

3-phase motor driver

BA6438S

The BA6438S is a 3-phase, full-wave, pseudo-linear motor driver suited for VCR capstan motors. The IC has a torque ripple cancellation circuit to reduce wow and flutter, and an output transistor saturation prevention circuit that provides superb motor control over a wide range of current. The built-in motor power switching regulator allows applications with low power consumption

●Applications

3-phase VCR capstan motors

●Features

- 1) 3-phase, full-wave, pseudo-linear drive system.
- 2) Torque ripple cancellation circuit.
- 3) Reversal brake based on the detection of motor direction.
- 4) Output transistor (high-and low-sides) saturation prevention circuit
- 5) Motor power switching regulator with oscillation circuit.
- 6) Output-to-GND short-circuit detection.
- 7) Available in SDIP 24-pin power package (with radiation fins).

●Absolute maximum ratings (Ta = 25°C)

Parameter	Symbol	Limits	Unit
Applied voltage	V _{CC}	7	V
Applied voltage	V _M	24	V
Power dissipation	P _d	2000* ¹	mW
Operating temperature	T _{opr}	-10 ~ +75	°C
Storage temperature	T _{stg}	-40 ~ +150	°C
Allowable output current	I _{Opeak}	1.7* ²	A

*1 Reduced by 16mW for each increase in Ta of 1°C over 25°C.

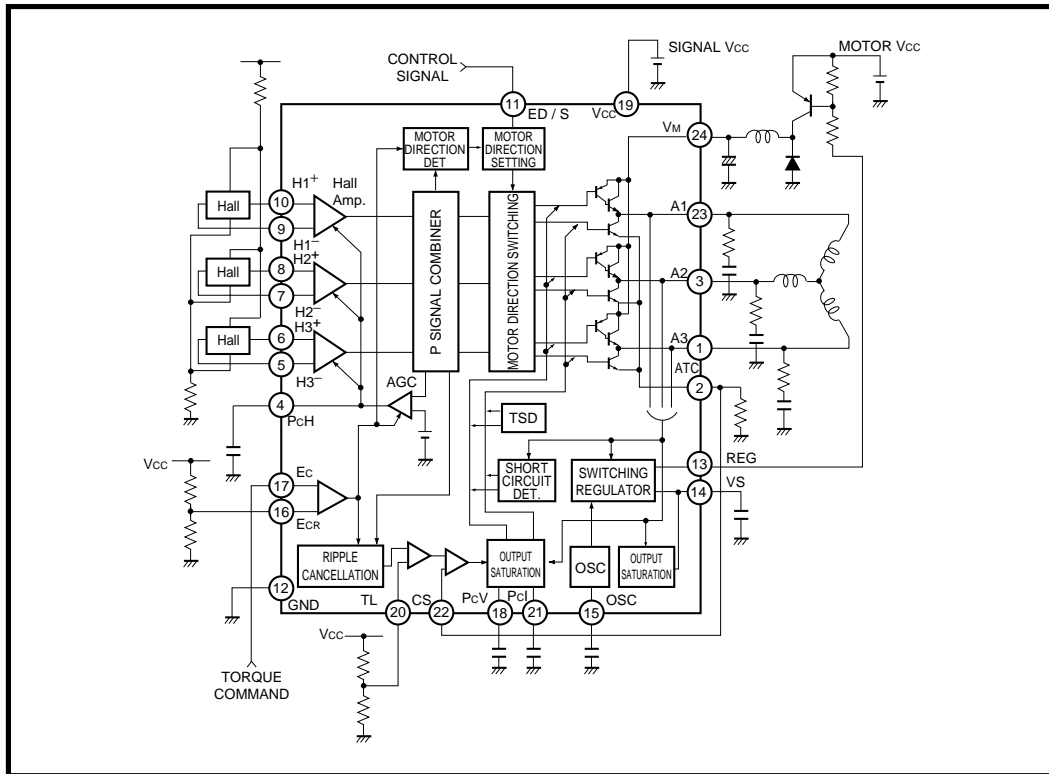
*2 Should not exceed the ASO value.

●Recommended operating conditions (Ta = 25°C)

Parameter	Symbol	Min.	Typ.	Max.	Unit
Operating power supply voltage	V _{CC}	4	5	6	V
Operating power supply voltage	V _M	3	12	23	V

Motor driver ICs

●Block diagram



Motor driver ICs

●Pin descriptions

Pin No.	Pin name	Function
1	A3	Motor output
2	ATC	Driver ground
3	A2	Motor output
4	PCH	Hall amplifier AGC phase compensation
5	H3 ⁻	Hall signal input
6	H3 ⁺	Hall signal input
7	H2 ⁻	Hall signal input
8	H2 ⁺	Hall signal input
9	H1 ⁻	Hall signal input
10	H1 ⁺	Hall signal input
11	ED / S	Forward when LOW; stop when MEDIUM; reverse when HIGH
12	GND	Signal ground
13	REG	Switching regulator output (sink output)
14	V _s	High-side saturation detection output
15	OSC	Oscillator capacitor connection
16	ECR	Torque control reference voltage input
17	EC	Torque control signal input
18	PCV	Phase compensation for preventing driver high-side saturation
19	V _{CC}	Signal power supply
20	TL	Torque limiter
21	PCI	Phase compensation for preventing driver low-side saturation
22	CS	Current sensing input
23	A1	Motor output
24	V _M	Motor power supply

●Electrical characteristics (unless otherwise noted, T_a = 25°C, V_{CC} = 5V, V_M = 12V)

Parameter	Symbol	Min.	Typ.	Max.	Unit	Conditions
Torque control input / output gain	G _{io}	0.25	0.31	0.36	–	E _C = 2.2→2.1V, Input = L, L, H
Ripple cancel ratio	V _{RCC}	4.6	6.4	7.2	%	Input = L, L, H→L, M, H
Output high level voltage	V _{OH}	1.1	1.5	1.9	V	I _o = 0.8A
Output low level voltage	V _{OL}	0.95	1.3	1.65	V	I _o = 0.8A
Oscillator frequency	f _{OSC}	100	135	160	kHz	C = 470pF
Saturation detection output gain	G _{us}	5.0	6.5	8.0	–	–
Regulator current capacity	I _{REGO}	30	–	–	mA	V _o = 5V

© Not designed for radiation resistance.

Motor driver ICs

●Circuit operation

(1) Pseudo-linear output and torque ripple cancellation
 The IC generates a trapezoidal (pseudo-linear) output current, whose waveform phase is 30 degrees ahead of that of the Hall input voltage (Fig. 1).

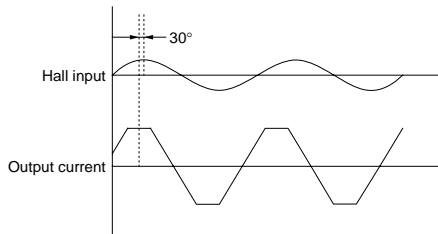


Fig. 1

The trapezoidal waveform of output current would create intermittence in the magnetic field generated by the 3-phase motor, and would result in an irregular rotation of the motor. To prevent this, the output waveform is obtained by superimposing a triangular wave on the trapezoidal wave (Fig. 2). This process is called torque ripple cancellation.

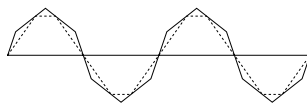


Fig. 2

(2) Torque control and reversal brake

The output current can be controlled by adjusting the voltage applied to the torque control pins (pins 16 and 17).

These pins are the inputs to a differential amplifier. A reference voltage between 2.3 ~ 3.0V (2.5V recommended) is applied to pin 16.

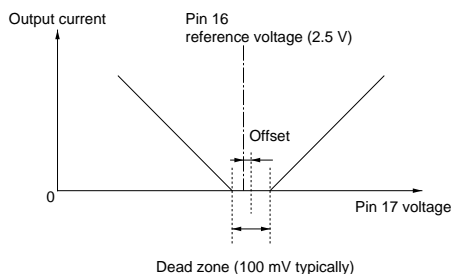


Fig. 3

A brake is applied to the motor as described in the following. When the motor is running, pin 17 is given a negative potential with respect to the reference potential. If the pin 17 potential becomes positive, the IC detects the rise of pin 17 potential above the reference potential and activates the motor direction detecting circuit.

The motor direction detecting circuit sends a signal to the motor direction setting circuit to reverse the motor direction. This causes a braking torque that depends on the pin 17 potential, so that the motor quickly reduces its speed. At the same time, the positive pin 17 potential is shifted to the reference potential, so that the motor stops smoothly.

(3) Output current sensing and torque limitation

Pin 2 is the ground pin for the output stage. To sense the output current, a resistor (0.5Ω recommended) is connected between pin 2 and the ground. The output current is sensed by applying the voltage developed across this resistor to pin 22 as a feedback.

The output current can be limited by adjusting the voltage applied to pin 20. The current is limited when pin 20 reaches the same potential as pin 22. The output current ($I_{MAX.}$) under this condition is given by:

$$I_{MAX.} = \frac{V_{20P}(TL-CS_{ofs})}{R_{2P}}$$

where R_{2P} is the value of the resistor connected between pin 2 and the ground, V_{20P} is the voltage applied to pin 20, and $(TL-CS_{ofs})$ is the offset between the TL and CS pins.

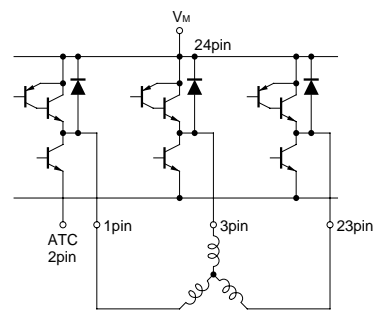


Fig.4 Output circuit

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(4) Motor direction control (pin 11)

The motor mode is :

Forward when the pin 11 voltage is less than 0.9V,

Stop when the voltage is between 1.3 ~ 3.0V,

Reverse when the voltage is above 3.5V.

In the stop mode, high-and low-side output transistors are turned off, resulting in a high impedance state.

(5) Output transistor saturation prevention circuit

This circuit monitors the output voltage and maintain the operation of the output transistors below their saturation levels. Operating the transistors in the linear characteristic range provides good control over a wide range of current and good torque characteristics even during overloading.

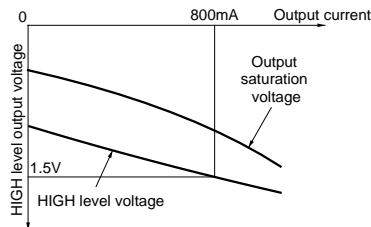


Fig.5 High level output voltage vs. output current (reference curves)

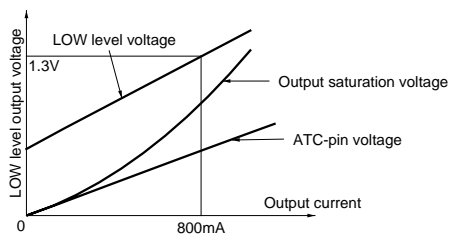


Fig.6 Low level output voltage vs. output current (reference curves)

(6) Switching regulator

The BA6438S has a switching regulator output pin. The IC outputs a PWM signal by comparing the output of the internal oscillator with the HIGH level output voltage monitored.

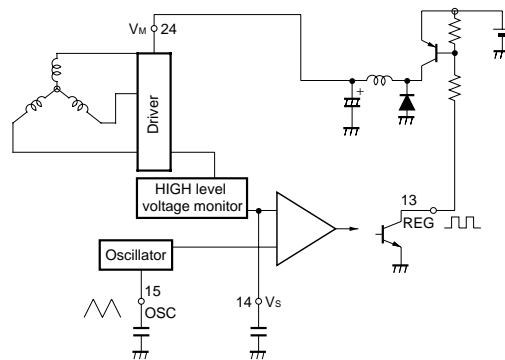


Fig. 7

As shown in Fig. 7, the switch regulator circuit reduces the power consumed by the IC by reducing the collector-to-emitter (C-E) voltage of the driver transistors.

Nearly all the power dissipated by the IC is dissipated between the collectors and emitters of the output transistors.

More power is consumed as the C-E voltage increases and as the output current increases.

The output transistor C-E voltage is equal to the difference between the supply voltage and the voltage applied to the motor. Because the voltage across the motor decreases with decreasing drive current, the C-E voltage must increase if the supply voltage is fixed.

Therefore, to improve the efficiency of the driver and to prevent the power rating of the IC being exceeded, the supply voltage must be varied in response to changes in the output current. The supply voltage is decreased at low current and increased at high current so that no excessive voltage is applied between the transistor collectors and emitters .

(7) Output-to-ground short-circuit detection

The motor output pins of the IC may be short-circuited to the ground by some fault conditions. A short-circuited output can destroy the output transistors because of excessive current, excessive voltage, or both. Even when a short-circuit condition does not completely destroy the device, it can still cause extreme overheating. To prevent this, the BA6438S contains a short-circuit detection circuit that turns off the motor drive current if the output-to-ground potential becomes abnormally low.

Motor driver ICs

●Application example

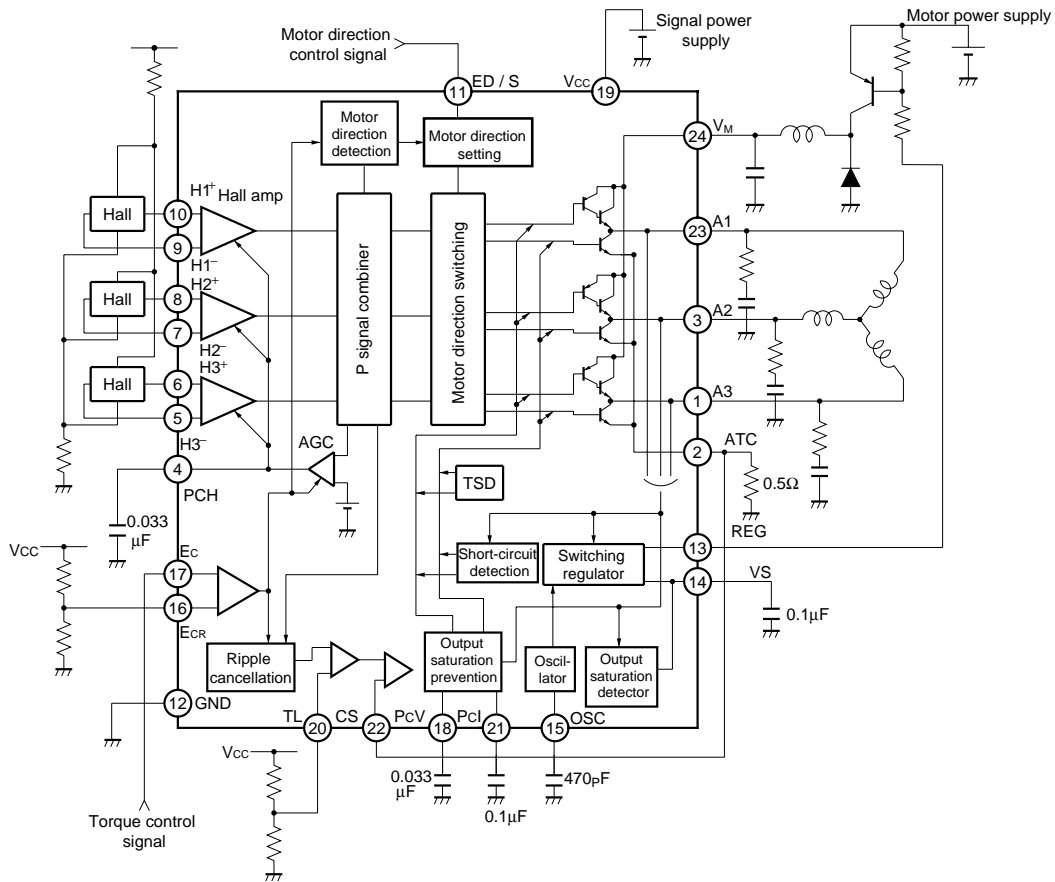


Fig. 8

●Operation notes

The BA6438S has two thermal shutdown circuits (TSD1 and TSD2) to protect the IC. The typical shutdown temperatures are 175°C for TSD1 and 215°C for TSD2. When the TSD1 is activated at an elevated chip temperature, the output pins (pins 1, 3, and 23) are set to the open state. TSD1 is functional against excessive power dissipation, output short-circuiting, and other irregularities in the output current, but does not work against overheating caused by high internal currents due to externally caused IC damage or pin-to-pin short-circuiting. When TSD2 is activated at a higher chip temperature, the high-and low-side output transistors are turned on, and the internal resistance between the motor power supply pin (pin 24) and the output ground pin (pin 2) drops to less

than 3Ω. The motor power supply current (I_M) is then given by

$$I_M = \frac{V_M[V]}{R_M + R_{2P} + 3[\Omega]}$$

where

I_M is the motor supply current,
 V_M is the motor supply voltage,
 R_M is the motor power supply output resistance,
 R_{2P} is the pin-2 resistance.

In your application, make sure to connect between the motor power supply and pin 24 a circuit breaker that operates at currents less than I_M .

Motor driver ICs

● Electrical characteristic curves

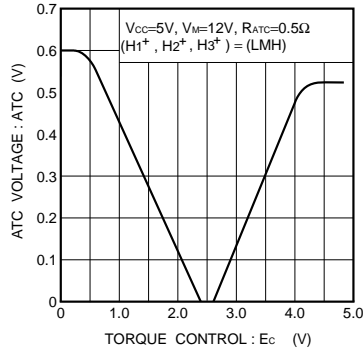


Fig.9 Output current vs. torque control voltage (I)

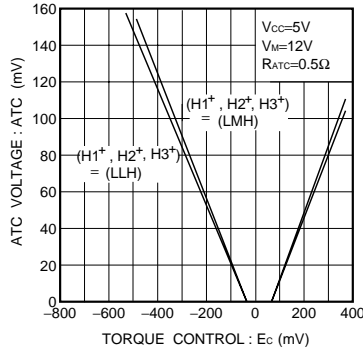


Fig.10 Output current vs. torque control voltage (II)

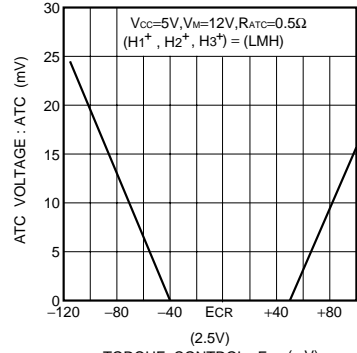


Fig.11 Output current vs. torque control voltage (III)

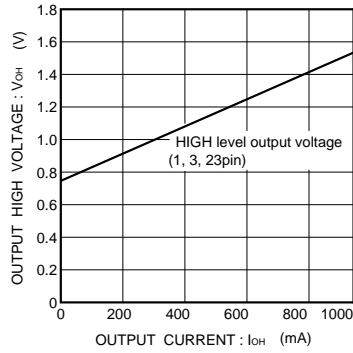


Fig.12 Output high level voltage vs. output current

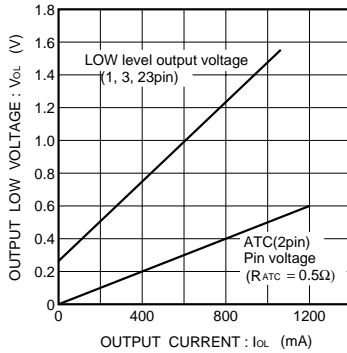


Fig.13 Output low level voltage vs. output current

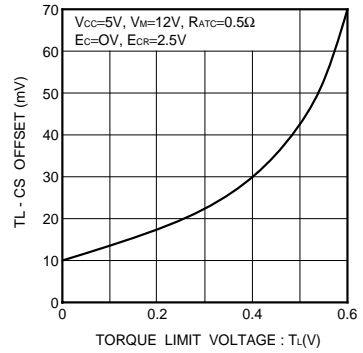


Fig.14 TL-CS offset vs. torque limit voltage

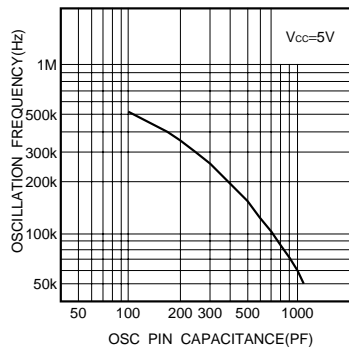


Fig.15 Capacitance of the capacitor connected to the OSC pin vs. oscillation frequency

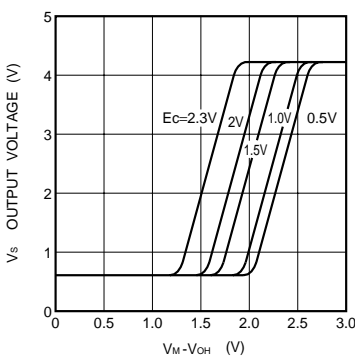


Fig.16 High-side saturation detection output voltage (pin 14) vs. output voltage

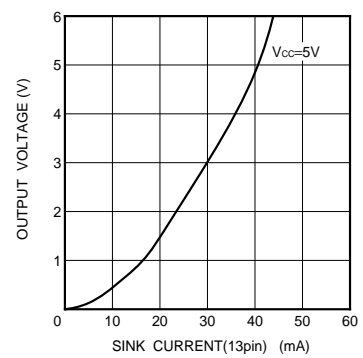


Fig.17 Switching regulator sink current vs. output voltage

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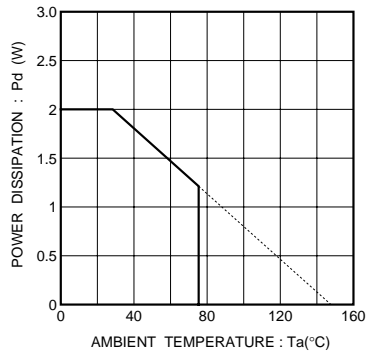


Fig.18 Thermal derating curve

●External dimensions (Units : mm)

