



LB1922

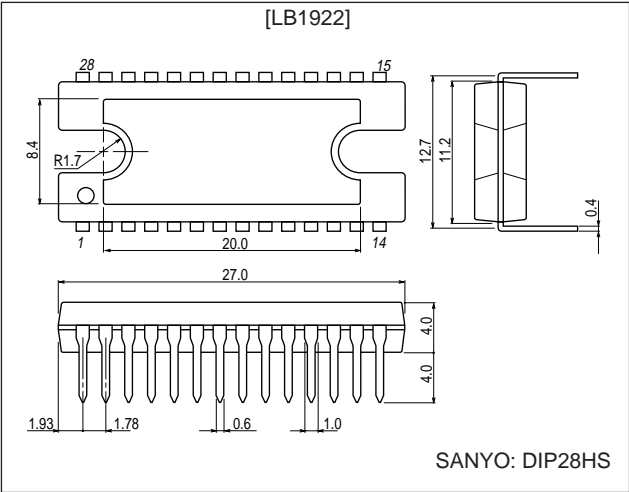
Three-Phase Brushless Motor Driver
for Office Automation Applications

Overview

The LB1922 is a single-chip drive circuit that provides the direct PWM drive output appropriate for the power brushless motors used in office automation equipment. It provides a variety of peripheral circuits on chip, including a speed control circuit and an FG amplifier. It is optimal in systems that use a 12-V power supply.

Package Dimensions

unit: mm
3147B-DIP28HS



Specifications

Absolute Maximum Ratings at Ta = 25°C

Parameter	Symbol	Conditions	Ratings	Unit
Supply voltage	V _{CC}		20	V
	V _M		20	V
Output current	I _O	T ≤ 100 ms	3.1	A
Allowable power dissipation	Pd max1	Independent IC	3	W
	Pd max2	With an arbitrarily large heat sink	20	W
Operating temperature	T _{opr}		−20 to +80	°C
Storage temperature	T _{stg}		−55 to +150	°C

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Allowable Operating Ranges at Ta = 25°C

Parameter	Symbol	Conditions	Ratings	Unit
Supply voltage range	V _{CC}		9.5 to 18	V
	V _M		9 to 18	V
FG Schmitt output applied voltage	V _{FGS}		0 to 8	V
Fixed-voltage output current	I _{O1}	7 V output	0 to -20	mA
	I _{O2}	5 V output	0 to -20	mA
	I _{O3}	4 V output	0 to -15	mA
FG Schmitt output current	I _{FGS}		0 to 5	mA
Lock detection output current	I _{LD}		0 to 20	mA

Electrical Characteristics at Ta = 25°C, V_{CC} = V_M = 12 V

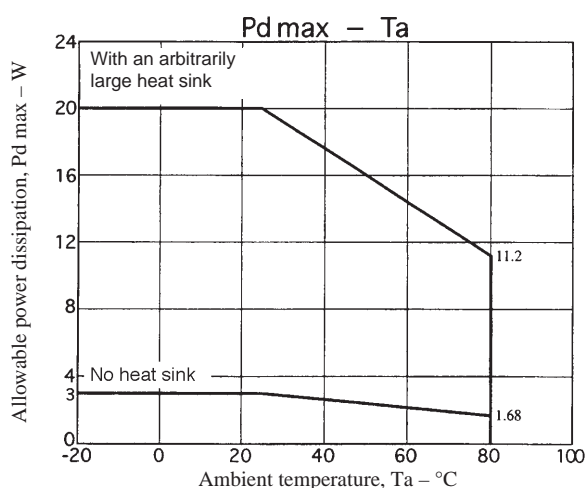
Parameter	Symbol	Conditions	Ratings			Unit
			min	typ	max	
Current drain 1	I _{CC1}			34	50	mA
Current drain 2	I _{CC2}	In stop mode		8	11	mA
Output saturation voltage 1	V _{O(sat)1}	I _O = 1 A, V _{CC} = V _M = 10.5 V		2.0	3.0	V
Output saturation voltage 2	V _{O(sat)2}	I _O = 2 A, V _{CC} = V _M = 10.5 V		2.7	4.2	V
Output leakage current	I _{Oleak}				100	μA
[7-V Fixed-Voltage Output]						
Output voltage	V _H	I _O = -10 mA	6.65	7.0	7.35	V
Line regulation	ΔV _{H1}	V _{CC} = 9.5 to 18 V		50	200	mV
Load regulation	ΔV _{H2}	I _O = -5 to -20 mA		40	200	mV
[5-V Fixed-Voltage Output]						
Output voltage	V _X	I _O = -5 mA	4.45	4.80	5.15	V
Line regulation	ΔV _{X1}	V _{CC} = 9.5 to 18 V		50	200	mV
Load regulation	ΔV _{X2}	I _O = -5 to -20 mA		5	200	mV
[4-V Fixed-Voltage Output]						
Output voltage	V _{FG}	I _O = -5 mA	3.65	4.0	4.35	V
Line regulation	ΔV _{FG1}	V _{CC} = 9.5 to 18 V		40	200	mV
Load regulation	ΔV _{FG2}	I _O = -5 to -15 mA		110	200	mV
[Hall Amplifier]						
Input bias current	I _{HB}		-4	-1		μA
Common-mode input voltage range	V _{ICM}		1.5		5.1	V
Hall input sensitivity			60			mVp-p
Hysteresis	ΔV _{IN}		8	14	24	mV
Input voltage (low → high)	V _{SLH}			7		mV
Input voltage (high → low)	V _{SHL}			-7		mV
[Oscillator]						
Output high-level voltage	V _{OH(CR)}		2.8	3.1	3.4	V
Output low-level voltage	V _{OL(CR)}		0.8	1.1	1.4	V
Oscillator frequency	f _(CR)	R = 56 kΩ, C = 1000 pF		15		kHz
Amplitude	V _(CR)			2.0		Vp-p
[Current Limiter Operation]						
Limiter	V _{CC-V_M}		0.4	0.5	0.6	V
[Thermal Shutdown Operation]						
Thermal shutdown operating temperature	TSD	Design target value	150	180		°C
Hysteresis	ΔTSD			50		°C
[FG Amplifier]						
Input offset voltage	V _{IO(FG)}		-10		+10	mV
Input bias current	I _{B(FG)}		-1		+1	μA
Output high-level voltage	V _{OH(FG)}	I _{FG} = -2 mA	5.5	6		V
Output low-level voltage	V _{OL(FG)}	I _{FG} = 2 mA		1	1.5	V
FG input sensitivity		Gain: 100 ×	3			mV
Following stage Schmitt amplitude			100	180	250	mV
Operating frequency range					2	kHz
Open-loop gain		f _(FG) = 2 kHz	45	51		dB

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LB1922

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Parameter	Symbol	Conditions	Ratings			Unit
			min	typ	max	
[FGS Output]						
Output saturation voltage 1	V _{O(FGS)}	I _{O(FGS)} = 2 mA		0.1	0.5	V
Output leakage current	I _{L(FGS)}	V _O = 5 V			10	μA
[Speed Discriminator]						
Output high-level voltage	V _{OH(D)}		4.0	4.3		V
Output low-level voltage	V _{OL(D)}			0.8	1.1	V
[PLL Output]						
Output high-level voltage	V _{OH(P)}		3.2	3.5	3.8	V
Output low-level voltage	V _{OL(P)}		1.2	1.5	1.8	V
[Number of Counts]				512		
[Lock Detection]						
Output low-level voltage	V _{OL(LD)}	I _{LD} = 10 mA		0.15	0.5	V
Lock range				6.25		%
[Integrator]						
Input bias current	I _{B(INT)}		−0.4		+0.4	μA
Output high-level voltage	V _{OH(INT)}		3.7	4.3		V
Output low-level voltage	V _{OL(INT)}			0.8	1.2	V
Open-loop gain			60			dB
Gain-bandwidth product				1.6		MHz
Reference voltage			−5%	V _X /2	+5%	V
[Crystal Oscillator]						
Operating frequency range	f _{OSC}		1		10	MHz
[Start/Stop Pin]						
Input high-level voltage	V _{IH(S/S)}		4.0			V
Input low-level voltage	V _{IL(S/S)}				1.5	V
Pull-down resistance	R _{D(S/S)}		30	50	70	kΩ
[Forward/Reverse Pin]						
Input high-level voltage	V _{IH(F/R)}		4.0			V
Input low-level voltage	V _{IL(F/R)}				1.5	V
Hysteresis	ΔV _{IN}			0.5		V
Pull-down resistance	R _{D(F/R)}		30	50	70	kΩ



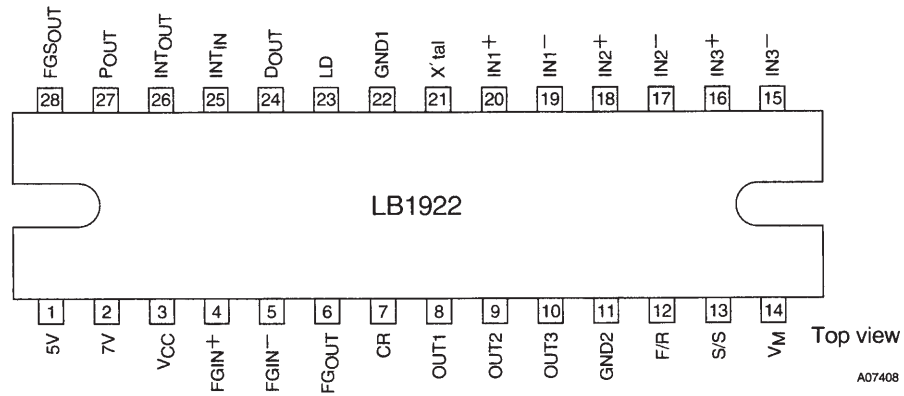
LB1922

Truth Table

	Source → Sink	F / R = L			F / R = H		
		IN1	IN2	IN3	IN1	IN2	IN3
1	OUT2 → OUT1	H	L	H	L	H	L
2	OUT3 → OUT1	H	L	L	L	H	H
3	OUT3 → OUT2	H	H	L	L	L	H
4	OUT1 → OUT2	L	H	L	H	L	H
5	OUT1 → OUT3	L	H	H	H	L	L
6	OUT2 → OUT3	L	L	H	H	H	L

Note: A high input is defined as $IN^+ > IN^-$.

Pin Assignment



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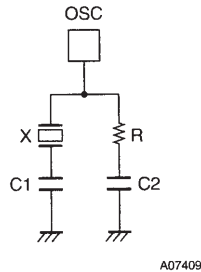
Pin Functions

Pin No.	Pin	Function
1	5 V	5-V power supply.
2	7 V	7-V power supply
3	V _{CC}	Power supply for all blocks other than the output block
4	FG _{IN} ⁺	FG pulse input (4-V power supply pin)
5	FG _{IN} ⁻	FG pulse input
6	FG _{OUT}	FG amplifier output
7	CR	PWM oscillator frequency setting
8	OUT1	Output 1
9	OUT2	Output 2
10	OUT3	Output 3
11	GND2	Ground for the output block
12	F/R	Forward/reverse control Forward: low, reverse: high
13	S/S	Start/stop control Start: low, stop: high
14	V _M	Output block power supply. This pin is also used for output current detection. The output current is converted to a voltage and detected by inserting a resistor (R _f) between this pin and V _{CC} .
20, 19	IN1 ⁺ , IN1 ⁻	Hall input for OUT1
18, 17	IN2 ⁺ , IN2 ⁻	Hall input for OUT2
16, 15	IN3 ⁺ , IN3 ⁻	Hall input for OUT3
21	X'tal	Crystal oscillator. Connect a crystal oscillator to this pin.
22	GND1	Ground for all circuits other than the output block.
23	LD	Lock detection Outputs a low level when the motor speed is within the lock range, i.e. within ±6.25% of the set speed.
24	D _{OUT}	Speed discriminator output Outputs a high level on overspeed.
25	INT _{IN}	Integrator input
26	INT _{OUT}	Integrator output (speed control pin)
27	P _{OUT}	PLL output
28	FGS _{OUT}	FG amplifier output (After the Schmitt circuit)

The following formula gives the relationship between the crystal oscillator frequency (f_{OSC}) and the FG frequency f_{FC} .

$$f_{FC}(\text{servo}) = f_{OSC} / (\text{ECL divided by 16 times the number of counts}) \\ = f_{OSC} / 8192$$

External Crystal Oscillator Circuit



External Constants (Provided for reference only.)

Xtal (MHz)	C1 (pF)	C2 (pF)	R (kΩ)
3 to 4	39	82	0.82
4 to 5	39	82	1.0
5 to 7	39	47	1.5
7 to 10	39	27	2.0

However, a crystal with a ratio between the impedance at the crystal fundamental frequency f_0 and the impedance at the third harmonic frequency ($3f_0$) of at least 1:5 must be used.

LB1922 Functional Description and Notes on External Components

1. Speed control circuit

Speed control in this IC is implemented with the combination of a speed discriminator circuit and a PLL circuit. The speed discriminator circuit outputs an error output once every two FG periods using a charge pump technique. The PLL circuit outputs a phase error once every FG period, also using a charge pump technique. As compared to the earlier technique of only using a speed discriminator circuit, the combination of a speed discriminator circuit and a PLL circuit is better able to suppress speed fluctuations when used in situations where large load variations are applied to the motor. Since the FG servo frequency is determined by the following formula, applications must determine the motor speed by setting the number of FG pulses and the crystal oscillator frequency.

$$f_{FG}(\text{servo}) = f_{OSC} / 8192$$

f_{OSC} : The crystal oscillator frequency

2. Direct PWM drive

To minimize power loss in the output, this IC adopts a direct PWM drive technique. The output transistors are always saturated when on, and motor drive is adjusted by changing the duty with which the output transistors are on. Since the output switching is performed by the lower side transistors, Schottky diodes (D1, D2, and D3) or similar devices must be connected between OUT and V_{CC} . (This is because if the devices used do not have a short reverse recovery time, through currents will flow at the instant the lower side transistors turn on.) Normal rectifying diodes can be used between OUT and ground.

3. Current limiter circuit

The current limiter circuit operates at a current determined by the formula $I = 0.5/R_f$, and operates as a peak current limiter. Its current limiting operation consists of reducing the duty with which the output is on to suppress the current drawn. No phase compensation capacitors are required.

4. Speed lock range

The speed lock range is $\pm 6.25\%$ of the set speed. When the motor speed is in the lock range the LD pin goes low. (The LD pin is an open-collector output.) If the motor speed goes out of the lock range, the motor drive output on duty is modified according to the speed error. This controls the motor speed to be in the lock range.

5. PWM frequency

The PWM frequency is determined by the resistor (R3) and the capacitor (C6) connected to the CR pin.

- If R3 is connected to the 4-V fixed-voltage supply:
 $f_{PWM} \approx 1 / (1.2 \times C \times R)$
- If R3 is connected to the 7-V fixed-voltage supply:
 $f_{PWM} \approx 1 / (0.5 \times C \times R)$

Do not use a value of 30 k Ω or less for R3. A PWM frequency of about 15 kHz is desirable. If the PWM frequency is too low, the motor may resonate at the PWM frequency during motor constraint, and if the PWM frequency is in the audible range result in noise. Inversely, if the PWM frequency is too high, the loss in the output transistors during switching will increase.

6. Ground leading

GND1 (pin 22) --- Ground for all circuits other than the output block

GND2 (pin 11) --- Output block ground (the sink transistor emitter)

D4, D5, and D6 must be connected to GND2. All other external components must be connected to GND1. A single ground point must be taken for GND1 and GND2 at the connector. Since GND2 carries large currents, the GND2 lines must be kept as short as possible.

7. Parasitic effects in the output

Parasitic effects occur when the output pin voltage falls -0.7 V below the GND1 and GND2 potential. (Note that the actual value may become smaller than -0.7 V due to device temperature characteristics.) Also, applications must be designed so that the output pin voltage never exceeds V_{CC} by 1 V or more. If a parasitic effect occurs, at first speed control will be lost intermittently. If the parasitic effects increase, the output transistors may be destroyed. Since D1, D2, and D3 are for through current prevention, use Schottky diodes with a small V_f . This will prevent the potential difference between the output pins and V_{CC} from becoming a problem. Although normal rectifying diodes can be used for D4, D5, and D6, design the ground lines carefully as described in item 6, "Ground leading", so that parasitic effects do not occur.

8. External interface pins

- LD pin

Output type: open collector

Voltage handling capacity: 20 V (absolute maximum)

Saturation voltage sample-to-sample variation reference value ($I_{LD} = 10$ mA)

0.0 to 0.5 V

- FGS pin

Output type: open collector

Voltage handling capacity: 20 V (absolute maximum)

Saturation voltage sample-to-sample variation reference value ($I_{FGS} = 2$ mA)

0.12 to 0.18 V

The FGS pin output is the FG amplifier output converted to a pulse output by a hysteresis comparator. It is used as a speed monitor. If the FGS pin is not used, the pull-up resistor is not required.

- Start/Stop pin

Input type: PNP transistor base with a 50-k Ω pull-down resistor connected to ground

Threshold level (typical): About 2.6 V

The 4-V, 5-V, and 7-V fixed-voltage supplies are turned off in stop mode.

- F/R pin

Input type: PNP transistor base with a 50-k Ω pull-down resistor connected to ground

Threshold level (typical): About 2.2 V (high \rightarrow low), about 2.7 V (low \rightarrow high)

Hysteresis: about 0.5 V

F/R switching must only be performed in stop mode when the motor is stopped.

9. Fixed-voltage supply temperature characteristics

- 4-V supply: about -0.5 mV/ $^{\circ}$ C
- 5-V supply: about -0.6 mV/ $^{\circ}$ C
- 7-V supply: about -2.5 mV/ $^{\circ}$ C

10. FG amplifier

The FG amplifier gain is determined by R1 and R2, and the DC gain, G, will be $R2/21$. The FG amplifier frequency characteristics are determined by C4 and C5. (R1 and C4 form a high-pass filter and R2 and C5 form a low-pass filter.) Since the FG amplifier output is input to a Schmitt comparator, set up values for R1, R2, C4, and C5 so that the FG amplifier output has an amplitude of at least 250 mV p-p. (It is desirable to set up the FG amplifier so that its output has an amplitude of between 1 and 3 V p-p during steady state motor operation.)

11. External capacitors

- C3

C3 is required to stabilize the FG_{IN}^+ pin fixed-voltage supply and to generate the initial reset pulse for the IC internal logic. Although a relatively small capacitance suffices for power supply stabilization, a larger capacitance (about 4.7 μ F) is required to generate the reset pulse. The reset pulse is generated at the time when the FG_{IN}^+ pin goes from 0 V to about 1.3 V. If the reset function does not operate, the LD pin may go on briefly at startup. If this phenomenon is not a problem, a capacitance of around 0.1 μ F can be used for C3. After C3 is charged to 4 V, if V_{CC} is turned off (or the IC is set to stop mode), the capacitor will be discharged by an IC-internal load of about 10 k Ω that is connected to this capacitor.

- C1 and C2

C1 and C2 are required for fixed-voltage supply stabilization. Since this IC adopts a direct PWM technique and switches large currents in the outputs, it is extremely easy for noise to be generated. Therefore, adequate power-supply stabilization is required to prevent that noise from causing incorrect circuit operation. C1 through C3 must be connected to GND1 with lines that are as short as possible. In particular, C1 can easily influence system characteristics and requires care.

12. External resistors

- R4 and R5

R4 and R5 are used to apply the high-level input to the F/R pin. Since the F/R pin has a built-in pull-down resistor which is about 50 k Ω , it will be at the low level when left open. A voltage of between 4.0 and 6.3 V must be applied to input a high level to the F/R pin.

- R15

R15 is used to apply the high-level input to the S/S pin. Since the S/S pin has a built-in pull-down resistor which is about 50 k Ω , it will be at the low level when left open. (A voltage of between 4.0 and 6.3 V must be applied to input a start-state high level to the S/S pin.) As is the case with the F/R input, using a two-resistor voltage divider to apply a voltage to the S/S pin provides better noise immunity since a lower input impedance can be set up. However, in applications where noise is not a problem, the high level may be applied with a single resistor, as is done with R15 in this circuit.

When V_{CC} is first applied, if V_{CC} comes up slowly (around 10 mV/ms or slower) the motor may turn somewhat even though the circuit is in stop mode. This is because the S/S pin input voltage is provided through a two-resistor voltage divider and when V_{CC} is still relatively low, the S/S pin input voltage will be below 2.6 V, which is the start mode input level. If it is impossible to increase the speed with which the power voltage is brought up and this is a problem, a capacitor may be inserted between V_{CC} and the S/S pin to resolve the problem.

13. Through currents due to the direct PWM technique

In the direct PWM technique, through currents may flow in the output due to the switching. (This occurs in both discrete component implementations as well as with the LB1822.) This is due to the delay and parasitic capacitors in the output transistors. Earlier application used capacitors to deal with this problem if it occurred. However, since this IC includes circuits designed to deal with this phenomenon, there is no need for external components to deal with these currents. During switching, whiskers of up to about 10 ns may appear in the Rf waveform, but they will not cause problems in applications.

14. Oscillators

Normally, applications using this IC will use a crystal oscillator. However, it may be possible to use a ceramic oscillator in applications in which the requirements on the speed control characteristics are not demanding. To avoid problems, always consult the manufacturer of the oscillator element concerning the values of the external capacitors and resistors used.

15. IC internal power dissipation calculation (calculated for $V_{CC} = 12\text{ V}$ with typical specifications)

- Power dissipation due to the supply current (I_{CC})
 Stop mode:
 $P1 = V_{CC} \times I_{CC1} = 12 \times 34\text{ m} = 0.41\text{ W}$
 Start mode:
 $P2 = V_{CC} \times I_{CC2} = 12 \times 8\text{ m} = 0.08\text{ W}$
- Power dissipation when a -10-mA load current is drawn from the 7-V fixed voltage output.
 $P3 = (V_{CC} - 7) \times 10\text{ m} = 5 \times 10\text{ m} = 0.05\text{ W}$
- Power dissipation due to the output drive current (when the output duty is 100%)
 $P4 = \{(V_{CC} - 1)^2/8k\} + \{(V_{CC} - 2)^2/10k\} = (11^2/2k) + (10^2/4k) = 0.09\text{ W}$
- Power dissipation in the output transistors (when $I_O = 2\text{ A}$, the output duty is 100%)
 $P5 = V_O(\text{sat})2 \times I_O = 2.7 \times 2 = 5.4\text{ W}$
 Therefore, the IC overall power dissipation will be:
 Start mode:
 $P = P2 = 0.08\text{ W}$
 Stop mode:
 $P = P1 + P3 + P4 + P5 = 5.95\text{ W}$
 (For an output duty of 100%)

16. Techniques for measuring IC internal temperature increases

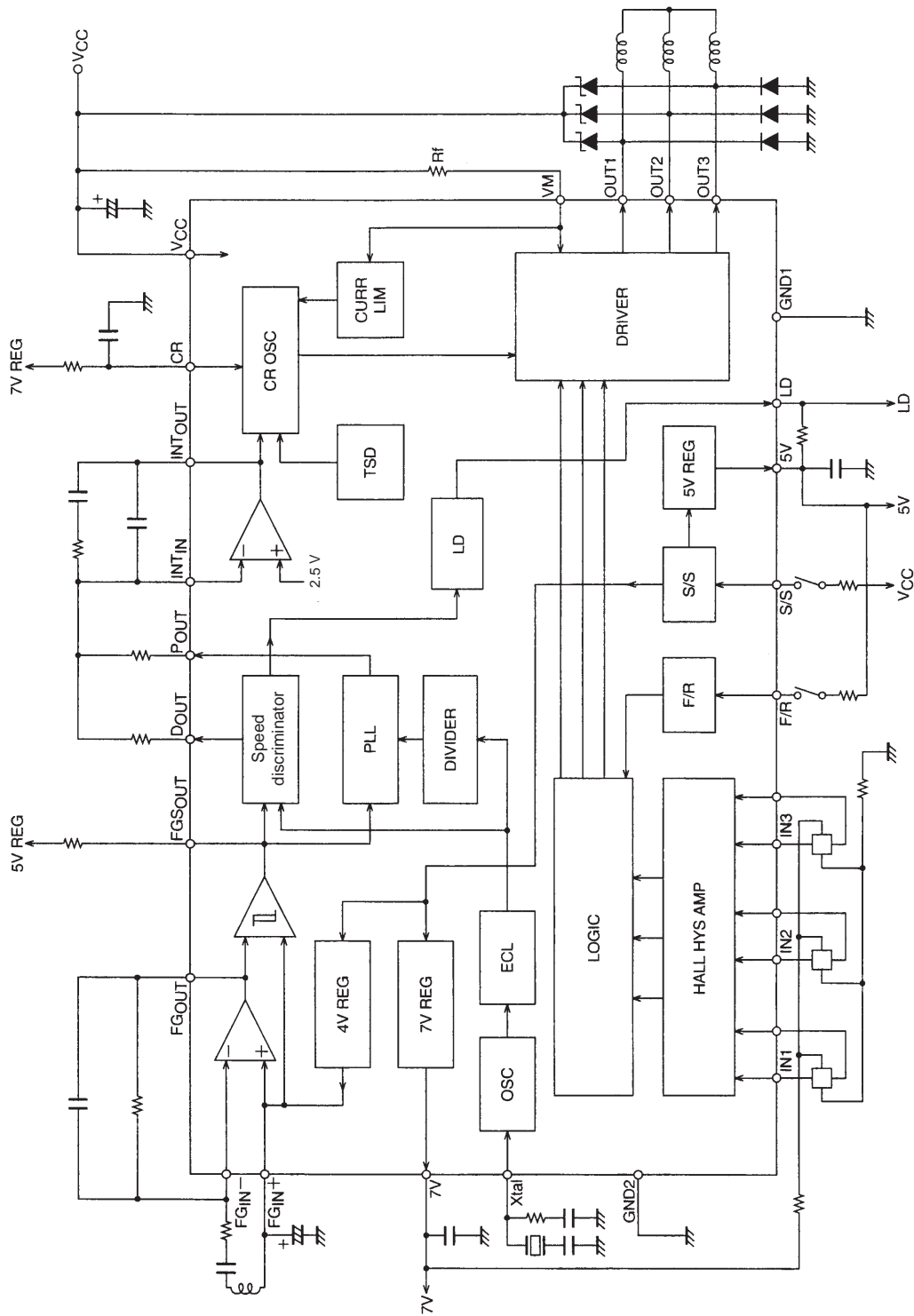
- Thermocouple measurement
 When using a thermocouple for temperature measurement, the thermocouple is attached to a fin on the heat sink. While this measurement technique is simple, it suffers from large measurement errors when the thermal generation process is not at steady state.
- Measurement using IC internal diode properties
 We recommend using the properties of the parasitic diode that exists between INT_{IN} and ground for measuring the temperature of this IC. (Sanyo data: For $I_D = 1\text{ mA}$, the temperature characteristic is about $1.8\text{ mV}/^\circ\text{C}$.) The external resistor must be disconnected when measuring the temperature.

17. Servo constants

The servo constant calculations depend strongly on the characteristics of the motor used and require special expertise. Normally, the motor manufacturer will set up these constants. Sanyo can provide the data required for the servo constant calculations. This data includes both the characteristics data for this IC as well as the frequency characteristics simulation data for the filter characteristics set up by the motor manufacturer.

If the resistor ($R10$) between D_{OUT} and INT_{IN} is too small, then $C8$ and $C9$ will become excessively large, and if $R10$ is too large, then speed errors due to the speed discriminator shutoff current and the integrator input current will become more likely to occur. Therefore, this resistor should have a value in the range 10 to $100\text{ k}\Omega$. If the resistor ($R8$) between P_{OUT} and INT_{IN} is too small, the influence of the PLL system will become excessive and the lock state pull-in characteristics will be degraded. Thus the value of this resistor must not be made too small. We recommend a value of around $1\text{ M}\Omega$ when $R10$ is $75\text{ k}\Omega$. Applications must be designed by first setting up only the speed discriminator system ($R9$, $R10$, $C8$, and $C9$) and only then setting up the PLL system resistor $R8$.

Equivalent Circuit Block Diagram



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- This catalog provides information as of July, 1999. Specifications and information herein are subject to change without notice.