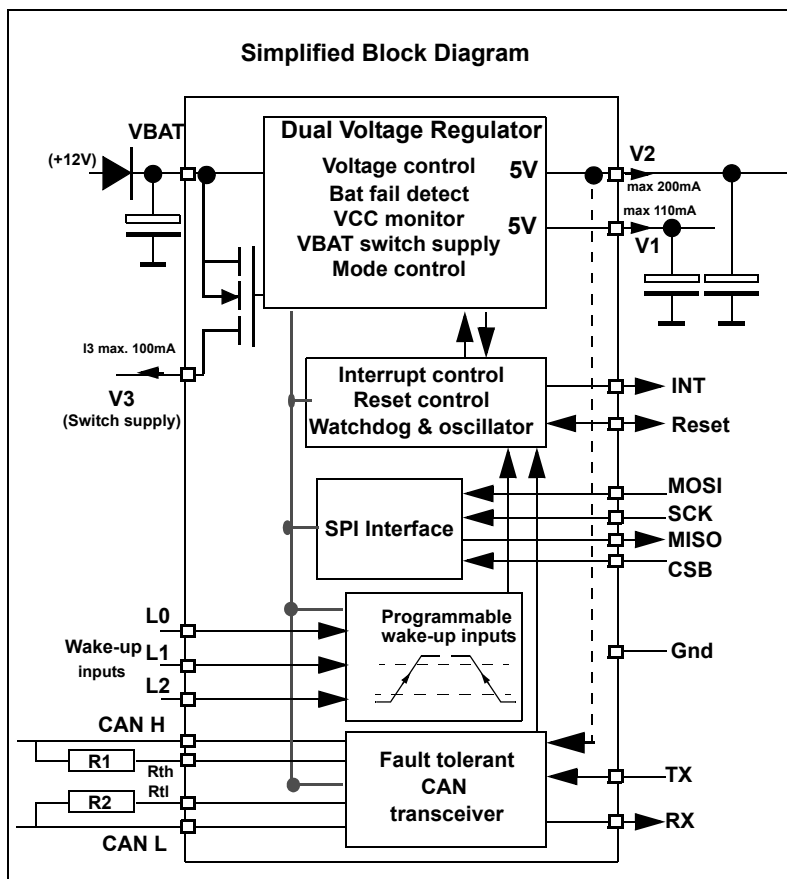


Advance Information

System Basis Chip with Low Speed Fault Tolerant CAN

The MC33389 is a monolithic integrated circuit combining many functions frequently used by automotive ECUs. It incorporates a low speed fault tolerant CAN transceiver.

- Dual Low Drop Voltage Regulators, with Respectively 100mA and 200mA Current Capabilities, Current Limitation and Over Temperature Detection with Prewarning
- 5V Output Voltage for V1 Regulator
- Three Operational Modes (Normal, Standby and Sleep Mode) Separated from the CAN Interface Operating Modes
- Low Speed 125kBaud Fault Tolerant CAN Interface, Compatible with MC33388 Standalone Physical Interface
- V1 Regulator Monitoring and Reset Function
- Three External High Voltage Wake-up Inputs, Associated with V3 V_{bat} Switch
- 100mA Output Current Capability for V3 V_{bat} Switch Allowing Drive of External Switches or Relays
- Low Standby and Sleep Current Consumption
- V_{bat} Monitoring and V_{bat} Failure Detection Capabilities
- DC Operating Voltage up to 27V
- 40V Maximum Transient Voltage
- Programmable Software Window Watchdog and Reset
- Wake up Capabilities (CAN Interface, Local Programmable Cyclic Wake up)
- Interface with MCU through SPI
- Programmable Interrupt Function



MC33389

AUTOMOTIVE SBC
SYSTEM BASIS CHIP

SILICON MONOLITHIC
INTEGRATED CIRCUIT

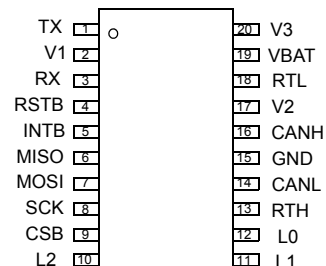
PIN CONNECTIONS

DH SUFFIX

POWER PACKAGE

CASE 979C

HSOP-20

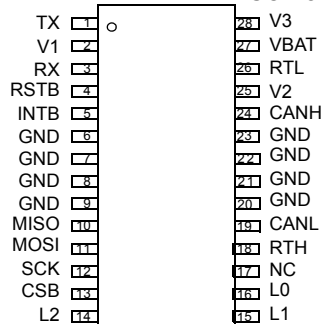
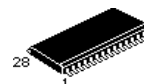


DW SUFFIX

PLASTIC PACKAGE

CASE 751F

SO-28



ORDERING INFORMATION

| Device and version | Operating Temperature Range | Package |
|--------------------|------------------------------------|---------|
| MC33389ADW (1) | $T_A = -40$ to 125°C | SO-28 |
| MC33389ADH (1) | $T_A = -40$ to 125°C | HSOP20 |
| MC33389CDW (2) | $T_A = -40$ to 125°C | SO-28 |
| MC33389CDH (2) | $T_A = -40$ to 125°C | HSOP20 |
| MC33389DDW (3) | $T_A = -40$ to 125°C | SO-28 |

(1) Version A: If device remains in reset greater than 100ms due to V1 undervoltage, device switches to sleep mode to minimise current consumption. Wake-up configuration active.

(2) Version C: In V1 undervoltage condition, device remains in permanent reset state until V1 returns to nominal conditions. V1 protected by overcurrent and over temperature functions.

(3) Version D: In V1 undervoltage condition, device remains in permanent reset state until V1 returns to nominal conditions. V1 protected by overcurrent and over temperature functions. Change of undervoltage reset threshold. Refer to electrical parameter table, V1 Pin 5V.

MAXIMUM RATINGS

| Description | Symbol | Min | Typ | Max | Unit | Test Conditions |
|--|-----------|------|-----|-----|--------------------|--|
| DC Voltage at Pin V_{bat} | V_{bat} | -0.3 | | 27 | V | |
| Transient Voltage at Pin V_{bat} | | | | 40 | V | $t < 500\text{ms}$ (Load Dump) |
| DC Voltage at Pins CANH CANL | | -20 | | 27 | V | |
| Transient Voltage at Pins CANH CANL | | -40 | | 40 | V | $0 < V_2 < 5.5$, $V_{bat} > 0$, $t < 500\text{ms}$ |
| Coupled Transient Voltage at Pins CANH CANL | | -100 | | 100 | V | With 100 Ω Termination Resistors. Coupled Through 1nF (note1) |
| DC Voltage at Pins V1 V2 | | -0.3 | | 6 | V | |
| DC Current at output pins: RX, MISO, RSTB, INTB | | -20 | | 20 | mA | |
| DC Voltage at input pins TX, MOSI, SCLK, CSB, RSTB | | -0.3 | | 6 | V | |
| DC Voltage at Pins L0, L1, L2 | | -0.3 | | 40 | V | $0 < V_{bat} < 40\text{V}$ |
| Current at Pins L0, L1, L2 | | -15 | | | mA | |
| Transient Current at Pin V3 | | -30 | | 20 | mA | |
| DC Voltage at Pins RTH, RTL | | -0.3 | | 40 | V | |
| ESD Voltage on any Pin (HBM 100pF, 1.5K) | | -2 | | 2 | kV | |
| ESD Voltage on L0, L1, L2, CANH, CANL, V_{bat} | | -2 | | 2 | kV | |
| ESD Voltage on any Pin (MM 200pF, 0 Ω). | | -150 | | 150 | V | |
| Junction Temperature | T_j | -40 | | 150 | $^{\circ}\text{C}$ | |
| Junction Temperature | T_{jt} | -40 | | 160 | $^{\circ}\text{C}$ | |
| Storage Temperature | T_s | -65 | | 150 | $^{\circ}\text{C}$ | |
| RTH, RTL Termination Resistance | | 500 | | 16k | Ω | |
| Junction to Heatsink Thermal Resistance for HSOP20 | | | 3.1 | | K/W | 33% Power on V1, 66% on V2 (Including CAN), Note 2 |
| Junction to Pin Thermal Resistance for SO28WB | | | 17 | | K/W | Note 2, Note 3 |

NOTE 1: Pulses 1, 2, 3a, 3b according to ISO7637.

NOTE 2: Refer to thermal management in device description section.

NOTE 3: pins 6,7,8,9,20,21,22,23 of SO28WB package

ELECTRICAL PARAMETERS $V_{bat}=5.5V$ to $18V$, $-40^{\circ}C < T_j < 150^{\circ}C$, unless otherwise specified

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|---------------------------------|--------------|-----|-----|-----|---------|---|
| V_{bat} PIN | | | | | | |
| Nominal Vbat Operating Range | | 5.5 | | 18 | V | |
| Functional Vbat Operating Range | | 5.5 | | 27 | V | |
| Vbat Threshold for BatFail Flag | BatFail | 2 | | 4 | V | $0 < V_1 < 5.1V$ |
| Delay for Signalling BatFail | T_{fail} | | 150 | 400 | μs | $V_{bat} < \text{BatFail}$, measured from Vbat low to INT active |
| Overvoltage Vbat Threshold | BAThigh | 18 | 20 | 22 | V | |
| Delay for Setting BAThigh Flag | T_{high} | 4 | 18 | 50 | μs | $V_{bat} > \text{BatHigh}$ |
| Supply Current in Sleep Mode | I_{sleep1} | | 75 | 125 | μA | Forced Wake-up and Cyclic Sense Disabled $V_{bat}=12V$, $T_j = 25^{\circ}C$ to $150^{\circ}C$ |
| Supply Current in Sleep Mode | I_{sleep2} | | | 210 | μA | Forced Wake-up and Cyclic Sense Disabled $V_{bat}=12V$, $T_j = -40^{\circ}C$ to $25^{\circ}C$ |
| Supply current in sleep mode | I_{sleep3} | | 105 | 155 | μA | Forced Wake-up or Cyclic Sense Enabled. $V_{bat}=12V$, $T_j = 25^{\circ}C$ to $150^{\circ}C$ |
| Supply Current in Sleep Mode | I_{sleep4} | | | 250 | | Forced Wake-up or Cyclic Sense Enabled $V_{bat} 12V$, $T_j -40$ to $25^{\circ}C$, |
| Supply Current in Sleep Mode | I_{sleep5} | | | 300 | | Forced Wake-up or Cyclic Sense Enabled. $V_{bat} 6V$ to $16V$, $T_j -40$ to $150^{\circ}C$ |
| Supply Current in Standby Mode | I_{stb2} | | 0.5 | 1 | mA | |
| Supply Current in Normal Mode | I_{nrec} | | 3.5 | 7 | mA | Normal Mode with $I(V_1)=I(V_2)=0$ Bus in Recessive State |

V1 PIN 5V

| | | | | | | |
|--|-------------------|------|------|------|-------------|---|
| Output Voltage | V_{1nom} | 4.85 | 5 | 5.15 | V | $0mA < I_{out} < 100mA$ $5.5V < V_{bat} < 27V$ |
| Output Voltage | V_1 | 4.8 | 5 | 5.2 | V | $I_{out} \leq 100mA$ $27V < V_{bat} < 40V$ |
| Drop Voltage | V_{1drop} | | 0.35 | 0.5 | V | $I_{out}=100mA$ (Note 4) |
| Output Current Limitation | I_{1max} | 130 | 170 | 200 | mA | $V_{1nom}-100mV$ |
| V1 Overtemp Shut-off Threshold | TV_{1h} | 160 | | 190 | $^{\circ}C$ | Junction Temperature |
| V1 Pre-warning Temp Threshold | TV_{1l} | 130 | | 160 | $^{\circ}C$ | Junction Temperature |
| Temperature Thresholds Difference | $TV_{1h}-TV_{1l}$ | 20 | | 40 | $^{\circ}C$ | |
| Reset Threshold on V1 (A and C versions) | V_{r1} | 4.1 | 4.3 | 4.8 | V | $5.5V < V_{bat} < 27V$ |

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|--|-----------|--------|----------|--------|---------|---|
| Reset Threshold on V1 (D version) | V_{r1} | V1-0.4 | V1-0.28 | V1-0.1 | V | $5.5V < V_{bat} < 27V$ |
| Reset Active V1 Range | $V1_r$ | 1 | V_{r1} | | V | |
| Reset Delay Time | t_d | 2 | | 20 | μs | |
| Line Regulation | | -15 | 2 | +15 | mV | $9V < V_{bat} < 16.5, I_{load} = 10mA$ |
| Line Regulation | | -50 | 10 | +50 | mV | $5.5V < V_{bat} < 27V, I_{load} = 10mA$ |
| Load Regulation | | -50 | | +50 | mV | $1mA < I_{load} < 100mA$ |
| Line Ripple Rejection | | 30 | 55 | | dB | 100Hz, $1V_{pp}$ on $V_{bat} = 12V$, $I_{load} = 100mA$, guaranteed by design |
| Line Transient Response | | | 27 | | mV | V_{bat} from 12V to 40V in $1\mu s$, ($10\mu F$, $ESR = 3\Omega$) |
| Load Transient Response | | | 400 | | mV | I_{load} from 10 μA to 100mA in $1\mu s$ ($C_{load} = 10\mu F$ $esr = 3\Omega$) (Note 5) |
| Load Transient Response | | | 16 | | mV | I_{load} from 10 μA to 100mA in $1\mu s$ ($C_{load} = 10\mu F$ $esr = 0.1\Omega$) |
| Reverse Current From V1 to V_{bat} and Gnd | I_{Rev} | | | 1 | mA | $V1 = 4.9V, 0 < V_{bat} < 4.9V$ |

NOTE 4: Measured when V1 has dropped 100mV below its nominal value.

NOTE 5: This condition does not produce reset.

V2 PIN

| | | | | | | |
|-----------------------------------|-------------|------|------|------|-------------|--|
| Output Voltage | $V2_{nom}$ | 4.75 | 5 | 5.25 | V | $0mA < I_{out} < 200mA$ $5.5V < V_{bat} < 40V$ |
| Drop Voltage | $V2_{drop}$ | | 0.2 | 0.5 | V | $I_{out} = 200mA$ (Note 6) |
| Drop Voltage | $V2_{drop}$ | | 0.05 | 0.15 | V | $I_{out} = 20mA$ (Note 6) |
| Output Current Limitation | $I1_{max}$ | 220 | 280 | 350 | mA | $V2_{nom} - 100mV$ |
| Threshold on V2 to Report V2 off | V_{r2} | 4.1 | 4.55 | 4.75 | V | V2 Nominal |
| V_{r2} Delay Time | | 20 | | 70 | μs | |
| V2 Overtemp Pre-warning Threshold | T_{V2l} | 130 | | 160 | $^{\circ}C$ | V2 Junction Temperature |
| V2 Overtemp Switch-off Threshold | T_{V2h} | 155 | | 185 | $^{\circ}C$ | V2 Junction Temperature |
| Line Regulation | | -15 | | +15 | mV | $9V < V_{bat} < 16.5$ |
| Load Regulation | | -75 | | +75 | mV | $4mA < I_{load} < 200mA$ |
| Line Ripple Rejection | | 30 | 55 | | dB | 100Hz, $1V_{pp}$ on V_{bat} , guaranteed by design |
| Percentage Difference V2-V1 | | -3 | | 3 | % | $V_{bat} > 9V, I_{V1} = 20mA,$ $I_{V2} = 40mA$ |

NOTE 6: Measured when V2 has dropped 100mV below its nominal value.

V3 PIN

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|---|-------------|-----|-----|-----|-------------|---|
| High Level Voltage Drop | V_{3drop} | | 0.4 | 1 | V | $I_{V3}=-50mA, 9V<V_{bat}<40V$ |
| High Level Voltage Drop | V_{3drop} | | | 1.5 | V | $I_{V3}=50mA, 6V<V_{bat}<9V$ |
| V3 Output Current Limitation | I_{3lim} | 100 | 15 | 250 | mA | $5.5V<V_{bat}<27V$ |
| V3 Leakage Current | I_{3leak} | | | 15 | μA | $V3=0$ (V3 off) |
| V3 Overtemp Detection | T_{V3} | 155 | | 185 | $^{\circ}C$ | Junction Temperature |
| V3 voltage with -30mA (negative current for Relay Switch off) | V_{V3} | 0.3 | | 0.5 | V | For $t\leq 100ms$, no Functional Error Allowed |

CAN TRANSCEIVER

| | | | | | | |
|---|-----------|---|-----|-----|---|--|
| V2 for Forced BusStandby Mode (Fail Safe) | V_{rc2} | 3 | 3.9 | 4.7 | V | |
|---|-----------|---|-----|-----|---|--|

CANH, CANL Pins

| | | | | | | |
|--|-----------------------|---------------|------|---------------|---------|---|
| Differential Receiver, Threshold Voltage | | -3.2 | | -2.5 | V | |
| Differential Receiver, Dominant to Recessive Threshold | | -3.2 | | -2.5 | V | (Bus failures 1, 2, 5) |
| CANH Recessive Output Voltage | V_{canh} | | | 0.2 | V | $TX=high, R(RTH)<4k$ |
| CANL Recessive Output Voltage | V_{canl} | $V2-0.2$ | | | V | $TX=high, R(RTL)<4k$ |
| CANH Output Voltage, Dominant | V_{canh} | $V2-1.4$ | | | V | $TX=0V$; BusNormal Mode, $I_{canh}=-40mA$ |
| CANL Output Voltage, Dominant | V_{canl} | | | 1.4 | V | $TX=0V$; BusNormal Mode, $I_{canl}=40mA$ |
| CANH Output Current Limit | I_{canh} | 50 | 75 | 100 | mA | ($V_{canh}=0, TX=0$) |
| CANL Output Current Limit | I_{canl} | 50 | 95 | 130 | mA | ($V_{canl}=14V, TX=0$) |
| Detection Threshold for Short-circuit to Battery Voltage | $V_{canh}V_{canl}$ | 7.3 | 7.9 | 8.9 | V | BusNormal Mode |
| Detection Threshold for Short-circuit to Battery Voltage | V_{canh} | $V_{bat}/2+3$ | | $V_{bat}/2+5$ | V | BusStandby Mode |
| CANH Output Current, Failure3 | | | 5 | 10 | μA | BusStandby Mode $V_{canh}=12V$ |
| CANL Output Current, Failure4 | | | 0 | 2 | μA | BusStandby Mode, $V_{canl}=0V, V_{bat}=12V$ |
| CANL Wake up Voltage Threshold | V_{wakeL} | 2.5 | 3.3 | 3.9 | V | BusStandby Mode |
| CANH Wake up Voltage Threshold | V_{wakeH} | 1.2 | 2 | 2.7 | V | BusStandby Mode |
| Wake up Threshold Difference | $V_{wakeL}-V_{wakeH}$ | 0.2 | | | V | |
| CANH Single Ended Receiver Threshold | V_{canh} | 1.5 | 1.85 | 2.15 | V | Failures 4,6,7 |
| CANL Single Ended Receiver Threshold | V_{canl} | 2.8 | 3.05 | 3.4 | V | Failures 3,8 |
| CANL Pull up Current | I_{canlpu} | 45 | 75 | 90 | μA | BusNormal Mode |

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|---|--------------|-----|-----|-----|------------------|-----------------|
| CANH Pull Down Current | I_{canlpd} | 45 | 75 | 90 | μA | BusNormal Mode |
| Receiver Differential Input Impedance CANH / CANL | R_{diff} | 100 | | 180 | $\text{k}\Omega$ | |
| Differential Receiver Common Mode Voltage Range | V_{com} | -8 | | 8 | V | |

RTH, RTL Pins

| | | | | | | |
|-------------------------------------|-----------|----|------|----|------------------|---|
| RTL to V2 Switch on Resistance | R_{rtl} | 10 | 25 | 70 | Ω | $I_{out} < -10\text{mA}$, BusNormal Operating Mode |
| RTL to BAT Switch Series Resistance | R_{rtl} | 8 | 12.5 | 20 | $\text{k}\Omega$ | BusStandby Mode |
| RTH to Ground Switch on Resistance | R_{rth} | | 25 | 70 | Ω | $I_{out} < 10\text{mA}$, All Mode |

THERMAL SHUTDOWN

| | | | | | | |
|----------------------|----------|--|-----|--|--------------------|--|
| Shutdown Temperature | T_{sd} | | 165 | | $^{\circ}\text{C}$ | |
|----------------------|----------|--|-----|--|--------------------|--|

AC CHARACTERISTICS

| | | | | | | |
|--|------------|------|-----|------|------------------------|--|
| CANL and CANH Slew Rates, Rising or Falling Edges, Tx from Recessive to Dominant State | | 3.5 | 5 | 10 | $\text{V}/\mu\text{s}$ | $C_{load} = 10\text{nF}$, 133Ω Termination Resistors |
| CANL and CANH Slew Rates, Rising or Falling Edges, Tx from Dominant to Recessive State | | 2 | 3.5 | 10 | $\text{V}/\mu\text{s}$ | $C_{load} = 10\text{nF}$, 133Ω Termination Resistors |
| Propagation Delay TX to RX Low | T_{dh} | | 1.2 | 2 | μs | $C_{load} = 10\text{nF}$, 133Ω Termination Resistors |
| Propagation Delay TX to RX High | T_{dl} | | 2 | 3 | μs | $C_{load} = 10\text{nF}$, 133Ω Termination Resistors |
| Min. Dominant Time for Wake-up on CANL or CANH | T_{wake} | 4 | | 40 | μs | BusStandby Mode, $V_{bat} = 12\text{V}$ |
| Failure 3 Detection Time | | 10 | | 60 | μs | BusNormal Mode |
| Failure 3 Recovery Time | | 10 | | 60 | μs | BusNormal Mode |
| Failure 6 Detection Time | | 50 | | 400 | μs | BusNormal Mode |
| Failure 6 Recovery Time | | 150 | | 1000 | μs | BusNormal Mode |
| Failure 4, 7, 8 Detection Time | | 0.75 | | 4 | ms | BusNormal Mode |
| Failure 4, 7, 8 Recovery Time | | 10 | | 60 | μs | BusNormal Mode |
| Failure 3, 4, 7 Detection Time | | 0.8 | | 8 | ms | BusStandby Mode, $V_{bat} = 12\text{V}$ |
| Failure 3, 4, 7 Recovery Time | | | 2.5 | | ms | BusStandby Mode, $V_{bat} = 12\text{V}$ |
| Edge Count Difference Between CANH and CANL for Failures 1, 2, 5 Detection | | | 3 | | | BusNormal Mode |
| Edge Count Difference Between CANH and CANL for Failures 1, 2, 5 Recovery | | | 3 | | | BusNormal Mode |

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|--|------------------|------|-----|-----|------|---------------------------------|
| TX Permanent Dominant Timer Disable Time | T_{txd} | 0.75 | | 4 | ms | BusNormal Mode and Failure Mode |

TX, MOSI, SCK, CSB

| | | | | | | |
|---------------------------------|-----------------|-------|------|---------|---------------|----------------------------|
| High Level Input Voltage | | 0.7V1 | | V1+0.3V | | |
| CSB Threshold for SPI Wake-up | | | 2.2 | | V | SBC in Sleep Mode, V1<1.5V |
| CSB Filter Time for SPI Wake-up | | | | 3 | μs | SBC in Sleep Mode, V1<1V |
| Low Level Input Voltage | | -0.3 | | 0.3 V1 | V | |
| High Level Input Current on CSB | | -100 | | -20 | μA | $V_i=4\text{V}$ |
| Low Level Input Current (CSB) | | -100 | | -20 | μA | $V_i=1\text{V}$ |
| TX High Level Input Current | I_{TX} | -200 | -80 | -25 | μA | $V_i=4\text{V}$ |
| TX Low Level Input Current | I_{TX} | -800 | -320 | -100 | μA | $V_i=1\text{V}$ |
| SI, SCK Input Current | | -10 | | 10 | μA | $0 < V_{\text{IN}} < V1$ |

RX, INTB, MISO

| | | | | | | |
|-----------------------------|-----------------|--------|--|-----|---------------|----------------------------------|
| High Level Output Voltage | V_{oh} | V1-0.9 | | V1 | V | $I_0=-250\mu\text{A}$ |
| Low Level Output Voltage | V_{ol} | 0 | | 0.9 | V | $I_0=1.5\text{mA}$ |
| Tristated SO Output Current | I_z | -2 | | +2 | μA | $0\text{V} < V_{\text{so}} < V1$ |

RSTB Pin

| | | | | | | |
|---|------------------|-------|------|---------|---------------|---|
| High Level Input Voltage | V_{ih} | 0.7V1 | | V1+0.3V | | |
| Low Level Input Voltage | V_{il} | -0.3 | | 0.3V1 | V | |
| High Level Output current 1 | | -50 | -30 | -10 | μA | $0 < V_{\text{out}} < 0.5V1$ |
| High Level Output current 2 | | | -300 | | μA | $0.5 < V_{\text{out}} < V1$ |
| Low Level Output Voltage ($I_0=1.5\text{mA}$) | | 0 | | 0.9 | V | $1\text{V} < V_{\text{bat}} < 27\text{V}$ |
| Reset Duration after V1High | t_{res} | | 1 | | ms | |

L0, L1, L2 WAKE-UP INPUTS

| | | | | | | |
|--|-------------------|-----|-----|-----|---------------|---|
| Positive Switching Threshold | V_{wup} | 3 | 3.7 | 4.5 | V | $6\text{V} < V_{\text{bat}} < 16\text{V}$ |
| Negative Switching Threshold | V_{wun} | 2.5 | 3 | 3.8 | V | $6\text{V} < V_{\text{bat}} < 16\text{V}$ |
| Hysteresis | V_{hyst} | | 700 | | mV | $6\text{V} < V_{\text{bat}} < 16\text{V}$ |
| Leakage Current $0 < V_{\text{wu}} < V_{\text{bat}}$ | | -5 | | +5 | μA | |
| Wake up Filter Time | | 8 | 20 | 38 | μs | |
| Lx input current @ 40V | V_{in} | | 350 | 600 | μA | |

DIGITAL INTERFACE TIMING

| | | | | | | |
|-------------------|--------------------|-----|--|--|----|--|
| SCLK Clock Period | t_{pSCLK} | 500 | | | ns | |
|-------------------|--------------------|-----|--|--|----|--|

| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|--|-------------------------------|-----|-----|------------|------|---|
| SCLK Clock High Time | t_{wSCLKH} | 175 | | | ns | |
| SCLK Clock Low Time | t_{wSCLKL} | 175 | | | ns | |
| Falling Edge of CSB to Rising Edge of SCLK | t_{lead} | 250 | 50 | | ns | |
| Falling Edge of SCLK to Rising Edge of CSB | t_{lead} | 250 | 50 | | ns | |
| SI to Falling Edge of SCLK | t_{SISU} | 125 | 25 | | ns | |
| Falling Edge of SCLK to SI | $t_{SI(hold)}$ | 125 | 25 | | ns | |
| SO Rise Time (CL = 220pF) | t_{rSO} | | 25 | 75 | ns | |
| SO Fall Time (CL = 220pF) | t_{fSO} | | 25 | 75 | ns | |
| SI, CSB, SCLK Incoming Signal Rise Time | t_{rSI} | | | 200 | ns | |
| SI, CSB, SCLK Incoming Signal Fall Time | t_{fSI} | | | 200 | | |
| Time from Falling Edge of CSB to SO Low Impedance High Impedance | $t_{SO(en)}$ $t_{SO(dis)}$ | | | 200 200 | ns | |
| Time from Rising Edge of SCLK to SO Data Valid | t_{valid} | | 50 | 125 | | 0.2 V1 or V2 ≤ SO ≤ 0.8V1 or V2, C _L = 200pF |

SOFTWARE WATCHDOG TIMINGS

(note 1: software watchdog timing accuracy are based on the running mode oscillator tolerance)

| | | | | | | |
|-----------------------------------|------|------|-----|------|----|--|
| Running mode oscillator tolerance | | -12 | | +12 | % | normal request, normal and standby modes. (Note 1) |
| Software Watchdog Timing 1 | SWt1 | 4.4 | 5 | 5.6 | ms | (Note 1) |
| Software Watchdog Timing 2 | SWt2 | 8.8 | 10 | 11.2 | ms | (Note 1) |
| Software Watchdog Timing 3 | SWt3 | 17.6 | 20 | 22.4 | ms | (Note 1) |
| Software Watchdog Timing 4 | SWt4 | 28 | 32 | 36 | ms | (Note 1) |
| Software Watchdog Timing 5 | SWt5 | 44.8 | 51 | 58 | ms | (Note 1) |
| Software Watchdog Timing 6 | SWt6 | 65 | 74 | 83 | ms | (Note 1) |
| Software Watchdog Timing 7 | SWt7 | 88 | 100 | 112 | ms | (Note 1) |
| Software Watchdog Timing 8 | SWt8 | 178 | 202 | 226 | ms | (Note 1) |

FORCED WAKE-UP AND CYCLIC SENSE TIMINGS

(note 2: cyclic sense and forced wake up timing accuracy are based on the sleep mode oscillator tolerance)

| | | | | | | |
|---------------------------------|------|------|-----|-------|----|---------------------|
| Sleep mode oscillator tolerance | | -30 | | +30 | % | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 1 | CYt1 | 22.4 | 32 | 41.6 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 2 | CYt2 | 44.8 | 64 | 83.2 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 3 | CYt3 | 89.6 | 128 | 166.4 | ms | sleep mode (Note 2) |

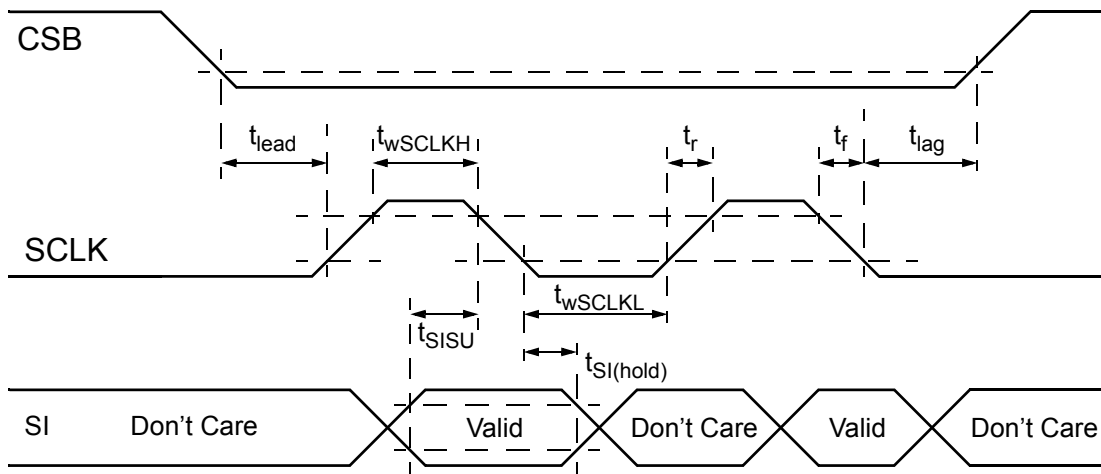
| Parameter | Symbol | Min | Typ | Max | Unit | Test Conditions |
|-----------------------------|--------|------|------|-------|------|---------------------|
| Cyclic Sense / FWU timing 4 | CYt4 | 179 | 256 | 333 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 5 | CYt5 | 358 | 512 | 665 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 6 | CYt6 | 717 | 1024 | 1331 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 7 | CYt7 | 1434 | 2048 | 2662 | ms | sleep mode (Note 2) |
| Cyclic Sense / FWU timing 8 | CYt8 | 5734 | 8192 | 10650 | ms | sleep mode (Note 2) |

GND SHIFT DETECTION

(note 3: no over lap between two adjacent thresholds).

| | | | | | | |
|-----------------------------------|-----|------|------|------|---|--|
| Ground Shift Threshold 1 (Note 3) | GS1 | -1 | -0.7 | -0.3 | V | CAN Transceiver Active In Two-wire Operation |
| Ground Shift Threshold 2 (Note 3) | GS2 | -1.5 | -1.2 | -0.8 | V | CAN Transceiver Active In Two-wire Operation |
| Ground Shift Threshold 3 (Note 3) | GS3 | -2 | -1.7 | -1.3 | V | CAN Transceiver Active In Two-wire Operation |
| Ground Shift Threshold 4 (Note 3) | GS4 | -2.6 | -2.2 | -1.7 | V | CAN Transceiver Active In Two-wire Operation |

Figure 1. Input Timing Switch Characteristics



DEVICE DESCRIPTION

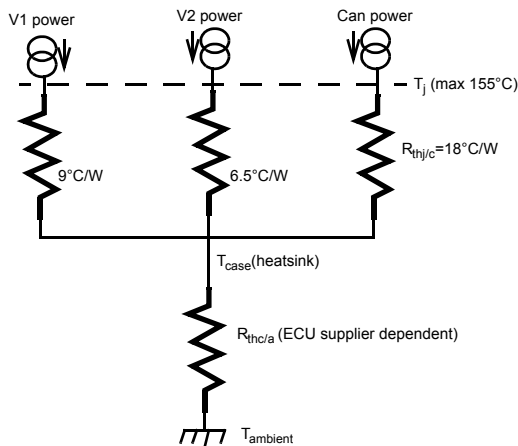
Thermal Management

The MC33389 is proposed in two different packages. HSOP20 for high power applications and SO28WB with 8 pins to the leadframe for medium power applications.

HSOP20 Package

For such a package, the heat flow is mainly vertical and each heat source (dissipating element) can be seen as an independent thermal resistance to the Heatsink. The thermal network can be roughly depicted as:

Figure 2. HSOP20 Simplified Thermal Model



Example

Assuming $I_{V1}=100\text{mA}$ at $V_{\text{bat}}=16\text{V}$,
 $I_{V2}=150\text{mA}$ at $V_{\text{bat}}=16\text{V}$ (Excluding CAN consumption).
 $I_{\text{CAN}}=50\text{mA}$ at $V_{\text{bat}}=16\text{V}$, we have :
 $P_{V1}=1.1\text{W}$, $P_{V2}=1.65\text{W}$, $P_{\text{can}}=0.55\text{W}$

System assumptions:

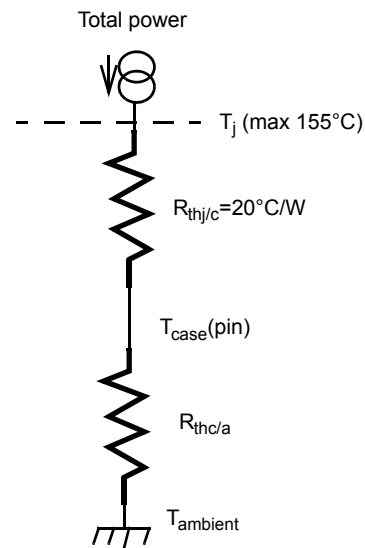
If $T_{\text{amb}}=85^\circ\text{C}$ and $R_{\text{thc/a}}=18^\circ\text{C/W}$, this gives:
 $T_{\text{case}}=T_{\text{amb}}+R_{\text{thc/a}} \times 3.3\text{W} = 85+18 \times 3.3=145^\circ\text{C}$
 and $T_{jV1}=T_{jV2}=T_{j\text{can}}=155^\circ\text{C}$.

This example represents the limit for the maximum power dissipations with a HSOP20.

SO28WB Package

The case(pin) to junction R_{th} is here represented by only one thermal resistance for the total power since the 3 power sources strongly interact on the silicon for such a package.

Figure 3. SO28WB Simplified Thermal Model



Example

Assuming $I_{V1}=45\text{mA}$ at $V_{\text{bat}}=16\text{V}$,
 $I_{V2}=45\text{mA}$ at $V_{\text{bat}}=16\text{V}$ (Excluding CAN consumption).
 $I_{\text{CAN}}=50\text{mA}$ at $V_{\text{bat}}=16\text{V}$, we have :
 $P_{V1}=0.5\text{W}$, $P_{V2}=0.5\text{W}$, $P_{\text{can}}=0.55\text{W}$ thus $P_{\text{total}}=1.55\text{W}$

System assumptions:

If $T_{\text{amb}}=85^\circ\text{C}$ and $R_{\text{thc/a}}=25^\circ\text{C/W}$, this gives:
 $T_{\text{case}}=T_{\text{amb}}+R_{\text{thc/a}} \times 1.55\text{W}=85+25 \times 1.55 = 124^\circ\text{C}$
 and $T_{jV1}=124 + 20 \times 1.55 = 155^\circ\text{C}$.

This example represents the limit for the maximum power dissipations with a SO28WB.

DEVICE DESCRIPTION

Introduction

The System Basis Chip is an integrated circuit dedicated to car body applications. It includes three main blocks :

- A dual voltage regulator
- Reset, watchdog, wake up inputs, cyclic wake up
- CAN low speed fault tolerant physical interface

Supplies

Two low drop regulators and one switch to V_{bat} are provided to supply the ECU microcontroller or peripherals, with independent control and monitoring through SPI.

Voltage Regulator V1

V1 is a 5V, 3% low drop voltage regulator dedicated to the microcontroller supply. It can deliver up to 100mA and is totally protected against short to ground (current limitation) and overtemperature. V1 is active in Normal request, Normal and standby modes.

No forward parasitic diode exists from V1 to V_{bat} . This means that, if V_{bat} voltage drops below V1, no high current flowing from V1 to V_{bat} will discharge the capacitor connected to V1. Its stored energy will only be used to supply the microcontroller and gives time to save all relevant data.

Undervoltage Reset

V1 is monitored for undervoltage (power up, power down) and a reset is provided at RSTB output for 1ms. This ensures proper initialization of the microcontroller at power-on or after supply is lost. On top of that, a flag is set in RSR register readable via the SPI.

Overtemperature Protection

V1 internal ballast transistor is monitored for overtemperature. Two detection thresholds are provided. A pre-warning threshold at 145°C and a shut-off threshold at 175°C. Once the first threshold is reached, a flag is set in the OTSR register. A maskable interrupt can be sent to the microcontroller. Once the second threshold is reached, a flag is set in the OTSR register, a maskable interrupt is sent to the microcontroller and V1 is switched off.

Once the junction temperature is back to the pre-warning threshold, V1 regulator it will be automatically switched on.

Table 4. V1 Control

| Conditions For V1 On | Conditions For V1 Off |
|--|--|
| NormalRequest mode (at V1 power on) | Sleep mode (via SPI) |
| Normal mode (via SPI) | Shut-off temperature threshold reached |
| Standby mode (via SPI) | No V_{bat} power supply (cold start) |
| V1 below pre-warning temperature threshold | Emergency mode |
| During Reset | |

Note: current capability of V1, V2 and V3 depends upon the thermal management. Over temperature shutdown might be reached and lead to turn off of V1, V2 and V3 for output current below their max current capability.

Voltage Regulator V2

V2 is a 5V low drop voltage regulator dedicated to peripherals supply. It can deliver up to 200mA and is protected

against short to ground (current limitation) and overtemperature. V2 is active in Normal mode.

Undervoltage Detection

V2 is monitored for undervoltage and a flag is set in the VSSR register.

Overtemperature Protection

V2 internal ballast transistor is monitored for overtemperature. Two detection thresholds are provided. A pre-warning threshold at 140°C and a shut-off threshold at 165°C. Once the first threshold is reached, a flag is set in the OTSR register which is readable. A maskable interrupt can be sent to microcontroller.

Once the second threshold is reached, a flag is set in the OTSR register, V2 is switched off. It can only be switched on again via the SPI.

Table 5. V2 Control

| Conditions For V2 On | Conditions For V2 Off |
|---|--|
| Normal mode (via SPI) AND V2 below shut off temperature threshold | Sleep mode, or standby mode or NormalRequest or emergency mode (via SPI) |
| | Shut-off temp. threshold reached |
| | V1 disabled (for any reason) |

Switch V3

V3 is a 10Ω switch to V_{bat} , it can be used to supply external contacts or relays. A great flexibility is given for the different possible ways for its control. It is protected against short to ground (current limitation).

Overtemperature Protection

V3 output transistor is monitored for overtemperature. Once the threshold is reached, a flag is set in the VSSR register, V3 is switched off. It will be automatically switched on once the junction temperature is back to the pre-warning threshold.

Table 6. V3 Control

| Conditions For V3 On | Conditions For V3 Off |
|---|--|
| Permanently in Normal mode if configured via SPI | Permanently in Normal mode if configured |
| Permanently in Standby mode if configured via SPI | NormalRequest mode |
| In sleep mode, during enable time of cyclic sense if configured | Permanently in Standby mode if configured |
| | Permanently in sleep mode if configured |
| | In sleep mode, during disable time of cyclic sense if configured |
| | Overtemp threshold reached |
| | V1 disabled (for any reason) |
| | V2 over temperature shutdown |

Supply and V_{bat} Block

V_{bat} Monitoring

V_{bat} is the main power supply coming from the Battery voltage after an external protection diode (for reverse battery).

DEVICE DESCRIPTION

V_{bat} is monitored for undervoltage and overvoltage.

V_{bat} Undervoltage

V_{bat} is monitored for undervoltage, if it is below 4V the BatFail flag is set in the VSSR register and a maskable interrupt is sent to the microcontroller.

V_{bat} Overvoltage

When V_{bat} is $> 20V$, the BatHigh flag is set in the VSSR register. A maskable interrupt is sent to the microcontroller. No specific action is taken to reduce current consumption (to limit power dissipation). This is to let the entire flexibility at the microcontroller for decision.

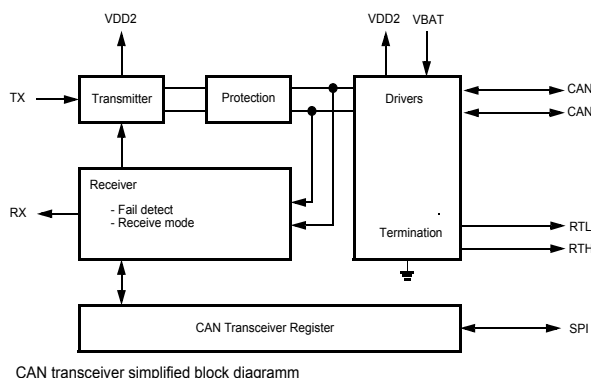
CAN Transceiver

The device incorporates a low speed 125kbaud CAN physical interface. Its electrical parameters for the CANL, CANH, Rtl, Rth, RX and TX pins are identical to the MC33388, standalone CAN physical interface.

The mode control for the CAN transceiver (normal, V_{bat} standby, sleep, etc...) are selectable through the MC33389 SPI interface.

- Baud Rate up to 125kbit/s
- Supports unshielded bus wires
- Short-circuit proof to Battery and Ground in 12V powered systems
- Supports single-wire transmission modes with Ground offset voltages up to 1.5V
- Automatic switching to single wire mode in case of Bus failures
- Automatic reset to differential mode if bus failure is removed
- Low EMI due to built in slope control and signal symmetry.
- Fully integrated receiver filters
- Thermally protected
- Bus lines protected against Automotive transients.
- Low Current BusStandby mode with wake-up capability via the Bus.
- An unpowered node does not disturb the bus lines.

Figure 7. CAN Simplified Block Diagram



CAN Transceiver Description

The CAN transceiver is an interface between CAN protocol controller and the physical bus. It is intended for low speed applications up to 125kbit/s in passenger cars. It

provides differential transmission capability, but will switch in error condition to single wire transmitter and/or receiver.

The rise and fall slopes are limited to reduce RFI. This allows use of an unshielded twisted pair or a parallel pair of wires for the bus. It supports transmission capability on either bus wire if one of the bus wire is corrupted. The logic failure detection automatically selects a suitable transmission mode.

In normal operation (no wiring failures), the differential bus state is output to RX. The differential receiver inputs are connected to CANH and CANL through integrated filters. The filtered inputs signals are also used for the single wire receivers. The CANH and CANL receivers have threshold voltages that assure maximum noise margin in single wire modes. In the RXOnly mode, the transmitter is disabled but the receive part of the transceiver remains active. In this mode, RX reports bus and TX activity ($R\bar{X} = \bar{T}X$ or Bus dominant). Failure detection and management is the same as BusNormal mode.

Failure Detector

The failure detector is active in RXTX and RXOnly operation mode and detects the following single bus failures and switches to an appropriate mode.

- 1- CANH wire interrupted
- 2- CANL wire interrupted or shorted to 5V
- 3- CANH short-circuited to battery
- 4- CANL short-circuited to ground
- 5- CANH short-circuited to ground
- 6- CANL short-circuited to battery
- 7- CANL mutually shorted to CANH
- 8- CANH to V2 (5V)

Note : Shorts-circuit failures are detected for 0 to 50Ω shorts.

The differential receiver (CANH-CANL) threshold is set at -2.8V, this assures a proper reception in the normal operating modes. In case of failures 1, 2 and 5 the on-going message is not destroyed due to noise margin

Failures 3 and 6 are detected by comparators respectively connected to CANH and CANL. If the comparator threshold is exceeded for a certain time, the reception is switched to single wire mode. This time is needed to avoid false triggering by external RF fields. Recovery from these failures is detected automatically after a certain time-out (filtering).

Failures 4 and 7 initially result in a permanent dominant level at RX. After a time out, the CANL driver and the RTL pin are switched off, only a weak pull up at CANL remains. Reception continues by switching to single wire mode through CANH. When the failures 4 or 7 are removed, the recessive bus levels are restored. If the differential voltage remains below the recessive threshold for a certain time, reception and transmission switch back to the differential mode.

If any of the 8 wiring failure occurs, a flag is set in the TESRH and TESRL status registers. 8 different types of errors are distinguished out of these 8 errors and are separately stored in these register (See SPI Register Description Section on page 21). A maskable interrupt is sent to the microcontroller. On error recovery, the corresponding flag is reset after read-out operation.

During all single wire transmissions, the EMC performance (both immunity and emission) is worse than in differential mode. Integrated receiver filters suppress any HF noise induced into the bus wires. The cut-off frequency of these filters is a compromise between propagation delay and HF suppression. In single wire mode, low frequency noise can not be distinguished from the wanted signal.

DEVICE DESCRIPTION

In the event of a permanent dominant TX state (for more than 2ms) the output drivers are disabled. That assures the operation of the complete system in case of a permanent dominant TX state of one control unit. A defect control unit autonomous go to RXOnly or TermVCC mode.

Low Power Modes

The transceiver provides a low power modes which can be entered and exit by a SPI command. This is the BusStandby mode with the lowest power consumption (for the transceiver). CANL is biased to the battery voltage via the RTL output and the pull-up current source on CANL and pull-down current source on CANH are disabled. Wake-up requests are recognized by the transceiver, when a dominant state is detected on either bus lines (Bus wake-up). On a Bus wake-up request the SBC will activate the INTB output or, if it is in sleep mode, switch to NormalRequest mode. This event is stored in the WUISR status register.

To prevent false wake-up due to transients or RF fields, wake-up threshold levels have to be maintained for a certain time. In the transceiver low power mode, failure detection circuit remains partly active to prevent increased power consumption in cases of error 3, 4, 7 and 8.

Power On

After the V_{bat} supply is switched on, the SBC is in NormalRequest mode. The corresponding mode for the CAN transceiver is BusStandby.

The CAN transceiver is supplied by V2. As long as V2 is below its undervoltage threshold, the transceiver is forced to BusStandby mode (fail safe property).

Protection

A current limiting circuit protects the transmitter output stages against short-circuit to positive and negative battery voltage. If the junction temperature exceeds a maximum value, the transmitter output stages are disabled. Because the transmitter is responsible for a part of the power dissipation, this will result in a reduced power dissipation and hence a lower chip temperature. All other parts of the transceiver will remain operating. The CANH and CANL inputs are protected against electrical transients which may occur in an automotive environment.

Consequence Of Failure Detections

S1 is the switch from RTH to Ground
 S2 is the switch from RTL to V2 and
 S3 is the switch from RTL to V_{bat}
 For each failure type is given which switch is open and which driver is disabled.

Failure 1 : nothing done
 Failure 2 : nothing done
 Failure3 : S1 open. Driver CANH is disabled
 Failure4 : S2 and S3 open. Driver CANL is disabled
 Failure5 : Nothing done
 Failure6 : S2 and S3 open. Driver CANL disabled
 Failure7: S2 and S3 open. Driver CANL disabled
 Failure8: S1 open. CANH driver disabled

CAN Transceiver Modes

The CAN transceiver has its own functioning modes: RXTX mode, TermVBAT/TermVCC mode, and RXOnly mode. They are controlled by TCR register.

RXTX mode

Full transmitting and receiving capabilities are enabled. Full failure detection is enabled.

Note: Standard/RXTX and Extended/RXTX are equivalent.

RXOnly mode

The transmitter is disabled but the receive part of the transceiver remains active. In this mode, RX reports bus and TX activity ($\overline{RX} = \overline{TX}$ or Bus dominant).

Note: Standard/RXOnly and Extended/RXOnly are equivalent.

BusStandby Mode

This is the low power mode for the CAN transceiver. The driver and receivers are disabled. Wake-up capability on both bus lines as well as failure 3, 4, 7, 8 detection are enabled. In bus standby mode RTL termination is set to V_{bat} .

Global Power Save Concept

The SBC allows to minimize power consumption of the ECU. Several operating modes are available to go to low power consumption when the full activity is not required. Several possibilities are provided to wake-up the ECU. This allows to have peripherals or the microcontroller switched off when no activity on the ECU is required.

Two switchable independent supply voltages (V1 and V2) are provided for optimum ECU power management.

Generalities

The SBC can be operated in four modes: Sleep, Standby, Normal and Emergency mode. After reset, the MC33389 is automatically initialised to a temporarily mode, NormalRequest, Waiting for microcontroller configuration.

Reset Mode

This mode is entered after SBC power up, or if an incorrect Software W/D trigger occurs. The minimum duration for reset mode is 1ms typical, and unless a V1 failure condition, the SBC enters the NormalRequest mode after reset.

In case of V1 failure condition leading to V1 low (ex: short to gnd), the SBC goes in reset mode. If V1 is still below reset threshold after 100ms, the behavior depends upon the device version A, C or D:

- A version : will enter sleep mode.
- C and D versions: will stay in reset mode.

NormalRequest Mode

This is the default mode after MC33389 reset. V1 is active, V2 and V3 are passive. The SBC is not configured. The default values are set in the registers. The SBC is waiting for configuration data via the SPI.

If no SPI data is received 75ms after the Reset is released, then the SBC switches itself to sleep mode.

The data the SBC must receive to consider that the microcontroller starts the configuration sequence is the SW timing word (in SWCR register). Once received this SW timing word, the watchdog timer becomes active. Then any other control data can be sent from the microcontroller to SBC.

The watchdog is not active in NormalRequest mode before the SW timing word is programmed into the SBC. In this mode, neither V2 nor the CAN transmitter are active.

DEVICE DESCRIPTION

SBC MODES

Table 8. NormalRequest: V1 active, V2&V3 passive

| Entering NormalRequest | Leaving NormalRequest |
|-------------------------|--|
| SBC reset just released | When firstly receiving the SW timing word, SBC goes to Normal |
| | If time-out without receiving SPI commands (75ms), SBC goes to sleep |

SBC Normal Mode

In this mode, V1 and V2 are active, V3 can be set active or passive via the SPI. Therefore, the whole ECU can be operated. Normal mode is entered by a SWCR register configuration in NormalRequest mode.

Table 9. SBC Normal Mode: V1 And V2 Are Active. V3 Is Active Or Passive

| Entering Normal Mode | Leaving Normal Mode |
|---|---|
| By SPI command | By SPI command, going to any other mode |
| After SWCR register configuration in NormalRequest mode | Watchdog time out, going to NormalRequest after activating Reset |
| | V1 undervoltage detection, going to NormalRequest mode after activating Reset |

SBC Standby Mode

In this mode V1 is active, V2 is passive. V3 can be either permanently active or permanently passive. This is a low power mode with V1 active in order to have a fast reaction time in case of any wake-up.

For standby mode, the SBC monitors the SW. It means the microcontroller runs and is monitored and must serve a watchdog trigger.

Table 10. Standby: V1 Active V2 Passive, V3 Active Or Passive, Watchdog Is Active

| Entering Standby | Leaving Standby |
|------------------|---|
| | If SW time-out going to NormalRequest after microcontroller Reset |
| By SPI command | By SPI command going to any other mode |
| | V1 undervoltage detection, going to NormalRequest mode after activating Reset |
| | External activation of the RSTB pin |

SBC Sleep Mode

This is a low power consumption mode. V1 and V2 are disabled. V3 can be permanently disabled or cyclically active.

Table 11. SBC Sleep Mode: V1 And V2 Are Passive, V3 Passive Or Cyclic.

| Entering Sleep Mode | Leaving Sleep Mode |
|--|---|
| If SW timing not configured 75ms after entering NormalRequest mode | CAN wake-up, going to NormalRequest |
| By SPI command | If a wake-up is detected with cyclic sense |
| For MC33389ADW only: If V1 is below V1 reset for more than 100ms | If a wake-up is detected with wake-up not connected to V3 (permanent sense) |
| | Forced wake-up (See Forced Wake up Section) |
| | SPI wake-up (See Wake up by SPI Section) |

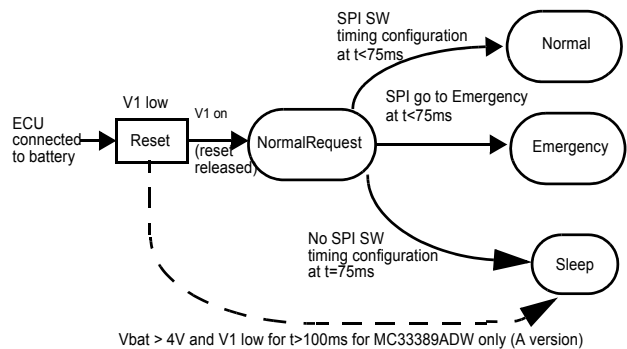
Emergency Mode

In case the microcontroller detects the ECU or the system is not under control any more, it may decide to switch the SBC to the Emergency mode. V1, V2, V3 will be passive and wake-up are not detected. The only way to leave this mode is to disconnect the ECU from the Battery voltage (BatFail detection).

Table 12. SBC Emergency Mode: V1 And V2 V3 Are Passive

| Entering Emergency Mode | Leaving Emergency Mode |
|-------------------------|--|
| By SPI command | SBC BatFail detection (Disconnection of the Battery voltage) |

Figure 13. Typical Behaviour At Power On



Note: In Normalrequest, if an SPI command is received before the SW timing configuration (SWCR register), it will not

DEVICE DESCRIPTION

SBC MODES

be taken into account by the SBC (except for the go to Emergency mode).

Correspondence between SBC and CAN Transceiver Modes

The table here below gives the different possible CAN transceiver modes versus SBC modes.

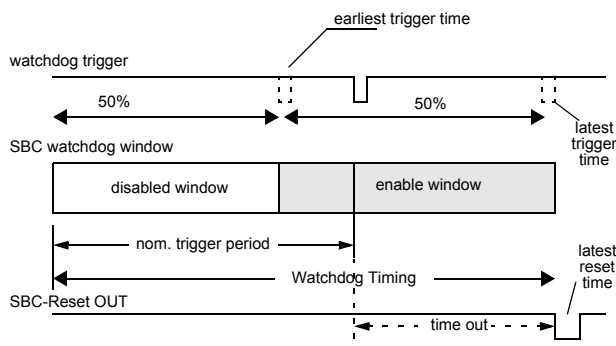
Table 14. CAN Modes Versus SBC Modes

| When SBC Is In The Following Mode | CAN Transceiver Can Be In |
|------------------------------------|------------------------------|
| Reset condition | Bus Standby mode |
| NormalRequest | Bus Standby mode |
| Normal | RXTX or RXOnly or BusStandby |
| Standby | Bus Standby |
| Sleep | Bus Standby |
| Emergency | Bus Standby |
| Normal & V2 off (over load) (note) | Bus standby |

Note: In case V2 is turned off either by SPI command (standby mode) or by the SBC itself due to V2 over load condition (V2 short to gnd or V2 over temperature) the CAN is automatically set into the Bus standby mode and does not return to TXRX mode automatically when V2 is back to 5V. The CAN must be re configured to TXRX or RXonly mode after a V2 turn off.

WatchdogGeneral

The software window watchdog function is used to monitors the microcontroller operation in Normal and in Standby modes. The window watchdog timing is derived from the SBC-clock. The desired watchdog timing must be first transmitted during the SBC configuration, in NormalRequest mode, via SPI to SWCR register. It can also be changed later on. Selectable watchdog timings are 5ms, 10ms, 20ms, 33ms, 50ms, 75ms, 100ms and 200ms. These timings correspond to the full disable window plus full enable window.

Figure 15. Window Watchdog Timing

As soon as the watchdog trigger is received in the enable window, the internal counter is reset and start a new disable window. The SBC triggers the watchdog word at CSB low to high transition. Any watchdog trigger outside the enable window leads to SBC reset.

In Normal and Standby Modes

In normal mode the SBC get the watchdog word from the microcontroller via SPI. In case of a trigger time failure (no trigger or trigger outside the enable window) the SBC-reset is switched to active.

NormalRequest, Sleep And Emergency Mode
Watchdog is not active in this modes.

DEVICE DESCRIPTION

WAKE-UP CAPABILITIES

Several wake up capabilities are available.

Forced Wake-up

The forced wake-up is enabled and disabled by SPI in V3R register. It is used in sleep mode to automatically wake-up the system by supplying V1 with proper reset. This correspond to jump into NormalRequest mode. If then, the SBC is not properly configured within 75ms, it switches back to sleep mode till the next wake-up. If both Cyclic sense and forced wake-up are enabled by the SPI in sleep mode, only Cyclic sense will be active.

The period of forced wake-up are 32ms, 64ms, 128ms, 256ms, 512ms, 1024ms, 2048ms, 8192ms, chosen by SPI in CYTCR register.

Wake-up Inputs (Local Wake-up) / Cyclic Sense

SBC provides 3 wake-up inputs to monitor external events such as closing/opening of switches. The wake-up feature is available in Normal, Standby and sleep modes. The switches can be directly connected to V_{bat} or to V3. The SBC must be properly configured by setting bit WI2V3 in register V3R. In this case, wake-ups are only detected when V3 is On. It can take advantage of V3 cyclic sense feature. If both Cyclic sense and forced wake-up are enabled by the SPI in sleep mode, only Cyclic sense will be active.

Options For Wake Input

Different conditions for wake-up can be chosen for wake-up input pins (via SPI in WUICR register).

No wake-up: No wake-up is detected, whatever occurs on wake-up inputs.

High state: if the input pin voltage is above the detection threshold during more than a $20\mu s$ filter time, a wake-up is detected. A flag is set in the WUISR register.

Low state: if the input pin voltage is below the detection threshold during more than a $20\mu s$ filter time, a wake-up is detected. A flag is set in the WUISR register.

Change of state: each change of the wake-up input pin is considered as a wake-up, if it lasts more than a $20\mu s$ filter time. The first reference state (no wake-up) is the wake-up input state when the SBC is programmed to this option. A flag is set in the WUISR register.

Multiple sampling events: when wake-up inputs are used with V3 in cyclic sense in sleep mode.

For positive edge sensitivity, 2 samples Low followed by 2 samples High are necessary to validate the wake-up condition.

For negative edge sensitivity, 2 samples High followed by 2 samples Low are necessary to validate the wake-up condition.

For both edge sensitivity, 2 samples at a given state followed by 2 samples in the opposite state are necessary to validate the wake-up condition.

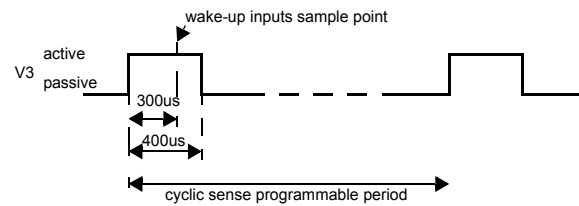
Wake-up Inputs With Cyclic Sense

Connecting the external switches to V3 allows power saving since V3 can be programmed to be active, passive or cyclic (cyclic sense). This gives a great flexibility to reduce total power consumption while allowing full wake-up capabilities. Cyclic sense is available only in sleep mode.

The period of the Cyclic sense can be chosen out of 8 different timings: 32ms, 64ms, 128ms, 256ms, 512ms, 1024ms, 2048ms, 8192ms programmable via SPI in CYTCR

register. Once activated, V3 remains 'on' during $400\mu s$. The wake-up inputs states are sampled at $300\mu s$.

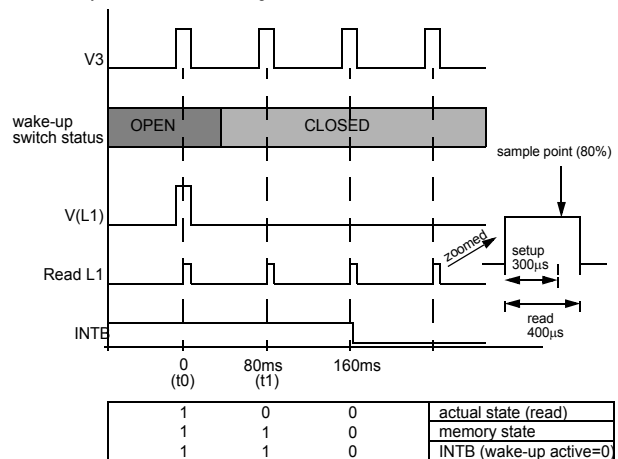
Figure 16. V3 Timing



Note: In sleep mode, the Cyclic Sense feature 'EXCLUSIVE OR' the forced Wake-up is chosen (not both).

Figure 17. Cyclic Sense Timing

Cyclic sense connected to wake-up inputs. Example with wake-up input L1 sensitivity to Low state and timing=80ms



Wake Up Inputs With Permanent Sense

Wake up detection can also be done on a permanent way in Normal and Standby mode. If the contacts are connected to V3, wake ups are only detected if V3 is on.

Wake ups are also detected on a permanent way in sleep mode if the contacts are directly connected to V_{bat} (if they are connected to V3, only cyclic sense is available in sleep mode).

Local Wake-up Consequences

In normal or standby modes, the real time state of each wake-up input pin is stored in the readable register WUIRTI. Wake-ups are detected according to the option chosen. A flag is set in the WUISR register. A maskable interrupt is sent via INTB output.

In sleep mode, a local wake-up leads to a jump to NormalRequest mode (via proper reset of the microcontroller). A flag is set in the WUISR register.

Table 18. SBC Mode Versus Local Wake-up Behaviour

| SBC Modes | Local Wake-up Behaviour |
|---------------|-------------------------|
| NormalRequest | No detection |

DEVICE DESCRIPTION

WAKE-UP CAPABILITIES

| SBC Modes | Local Wake-up Behaviour |
|--------------------|---|
| Normal and Standby | Detection active according to the option. The event is stored in WUISR register. The SBC may activate INTB output. Real time state of each wake-up input pin available in WUIRTI register |
| Sleep | Detection active according to the option. The event is stored in WUISR register. The SBC switches to NormalRequest mode |
| Emergency | No detection |

Wake-up By SPI

In some applications, the microcontroller might be supplied by an external VDD and remains powered in SBC Sleep mode. In this case, a feature is provided which makes possible to wake-up the SBC by SPI activity.

After V1 is totally switched off in sleep mode ($V1 < 1.5V$), if a falling edge occurs on CSB (crossing 2.5V threshold), a wake-up by SPI is detected, the SBC switches to NormalRequest mode. A flag is set in ISR2.

Interrupt Output

The INTB output may be activated in the following cases:

- V_{bat} overvoltage (BatHigh)
- V_{bat} undervoltage (BatFail)
- High temperature on V1 or V2
- Pre-warning temperature on V1 or V2
- CAN bus failure
- SPI error
- Local wake-up (can be used for low battery detection)
- Bus wake-up

All these interrupts are maskable (See Register Description Section).

RSTB Input/Output

The RSTB (reset) pin is an input/output pin. The typical reset duration from SBC to microcontroller is 1ms. If longer times are required, an external capacitor can be used. SBC provides two RSTB output pull-up currents.

A typical 30 μ A pull up when Vreset is below 2.5V and a 300 μ A pull up when reset voltage is higher than 2.5V.

RSTB is also an input for the SBC. It means the MC33389 is forced to NormalRequest mode after RSTB is released by the microcontroller

GND SHIFT DETECTION

General

When normally working in two-wire operating mode, the CAN transmission can afford some ground shift between different nodes without trouble. Nevertheless, in case of bus failure, the transceiver switches to single-wire operation, therefore working with less noise margin. The affordable ground shift is decreased in this case.

The SBC is provided with a ground shift detection for diagnosis purpose. Four ground shift levels are selectable and the detection is stored in the GSLR register which is accessible via the SPI.

Detection Principle

The gnd shift to detect is selected via the SPI out of 4 different values (-0.7V, -1.2V, -1.7V, -2.2V). At each TX falling edge (end of recessive state) CANH voltage is sensed. If it is detected to be below the selected gnd shift threshold, the bit SHIFT is set at 1 in GSLR register. No filter is implemented. Required filtering for reliable detection should be done by software (e.g. several trials).

DEVICE DIFFERENT VERSIONS

The MC33389 is proposed in several package versions, and also offers slight differences in term of functionalities.

The device version is identified in the device part number by the first letter after the 389 number.

The package identification is done by the last two letters of the part number (DW for SO28 wide body, DH for power SO20).

Differences between A, C and D versions:

Behavior for V1 low:

A version:

If V1 is below reset threshold, device enters reset mode, and if V1 stays below reset threshold for more than 100ms, then the SBC automatically enters sleep mode. This could be the case if V1 is shorted or permanently over loaded, and going to sleep mode would then avoid system over current consumption.

This concerns the device reference: MC33389ADW and MC33389ADH.

C and D versions:

If V1 is below reset threshold, the SBC enters and stays in reset mode (reset low) permanently.

This concerns the device reference: MC33389CDW and MC33389CDH and MC33389DDW

Reset threshold specification:

A and C versions:

The reset threshold is defined per table "electrical parameter, V1 pin 5V.

This concerns device MC33389ADW, ADH, CDW and CDH

D version : The reset threshold for the D version is slightly higher than the A and C versions. Refer to device electrical parameter table, V1 pin 5V

This concerns device reference MC33389DDW.

DEVICE DESCRIPTION

Table 19. SBC Operation Mode

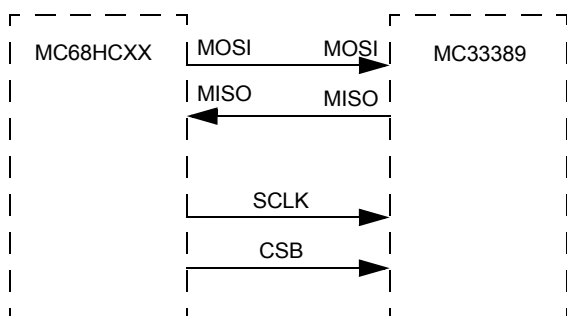
| mode | V1 & V2 regulators, V3 switch | Wake up capabilities (if enabled) | Reset pin | INT | Software Watchdog | CAN cell |
|----------------|--|--|---|---|-------------------|--------------------------------|
| Reset state | V1: ON (unless failure condition V2: OFF V3: OFF | | Low (duration 1ms) | | | TermVbat |
| Normal Request | V1: ON (75ms time out) V2: OFF V3: OFF | | High. (Active low -go to reset state- if V1 under voltage occurs) | | | Term Vbat |
| Normal | V1: ON V2: ON V3: ON or OFF | | High. (Active low -go to reset state- if W/D or V1 under voltage occurs) | If enabled, signal failure condition or L0/L1/L2 inputs state change. | Running | Tx/Rx, or Rx Only, or TermVbat |
| Standby | V1: ON V2: OFF V3: ON or OFF | | same as Normal Mode | same as Normal Mode | Running | TermVbat |
| Sleep | V1: OFF V2: OFF V3 OFF or cyclic | - CAN - SPI - L0,L1,L2 - Cyclic sense - Forced Wake up | Low | Not active | Not Running | TermVbat + Wake up capability |
| Emergency | V1: OFF V2: OFF V3 OFF | none | Low | Not active | Not Running | TermVbat |

SPI FUNCTIONAL DESCRIPTION

General Description

The SPI system is flexible enough to communicate directly with numerous standard peripherals and MCUs available from Motorola and other semiconductor manufacturers. SPI reduces the number of pins necessary for input/output on the MC33389. The SPI system of communication consists of the MCU transmitting, and in return, receiving one databit of information per clock cycle. Databits of information are simultaneously transmitted by one pin, Microcontroller Out Serial In (MOSI), and received by another pin, Microcontroller In Serial Out (MISO), of the MCU. Figure 21 below shows the basic SPI configuration between an MCU and one MC33389. The SPI serial operation is guaranteed to 2.0 MHz.

Figure 21. SPI Interface With Microcontroller



Control and Status Reporting of the MC33389

The MCU is responsible for the control data transfer to the MC33389, while the MC33389 reports its status to the MCU. Summarized below are the major data for control and status reporting.

- SPI initialization during start up
- MC33389 control during operation
- Watchdog triggering
- Reading status registers of the MC33389

Control Data

The control data are transferred from the MCU to the MC33389. A control word includes an address of a certain control register and the appropriate data. Basically the following data will be transferred (See the SPI Register Description section on page 21).

- MC33389 mode control
- Supply control
- Forced wake-up timing
- Cyclic sense control
- Watchdog control
- Transceiver control

Status Data

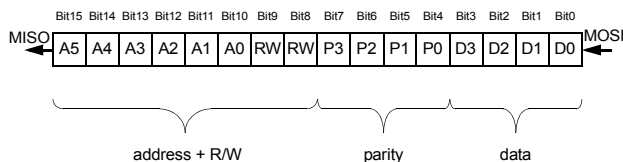
The status data are transmitted from the MC33389 to the MCU. After receiving a valid register address from the MCU, the MC33389 returns the appropriate status. Some of the major status data are listed below:

- Current operation mode status
- Wake-up sources
- Reset status
- Error status
- Overtemperature status
- Transceiver status

Data Transfer

The data to and from the MC33389 are transferred in form of two bytes. The structure of the transferred information is the same for control the MC33389 and status reporting. The address field A5 to A0 (Bit15 to Bit10) contains the address of a control or status register in the MC33389. RW (Bit9 and Bit8) contains the read/write flag for the data field. The parity field is located at P3 to P0 (Bit7 to Bit4). The data field D3 to D0 (Bit3 to Bit0) is attached to the 2 byte data word, see figure below.

Figure 22.



The SBC is accessible via the SPI interface in NormalRequest mode, Normal mode and Standby mode. In all other modes (Sleep mode, Emergency mode), the voltage supply for the microcontroller in permanently switched off and the SBC input logic for MISO, MOSI, CSB and SCLK isn't working (except SPI wake-up function in Sleep mode).

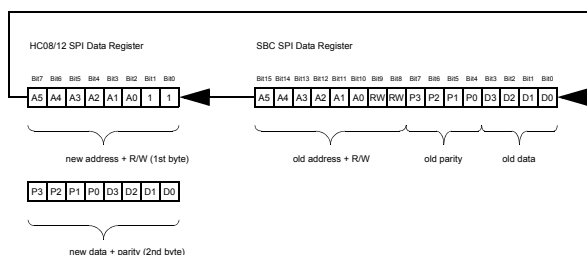
Writing Data

To write data in a SPI register, two one-byte transmissions have to be performed. The first byte contains the address of the register (MSB first) and the read/write bits which have to be set to 1. The second byte contains the new data addressed by the previous byte (MSB first) and the parity information. The calculation of the parity field P3-P0 has to follow the equations below:

$$\begin{aligned}
 P3 &= D3 \oplus D0 && \text{(EX-OR)} \\
 P2 &= D3 \oplus D2 \\
 P1 &= D2 \oplus D1 \\
 P0 &= D1 \oplus D0
 \end{aligned}$$

Note, that during the transmission of the two bytes the CSB pin remains 0. See figure23 hereafter.

Figure 23.



The SBC sends back the old address, R/W, parity, and data information from a previous transmission. This data contains no useful information (e.g. status). It shouldn't be used.

In case of a wrong address field or parity mismatch, an interrupt will be issued and the SBC retains the old state.

Reading Data

To read data from a dedicated register two one-byte transmissions have to be performed. The first byte contains the address of the register (MSB first) and the read/write flag setting to 0. The second byte needn't contain valid data,

SPI FUNCTIONAL DESCRIPTION

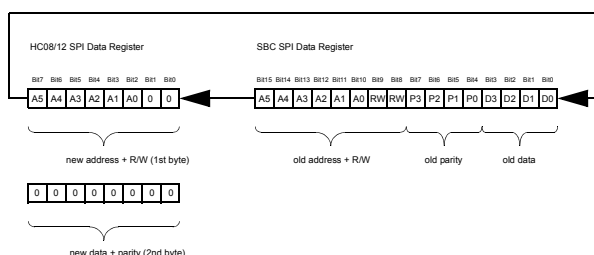
nevertheless the parity calculation has to be performed to avoid an interrupt caused by a parity mismatch.

During a read operation the SBC sends back the old address and R/W bits and the new data addressed by the first transmitted byte starting with P3 after the last valid read/write bit has been received.

Note, that during the transmission of the two bytes the CSB pin remains 0.

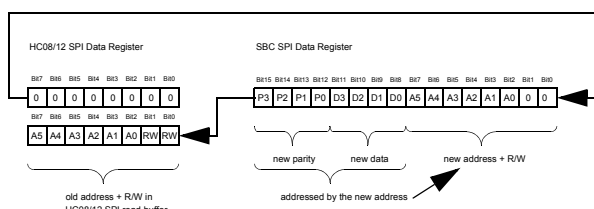
Figure below shows the content of the HC08/12 SPI Data Register and the SBC SPI Data Register before the transmission. The new address and R/W bits are already in the SPI Data Register while the new data and parity bits are still in an appropriate microcontroller register or memory. This 2nd byte has to be loaded into the HC08/12 SPI Data Register after the first byte has been transmitted to the SBC.

Figure 24.



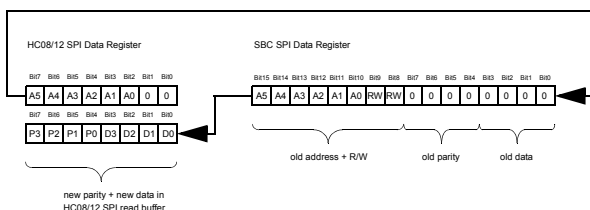
After transmission of the 1st byte the HC08/12 SPI read buffer contains the old address and R/W bits received from the SBC. An appropriate operation in the microcontroller loads the new data and parity into the HC08/12 SPI Data Register (2nd byte). In the SBC the internal logic loads P3-P0 and D3-D0 to the location of Bit15 to Bit8 in the SBC SPI Data Register and will shift this data within the remaining eight clock cycles (Figure below 25).

Figure 25.



After sixteen clock cycles the microcontrollers read buffer contains the new parity and data and is now ready for the next transmission (See figure hereafter 26)

Figure 26. .



Safety Concept

Due the fact the SPI interface is an on-board interface without any data fault detection capabilities, the SPI interface of the MC33389 provides built-in fail save functions.

Address coding, based on increasing the Hamming distance, parity check and generation for data.

For the address and the read/write bits only codes with a Hamming distance < 2 will be used. So, any single bit failure caused by disturbances will be recognized and handled. When one bit toggles in the address field during the transmission, no misbehaviour occurs.

Additionally, validation registers are implemented to validate safety critical settings in the MC33389, e.g. the mode control register MCR and its validation register MCVR. To change the appropriate settings, both registers must have the same content to switch to another mode.

To increase data integrity a parity check is used. A parity module in the MC33389 ascertains the parity of the data field and compares the result with the received parity. When the parity check is successfully passed, data will be written into the addressed registers. The parity bits P3 to P0 results from the logic equations below:

$$P3 = D3 \oplus D0 \quad (\text{EX-OR})$$

$$P2 = D3 \oplus D2$$

$$P1 = D2 \oplus D1$$

$$P0 = D1 \oplus D0$$

In case of error detection, the incoming data is not taken in the SBC and an error flag is set in an SPI register. CSB Pin

The system MCU selects the MC33389 to be communicated with, through the use of the CSB pin. Whenever the pin is in logic low state, data can be transferred from the MCU to the MC33389 and vice versa. Clocked-in data from the MCU is transferred from the MC33389 shift register and latched into the addressed registers on the rising edge of the CSB signal if the read/write bit is set and the parity check was successful.

The CSB pin controls the output driver of the serial output pin. Whenever the CSB pin goes to a logic low state, the MISO pin output driver is enabled allowing information to be transferred from the MC33389 to the MCU. To avoid any spurious data, it is essential that the high-to-low transition of the CSB signal occur only when SCLK is in a logic low state.

SCLK Pin

The system clock pin (SCLK) clocks the internal shift registers of the MC33389. The serial input pin (MOSI) accepts data into the input shift register on the falling edge of the SCLK signal while the serial output pin (MISO) shifts data information out of the shift register on the rising edge of the SCLK signal. False clocking of the shift register must be avoided to guarantee validity of data. It is essential that the SCLK pin be in a logic low state whenever chip select bar pin (CSB) makes any transition. For this reason, it is recommended though not necessary, that the SCLK pin be kept in a low logic state as long as the device is not accessed (CSB in logic high state). When CSB is in a logic high state, any signal at the SCLK and MOSI pin is ignored and MISO is tristated (high impedance).

MOSI Pin

This pin is for the input of serial instruction data. MOSI information is read in on the falling edge of SCLK. To program the MC33389 by setting appropriate programming registers, an sixteen bit serial stream of data is required to be entered

SPI REGISTER DESCRIPTION

the MOSI pin starting with Bit15, followed by Bit14, Bit13, etc., to Bit0. For each fall of the SCLK signal, with CSB held in a logic low state, a databit is loaded into the shift register per the databit MOSI state. The shift register is full after sixteen bits of information have been entered.

MISO Pin

The serial output (MISO) pin is the tri-stateable output from the shift register. The MISO pin remains in a high impedance state until the CSB pin goes to a logic low state. The MISO pin changes state on the rising edge of SCLK and reads out on the falling edge of SCLK. The MOSI/MISO shifting of data follows a first-in-first-out protocol with both input and output words transferring the MSB first.

Module Address Map, the module address map is shown in table below.

Table 27. Module Address Map

| Address | Register | Register Name |
|---------|--|---------------|
| \$000 | Mode Control Register | MCR |
| \$003 | Mode Control Validation Register | MCVR |
| \$005 | V3 control register | V3R |
| \$006 | Cyclic timing control register | CYTCR |
| \$009 | Software watchdog control register | SWCR |
| \$00A | Ground shift level register | GSLR |
| \$00C | Wake-up input control register | WUICR |
| \$00F | Wake-up input status register | WUISR |
| \$011 | Wake up input real time information | WUIRTI |
| \$012 | Overtemperature status register | OTSR |
| \$014 | Transceiver error status register for CANH | TESRH |
| \$017 | Transceiver error status register for CANL | TESRL |
| \$018 | Reset source register | RSR |
| \$01B | Voltage supply status register | VSSR |
| \$01D | Interrupt mask control register 1 | IMR1 |
| \$01E | Interrupt mask control register 2 | IMR2 |
| \$021 | Interrupt source register 1 | ISR1 |
| \$022 | Interrupt source register 2 | ISR2 |
| \$024 | Transceiver control register | TCR |

SPI REGISTERS DESCRIPTION

Table 28. MCR — Mode Control Register

MCR and MCVR registers are used to control the mode of the SBC. To change the operating mode of the SBC, both registers must have the same content. The order of writing the registers has to be taken into account. To set the SBC mode properly, MCR has to be written first then followed by MCVR write. A write operation sets the MCR and MCVR registers, a read operation perform a read out of the current status (MSR - mode status register).

The Emergency mode is a regular mode.

A reset of both MCR and MCVR registers occurs when RSTB = low and the SBC is set to NormalRequest mode.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| MCR \$000 | R | | | | | | MSR2 | MSR1 | MSR0 |
| | W | | | | | | MCR2 | MCR1 | MCR0 |
| RESET | | | | | | | 0 | 0 | 0 |

Table 29. MCVR — Mode Control Validating Register

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| MCVR \$003 | R | | | | | | MSVR2 | MSVR1 | MSVR0 |
| | W | | | | | | MCR2 | MCR1 | MCR0 |
| RESET | | | | | | | 0 | 0 | 0 |

Table 30.

| MC(V)R2 | MC(V)R1 | MC(V)R0 | | MSR2 | MSR1 | MSR0 |
|-----------------------------------|---------|---------|---------------|------|------|------|
| Automatically entered after reset | | | NormalRequest | 0 | 0 | 0 |
| 0 | 0 | 1 | Normal | 0 | 0 | 1 |
| 0 | 1 | 0 | Standby | 0 | 1 | 0 |
| 1 | 0 | 0 | Sleep | 1 | 0 | 0 |
| 1 | 1 | 1 | Emergency | 1 | 1 | 1 |

Table 31. V3R — V3R Control Register

This register is used to configure the state of V3 high side switch in normal and standby modes, and the V3 operation and the Forced wake up or the cyclic sense option for the sleep mode operation.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| V3R \$005 | R | | | | | WI2V3 | FWU | CYS | V3R0 |
| | W | | | | | | | | |
| RESET | | | | | | 1 | 0 | 0 | 0 |

Table 32.

| WI2V3 | FWU | CYS | V3R0 | | Comments |
|-------|-----|-----|------|-----------------|---|
| X | 0 | 0 | 0 | V3 off | Only In Normal And Standby Mode Available |
| X | 0 | 0 | 1 | V3 on | |
| X | X | 1 | X | Cyclic Sense On | |

SPI REGISTERS DESCRIPTION

| WI2V3 | FWU | CYS | V3R0 | | Comments |
|-------|-----|-----|------|-----------------------------|------------------------------|
| X | 1 | 0 | X | Forced Wake-up On | Only In Sleep Mode Available |
| 1 | X | X | X | wake-up inputs linked to V3 | |

Note: In low power modes cyclic sense has priority. A reset of the register occurs when RSTB = low.

Table 33. CYTCR — Cyclic Timing Control Register

This register is used to select the cyclic sense or force wake up timing.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|----------------|---|-------|-------|-------|-------|-------|--------|--------|--------|
| CYTCR \$006 | R | | | | | | CYTCR2 | CYTCR1 | CYTCR0 |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

Table 34.

| CYTCR2 | CYTCR1 | CYTCR0 | Comments | t(ms) typical |
|--------|--------|--------|------------------------|---------------|
| 0 | 0 | 0 | Timer on, t1 (default) | 32 |
| 0 | 0 | 1 | Timer on, t2 | 64 |
| 0 | 1 | 0 | Timer on, t3 | 128 |
| 0 | 1 | 1 | Timer on, t4 | 256 |
| 1 | 0 | 0 | Timer on, t5 | 512 |
| 1 | 0 | 1 | Timer on, t6 | 1024 |
| 1 | 1 | 0 | Timer on, t7 | 2048 |
| 1 | 1 | 1 | Timer on, t8 | 8192 |

A reset of the register occurs when RSTB = low

Table 35. SWCR — Software Watchdog Control Register

This register is used to select the window watchdog time period. Open window of the selected period is only the second half of the selected period.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| SWCR \$009 | R | | | | | | SWCR2 | SWCR1 | SWCR0 |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

Table 36.

| SWCR2 | SWCR1 | SWCR0 | Comments | t(ms) typical |
|-------|-------|-------|------------------------|---------------|
| 0 | 0 | 0 | Timer on, t1 (default) | 5 |

SPI REGISTERS DESCRIPTION

| SWCR2 | SWCR1 | SWCR0 | Comments | t(ms) typical |
|-------|-------|-------|--------------|---------------|
| 0 | 0 | 1 | Timer on, t2 | 10 |
| 0 | 1 | 0 | Timer on, t3 | 20 |
| 0 | 1 | 1 | Timer on, t4 | 33 |
| 1 | 0 | 0 | Timer on, t5 | 50 |
| 1 | 0 | 1 | Timer on, t6 | 75 |
| 1 | 1 | 0 | Timer on, t7 | 100 |
| 1 | 1 | 1 | Timer on, t8 | 200 |

The SW watchdog is only running in Normal and Standby mode. A reset of this register occurs when RSTB = low

Table 37. GSLR — Ground Shift Level Register

This register is used to monitor the ground shift of the vehicle network.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| GSLR \$00A | R | | | | | TXDOM | SHIFT | GSLR1 | GSLR0 |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

Table 38.

| GSLR1 | GSLR0 | Typ GND Shift Level |
|-------|-------|---------------------|
| 0 | 0 | 0.7V |
| 0 | 1 | -1.2V |
| 1 | 0 | -1.7V |
| 1 | 1 | -2.2V |

SHIFT

1=ground shift above the threshold selected by GSLR1 and GSLR2. 0=no ground shift

The SHIFT information is latched until a read operation of the GSLR register occurs. The GSLR register is set to 0 after power on reset. A reset of GSLR1 and GSLR0 occurs when RSTB = low.

TXDOM

0 = no failure on TX

1 = TX permanent dominant

Table 39. WUICR — Wake-up Input Control Register/SPI And Bus Wake-up Status

This register is used to configure the wake up level for the L0, L1 and L2 inputs. in read operation it reports the CAN wake up and SPI (csb) wake up events

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|----------------|---|-------|-------|-------|-------|-------|-------|--------|--------|
| WUICR \$00C | R | | | | | SPIWU | BUSWU | WUICR1 | WUICR0 |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

SPI REGISTERS DESCRIPTION

Table 40.

| WUICR1 | WUICR0 | Description | Comments |
|--------|--------|---------------------------------|----------|
| 0 | 0 | Wake-up inputs disabled | |
| 0 | 1 | Positive edge sensitive | |
| 1 | 0 | Negative edge sensitive | |
| 1 | 1 | Positive and negative sensitive | |

Table 41.

| SPIWU | BUSWU | Description | Comments |
|-------|-------|--------------------------|----------|
| 0 | 0 | No wake-up events | |
| X | 1 | Wake-up event on CAN bus | |
| 1 | X | Wake-up event on SPI bus | |

The information in SPIWU and BUSWU is latched. Bits SPIWU and BUSWU will be reseted by a read operation of the WUICR register and are set to 0 after a power on reset. A reset of WUICR1 and WUICR0 occurs when RSTB = low.

Table 42. WUISR — Wake-up Input Status Register

This register is used to read back the wake input (L0, L1 or L2) which has cause the SBC to wake up.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|----------------|---|-------|-------|-------|-------|-------|--------|--------|--------|
| WUISR \$00F | R | | | | | | WUISR2 | WUISR1 | WUISR0 |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

Table 43.

| WUISR2 | WUISR1 | WUISR0 | Description | Comments |
|--------|--------|--------|----------------------------|----------|
| 0 | 0 | 0 | No Event on Wake-up Inputs | |
| X | X | 1 | Event on L0 | |
| X | 1 | X | Event on L1 | |
| 1 | X | X | Event on L2 | |

In case of a wake-up event, the appropriate bit is set to 1. The bits will be reseted by a read operation of the register. After power on reset all bits are set to 0.

Table 44. WUIRTI — Wake-up Input Real-time Information

This register reports the real time information on the state (high or low) of the L0, L1 and L2 inputs.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|-----------------|---|-------|-------|-------|-------|-------|---------|---------|---------|
| WUIRTI \$011 | R | | | | | | WUIRTI2 | WUIRTI1 | WUIRTI0 |
| | W | | | | | | | | |
| RESET | | | | | | | | | |

The bits WUIRTI2-0 contain the real time logic value coming from the wake-up inputs (0 mean input below threshold, 1 mean input above threshold. Typical threshold is 3.5V).

Table 45. OTSR — Overtemperature Status Register

SPI REGISTERS DESCRIPTION

This register is used to read back the overtemperature status for the V1 and V2 regulators. In write mode, it is used to turn V2 on after a V2 over temperature shutdown has occurred.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| OTSR \$012 | R | | | | | OPWV2 | OPWV1 | OTV2 | OTV1 |
| | W | | | | | | | OTV2C | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

OTV1: 1=V1 overtemperature shutdown, 0=V1 no overtemperature

OTV2: 1=V2 overtemperature shutdown, 0=V2 no overtemperature

OPWV1: 1=V1 overtemperature pre-warning, 0=V1 normal temperature

OPWV2: 1=V2 overtemperature pre-warning, 0=V2 normal temperature

In case of V1 or V2 overtemperature the appropriate voltage regulators are switched off automatically and the overtemperature flags are set (latched). The flags can be reset by a read operation of the register OTSR.

Once V2 has been switched off because of overtemp (OTV2=1) it can only be switched on again by forcing OTV2C=0 by a write operation.

The V1 and V2 pre-warning flags are set as long as the first overtemperature exists. The flags disappear, when the temperature is below the threshold. An overtemperature of the V2 power supply will also switch off V3. After a power on reset all bits of the register are set to 0.

Table 46. TESRH — Transceiver Error Status Register For CANH

Register used to report the CAN H failure status

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|----------------|---|-------|-------|-------|-------|--------|--------|--------|--------|
| TESRH \$014 | R | | | | | TESRH3 | TESRH2 | TESRH1 | TESRH0 |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

Table 47.

| TESRH3 | TESRH2 | TESRH1 | TESRH0 | |
|--------|--------|--------|--------|-----------------------------------|
| 0 | 0 | 0 | 0 | No failure on CANH |
| 0 | X | 0 | 1 | CANH wire interruption |
| X | X | 1 | X | CANH short circuited to V_{bat} |
| 0 | 1 | 0 | X | CANH short circuited to ground |
| 1 | X | 0 | X | CANH short circuited to V_{CC} |

In case of CANH line failures, the appropriate bit(s) are set according to table 46. This information is latched. The register can be reset by a read operation. After power on reset, all bits are set to 0.

Table 48. TESRL — Transceiver Error Status Register For CANL And Tx

Register used to report the CANL and Tx permanent dominant failure status

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|----------------|---|-------|-------|-------|-------|--------|--------|--------|--------|
| TESRL \$017 | R | | | | | TESRL3 | TESRL2 | TESRL1 | TESRL0 |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

SPI REGISTERS DESCRIPTION

Table 49.

| TESRL3 | TESRL2 | TESRL1 | TESRL0 | |
|--------|--------|--------|--------|--|
| 0 | 0 | 0 | 0 | No failure |
| 0 | X | 0 | 1 | CANL wire interruption |
| 0 | 1 | 0 | X | CANL short circuited to ground/ CANH mutually shorted to CANL |
| X | X | 1 | X | CANL short circuited to V_{bat} |
| 1 | X | 0 | X | CANL short circuited to Vdd |

In case of CANL line failures, the appropriate bit(s) are set according to table 48. This information is latched and the register can be reset by a read operation. After power on reset, all bits are set to 0.

Table 50. RSR — Reset Source Register

This register reports the source of a reset that has occurred

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| RSR \$018 | R | | | | | | RSR2 | RSR1 | RSR0 |
| | W | | | | | | | | |
| RESET | | | | | | | 1 | 0 | 1 |

RSR0: 1 => VDD1 undervoltage occurred (RSR2=1 in this case), 0=> no undervoltage on VDD1 occurred

RSR1: 1 => SW watchdog reset occurred (RSR2=1 in this case), 0=>no SW watchdog reset occurred

RSR2: 1 =>external reset occurred (RSR0=RSR1=0 in this case), 0=>no external reset occurred

Events related to the bits in register RSR are latched. All bits can be reset by a read operation of the register. After a power on reset, RSR2 and RSR0 are set to 1. Therefore the first read out of the register after power on delivers RSR[2:0] = [101].

Table 51. VSSR — Voltage Supply Status Register

Register used to monitor the status of the V2, V3 and Vbat voltage level.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| VSSR \$01B | R | | | | | V3SR | V2SR | VBSR1 | VBSR0 |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | | |
| POR | | | | | | 0 | 0 | 0 | 1 |

Table 52.

| VBSR1 | VBSR0 | |
|-------|-------|-------------------------|
| 0 | 0 | No failure on V_{bat} |
| X | 1 | Undervoltage (BatFail) |
| 1 | X | Overvoltage (BatHigh) |

V2SR: 1=V2 on, 0=V2 off

V3SR: 1=V3 overtemperature, 0=V3 no overtemperature

VBSR1 is a real time information and cannot be reseted. Bits V3SR, V2SR and VBSR0 are latched and can be reseted by a read operation of the register.

Table 53. IMR1 — Interrupt Mask Control Regis

SPI REGISTERS DESCRIPTION

The next two registers (IMR1 and IMR2) are used to mask the interrupt function.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| IMR1 \$01D | R | | | | | HV | HTPW | MTPW | BATU |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

Table 54. IMR2 — Interrupt Mask Control Register 2

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|---------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| IMR2 \$01E | R | | | | | | BUSF | SPIE | WU |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

To enable the appropriate interrupt, the mask bit has to be set to 1. For disabling the interrupt the bit must be cleared to 0. After a power on reset or RSTB = low, the bits are cleared to 0. All interrupts are disabled. Explanation for the abbreviations:

HV : V_{bat} high voltage

HT : High temperature on V1 or V2

MTPW : Medium temperature pre-warning on V1 or V2

BATU: Battery undervoltage (BatFail)

BUSF : CAN bus failure

SPIE : SPI error

WU : Wake-up

Table 55. ISR1 — Interrupt Source Register

The next two registers (ISR1 and ISR2) are used to read the interrupt source.

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| ISR \$021 | R | | | | | HV | HTPW | MTPW | BATU |
| | W | | | | | | | | |
| RESET | | | | | | 0 | 0 | 0 | 0 |

Table 56. ISR2 — Interrupt Source Register 2

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| ISR \$022 | R | | | | | | BUSF | SPIE | WU |
| | W | | | | | | | | |
| RESET | | | | | | | 0 | 0 | 0 |

All bits in registers ISR1 and ISR2 are copies of the appropriate bits in different SPI registers. For a faster read out, these bits are merged in ISR1 and ISR2. A reset cannot be done for registers ISR1 and ISR2.

Table 57. TCR—Transceiver Control/Status Register

SPI REGISTERS DESCRIPTION

This register is used to control the state of the CAN transceiver (CAN transceiver state is also dependant upon the SBC mode). When it is read, this register reports the CAN transceiver state and a CAN overtemperature condition

| | | BIT 7 | BIT 6 | BIT 5 | BIT 4 | BIT 3 | BIT 2 | BIT 1 | BIT 0 |
|--------------|---|-------|-------|-------|-------|-------|-------|-------|-------|
| TCR \$024 | R | | | | | TOT | TSR2 | TSR1 | TSR0 |
| | W | | | | | | TCR2 | TCR1 | TCR0 |
| RESET | | | | | | 0 | 0 | 0 | 0 |

Table 58.

| TCR2 | TCR1 | TCR0 | | TSR2 | TSR1 | TSR0 |
|------|------|------|-------------------------------|------|------|------|
| 0 | 0 | 0 | Standard/TermV _{bat} | 0 | 0 | 0 |
| | 1 | 0 | Standard/RXOnly | 0 | 1 | 0 |
| | 1 | 1 | Standard/RXTX | 0 | 1 | 1 |

TOT

1 => Transceiver overtemperature

0 => normal temperature

The MODE bit selects between the standard and extended physical layer mode.

Any conditions forcing the transceiver to TermV_{bat} lead to reset of TCR0 TCR1 bits.

After power on reset all bits of the register are set to 0. The information TOT is latched.

To reset TOT a read operation of TCR has to be performed. In case of RSTB = low the register content remains unchanged.

APPLICATION

Sleep Mode Activation

Once in sleep mode, the SBC turns off V1 and V2 regulator. Thus the micro controller can not run any mode.

In order to have it run again, the SBC should enable and turn on V1, and this is achieved by an SBC wake up event.

Several options are available to wake up the SBC and the application and have the micro controller in run mode.

Some wake up are selectable, some are always active in sleep mode.

- Wake up from CAN interface and wake up from SPI (CSB) are always active.

- Wake up from L0/L1/L2 inputs, with and without cyclic sense and the FWU (Forced Wake Up) are selectable. The selection must be done while the SBC is in Normal or Standby mode, and prior to enter sleep mode.

General Condition To Enter Sleep Mode

In order to make sure the SBC enters the sleep mode, and in addition to the write into MCR and MCVR register, all previous wake up conditions must have been cleared. To clear a wake up condition requires that the appropriate register is read.

After an SBC power up from "zero" (battery power up or cold start), the following registers must be read:

- WUICR: possible wake up event report from CAN bus
- RSR: report a V1 undervoltage
- VSSR: reports a Vbat fail flag

Once these read operation are done, the wake up conditions or flag are reset.

The VSSR register bit VBRS0 can be used to determine if the SBC has experienced a loss of battery voltage.

After an SBC wake up from "sleep mode" the following registers indicate the wake up source and must be cleared in order to allow the SBC to enter sleep mode again:

- WUICR: wake up event report for CAN or SPI buses.
- WUISR: Wake up event report for the L0/L1/L2 inputs.
- RSR: report a V1 undervoltage
- VSSR: reports a Vbat fail flag
- etc

The paragraphs below describe the write operation to be done for the several sleep mode and wake up control options.

In addition to FWU, cyclic sense and direct wake up, the CAN and SPI wake will always be activated.

Sleep Mode With CAN And SPI Wake Up

To enter sleep mode and activate only the CAN or SPI wake up, no dedicated wake up condition must be done. In sleep mode the SBC has CAN and SPI wake up always active. To enter sleep mode in this case, while the SBC is in normal or standby mode:

- Write to V3R register: data 0000 (this clears the bit WI2V3 which is set to 1 after reset).

- Write to MCR register: data SLEEP (100)
- Write to MCVR register: data SLEEP (100)

The SBC then enters sleep mode.

Sleep Mode Enter With Forced Wake Up

To enter sleep mode and activate the forced wake up the following register must be written:

- Write to V3R register, data 0100, this sets the FWU bit to 1.
- Write to CYTCR register the desired wake up time. (This sets the time the SBC will stay in sleep mode).
- Write to MCR register: data SLEEP (100)
- Write to MCVR register: data SLEEP (100)

The SBC then enters sleep mode. It will wake up after the time period selected in the CYTCR register.

Sleep Mode Enter With Cyclic Sense

To enter sleep mode and activate the cyclic sense wake up the following register must be written:

- Write to V3R register, data 1010, this sets the VI2V3 and CYS bits to 1.

- Write to CYTCR register the desired cyclic sense period. (This sets the time the SBC will wait in sleep mode to turn on V3 and sense the Lx inputs).

- Write to WUICR bits 0 and 1 to select the edge sensitivity for the Lx inputs.

- Write to MCR register: data SLEEP (100)

- Write to MCVR register: data SLEEP (100)

The SBC then enters sleep mode. It will periodically turn on V3 and while V3 is on, sample the level of the Lx inputs.

If any of the 3 Lx inputs is in the correct state for two consecutive samples, SBC will wake up. If not, it will stay in sleep mode. (refer to device description for detail).

Sleep Mode Enter With Direct Lx Input Wake Up

To enter sleep mode and activate the direct wake up from the Lx inputs, the following register must be written:

- Write to V3R register, data 0000, this clears VI2V3 bit.

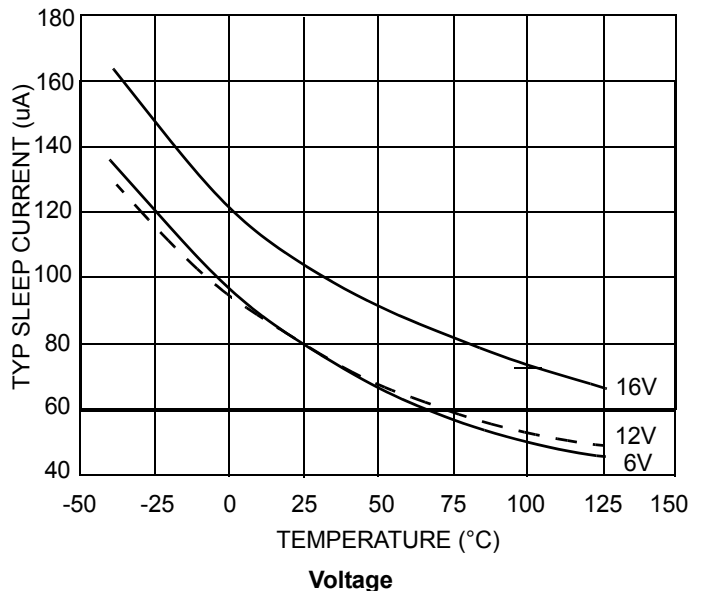
- Write to WUICR bits 0 and 1 to select the edge sensitivity for the Lx inputs.

- Write to MCR register: data SLEEP (100)

- Write to MCVR register: data SLEEP (100)

The SBC then enters sleep mode. It will wake up as soon as any of the Lx input reads the correct state.

Figure 59. Typical Sleep Current vs Temp and Batt



MC33389
APPLICATION

Figure 60. Typical Application Schematic 1

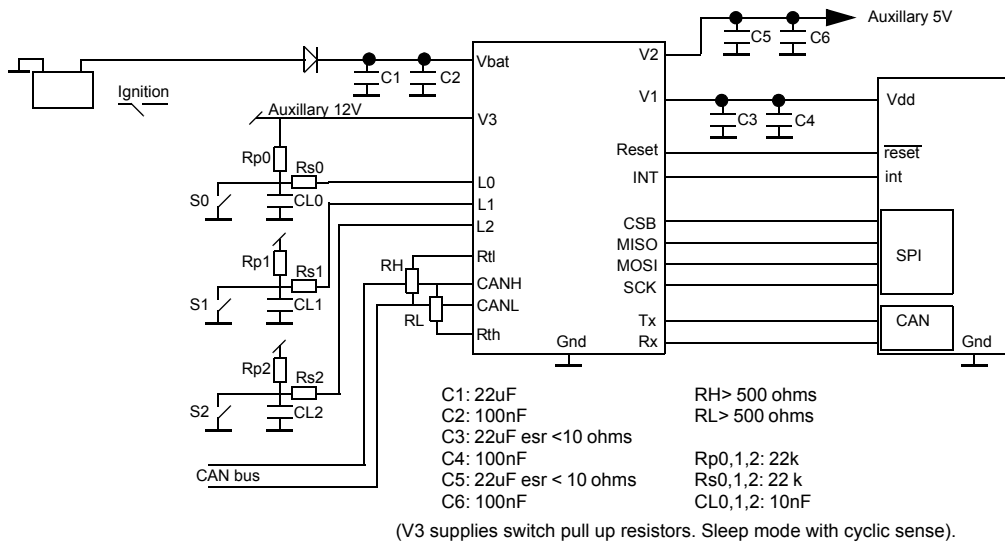


Figure 61. Typical Application: V3 used as auxiliary ECU supply - Reset Duration Extension

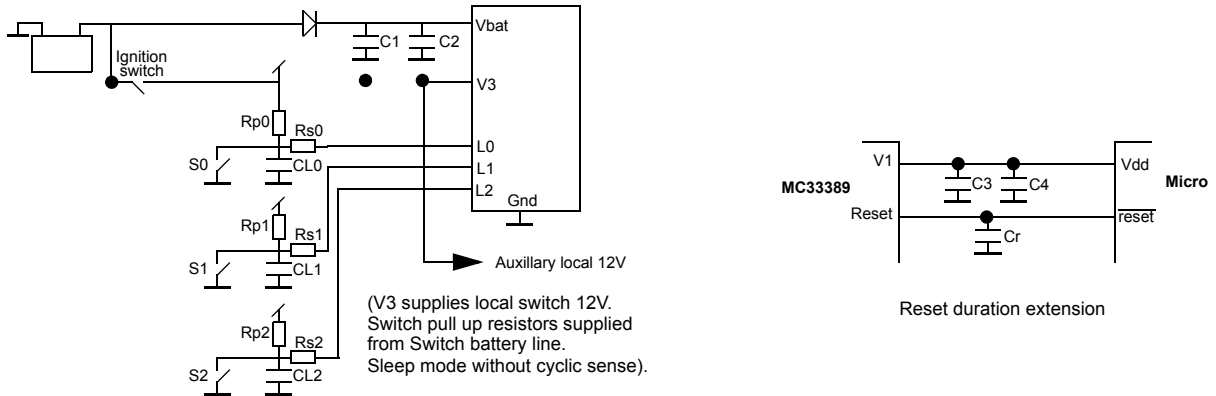
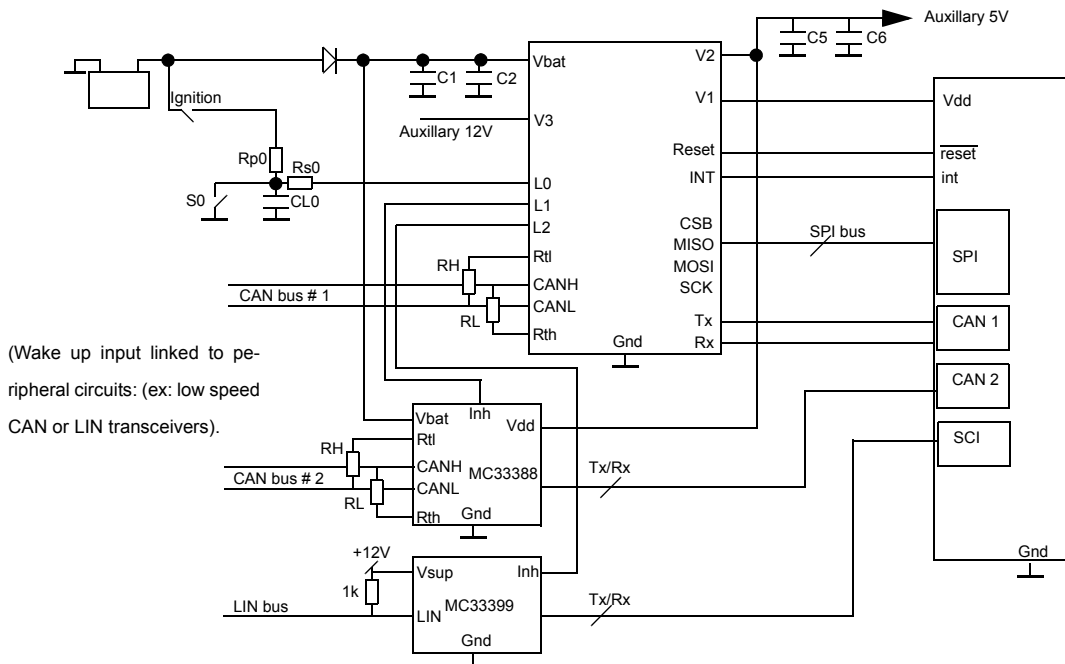


Figure 62. Typical Application Schematic



APPLICATION

The SBC offers several capabilities to help user debug its application.

- External bias of V1 and reset pin.
- Turn off of the software watchdog in standby mode.
- Special debug samples with software watchdog disable at power up (contact local Motorola representative).

Debug And Program Download Into Flash Memory

While the SBC is powered it enters normal request and expect within the 75ms time period of the NR mode an SPI trigger word (to enter normal mode and select the W/D time period). If this does not occurs, the SBC enter sleep mode and turn off V1.

When the software is been debug, and when using development tools, it is not always easy to make sure these events properly. It is thus possible to externally power the V1 line with an external 5V supply, and to force the Reset pin to V1 or to an external 5V. These can be done at nominal voltage and temperature. By doing this, 5V is provided to the MCU Vdd and reset lines.

Under this condition the SBC is not operational. However the reset pin is pulled low and is sinking 5mA to ground. This means that the external circuitry which drive reset must have a current capability higher than 5mA in order to drive the reset in high state.

Disable Of Software Watchdog In Standby Mode

The software watchdog can be disable in standby mode only. In order to disable it the following operation must be done:

- Write to MCR register: data 011 (bit 2, bit 1, bit 0)
- Write to MCVR register: data 011 (bit 2, bit 1, bit 0)

Then the SBC enters the standby mode without software watchdog. However the V2 can not be turn on, and the CAN cell can not be used.

Special Device

Special components are available to make the debug even easier. These device has a special behaviour which at power up disable the watchdog. These device can be available through marketing only. Contact local Motorola representative for more detail.

The behaviour of such special parts is as follow:

- At power up (from Vbat =0V), the SBC enters "normal request mode" and stays in this mode permanently. V1 is on, V2 and V3 off, CAN in Term Vbat. For reference, with MC33389ADW and MC33389CDH units it stays there 75ms only and go to sleep if no SPI.

- To get the SBC out on NormalRequest mode, write to SWCR register any valid data. This will enable the SBC to enter Normal mode, with V1 and V2 on. Once this is done, the SBC is controllable through SPI, in the same way as the normal versions. It can be turned in sleep. After wake up it enters NR mode (same as after power up described above).

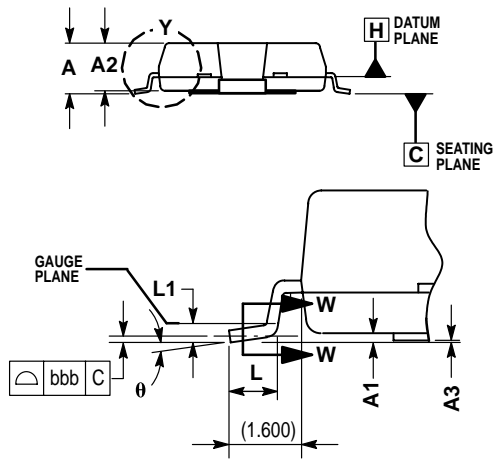
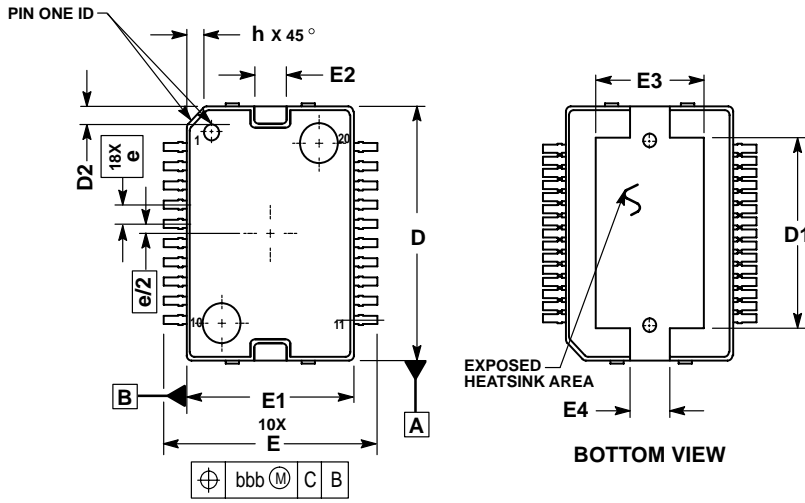
Only difference is that there is no need to refresh the software watchdog. Internally, the watchdog is running but when time out elapsed a reset is not generated.

When application debug is advanced enough, it is possible to enable the W/D-reset function.

To re activated the W/D effect, the VSSR register, bit VBSR0 (bat fail) must be read (cleared). When this is done, the W/D and 75ms timer of the NR mode effects are activated.

However, due to re synchronisation, it is likely that at some point a reset is generated and that the SBC enter reset state then Normalrequest mode.

When the SBC has had it W/D reactivated it is not possible to deactivated it again by software. The only way to do this is to remove battery supply voltage (Vbat < 3V for more than 200us) and then power up the SBC.



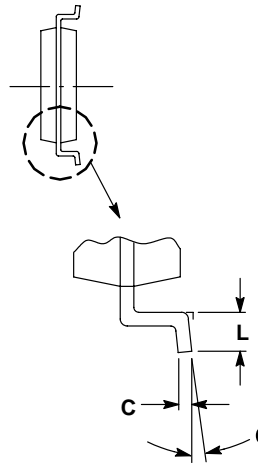
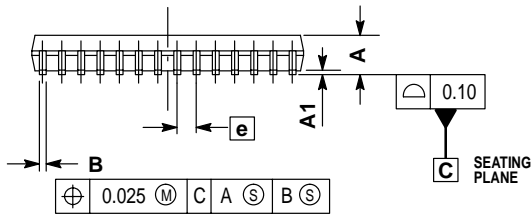
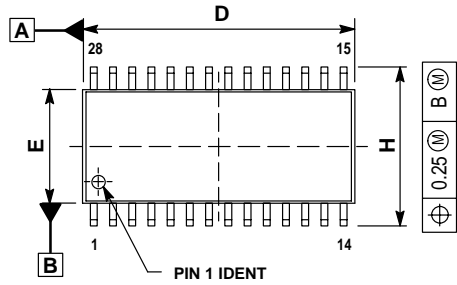
DETAIL Y

CASE 979C-02
ISSUE A

NOTES:

1. CONTROLLING DIMENSION: MILLIMETER.
2. DIMENSIONS AND TOLERANCES PER ASME Y14.5M, 1994.
3. DATUM PLANE -H- IS LOCATED AT BOTTOM OF LEAD AND IS COINCIDENT WITH THE LEAD WHERE THE LEAD EXITS THE PLASTIC BODY AT THE BOTTOM OF THE PARTING LINE.
4. DIMENSIONS D AND E1 DO NOT INCLUDE MOLD PROTRUSION. ALLOWABLE PROTRUSION IS 0.150 PER SIDE. DIMENSIONS D AND E1 DO INCLUDE MOLD MISMATCH AND ARE DETERMINED AT DATUM PLANE -H-.
5. DIMENSION b DOES NOT INCLUDE DAMBAR PROTRUSION. ALLOWABLE DAMBAR PROTRUSION SHALL BE 0.127 TOTAL IN EXCESS OF THE b DIMENSION AT MAXIMUM MATERIAL CONDITION.
6. DATUMS -A- AND -B- TO BE DETERMINED AT DATUM PLANE -H-.
7. DIMENSION D DOES NOT INCLUDE TIEBAR PROTRUSIONS. ALLOWABLE TIEBAR PROTRUSIONS ARE 0.150 PER SIDE.

| MILLIMETERS | | |
|-------------|-----------|--------|
| DIM | MIN | MAX |
| A | 3.000 | 3.400 |
| A1 | 0.100 | 0.300 |
| A2 | 2.900 | 3.100 |
| A3 | 0.00 | 0.100 |
| D | 15.800 | 16.000 |
| D1 | 11.700 | 12.600 |
| D2 | 0.900 | 1.100 |
| E | 13.950 | 14.450 |
| E1 | 10.900 | 11.100 |
| E2 | 2.500 | 2.700 |
| E3 | 6.400 | 7.200 |
| E4 | 2.700 | 2.900 |
| L | 0.840 | 1.100 |
| L1 | 0.350 BSC | |
| b | 0.400 | 0.520 |
| b1 | 0.400 | 0.482 |
| c | 0.230 | 0.320 |
| c1 | 0.230 | 0.280 |
| e | 1.270 BSC | |
| h | — | 1.100 |
| θ | 0° | 8° |
| aaa | 0.200 | |
| bbb | 0.100 | |



NOTES:

1. DIMENSIONS ARE IN MILLIMETERS.
2. INTERPRET DIMENSIONS AND TOLERANCES PER ASME Y14.5M, 1994.
3. DIMENSIONS D AND E DO NOT INCLUDE MOLD PROTRUSIONS.
4. MAXIMUM MOLD PROTRUSION 0.015 PER SIDE.
5. DIMENSION B DOES NOT INCLUDE DAMBAR PROTRUSION. ALLOWABLE DAMBAR PROTRUSION SHALL BE 0.13 TOTAL IN EXCESS OF B DIMENSION AT MAXIMUM MATERIAL CONDITION.

| MILLIMETERS | | |
|-------------|----------|-------|
| DIM | MIN | MAX |
| A | 2.35 | 2.65 |
| A1 | 0.13 | 0.29 |
| B | 0.35 | 0.49 |
| C | 0.23 | 0.32 |
| D | 17.80 | 18.05 |
| E | 7.40 | 7.60 |
| e | 1.27 BSC | |
| H | 10.05 | 10.55 |
| L | 0.41 | 0.90 |
| θ | 0° | 8° |

CASE 751F-05
ISSUE F

Motorola reserves the right to make changes without further notice to any products herein. Motorola makes no warranty, representation or guarantee regarding the suitability of its products for any particular purpose, nor does Motorola assume any liability arising out of the application or use of any product or circuit, and specifically disclaims any and all liability, including without limitation consequential or incidental damages. "Typical" parameters can and do vary in different applications and actual performance may vary over time. All operating parameters, including "Typicals", must be validated for each customer application by customer's technical experts. Motorola does not convey any license under its patent rights nor the rights of others. Motorola products are not designed, intended, or authorized for use as components in systems intended for surgical implant into the body, or other applications intended to support or sustain life, or for any other application in which the failure of the Motorola product could create a situation where personal injury or death may occur. Should Buyer purchase or use Motorola products for any such unintended or unauthorized application, Buyer shall indemnify and hold Motorola and its officers, employees, subsidiaries, affiliates, and distributors harmless against all claims, costs, damages, and expenses, and reasonable attorney fees arising out of, directly or indirectly, any claim of personal injury or death associated with such unintended or unauthorized use, even if such claim alleges that Motorola was negligent regarding the design or manufacture of the part. Motorola and are registered trademarks of Motorola, Inc. Motorola, Inc. is an Equal Opportunity/Affirmative Action Employer.

MOTOROLA and the Stylized M Logo are registered in the US Patent and Trademark Office. All other product or service names are the property of their respective owners.

© Motorola, Inc. 2002

How to reach us:

USA / EUROPE / Locations Not Listed: Motorola Literature Distribution; P.O. Box 5405, Denver, Colorado 80217. 1-303-675-2140 or 1-800-441-2447

JAPAN: Motorola Japan Ltd.; SPS, Technical Information Center, 3-20-1, Minami-Azabu, Minato-ku, Tokyo 106-8573 Japan. 81-3-344-3569

Technical Information Center: 1-800-521-6274

ASIA / PACIFIC: Motorola Semiconductors H.K. Ltd.; Silicon Harbour Centre, 2, Dai King Street, Tai Po Industrial Estate, Tai Po, N.T., Hong Kong. 852-26668334

HOME PAGE: <http://www.motorola.com/semiconductors>

