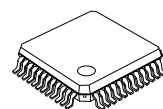


DUAL STEPPER MOTOR DRIVER

■ GENERAL DESCRIPTION

The **NJM13775** is a switch-mode (chopper), constant current driver with two channels: one for each winding of a two-phase stepper motor. **NJM13775** is equipped with a Disable input to simplify half-stepping operation. The **NJM13775** contains a clock oscillator, a set of comparators and flip-flops implementing the switching control, and two output H-bridges, including recirculation diodes. Voltage supply requirements are +5 V for logic and +10 to +45 V for the motor. Maximum output current is 500mA per channel. **NJM13775** achieved downsizing a motor control board by adopting small LQFP package, making this IC ideal for a multiple motor control board.

■ PACKAGE OUTLINE



NJM13775FR3

■ FEATURES

- Dual chopper driver
- 350mA continuous output current per channel
- Digital filter on chip eliminates external filtering components
- Packages LQFP48

■ BLOCK DIAGRAM

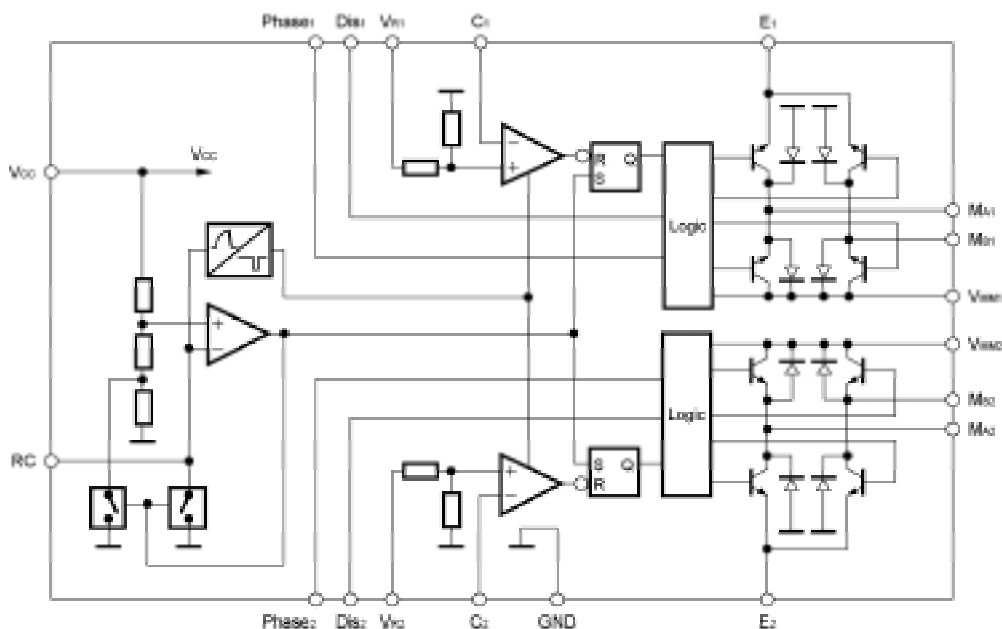


Figure 1. Block diagram

PIN CONFIGURATION

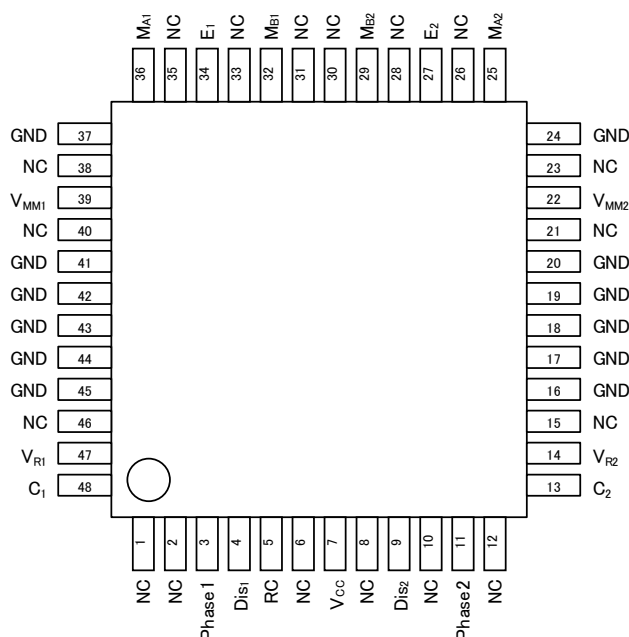


Figure 2. Pin configurations

PIN DESCRIPTION

| PIN # | Symbol | Description |
|---|--------------------|--|
| 32 | M _{B1} | Motor output B, channel 1. Motor current flows from M _{A1} to M _{B1} when Phase ₁ is HIGH. |
| 34 | E ₁ | Common emitter, channel 1. This pin connects to a sensing resistor R _S to ground. |
| 36 | M _{A1} | Motor output A, channel 1. Motor current flows from M _{A1} to M _{B1} when Phase ₁ is HIGH. |
| 39 | V _{MM1} | Motor supply voltage, channel 1, +10 to +40 V. V _{MM1} and V _{MM2} should be connected together. |
| 16,17,18,19,20,24,37, 41,42,43,44,45 | GND | Ground and negative supply. Note: these pins are used thermally for heat-sinking. Make sure that all ground pins are soldered onto a suitably large copper ground plane for efficient heat sinking. |
| 47 | V _{R1} | Reference voltage, channel 1. Controls the comparator threshold voltage and hence the output current. |
| 48 | C ₁ | Comparator input channel 1. This input senses the instantaneous voltage across the sensing resistor, filtered by the internal digital filter or an optional external RC network. |
| 3 | Phase ₁ | Controls the direction of motor current at outputs M _{A1} and M _{B1} . Motor current flows from M _{A1} to M _{B1} when Phase ₁ is HIGH. |
| 4 | Dis ₁ | Disable input for channel 1. When HIGH, all four output transistors are turned off, which results in a rapidly decreasing output current to zero. |
| 5 | RC | Clock oscillator RC pin. Connect a 12 kohm resistor to V _{CC} and a 4 700 pF capacitor to ground to obtain the nominal switching frequency of 23.0 kHz and a digital filter blanking time of 1.0μs. |
| 7 | V _{CC} | Logic voltage supply, nominally +5 V. |
| 9 | Dis ₂ | Disable input for channel 2. When HIGH, all four output transistors are turned off, which results in a rapidly decreasing output current to zero. |
| 11 | Phase ₂ | Controls the direction of motor current at outputs M _{A2} and M _{B2} . Motor current flows from M _{A2} to M _{B2} when Phase ₂ is HIGH. |
| 13 | C ₂ | Comparator input channel 2. This input senses the instantaneous voltage across the sensing resistor, filtered by the internal digital filter or an optional external RC network. |
| 14 | V _{R2} | Reference voltage, channel 2. Controls the comparator threshold voltage and hence the output current. |
| 22 | V _{MM2} | Motor supply voltage, channel 2, +10 to +40 V. V _{MM1} and V _{MM2} should be connected together. |
| 25 | M _{A2} | Motor output A, channel 2. Motor current flows from M _{A2} to M _{B2} when Phase ₂ is HIGH. |
| 27 | E ₂ | Common emitter, channel 2. This pin connects to a sensing resistor R _S to ground. |
| 29 | M _{B2} | Motor output B, channel 2. Motor current flows from M _{A2} to M _{B2} when Phase ₂ is HIGH. |
| 1,2,6,8,10,12,15,21,23, 26,28,30,31,33,35,38, 40,46 | NC | No connection. |

■ ABSOLUTE MAXIMUM RATINGS

(Ta=+25°C)

| Parameter | PIN No. | Symbol | Min | Max | Unit |
|---|----------------|------------------|------|-----------------|------|
| Voltage | | | | | |
| Logic voltage supply | 7 | V _{CC} | 0 | 7 | V |
| Motor voltage supply | 22, 39 | V _{MM} | 0 | 45 | V |
| Logic Input voltage | 3, 4, 9, 11 | V _I | -0.3 | 6 | V |
| Analog Input voltage | 13, 14, 47, 48 | V _A | -0.3 | V _{CC} | V |
| Current | | | | | |
| Motor output current | 25, 29, 32, 36 | I _M | -500 | +500 | mA |
| Logic input current | 3, 4, 9, 11 | I _I | -10 | - | mA |
| Analog input current | 13, 14, 47, 48 | I _A | -10 | - | mA |
| Temperature | | | | | |
| Operating ambient temperature | | T _a | -40 | +85 | °C |
| Operating junction temperature | | T _j | -40 | +150 | °C |
| Storage temperature | | T _{stg} | -55 | +150 | °C |
| Power Dissipation | | | | | |
| 114.3mm X 76.2mm X 1.6mm, 2-phase, FR-4 mounted on EIA/JEDC specified board | | P _D | - | 1.8 | W |
| 114.3mm X 76.2mm X 1.6mm, 4-phase, FR-4 mounted on EIA/JEDC specified board | | P _D | - | 3.0 | W |

■ RECOMMENDED OPERATING Range

(Ta=+25°C)

| Parameter | Symbol | Min | Typ | Max | Unit |
|---------------------------------|---------------------------------|------|-----|------|------|
| Logic supply voltage | V _{CC} | 4.75 | 5 | 5.25 | V |
| Motor supply voltage | V _{MM} | 10 | - | 40 | V |
| Output emitter voltage | V _E | - | - | 1.0 | V |
| Motor output current | I _M | -350 | - | +350 | mA |
| Rise and fall time logic inputs | t _r , t _f | - | - | 2 | μs |
| Oscillator timing resistor | R _T | 2 | 12 | 20 | kΩ |

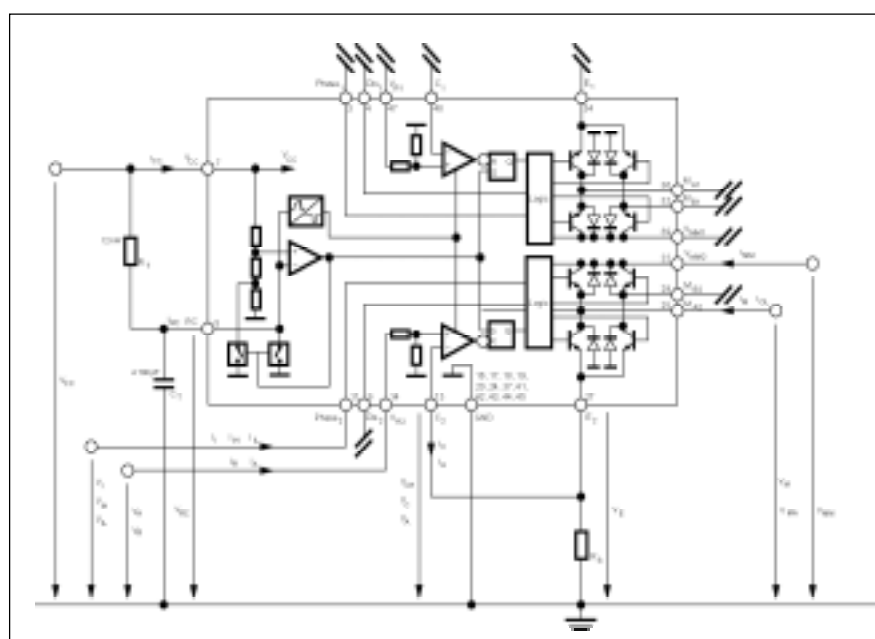


Figure 3. Definition of symbols

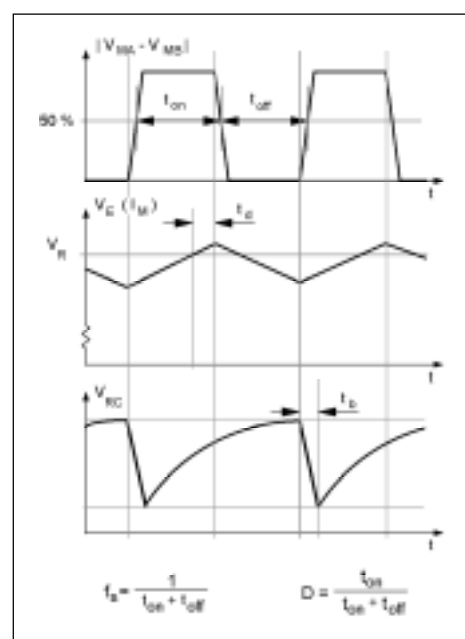


Figure 4. Definition of terms

■ ELECTRICAL CHARACTERISTICS

(Tj=+25, V_{CC}=5V, V_{MM}=41V)

| Parameter | Symbol | Conditions | Min | Typ | Max | Unit |
|---|--------------------|---|------|------|------|------|
| General | | | | | | |
| Supply current1 | I _{CC_1} | f _s =23.0kHz, Duty Cycle D=30% | - | 55 | 70 | mA |
| Supply current2 | I _{CC_2} | Dis ₁ =Dis ₂ =H | - | 7 | 10 | mA |
| Total power dissipation1 | P _{D_1} | V _{MM} =24V, I _{M1} =I _{M2} =250mA, f _s =23.0kHz, Duty Cycle D=30% | - | 1.1 | - | W |
| Total power dissipation2 | P _{D_2} | V _{MM} =24V, I _{M1} =350mA, I _{M2} =0mA, f _s =23.0kHz, Duty Cycle D=30% | - | 1.0 | - | W |
| Thermal shutdown junction temperature | T _{TSD} | | - | 160 | - | °C |
| Turn-off delay | t _d | dV _O /dt ≥ 50mV/μs, I _M =100mA | - | 1.1 | - | μs |
| Logic Inputs | | | | | | |
| Logic HIGH input voltage | V _{IH} | | 2.0 | - | - | V |
| Logic LOW input voltage | V _{IL} | | - | - | 0.6 | V |
| Logic HIGH input current | I _{IH} | V _I =2.4V | - | - | 20 | μA |
| Logic LOW input current | I _{IL} | V _I =0.4V | -0.2 | -0.1 | - | mA |
| Analog Inputs | | | | | | |
| Threshold voltage | V _{CH} | V _R =5V | 480 | 500 | 520 | mV |
| Input current | I _A | V _R =5V | - | 500 | - | μA |
| V _{C1} -V _{C2} mismatch | V _{Cdiff} | | - | 1 | - | mV |
| Motor Outputs | | | | | | |
| Lower transistor saturation voltage | V _{SL} | I _M =250mA | - | 0.25 | 0.6 | V |
| Lower transistor leakage current | I _{LL} | Dis ₁ =Dis ₂ =H | - | - | 100 | μA |
| Lower diode forward voltage drop | V _{CL} | I _M =250mA | - | 0.95 | 1.3 | V |
| Upper transistor saturation voltage | V _{SU} | I _M =250mA | - | 0.95 | 1.3 | V |
| Upper transistor leakage current | I _{LU} | Dis ₁ =Dis ₂ =H | - | - | 100 | μA |
| Upper diode forward voltage drop | V _{CU} | I _M =250mA | - | 1.05 | 1.3 | V |
| Chopper Oscillator | | | | | | |
| Chopping frequency | f _s | C _T =4700 pF, R _T =12 kΩ | 21.5 | 23.0 | 24.5 | kHz |
| Digital filter blanking time | t _b | C _T =4700 pF | - | 1.0 | - | μs |

■ THERMAL CHARACTERISTICS

| Parameter | Symbol | Conditions | Min | Typ | Max | Unit |
|---|-------------------|---|-----|-----|------|------|
| Junction to ambient thermal resistance 1 | θ _{ja_1} | EIA/JEDEC Specified board 114.3mm X 76.2mm X 1.6mm, 2-phase, FR-4 mounted | - | - | 69.5 | °C/W |
| Junction to case surface thermal resistance 1 | ψ _{jt_1} | EIA/JEDEC Specified board 114.3mm X 76.2mm X 1.6mm, 2-phase, FR-4 mounted | - | 5.1 | - | °C/W |
| Junction to ambient thermal resistance 2 | θ _{ja_2} | EIA/JEDEC specified board 114.3mm X 76.2mm X 1.6mm, 4-phase, FR-4 mounted | - | - | 41.7 | °C/W |
| Junction to case surface thermal resistance 2 | ψ _{jt_2} | EIA/JEDEC specified board 114.3mm X 76.2mm X 1.6mm, 4-phase, FR-4 mounted | - | 3.9 | - | °C/W |

■ FUNCTIONAL DESCRIPTION

Each channel of the **NJM13775** consists of the following sections: an output H-bridge with four transistors and four recirculation diodes, capable of driving up to 350mA continuous current to the motor winding, a logic section that controls the output transistors, an S-R flip-flop, and a comparator. The clock-oscillator is common to both channels.

Constant current control is achieved by switching the output current to the windings. This is done by sensing the peak current through the winding via a current-sensing resistor R_S , effectively connected in series with the motor winding. As the current increases, a voltage develops across the sensing resistor, which is fed back to the comparator. At the predetermined level, defined by the voltage at the reference input V_R , the comparator resets the flip-flop, which turns off the upper output transistor. The turn-off of one channel is independent of the other channel. The current decreases until the clock oscillator triggers the flip-flops of both channels simultaneously, which turns on the output transistors again, and the cycle is repeated.

To prevent erroneous switching due to switching transients at turn-on, the **NJM13775** includes a digital filter. The clock oscillator provides a blanking pulse which is used for digital filtering of the voltage transient across the current sensing resistor during turn-on.

The current paths during turn-on, turn-off and phase shift are shown in figure 5.

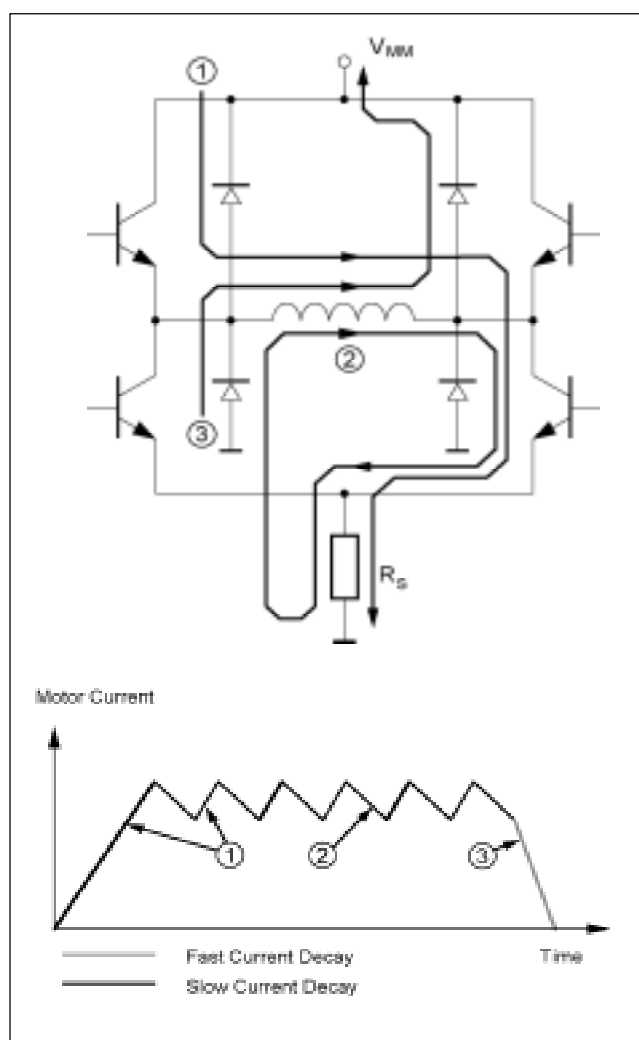


Figure 5. Output stage with current paths during turn-on, turn-off and phase shift.

APPLICATIONS INFORMATION

Current control

The regulated output current level to the motor winding is determined by the voltage at the reference input and the value of the sensing resistor, R_S . The peak current through the sensing resistor (and the motor winding) can be expressed as:

$$I_{M,peak} = 0.1 \cdot V_R / R_S \text{ [A]}$$

With a recommended value of 0.5 ohm for the sensing resistor R_S , a 2.5 V reference voltage will produce an output current of approximately 500 mA. R_S should be selected for maximum motor current. Be sure not to exceed the absolute maximum output current of 500 mA. Chopping frequency, winding inductance and supply voltage also affect the current, but to much less extent.

For accurate current regulation, the sensing resistor should be a 0.5 -1.0 W precision resistor, i. e. less than 1% tolerance and low temperature - coefficient.

Constant Voltage Control

Since there is no current detection, R_S is unnecessary. Therefore E_1 , E_2 , C_1 , C_2 connect to GND and V_{R1} , V_{R2} connect to V_{CC} . RC Pin require $R_T(12k\Omega)$ and $C_T(4700pF)$ to reset inner RS flip-flop at the time of turn-on.

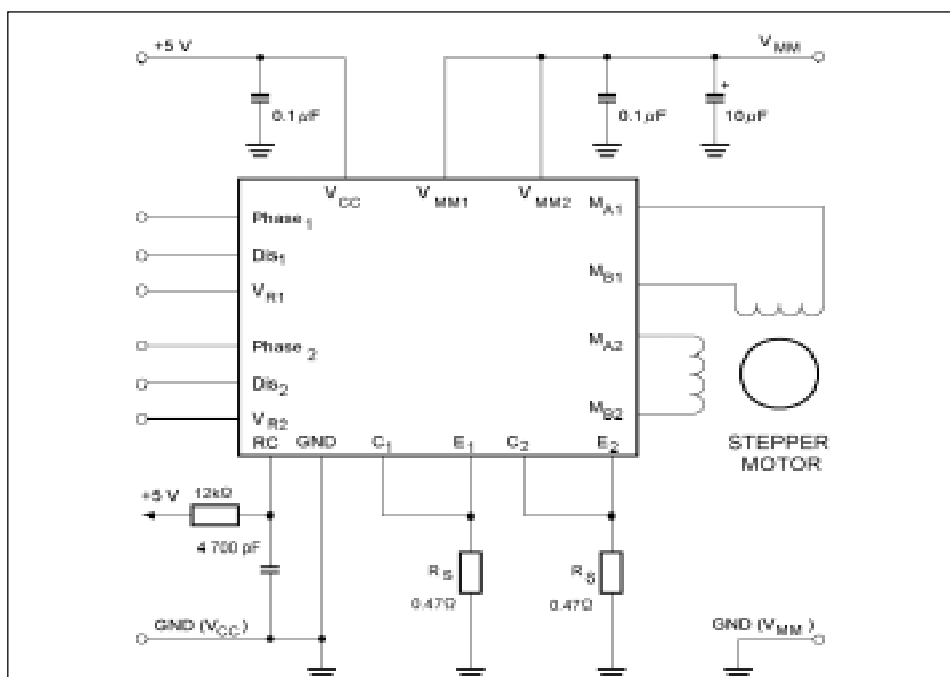


Figure 6. Typical stepper motor driver application with **NJM13775**.

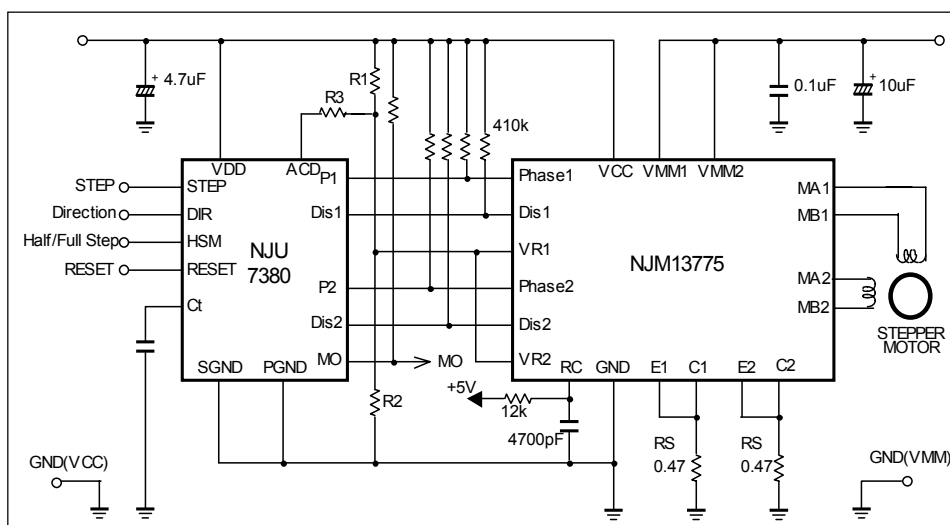


Figure 7. Half stepping system where **NJU7380** is used as controller circuit in order to generate the necessary sequence to the **NJM13775**.

Current sense filtering

At turn-on a current spike occurs from the recovery of the recirculation diodes and the capacitance of the motor winding. The clock oscillator generates a blanking pulse at turn-on to prevent flip-flops from resetting through the current sensing comparators due to the current spike. The blanking pulse disables the comparators for a short time. Thereby any voltage transient across the sensing resistor will be ignored during the blanking time.

Choose the blanking pulse time to be longer than the duration of the switching transients by selecting a proper C_T value. The time is calculated as:

$$t_b = 210 \cdot C_T [s]$$

As the C_T value may vary from approximately 2 200 pF to 33 000 pF, a blanking time ranging from 0.5 μ s to 7 μ s is possible. Nominal value is 4 700 pF, which gives a blanking time of 1.0 μ s.

As the filtering action introduces a small delay, the peak value across the sensing resistor, and hence the peak motor current, will reach a slightly higher level than what is defined by the reference voltage. The filtering delay also limits the minimum possible output current. As the output will be on for a short time each cycle, equal to the digital filtering blanking time plus additional internal delays, an amount of current will flow through the winding. Typically this current is 1-10 % of the maximum output current set by R_S .

When optimizing low current performance, the filtering may be done by adding an external low pass filter in series with the comparator C input. In this case the digital blanking time should be as short as possible. The recommended filter component values are 1 kohm and 820 pF. Lowering the switching frequency also helps reducing the minimum output current.

To create an absolute zero current, the Dis input should be HIGH.

Switching frequency

The frequency of the clock oscillator is set by the timing components R_T and C_T at the RC-pin. As C_T sets the digital filter blanking time, the clock oscillator frequency is adjusted by R_T . The value of R_T is limited to 2 - 20 kohm. The frequency is approximately calculated as:

$$f_s = 1 / (0.77 \cdot R_T \cdot C_T)$$

Nominal component values of 12k Ω and 4 700pF results in a clock frequency of 23.0 kHz. A lower frequency will result in higher current ripple, but may improve low level linearity. A higher clock frequency reduces current ripple, but increases the switching losses in the IC and possibly the iron losses in the motor.

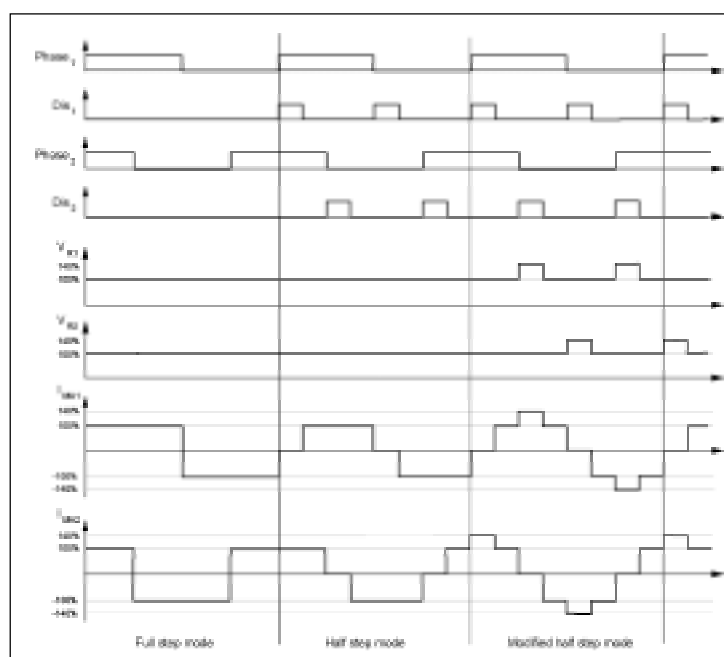


Figure 8. Stepping modes

Phase inputs

A logic HIGH on a Phase input gives a current flowing from pin M_A into pin M_B . A logic LOW gives a current flow in the opposite direction. A time delay prevents cross conduction in the H-bridge when changing the Phase input.

Dis (Disable) inputs

A logic HIGH on the Dis inputs will turn off all four transistors of the output H-bridge, which results in a rapidly decreasing output current to zero.

VR (Reference) inputs

The Vref inputs of the **NJM13775** have a voltage divider with a ratio of 1 to 10 to reduce the external reference voltage to an adequate level. The divider consists of closely matched resistors. Nominal input reference voltage is 5V.

Interference

Due to the switching operation of **NJM13775**, noise and transients are generated and might be coupled into adjacent circuitry. To reduce potential interference there are a few basic rules to follow:

- Use separate ground leads for power ground (the ground connection of R_S), the ground leads of **NJM13775**, and the ground of external analog and digital circuitry. The grounds should be connected together close to the GND pins of **NJM13775**.
- Decouple the supply voltages close to the **NJM13775** circuit. Use a ceramic capacitor in parallel with an electrolytic type for both V_{CC} and V_{MM} . Route the power supply lines close together.
- Do not place sensitive circuits close to the driver. Avoid physical current loops, and place the driver close to both the motor and the power supply connector. The motor leads could preferably be twisted or shielded.

Motor selection

The **NJM13775** is designed for two-phase bipolar stepper motors, i.e. motors that have only one winding per phase.

The chopping principle of the **NJM13775** is based on a constant frequency and a varying duty cycle. This scheme imposes certain restrictions on motor selection. Unstable chopping can occur if the chopping duty cycle exceeds approximately 50 %. See figure 5 for definitions. To avoid this, it is necessary to choose a motor with a low winding resistance and inductance, i.e. windings with a few turns.

It is not possible to use a motor that is rated for the same voltage as the actual supply voltage. Only rated current needs to be considered. Typical motors to be used together with the **NJM13775** have a voltage rating of 1 to 6 V, while the supply voltage usually ranges from 12 to 40 V.

Low inductance, especially in combination with a high supply voltage, enables high stepping rates. However, to give the same torque capability at low speed, the reduced number of turns in the winding in the low resistive, low inductive motor must be compensated by a higher current. A compromise has to be made. Choose a motor with the lowest possible winding resistance and inductance, that still gives the required torque, and use as high supply voltage as possible, without exceeding the maximum recommended 40 V. Check that the chopping duty cycle does not exceed 50 % at maximum current.

Thermal shutdown

The circuit is equipped with a thermal shutdown function that turns the outputs off at a chip (junction) temperature above 160°C. Normal operation is resumed when the temperature has decreased.

Programming

Figure 8 shows the different input and output sequences for full-step, half-step and modified half-step operations.

Full-step mode

Both windings are energized at all the time with the same current, $I_{M1} = I_{M2}$. To make the motor take one step, the current direction (and the magnetic field direction) in one phase is reversed. The next step is then taken when the other phase current reverses. The current changes go through a sequence of four different states which equal four full steps until the initial state is reached again.

Half-step mode

In the half-step mode, the current in one winding is brought to zero before a complete current reversal is made.

The motor will then have taken two half steps equalling one full step in rotary movement. The cycle is repeated, but on the other phase. A total of eight states are sequenced until the initial state is reached again.

Half-step mode can overcome potential resonance problems. Resonance appear as a sudden loss of torque at one or more distinct stepping rates and must be avoided so as not to loose control of the motor's shaft position.

One disadvantage with the half-step mode is the reduced torque in the half step positions, in which current flows through one winding only. The torque in this position is approximately 70 % of the full step position torque.

Modified half-step mode

The torque variations in half step mode will be eliminated if the current is increased about 1.4 times in the half-step position. A constant torque will further reduce resonance and mechanical noise, resulting in better performance, life expectancy and reliability of the mechanical system.

Modifying the current levels must be done by bringing the reference voltage up (or down) correspondingly from its nominal value. This can be done by using DAC or simple resistor divider networks. The **NJM13775** is designed to handle about 1.4 times higher current in one channel on mode, for example 2 x 500mA in the full-step position, and 1 x 700mA in the half-step position.

Heat sink design

Heat sink of **NJM13775** is achieved by soldering the ground leads onto a copper ground plane on the PCB. By obtaining of a copper area on the PCB, its ability in transmitting heat away is improved.

Maximum continuous output current is heavily dependent on the permissible loss and ambient temperature. Consult figure 9. (Typical Characteristics of IM VS. PD) to find the maximum output current under varying conditions.

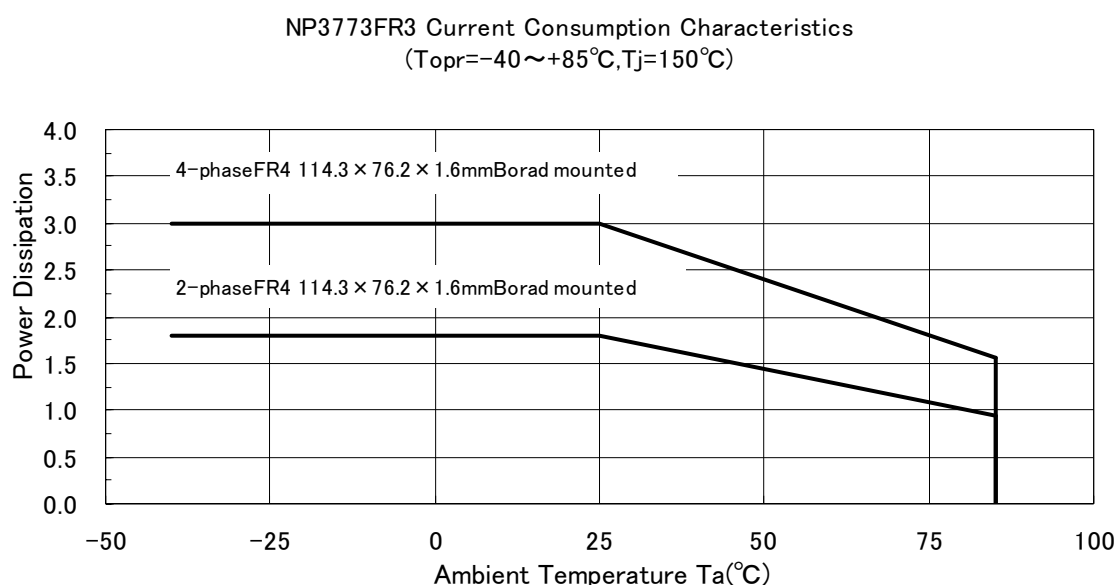
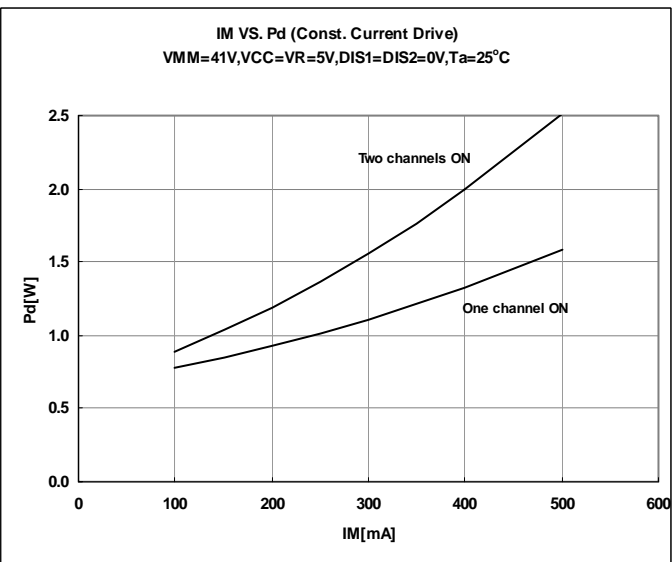
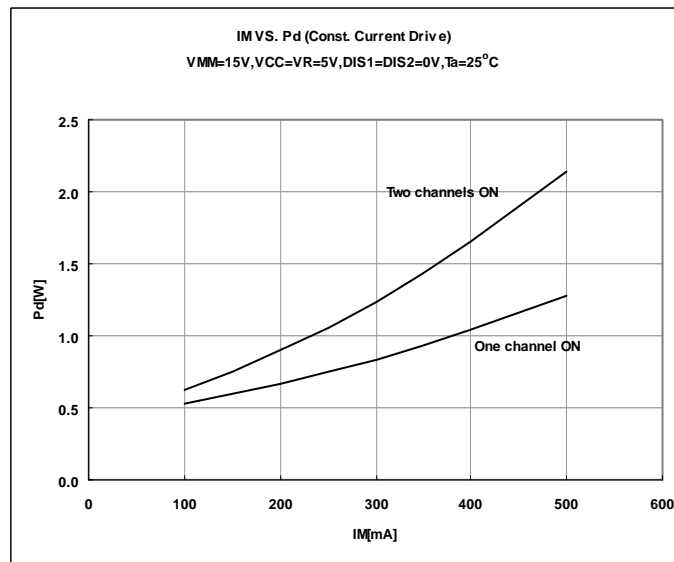
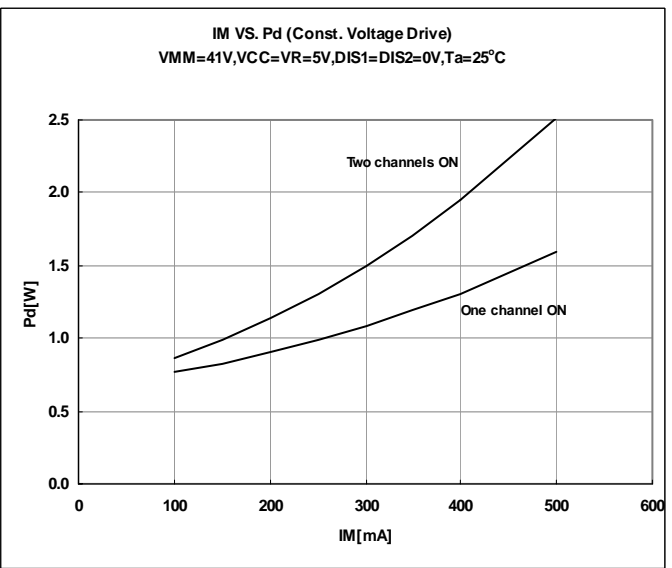
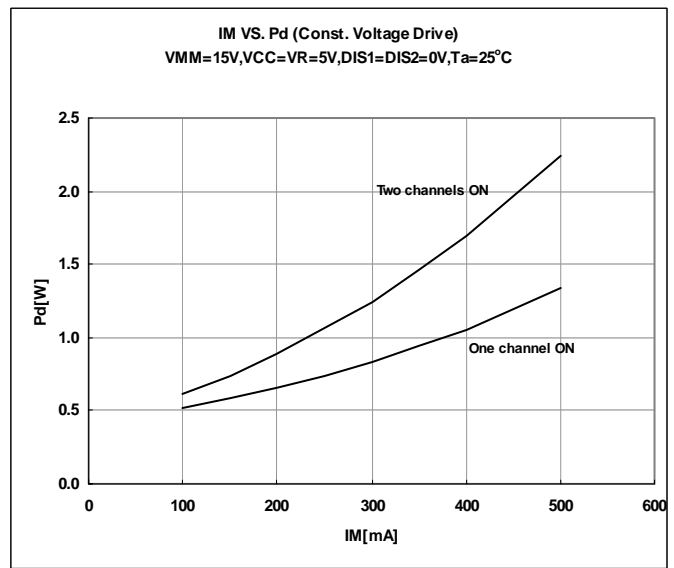
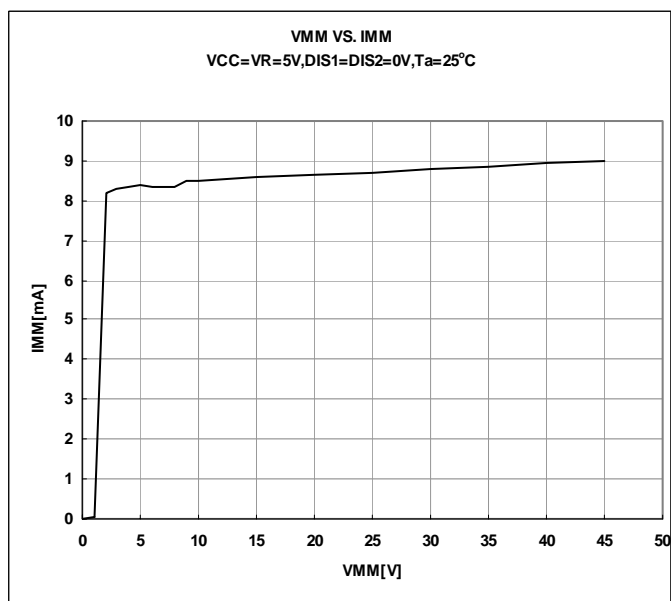
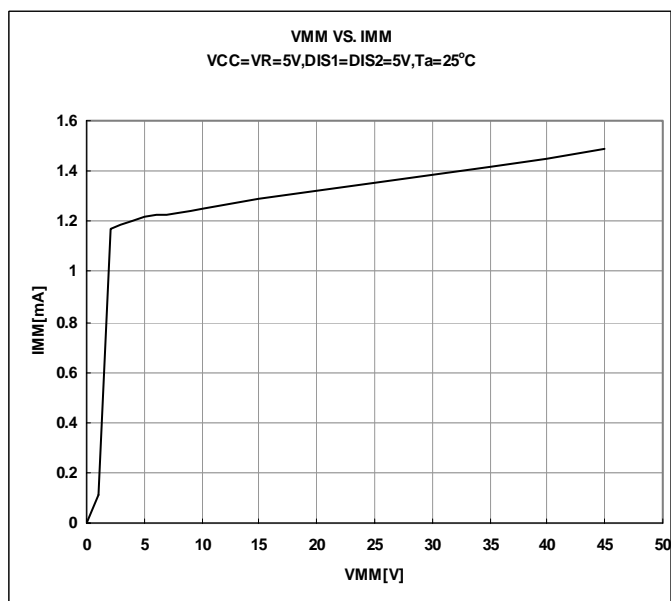
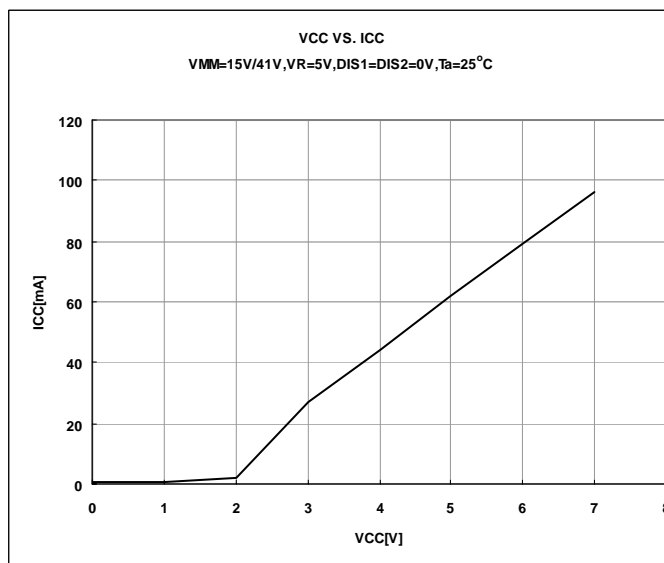
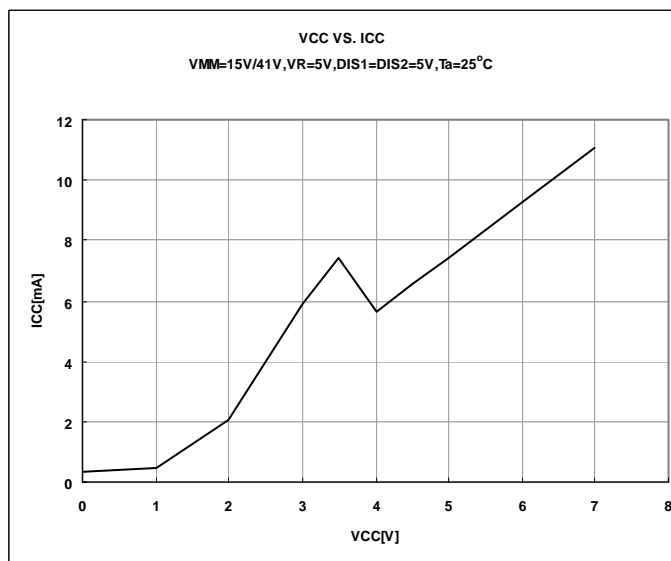


Figure 9 Ambient Temperature VS. Current Consumption (Derating Curve)

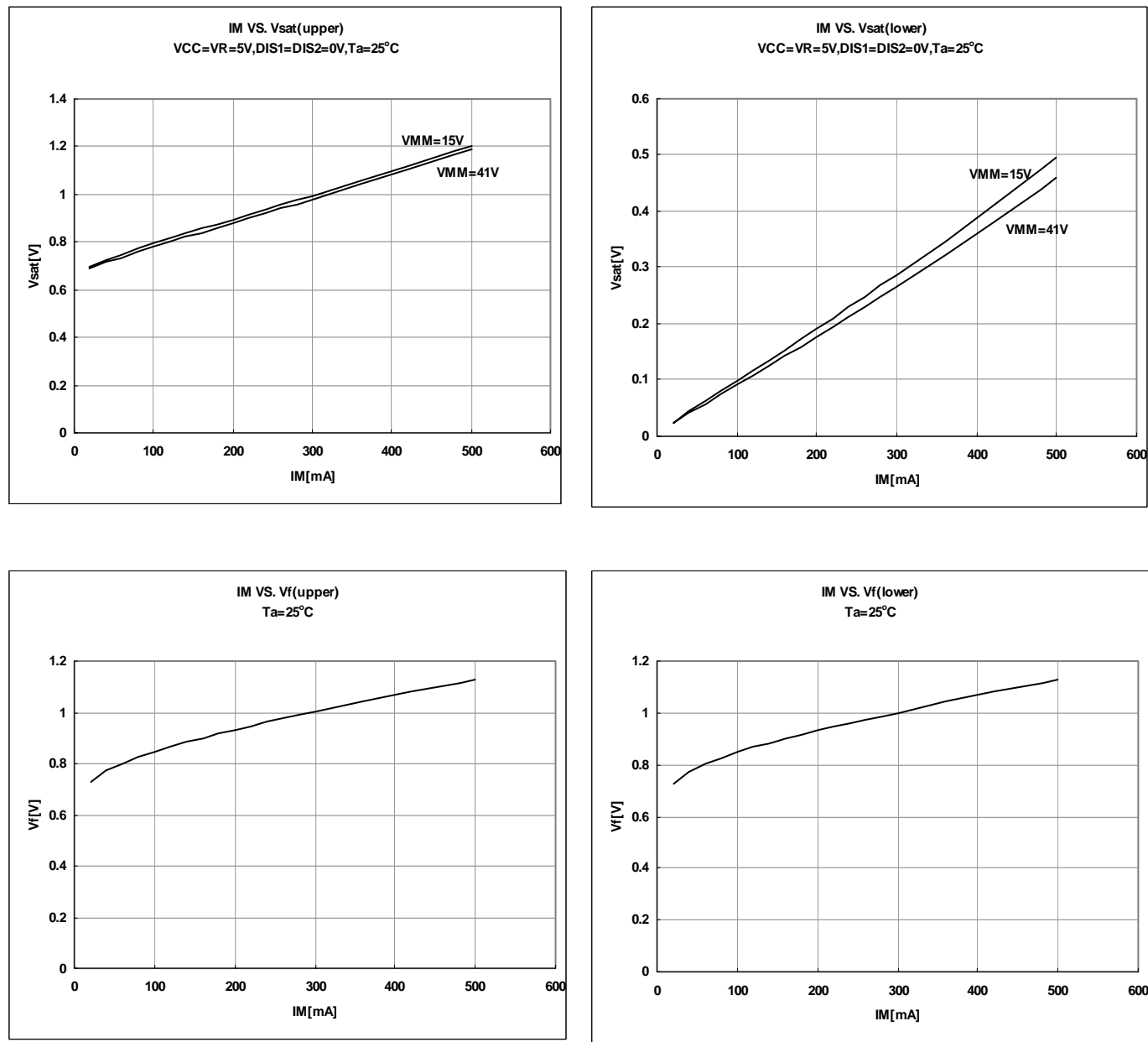
TYPICAL CHARACTERISTICS



■ TYPICAL CHARACTERISTICS



TYPICAL CHARACTERISTICS



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