TMC236B DATASHEET

Highly efficient SPI or Classic Analog Interface Stepper Driver for Two-Phase Bipolar Motors with full set of protection & diagnostics.

APPLICATIONS

Replace Classic Bipolar Driver ICs
Office Automation
Printer and Scanner
ATM, Cash recycler
POS
CCTV, Security
Antenna Positioning
Pumps and Valves
Lab Automation
Liquid Handling
Medical

FEATURES AND BENEFITS

High Current up to 1500mA and 1000mA at 105°C

Voltage Range 7 V… 36 V DC

3.3 V or 5 V for digital part

SPI & External Analogue / Digital Signals

Microstep Resolution 16 microsteps using internal DACs

Low Power Dissipation via low RDS-ON power stage

Protection: overvoltage, overtemperature & short circuit

Diagnostics: overcurrent, open load, 2 level overtemperature

Mixed Decay for smooth motor operation

Slope Control for reduced electromagnetic emissions

**Current Control** for cool motor and driver

Standby and Shutdown Mode

Optical Inspectable Package 10x10mm Standard TQFP-44 package

DESCRIPTION

The TMC236 driver for two-phase stepper motors offers a competitive feature set, including 16x micro-stepping and digital or analog current control. Standard SPI™ and communication via external analog & digital signals are available. The TMC236 is a multichip-package, integrating eight Low-RDS-ON high efficiency MOSFETs for motor currents up to 1.5A (1.1A RMS) and up to 36V. Integrated protection and diagnostic features support robust and reliable operation. High integration and small form factor enable miniaturized designs with low external component count for cost-effective and highly competitive solutions .

BLOCK DIAGRAM

TRINAMIC Motion Control GmbH & Co. KG
Hamburg, Germany
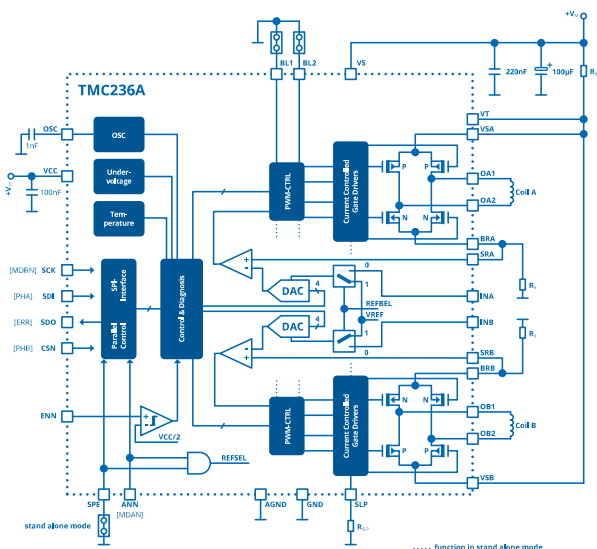
## APPLICATION EXAMPLES: HIGH POWER – SMALL SIZE

The TMC236B scores with its classic interface and high efficiency allowing a standard package operating up to 105°C environment without heat slug, and a versatility that covers a wide spectrum of applications and motor sizes. The TMC236B is the latest variant of the TMC236 family, offering enhanced MOSFETs with lower RDSon than the preceding TMC236A version. It is pin and function compatible to the TMC246B, that additionally offers StallGuard for sensorless homing. The TMC239 and TMC249 offer the same functionality for higher motor currents up to 4A RMS (7A max.).

APPLICATION EXAMPLES

COMPACT DESIGN FOR UP TO 3 MOTORS USING SPI INTERFACE
OFFLOAD THE MOTION CONTROL FUNCTION TO TRINAMICS TMC429. GET A COMPETITIVE DESIGN FOR MULTIPLE MOTORS!
By offloading the motion-control function to the TMC429, up to three motors can be operated reliably with very little demand for service from the microcontroller.
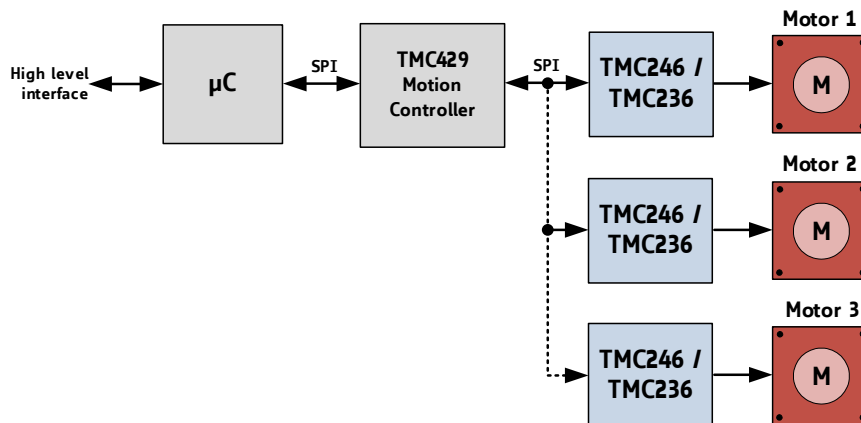
MINIATURIZED DESIGN WITH SIMPLE DIGITAL DRIVER CONTROL
*BENEFIT FROM A LARGE CURRENT CONTROL RANGE VIA ANALOG INPUTS!*
The TMC246/TMC236 is controlled via SPI bus. The microcontroller initializes the chip and writes control parameters, mode bits, and values for coil currents in the driver chip. Analog A/B inputs allow for a large current control range.
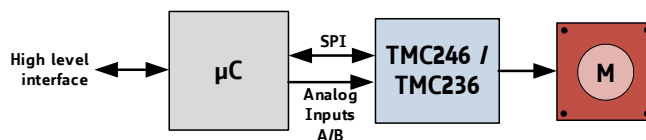
MINIATURIZED DESIGN FOR STANDALONE MODE
REPLACE BIPOLAR DRIVER BY A MODERN CMOS DRIVER. USE NEW HARDWARE AND KEEP YOUR SOFTWARE INVEST!
The TMC246/TMC236 is controlled by analog current control signals and digital phase signals. Especially for lower speeds inimitable smoothness will be achieved with TRINAMICs low noise chopper.
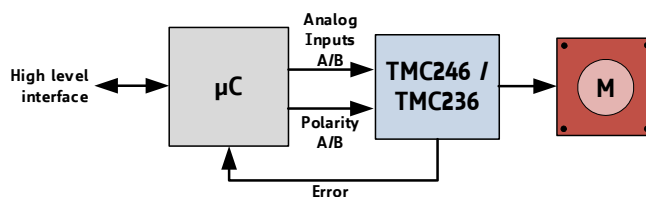
ORDER CODES

Order code	Description	Size
TMC236B-PA	1.5 A stepper driver with SPI, TQFP44	10 x 10 mm^2

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1   Key Concepts

Figure 1.1 TMC236 block diagram

The TMC236 is a dual full bridge driver IC for bipolar stepper motor control applications. The chip is realized in a HVCMOS technology and integrates eight separate low-RDSon high efficiency trench MOSFETs in a multichip-package. A 1.1A RMS driver can be realized in the size of a stamp.

The TMC236 motor driver implements advanced features which are characteristic to Trinamic products. These features contribute toward precision, energy efficiency, reliability, smooth motion, and cooler operation in stepper motor applications.

In addition to these performance enhancements, Trinamic motor drivers also offer safeguards to detect and protect against short circuit, overtemperature, overvoltage, and undervoltage conditions for enhancing safety and recovery from equipment malfunctions.

1.1 Advanced Features

Current Control	Current control serves a cool driver and motor. Internal DACs allow microstepping as well as smart current control. Its low power dissipation makes the TMC236 an optimum choice for drives, where a high reliability is desired.
Microstepping via SPI	Easy to use digital control of microstepping. After choosing the desired microstep resolution the microcontroller sends digital values for each microstep current via SPI. DACs and comparators convert these digital values to analog signals for coil currents. This way, every microstep is initialized and controlled by the microcontroller. The TMC236 serves for the execution.
Mixed Decay	Mixed decay can be used for smoother operation.
Low Noise Chopper	The TMC236 allows implementing a low noise voltage PWM chopper by two microcontroller PWM outputs using its simple standalone mode. This way, a motor can be moved very smoothly at high microstep resolution without any noise.
Slope Control	Programmable slope control reduces electromagnetic emissions.
Oscillator and Clock Selector	Oscillator and clock selector provide the system clock from the on-chip oscillator or an external source.

1.2 Control Interfaces

There are two control interfaces from the motion controller to the motor driver: the SPI serial interface and the classical analog interface.

1.2.1 SPI Interface

The SPI interface is used to write control information to the chip and read back status information. This interface must be used to initialize parameters and modes necessary to enable driving the motor. This interface may also be used for directly setting the currents flowing through the motor coils. The motor can be controlled through the SPI interface alone.

The SPI interface is a bit-serial interface synchronous to a bus clock. For every bit sent from the bus master to the bus slave, another bit is sent simultaneously from the slave to the master. Communication between an SPI master and the TMC236 slave always consists of sending one 12-bit command word and receiving one 12-bit status word.

The SPI command rate typically corresponds to the microstep rate at low velocities. At high velocities, the rate may be limited by CPU bandwidth to 10,000 to 100,000 commands per second, so the application may need to change to fullstep resolution.

1.2.2 Classical Non-SPI Control Mode (Standalone Mode)

The driver can be controlled by analog current control signals and digital phase signals.

2 Pin Assignments

2.1 Package Outline
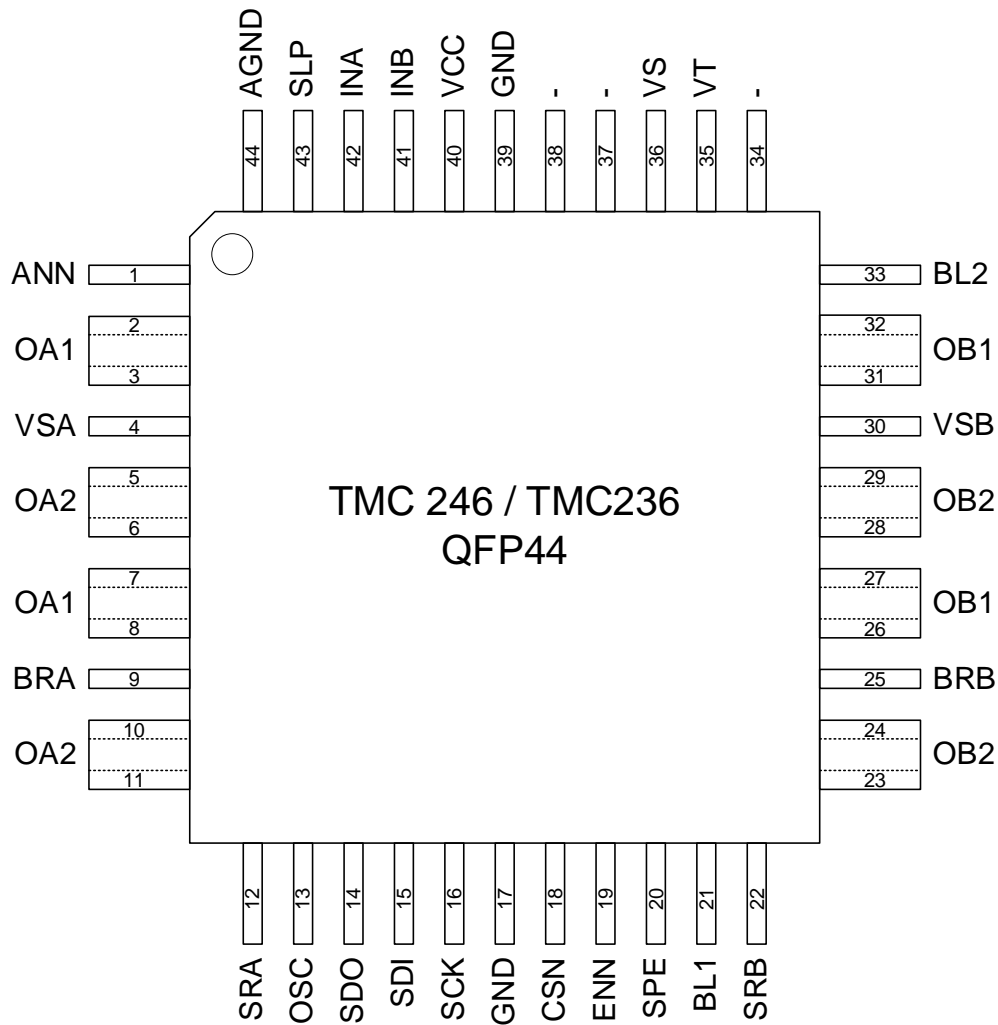
Figure 2.1 TMC236 pin assignments

2.2 Signal Descriptions

Pin	Pin	Function
AGND	44	Analog ground (reference for SRA, SRB, OSC, SLP, INA, INB, SLP)
INA	42	Analog current control phase A
INB	41	Analog current control phase B
GND	17, 39	Digital and power GND
OSC	13	Oscillator capacitor or external clock input for chopper
OA1	2, 3	Output and heat slug of high side P-channel transistors
OA2	5, 6	Tie to same net of N-channel output.
OB1	31, 32	Provide identical size heat slug on each of the pins with as much
OB2	28, 29	area as possible.
OA1	7, 8	Output and heat slug of low side N-channel transistors
OA2	10, 11	Tie to same net of P-channel output.
OB1	26, 27	Provide identical size heat slug on each of the pins with as much
OB2	23, 24	area as possible.
BRA	9	Bridge A / B foot point. Tie to sense resistor using wide and straight
BRB	25	trace.
SRA	12	Bridge A / B current sense resistor input

Pin	Pin	Function
SRB	22	Tie to positive side of sense resistor.
SDO	14	Data output of SPI interface (tri-state)
SDI	15	Data input of SPI interface
SCK	16	Serial clock input of SPI interface
CSN	18	Chip select input of SPI interface
SPE	20	Enable SPI mode (high active). Tie to GND for non-SPI applications
SLP	43	Slope control resistor. Tie to GND for fastest slope
ENN	19	Device enable (low active) and overvoltage shutdown input
ANN	1	Enable analog current control via INA and INB (low active)
BL1	21	Digital blank time select
BL2	33	
VS	1	Motor supply voltage
VSA	4	Supply voltage for bridge A/B.
VSB	30	Tie to VS voltage. Use wide trace for connection.
VCC	40	3.0… 5.5V supply voltage for analog and logic circuits
VT	35	Short to GND detection comparator – connect to VS if not used

3 SPI Interface

To drive a motor in SPI mode, the TMC236 requires setting current absolute values and polarity for each microstep. The resulting curves for both coils shall describe a sine and a cosine wave. Toggling just the polarities gives fullstepping. The SPI interface also allows reading back status values and bits.

3.1 Bus Signals

The SPI bus on the TMC236 has five signals:

SCK	bus clock input
SDI	serial data input
SDO	serial data output
CSN	chip select input (active low)
ENN	enable input has to be active (low) in order to use SPI

The slave is enabled for an SPI transaction by a low on the chip select input CSN. Bit transfer is synchronous to the bus clock SCK, with the slave latching the data from SDI on the rising edge of SCK and driving data to SDO following the falling edge. The most significant bit is sent first. A minimum of 12 SCK clock cycles is required for a bus transaction with the TMC236.

If more than 12 clocks are driven, the additional bits shifted into SDI are shifted out on SDO after a 12-clock delay through an internal shift register. This can be used for daisy chaining multiple chips.

CSN must be low during the whole bus transaction. When CSN goes high, the contents of the internal shift register are latched into the internal control register and recognized as a command from the master to the slave. If more than 12 bits are sent, only the last 12 bits received before the rising edge of CSN are recognized as the command.

The SPI data word sets the current and polarity for both coils. By applying consecutive values, describing a sine and a cosine wave, the motor can be driven in microsteps. Every microstep is initiated by its own telegram. Please refer to the description of the analog mode for details on the waveforms required. The SPI interface timing is described in the timing section.

We recommend the TMC429 or TMC4361A to automatically generate the microstepping sequence and motor ramps for up to three motors.

SERIAL DATA WORD TRANSMITTED TO TMC236

MSB TRANSMITTED FIRST

Bit	Name	Function	Remark
11	MDA	Mixed decay enable phase A	1 = mixed decay
10	CA3	Current bridge A.3	MSB
9	CA2	Current bridge A.2	
8	CA1	Current bridge A.1	
7	CA0	Current bridge A.0	LSB
6	PHA	Polarity bridge A	0 = current flow from OA1 to OA2
5	MDB	Mixed decay enable phase B	1 = mixed decay
4	CB3	Current bridge B.3	MSB
3	CB2	Current bridge B.2	
2	CB1	Current bridge B.1	
1	CB0	Current bridge B.0	LSB
0	PHB	Polarity bridge B	0 = current flow from OB1 to OB2

SERIAL DATA WORD TRANSMITTED FROM TMC236

MSB TRANSMITTED FIRST

Bit	Name	Function	Remark
11	-	Always 0 for TMC236	Not used for TMC236
10	-	Always 0 for TMC236	
9	-	Always 0 for TMC236	
8	1	Always 1	
7	OT	Overtemperature	1 = Chip off due to overtemperature
6	OTPW	Temperature prewarning	1 = Prewarning temperature exceeded
5	UV	Driver undervoltage	1 = Undervoltage on VS
4	OCHS	Overcurrent high side	3 PWM cycles with overcurrent within 63 PWM cycles
3	OLB	Open load bridge B	Target current not reached within 14 oscillator cycles
2	OLA	Open load bridge A	Target current not reached within 14 oscillator cycles
1	OCB	Overcurrent bridge B low side	3 PWM cycles with overcurrent within 63 PWM cycles
0	OCA	Overcurrent bridge A low side	3 PWM cycles with overcurrent within 63 PWM cycles

> *Note*:
> - The current values correspond to a standard 4 Bit DAC, where 100% = 15/16.
> - The content of all registers is cleared to 0 on power-on reset or disable via the ENN pin, bringing the IC to a low power standby mode.
> - All SPI inputs have Schmitt-Trigger function.

3.2   Motor Coil Current Setting via SPI

Current Setting CA3..0 / CB3..0	Percentage of Current	TYPICAL TRIP VOLTAGE OF THE CURRENT SENSE COMPARATOR - INTERNAL REFERENCE OR ANALOG INPUT VOLTAGE OF 2V IS USED -
0000	0%	0 V (bridge continuously in slow decay condition)
0001	6.7%	23 mV
0010	13.3%	45 mV
...	...	
1110	93.3%	317 mV
1111	100%	340 mV

3.3   Base Current Control Mode via INA / INB in SPI Mode

In SPI mode the IC can use an external reference voltage for each DAC. This allows the adaptation to different motors.

> *Note*:
> - This *Base Current Control Mode* is enabled by tying pin ANN to GND.
> - A 2.0 V input voltage V_{IN} gives full scale current of 100%, corresponding to the internal reference voltage.
> - The range for V_{IN} is 0…3V. Min. 1 V recommended for best microstepping.
> - The trip voltage of the current sense comparator is determined by the input voltage V_{IN} and the DAC current setting (see table above).
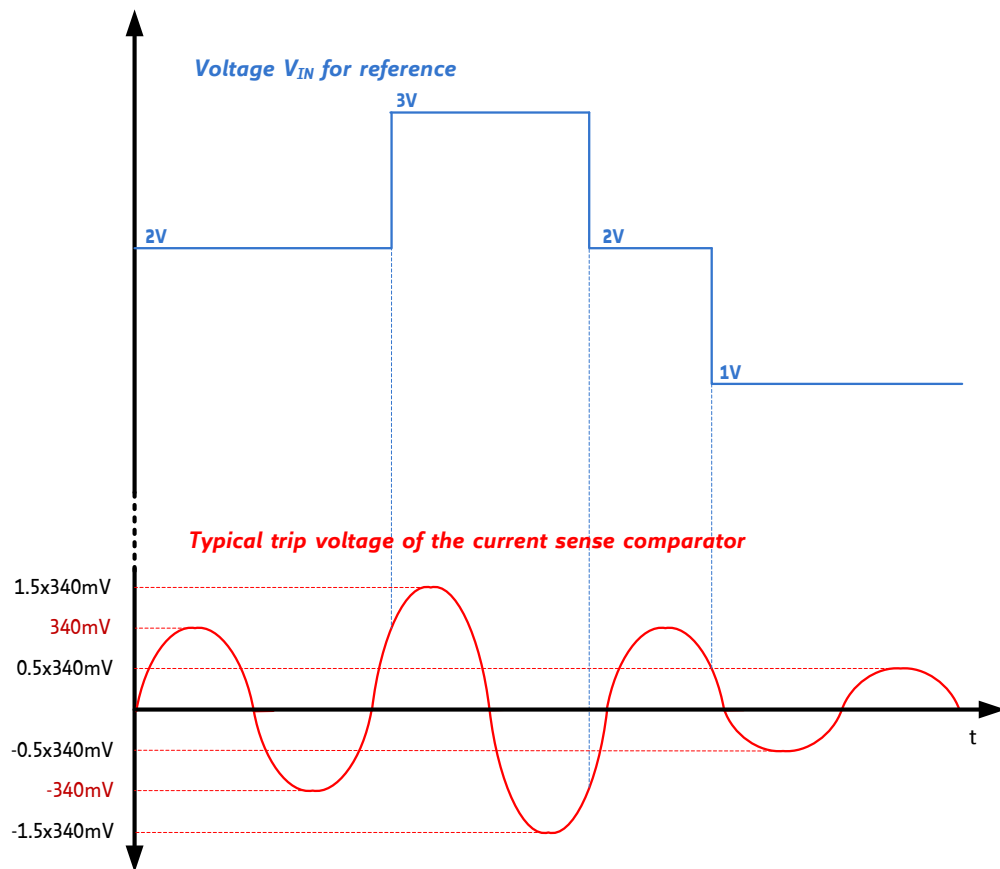
Figure 3.1 Relation between V_{IN} and trip voltage of current sense comparator

IN CASE A VARIABLE INPUT VOLTAGE V_{IN} IS USED THE TYPICAL TRIP VOLTAGE IS CALCULATED:

$V_{TRIP,A}$ = 0.17 V_{INA} × percentage SPI current setting A
$V_{TRIP,B}$ = 0.17 V_{INB} × percentage SPI current setting B

GENERATING INPUT VOLTAGE V_{IN}

A maximum of 3.0V V_{IN} is possible. Multiply the percentage of base current setting and the DAC table to get the overall coil current. It is advised to operate at a high base current setting, to reduce the effects of noise voltages. This feature allows a high-resolution setting of the required motor current using an external DAC or PWM-DAC (see schematic for examples). Consider INA and INB input resistance of typically 264kΩ.

Figure 3.2 External DAC and PWM-DAC

3.4   Controlling Power Down via the SPI Interface

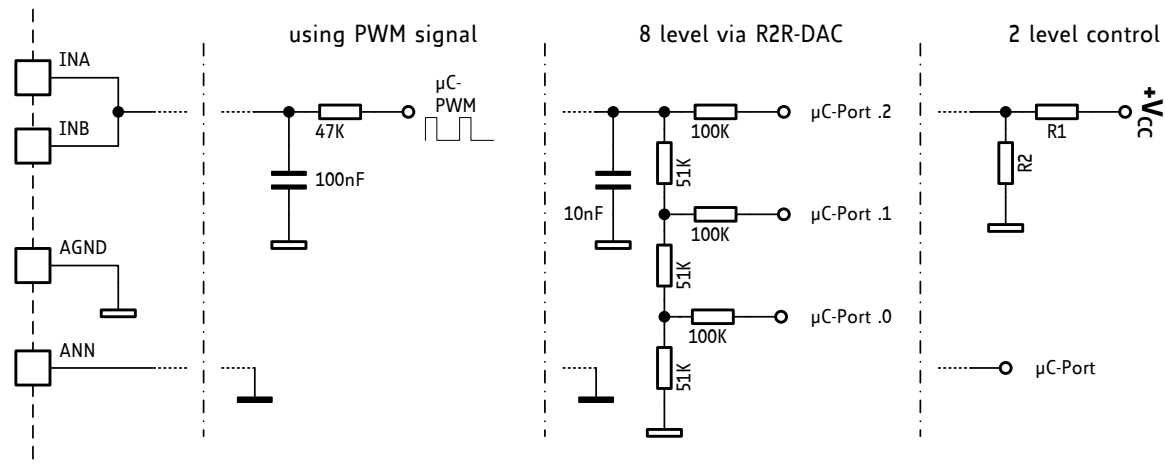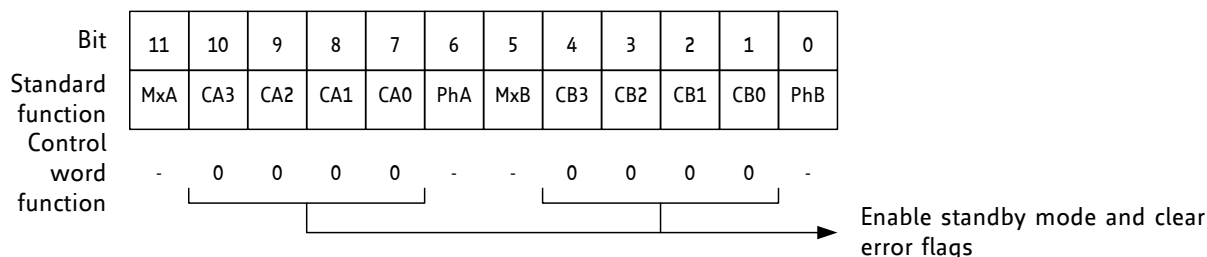| Bit	11	10	9	8	7	6	5	4	3	2	1	0
Standard function	MxA	CA3	CA2	CA1	CA0	PhA	MxB	CB3	CB2	CB1	CB0	PhB
Control word function	-	0	0	0	0	-	-	0	0	0	0	-

Enable standby mode and clear error flags

> Programming current value 0000 for both coils at a time clears the overcurrent flags and switches the TMC236 into a low current standby mode with coils switched off.

3.5   Open Load Detection

Open load is signaled when the IC is not able to reach the target current (trip point of comparator) within more than 14 oscillator cycles. During overcurrent, undervoltage, or overtemperature conditions, the open load flags also become active. The flag has a purely informative character.

> *Attention*
> Open load detection is disabled for each coil, while the coil current is set to 0000. In this condition the chopper is off, and the open load flag is read as inactive (0).

> To detect an interruption of the connection to the motor, evaluate the open load flags during stand still at a position where both motor coils have a minimum current, or during low velocities only (e.g., for the first or last steps of a movement). The open load flags might also come active due to a torque loss of the motor, especially at high motor velocities, or when working with fullstepping or coarse microstep resolution.

3.6   Standby and Shutdown Mode

The TMC236 offers two possibilities for reducing power consumption under special conditions: the standby mode and the shutdown mode.

STANDBY MODE
-   The circuit automatically goes to standby on VCC undervoltage conditions.
-   Activate standby mode via the interface in SPI-mode and via the ENN pin in non-SPI mode.

Before entering standby mode, the TMC236 switches off the power stage and the outputs go floating. In standby mode the oscillator becomes disabled, and the oscillator pin is held at a low state.

SHUTDOWN MODE
-   The shutdown mode is used for a further reduction of the supply current.
-   The shutdown mode can be entered in SPI-mode by pulling the ENN pin high.
-   In shutdown mode additionally all internal reference voltages become switched off and the SPI circuit is held in reset.

3.7   Power Saving

The possibility to control the output current can dramatically save energy, reduce heat generation, and increase precision by reducing thermal stress on the motor and attached mechanical components. Just reduce motor current during stand still: A slight reduction of the coil currents to 70% of the current of the last step halves power consumption!

> In typical applications a 50% current reduction during stand still is reasonable.

3.8 Bus Timing

The SPI interface operates completely asynchronous. It is clocked by SCK and CSN, only. Figure 3.3 shows the timing parameters of an SPI bus transaction, and the table below specifies their values.
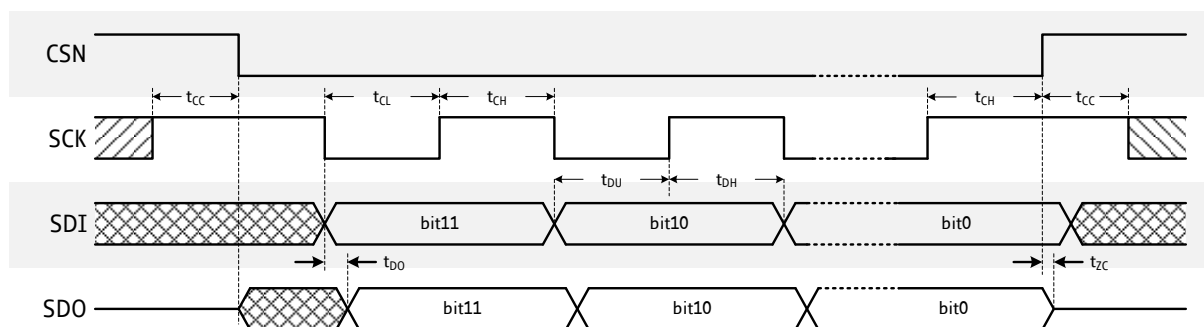

Figure 3.3 SPI Timing

PROPAGATION TIMES

$(3.0 \text{ V} \leq \text{VCC} \leq 5.5 \text{ V}, -40°C \leq \text{Tj} \leq 150°C; V_{IH} = 2.8V, V_{IL} = 0.5V; \text{tr, tf} = 10\text{ns}; C_L = 50\text{pF}$, unless otherwise specified)

SPI Interface Timing		AC-Characteristics clock period is t_{CLK}					
Parameter	Symbol	Conditions	Min	Typ	Max	Unit
SCK frequency	f_{SCK}	ENN = 0	DC	1…5	8	MHz
SCK stable before and after CSN change	t_1		50			ns
Width of SCK high pulse	t_{CH}		100			ns
Width of SCK low pulse	t_{CL}		100			ns
SDI setup time	t_{DU}		40			ns
SDI hold time	t_{DH}		50			ns
SDO delay time	t_D	C_L = 50pF		40	100	ns
CSN high to SDO high impedance	t_{ZC}	*)	50			ns
ENN to SCK setup time	t_{ES}		30			µs
CSN high to OA/OB output polarity change delay	t_{PD}	**)		3	t_{OSC} + 4	µs

*) SDO is tri-stated whenever ENN is inactive (high) or CSN is inactive (high).
**) Whenever the PHA / PHB polarity is changed, the chopper is restarted for that phase. The chopper does not switch on, when the SRA resp. SRB comparator threshold is exceeded upon the start of a chopper period.

3.9 Using the SPI Interface with One or Multiple Devices

The SPI interface allows either cascading of multiple devices, giving a longer shift register, or working with a separate chip select signal for each device, paralleling all other lines. Even when there is only one device attached to a CPU, the CPU can communicate with it using a 16-bit transmission. In this case, the upper 4 bits are dummy bits. With two devices in a chain, a 24-bit transmission controls both.

3.10 SPI Filter

To prevent spikes from changing the SPI settings, SPI data words are only accepted, if their length is at least 12 bit. Shorter datagrams are ignored and will not modify register content.

4 Classical Non-SPI Control Mode (Standalone Mode)

The driver can be controlled by analog current control signals and digital phase signals.

Proceed as follows:

- Tie pin SPE to GND for enabling non-SPI mode. In non-SPI mode the SPI interface is disabled, and the SPI input pins have alternate functions.
- The internal DACs are forced to 1111.

4.1 Pin Functions in Standalone Mode

Pin	Standalone mode name	Function in standalone mode
SPE	(GND)	Tie to GND to enable standalone mode
ANN	MDAN	Enable mixed decay for bridge A (low = enable)
SCK	MDBN	Enable mixed decay for bridge B (low = enable)
SDI	PHA	Polarity bridge A (low = current flow from output OA1 to OA2)
CSN	PHB	Polarity bridge B (low = current flow from output OB1 to OB2)
SDO	ERR	Error output (high = overcurrent on any bridge, or over temperature). In this mode, the pin is never tri-stated.
ENN	ENN	Standby mode (high active), high causes a low power mode of the device. Setting this pin high also resets all error conditions.
INA, INB	INA, INB	Current control for bridge A, resp. bridge B. Refer to AGND. The sense resistor trip voltage is 0.34V when the input voltage is 2.0V. Maximum input voltage is 3.0V.

4.2 Input Signals for Microstep Control

> *Hint*
> When transferring these waves to SPI operation, note that the mixed decay bits are inverted when compared to standalone mode.
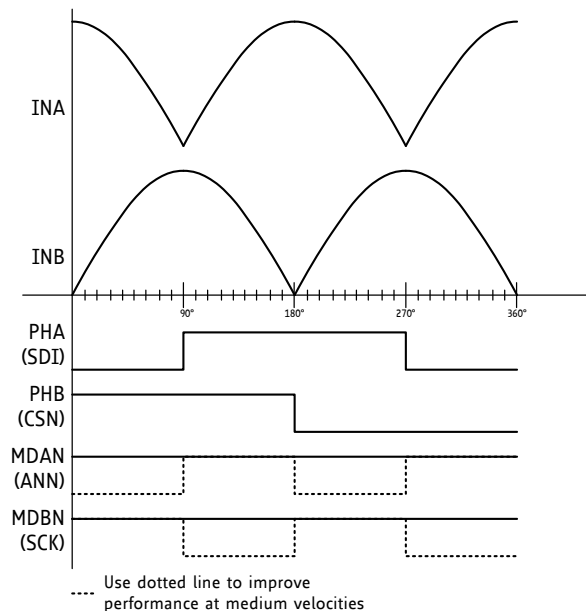

Figure 4.1 Analog control for standalone mode

5   Current Setting

5.1   Sense Resistor for Current Setting

Choose an appropriate sense resistor R_S for setting the desired motor current.

> Basic information:
> - The maximum motor current is reached when the coil current setting is programmed to 1111.
> - This results in a current sense trip voltage of 0.34V if the internal reference or a reference voltage of 2V is used (up to 3V possible). (Refer to chapter 3.3 for more information about current setting in SPI mode.)
> - The current sense resistor of bridge A, B is calculated as:
>
> R_{SENSE} = V_{TRIP} / I_{max}
>
> R_{SENSE} Current sense resistor of bridge A, B
> V_{TRIP} Programmed trip voltage of the current sense comparators
> I_{max} Desired maximum coil current

Mode of operation	Maximum motor current
Operation in fullstep mode	The maximum motor current is specified by the manufacturer.
Operation in microstep mode	Multiply the value for fullstep mode by 1.41 for the maximum current I_{max}.

EXAMPLE FOR TYPICAL APPLICATION

R_{SENSE} = 0.34V / I_{max}

SENSE RESISTOR EXAMPLES AND RESULTING I_{MAX} AT 100% CURRENT SCALING (INA/INB=2V, OR INTERNAL REFERENCE)

R_S	I_{max}
0.47Ω	723mA
0.43Ω	790mA
0.39Ω	870mA
0.33Ω	1030mA
0.27Ω	1259mA
0.22Ω	1545mA

5.2   Resistor R_{SH} for High Side Overcurrent Detection

The TMC236 detects an overcurrent to ground, when the voltage between VS (supply voltage) and VT (threshold voltage) exceeds 150mV. The high side overcurrent detection resistor should be chosen in a way that 100mV voltage drop are not exceeded between VS and VT, when both coils draw the maximum current. In a microstep application, this is the case when sine and cosine wave have their highest sum, i.e., at 45 degrees electrical angle. This corresponds to 1.41 times the maximum current setting for one coil. In a fullstep application it equals the double coil current.

IN A MICROSTEP APPLICATION:

R_{SH} = 0.1V / (1.41 $\times$ I_{max})

IN A FULLSTEP APPLICATION:

R_{SH} = 0.1V / (2 $\times$ I_{max})

R_{SH}:   High side overcurrent detection resistor
I_{max}:   Maximum coil current

If higher resistance values are desired, a voltage divider in the range of 10Ω to 100Ω can be used for VT. This might also be desired to limit the peak short to GND current, as described in the following chapter.

> *A careful PCB layout is required for the sense resistor traces and for the R_{SH} traces.*

5.2.1 Making the Circuit Short Circuit Proof

In most applications, a short circuit does not describe only one special condition. It typically involves inductive, resistive, and capacitive components. Worst events are unclamped switching events, because huge voltages can build up in inductive components and result in a high energy spark going into the driver, which can destroy the power transistors.

Attention
Never disconnect the motor during operation as this can destroy the power transistors!

An absolute protection against random short circuit conditions is not given, but pre-cautions can be taken to improve robustness of the circuit:

In a short condition, the current can become very high before it is interrupted by the short detection, due to the blanking during switching and internal delays. The high-side transistors allow a high current flowing for the selected blank time. The lower the (remaining) external inductivity, the faster the current climbs. If inductive components are involved in the short, the same current will shoot through the low-side resistor and cause a high negative voltage spike at the sense resistor. *Both, the high current and the voltage spikes are dangerous for the driver.*

PROCEED AS FOLLOWS, IF SHORT CIRCUITS ARE EXPECTED:
1. Protect SRA/SRB inputs using a series resistance.
2. Increase R_{SH} (high side overcurrent detection resistor) to reduce the maximum high-side transistor current. Use the same value as for the sense resistors.
3. Set the blank time as short as possible.

The second point effectively limits the short circuit current, because the upper driver transistor with fixed ON gate voltage of 6V forms a constant current source together with its internal resistance and the high side overcurrent detection resistor R_{SH}.

A positive side effect is that only one type of low resistive resistor is required.
The drawback is that power dissipation increases.
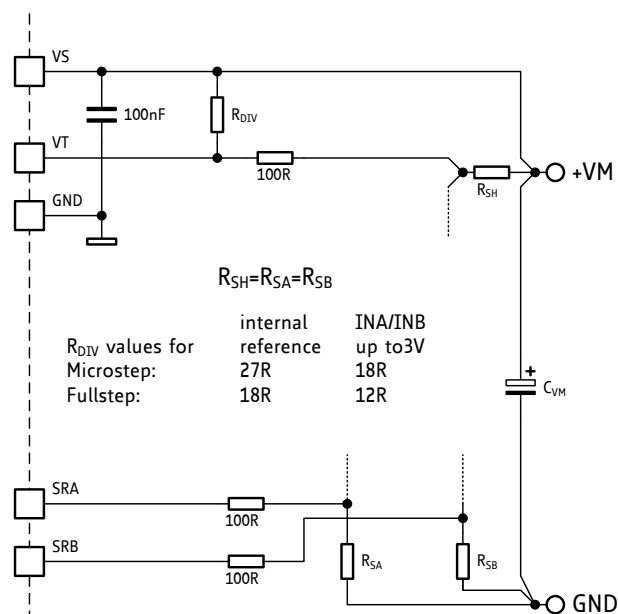
Example:

A 0.33 Ohms sense resistor allows for roughly 1 A motor coil current.
A high side short detection resistor of 0.33 Ohms limits maximum high side transistor current to typically 4A during a short circuit condition. The schematic shows the modifications to be done.

The effectiveness of the steps described above should be tested in the given application!

Figure 5.1 Schematic with $R_{SH}=R_{SA}=R_{SB}$

6   Chopper Operation

The currents through both motor coils are controlled using a chopper. The TMC236 uses a quiet fixed frequency chopper. Both coils are chopped with a phase shift of 180 degrees. The chopper cycles through three phases: on, fast decay, and slow decay.
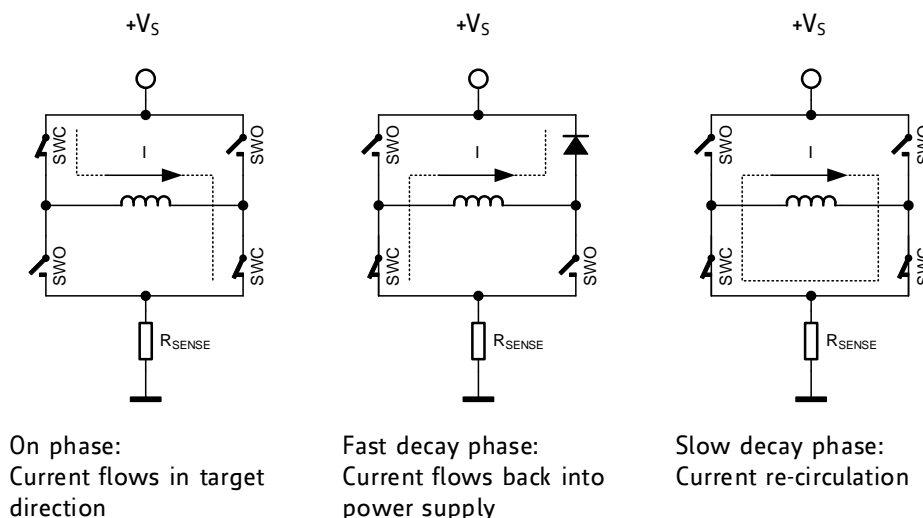

On phase:
Current flows in target direction

Fast decay phase:
Current flows back into power supply

Slow decay phase:
Current re-circulation

Figure 6.1 Chopper phases

Fast decay switches off both upper transistors and uses the body diodes to re-circulate current back to the supply, while enabling the lower transistor opposite to the selected polarity. Slow decay always enables both lower side transistors.

When the polarity is changed on one bridge, the PWM cycle on that bridge becomes restarted at once.

6.1   Mixed Decay Mode

The mixed decay option is realized as a self-stabilizing system, by shortening the fast decay phase, if the ON phase becomes longer. Mixed decay can be used continuously on, continuously off, or in a mixed fashion during periods of falling absolute current, only.

> To reduce motor resonance, enable mixed decay for each coil individually during the second half of each microstepping half-wave, when the current is meant to decrease.

MIXED DECAY IN APPLICATIONS WITH HIGH RESOLUTION OR LOW INDUCTIVITY MOTORS
In applications requiring high resolution, or using low inductivity motors, the mixed decay mode should be enabled continuously to reduce the minimum motor current which can be achieved. This gives the smoothest current wave.

USING MIXED DECAY CONTINUOUSLY OR WITH HIGH INDUCTIVITY MOTORS AT LOW SUPPLY VOLTAGE
If mixed decay mode is continuously on or high inductivity motors are used at low supply voltage, it is advised to raise the chopper frequency to minimum 36 kHz, because the half chopper frequency could become audible.

> *With low velocities or during standstill, mixed decay should be switched off.*
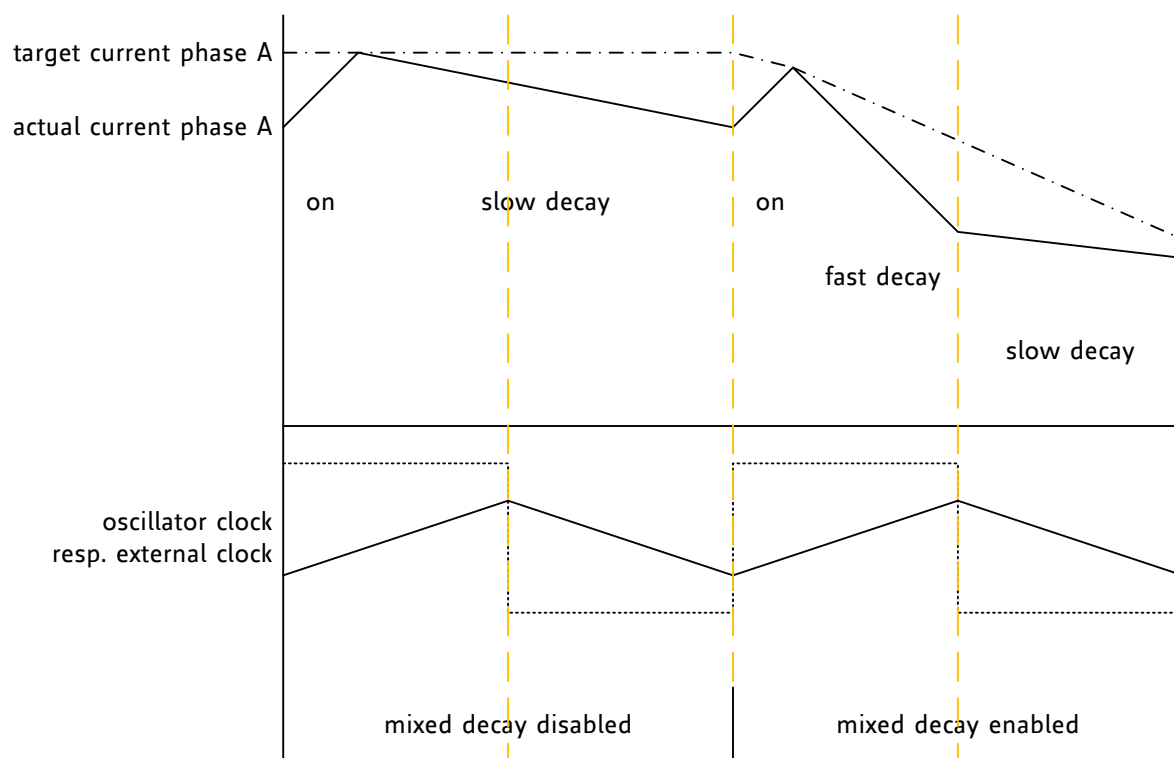
Figure 6.2 Chopper cycle showing use of mixed decay with falling current

6.2   Chopper Frequency

The PWM oscillator frequency can be set by an external capacitor. The internal oscillator uses a 28kΩ resistor to charge / discharge the external capacitor to a trip voltage of 2/3 VCC respectively 1/3 VCC. It can be overdriven using an external CMOS level square wave signal. Do not set the frequency higher than 100 kHz and do not leave the OSC terminal open! The two bridges are chopped with a phase shift of 180 degrees at the positive and at the negative edge of the clock signal.

The PWM oscillator frequency is calculated as: $f_{OSC} = \frac{1}{40\mu s \times C_{OSC}\,[nF]}$

f_{OSC}:   PWM oscillator frequency
C_{OSC}:   Oscillator capacitor in nF

OSCILLATOR FREQUENCIES

f_{OSC} typ.	C_{OSC}	Recommendation
16.7kHz	1.5nF	-
20.8kHz	1.2nF	Low dynamic loss for slow decay operation
25.0kHz	1.0nF	Good choice for slow decay
30.5kHz	820pF	-
36.8kHz	680pF	Most universal balanced choice with slow and mixed decay regarding chopper noise and power dissipation
44.6kHz	560pF	Most silent choice for mixed decay, half frequency components far outside audible range

An unnecessary high frequency leads to high switching losses in the power transistors.
For many applications a chopper frequency slightly above audible range is sufficient. When audible noise occurs in an application, especially with mixed decay continuously enabled, the chopper frequency should be *two times* the audible range, i.e., min. 36kHz, because the mixed decay operation often generates current jitter components with half chopper frequency.

6.3   CPU controlled Low Noise Voltage Mode PWM

This chapter describes an optional chopper method requiring two CPU PWM outputs.

The TMC236 uses a cycle-by-cycle based chopper system, because it brings the best performance over a wide range of velocities. It regulates the current by terminating each chopper cycle as soon as the target current has been reached. This direct current regulation provides good dampening of motor resonance, low motor power loss and automatic adaptation to the specific motor. On the other hand, chopper stability requires good decoupling between both motor coils, and it needs a precise layout of the high current paths. Instabilities caused by magnetic coupling in the motor or by coupling of the coil current regulators due to electric coupling can lead to chopper noise and fine vibrations. Under normal conditions, these will not do any harm. *In applications, where the motor moves very slowly or where precise standstill with low mass on the motor axis is required, a voltage PWM chopper is a good choice.*

The low noise feed forward chopper principle uses a voltage PWM controlled driving rather than current controlled driving. This is possible because the stepper motor has a certain coil resistance. This resistance converts an externally applied voltage to current. As long as the motor velocity is low, back EMF caused by the motor rotation does not need to be taken into account. At increasing velocities, the motors back EMF has an increasing influence and influences coil current. This can be compensated by increasing the driver voltage with increasing velocity. Effects like motor temperature dependency of the coil resistance should be considered, in case the motor operates in an increased temperature range. The described compensation principle can be realized in a completely feed-forward way, based on the motor data, or by measuring the effective current and adding a regulation loop.

The chopper principle described generates a certain motor voltage by toggling each motor phase with a certain PWM frequency. Therefore, the motor full bridges either switch on the motor current in one direction or in the opposite direction.

This way, the duty cycle of toggling the coil polarity produces a certain effective voltage on the coils:
-   A 50 percent duty cycle gives a mean current of zero.
-   A higher or lower duty cycle gives a positive or negative current.
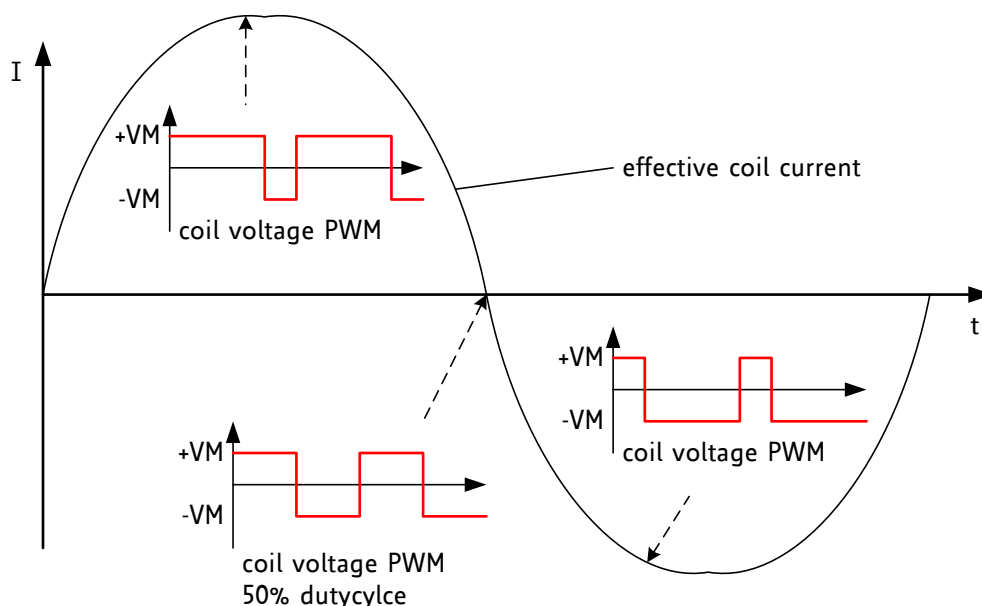-   A high PWM resolution will bring a high microstep resolution.

Figure 6.3 Voltage PWM generates motor current

6.3.1   Calculating the PWM for Low Noise Chopper

A microcontroller with PWM outputs can be used for generating the two PWMs required to drive the motor. For a 256 microstep resolution a PWM resolution of 9 to 10 bit is required. Assuming a target

chopper frequency of roughly 20 kHz, a base clock frequency of 20 MHz (=2^{10} x 20 kHz) is required to yield a 10-bit PWM. A 16 MHz clock frequency will allow realizing a 9-bit PWM with 31 kHz, or a resolution of 800 PWM steps with 20 kHz. This is a feasible value for most standard 8 bit or better microcontrollers.

Basically, one motor coil is driven with a PWM, which duty cycle is modulated using a sine wave. The second coil with a cosine modulated PWM. Assuming, that the system supply voltage would exactly match the motor voltage required for nominal current, the PWM duty cycle will be altered between 100% for maximum positive current and 0% for maximum negative current. As this is not a typical constellation, the PWM modulation required to match the motor needs to be calculated.

The PWM modulation is calculated as:

$$PWMAmpl = I_{COILpeak} \frac{R_{COIL}}{(V_M - V_{BEMF})}$$

PWMAmpl	PWM amplitude required to reach the nominal motor current. Half of this amplitude is applied in positive direction (additional to 50% duty cycle), and half of it is applied in negative direction (subtracted from 50% duty cycle)
$I_{COILpeak}$	Nominal peak coil current of the motor, i.e., $I_{COILRMS}$ * 1.41
R_{COIL}	Resistance of the motor coil
V_M	Motor driver supply voltage (may be measured in the application)
V_{BEMF}	Velocity dependent back EMF voltage of the motor. It is measured in V/rad/s. At standstill V_{BEMF} is zero and can be ignored for low RPM. For higher velocities, multiply it by the angular velocity of the motor.

EXAMPLE

A 1A RMS motor with 6.5Ohm coil resistance is to be operated from a 12V supply at low velocity.

$$1A * 1.41 \frac{6.5\Omega}{(12V - 0V)} = 0.76$$

Therefore, the duty cycle needs to be modulated between 0.5 + 0.76/2 = 88% for the positive sine wave peak and 0.5 - 0.76/2 = 12% for the negative sine wave peak.

6.3.2 Hardware Setup for Low Noise Chopper

The TMC236 provides a standalone mode, which allows direct control of coil polarity using a digital signal. Further, the coil current can be controlled using an analog voltage in the range 0 V… 3 V.
As current control is done by PWM duty cycle, the integrated PWM based analog current control of the IC is not used. Therefore, in principle it would be possible to work without sense resistors.

We recommend using the analog current limit as a safety feature. Further it can be used for allowing a fallback to classical fullstepping at higher velocity (to also allow faster movements):
During voltage PWM mode the analog current control can be used to limit the motor current in case of an error. Therefore, the current limit must be set at least 20% to 30% higher than the desired maximum motor current for PWM operation (peak current value plus additional ripple). The mixed decay mode must be switched off (MDAN=MDBN=VCC) because it would interfere with voltage PWM operation. *Both motor coil limits can be set to the same analog current limiting value: for a safety limit and for a change to fullstepping.*
In fullstepping switching to a lower value may be desired in order to match motor RMS current.

The processor controlled PWM uses the polarity inputs (PHA, PHB) for both coils to control motor PWM.
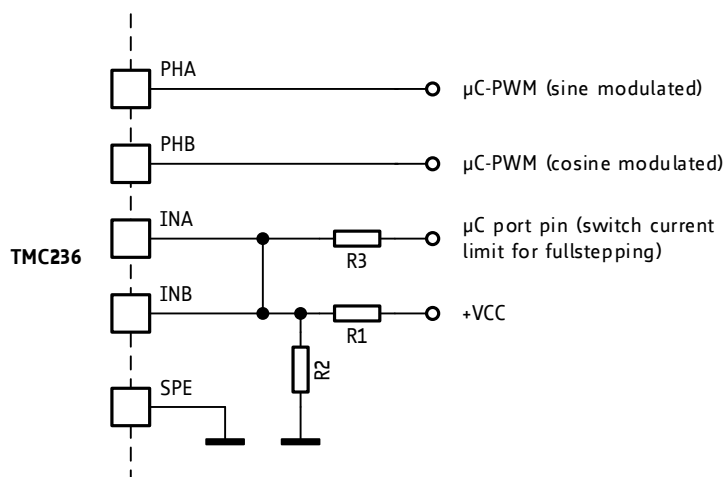
Figure 6.4 Controlling the driver with two PWMs in standalone mode

6.4 Adapting the Sine Wave for Smooth Motor Operation

An optimization of the sine wave improves microstepping and vibration for both, mixed decay mode and voltage PWM mode. Despite reaching the target current in each chopper cycle, both, the slow decay and the fast decay cycle reduce the current by some amount. Especially the fast decay cycle has a larger impact. Thus, the medium coil current always is a bit lower than the target current. This leads to a flat line in the current shape flowing through the motor. It can be corrected, by applying an offset to the sine shape. In mixed decay operation via SPI, an offset of 1 does the job for most motors.
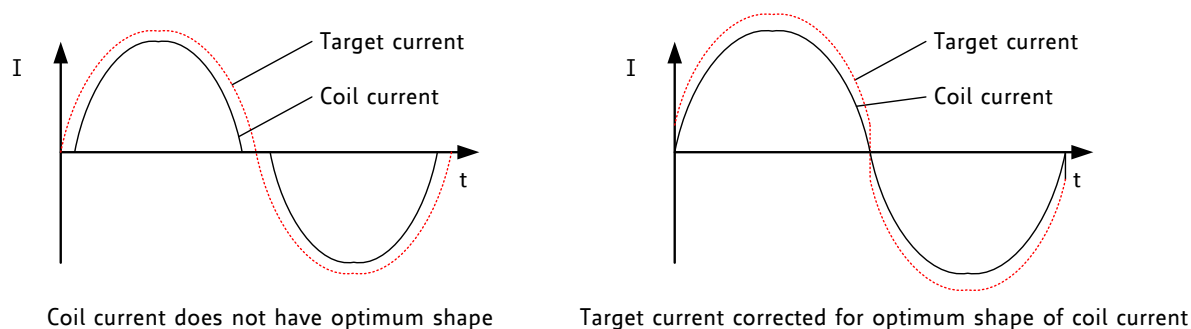

Coil current does not have optimum shape

Target current corrected for optimum shape of coil current

Figure 6.5 Adapting sine wave for smooth motor operation

Try out the best wave offset for the target motor to yield equidistant microstepping and vibration-free motion.

6.5 Blank Time

The TMC236 uses a digital blanking pulse for the current chopper comparators. This prevents the driver to react to current spikes, which can occur during switching action due to capacitive loading, by terminating the chopper cycle.

The lowest possible blanking time covering all spikes gives the best results for microstepping. A long blank time leads to a long minimum turn-on time, thus giving an increased minimum PWM duty cycle and with this an increased lower limit for the coil current. This negatively impacts microstep precision.

> *Hint*
> The blank time should cover both, switch time of driver MOSFETs and inductive ringing in the sense resistors and layout and any current ringing in the coils resulting from capacitive loads, e.g., in motor coil capacity or cable capacity. Choose blank time as low as possible to yield this.

The TMC236 allows adapting the blank time to the load conditions and to the selected slope in four steps:

BLANK TIME SETTINGS

BL2	BL1	Typical blank time	Remarks
GND	GND	0.6 µs	Very short. May require additional filtering on SRA and SRB.
GND	VCC	0.9 µs	Works well in low inductivity layouts.
VCC	GND	1.2 µs	Default for most applications.
VCC	VCC	1.5 µs	May be used with slow bridges or high sense resistor trace inductivity.

7 Slope Control

The driver offers a motor output slope control to yield low electromagnetic emission. The output-voltage slopes of the full bridges are controlled by a constant current gate charge / discharge of the internal driver MOSFETs. The slope is set by a single resistor: a reference current is generated by internally pulling the SLP-Pin to 1.25V via an integrated 4.7KΩ series resistor. The resulting current is used to generate the current for switching on and off the power transistors and with this results in a certain switching slope. The SLP-pin can directly be connected to AGND for the fastest output-voltage slope (respectively maximum output current). The following table and graph depict typical behavior measured from 15% of output voltage to 85% of output voltage. However, the actual values measured in an application depend on multiple parameters and may stray in a user application.

t_{SLP} typ.	R_{SLP}	Recommendation
25ns	0	Lowest power dissipation for high chopper frequency
30ns	2.2KΩ	
60ns	10KΩ	Choice of low power dissipation for high motor current and reduced slopes for lower emission
110ns	22KΩ	Low emission
245ns	51KΩ	Further reduced emission slope with additional 1nF…2.2nF capacitor filtering at the motor outputs
460ns	100KΩ	Lowest emission, higher power dissipation. <800mA motor current recmd.

Note
There is a tradeoff between reduced electromagnetic emissions (slow slope) and efficiency, due to dynamic losses occurring within each switching event. With slow slopes, an increased chopper frequency drastically increases power dissipation, while the effect is low with fast slopes (<100ns). Typical emission optimized slope times range between 50ns and 200ns. For lowest power dissipation, slopes can be reduced to roughly 25ns.

For applications where electromagnetic emission is extremely critical, add LC (or capacitor only) filtering on the motor connections. This dampens the effect of MOSFET body diode reverse recovery ringing, occurring within each power MOSFET stage following a diode conduction. For these applications emission is even lower, if only slow decay operation is used.
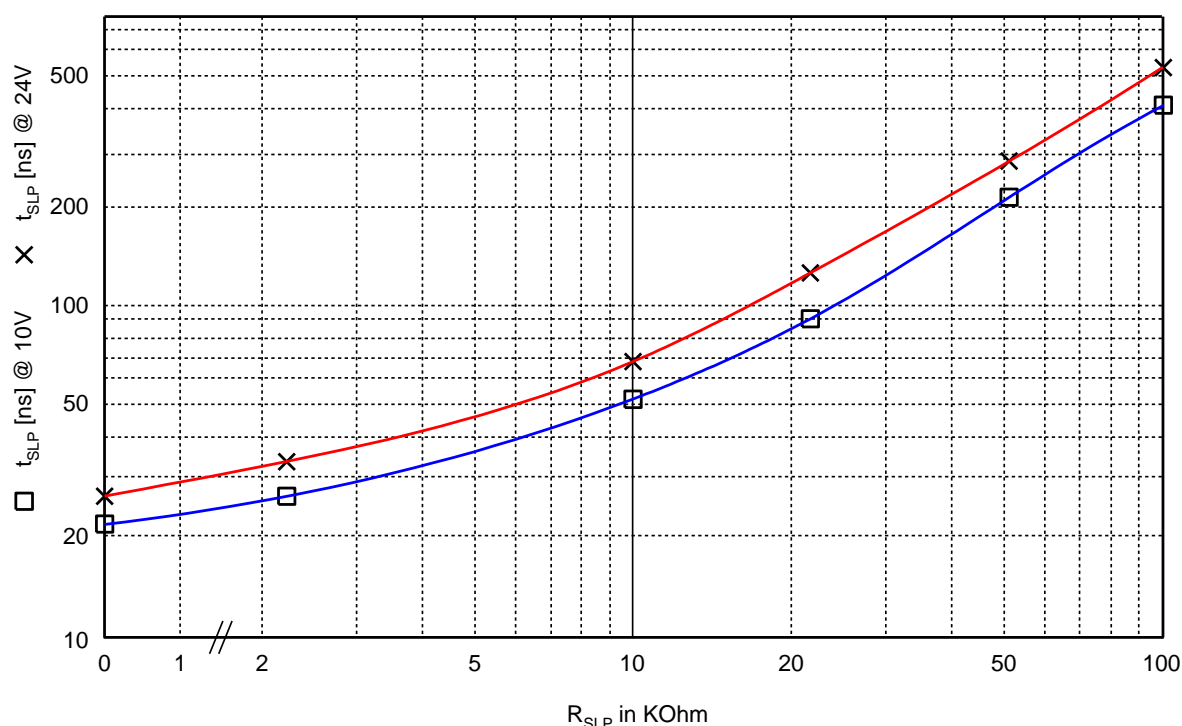

Figure 7.1 External R_{SLP} controls switching slopes

8   Protection Functions

8.1   Overcurrent Protection and Diagnostics

8.1.1 Low Side Overcurrent

The TMC236 uses the current sense resistors on the low side to detect an overcurrent. If a voltage above 0.61 V is detected after expiration of the blanking time, the PWM cycle is terminated at once and all transistors of the bridge are switched off for the rest of the PWM cycle. The error counter is increased by one. If the error counter reaches 3, the bridge remains switched off for 63 PWM cycles and the error flag is read as *active*.

CLEARING ERROR FLAG AND COUNTER

Clear the error condition in advance by clearing the error flag.
The error counter also becomes cleared, whenever there are more than 63 PWM cycles without overcurrent. There is one error counter for each of the low side bridges, and one for the high side.

> *Note*
> To suppress spikes occurring during switching, the overcurrent detection is inactive during the blank pulse time for each bridge.

8.1.2 Short to Ground and Overcurrent Detection

The high side comparator detects a short to GND or an overcurrent, whenever the voltage between VS and VT becomes higher than 0.15 V at any time (except for the blank time period which is logically ORed for both bridges). If a voltage higher than 0.15 V is detected between VS and VT, *all* transistors become switched off for the rest of the PWM cycle, because the bridge with the failure is unknown.

Determine which bridge causes the high-side overcurrent, by selectively switching on only one of the bridges with each polarity (therefore the other bridge should remain programmed to 0000).

CLEARING ERROR FLAGS

The overcurrent flags can be cleared by disabling and re-enabling the chip either via the ENN pin or by sending a telegram with both current control words set to 0000.

8.2   Overtemperature Protection and Diagnostics

The circuit switches off all output power transistors during an over temperature condition. The over temperature flag should be monitored to detect this condition. The circuit resumes operation after cool-down below the temperature threshold. However, operation near the over temperature threshold should be avoided if a high lifetime is desired.

> *Attention*
> The overtemperature protection cannot fully protect the circuit in case of thermally insufficient design or a defect of a motor coil. It mainly is intended to detect and protect against heat accumulation occurring due to high environment temperature. A more sensitive protection can be realized when checking the pre-warning flag and reacting to it by reducing motor current.

8.3   Overvoltage Protection and ENN Pin

Quick motor deceleration from high velocity can result in high energy being fed back from the motor and mechanics to the power supply. This might endanger the TMC236 or other circuitry on the PCB which is more sensitive to higher voltage. The TMC236 allows disabling the driver stage in case of excessive voltage to reduce the danger of voltage fed back:

The enable pin ENN provides a fixed threshold of ½ V_{CC} to allow a simple overvoltage protection up to 40V using an external voltage divider (see schematic).

For switch off at 26 - 29V:
at VCC=5V: R1=100K; R2=10K
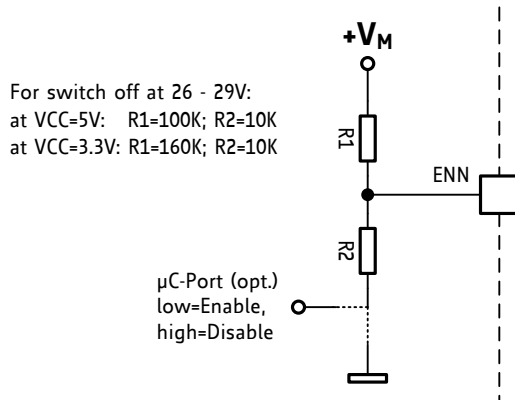at VCC=3.3V: R1=160K; R2=10K

Figure 8.1 Overvoltage protection example for limiting to 30V

However, this scheme does not prevent the supply voltage being pumped up, when the motor becomes rotated at a very high velocity where its back EMF exceeds the supply voltage rating, as the MOSFETs conduct its back-EMF to the supply rails.

9 Moving the Motor

To move the motor, send a sequence of current patterns to the driver via its SPI interface (graphical example: see 4.2). Each pattern moves the motor by one microstep. The following example shows a simple microcontroller code. An option is to use an integrated motion controller like the TMC429 or TMC4361A to automatically generate microstep patterns and motion ramps.

SINE WAVE TABLE
- The sine wave table below implements 4-bit microstepping.
- The absolute values are left-shifted by one bit.
- Bit 0 is the sign bit (phase direction bit).
- Bit 5 is the mixed decay bit. It is set when the absolute value is falling.
- Optionally set mixed decay constant off (0), or constant on (1) using an AND or OR instruction

FUNCTION
The function in the example below generates the microsteps. Values are read from the sine wave table and output to the TMC236 (via SPI interface). Call this function with the *ccw* parameter set to 1 (to step in negative direction) or with *ccw* set to 0 (to step in positive direction). The function can be called in a timer interrupt, to generate equidistant time intervals.

SENDING VALUES VIA SPI
Set the CS line low and send out the value of *io* by SPI (MSB first). Thereafter, set the CS line high again. Send out each microstep unless the interface is still busy. In case the interface is still busy, the transmission can be skipped. This way, the update rate adapts to the available SPI bandwidth at higher velocity. It does not significantly affect the motor performance with >1Mbit bandwidth.

EXAMPLE FOR GENERATING MICROSTEPS

```c
unsigned char sinus_tab[64]=
    {0x00, 0x02, 0x06, 0x08, 0x0c, 0x0e, 0x10, 0x14,
     0x16, 0x18, 0x18, 0x1a, 0x1c, 0x1c, 0x1e, 0x1e,
     0x3e, 0x3e, 0x3e, 0x3c, 0x3c, 0x3a, 0x38, 0x38,
     0x36, 0x34, 0x30, 0x2e, 0x2c, 0x28, 0x26, 0x22,
     0x01, 0x03, 0x07, 0x09, 0x0d, 0x0f, 0x11, 0x15,
     0x17, 0x19, 0x19, 0x1b, 0x1d, 0x1d, 0x1f, 0x1f,
     0x3f, 0x3f, 0x3f, 0x3d, 0x3d, 0x3b, 0x39, 0x39,
     0x37, 0x35, 0x31, 0x2f, 0x2d, 0x29, 0x27, 0x23};

volatile unsgined char PhaseCount=0;

// Call this procedure for each step and send out the resulting IO word to
// the TMC24x/TMC23x SPI interface
void step(char ccw)
{
    unsigned integer MixedDecayXOR=0, io;

    if(!ccw)
    {
        PhaseCount++;
    }
    else
    {   //Reverse the "Mixed Decay" bits when running in CCW direction
        PhaseCount--;
        MixedDecayXOR=0x820;
    }

    io= ((sinus_tab[PhaseCount & 63]<<6 |
        sinus_tab[(PhaseCount+16) & 63]) ^ MixedDecayXOR);
}
```

10 Layout Considerations

For optimal operation of the circuit a careful board layout is important, because of the combination of high current chopper operation coupled with high accuracy threshold comparators. Power dissipation of the IC to the PCB also has to be considered.

10.1 Thermal properties

Connect all pins of the PQFP package for each of the double/quad output pins externally. Each two of these output pins should be treated as if they were fused to a single wide pin. Each two pins are used as cooling fin for one of the eight integrated output power transistors. Use massive motor current traces on all these pins and multiple vias, if the output trace is changed to a different layer near the package.

> *Attention*
> Ensure a symmetrical connection of all motor outputs with large and identical size copper areas located directly at the pads for cooling of the power MOSFETs. Otherwise, proper function of the thermal protection cannot be guaranteed!

A multi-layer PCB shows superior thermal performance, because it allows usage of a massive GND plane, which will act as a heat spreader. The heat will be coupled vertically from the output traces to the GND plane since vertical heat distribution in PCBs is quite effective. Heat dissipation can be improved by attaching a heat sink to the package directly.

10.2 Grounding

Please pay special attention to massive grounding. A single massive ground plane provides the best solution. The schematic highlights the high current paths which shall be routed separately, in case a GND plane cannot be realized, so that the chopper current does not flow through the system's GND interconnections. Tie the pins AGND and GND to the GND plane, and directly connect both sense resistors' GND side to GND plane. The schematic highlights the high current path and shows the required symmetry. Optional short protection / motor cable break protection elements are shown.
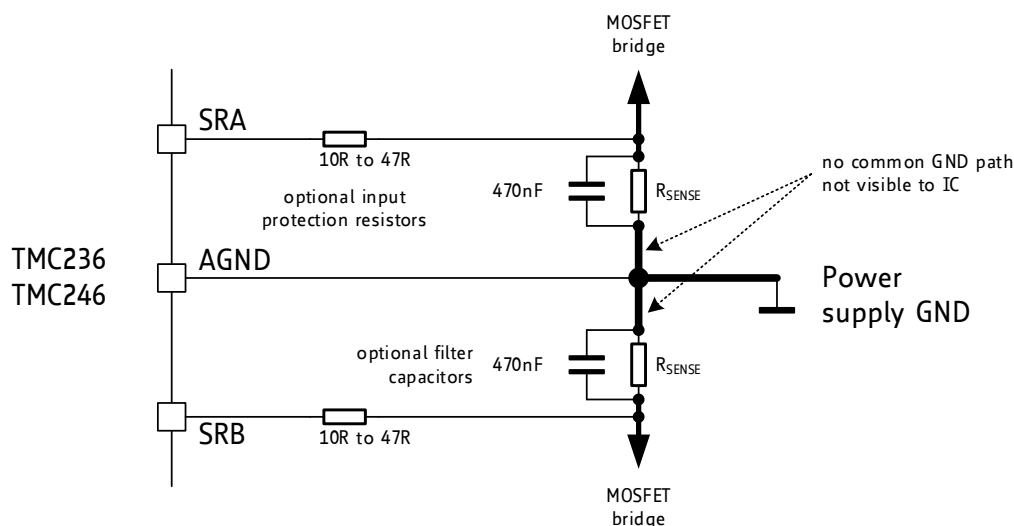

Figure 10.1 Sense resistor grounding and protection components

10.3 Selection of Additional Components

Add supply filtering capacitors located near to the boards power supply input and small ceramic capacitors near to the power supply connections of the TMC236. Electrolytic capacitors on the VS

supply should be low-ESR types. Use low inductance sense resistors or add a ceramic capacitor in parallel to each resistor to avoid high voltage spikes.

In case of long motor cables, it may be beneficial to introduce additional RC-filtering into the SRA / SRB line (see Figure 10.2) to prevent spikes from triggering the short circuit protection or the chopper comparator.

Attention
Long or thin traces to the sense resistors may add substantial resistance and thus reduce the output current. Further, resulting inductivity will lead to poor chopper behavior.
This is valid for the high side shunt resistor, too. Place the optional shunt resistor voltage divider near the TMC236. This avoids voltage drop in the VS trace adding up to the measured voltage.
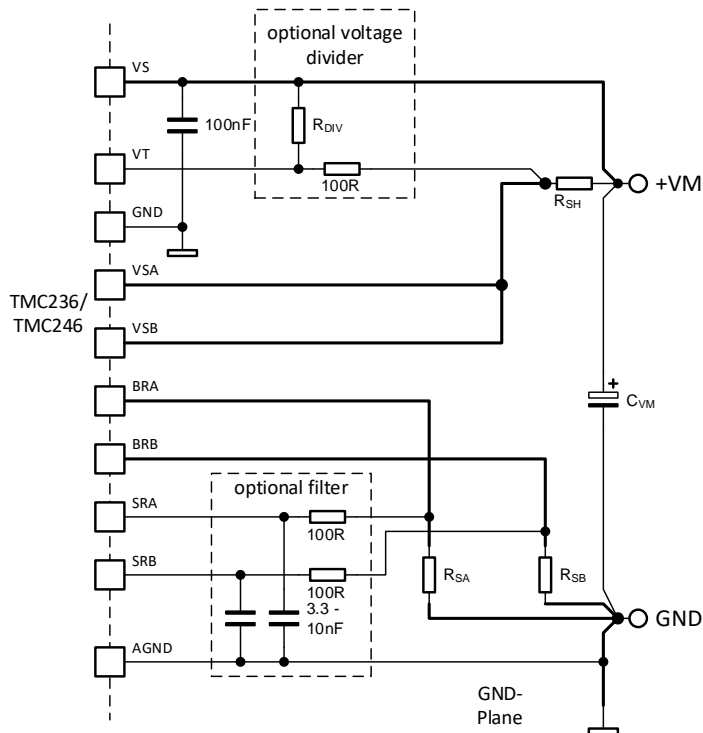

Figure 10.2 Grounding and power routing

10.4 Pull-up Resistors on Unused Inputs

The digital inputs all have integrated pull-up resistors, except for the ENN input, which is in fact an analog input. Thus, no external pull-up resistors are required for unused digital inputs which are meant to be positive.

10.5 Power Supply Sequencing Considerations

Upon power up, the driver initializes and switches off all bridge power transistors. The minimum VCC supply voltage for this is 1.0 V and the VS supply voltage has to be at least 5.0 V. When VS goes up with VCC at 0 V, a medium current temporary cross conduction of the power stage can result at supply voltages between 2.4V and 4.8V. In this voltage range, the upper power MOSFETs conduct, while the gates of the lower power MOSFETs are still floating. Due to the MOSFET gate to drain capacity, the lower MOSFETs partially can start conducting, which in turn leads to a bridge cross-conduction with its peak at VS=4.8V. Due to the low gate voltages, current is limited as determined by the MOSFETs properties and sense resistor values.

> *Attention*
> Powering up VS with VCC near 0V leads to a high temporary current flow in the VS supply range of 2.4V to 5V due to parasitic cross conduction of the power stage.
> *While this parasitic conduction of the power stage does no harm to the driver, it may hinder the power supply from coming up properly, depending on the power supply start up behavior.*
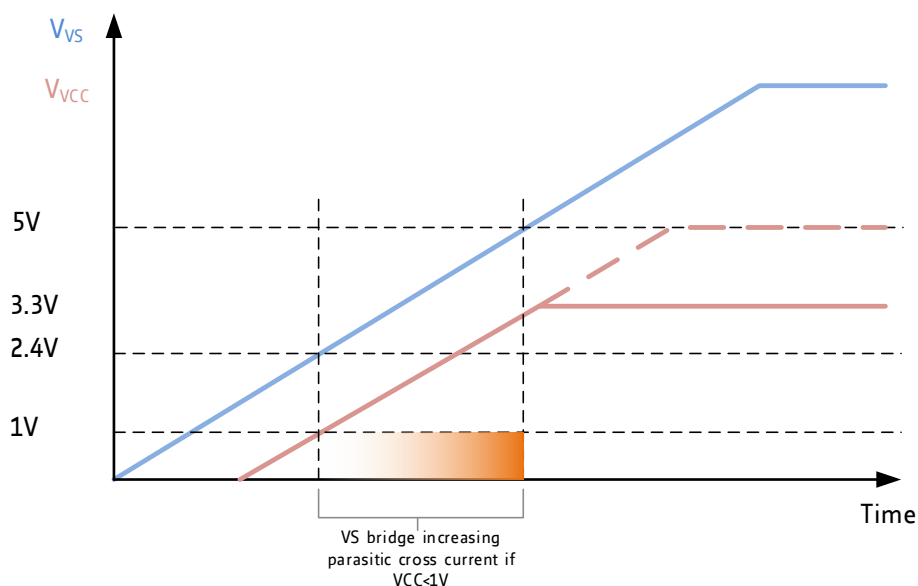
PREVENT CROSS CONDUCTION UPON POWER-UP

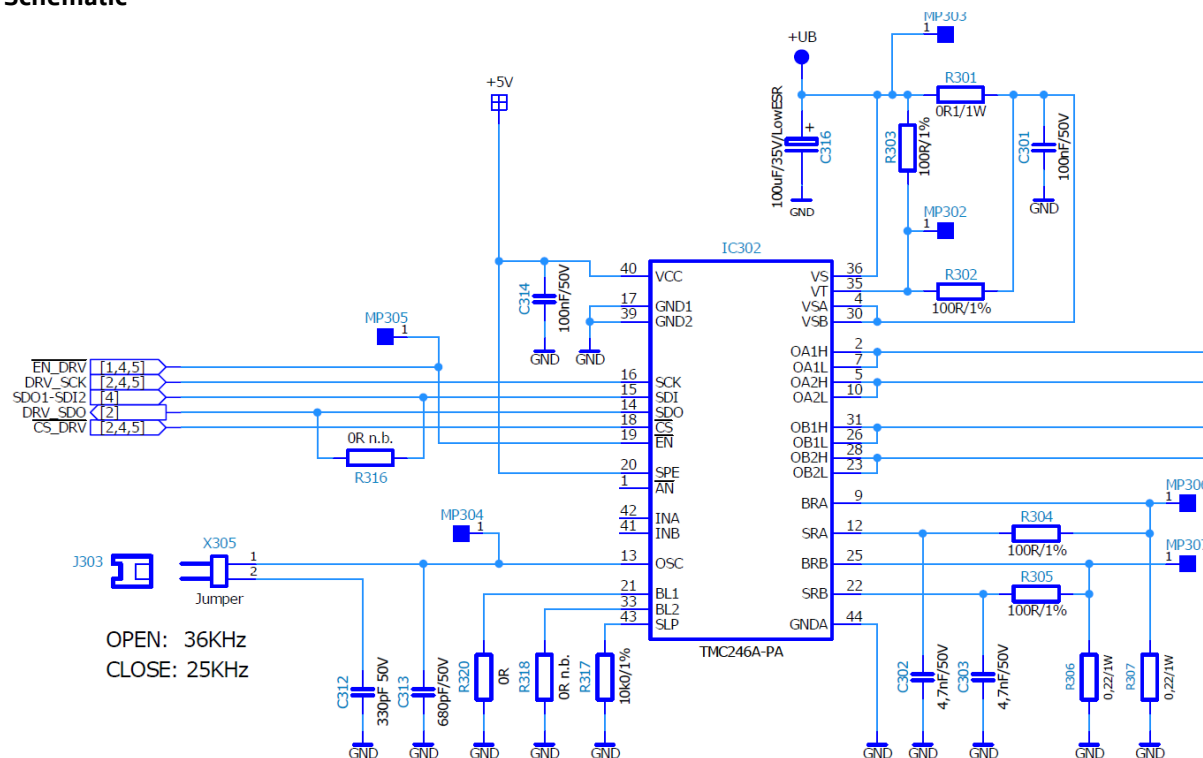**Figure 10.3 Optimum / Latest VCC power up avoiding significant power draw**

> Use a VCC supply, that comes up in parallel to VS. A local voltage regulator with low start-up voltage will satisfy this, generating the 5 V or 3.3 V VCC voltage from VS. Ramping up VCC before VS also is fine.
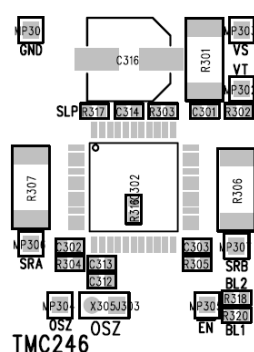
> *Attention*
> Some switching regulators do not start before the input voltage has reached 5V. Use a low-drop regulator starting up Therefore, it is recommended to use a standard linear regulator like 7805 or LM317 series or a low drop regulator or a switching regulator like the LM2595, starting at relatively low input voltages.
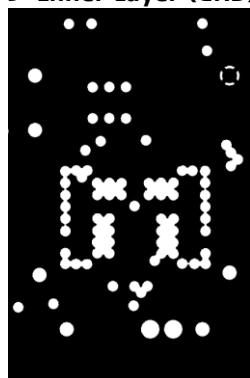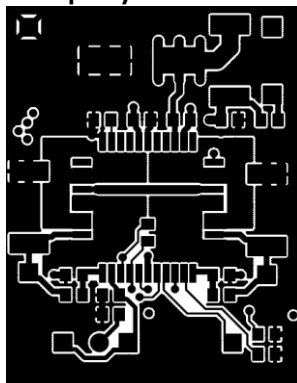
10.6 Schematic and Layout Examples
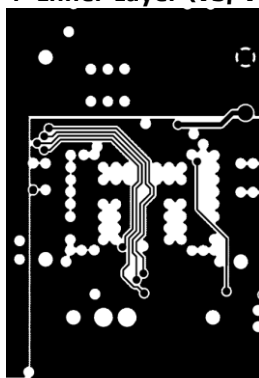
Schematic

1- Components

2- Top Layer

The layout example is shown to demonstrate the principle of a compact layout with large heat spreading areas for all motor outputs. The short to GND detection uses a voltage divider to allow simple adaptation of the triggering current. RC filtering is included for SRA and SRB for best performance.

3- Inner Layer (GND)

4- Inner Layer (VS, VCC)

Bottom Layer


Figure 10.4 Layout example

11 Application Notes

11.1 Extending the Microstep Resolution

For some applications it might be desired to have a higher microstep resolution, while keeping the advantages of control via the serial interface. The following schematic shows a solution, which adds two LSBs by selectively pulling up the SRA / SRB pin by a small voltage difference. Please remark, that the lower two bits are inverted when using the depicted circuit. A full-scale sense voltage of 340mV is assumed. The circuit still takes advantage of completely switching off of the coils when the internal DAC bits are set to "0000". This results in the following comparator trip voltages:

Current setting (MSB first)	Trip voltage
0000xx	0 V
000111	5.8 mV
000110	11.5 mV
000101	17.3 mV
000100	23 mV
...	
111101	334.2 mV
111100	340 mV

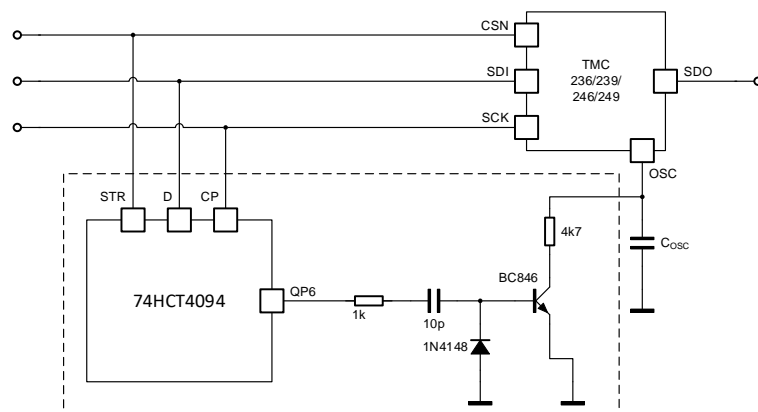| SPI bit	15	14	13	12	11	10	9	8
DAC bit	/B1	/B0	/A1	/A0	MDA	A5	A4	A3
SPI bit	7	6	5	4	3	2	1	0
DAC bit	A2	PHA	MDB	B5	B4	B3	B2	PHB
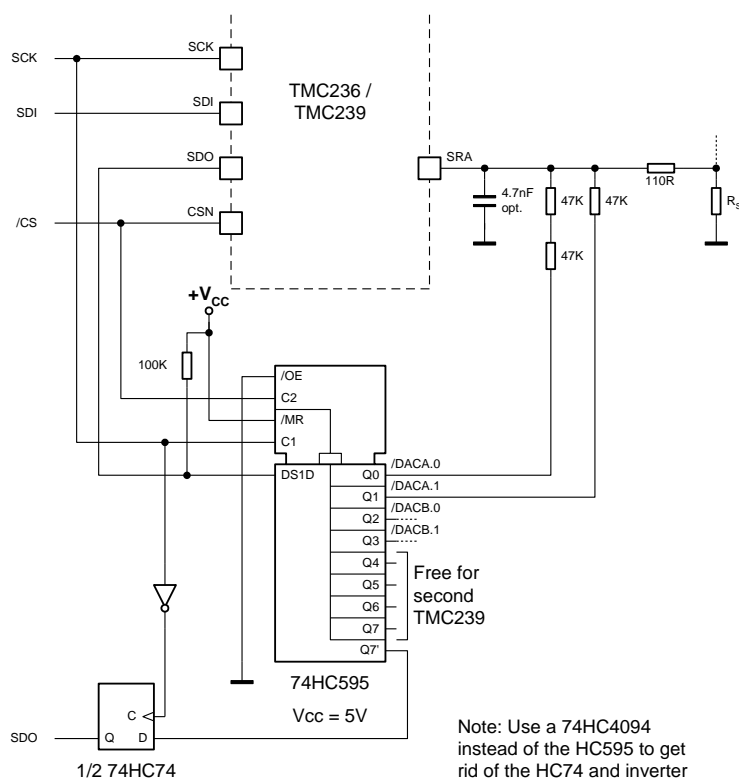
11.2 Synchronizing the Chopper Clock

Figure 11.1 Synchronizing the chopper clock

This circuit shows an additional shift-register that synchronizes the chopper clock of the TMC236 to the toggling of a phase polarity bit (bit 6) to allow highest RPM by avoiding a beat between the chopper clock and the step sequence. Use this circuit in single motor drives, where no datagrams are skipped to increase the possible motor velocity. It is beneficial for velocities above a few RPM.

11.3 Operating DC motors

The TMC236 and TMC246 can operate 2 DC motors with their two coil outputs. However, the current controlled driving mode is not optimum for motor speed control. A current controlled driver will lead to a motor torque control, rather than speed control. To allow speed control, a different kind of feedback is required.

The following schematic illustrates control of a DC motor with one of the driver channels:
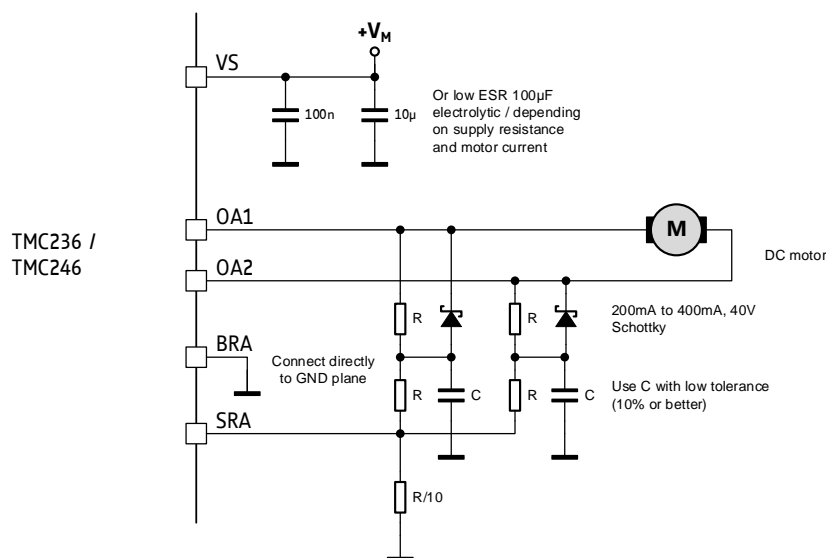
Figure 11.2 Driving a DC motor

The TMC236 / TMC246 use a constant frequency PWM. At the beginning of each PWM cycle, one of the coil outputs (OA1 resp. OB1, or OA2 resp. OB2, depending on the polarity bits PHA resp. PHB) becomes turned on. It will turn off once the trip point level on SRA resp. SRB is reached. The trip point level can be varied by CA / CB settings or by INA / INB level in a nominal range of 0 to 0.5V.

A combination of a resistor R, a Schottky diode (small signal Schottky diode with 200mA to 400mA current rating like BAT54 or BAT46) and a capacitor C is used to convert the duty cycle at the active motor output to a saw tooth wave, with up to 3.5V amplitude. 1/10 of this level is fed to the sense

resistor input (SRA resp. SRB) to switch off the PWM upon reaching the programmed trip point level, and with this a certain duty cycle.

Use slow decay mode, only (MDA=MDB=0).

Dimensioning:

Choose R in a range of 10k to 33k.

Choose the oscillator frequency fOSC, e.g., 25kHz with C$_{OSC}$=1nF.
Calculate C, to yield a programmed duty cycle fitting to the motor voltage rating VMOT relative to the supply level VM:

$$C = \frac{(VM - 3.5V)}{R * fOSC * 3.5V} * \frac{VMOT}{VM}$$

This simplified formula works well, if VM is significantly higher than 3.5V, i.e., at 12V supply or more.

Example:
Operation of a 12V motor from 24V supply:
Choose R=22k, fOSC=25kHz

$$C = \frac{(24V - 3.5V) * 12V}{22kOhm * 25kHz * 3.5V * 24V} = 5.3nF$$

➔   Choose C=5.6nF to cover the nominal motor voltage.

As the relation of R, C and fOSC determine the peak motor voltage, use low tolerance components to give a better tolerance of the maximum effective motor voltage. However, the biggest stray will come from the stray of the oscillator frequency, in case the internal oscillator is used.

Hint
The circuit will work best up to a certain upper duty cycle. Above roughly 90%, the capacitor will not fully discharge, and the duty cycle control will not be linear. This does not impose a limit as longs as the desired motor voltage is significantly lower than VM.

12 Absolute Maximum Ratings

The maximum ratings may not be exceeded under any circumstances. Operating the circuit at or near more than one maximum rating at a time for extended periods shall be avoided by application design. Parameters are given for TMC236B (limits identical to TMC236A), and partially for the obsolete TMC236.

Symbol	Parameter		Min	Max	Unit
V_S	Supply voltage (A-type/B-type)		-0.3	36	V
V_S	Supply voltage (non-A/B-type)		-0.3	30	V
V_{MD}	Supply and bridge voltage max. 20000s (non-A/B-type: device disabled)			40	V
V_{TR}	Power transistor voltage V_{OA}-V_{BRA}, V_{OB}-V_{BRB}, V_{SA}-V_{OA}, V_{SB}-V_{OB} (A/B-type)			40	V
V_{TR}	Power transistor voltage V_{OA}-V_{BRA}, V_{OB}-V_{BRB}, V_{SA}-V_{OA}, V_{SB}-V_{OB} (non-A/B-type)			30	V
V_{CC}	Logic supply voltage		-0.5	6.0	V
I_{OP}	Output peak current (10µs pulse)			+/-7	A
I_{OC}	Output current (continuous, per bridge)	$T_A \leq 85°C$		1500	mA
		$T_A \leq 105°C$		1000	
		$T_A \leq 125°C$		800	
V_I	Logic input voltage		-0.3	V_{CC}+0.3V	V
V_{IA}	Analog input voltage		-0.3	V_{CC}+0.3V	V
I_{IO}	Maximum current to / from digital pins and analog inputs			+/-10	mA
V_{VT}	Short-to-ground detector input voltage		V_S-1V	V_S+0.3V	V
T_J	Junction temperature		-40	150	°C
T_{STG}	Storage temperature		-55	150	°C

13 Electrical Characteristics

Parameters are given for TMC236B, and for reference for its predecessor TMC236A, and partially for the obsolete TMC236.

13.1 Operational Range

Symbol	Parameter	Min	Max	Unit
T_{AI}	Ambient temperature industrial *1	-25	125	°C
T_{AA}	Ambient temperature automotive	-40	125	°C
T_J	Junction temperature	-40	140	°C
V_S	Bridge supply voltage (A-type/B-type)	7	34	V
V_S	Bridge supply voltage (non-A/B-type)	7	28.5	V
V_{CC}	Logic supply voltage	3.0	5.5	V
f_{CLK}	Chopper clock frequency		50	kHz
R_{SLP}	Slope control resistor	0	110	KΩ

*1 The circuit can be operated up to 140°C, but output power derates.

13.2 DC Specifications

DC characteristics contain the spread of values guaranteed within the specified supply voltage and temperature range unless otherwise specified. Typical values represent the average value of all parts.

Logic supply voltage: V_{CC} = 3.0 V… 5.5 V,   Junction temperature: T_J = -40 °C … 140 °C,
Bridge supply voltage: V_S = 7 V… 34 V   (unless otherwise specified)

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
$R_{OUT,Sink}$	R_{DSON} of sink-FET (A-type)	T_J = 25°C $V_S \geq 8V$		0.12	0.19	Ω
$R_{OUT,Source}$	R_{DSON} of source-FET (A-type)			0.22	0.36	Ω
$R_{OUT,Sink}$	R_{DSON} of sink-FET max. (A-type)	T_J =150°C $V_S \geq 8V$		0.20	0.26	Ω
$R_{OUT,Source}$	R_{DSON} of source-FET max. (A-Type)			0.37	0.47	Ω
$R_{OUT,Sink}$	R_{DSON} of sink-FET (B-type)	T_J = 25°C $V_S \geq 8V$		0.10	0.14	Ω
$R_{OUT,Source}$	R_{DSON} of source-FET (B-type)			0.17	0.23	Ω
$R_{OUT,Sink}$	R_{DSON} of sink-FET max. (B-type)	T_J =150°C $V_S \geq 8V$		0.16	0.23	Ω
$R_{OUT,Source}$	R_{DSON} of source-FET max. (B-Type)			0.28	0.38	Ω
V_{DIO}	Diode forward voltages of O_{xx} MOSFET diodes (A-type)	T_J = 25°C I_{OXX} = 1.05A		0.84	1.21	V
V_{DIO}	Diode forward voltages of O_{xx} MOSFET diodes (B-type)	T_J = 25°C I_{OXX} = 1.05A		0.77	1.2	V
V_{CCUV}	VCC undervoltage		2.5	2.7	2.9	V
V_{CCOK}	VCC voltage o.k.		2.7	2.9	3.0	V
I_{CC}	VCC supply current	f_{osc} = 25 kHz		0.85	1.35	mA
I_{CCSTB}	VCC supply current standby			0.45	0.75	mA

I_{CCSD}	VCC supply current shutdown	ENN = 1		37	70	µA
V_{SUV}	VS undervoltage		5.5	5.9	6.2	V
V_{CCOK}	VS voltage o.k.		6.1	6.4	6.7	V
I_{SSM}	VS supply current with fastest slope setting (static state)	V_S = 14V, R_{SLP} = 0K		6		mA
I_{SSD}	VS supply current shutdown or standby	V_S = 14V		28	50	µA
V_{IH}	High input voltage (SDI, SCK, CSN, BL1, BL2, SPE, ANN)		2.2		VCC + 0.3 V	V
V_{IL}	Low input voltage (SDI, SCK, CSN, BL1, BL2, SPE, ANN)		-0.3		0.7	V
V_{IHYS}	Input voltage hysteresis (SDI, SCK, CSN, BL1, BL2, SPE, ANN)		100	300	500	mV
V_{OH}	High output voltage (output SDO)	$-I_{OH}$ = 1mA	VCC – 0.6	VCC – 0.2	VCC	V
V_{OL}	Low output voltage (output SDO)	I_{OL} = 1mA	0	0.1	0.4	V
$-I_{ISL}$	Low input current (SDI, SCK, CSN, BL1, BL2, SPE, ANN)	V_I = 0 V_{CC} = 3.3V V_{CC} = 5.0V	2	10 25	70	µA µA µA
V_{ENNH}	High input voltage threshold (input ENN)			1/2 VCC		
V_{EHYS}	Input voltage hysteresis (input ENN)			0.1 V_{ENNH}		
V_{OSCH}	High input voltage threshold (input OSC)			2/3 VCC		V
V_{OSCL}	Low input voltage threshold (input OSC)			1/3 VCC		V
V_{VTD}	VT threshold voltage (referenced to VS)		-130	-155	-180	mV
V_{TRIP}	SRA / SRB voltage at DAC="1111"	internal ref. or 2V at INA / INB	315	350	385	mV
V_{SRS}	SRA / SRB overcurrent detection threshold		570	615	660	mV
V_{SROFFS}	SRA / SRB comparator offset voltage		-10	0	10	mV
R_{INAB}	INA / INB input resistance	Vin $\leq$ 3 V	175	264	300	kΩ

13.3 AC Specifications

AC characteristics contain the spread of values guaranteed within the specified supply voltage and temperature range unless otherwise specified. Typical characteristics represent the average value of all parts.

Logic supply voltage: V_{CC} = 3.3 V,   Bridge supply voltage: V_S = 14.0 V,
Ambient temperature: T_A = 27 °C,   External MOSFET gate charge = 3.2 nC

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
f_{OSC}	Oscillator frequency using internal oscillator	C_{OSC} = 1nF ±1%	20	25	31	kHz
t_{RS}, t_{FS}	Rise and fall time of outputs Oxx with R_{SLP}=0	V_o 15% to 85% I_{OXX} = 800mA		25		ns
t_{RS}, t_{FS}	Rise and fall time of outputs Oxx with R_{SLP} = 25KΩ	V_o 15% to 85% I_{OXX} = 800mA		125		ns
t_{RS}, t_{FS}	Rise and fall time of outputs Oxx with R_{SLP} = 50KΩ	V_o 15% to 85% I_{OXX} = 800mA		250		ns
T_{BL}	Effective Blank time	BL1, BL2 = V_{CC}	1.35	1.5	1.65	µs
T_{ONMIN}	Minimum PWM on-time	BL1, BL2 = GND		0.7		µs

13.4 Thermal Protection

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
T_{JOT}	Thermal shutdown		145	155	165	°C
T_{JOTHYS}	T_{JOT} hysteresis			15		°C
T_{JWT}	Prewarning temperature		135	145	155	°C
T_{JWTHYS}	T_{JWT} hysteresis			15		°C

13.5 Thermal Characteristics

Symbol	Parameter	Conditions	Typ	Unit
R_{THA12}	Thermal resistance bridge transistor junction to ambient, one bridge chopping, fixed polarity	soldered to 2-layer PCB	88	°K/W
R_{THA22}	Thermal resistance bridge transistor junction to ambient, two bridges chopping, fixed polarity	soldered to 2-layer PCB	68	°K/W
R_{THA14}	Thermal resistance bridge transistor junction to ambient, one bridge chopping, fixed polarity	soldered to 4-layer PCB (pessimistic)	84	°K/W
R_{THA24}	Thermal resistance bridge transistor junction to ambient, two bridges chopping, fixed polarity	soldered to 4-layer PCB (pessimistic)	51	°K/W

13.6 Typical Power Dissipation

The table shows characteristic values measured with a Nema42 1A motor. The new B-type provides a roughly 20% lower power dissipation thanks to improved MOSFETs.

Motor coil parameters: L_W = 10mH, R_W = 5.0Ω
Chopping with: t_{DUTY} = 33% ON, only slow decay operation

Coil Current (Both bridges on)	Coil Current (Single bridge, sine peak)	Ambient temperature T_A	Supply voltage V_M	Slope t_{SLP}	Chopper frequency f_{CHOP}	TMC236B power dissipation P_D
560 mA	-	105 °C	16 V	400 ns	25 KHz	390 mW
-	800 mA	105 °C	16 V	400 ns	25 KHz	360 mW
560 mA		125 °C	14 V	60ns	20 KHz	280 mW
	800 mA	125 °C	14 V	60ns	20 KHz	270 mW
1000 mA	-	70 °C	28 V	60ns	25 KHz	800 mW
-	1500 mA	70 °C	28 V	60ns	25 KHz	880 mW

14 Package Mechanical Data

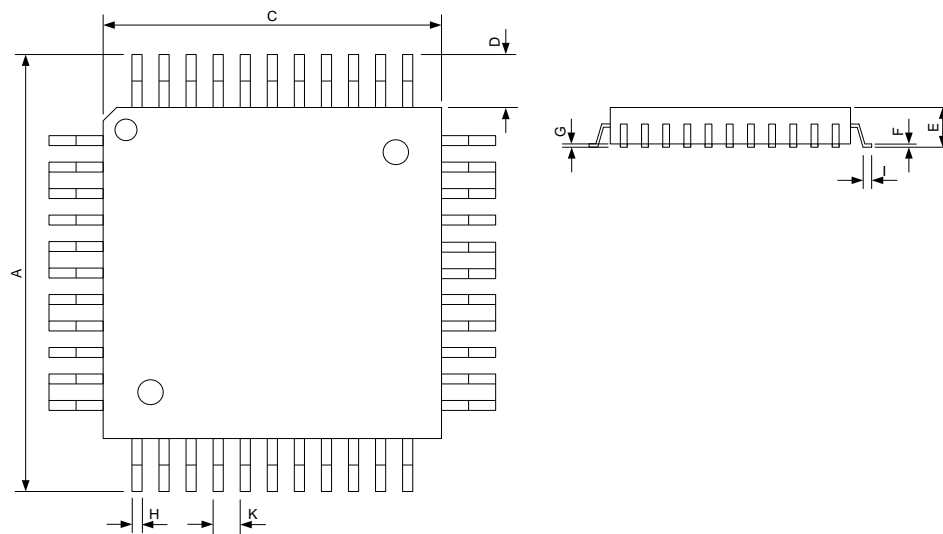## 14.1 Dimensional Drawings

Attention: Drawings not to scale.

Figure 14.1 Dimensional drawings (PQFP44)

Parameter	Ref	Min	Nom	Max
Size over pins (X and Y)	A		12	
Body size (X and Y)	C		10	
Pin length	D		1	
Total thickness	E			1.6
Lead frame thickness	F	0.09		0.2
Stand off	G	0.05	0.10	0.15
Pin width	H	0.30		0.45
Flat lead length	I	0.45		0.75
Pitch	K		0.8	
Coplanarity	ccc			0.08

14.2 Package Code

Device	Package	Temperature range	Code/ Marking
TMC236B-PA	TQFP-44 (RoHS)	-50… +125°C	TMC236B-PA YYWW

YY=Year of production, WW=Week of production

15 Disclaimer

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16 ESD Sensitive Device

Please be aware, that the TMC236 is an ESD sensitive device due to integrated high performance MOS transistors.
If the ICs are manually handled before / during soldering, special precautions have to be taken to avoid ESD voltages above 100V HBM (Human body model). For automated SMD equipment the internal device protection is specified with 1000V CDM (charged device model).

When soldered to the application board, all inputs and outputs withstand at least 1000V HBM.

Note: In a modern SMD manufacturing process, ESD voltages well below 100V are standard. A major source for ESD is hot-plugging the motor during operation. As the power MOSFETs are discrete devices, the device in fact is very rugged concerning any ESD event on the motor outputs. All other connections are typically protected due to external circuitry on the PCB.

17 Designed for Sustainability

Sustainable growth is one of the most important and urgent challenges today. We at Trinamic try to contribute by designing highly efficient IC products, to minimize energy consumption, ensure best customer experience and long-term satisfaction by smooth and silent run, while minimizing the demand for external resources, e.g., for power supply, cooling infrastructure, reduced motor size and magnet material by intelligent control interfaces and advanced algorithms.

Please help and design efficient and durable products made for a sustainable world.

18 Table of Figures

19 Revision History

Version	Date	Author BD = Bernhard Dwersteg SD – Sonja Dwersteg	Description
0.90		BD	Datasheet based on TMC239 datasheet V2.1, removed higher voltage and 64 microstep application notes, increased SPI frequency limit to 8MHz
1.0	2012-JUN-22	SD	- New design. - Further information about low noise chopper. - Layout example added.
1.01	2013-MAR-26	BD	MOSFET list updated, updated criteria for necessity of gate driver output protection diodes
2.10	2016-JUN-06	BD	Added IC revision TMC236B with improved MOSFETs
2.11	2018-MAR-01	BD	Added TMC236B to package code list
2.12	2020-JUN-08	BD	Updated logo
2.22	2022-JUN-09	BD	Re-Targeted TMC239 V2.22 Datasheet to TMC236. Updated descriptions, wording, and logo and added examples.

20 References

Please refer to our web page http://www.trinamic.com.
For trouble shooting please see Application Note 042 - FAQs TMC236, TMC246, TMC239, TMC249

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