



HT32F66446A

Datasheet

**32-Bit Arm® Cortex®-M0+ BLDC Motor Microcontroller with
36V Half-bridge P/N Gate-Driver, CORDIC and PID Engine,
64 KB Flash and 8 KB SRAM with 2.5 Msps ADC, PGA, CMP,
PDMA, DIV, CAN, USART, UART, SPI, I²C, GPTM, MCTM,
SCTM, BFTM, CRC, UID, LSTM and WDT**



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1 General Description

The Holtek HT32F66446A is a high performance, low power consumption 32-bit microcontroller based around an Arm® Cortex®-M0+ processor core. The Cortex®-M0+ is a next-generation processor core which is tightly coupled with Nested Vectored Interrupt Controller (NVIC), SysTick timer, and including advanced debug support.

The device operates at a frequency of up to 80 MHz with a Flash accelerator to obtain maximum efficiency. The device provides 64 KB of embedded Flash memory for code/data storage and 8 KB of embedded SRAM memory for system operation and application program usage. A variety of peripherals, such as CORIDC, PID, Hardware Divider DIV, ADC, PGA, CMP, I²C, USART, UART, SPI, CAN, BFTM, MCTM, GPTM, SCTM, LSTM, WDT, CRC-16/32, 96-bit Unique ID, PDMA and SW-DP (Serial Wire Debug Port), etc., are also implemented in the device series. Several power saving modes provide the flexibility for maximum optimization between wakeup latency and power consumption, an especially important consideration in low power applications.

The device integrates PGA, CMP, DAC and MCTM's brake functions, which are combined for OCP protection. In order to implement the FOC algorithm, the MCTM can be used to trigger ADC to read PGA output at the same time for detecting real-time phase current information.

The device also includes a gate-driver for 3-phase motor driving applications. The gate-driver has several protection functions and provides an integrated 5 V low quiescent current LDO which can provide power supply for internal and external circuits.

The above features ensure that the device is suitable for use in dexterous robotic hands, servo-controlled gimbals and other products requiring CAN bus communication.



2 Features

Core

- 32-bit Arm® Cortex®-M0+ processor core
- Up to 80 MHz operating frequency
- Single-cycle multiplication
- Integrated Nested Vectored Interrupt Controller (NVIC)
- 24-bit SysTick timer

The Cortex®-M0+ processor is a very low gate count, highly energy efficient processor that is intended for microcontroller and deeply embedded applications that require an area optimized, low-power processor. The processor is based on the ARMv6-M architecture and supports Thumb® instruction sets, single-cycle I/O ports, hardware multiplier and low latency interrupt respond time.

On-Chip Memory

- 64 KB on-chip Flash memory for instruction/data and option byte storage
- 8 KB on-chip SRAM
- Supports multiple booting modes

The Arm® Cortex®-M0+ processor access and debug access share the single external interface to external AHB peripherals. The processor access takes priority over debug access. The maximum address range of the Cortex®-M0+ is 4 GB since it has a 32-bit bus address width. Additionally, a pre-defined memory map is provided by the Cortex®-M0+ processor to reduce the software complexity of repeated implementation by different device vendors. However, some regions are used by the Arm® Cortex®-M0+ system peripherals. Refer to the Arm® Cortex®-M0+ Technical Reference Manual for more information. Figure 2 in the Overview chapter shows the memory map of the device, including code, SRAM, peripheral and other pre-defined regions.

Flash Memory Controller – FMC

- Flash accelerator for maximum efficiency
- 32-bit word programming with In System Programming (ISP) and In Application Programming (IAP)
- Flash protection capability to prevent illegal access

The Flash Memory Controller, FMC, provides all the necessary functions and pre-fetch buffer and branch cache for the embedded on-chip Flash Memory. Since the access speed of the Flash Memory is slower than the CPU, a wide access interface with a pre-fetch buffer and branch cache are provided for the Flash Memory in order to reduce the CPU waiting time which will cause CPU instruction execution delays. Flash Memory word programming/page erase functions are also provided.

Reset Control Unit – RSTCU

- Supply supervisor
 - Power On Reset / Power Down Reset – POR / PDR
 - Brown-out Detector – BOD
 - Programmable Low Voltage Detector – LVD

The Reset Control Unit, RSTCU, has three kinds of reset, a power on reset, a system reset and an APB unit reset. The power on reset, known as a cold reset, resets the full system during power up. A system reset resets the processor core and peripheral IP components with the exception of the SW-DP controller. The resets can be triggered by external signals, internal events and the reset generators.

Clock Control Unit – CKCU

- External 4 to 16 MHz crystal oscillator
- Internal 8 MHz RC oscillator trimmed to $\pm 2\%$ accuracy at 5.0 V operating voltage and 25 °C operating temperature
- Internal 32 kHz RC oscillator
- Integrated system clock PLL
- Independent clock divider and gating bits for peripheral clock sources

The Clock Control Unit, CKCU, provides a range of oscillator and clock functions. These include a High Speed Internal RC oscillator (HSI), a High Speed External crystal oscillator (HSE), a Low Speed Internal RC oscillator (LSI), a Phase Lock Loop (PLL), an HSE clock monitor, clock pre-scalers, clock multiplexers, APB clock divider and gating circuitry. The AHB, APB and Cortex®-M0+ clocks are derived from the system clock (CK_SYS) which can come from HSI, HSE, LSI or system PLL. The Watchdog Timer (WDT) and Low Speed Timer (LSTM) use the LSI as their clock source.

Power Management – PWRCU

- V_{DD} power supply: 2.5 V to 5.5 V
- Integrated 1.5 V LDO regulator for MCU core, peripherals and memories power supply
- V_{DD} and V_{CORE} power domains
- Two power saving modes: Sleep and Deep-Sleep modes

Power consumption can be regarded as one of the most important issues for many embedded system applications. Accordingly the Power Control Unit, PWRCU, in the device provides many types of power saving modes such as Sleep and Deep-Sleep modes. These operating modes reduce the power consumption and allow the application to achieve the best trade-off between the conflicting demands of CPU operating time, speed and power consumption.

Gate-Driver

- 3-Channel Half-Bridge Driver: Driver 3 High-Side P-type MOSFETs and 3 Low-Side N-type MOSFETs
- Motor Power Supply Range V_{CC} : 6.0 V to 32 V
- Maximum Motor Sustainable Voltage Up to 36 V
- Integrated 50 mA LDO with 5.0 V ± 2.0 % Accuracy
- Low Sleep Current $\leq 2 \mu\text{A}$ ($V_{REG} = 0$ V)
- Support clamping voltage of $|12V_{GS}|$ when High-Side P-type MOSFETs and Low-Side N-type MOSFETs are conducted
- Integrated Dead time with 120 ns
- Support external signal wake-up, implementing ultra-low power consumption when device in the SLEEP mode
- FG High-Voltage Open-Drain Output, providing Motor Speed Information
- Gate Driving Current Capability
 - 0.35 A Peak Source Current
 - 0.5 A Peak Sink Current
- Protection Features
 - V_{CC} Power Supply Input Under Voltage Lock-Out (V_{CC_UVLO})
 - 5V LDO Output Under Voltage Lock-Out (V_{REG_UVLO})

External Interrupt/Event Controller – EXTI

- Up to 16 EXTI lines with configurable trigger source and type
- All GPIO pins can be selected as EXTI trigger source
- Source trigger type includes high level, low level, negative edge, positive edge, or both edges
- Individual interrupt enable, wakeup enable and status bits for each EXTI line
- Software interrupt trigger mode for each EXTI line
- Integrated deglitch filter for short pulse blocking

The External Interrupt/Event Controller, EXTI, comprises 16 edge detectors which can generate a wake-up event or interrupt requests independently. Each EXTI line can also be masked independently.

Coordinate Rotation Digital Computer – CORDIC

- 24-bit CORDIC rotation engine
- Circular and Hyperbolic modes
- Rotation and Vectoring modes
- Functions: Cosine, Sine, Phase, Modulus, Arctangent, Hyperbolic cosine, Hyperbolic sine, Hyperbolic arctangent, Natural logarithm, Square root, Rotation matrix, Integer Modulus and Integer square root

- Programmable precision
- Low latency AHB slave interface
- Results can be read as soon as ready, without polling or interrupt

The CORDIC co-processor provides hardware acceleration of certain mathematical functions (mainly trigonometric ones) commonly used in motor control, metering, signal processing and many other applications.

It speeds up the calculation of these functions compared to a software implementation, making it possible the use of a lower operating frequency, or freeing up processor cycles in order to perform other tasks.

Proportion Integration Differentiation – PID

- 20-bit PID calculation engine
- Contains two input and output formats
 - S16 format
 - ◆ Two input parameters: PIDout_max and PIDout_min
 - ◆ Single output parameter: PIDout
 - S20 format
 - ◆ 9 input parameters: ERR(n-1), ERR(n), KP, KI, KD, UI(n-1), UI_max, UI_min and UI_input(n)
- Internal computing parameters
 - The S24 format has 1 internal calculation parameter: PIDsum
 - The S20 format has 3 internal calculation parameters: UP, UI, UD
- Contains 6 sets of calculation registers: SPD, IQ, ID, FWNK, PLL, USR
- Contains completion interrupt and overflow interrupt

The Proportion-Integration-Differentiation, PID, controller performs an echo control by calculating the error between the actual value and the echo value to obtain a stable control system. The PID controller normally performs operations by sampling at periodic intervals and the system response can be adjusted by changing the KP, KI and KD gain values. It is used to measurable control system, such as speed, torque, field weakening, and phase-locked loops.

Analog to Digital Converter – ADC

- 12-bit SAR A/D engines
- Up to 2.5 Msps conversion rate – 0.4 μ s at 80 MHz
- Up to 11 external analog input channels

A 12-bit multi-channel Analog to Digital Converter is integrated in the device. There are multiplexed channels, which include 11 external channels on which the external analog signal can be supplied, 1 channel for internal connection with the pre-driver and 5 internal channels. If the input voltage is required to remain within a specific threshold window, the Analog Watchdog function will monitor and detect the signals. An interrupt will then be generated to inform the device that the input voltage is higher or lower than the preset thresholds. There are three conversion modes to convert an analog signal to digital data. The A/D conversion can be operated in one shot, continuous and discontinuous conversion mode.

Programmable Gain Amplifier – PGA

- Each programmable gain amplifier has fixed dedicated I/O pin
- Internal output path to A/D converter or comparator
- 5-bit scaler can be configurable for offset calibration

The PGA has dedicated input/output pins, which are the input pair of PGAnN and PGAnP, and an analog output pin of PGAnO. The analog output signals can also be connected internally to the ADC analog channels or the Comparator positive input.

Comparator – CMP

- Two Rail-to-rail comparators
- Each comparator has configurable negative or positive inputs used for flexible voltage selection
 - Dedicated I/O pins
 - Internal voltage reference provided by 8-bit scaler
 - Internal operational amplifier output
- Programmable hysteresis
- Programmable respond speed and power consumption
- Comparator output can be routed to I/O pin, to multiple timer or ADC trigger input
- 8-bit scaler can be configured to dedicated I/O for voltage reference
- Interrupt generation capability with wakeup from Sleep or Deep-Sleep mode through the EXTI controller

Two general purpose comparators, CMP, are implemented within the device. They can be configured either as standalone comparators or combined with the different kinds of peripheral IP. Each comparator is capable of asserting interrupts to the NVIC or waking up the CPU from the Sleep or Deep-Sleep mode through the EXTI wakeup event management unit.

I/O Ports – GPIO

- Up to 29 GPIOs
- Port A, B, C are mapped as 16-line EXTI interrupts
- Almost I/O pins are configurable output driving current

There are up to 29 General Purpose I/O pins, GPIO, for the implementation of logic input/output functions. Each of the GPIO ports has a series of related control and configuration registers to maximize flexibility and to meet the requirements of a wide range of applications.

The GPIO ports are pin-shared with other alternative functions (AFs) to obtain maximum functional flexibility on the package pins. The GPIO pins can be used as alternative functional pins by configuring the corresponding registers regardless of the input or output pins. The external interrupts on the GPIO pins of the device have related control and configuration registers in the External Interrupt Control Unit, EXTI.

Motor Control Timer – MCTM

- 16-bit up, down, up/down auto-reload counter
- Up to 4 independent channels
- 16-bit programmable prescaler that allows division of the prescaler clock source by any factor between 1 and 65536 to generate the counter clock frequency
- Input Capture function
- Compare Match Output
- PWM waveform generation with edge-aligned and center-aligned counting modes
- Single Pulse Mode Output
- Complementary Outputs with programmable dead-time insertion
- Up to two Break inputs to force the timer's output signals into a reset state or in a known state

The Motor Control Timer Module, MCTM, consists of a single 16-bit up/down counter, four 16-bit Capture/Compare Registers (CCRs), one 16-bit Counter-Reload Register (CRR), one 8-bit repetition counter and several control/status registers. It can be used for a variety of purposes which include input signal pulse width measurement, output waveform generation for signals such as compare match outputs, PWM outputs or complementary PWM outputs with dead-time insertion. The MCTM is capable of offering full functional support for motor control, hall sensor interfacing and break input.

General-Purpose Timer – GPTM

- 16-bit up, down, up/down auto-reload counter
- Up to 4 independent channels
- 16-bit programmable prescaler that allows division of the prescaler clock source by any factor between 1 and 65536 to generate the counter clock frequency
- Input Capture function
- Compare Match Output
- PWM waveform generation with edge-aligned and center-aligned counting modes
- Single Pulse Mode Output
- Encoder interface controller with two inputs using quadrature decoder and Pulse/Direction Mode
- Master/Slave mode controller

The General-Purpose Timer, GPTM, consists of one 16-bit up/down-counter, four 16-bit Capture/Compare Registers (CCRs), one 16-bit Counter Reload Register (CRR) and several control/status registers. It can be used for a variety of purposes including general timer, input signal pulse width measurement, output waveform generation such as single pulse generation or PWM outputs. The GPTM also supports an encoder interface using a quadrature decoder with two inputs.

Single Channel Timer – SCTM

- 16-bit auto-reload up-counter
- One channel for each timer
- 16-bit programmable prescaler that allows division of the prescaler clock source by any factor between 1 and 65536 to generate the counter clock frequency
- Input Capture function
- Compare Match Output
- PWM waveform generation with edge-aligned counting mode

The Single Channel Timer, SCTM, consists of one 16-bit up-counter, one 16-bit Capture/Compare Register (CCR), one 16-bit Counter-Reload Register (CRR) and several control/status registers. It can be used for a variety of purposes including general timer, input signal pulse width measurement or output waveform generation such as PWM outputs.

Basic Function Timer – BFTM

- 32-bit compare match up-counter – no I/O control
- One shot mode – stops counting when compare match occurs
- Repetitive mode – restarts counter when compare match occurs

The Basic Function Timer, BFTM, is a simple 32-bit up-counting counter designed to measure time intervals, generate one shot pulses or generate repetitive interrupts. The BFTM can operate in two modes which are repetitive and one shot modes. In the repetitive mode, the counter is restarted at each compare match event. The BFTM also supports a one shot mode which will force the counter to stop counting when a compare match event occurs.

Watchdog Timer – WDT

- 12-bit down-counter with a 3-bit prescaler
- Provides reset to the system
- Programmable watchdog timer window function
- Registers write protection function

The Watchdog Timer is a hardware timing circuitry that can be used to detect a system lock-up due to software trapped in a deadlock. It includes a 12-bit count-down counter, a prescaler, a WDT delta value register, WDT operation control circuitry and a WDT protection mechanism. If the software does not reload the counter value before a Watchdog Timer underflow occurs, a reset will be generated when the counter underflows. In addition, a reset is also generated if the software reloads the counter before it reaches a delta value. It means that the counter reload must occur when the Watchdog timer value has a value within a limited window using a specific method. The Watchdog Timer counter can be stopped when the processor is in the debug mode. The register write protection function can be enabled to prevent an unexpected change in the Watchdog timer configuration.

Low Speed Timer – LSTM

- 24-bit up-counter with a programmable prescaler
- Alarm function
- Interrupt and Wake-up event

The Low Speed Timer, LSTM, circuitry includes the APB interface, a 24-bit count-up counter, a control register, a prescaler, a compare register and a status register. The LSTM circuits are located in the V_{CORE} power domain. When the device enters the power-saving mode, the LSTM counter is used as a wake-up timer to let the system resume from the power saving mode.

Inter-integrated Circuit – I²C

- Supports both master and slave modes with a frequency of up to 1 MHz
- Provides an arbitration function and clock synchronization
- Supports 7-bit and 10-bit addressing modes and general call addressing
- Supports slave multi-addressing mode with maskable address

The I²C module is an internal circuit allowing communication with an external I²C interface which is an industry standard two-wire serial interface used for connection to external hardware. These two serial lines are known as a serial data line SDA, and a serial clock line SCL. The I²C module provides three data transfer rates: 100 kHz in the Standard mode; 400 kHz in the Fast mode; 1 MHz in the Fast plus mode. The SCL period generation registers are used to set different kinds of duty cycle implementation for the SCL pulse.

The SDA line which is connected directly to the I²C bus is a bidirectional data line between the master and slave devices and is used for data transmission and reception. The I²C module also has an arbitration detection and clock synchronization function to prevent situations where more than one master attempts to transmit data to the I²C bus at the same time.

Serial Peripheral Interface – SPI

- Supports both master and slave modes
- Frequency of up to ($f_{CLK}/2$) MHz for master mode and ($f_{CLK}/3$) MHz for slave mode
- FIFO Depth: 8 levels
- Multi-master and multi-slave operation

The Serial Peripheral Interface, SPI, provides an SPI protocol data transmit and receive function in both master and slave modes. The SPI interface uses 4 pins, among which are serial data input and output lines MISO and MOSI, the clock line, SCK, and the slave select line, SEL. One SPI device acts as a master device which controls the data flow using the SEL and SCK signals to indicate the start of data communication and the data sampling rate. To receive a data byte, the streamlined data bits are latched on a specific clock edge and stored in the data register or in the RX FIFO. Data transmission is carried out in a similar way but in a reverse sequence. The mode fault detection provides a capability for multi-master applications.

Universal Asynchronous Receiver Transmitter – UART

- Asynchronous serial communication operating baud-rate clock frequency up to ($f_{PCLK}/16$) MHz
- Full duplex communication capability
- Supports LIN (Local Interconnect Network) mode
- Supports single-wire mode
- Fully programmable serial communication characteristics including:
 - Word length: 7, 8 or 9-bit character
 - Parity: Even, odd or no-parity bit generation and detection
 - Stop bit: 1 or 2 stop bits generation
 - Bit order: LSB-first or MSB-first transfer
- Error detection: Parity, overrun and frame error

The Universal Asynchronous Receiver Transceiver, UART, provides a flexible full duplex data exchange using asynchronous transfer. The UART is used to translate data between parallel and serial interfaces, and is commonly used for RS232 standard communication. The UART peripheral function supports Line Status Interrupt. The software can detect a UART error status by reading the UART Status & Interrupt Flag Register, URSIFR. The status includes the type and the condition of transfer operations as well as several error conditions resulting from Parity, Overrun, Framing and Break events.

Universal Synchronous Asynchronous Receiver Transmitter – USART

- Supports both asynchronous and clocked synchronous serial communication modes
- Programmable baud rate clock frequency up to ($f_{PCLK}/16$) MHz for asynchronous mode and ($f_{PCLK}/8$) MHz for synchronous mode
- Full duplex communication capability
- Supports LIN (Local Interconnect Network) mode
- Supports single-wire mode
- Fully programmable serial communication characteristics including:
 - Word length: 7, 8 or 9-bit character
 - Parity: Even, odd or no-parity bit generation and detection
 - Stop bit: 1 or 2 stop bits generation
 - Bit order: LSB-first or MSB-first transfer
- Error detection: Parity, overrun and frame error
- Auto hardware flow control mode – RTS, CTS
- IrDA SIR encoder and decoder
- RS485 mode with output enable control
- FIFO Depth: 8-level for both receiver and transmitter

The Universal Synchronous Asynchronous Receiver Transceiver, USART, provides a flexible full duplex data exchange using synchronous or asynchronous data transfer. The USART is used to translate data between parallel and serial interfaces, and is commonly used for RS232 standard

communication. The USART peripheral function supports four types of interrupt including Line Status Interrupt, Transmitter FIFO Empty Interrupt, Receiver Threshold Level Reaching Interrupt and Time Out Interrupt. The USART module includes an 8-level transmitter FIFO, (TX_FIFO) and an 8-level receiver FIFO (RX_FIFO). The software can detect a USART error status by reading USART Status & Interrupt Flag Register, USRSIFR. The status includes the type and the condition of transfer operations as well as several error conditions resulting from Parity, Overrun, Framing and Break events.

Controller Area Network – CAN

- Conform to ISO11898-1, 2003
- 32 Message Objects
- Each Message Object has its own identifier mask
- Programmable FIFO mode (concatenation of Message Objects)
- Maskable interrupt
- Programmable loop-back mode for self-test operation

The CAN_Core performs communication according to the CAN protocol version 2.0 A, B and ISO11898-1. The internal State Machine controls the data transfer between the RX/TX Shift Register of the CAN_Core and the Message RAM as well as the generation of interrupts as programmed in the Control and Configuration Registers.

Cyclic Redundancy Check – CRC

- Supports CRC16 polynomial: 0x8005,
 $X^{16} + X^{15} + X^2 + 1$
- Supports CCITT CRC16 polynomial: 0x1021,
 $X^{16} + X^{12} + X^5 + 1$
- Supports IEEE-802.3 CRC32 polynomial: 0x04C11DB7,
 $X^{32} + X^{26} + X^{23} + X^{22} + X^{16} + X^{12} + X^{11} + X^{10} + X^8 + X^7 + X^5 + X^4 + X^2 + X + 1$
- Supports 1's complement, byte reverse & bit reverse operation on data and checksum
- Supports byte, half-word & word data size
- Programmable CRC initial seed value
- CRC computation executed in 1 AHB clock cycle for 8-bit data and 4 AHB clock cycles for 32-bit data
- Supports PDMA to complete a CRC computation of a block of memory

The CRC calculation unit is an error detection technique test algorithm and is used to verify data transmission or storage data correctness. A CRC calculation takes a data stream or a block of data as its input and generates a 16-bit or 32-bit output remainder. Ordinarily, a data stream is suffixed by a CRC code and used as a checksum when being sent or stored. Therefore, the received or restored data stream is calculated by the same generator polynomial as described above. If the new CRC code result does not match the one calculated earlier, that means the data stream contains a data error.

Peripheral Direct Memory Access – PDMA

- 6 channels with trigger source grouping
- 8-bit, 16-bit and 32-bit width data transfer
- Supports linear address, circular address and fixed address modes
- 4-level programmable channel priority
- Auto reload mode
- Supports trigger sources:

ADC, SPI, USART, UART, I²C, MCTM, GPTM, SCTM, CORDIC and software request

The Peripheral Direct Memory Access circuitry, PDMA, moves data between the peripherals and the system memory on the AHB bus. Each PDMA channel has a source address, destination address, block length and transfer count. The PDMA can exclude the CPU intervention and avoid interrupt service routine execution. It improves system performance as the software does not need to connect each data movement operation.

Hardware Divider – DIV

- Signed/unsigned 32-bit divider
- Calculate in 8 clock cycles, load in 1 clock cycle
- Division by zero error flag

The divider is the truncated division and requires a software triggered start signal by controlling the “START” bit in the control register. The divider calculation complete flag will be set to 1 after 8 clock cycles, however, if the divisor register data is zero during the calculation, the division by zero error flag will be set to 1.

Unique Identifier – UID

- Total 96-bit UID is unique and not duplicate with other HT32 MCU devices
- It is unchangeable and determined by MCU manufacturer

Debug Support

- Serial Wire Debug Port – SW-DP
- 4 comparators for hardware breakpoint or code / literal patch
- 2 comparators for hardware watch points

Package and Operation Temperature

- 46-pin QFN and 48-pin LQFP-EP packages
- Operation temperature: -40 °C to 105 °C

3 Overview

Device Information

Table 1. Features and Peripheral List

Peripherals		HT32F66446A
Main Flash (KB)		63
Option Bytes Flash (KB)		1
SRAM (KB)		8
Timers	MCTM	1
	GPTM	1
	SCTM	4
	BFTM	2
	LSTM	1
	WDT	1
Communication	USART	1
	UART	1
	SPI	1
	I ² C	1
	CAN	1
CORDIC		1
PID		1
PDMA		6 channels
CRC-16/32		1
EXTI		16
12-bit 2.5 Msps ADC		1
Number of channels		11 external channels
CMP		2
Programmable Gain Amplifier		4
Gate-Driver		1
GPIO		29 (Max.)
CPU frequency		Up to 80 MHz
Supply voltage (V _{CC})		6 V ~ 32 V
Operating voltage (V _{DD})		2.5 V ~ 5.5 V
5V LDO Regulator output drive current		50 mA
Operating temperature		-40 °C ~ 105 °C
Package		46-pin QFN and 48-pin LQFP-EP

Block Diagram

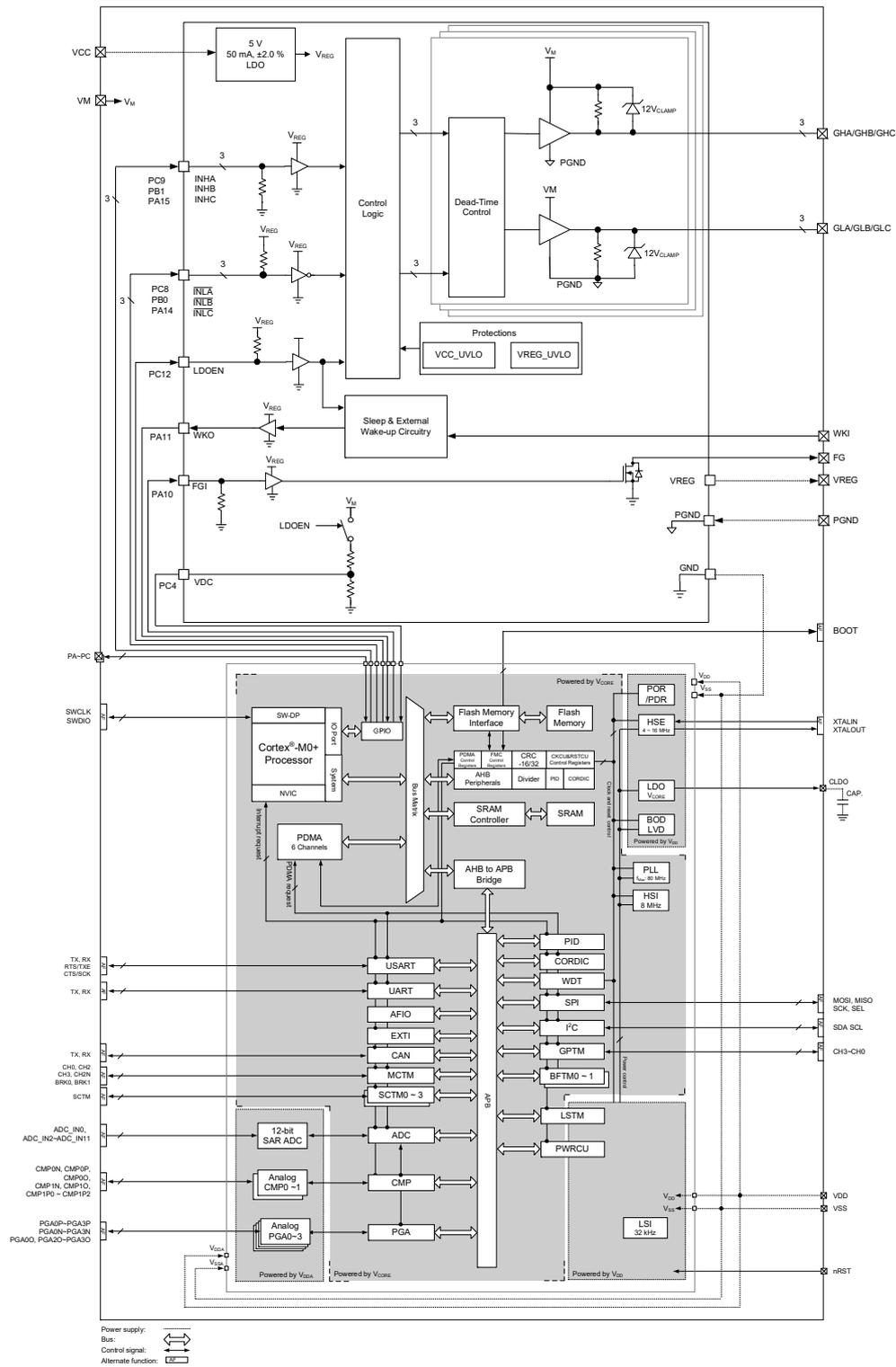


Figure 1. Block Diagram

Memory Map

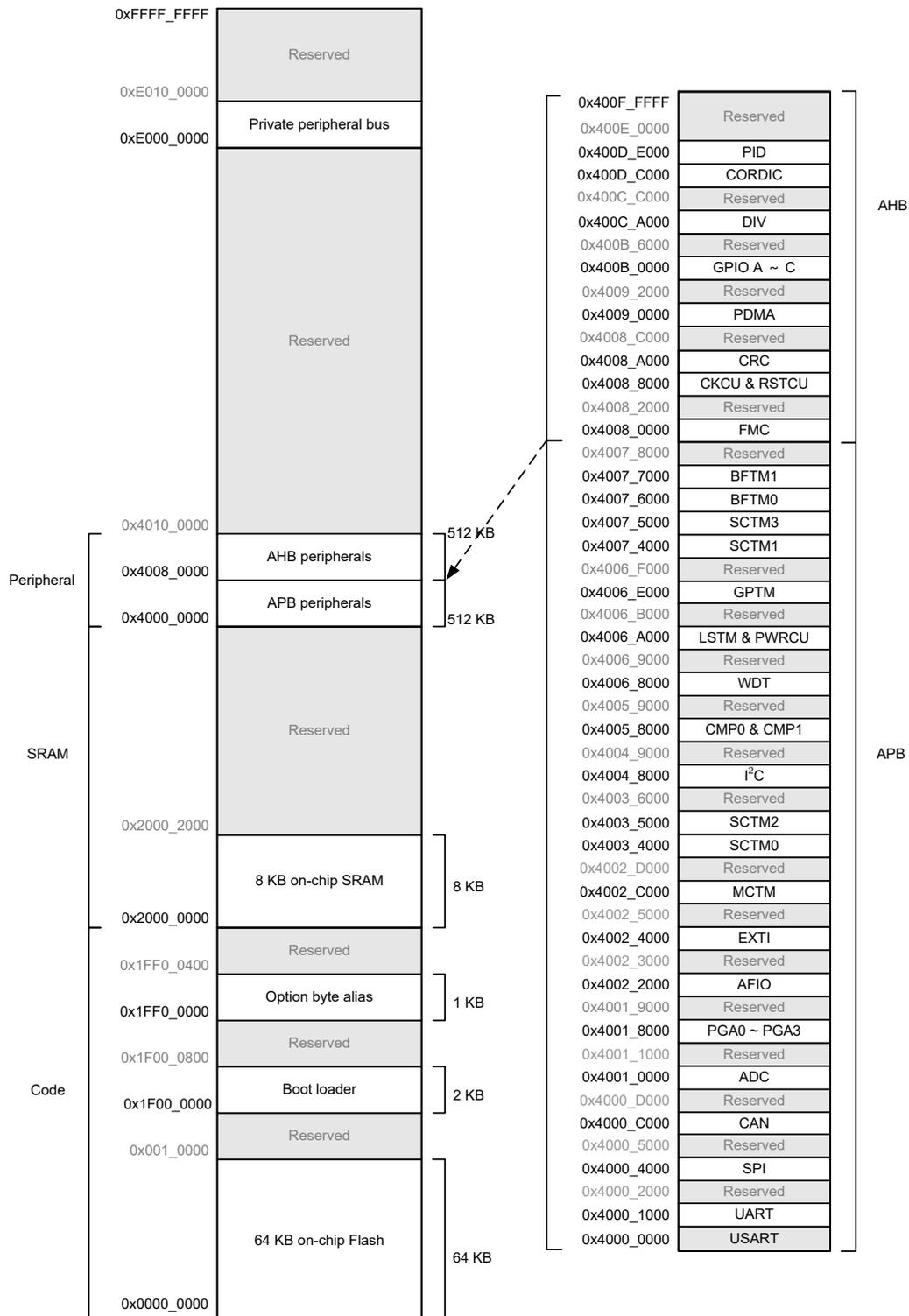


Figure 2. Memory Map

Table 2. Register Map

Start Address	End Address	Peripheral	Bus
0x4000_0000	0x4000_0FFF	USART	APB
0x4000_1000	0x4000_1FFF	UART	
0x4000_2000	0x4000_3FFF	Reserved	
0x4000_4000	0x4000_4FFF	SPI	
0x4000_5000	0x4000_BFFF	Reserved	
0x4000_C000	0x4000_CFFF	CAN	
0x4000_D000	0x4000_FFFF	Reserved	
0x4001_0000	0x4001_0FFF	ADC	
0x4001_1000	0x4001_7FFF	Reserved	
0x4001_8000	0x4001_8FFF	PGA0 ~ PGA3	
0x4001_9000	0x4002_1FFF	Reserved	
0x4002_2000	0x4002_2FFF	AFIO	
0x4002_3000	0x4002_3FFF	Reserved	
0x4002_4000	0x4002_4FFF	EXTI	
0x4002_5000	0x4002_BFFF	Reserved	
0x4002_C000	0x4002_CFFF	MCTM	
0x4002_D000	0x4003_3FFF	Reserved	
0x4003_4000	0x4003_4FFF	SCTM0	
0x4003_5000	0x4003_5FFF	SCTM2	
0x4003_6000	0x4004_7FFF	Reserved	
0x4004_8000	0x4004_8FFF	I ² C	
0x4004_9000	0x4005_7FFF	Reserved	
0x4005_8000	0x4005_8FFF	CMP0 & CMP1	
0x4005_9000	0x4006_7FFF	Reserved	
0x4006_8000	0x4006_8FFF	WDT	
0x4006_9000	0x4006_9FFF	Reserved	
0x4006_A000	0x4006_AFFF	LSTM & PWRCU	
0x4006_B000	0x4006_DFFF	Reserved	
0x4006_E000	0x4006_EFFF	GPTM	
0x4006_F000	0x4007_3FFF	Reserved	
0x4007_4000	0x4007_4FFF	SCTM1	
0x4007_5000	0x4007_5FFF	SCTM3	
0x4007_6000	0x4007_6FFF	BFTM0	
0x4007_7000	0x4007_7FFF	BFTM1	
0x4007_8000	0x4007_FFFF	Reserved	

Start Address	End Address	Peripheral	Bus
0x4008_0000	0x4008_1FFF	FMC	AHB
0x4008_2000	0x4008_7FFF	Reserved	
0x4008_8000	0x4008_9FFF	CKCU & RSTCU	
0x4008_A000	0x4008_BFFF	CRC	
0x4008_C000	0x4008_FFFF	Reserved	
0x4009_0000	0x4009_1FFF	PDMA	
0x4009_2000	0x400A_FFFF	Reserved	
0x400B_0000	0x400B_1FFF	GPIO A	
0x400B_2000	0x400B_3FFF	GPIO B	
0x400B_4000	0x400B_5FFF	GPIO C	
0x400B_6000	0x400C_9FFF	Reserved	
0x400C_A000	0x400C_BFFF	DIV	
0x400C_C000	0x400D_BFFF	Reserved	
0x400D_C000	0x400D_DFFF	CORDIC	
0x400D_E000	0x400D_FFFF	PID	
0x400E_0000	0x400F_FFFF	Reserved	

4 Gate-Driver

The device includes a 3-channel gate-drivers, which can be used for high-side P-type MOSFETs and low-side N-type MOSFETs driving. It includes a 5 V LDO, 3-channel high-side and low-side gate-driver circuits. The device also has two protection functions, which are V_{CC} Power Supply Input Under Voltage Lock-Out and 5 V LDO Output Under Voltage Lock-Out, to avoid abnormal output situations.

The input signals of INH_x , \overline{INL}_x and LDOEN are input to the control logic which will determine the high-side and low-side gate-driver outputs. The INH_x has an internal pull-down resistor and the \overline{INL}_x has an internal pull-up resistor. Additionally, there is a fixed dead time insertion when switching between the high-side and low-side gate driving to avoid short-circuit between V_M and ground.

The gate-driver output voltage will vary with the power supply. The gate-driver provides 0.35 A peak source current and 0.5 A peak sink current when V_{CC} is 24 V. Either high-side and low-side gate has an internal hold-off resistor in order to avoid error conduction of external power MOSFET due to interference when the power is off.

The gate-driver also provide a high voltage open-drain output FG signal, providing information about rotation speed of the motor.

In addition, if the gate-driver enters the SLEEP mode, all functions will be turned off to greatly reduce the sleep current. It is important not to confuse this SLEEP mode with the Sleep mode which is described in the “Power Management Control Unit” section of this datasheet.

Voltage Regulator

The integrated 5 V LDO can supply power for both internal and external circuits, with a output current over 50 mA. The LDO will act as a fully turned on switch when the power supply V_{CC} is less than 5 V, in which condition its output voltage is almost equal to the power supply if there is no load.

Gate-Driver Control Logic

As a gate-driver for driving high-side P-type MOSFETs and low-side N-type MOSFETs, the control signals are input from LDOEN, INH_x , \overline{INL}_x . Usually a 6-wire input control method is used, where the dead time width is determined by the control signals but has a minimum value equal to the fixed dead time designed in the gate-driver .

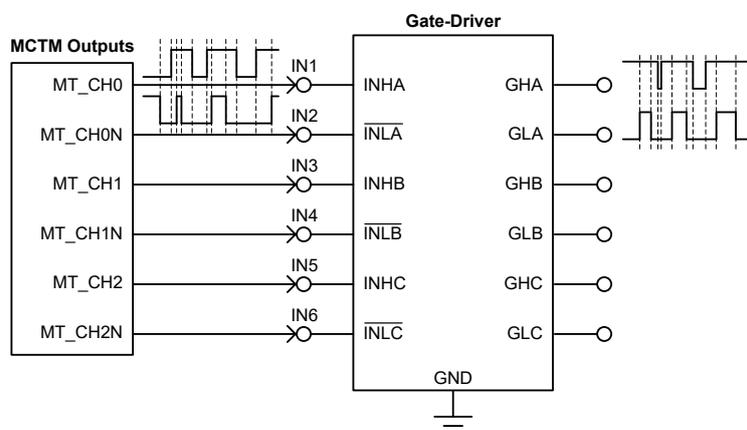


Figure 4. 6-Wire Control

Both high-side and low-side gate-driver outputs are controlled by the LDOEN, INHx and $\overline{\text{INLx}}$ input signals. For example, the on/off true table of the external power MOSFETs is shown as follows.

Table 3. Gate-Driver Operation Truth Table

LDOEN	INHx	$\overline{\text{INLx}}$	GHx-to-PGND	GLx-to-PGND	V _{REG}	External High-Side Power MOSFET	External Low-Side Power MOSFET
0	X	X	H	L	0V	OFF	OFF
1	0	0	H	H	V _{REG}	OFF	ON
1	0	1	H	L	V _{REG}	OFF	OFF
1	1	0	H	L	V _{REG}	OFF	OFF
1	1	1	L	L	V _{REG}	ON	OFF

X: No care; L: Low; H: High

Protection Function Operation

When the device operates in an abnormal situation, such as a V_{CC} Power Supply Input Under Voltage Lock-Out or 5 V LDO Output Under Voltage Lock-Out condition has occurred, it will activate the corresponding protection mechanism to turn off the affected power MOSFET. The protection mechanisms are summarized below.

Table 4. Protection Function Conditions

Protection	Protection Entry Condition	Protection Reaction			Release Condition
		V _{REG}	GHx-to-PGND	GLx-to-PGND	
V _{CC_UVLO}	V _{CC} < V _{CC_UVLO-}	0V	H	L	V _{CC} ≥ V _{CC_UVLO+}
V _{REG_UVLO}	V _{REG} < V _{REG_UVLO-}	—	H	L	V _{REG} ≥ V _{REG_UVLO+}

L: Low; H: High

Note: The LDO will not be turned off after the protection is triggered.

V_{CC} Power Supply Input Under Voltage Lock-Out – V_{CC_UVLO}

This integrated protection function is to avoid unstable gate-driver output when the power supply voltage falls to a certain low level. During V_{CC} power-on period, both high-side and low-side power MOSFETs are turned off and the LDO is in the sleep state and the LDO output is 0 V before the power supply voltage reaching the threshold V_{CC_UVLO+}. When the power supply voltage is greater than V_{CC_UVLO+}, the gate-driver outputs are determined by the input signals, the LDO is woken-up and the LDO output is determined by the input signals. If the power supply voltage falls below the under voltage lock-out threshold V_{CC_UVLO-}, both high-side and low-side power MOSFETs will remain off and the LDO will enter sleep state and output 0V.

5 V LDO Output Under Voltage Lock-Out – V_{REG_UVLO}

When the internal 5 V LDO output voltage, V_{REG}, is too low, the integrated 5 V LDO output under voltage lock-out function will be activated to avoid unstable signals input to the gate-driver. After V_{REG} exceeds the threshold V_{REG_UVLO+}, the gate-driver output is determined by the input signals. If V_{REG} is less than the under voltage lock-out threshold V_{REG_UVLO-}, both high-side and low-side power MOSFETs will remain off.

Ultra-low Power Consumption

When the control signal LDOEN is cleared to zero, the LDO will be turned off, that is, the system power in the V_{REG} domain will be turned off. In the SLEEP mode, the current consumption is less than $2 \mu\text{A}$, the gate-driver will wait for an external wake-up signal by monitoring the WKI pin. Once a valid wake-up signal on the WKI pin is triggered, if the voltage level is boosted by more than 4 V within 1 ms, the LDO output will be restored and the system will return to normal operation.

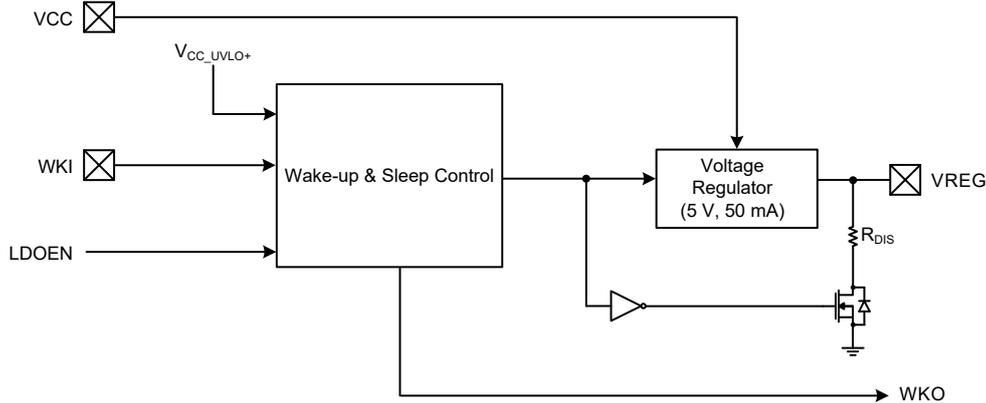


Figure 5. Enter the SLEEP Mode and Wake-up Function Block Diagram

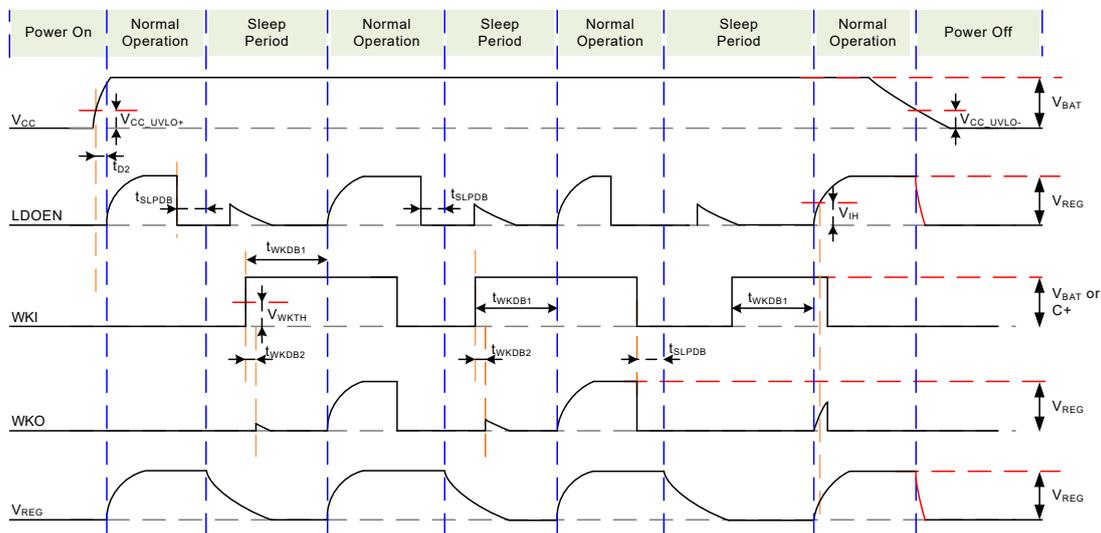


Figure 6. Enter the SLEEP Mode and Wake-up Function Timing

After V_{CC} power on, the gate-driver waits for V_{REG} to rise up. The control signal LDOEN reset to '0', V_{REG} turns off. Whether V_{REG} is turned on or not, WKI can control WKO signal.

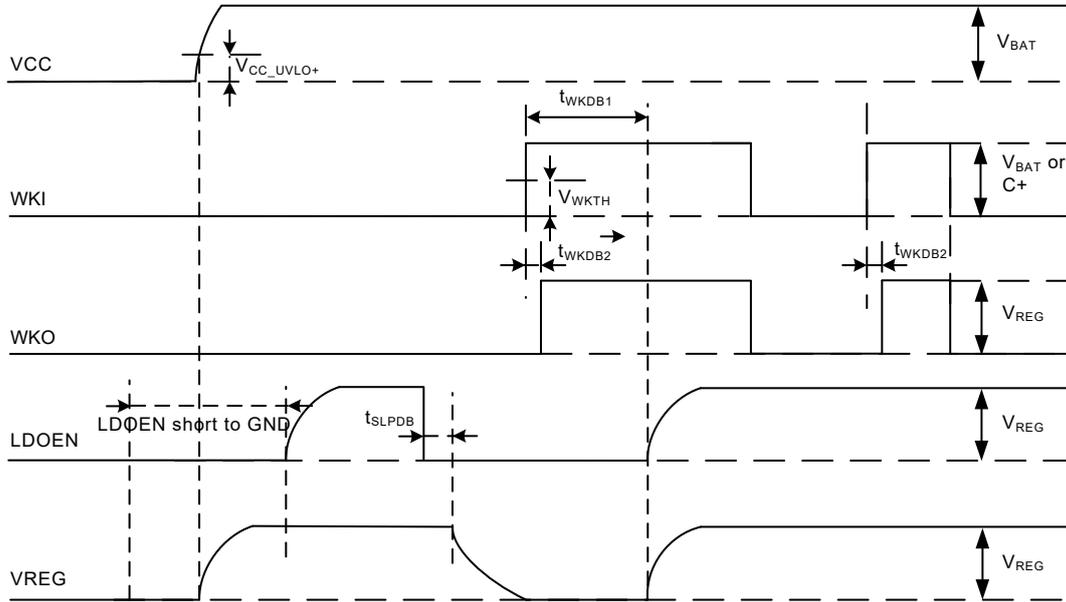


Figure 7. After Power on Enter SLEEP Mode and WKI Control WKO Timing

FG High Voltage Motor Speed Signal

The gate-driver provides a high-voltage open-drain mechanism, which can convert the low-voltage signal input from the FGI to a high-voltage signal and output it to the FG pin. This mechanism provides an external interface to monitor the motor speed signal. When FGI input is high level, the FG output will be 0 V, and when FGI input is low, the FG output is in high impedance state.

Table 5. FG Output Truth Table

LDOEN	FGI	FG
LDOEN = '0'	X	Z
LDOEN = '1'	'1'	L
LDOEN = '1'	'0'	Z

X: No care; L: Low; Z: High impedance

Component Selections

Gate Resistor Circuit

The main function of the gate resistors, R_{G1} , R_{G2} , R_{G3} and R_{G4} , is to reduce the vibration of U, V, W output voltages and reduce the EMI noise generation. Adjusting R_{G1} and R_{G3} controls the on time of the high-side and low-side switches, adjusting R_{G2} and R_{G4} controls the off time of the high-side and low-side switches. The gate resistors are optional and can be used according to the requirements.

It is recommended to select the gate resistance value according to the desired gate voltage rising time (t_r) or falling time (t_f), which are shown in the figure below. R_{G1} , R_{G2} , R_{G3} and R_{G4} , if used, are recommended to have a typical value of $10\ \Omega \sim 200\ \Omega$. It is recommended to use a 1N4148 switch diode for both D_{G1} and D_{G2} .

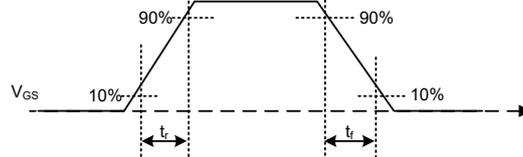


Figure 8. Gate Voltage (V_{GS}) Rising Time (t_r) and Falling Time (t_f)

Current Sensing Resistors

The current sensing resistors, R_S , turns the current flowing through it into a voltage for the controller to detect. The current sensing resistors are optional and can be used according to the requirements. It is recommended that the current sensing resistors be used when the cross voltage is less than 0.5 V.

Pay attention to the power that the current sensing resistors can withstand, P_{RS} , which is calculated by $P_{RS} = R_S \times I_{RMS}^2$, where R_S is the resistance value, I_{RMS} is the effective value of the current flowing through the resistor. The package of the current sensing resistor should be selected based on the power calculated above.

FG Pull-Up Resistors

The suggested value for the pull-up resistor, R_1 , connected between the FG pin and the V_M is 10 k Ω .

Gate-Driver Supply Capacitor

The power supply regulator capacitors, C_1 and C_5 can reduce input voltage fluctuation. C_1 is recommended to use at least a 4.7 μF capacitor and C_5 is recommended to use at least a 10 μF capacitor.

Power Supply Bypass Capacitor

When the board power supply is mains, the power supply bypass capacitor, C_4 , can filter out the high-frequency noise input from the power supply. It is recommended to use a 0.1 μF capacitor. This capacitor is optional and can be used according to the requirements.

Motor Supply Capacitor

The motor power supply capacitor, C_3 , can absorb the current that is fed back to the V_M power supply when the motor is running, and can also provide a transient power for motor to compensate for the power response speed or the influence of external wire length.

LDO Output Capacitor

The LDO output regulator capacitor, C_2 , can reduce the voltage ripple of the LDO output. It is recommended to use at least a 2.2 μF capacitor.

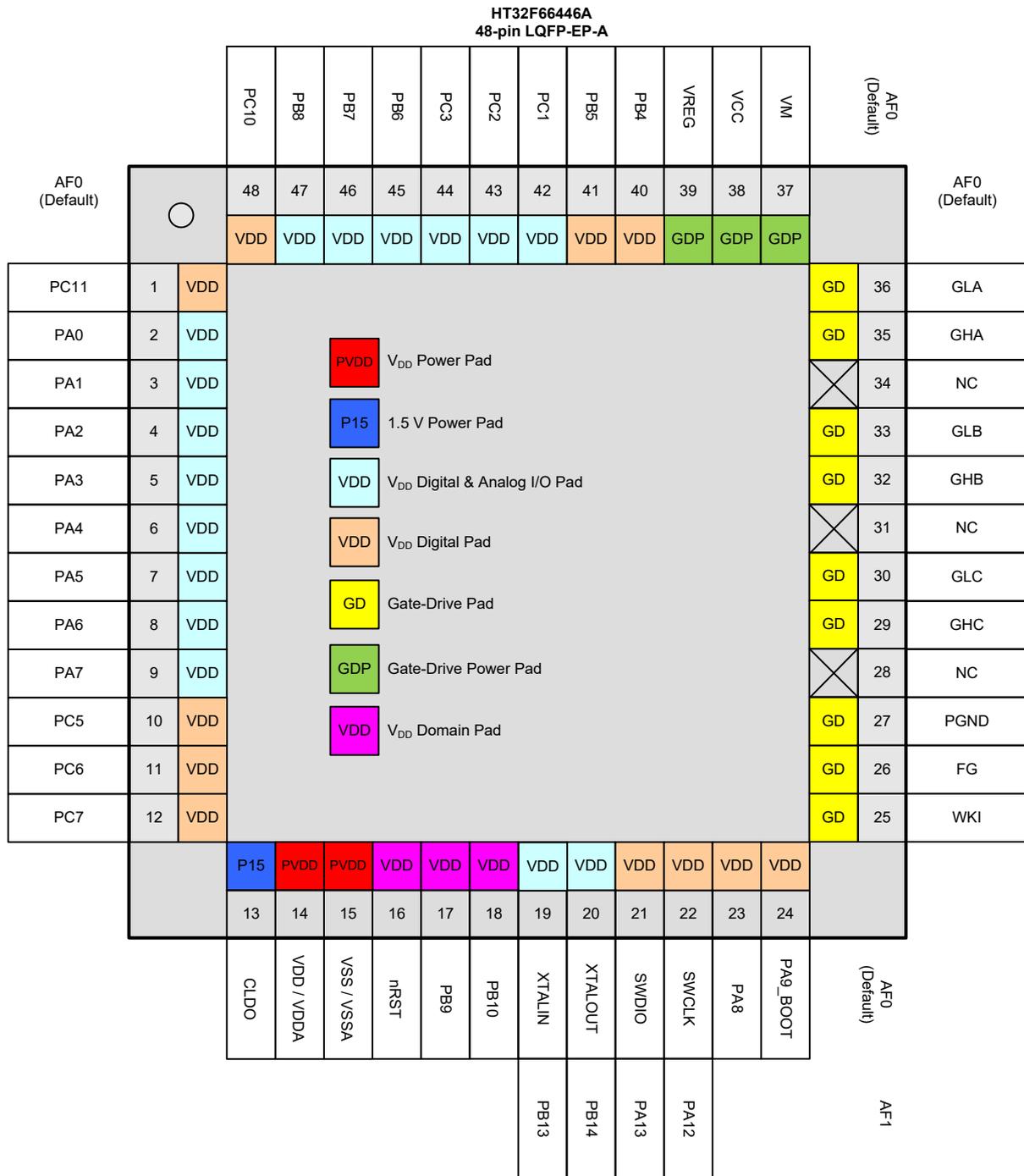
5 Pin Assignment

**HT32F66446A
46-pin QFN-A**

		PA1	PA0	PC11	PC10	PB8	PB7	PB6	PC3	PC2	PC1	PB5	PB4	VREG	VCC	AF0 (Default)		AF0 (Default)
		46	45	44	43	42	41	40	39	38	37	36	35	34	33			
		VDD	VDD	VDD	VDD	VDD	VDD	VDD	VDD	VDD	VDD	VDD	VDD	GDP	GDP			
PA2	1	VDD	<div style="display: flex; flex-direction: column; align-items: center;"> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: red; margin-right: 5px;"></div> V_{DD} Power Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: blue; margin-right: 5px;"></div> 1.5 V Power Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: cyan; margin-right: 5px;"></div> V_{DD} Digital & Analog I/O Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: orange; margin-right: 5px;"></div> V_{DD} Digital I/O Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: yellow; margin-right: 5px;"></div> Gate-Drive Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: green; margin-right: 5px;"></div> Gate-Drive Power Pad </div> <div style="display: flex; align-items: center; margin-bottom: 5px;"> <div style="width: 15px; height: 15px; background-color: magenta; margin-right: 5px;"></div> V_{DD} Domain Pad </div> </div>															

5 Pin Assignment

Figure 9. 46-pin QFN Pin Assignment



5 Pin Assignment

Figure 10. 48-pin LQFP-EP Pin Assignment

Table 6. Pin Assignment

Packages		Alternate Function Mapping															
		AF0	AF1	AF2	AF3	AF4	AF5	AF6	AF7	AF8	AF9	AF10	AF11	AF12	AF13	AF14	AF15
48 LQFP-EP	46 QFN	System Default	GPIO	ADC	N/A	GPTM /MCTM	SPI	USART /UART	I ² C	CMP /PGA	SCTM	N/A	N/A	CAN	MCTM	MCTM	System Other
2	45	PA0		ADC_IN3		MT_CH2N		USR_RTS		PGA3O	SCTM3			CAN_RX			
3	46	PA1				GT_CH2		USR_CTS	I2C_SCL	PGA3N	SCTM2			CAN_TX			
4	1	PA2				GT_CH1	SPL_SCK	USR_RX	I2C_SDA	PGA3P	SCTM1						
5	2	PA3		ADC_IN2			SPL_SEL			PGA2O							
6	3	PA4				GT_CH2	SPL_SCK	UR_RX	I2C_SCL	PGA2N	SCTM2			CAN_RX			
7	4	PA5				GT_CH3		UR_TX	I2C_SDA	PGA2P	SCTM3			CAN_TX			
8	5	PA6				GT_CH1		USR_TX		PGA1P	SCTM1			CAN_RX			
9	6	PA7					SPL_MISO	USR_RTS		PGA1N				CAN_TX			
10	7	PC5				GT_CH0		USR_RX		PGA0P	SCTM0			CAN_TX			
11	8	PC6						UR_RX	I2C_SDA	PGA0N				CAN_RX			
12	9	PC7		ADC_IN0		MT_BRK1		UR_TX	I2C_SCL	PGA0O							VBG
13	10	CLDO															
14	11	VDD/VDDA															
15	12	VSS/VSSA															
16	13	nRST															
17		PB9						USR_RX			SCTM0						
18		PB10						USR_TX			SCTM1						
19	14	XTALIN	PB13			MT_CH3	SPL_SEL	UR_RX	I2C_SCL		SCTM0			CAN_RX			
20	15	XTALOUT	PB14			MT_BRK0	SPL_SCK	UR_TX	I2C_SDA		SCTM1			CAN_TX			
21	16	SWDIO	PA13			MT_CH3	SPL_MOSI	USR_TX	I2C_SDA					CAN_TX			
22	17	SWCLK	PA12				SPL_MISO	USR_RX	I2C_SCL					CAN_RX			
23		PA8				GT_CH0	SPL_MOSI	UR_TX			SCTM0						
24	18	PA9_BOOT				GT_CH3	SPL_MISO	UR_RX			SCTM3			MT_CH2	MT_CH0	CKOUT	
25	22	WKI															
26	23	FG															
27	24	PGND															
29	26	GHC															
30	27	GLC															
32	28	GHB															
33	29	GLB															
35	30	GHA															
35	31	GLA															
37	32	VM															
38	33	VCC															
39	34	VREG															
40	35	PB4				MT_BRK0		UR_TX	I2C_SDA		SCTM2			CAN_TX	MT_CH2N		
41	36	PB5				MT_BRK1		UR_RX	I2C_SCL		SCTM0			CAN_RX			
42	37	PC1		ADC_IN11		MT_BRK0	SPL_SCK	USR_RTS	I2C_SDA	CMP1O	SCTM2			CAN_TX			

Packages		Alternate Function Mapping															
48 LQFP-EP	46 QFN	AF0	AF1	AF2	AF3	AF4	AF5	AF6	AF7	AF8	AF9	AF10	AF11	AF12	AF13	AF14	AF15
		System Default	GPIO	ADC	N/A	GPTM/MCTM	SPI	USART/UART	I ² C	CMP/PGA	SCTM	N/A	N/A	CAN	MCTM	MCTM	System Other
43	38	PC2		ADC_IN10		GT_CH3	SPI_MISO	USR_RX	I2C_SDA	CMP1N	SCTM3			CAN_RX			
44	39	PC3		ADC_IN9		GT_CH2	SPI_MOSI	USR_TX	I2C_SCL	CMP1P2	SCTM2						
45	40	PB6		ADC_IN8		GT_CH1	SPI_SEL	USR_CTS		CMP1P1	SCTM1						
46	41	PB7		ADC_IN7		GT_CH0		UR_TX		CMP1P0	SCTM0			CAN_RX			
47	42	PB8		ADC_IN6		MT_BRK1	SPI_MOSI	UR_RX	I2C_SCL	CMP00				CAN_TX			
48	43	PC10		ADC_IN5		MT_BRK0	SPI_SEL	UR_TX		CMP0N							
1	44	PC11		ADC_IN4		GT_CH0	SPI_MISO	USR_TX		CMP0P	SCTM0						

Table 7. Pin Description

Pin Number		Pin Name	Type ⁽¹⁾	I/O Structure ⁽²⁾	Output Driving	Description
48 LQFP-EP	46 QFN					Default Function (AF0)
2	45	PA0	AI/O	5V	4/8/12/16 mA	PA0
3	46	PA1	AI/O	5V	4/8/12/16 mA	PA1
4	1	PA2	AI/O	5V	4/8/12/16 mA	PA2
5	2	PA3	AI/O	5V	4/8/12/16 mA	PA3
6	3	PA4	AI/O	5V	4/8/12/16 mA	PA4, this pin provides a UART_RX function in the Boot loader mode.
7	4	PA5	AI/O	5V	4/8/12/16 mA	PA5, this pin provides a UART_TX function in the Boot loader more.
8	5	PA6	AI/O	5V	4/8/12/16 mA	PA6
9	6	PA7	AI/O	5V	4/8/12/16 mA	PA7
10	7	PC5	I/O	5V	4/8/12/16 mA	PC5
11	8	PC6	I/O	5V	4/8/12/16 mA	PC6
12	9	PC7	I/O	5V	4/8/12/16 mA	PC7
13	10	CLDO	P	—	—	Core power LDO V _{CORE} output It must be connected a 2.2 μF capacitor as close as possible between this pin and VSS.
14	11	VDD/VDDA	P	—	—	Digital and analog voltage input
15	12	VSS/VSSA ⁽⁵⁾	P	—	—	Ground reference
16	13	nRST ⁽³⁾	I	5V_PU	—	External reset pin
17		PB9 ⁽³⁾	I/O (V _{DD})	5V	4/8/12/16 mA	PB9
18		PB10 ⁽³⁾	I/O (V _{DD})	5V	4/8/12/16 mA	PB10
19	14	PB13	AI/O	5V	4/8/12/16 mA	XTALIN
20	15	PB14	AI/O	5V	4/8/12/16 mA	XTALOUT
21	16	PA13	I/O	5V_PU	4/8/12/16 mA	SWDIO

Pin Number		Pin Name	Type ⁽¹⁾	I/O Structure ⁽²⁾	Output Driving	Description
48 LQFP-EP	46 QFN					Default Function (AF0)
22	17	PA12	I/O	5V_PU	4/8/12/16 mA	SWCLK
23		PA8	I/O	5V	4/8/12/16 mA	PA8
24	18	PA9	I/O	5V_PU	4/8/12/16 mA	PA9_BOOT
25	22	WKI	I	—	—	External wake-up input. Keep floating when no use
26	23	FG	O	—	—	High voltage level shifter open-drain output
27	24	PGND	P	—	—	Gate-driver ground terminal
29	26	GHC	O	—	—	High-side P-type MOSFET gate-drive phase C
30	27	GLC	O	—	—	Low-side N-type MOSFET gate-drive phase C
32	28	GHB	O	—	—	High-side P-type MOSFET gate-drive phase B
33	29	GLB	O	—	—	Low-side N-type MOSFET gate-drive phase B
35	30	GHA	O	—	—	High-side P-type MOSFET gate-drive phase A
35	31	GLA	O	—	—	Low-side N-type MOSFET gate-drive phase A
37	32	VM	P	—	—	Motor supply and gate-driver supply input
38	33	VCC	P	—	—	V _{CC} power supply input
39	34	VREG	O	—	—	Supplied from VCC. Regulated 5 V output
40	35	PB4	I/O	5V	4/8/12/16 mA	PB4
41	36	PB5	I/O	5V	4/8/12/16 mA	PB5
42	37	PC1	AI/O	5V	4/8/12/16 mA	PC1
43	38	PC2	AI/O	5V	4/8/12/16 mA	PC2
44	39	PC3	AI/O	5V	4/8/12/16 mA	PC3
45	40	PB6	AI/O	5V	4/8/12/16 mA	PB6
46	41	PB7	AI/O	5V	4/8/12/16 mA	PB7
47	42	PB8	AI/O	5V	4/8/12/16 mA	PB8
48	43	PC10	I/O	5V	4/8/12/16 mA	PC10
1	44	PC11	I/O	5V	4/8/12/16 mA	PC11

Note: 1. I = Input, O = Output, A = Analog Port, P = Power Supply, V_{DD} = V_{DD} Power.

2. 5V = 5 V operation I/O type, PU = Pull-up.

3. These pins are located at the V_{DD} power domain.

4. In the Boot loader mode, the UART interface can be used for communication.

5. The VSS/VSSA is internally connected to the gate-drive GND line.

Internal Connection Signals

The MCU generated signals such as the MCTM channel outputs have been internally connected to the gate-driver inputs for control purpose. The connections are listed in the following table and the related control registers should be configured correctly using application program.

Table 8. Internal Connection Signal Lines

MCU Signal Name	Connection Gate-Driver Signal Name	Description
PC9 / MT_CH0 (MCTM)	INHA	Control input for high-side gate-drive phase A. High active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PC8 / MT_CH0N (MCTM)	$\overline{\text{INLA}}$	Control input for low-side gate-drive phase A. Low active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PB1 / MT_CH1 (MCTM)	INH B	Control input for high-side gate-drive phase B. High active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PB0 / MT_CH1N (MCTM)	$\overline{\text{INLB}}$	Control input for low-side gate-drive phase B. Low active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PA15 / MT_CH2 (MCTM)	INHC	Control input for high-side gate-drive phase C. High active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PA14 / MT_CH2N (MCTM)	$\overline{\text{INLC}}$	Control input for low-side gate-drive phase C. Low active. The MCU AFIO setting should be AF4 to select the MCTM pin function.
PC12	LDOEN	LDO enable pin. It is pulled-up and connected to VREG internally. The MCU AFIO setting should be AF0 to select the General Purpose Input/Output pin function.
PC4 / ADC_IN1 (ADC)	VDC	Motor power supply voltage divider output. The MCU AFIO setting should be AF2 to select the ADC pin function.
PA11	WKO	External wake-up output. An external high voltage wake-up signal input on the WKI pin will be converted into a low voltage, V_{REG} , which is output by the WKO pin and can be used as an interrupt signal for the MCU. Keep floating when no use. The MCU AFIO setting should be AF0 to select the General Purpose Input/Output pin function.
PA10	FGI	Control input of high voltage level shifter to FG. The MCU AFIO setting should be AF0 to select the General Purpose Input/Output pin function.

6 Application Circuit

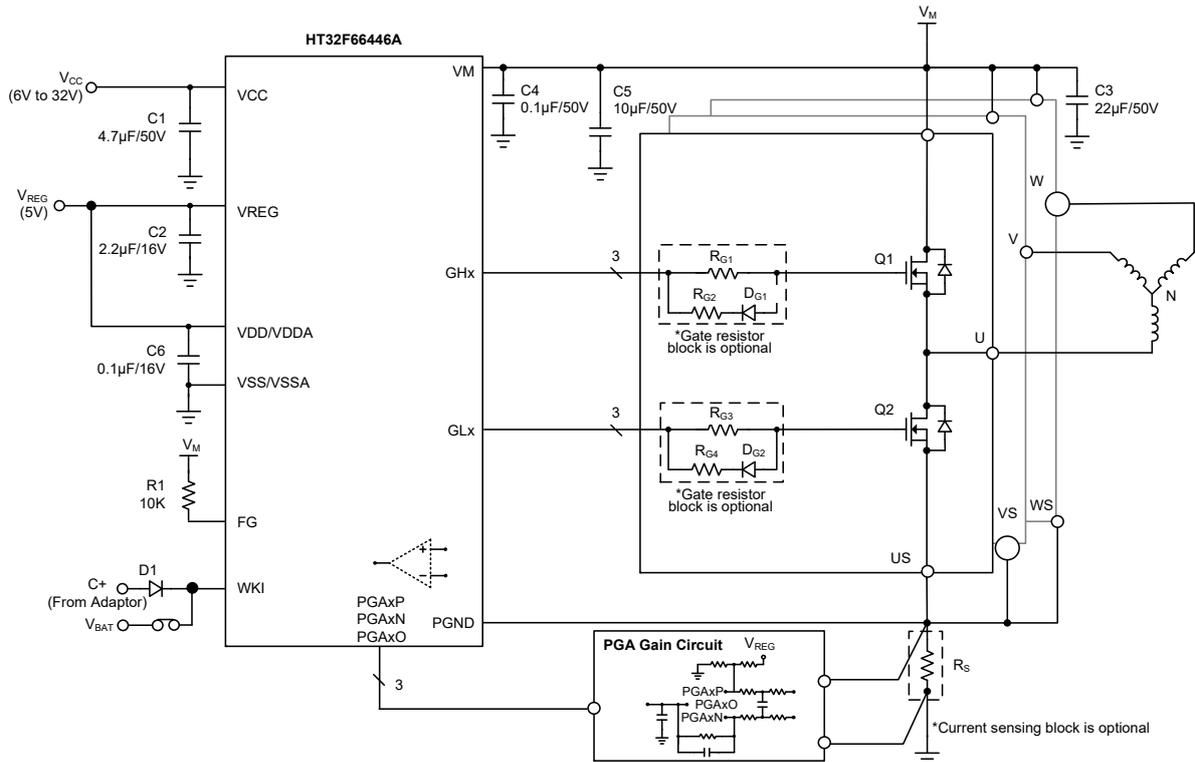


Figure 11. Typical Application Circuit – 1-Shunt Current Sensing

7 Electrical Characteristics

Power Supply Scheme

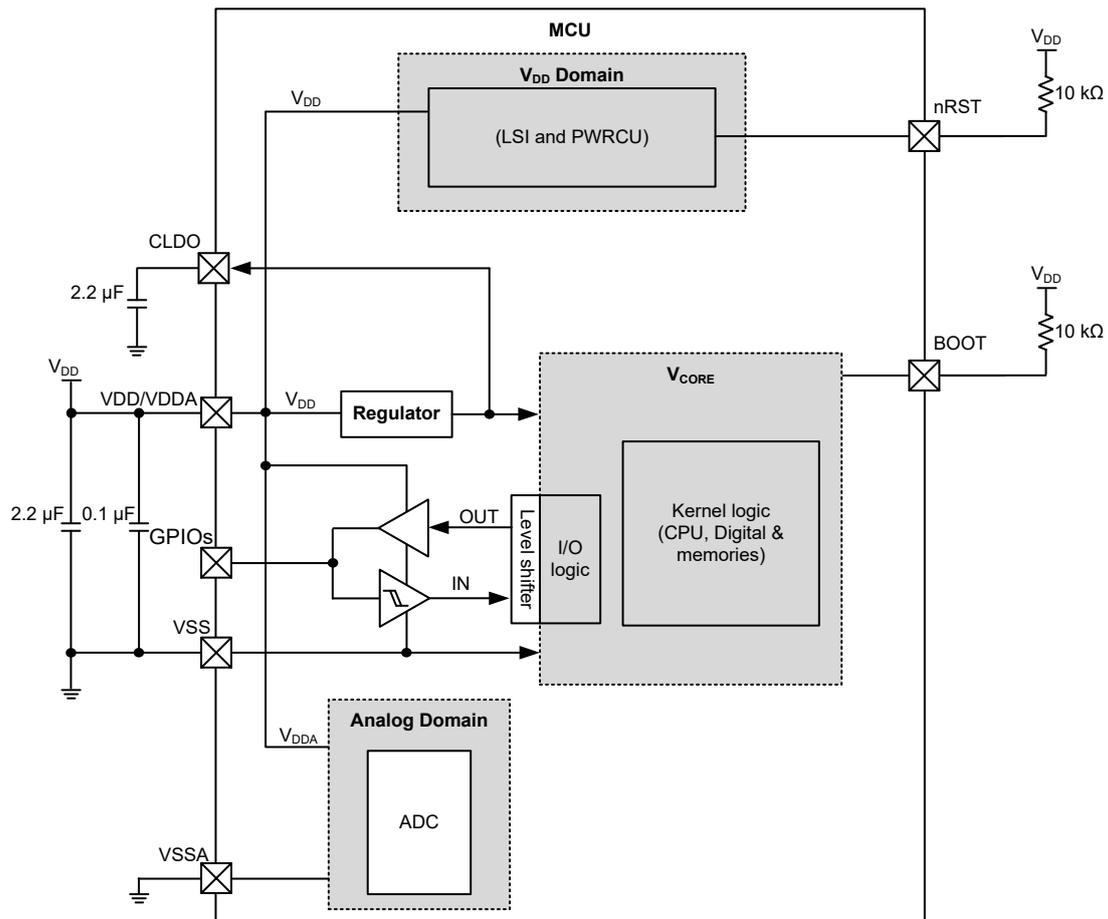


Figure 12. Power Supply Scheme

- Note:
1. All regulator capacitors must be placed as close to the MCU as possible.
 2. It is recommended that the pull-up resistor of the BOOT pin is 10 kΩ.
 3. It is recommended that the pull-up resistor of the nRST pin is 10 kΩ.

Absolute Maximum Ratings

The following table shows the absolute maximum ratings of the device. These are stress ratings only. Stresses beyond absolute maximum ratings may cause permanent damage to the device. Note that the device is not guaranteed to operate properly at the maximum ratings. Exposure to the absolute maximum rating conditions for extended periods may affect device reliability.

Table 9. Absolute Maximum Ratings

Parameter	Value	Unit
V_{DD} , V_{DDA}	$(V_{SS} - 0.3)$ to $(V_{SS} + 5.5)$	V
VCC, VM, WKI, FG	-0.3 to 36	V
VM-to-GHx	-0.3 to 36	V
GLx-to-PGND	-0.3 to 36	V
VREG	-0.3 to 7.0	V
PGND	-0.7 to 0.7	V
Operating Ambient Temperature Range	-40 to 105	°C
Maximum Junction Temperature	150	°C
Storage Temperature Range	-60 to 150	°C
Lead Temperature (Soldering 10s)	260	°C
Electrostatic Discharge Voltage	Human Body Model	±2000
Junction-to-Ambient Thermal Resistance, θ_{JA}	48 LQFP-EP	50
	46 QFN	28.6

Recommended DC Operating Conditions

Table 10. Recommended DC Operating Conditions

$T_A = 25\text{ }^\circ\text{C}$, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V_{CC}	Power Supply Input	—	6	—	32	V
V_{DD}	Operating Voltage	—	2.5	5.0	5.5	V
V_{DDA}	Analog Operating Voltage	—	2.5	5.0	5.5	V

On-Chip LDO Voltage Regulator Characteristics

Table 11. LDO Characteristics

$T_A = 25\text{ }^\circ\text{C}$, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V_{LDO}	Internal Regulator Output Voltage	$V_{DD} \geq 2.5\text{ V}$ Regulator input @ $I_{LDO} = 25\text{ mA}$ and voltage variant = $\pm 5\%$ after trimming	1.425	1.5	1.57	V
I_{LDO}	Output Current	$V_{DD} = 2.5\text{ V}$ Regulator input @ $V_{LDO} = 1.5\text{ V}$	—	30	35	mA
C_{LDO}	External Filter Capacitor Value for Internal Core Power Supply	The capacitor value is dependent on the core power current consumption	1	2.2	—	μF

Power Consumption

Table 12. Power Consumption Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
I _{DD}	Supply Current (Run Mode)	V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 80 MHz, f _{HCLK} = 80 MHz, f _{PCLK} = 80 MHz, all peripherals enabled	—	17.76	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 80 MHz, f _{HCLK} = 80 MHz, f _{PCLK} = 80 MHz, all peripherals disabled	—	8.33	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 60 MHz, f _{HCLK} = 60 MHz, f _{PCLK} = 60 MHz, all peripherals enabled	—	14.38	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 60 MHz, f _{HCLK} = 60 MHz, f _{PCLK} = 60 MHz, all peripherals disabled	—	7.2	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 20 MHz, f _{HCLK} = 20 MHz, f _{PCLK} = 20 MHz, all peripherals enabled	—	5.76	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 20 MHz, f _{HCLK} = 20 MHz, f _{PCLK} = 20 MHz, all peripherals disabled	—	3.3	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL off, f _{HCLK} = 8 MHz, f _{PCLK} = 8 MHz, all peripherals enabled	—	2.32	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL off, f _{HCLK} = 8 MHz, f _{PCLK} = 8 MHz, all peripherals disabled	—	1.34	—	mA
		V _{DD} = 5.0 V, HSI off, PLL off, LSI on, f _{HCLK} = 32 kHz, f _{PCLK} = 32 kHz, all peripherals enabled	—	36.7	—	μA
		V _{DD} = 5.0 V, HSI off, PLL off, LSI on, f _{HCLK} = 32 kHz, f _{PCLK} = 32 kHz, all peripherals disabled	—	32.6	—	μA
	Supply Current (Sleep Mode)	V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 80 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 80 MHz, all peripherals enabled	—	11.52	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 80 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 80 MHz, all peripherals disabled	—	1.03	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 60 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 60 MHz, all peripherals enabled	—	8.78	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 60 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 60 MHz, all peripherals disabled	—	0.85	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 20 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 20 MHz, all peripherals enabled	—	3.32	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL = 20 MHz, f _{HCLK} = 0 MHz, f _{PCLK} = 20 MHz, all peripherals disabled	—	0.58	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL off, f _{HCLK} = 0 MHz, f _{PCLK} = 8 MHz, all peripherals enabled	—	1.34	—	mA
		V _{DD} = 5.0 V, HSI = 8 MHz, PLL off, f _{HCLK} = 0 MHz, f _{PCLK} = 8 MHz, all peripherals disabled	—	0.25	—	mA
	Supply Current (Deep-Sleep Mode)	V _{DD} = 5.0 V, HSE/HIS/PLL off, LDO in low power mode, LSI on, LSTM on	—	28	—	μA

Note:1. HSE means high speed external oscillator. HSI means 8 MHz high speed internal oscillator.

2. LSI means 32 kHz low speed internal oscillator.

3. Code = while (1) {208 NOP} executed in Flash.

Reset and Supply Monitor Characteristics

Table 13. V_{DD} Power Reset Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{POR}	Power On Reset Threshold (Rising Voltage on V _{DD})	T _A = -40 °C ~ 105 °C	2.22	2.35	2.48	V
V _{PDR}	Power Down Reset Threshold (Falling Voltage on V _{DD})		2.12	2.2	2.33	V
V _{PORHYST}	POR Hysteresis	—	—	150	—	mV
t _{POR}	Reset Delay Time	V _{DD} = 5.0 V	—	0.1	0.2	ms

Note:1. Data based on characterization results only, not tested in production.

2. If the LDO is turned on, the V_{DD} POR has to be in the de-assertion condition. When the V_{DD} POR is in the assertion state then the LDO will be turned off.

Table 14. LVD / BOD Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit	
V _{BOD}	Voltage of Brown-Out Detection	After factory-trimmed, V _{DD} falling edge	2.37	2.45	2.53	V	
V _{LVD}	Voltage of Low Voltage Detection	V _{DD} falling edge	LVDS = 000	2.57	2.65	2.73	V
			LVDS = 001	2.77	2.85	2.93	V
			LVDS = 010	2.97	3.05	3.13	V
			LVDS = 011	3.17	3.25	3.33	V
			LVDS = 100	3.37	3.45	3.53	V
			LVDS = 101	4.15	4.25	4.35	V
			LVDS = 110	4.35	4.45	4.55	V
			LVDS = 111	4.55	4.65	4.75	V
V _{LVDHTST}	LVD Hysteresis	V _{DD} = 5.0 V	—	—	100	mV	
t _{SULVD}	LVD Setup Time	V _{DD} = 5.0 V	—	—	5	μs	
t _{AILVD}	LVD Active Delay Time	V _{DD} = 5.0 V	—	—	200	μs	
I _{DDLVD}	Operation Current ⁽²⁾	V _{DD} = 5.0 V	—	—	10	μA	

Note:1. Data based on characterization results only, not tested in production.

2. Bandgap current is not included.

3. LVDS field is in the PWRCU LVDCSR register.

External Clock Characteristics

Table 15. High Speed External Clock (HSE) Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{DD}	Operation Voltage Range	—	2.5	—	5.5	V
f _{HSE}	HSE Frequency	—	4	—	16	MHz
C _L	Load Capacitance	V _{DD} = 5.0 V, R _{ESR} = 100 Ω @ 16 MHz	—	—	12	pF
R _{FHSE}	Internal Feedback Resistor between XTALIN and XTALOUT Pins	V _{DD} = 5.0 V	—	0.5	—	MΩ

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
R _{ESR}	Equivalent Series Resistance	V _{DD} = 5.0 V, C _L = 12 pF @ 16 MHz, HSEGAIN = 0	—	—	110	Ω
		V _{DD} = 2.5 V, C _L = 12 pF @ 16 MHz, HSEGAIN = 1				
D _{HSE}	HSE Oscillator Duty Cycle	—	40	—	60	%
I _{DDHSE}	HSE Oscillator Current Consumption	V _{DD} = 5.0 V, R _{ESR} = 25 Ω, C _L = 12 pF @ 16 MHz, HSEGAIN = 1	—	3	—	mA
I _{PWDHSE}	HSE Oscillator Power Down Current	V _{DD} = 5.0 V	—	—	0.01	μA
t _{SUHSE}	HSE Oscillator Startup Time	V _{DD} = 5.0 V	—	—	4	ms

Note: The following guidelines are recommended to increase the stability of the crystal circuit of the HSE clock in the PCB layout.

1. The crystal oscillator should be located as close as possible to the MCU to keep the trace length as short as possible to reduce any parasitic capacitance.
2. Shield lines in the vicinity of the crystal by using a ground plane to isolate signals and reduce noise.
3. Keep any high frequency signal lines away from the crystal area to prevent the crosstalk adverse effects.

Internal Clock Characteristics

Table 16. High Speed Internal Clock (HSI) Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{DD}	Operation Voltage Range	T _A = -40 °C ~ 105 °C	2.5	—	5.5	V
f _{HSI}	HSI Frequency	V _{DD} = 5.0 V @ 25 °C	—	8	—	MHz
ACC _{HSI}	Factory Calibrated HSI Oscillator Frequency Accuracy	V _{DD} = 5.0 V, T _A = 25 °C	-2	—	2	%
		V _{DD} = 2.5 V ~ 5.5 V T _A = -20 °C ~ 85 °C	-3	—	3	%
		V _{DD} = 2.5 V ~ 5.5 V T _A = -40 °C ~ -20 °C or 85 °C ~ 105 °C	-3.5	—	3.5	%
Duty	HSI Oscillator Duty Cycle	f _{HSI} = 8 MHz	35	—	65	%
I _{DDHSI}	HSI Oscillator Oscillator Supply Current	f _{HSI} = 8 MHz	—	300	500	μA
	HSI Oscillator Power Down Current		—	—	0.05	μA
t _{SUHSI}	HSI Oscillator Startup Time	f _{HSI} = 8 MHz	—	—	10	μs

Table 17. Low Speed Internal Clock (LSI) Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{DD}	Operation Voltage Range	—	2.5	—	5.5	V
f _{LSI}	LSI Frequency	V _{DD} = 5.0 V, T _A = -40 °C ~ 105 °C	21	32	43	kHz
ACC _{LSI}	LSI Frequency Accuracy	After factory-trimmed, V _{DD} = 5.0 V	-10	—	+10	%
I _{DDL}	LSI Oscillator Operating Current	V _{DD} = 5.0 V	—	0.4	0.8	μA
t _{SULSI}	LSI Oscillator Startup Time	V _{DD} = 5.0 V	—	—	100	μs

System PLL Characteristics

Table 18. System PLL Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
f _{PLLIN}	System PLL Input Clock	—	4	—	16	MHz
f _{CK_PLL}	System PLL Output Clock	—	16	—	80	MHz
t _{LOCK}	System PLL Lock Time	—	—	200	—	μs

Memory Characteristics

Table 19. Flash Memory Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
N _{ENDU}	Number of Guaranteed Program/Erase Cycles before failure (Endurance)	T _A = -40 °C ~ 105 °C	20	—	—	K cycles
t _{RET}	Data Retention Time	T _A = -40 °C ~ 105 °C	10	—	—	Years
t _{PROG}	Word Programming Time	T _A = -40 °C ~ 105 °C	20	—	—	μs
t _{ERASE}	Page Erase Time	T _A = -40 °C ~ 105 °C	2	—	—	ms
t _{MERASE}	Mass Erase Time	T _A = -40 °C ~ 105 °C	10	—	—	ms

I/O Port Characteristics

Table 20. I/O Port Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit	
I _{IL}	Low Level Input Current	5.0 V I/O	V _I = V _{SS} , On-chip pull-up resistor disabled	—	—	3	μA
		Reset pin		—	—	3	
I _{IH}	High Level Input Current	5.0 V I/O	V _I = V _{DD} , On-chip pull-down resistor disabled	—	—	3	μA
		Reset pin		—	—	3	
V _{IL}	Low Level Input Voltage	5.0 V I/O	-0.5	—	V _{DD} × 0.35	V	
		Reset pin	-0.5	—	V _{DD} × 0.35		
V _{IH}	High Level Input Voltage	5.0 V I/O	V _{DD} × 0.65	—	V _{DD} + 0.5	V	
		Reset pin	V _{DD} × 0.65	—	V _{DD} + 0.5		
V _{HYS}	Schmitt Trigger Input Voltage Hysteresis	5.0 V I/O	—	0.12 × V _{DD}	—	mV	
		Reset pin	—	0.12 × V _{DD}	—		
I _{OL}	Low Level Output Current (GPIO Sink Current)	5.0 V I/O 4 mA drive, V _{OL} = 0.4 V	4	—	—	mA	
		5.0 V I/O 8 mA drive, V _{OL} = 0.4 V	8	—	—	mA	
		5.0 V I/O 12 mA drive, V _{OL} = 0.4 V	12	—	—	mA	
		5.0 V I/O 16 mA drive, V _{OL} = 0.4 V	16	—	—	mA	
		V _{DD} Domain I/O drive @ V _{DD} = 5.0 V, V _{OL} = 0.4 V, PB9, PB10	4	—	—	mA	

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
I _{OH}	High Level Output Current (GPIO Source Current)	5.0 V I/O 4 mA drive, V _{OH} = V _{DD} - 0.4 V	4	—	—	mA
		5.0 V I/O 8 mA drive, V _{OH} = V _{DD} - 0.4 V	8	—	—	mA
		5.0 V I/O 12 mA drive, V _{OH} = V _{DD} - 0.4 V	12	—	—	mA
		5.0 V I/O 16 mA drive, V _{OH} = V _{DD} - 0.4 V	16	—	—	mA
		V _{DD} Domain I/O drive @ V _{DD} = 5.0 V, V _{OH} = V _{DD} - 0.4 V, PB9, PB10	—	—	2	mA
V _{OL}	Low Level Output Voltage	5.0 V 4 mA drive I/O, I _{OL} = 4 mA	—	—	0.4	V
		5.0 V 8 mA drive I/O, I _{OL} = 8 mA	—	—	0.4	
		5.0 V 12 mA drive I/O, I _{OL} = 12 mA	—	—	0.4	
		5.0 V 16 mA drive I/O, I _{OL} = 16 mA	—	—	0.4	
V _{OH}	High Level Output Voltage	5.0 V 4 mA drive I/O, I _{OH} = 4 mA	V _{DD} - 0.4	—	—	V
		5.0 V 8 mA drive I/O, I _{OH} = 8 mA	V _{DD} - 0.4	—	—	
		5.0 V 12 mA drive I/O, I _{OH} = 12 mA	V _{DD} - 0.4	—	—	
		5.0 V 16 mA drive I/O, I _{OH} = 16 mA	V _{DD} - 0.4	—	—	
R _{PU}	Internal Pull-up Resistor	5.0 V I/O, V _{DD} = 5.0 V	—	60	—	kΩ
R _{PD}	Internal Pull-down Resistor	5.0 V I/O, V _{DD} = 5.0 V	—	60	—	kΩ

ADC Characteristics

Table 21. ADC Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{DDA}	A/D Converter Operating Voltage	—	2.5	5.0	5.5	V
V _{ADCIN}	A/D Converter Input Voltage Range	—	0	—	V _{REF+}	V
V _{REF+}	A/D Converter Reference Voltage	—	—	V _{DDA}	V _{DDA}	V
I _{ADC}	Current Consumption	V _{DDA} = 5.0 V	—	1.4	1.5	mA
I _{ADC_DN}	Power Down Current Consumption	V _{DDA} = 5.0 V	—	—	0.1	μA
f _{ADC}	A/D Converter Clock Frequency	—	0.7	—	40	MHz
f _s	Sampling Rate	—	0.05	—	2.5	Msp/s
t _{DL}	Data Latency	—	—	12.5	—	1/f _{ADC} Cycles
t _{S&H}	Sampling & Hold Time	—	—	3.5	—	1/f _{ADC} Cycles
t _{ADCCONV}	A/D Converter Conversion Time	ADST[7:0] = 2	—	16	—	1/f _{ADC} Cycles
R _I	Input Sampling Switch Resistance	—	—	—	1	kΩ
C _I	Input Sampling Capacitance	No pin/pad capacitance included	—	16	—	pF
t _{SU}	Start Up Time	—	—	—	1	μs
N	Resolution	—	—	12	—	bits
INL	Integral Non-linearity Error	f _s = 750 ksps, V _{DDA} = 5.0 V	—	—	±2	LSB
DNL	Differential Non-linearity Error	f _s = 750 ksps, V _{DDA} = 5.0 V	—	—	±1	LSB
E _O	Offset Error	—	—	—	±10	LSB
E _G	Gain Error	—	—	—	±10	LSB

Note: 1. Data based on characterization results only, not tested in production.

2. The figure below shows the equivalent circuit of the A/D Converter Sample-and-Hold input stage where C_i is the storage capacitor, R_i is the resistance of the sampling switch and R_s is the output impedance of the

signal source V_s . Normally the sampling phase duration is approximately, $3.5/f_{ADC}$. The capacitance, C_i , must be charged within this time frame and it must be ensured that the voltage at its terminals becomes sufficiently close to V_s for accuracy. To guarantee this, R_s is not allowed to have an arbitrarily large value.

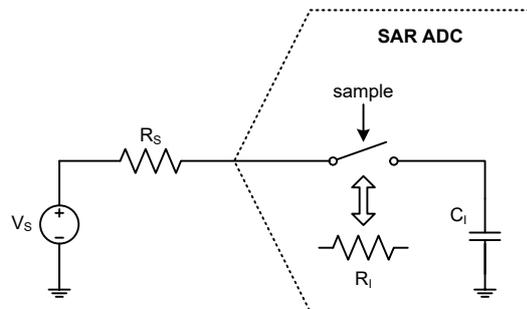


Figure 13. ADC Sampling Network Model

The worst case occurs when the extremities of the input range (0 V and V_{REF}) are sampled consecutively. In this situation a sampling error below 1/4 LSB is ensured by using the following equation:

$$R_s < \frac{3.5}{f_{ADC} C_i \ln(2^{N+2})} - R_i$$

Where f_{ADC} is the ADC clock frequency and N is the ADC resolution ($N = 12$ in this case). A safe margin should be considered due to the pin/pad parasitic capacitances, which are not accounted for in this simple model.

If, in a system where the A/D Converter is used, there are no rail-to-rail input voltage variations between consecutive sampling phases, R_s may be larger than the value indicated by the equation above.

Comparator Characteristics

Table 22. Comparator Characteristics

$T_A = 25^\circ\text{C}$, unless otherwise specified.

Symbol	Parameter	Conditions	Min	Typ	Max	Unit	
V_{DDA}	Operating Voltage	Comparator mode	2.5	5.0	5.5	V	
V_{IN}	Input Common Mode Voltage Range	CP or CN	V_{SSA}	—	V_{DDA}	V	
V_{IOS}	Input Offset Voltage (Note)	—	-15	—	15	mV	
V_{HYS}	Input Hysteresis $V_{DDA} = 5.0\text{ V}$	No hysteresis, CMPHM[1:0] = 00	—	0	—	mV	
		Low hysteresis, CMPHM[1:0] = 01	—	30	—	mV	
		Middle hysteresis, CMPHM[1:0] = 10	—	60	—	mV	
		High hysteresis, CMPHM[1:0] = 11	—	100	—	mV	
t_{RT}	Response Time Input Overdrive = $\pm 100\text{ mV}$	High Speed Mode	$V_{DDA} \geq 3.6\text{ V}$	—	50	100	ns
			$V_{DDA} < 3.6\text{ V}$	—	100	250	
		Low Speed Mode	—	2	5	μs	
I_{CMP}	Current Consumption $V_{DDA} = 5.0\text{ V}$	High Speed Mode	—	180	350	μA	
		Low Speed Mode	—	50	90	μA	
t_{CMPST}	Comparator Startup Time	Comparator enabled to output valid	—	—	50	μs	

Symbol	Parameter	Conditions	Min	Typ	Max	Unit
I _{COMP_DN}	Power Down Supply Current	CMPEN = 0 CVREN = 0 CVROE = 0	—	—	0.1	μA
Comparator Voltage Reference (CVR)						
V _{CVR}	Output Voltage Range	—	V _{SSA}	—	V _{DDA}	V
N _{Bits}	CVR Scaler Resolution	—	—	8	—	bits
t _{CVRST}	Setting Time	CVR Scaler Setting Time from CVRVAL = "00000000" to "11111111"	—	—	100	μs
I _{CVR}	Current Consumption V _{DDA} = 5.0 V	CVREN = 1, CVROE = 0	—	100	120	μA
		CVREN = 1, CVROE = 1	—	125	150	μA

Note: Data based on characterization results only, not tested in production.

Programmable Gain Amplifier Characteristics

Table 23. Programmable Gain Amplifier Characteristics

T_A = 25 °C, unless otherwise specified.

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
V _{DDA}	Operating Voltage	PGA mode	3.0	5.0	5.5	V
I _{PGA_DN}	Power Down Current	—	—	—	0.1	μA
I _{PGA}	Operating Current	V _{DD} = 5V	—	800	—	μA
V _{OS}	Input Offset Voltage	Without calibration (OnOF[4:0] = b10000) V _{IN} = 0 ~ V _{CM_max} /2	-15	—	+15	mV
		With calibration V _{IN} = 0 ~ V _{CM_max} /2	-2	—	+2	
G _E	DC Gain Error	Gain = 6/8/12/16/24/32 (PGAnPGA = 1, PGAnMVDDEN[1:0] = b0X, PGAnNUG = 0 and PGAnREF = 0), V _{OUT} = 0.2 ~ (V _{DD} - 0.2 V)	—	—	2	%
		Gain = 5/7/11/15/23/31 (PGAnPGA = 1, PGAnDACEN[1:0] = b10, PGAnNUG = 0 and PGAnREF = 0) V _{OUT} = 0.2 ~ (V _{DD} - 0.2 V)	—	—	—	
V _{OR}	Maximum Output Voltage Range	—	V _{SS} + 0.2	—	V _{DD} - 0.2	V
I _{OS}	Input Offset Current	V _{IN} = 1/2 V _{CM}	—	1	10	nA
PSRR	Power Supply Rejection Ratio	—	—	60	—	dB
CMRR	Common Mode Rejection Ratio	V _{CM} = 0 ~ (V _{DD} - 1.4)	—	60	—	dB
SR	Slew Rate+, Slew Rate-	R _L = 100 kΩ, C _L = 50 pF	—	6	—	V/μs
GBW	Gain Band Width	R _L = 100 kΩ, C _L = 50 pF	—	6	—	MHz
A _{OL}	Open Loop Gain	R _L = 100 kΩ, C _L = 50 pF	60	80	—	dB
PM	Phase Margin	R _L = 100 kΩ, C _L = 50 pF	50	60	—	Deg
V _{CM}	Common Mode Voltage Range	—	V _{SS}	—	V _{DD} - 1.4	V

GPTM / MCTM / SCTM Characteristics

Table 24. GPTM / MCTM / SCTM Characteristics

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
f _{TM}	Timer Clock Source for GPTM, MCTM, SCTM	—	—	—	f _{PCLK}	MHz
t _{RES}	Timer Resolution Time	—	1	—	—	1/f _{TM}
f _{EXT}	External Signal Frequency on Channel 0 ~ 3	—	—	—	1/2	f _{TM}
RES	Timer Resolution	—	—	—	16	bits

Gate-Driver Characteristics

V_{CC} = V_M = 24 V, C₁ = 4.7 μF, C₂ = 2.2 μF and T_A = 25 °C, unless otherwise specified

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
Power Supply/Regulators						
V _{CC}	Supply Voltage	—	6.0	—	32.0	V
I _{CC}	Supply Standby Current	LDOEN = '1', V _{REG} with no load	—	5	10	μA
I _{CC(SLP)}	Supply Sleep Current	LDOEN = '0'	—	—	2	μA
V _{REG}	V _{REG} Output Voltage	I _{LOAD} = 1 mA	4.9	5.0	5.1	V
Gate-Driver (GHx, GLx)						
I _{DRVp}	High-Side and Low-Side Gate Peak Source Current	C _{LOAD} = 200 nF	—	350	—	mA
I _{DRVn}	High-Side and Low-Side Gate Peak Sink Current	C _{LOAD} = 200 nF	—	500	—	mA
t _{DEAD}	Dead Time	—	—	120	200	ns
t _{DEAD_MIS}	Dead Time Mismatch	Dead time difference between rising and falling edges	—	50	—	ns
t _{PD}	Propagation Delay	INHx to GHx and INLx to GLx transition (No connected capacitor with GHx/GLx)	—	160	250	ns
t _{PD_MIS}	High-Side/Low-Side Propagation delay mismatch	Propagation delay difference between different phase or different side.	—	100	—	ns
R _{OFF1}	Low-Side Gate Hold-off Resistor	GLx to PGND	—	150	—	kΩ
R _{OFF2}	High-Side Gate Hold-off Resistor	VM to GHx	—	150	—	kΩ
Protections						
V _{CC_UVLO+}	V _{CC} Turn On Level	V _{CC} rises	—	—	5.5	V
V _{CC_UVLO-}	V _{CC} Turn Off Level	V _{CC} falls	3	—	—	V
V _{REG_UVLO+}	V _{REG} Turn On Level	V _{REG} rises	—	—	4.5	V
V _{REG_UVLO-}	V _{REG} Turn Off Level	V _{REG} falls	3.0	—	—	V
External Wake-up						
t _{WKDB1}	Debounce Time between WKI Input being Triggered to LDO Wake-up	—	—	1.2	—	ms
t _{WKDB2}	Debounce Time between WKI Input being Triggered and WKO output	—	—	10	—	μs
Voltage Divider						
V _{DIV}	Power Supply Voltage Divider VDC Output Voltage	LDOEN = '1'	2.85	3.00	3.15	V
R _{DIV}	Power Supply Voltage Divider Resistor	LDOEN = '0' disable voltage divider	—	8	—	kΩ

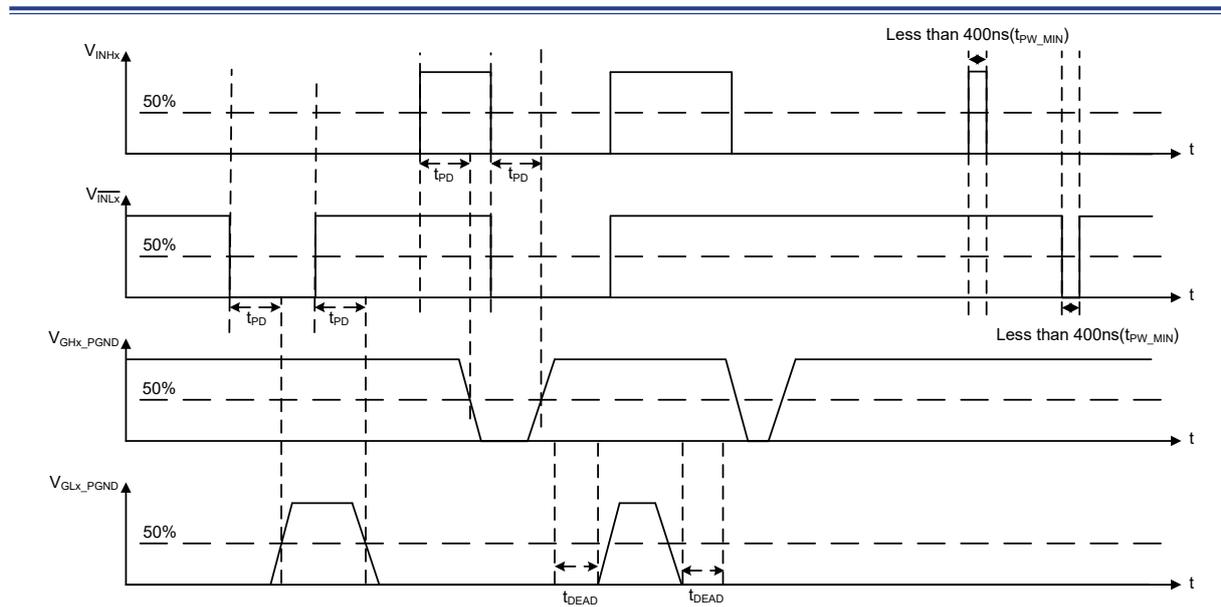


Figure 14. Gate-Driver Timing Diagram

I²C Characteristics

Table 25. I²C Characteristics

Symbol	Parameter	Standard Mode		Fast Mode		Fast Plus Mode		Unit
		Min.	Max.	Min.	Max.	Min.	Max.	
f _{SCL}	SCL Clock Frequency	—	100	—	400	—	1000	kHz
t _{SCL(H)}	SCL Clock High Time	4.5	—	1.125	—	0.45	—	μs
t _{SCL(L)}	SCL Clock Low Time	4.5	—	1.125	—	0.45	—	μs
t _{FALL}	SCL and SDA Fall Time	—	1.3	—	0.34	—	0.135	μs
t _{RISE}	SCL and SDA Rise Time	—	1.3	—	0.34	—	0.135	μs
t _{SU(SDA)}	SDA Data Setup Time	500	—	125	—	50	—	ns
t _{H(SDA)}	SDA Data Hold Time ⁽⁵⁾	0	—	0	—	0	—	ns
	SDA Data Hold Time ⁽⁶⁾	—	1.6	—	0.475	—	0.25	μs
t _{VD(SDA)}	SDA Data Valid Time	—	1.6	—	0.475	—	0.25	μs
t _{SU(STA)}	START Condition Setup Time	500	—	125	—	50	—	ns
t _{H(STA)}	START Condition Hold Time	0	—	0	—	0	—	ns
t _{SU(STO)}	STOP Condition Setup Time	500	—	125	—	50	—	ns

Note: 1. Data based on characterization results only, not tested in production.

2. To achieve 100 kHz standard mode, the peripheral clock frequency must be higher than 2 MHz.

3. To achieve 400 kHz fast mode, the peripheral clock frequency must be higher than 8 MHz.

4. To achieve 1 MHz fast plus mode, the peripheral clock frequency must be higher than 20 MHz.

5. The above characteristic parameters of the I²C bus timing are based on: COMBFILTEREN = 0 and SEQFILTER = 00.

6. The above characteristic parameters of the I²C bus timing are based on: COMBFILTEREN = 1 and SEQFILTER = 00.

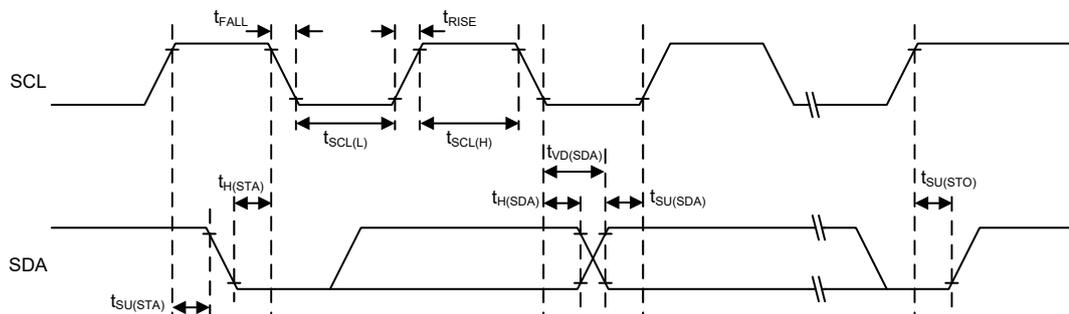


Figure 15. I²C Timing Diagram

SPI Characteristics

Table 26. SPI Characteristics

Symbol	Parameter	Conditions	Min.	Typ.	Max.	Unit
SPI Master Mode						
f_{SCK}	SPI Master Output SCK Clock Frequency	Master mode SPI peripheral clock frequency f_{PCLK}	—	—	$f_{PCLK}/2$	MHz
$t_{SCK(H)}$ $t_{SCK(L)}$	SCK Clock High and Low Time	—	$t_{SCK}/2 - 2$	—	$t_{SCK}/2 + 1$	ns
$t_{V(MO)}$	Data Output Valid Time	—	—	—	5	ns
$t_{H(MO)}$	Data Output Hold Time	—	2	—	—	ns
$t_{SU(MI)}$	Data Input Setup Time	—	5	—	—	ns
$t_{H(MI)}$	Data Input Hold Time	—	5	—	—	ns
SPI Slave Mode						
f_{SCK}	SPI Slave Input SCK Clock Frequency	Slave mode SPI peripheral clock frequency f_{PCLK}	—	—	$f_{PCLK}/3$	MHz
$Duty_{SCK}$	SPI Slave Input SCK Clock Duty Cycle	—	30	—	70	%
$t_{SU(SEL)}$	SEL Enable Setup Time	—	$3 t_{PCLK}$	—	—	ns
$t_{H(SEL)}$	SEL Enable Hold Time	—	$2 t_{PCLK}$	—	—	ns
$t_{A(SO)}$	Data Output Access Time	—	—	—	$3 t_{PCLK}$	ns
$t_{DIS(SO)}$	Data Output Disable Time	—	—	—	10	ns
$t_{V(SO)}$	Data Output Valid Time	—	—	—	25	ns
$t_{H(SO)}$	Data Output Hold Time	—	15	—	—	ns
$t_{SU(SI)}$	Data Input Setup Time	—	5	—	—	ns
$t_{H(SI)}$	Data Input Hold Time	—	4	—	—	ns

Note: 1. f_{SCK} is SPI output/input clock frequency and $t_{SCK} = 1/f_{SCK}$.
2. f_{PCLK} is SPI peripheral clock frequency and $t_{PCLK} = 1/f_{PCLK}$.

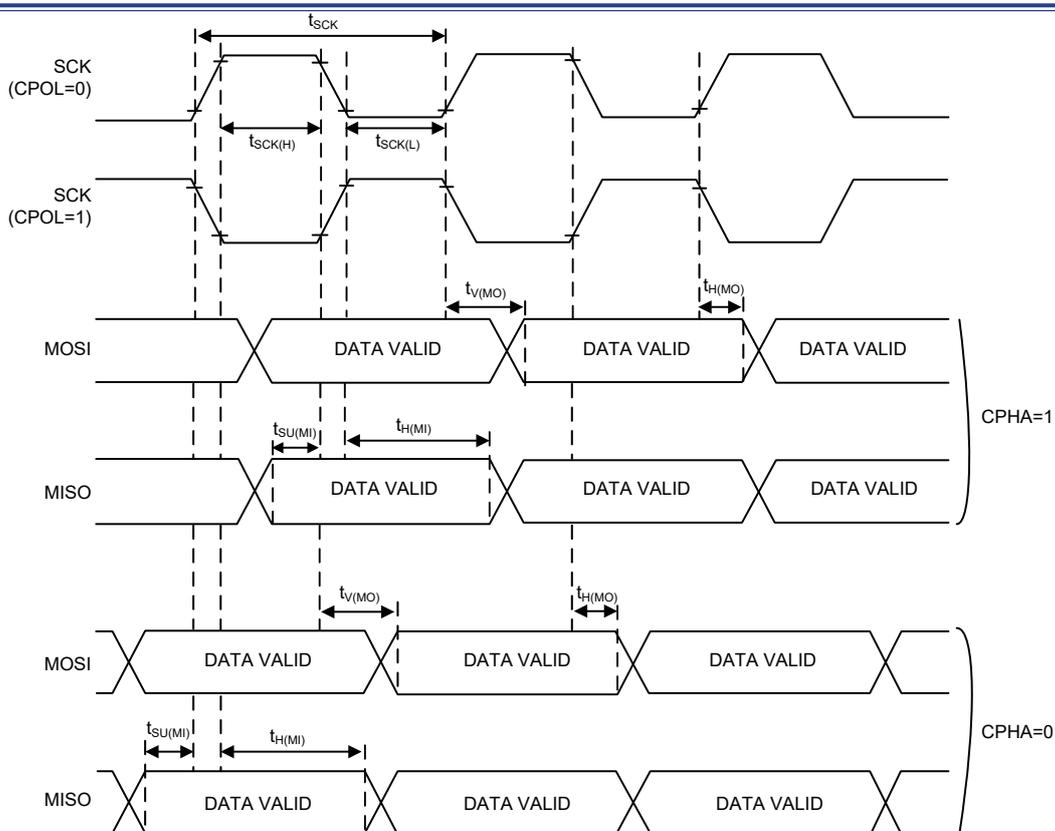


Figure 16. SPI Timing Diagram – SPI Master Mode

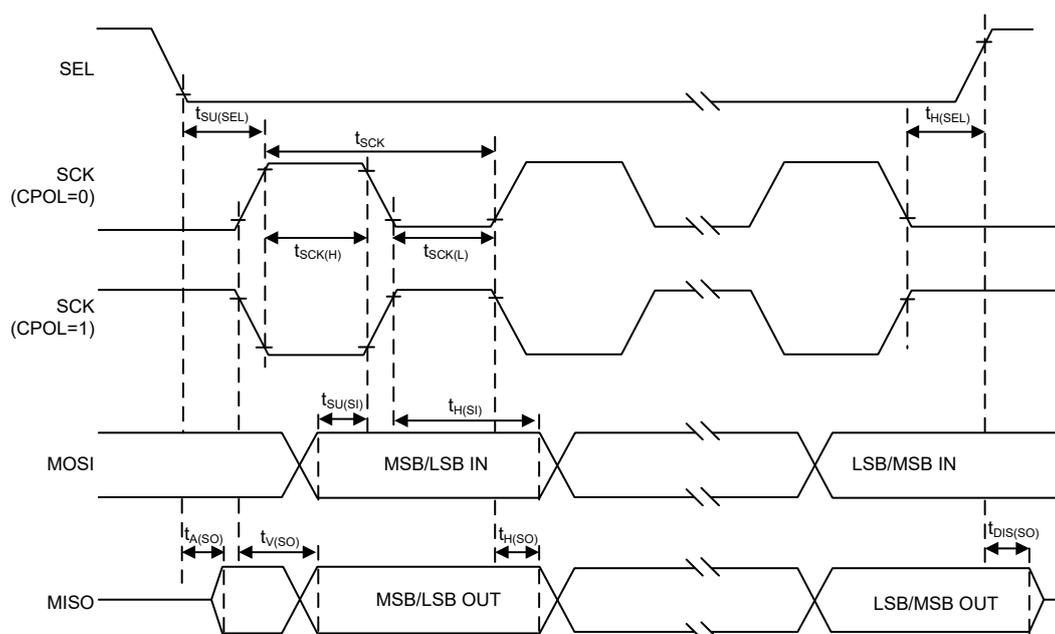


Figure 17. SPI Timing Diagram – SPI Slave Mode with CPHA = 1

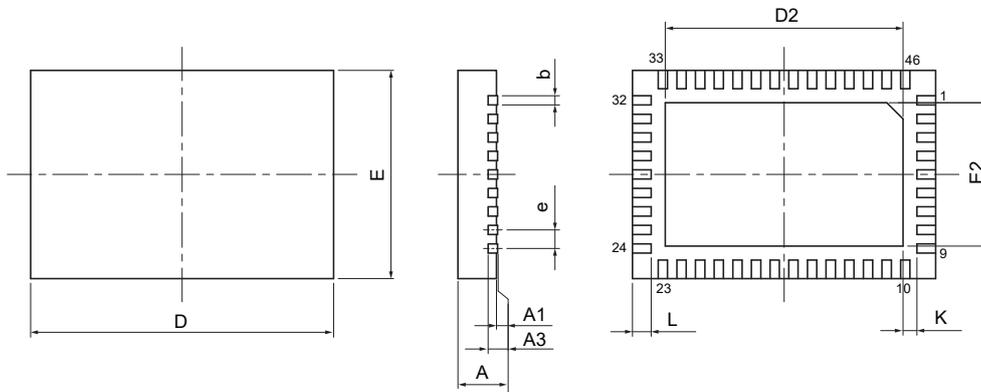
8 Package Information

Note that the package information provided here is for consultation purposes only. As this information may be updated at regular intervals users are reminded to consult the [Holtek website](#) for the latest version of the [Package/Carton Information](#).

Additional supplementary information with regard to packaging is listed below. Click on the relevant section to be transferred to the relevant website page.

- Package Information (include Outline Dimensions, Product Tape and Reel Specifications)
- The Operation Instruction of Packing Materials
- Carton information

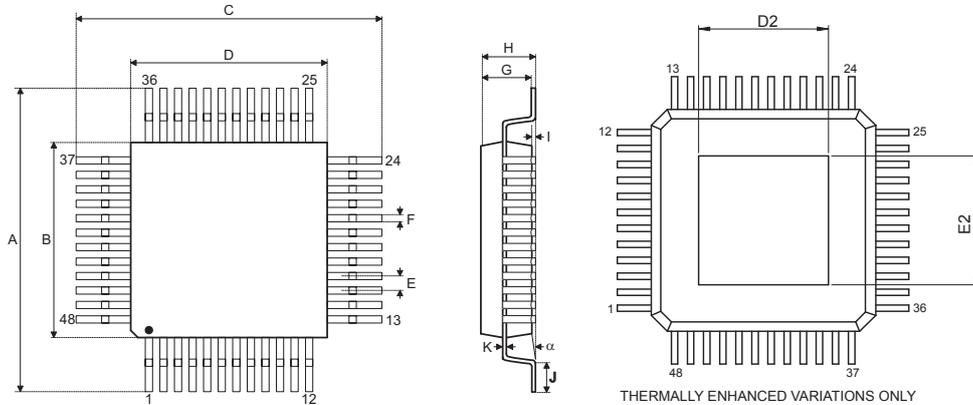
SAW Type 46-pin QFN (6.5 mm × 4.5 mm × 0.75 mm) Outline Dimensions



Symbol	Dimensions in inch		
	Min.	Nom.	Max.
A	0.028	0.030	0.031
A1	0.000	0.001	0.002
A3	0.008 REF		
b	0.006	0.008	0.010
D	0.256 BSC		
E	0.177 BSC		
e	0.016 BSC		
D2	0.197	—	0.205
E2	0.118	—	0.126
L	0.014	0.016	0.018
K	0.008	—	—

Symbol	Dimensions in mm		
	Min.	Nom.	Max.
A	0.70	0.75	0.80
A1	0.00	0.02	0.05
A3	0.203 REF		
b	0.15	0.20	0.25
D	6.50 BSC		
E	4.50 BSC		
e	0.40 BSC		
D2	5.00	—	5.20
E2	3.00	—	3.20
L	0.35	0.40	0.45
K	0.20	—	—

48-pin LQFP-EP (7 mm × 7 mm) Outline Dimensions



Symbol	Dimensions in inch		
	Min.	Nom.	Max.
A		0.354 BSC	
B		0.276 BSC	
C		0.354 BSC	
D		0.276 BSC	
E		0.020 BSC	
D2	0.170	—	0.211
E2	0.170	—	0.211
F	0.007	0.009	0.011
G	0.053	0.055	0.057
H	—	—	0.063
I	0.002	—	0.006
J	0.018	0.024	0.030
K	0.004	—	0.008
α	0°	—	7°

Symbol	Dimensions in mm		
	Min.	Nom.	Max.
A		9.00 BSC	
B		7.00 BSC	
C		9.00 BSC	
D		7.00 BSC	
E		0.50 BSC	
D2	4.31	—	5.36
E2	4.31	—	5.36
F	0.17	0.22	0.27
G	1.35	1.40	1.45
H	—	—	1.60
I	0.05	—	0.15
J	0.45	0.60	0.75
K	0.09	—	0.20
α	0°	—	7°



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