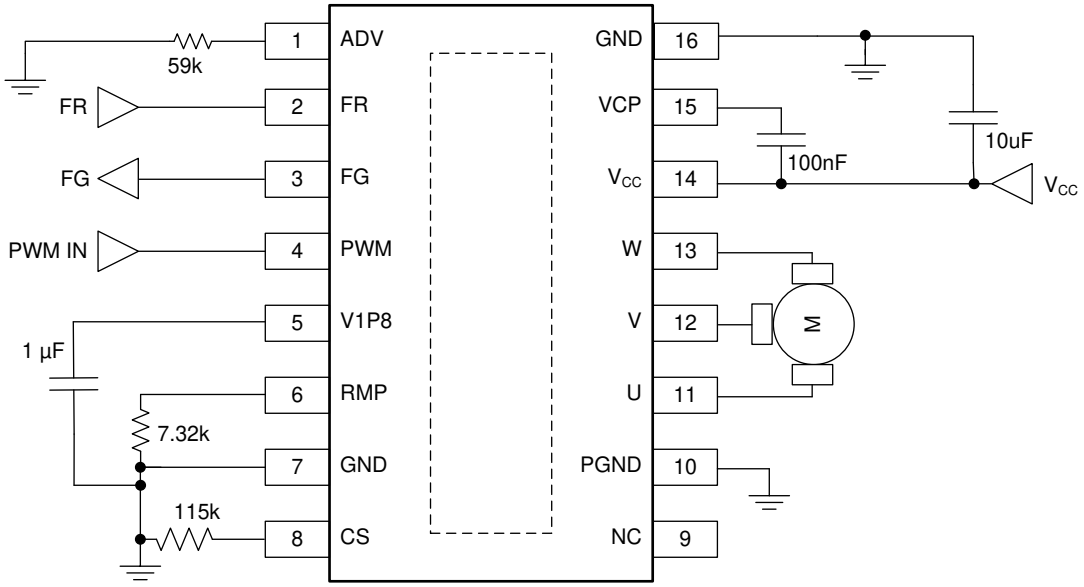


图 8-1. Typical Application Schematic

表 8-1. Recommended External Components

NODE 1	NODE 2	COMPONENT
V_{CC}	GND	10- µ F, 25-V ceramic capacitor tied from V_{CC} to ground
VCP	V_{CC}	100-nF, 10-V ceramic capacitor tied from VCP to V_{CC}
V1P8	GND	1- µ F ±30%, 6.3-V ceramic capacitor tied from V1P8 to ground
RMP	GND	1%, 1/8 watt resistor tied from RMP to ground to set the desired acceleration profile
CS	GND	1%, 1/8-watt resistor tied from CS to ground to set the desired current limit
ADV	GND	1%, 1/8-watt resistor tied from ADV to ground to set the desired lead angle (time)

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8.2.1 Design Requirements

表 8-2 provides design input parameters and motor parameters for system design.

表 8-2. Recommended Application Range

		MIN	NOM	MAX	UNIT
Motor voltage		4.4	12	18	V
BEMF constant	Phase to center tap, measured while motor is coasting	5		150	mV/Hz
Motor phase resistance	Phase to center tap	1		20	Ω
Motor electrical constant	1 phase; inductance divided by resistance, measured phase to phase, yields the electrical constant for 1 phase.	100		5000	μs
Motor winding current (rms)				1	A
Absolute maximum current	During locked condition			2.5	A

8.2.2 Detailed Design Procedure

Assuming the motor used in the application falls within the recommended application range shown in 表 8-2, the DRV10974 device is simple and intuitive to interface with. The DRV10974 device receives a PWM input that it uses to control the speed of the motor. The duty cycle of the PWM input is used to determine the magnitude of the voltage applied to the motor. The resulting motor speed can be monitored on the FG pin. The FR pin is used to control the direction of rotation for the motor. As a result, the only configuration and customization is dictated by the RMP, ADV, and CS pins.

The resistor on the CS pin is usually determined by the application specifications. Because the CS pin determines the current limit, specifications such as motor current or input power can determine what value the current limit can be set to. Then, the RMP and ADV resistors must be set experimentally through tuning. The RMP pin sets the acceleration profile of the motor. If the RMP pin is set to faster acceleration, the motor starts up faster but may be more likely to fail start-up. In addition, the ADV resistor controls the lead time so the applied current is aligned with the BEMF of the motor. If the ADV resistor is incorrectly selected, the motor may not run efficiently or at all.

As a result, the RMP pin is usually set to the slowest profile while ADV is correctly tuned. Then, the RMP can be set to a different value that allows for a faster acceleration with no impact to start-up reliability. This process, and other design considerations, are documented extensively in the DRV10974 Technical Documents tab on the DRV10974 product page.

8.2.3 Application Curves

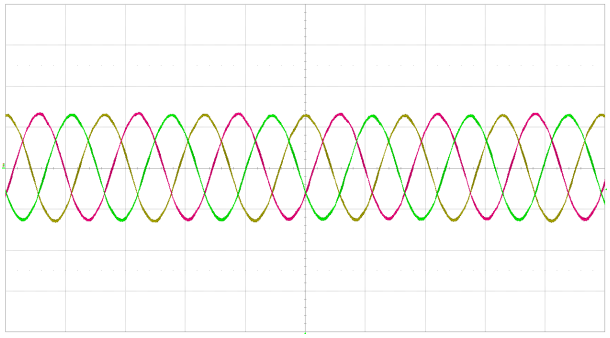


图 8-2. DRV10974 Operation Current Waveform

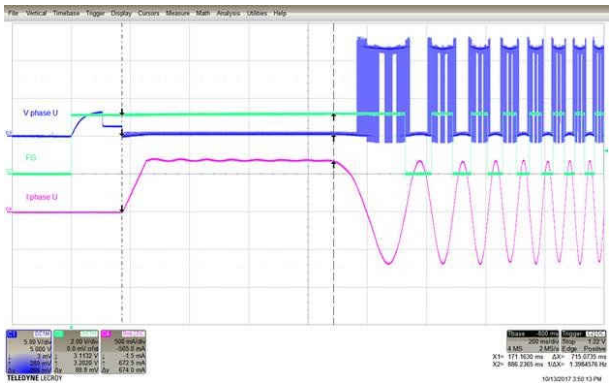


图 8-3. DRV10974 Start-Up Waveform

9 Power Supply Recommendations

The DRV10974 device is designed to operate from an input voltage supply, V_{CC} , range between 4.4 V and 18 V. The user must place a minimum of a 10-µF capacitor rated for V_{CC} between the V_{CC} and GND pins and as close as possible to the V_{CC} and GND pins.

If the power supply ripple is more than 200 mV, in addition to the local decoupling capacitors, a bulk capacitance is required and must be sized according to the application requirements.

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10 Layout

10.1 Layout Guidelines

- Use thick traces when routing to the V_{CC}, GND, U, V, and W pins, because high current passes through these traces.
- Place the 10-µF capacitor between V_{CC} and GND, and as close to the V_{CC} and GND pins as possible.
- Place the 100-nF capacitor between VCP and V_{CC}, and as close to the VCP and V_{CC} pins as possible.
- Connect GND and PGND under the thermal pad.
- Keep the thermal pad connection as large as possible. It should be one piece of copper without any gaps.

10.2 Layout Example

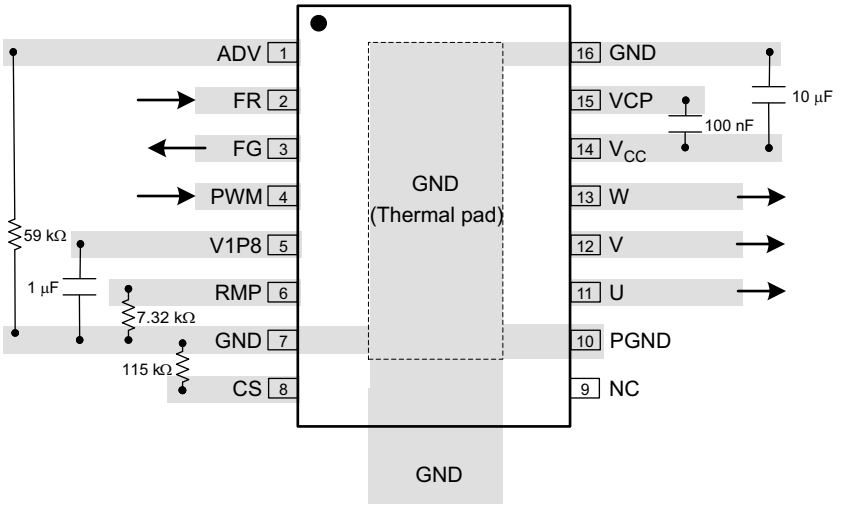


图 10-1. HTSSOP Layout Example

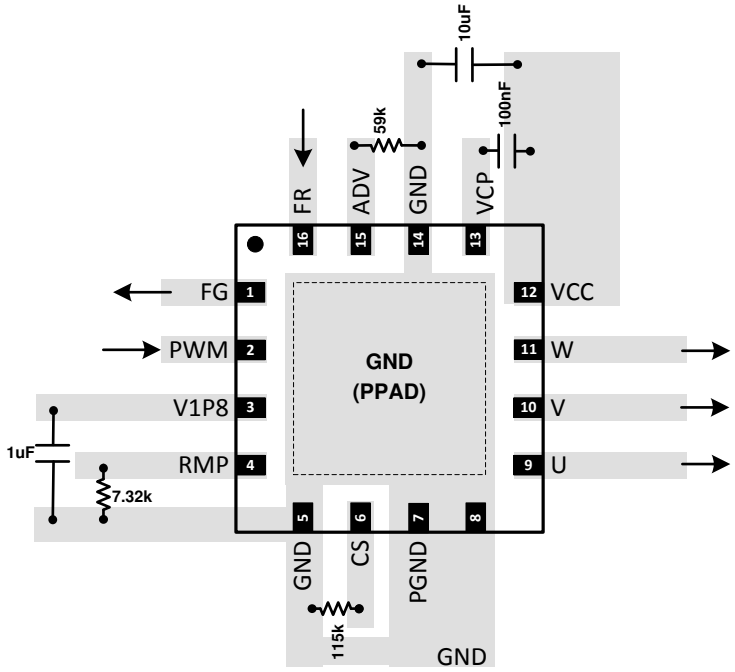


图 10-2. QFN Layout Example

11 Device and Documentation Support

11.1 Device Support

11.2 接收文档更新通知

要接收文档更新通知，请导航至 ti.com 上的器件产品文件夹。点击 *订阅更新* 进行注册，即可每周接收产品信息更改摘要。有关更改的详细信息，请查看任何已修订文档中包含的修订历史记录。

11.3 支持资源

TI E2E™ 支持论坛是工程师的重要参考资料，可直接从专家获得快速、经过验证的解答和设计帮助。搜索现有解答或提出自己的问题可获得所需的快速设计帮助。

链接的内容由各个贡献者“按原样”提供。这些内容并不构成 TI 技术规范，并且不一定反映 TI 的观点；请参阅 TI 的《使用条款》。

11.4 Trademarks

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11.5 静电放电警告



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ESD 的损坏小至导致微小的性能降级，大至整个器件故障。精密的集成电路可能更容易受到损坏，这是因为非常细微的参数更改都可能会导致器件与其发布的规格不相符。

11.6 术语表

TI 术语表　　本术语表列出并解释了术语、首字母缩略词和定义。

12 Mechanical, Packaging, and Orderable Information

The following pages include mechanical, packaging, and orderable information. This information is the most-current data available for the designated device. This data is subject to change without notice and without revision of this document. For browser-based versions of this data sheet, see the left-hand navigation pane.

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PACKAGING INFORMATION

Orderable part number	Status (1)	Material type (2)	Package | Pins	Package qty | Carrier	RoHS (3)	Lead finish/ Ball material (4)	MSL rating/ Peak reflow (5)	Op temp (°C)	Part marking (6)
DRV10974PWPR	Active	Production	HTSSOP (PWP) | 16	2000 | LARGE T&R	Yes	NIPDAU	Level-3-260C-168 HR	-40 to 125	10974
DRV10974PWPR.A	Active	Production	HTSSOP (PWP) | 16	2000 | LARGE T&R	Yes	NIPDAU	Level-3-260C-168 HR	-40 to 125	10974
DRV10974RUMR	Active	Production	WQFN (RUM) | 16	3000 | LARGE T&R	Yes	NIPDAU	Level-1-260C-UNLIM	-40 to 125	DRV 10974
DRV10974RUMR.A	Active	Production	WQFN (RUM) | 16	3000 | LARGE T&R	Yes	NIPDAU	Level-1-260C-UNLIM	-40 to 125	DRV 10974

(1) **Status:** For more details on status, see our product life cycle.

(2) **Material type:** When designated, preproduction parts are prototypes/experimental devices, and are not yet approved or released for full production. Testing and final process, including without limitation quality assurance, reliability performance testing, and/or process qualification, may not yet be complete, and this item is subject to further changes or possible discontinuation. If available for ordering, purchases will be subject to an additional waiver at checkout, and are intended for early internal evaluation purposes only. These items are sold without warranties of any kind.

(3) **RoHS values:** Yes, No, RoHS Exempt. See the TI RoHS Statement for additional information and value definition.

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

(5) **MSL rating/Peak reflow:** The moisture sensitivity level ratings and peak solder (reflow) temperatures. In the event that a part has multiple moisture sensitivity ratings, only the lowest level per JEDEC standards is shown. Refer to the shipping label for the actual reflow temperature that will be used to mount the part to the printed circuit board.

(6) **Part marking:** There may be an additional marking, which relates to the logo, the lot trace code information, or the environmental category of the part.

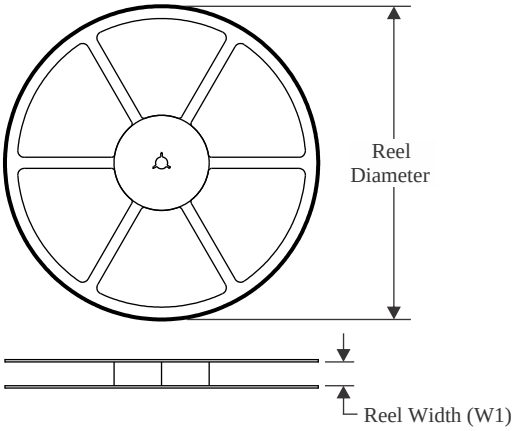
Multiple part markings will be inside parentheses. Only one part marking contained in parentheses and separated by a "~" will appear on a part. If a line is indented then it is a continuation of the previous line and the two combined represent the entire part marking for that device.

Important Information and Disclaimer: The information provided on this page represents TI's knowledge and belief as of the date that it is provided. TI bases its knowledge and belief on information provided by third parties, and makes no representation or warranty as to the accuracy of such information. Efforts are underway to better integrate information from third parties. TI has taken and continues to take reasonable steps to provide representative and accurate information but may not have conducted destructive testing or chemical analysis on incoming materials and chemicals. TI and TI suppliers consider certain information to be proprietary, and thus CAS numbers and other limited information may not be available for release.

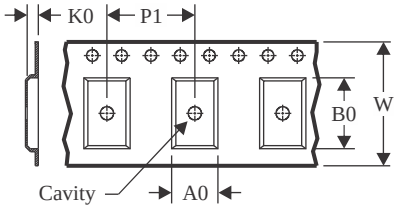
In no event shall TI's liability arising out of such information exceed the total purchase price of the TI part(s) at issue in this document sold by TI to Customer on an annual basis.

TAPE AND REEL INFORMATION

REEL DIMENSIONS

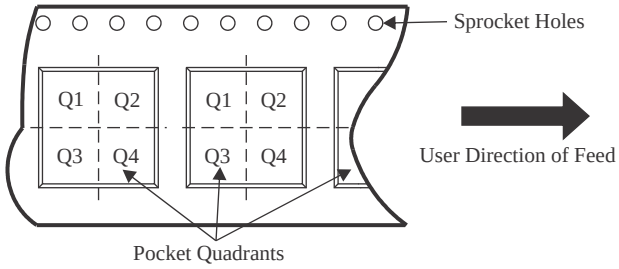


TAPE DIMENSIONS



A0	Dimension designed to accommodate the component width
B0	Dimension designed to accommodate the component length
K0	Dimension designed to accommodate the component thickness
W	Overall width of the carrier tape
P1	Pitch between successive cavity centers

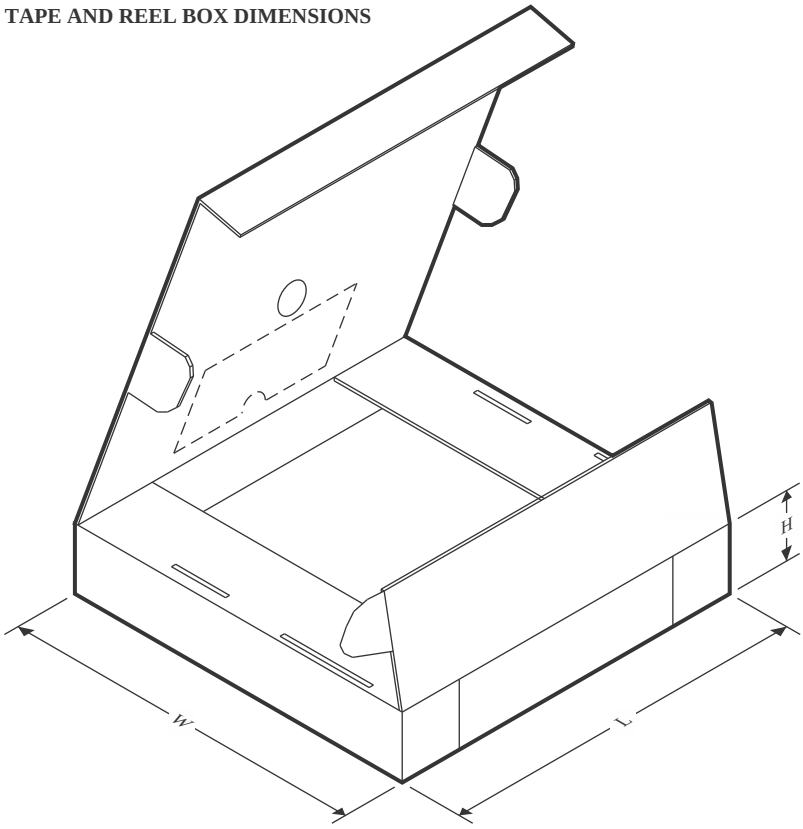
QUADRANT ASSIGNMENTS FOR PIN 1 ORIENTATION IN TAPE



*All dimensions are nominal

Device	Package Type	Package Drawing	Pins	SPQ	Reel Diameter (mm)	Reel Width W1 (mm)	A0 (mm)	B0 (mm)	K0 (mm)	P1 (mm)	W (mm)	Pin1 Quadrant
DRV10974PWPR	HTSSOP	PWP	16	2000	330.0	12.4	6.9	5.6	1.6	8.0	12.0	Q1
DRV10974RUMR	WQFN	RUM	16	3000	330.0	12.4	4.25	4.25	1.15	8.0	12.0	Q2

TAPE AND REEL BOX DIMENSIONS



*All dimensions are nominal

Device	Package Type	Package Drawing	Pins	SPQ	Length (mm)	Width (mm)	Height (mm)
DRV10974PWPR	HTSSOP	PWP	16	2000	350.0	350.0	43.0
DRV10974RUMR	WQFN	RUM	16	3000	360.0	360.0	36.0

GENERIC PACKAGE VIEW

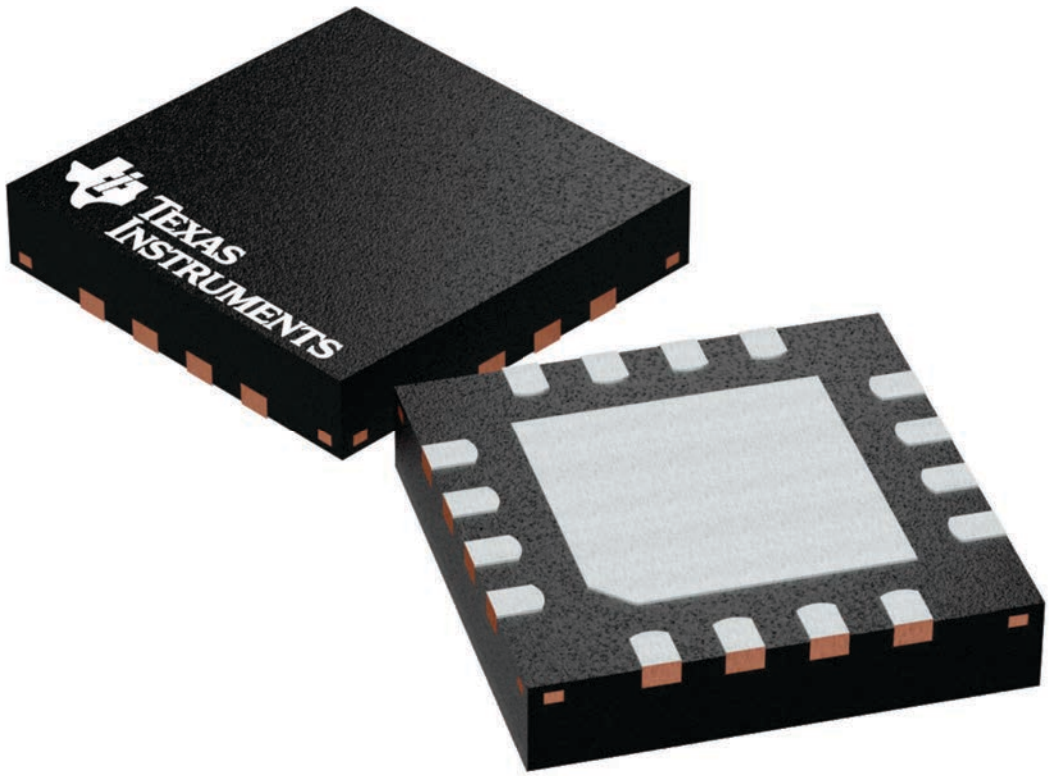
RUM 16

WQFN - 0.8 mm max height

4 x 4, 0.65 mm pitch

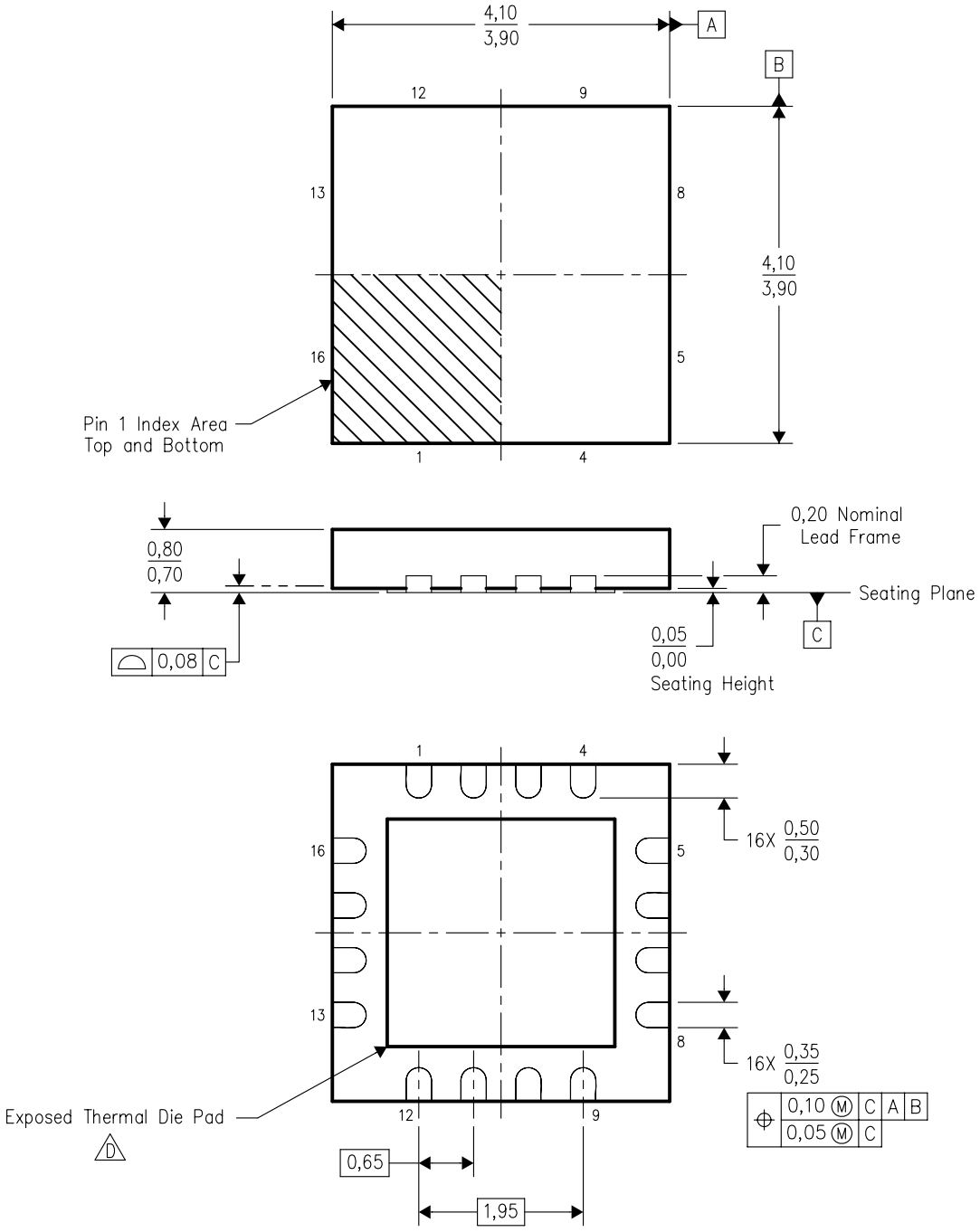
PLASTIC QUAD FLATPACK - NO LEAD

This image is a representation of the package family, actual package may vary.
Refer to the product data sheet for package details.



4224843/A

RUM (S–PQFP–N16) PLASTIC QUAD FLATPACK



4209092/A 10/2007

NOTES:
A. All linear dimensions are in millimeters. Dimensioning and tolerancing per ASME Y14.5M–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.
E. Package complies to JEDEC MO–220 variation WGGC–3.

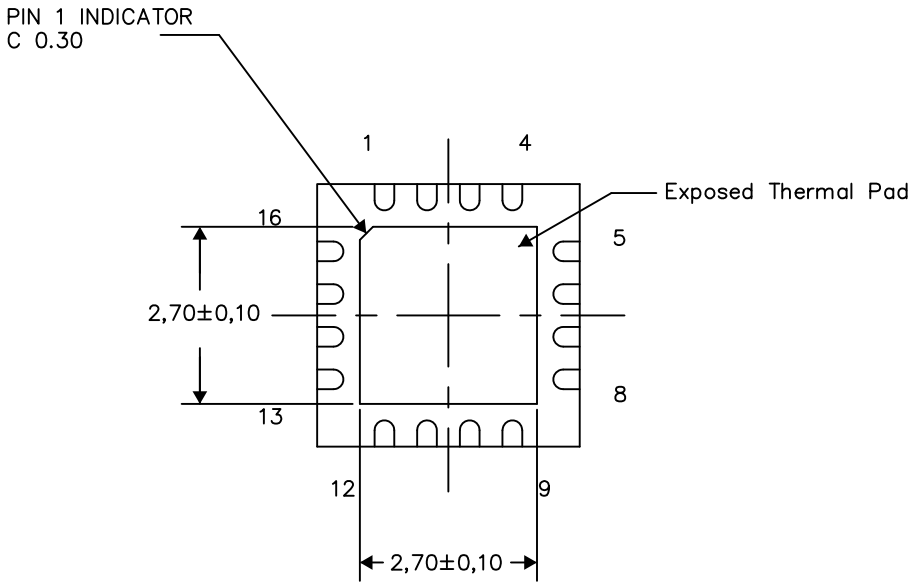
RUM (S–PWQFN–N16) PLASTIC QUAD FLATPACK NO–LEAD

THERMAL INFORMATION

This package incorporates an exposed thermal pad that is designed to be attached directly to an external heatsink. The thermal pad must be soldered directly to the printed circuit board (PCB). After soldering, the PCB can be used as a heatsink. In addition, through the use of thermal vias, the thermal pad can be attached directly to the appropriate copper plane shown in the electrical schematic for the device, or alternatively, can be attached to a special heatsink structure designed into the PCB. This design optimizes the heat transfer from the integrated circuit (IC).

For information on the Quad Flatpack No–Lead (QFN) package and its advantages, refer to Application Report, QFN/SON PCB Attachment, Texas Instruments Literature No. SLUA271. This document is available at www.ti.com.

The exposed thermal pad dimensions for this package are shown in the following illustration.



Bottom View

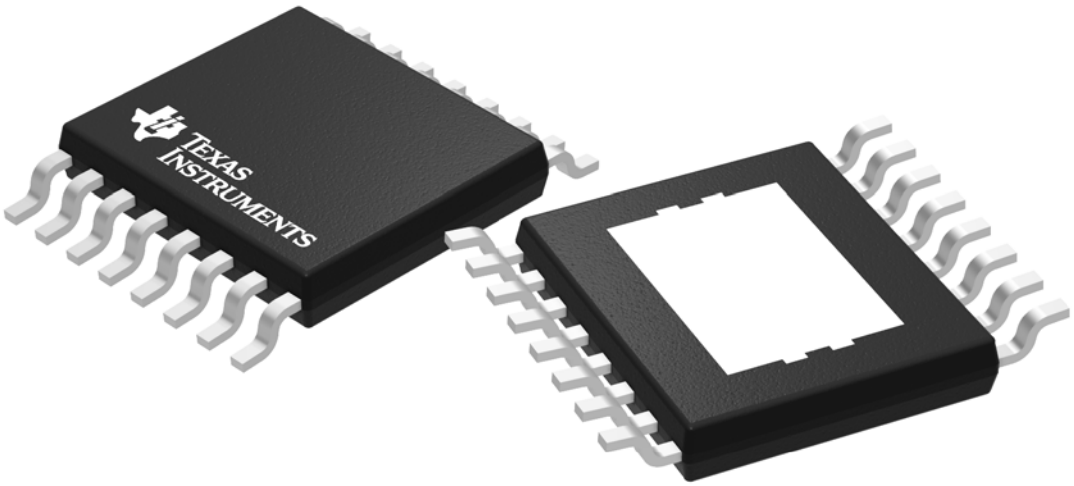
Exposed Thermal Pad Dimensions

4209093–2/F 09/15

NOTES: All linear dimensions are in millimeters

PWP 16 PowerPAD™ TSSOP - 1.2 mm max height

PLASTIC SMALL OUTLINE



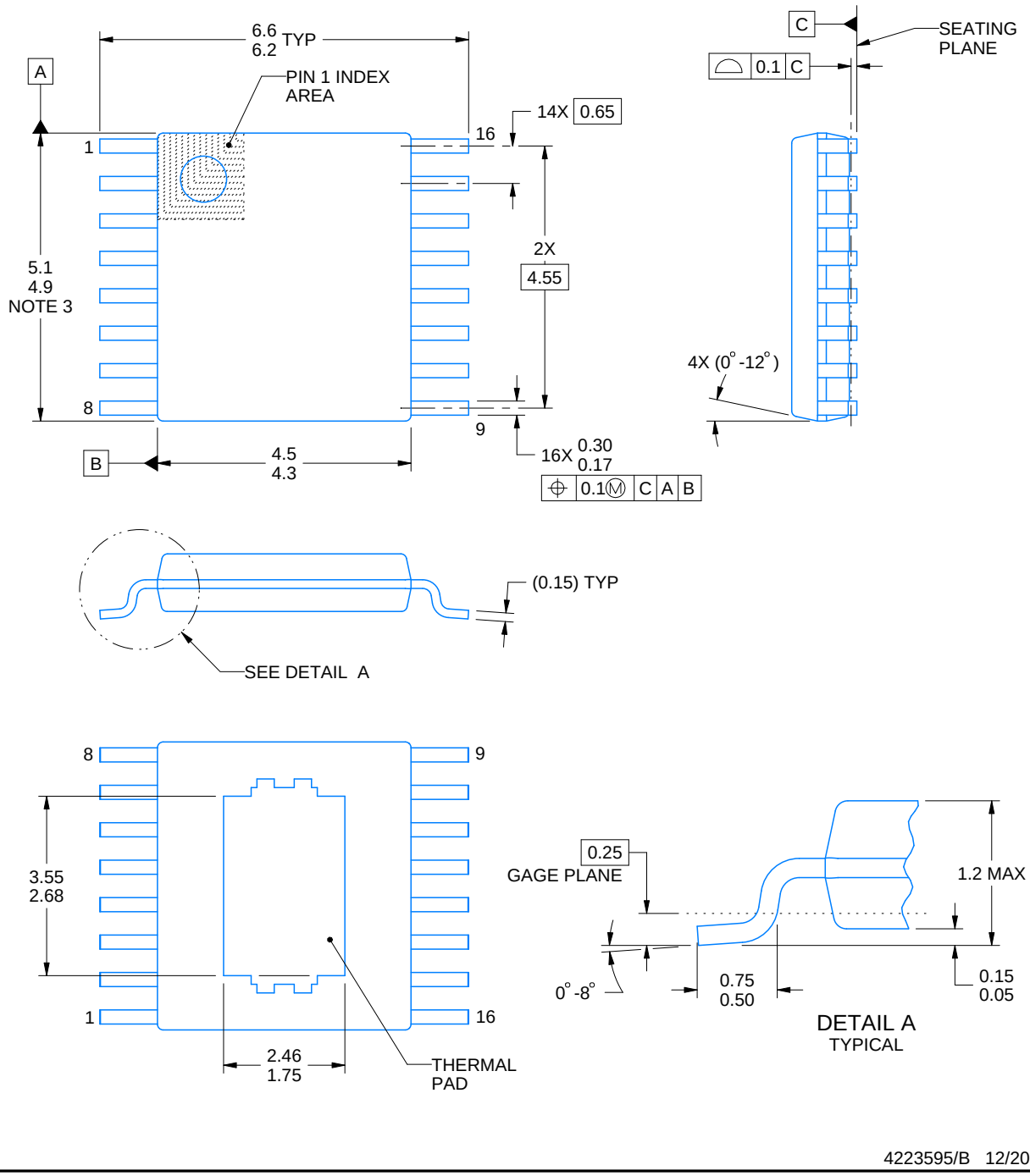
Images above are just a representation of the package family, actual package may vary.
Refer to the product data sheet for package details.

PACKAGE OUTLINE

PWP0016J

PowerPAD™ TSSOP - 1.2 mm max height

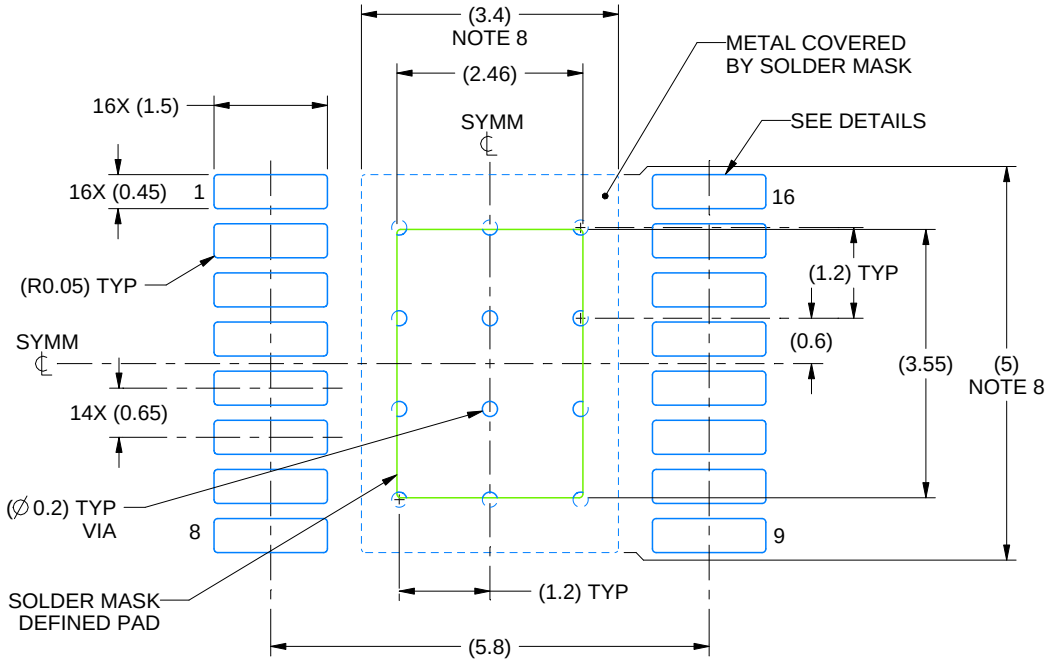
SMALL OUTLINE PACKAGE



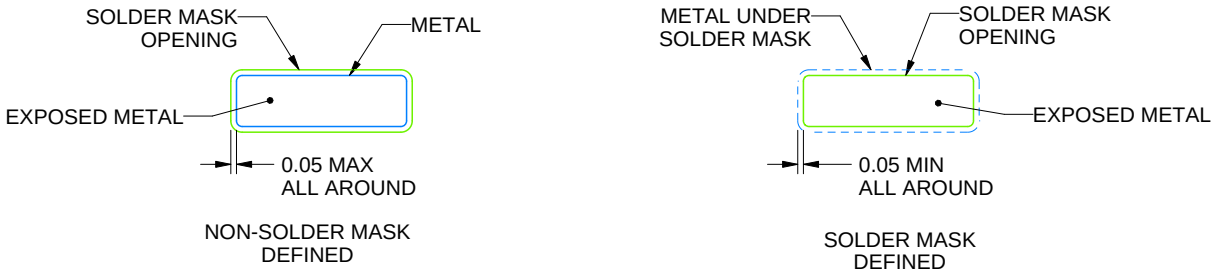
PowerPAD is a trademark of Texas Instruments.

NOTES:

1. All linear dimensions are in millimeters. Any dimensions in parenthesis are for reference only. Dimensioning and tolerancing per ASME Y14.5M.
2. This drawing is subject to change without notice.
3. This dimension does not include mold flash, protrusions, or gate burrs. Mold flash, protrusions, or gate burrs shall not exceed 0.15 mm per side.
4. Reference JEDEC registration MO-153.



LAND PATTERN EXAMPLE
EXPOSED METAL SHOWN
SCALE: 10X

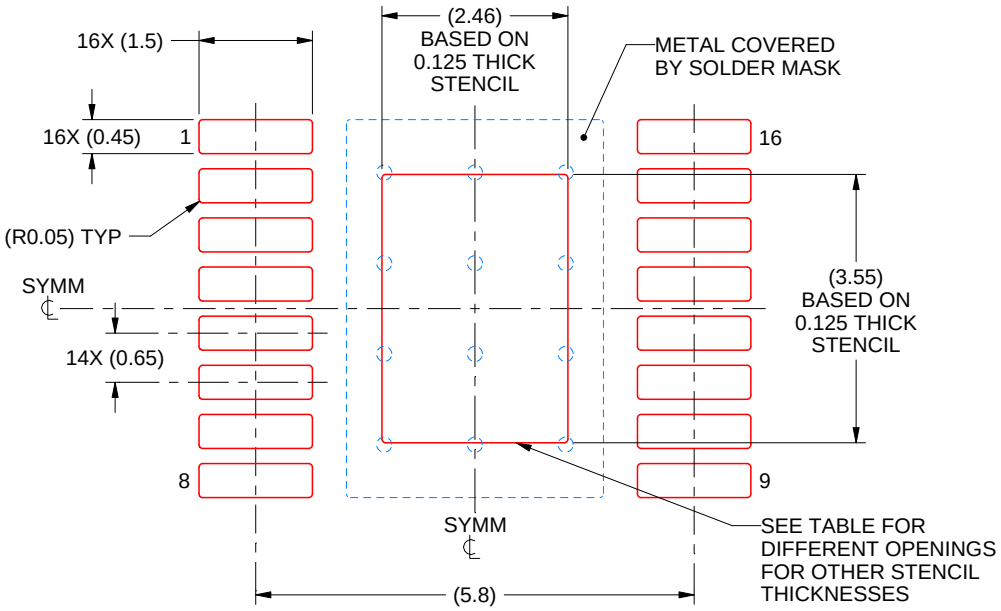


SOLDER MASK DETAILS

4223595/B 12/2023

NOTES: (continued)

5. Publication IPC-7351 may have alternate designs.
6. Solder mask tolerances between and around signal pads can vary based on board fabrication site.
7. This package is designed to be soldered to a thermal pad on the board. For more information, see Texas Instruments literature numbers SLMA002 (www.ti.com/lit/slma002) and SLMA004 (www.ti.com/lit/slma004).
8. Size of metal pad may vary due to creepage requirement.
9. Vias are optional depending on application, refer to device data sheet. It is recommended that vias under paste be filled, plugged or tented.



SOLDER PASTE EXAMPLE
BASED ON 0.125 mm THICK STENCIL
SCALE: 10X

STENCIL THICKNESS	SOLDER STENCIL OPENING
0.1	2.75 X 3.97
0.125	2.46 X 3.55 (SHOWN)
0.15	2.25 X 3.24
0.175	2.08 X 3.00

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NOTES: (continued)

10. Laser cutting apertures with trapezoidal walls and rounded corners may offer better paste release. IPC-7525 may have alternate design recommendations.
11. Board assembly site may have different recommendations for stencil design.

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最后更新日期：2025 年 10 月