
PAW3602DH CMOS LASER MOUSE SENSOR

General Description

PAW3602DH is a CMOS laser mouse sensor with DSP integration chip that serves as a non-mechanical motion estimation engine for implementing a computer mouse.

Features

- ☐ Single power supply
- ☐ Precise laser motion estimation technology
- ☐ Complete 2-D motion sensor
- ☐ No mechanical parts
- ☐ Accurate motion estimation over most of surfaces
- ☐ High speed motion detection up to 28 inches/sec and acceleration can be up to 20g
- ☐ High resolution up to 1600dpi
- ☐ Power down pin and register setting for low power dissipation
- ☐ Power saving mode during times of no movement
- ☐ Serial Interface for programming and data transfer
- ☐ Low power for wireless application
- ☐ Eye safety protection circuit

Key Specification

Power Supply	4.25V ~ 5.5V (VDD) 3.0V~3.6V (VDDD, VDDA)
System Clock	27 MHz
Speed	28+ inches/sec
Acceleration	20g
Resolution	800/1600dpi
Frame Rate	6600 frames/sec
Operating Current (Sensor + LD)	17 mA @Mouse moving (Normal) 5 mA @Mouse not moving (Sleep) 200 uA @Shutdown mode
Package	Shrunk DIP20

Ordering Information

Order number	I/O	Resolution
PAW3602DH	CMOS output	800/1600 dpi

1. Pin Description

Pin No.	Name	Type	Definition
1	LD_P	PWR	LD control
2	LD_N	PWR	LD control
3	OSCOUT	OUT	Resonator output
4	OSCIN	IN	Resonator input
5	VDDD	PWR	Chip digital power, 3.3V
6	VSSD	GND	Chip digital ground
7	VSSA	GND	Chip analog ground
8	VDD	PWR	Chip power, 5V power supply
9	VDDA	PWR	Chip analog power, 3.3V
10	LDRES	IN	Connect to resistor input
11	YA	I/O	LD BIST mode input / YA quadrature output
12	YB	I/O	LD BIST mode input / YB quadrature output
13	XA	I/O	LD BIST mode input / XA quadrature output
14	XB	OUT	LD BIST mode fail output / XB quadrature output
15	CPI	IN	CPI select pin ➤ Pull-high to VDD: 800 cpi (Default) ➤ Pull-down to GND: 1600 cpi
16	LDTEST	IN	LD test pin ➤ Floating (Chip internal pull-down): Disable LD test mode ➤ Pull-high (3.3V ONLY) : Enable LD test mode
17	NC	-	No connection
18	SCLK	IN	Serial interface clock
19	SDIO	I/O	Serial interface bi-direction data
20	PD	IN	Power down pin, active high

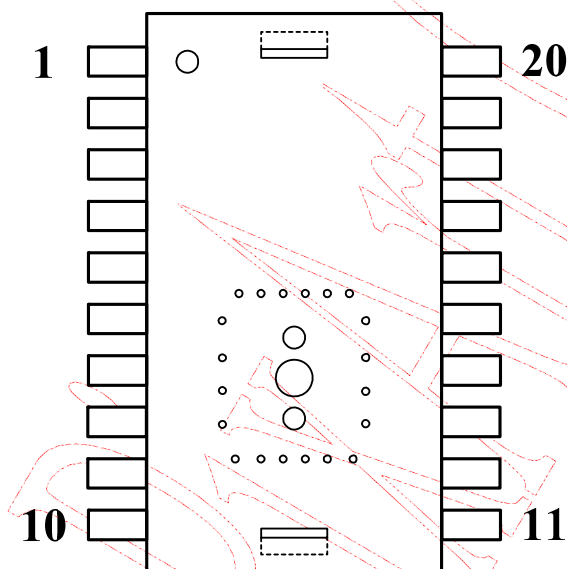


Figure 1. Top View Pinout

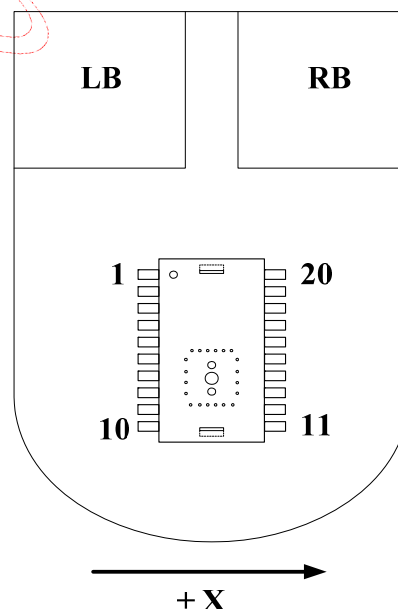


Figure 2. Top View of Mouse

2. Block Diagram and Operation

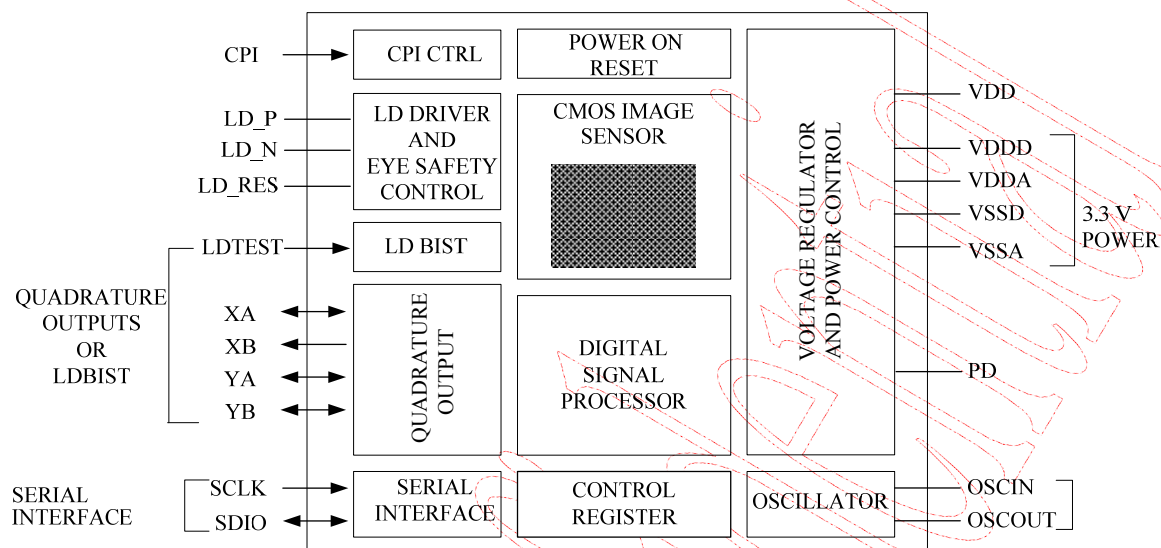


Figure 3. Block Diagram

The PAW3602DH is a high performance CMOS laser mouse sensor with DSP integration chip that serves as a non-mechanical motion estimation engine for implementing a computer mouse. It is based on new laser speckle navigation technology. In the laser mouse, it uses laser diode (LD), specially uses VCSEL (Vertical Cavity Surface Emitting Laser) as light source, where laser is one kind of coherent light. When this light illuminates on the working surface, the surface will reflect and diffuse the incident light and generates speckle pattern. The imaging sensor in the laser mouse chip detects the speckle pattern that generated from the working surface and determines the movement and direction. Since the speckle pattern can be generated on the most of the surface if this surface is not perfect smooth or transparent, the laser mouse can adapt on more surfaces as compared with traditional LED-based optical mouse.

The PAW3602DH has an extra function, eye safety protection circuit. The embedded eye safety protection circuit will detect if LD_P pin is short to power, if LD_N pin is short to ground, or if LD_RES pin is short to ground to be a large LD power. And this will protect users from eye injured for large LD power. This mouse sensor is in a 20-pin optical package. The output format is two-channel quadrature (X and Y direction), which emulates encoder phototransistors. The current X and Y information are also available in registers accessed via a serial port. The word "mouse sensor," instead of PAW3602DH, is used in the document.

3. Registers and Operation

The mouse sensor can be programmed through registers, via the serial port, and DSP configuration and motion data can be read from these registers. All registers not listed are reserved, and should never be written by firmware.

3.1 Registers

Address	Name	R/W	Default	Data Type
0x00	Product_ID	R	0x30	Eight bits [11:4] number with the product identifier
0x01	Product_ID	R	0x3N	Four bits [3:0] number with the product identifier Reserved [3:0] number is reserved for further
0x02	Motion_Status	R	-	Bit field
0x03	Delta_X	R	-	Eight bits 2's complement number
0x04	Delta_Y	R	-	Eight bits 2's complement number
0x05	Operation_Mode	R/W	-	Bit field
0x06	Configuration	R/W	-	Bit field
0x07	Image_Quality	R	-	Bit field

3.2 Register Descriptions

0x00	Product_ID							
Bit	7	6	5	4	3	2	1	0
Field	PID[11:4]							
Usage	The value in this register can't change. It can be used to verify that the serial communications link is OK.							
0x01	Product_ID							
Bit	7	6	5	4	3	2	1	0
Field	PID[3:0]				Reserved [3:0]			
Usage	The value in this register can't change. PID[3:0] can be used to verify that the serial communications link is OK. Reserved[3:0] is a value between 0x0 and 0xF, it can't be used to verify that the serial communication.							

0x02	Motion_Status							
Bit	7	6	5	4	3	2	1	0
Field	Motion	Reserved[3:2]		DYOVF	DXOVF	Reserved[1:0]		RES
Usage	<p>Register 0x02 allows the user to determine if motion has occurred since the last time it was read. If so, then the user should read registers 0x03 and 0x04 to get the accumulated motion. It also tells if the motion buffers have overflowed since the last reading. The current resolution is also shown.</p> <p>Reading this register freezes the <i>Delta_X</i> and <i>Delta_Y</i> register values. Read this register before reading the <i>Delta_X</i> and <i>Delta_Y</i> registers. If <i>Delta_X</i> and <i>Delta_Y</i> are not read before the motion register is read a second time, the data in <i>Delta_X</i> and <i>Delta_Y</i> will be lost.</p>							
Notes	Field Name	Description						
	Motion	Motion since last report or PD 0 = No motion (Default) 1 = Motion occurred, data ready for reading in Delta_X and Delta_Y registers						
	Reserved[3:2]	Reserved for future						
	DYOVF	Motion Delta Y overflow, ΔY buffer has overflowed since last report 0 = No overflow (Default) 1 = Overflow has occurred						
	DXOVF	Motion Delta X overflow, ΔX buffer has overflowed since last report 0 = No overflow (Default) 1 = Overflow has occurred						
	Reserved[1:0]	Reserved for future						
	RES	Resolution in counts per inch 0 = 1600 1 = 800						
0x03	Delta_X							
Bit	7	6	5	4	3	2	1	0
Field	X7	X6	X5	X4	X3	X2	X1	X0
Usage	X movement is counts since last report. Absolute value is determined by resolution. Reading clears the register. Report range -128~+127.							
0x04	Delta_Y							
Bit	7	6	5	4	3	2	1	0
Field	Y7	Y6	Y5	Y4	Y3	Y2	Y1	Y0
Usage	Y movement is counts since last report. Absolute value is determined by resolution. Reading clears the register. Report range -128~+127.							

0x05	Operation_Mode							
Bit	7	6	5	4	3	2	1	0
Field	LDsht_enh	XY_enh	Reserved	Slp_enh	Slp2au	Slp2mu	Slp1mu	Wakeup
Usage	<p>Register 0x05 allows the user to change the operation of the sensor. Shown below are the bits, their default values, and optional values.</p> <p>Operation_Mode[4:0] "0xxxx"=Disable sleep mode "10xxx"=Enable sleep mode¹ "11xxx"=Enable sleep mode² "1x100"=Force enter sleep2³ "1x010"=Force enter sleep1³ "1x001"=Force wakeup from sleep mode³</p> <p>Notes:</p> <ol style="list-style-type: none"> 1. Enable sleep mode, but disable automatic entering sleep2 mode, that is, only 2 modes will be used, normal mode and sleep1 mode. After 0.45 sec not moving during normal mode, the chip will enter sleep1 mode, and keep on sleep1 mode until moving is detected or wakeup is asserted. 2. Enable sleep mode full function, that is 3 modes will be used, normal mode, sleep1 mode and sleep2 mode. After 0.45 sec not moving during normal mode, chip will enter sleep1 mode, and keep on sleep1 mode until moving is detected or wakeup is asserted. And after 27.3 sec not moving during sleep1 mode, the chip will enter sleep2 mode, and keep on sleep2 mode until detect moving or force wakeup to normal mode. 3. Only one of these three bits slp2mu_enh, slp1mu_enh, and wakeup can be set to 1 at the same time, others have to be set to 0. After a period of time, the bits, which was set to 1, will be reset to 0 by internal signal. 							
Notes	Field Name	Description						
	LDsht_enh	LD shutter enable / disable 0 = Disable 1 = Enable (Default)						
	XY_enh	XY quadrature output enable/disable 0 = Disable 1 = Enable (Default)						
	Reserved	Reserved for future. Must be written to zero						
	Slp_enh	Sleep mode enable/disable 0 = Disable 1 = Enable (Default)						
	Slp2au	Automatic enter sleep2 mode enable/disable 0 = Disable (Default) 1 = Enable						
	Slp2mu	Manual enter sleep2 mode, set "1" will enter sleep2 and this bit will be reset to "0"						
	Slp1mu	Manual enter sleep1 mode, set "1" will enter sleep2 and this bit will be reset to "0"						
	Wakeup	Manual wake up from sleep mode, set "1" will enter wakeup and this bit will be reset to "0"						

0x06	Configuration							
Bit	7	6	5	4	3	2	1	0
Field	Reset	Reserved[3:2]			PD	Reserved[1:0]		RES
Usage	The Configuration register allows the user to change the configuration of the sensor. Shown below are the bits, their default values, and optional values.							
Notes	Field Name	Description						
	Reset	Reset full chip 0 = Normal operation (Default) 1 = Reset the fully chip						
	Reserved[3:2]	Reserved for future. Must be written to “00”						
	PD	Power down mode 0 = Normal operation (Default) 1 = Power down mode						
	Reserved[1:0]	Reserved for future. Must be written to “00”						
	RES	Output resolution setting. In the power-on initial state, the resolution is depend on the CPI IO trap select pin. If MCU write the register, it is depend on the register value. 0 = 1600 1 = 800						
0x07	Image_Quality							
Bit	7	6	5	4	3	2	1	0
Field	Imgqa[7:0]							
Usage	Image Quality is a quality level of the sensor in the current frame. Report range 0~255. The minimum level for normally working is 45.							
Notes	Field Name	Description						
	Imgqa[7:0]	Image quality report range: 0(worst) ~ 255(best).						

4. LD BIST (Built in Self Test) Mode

The mouse sensor can be performed the LD driver error detection function by manufactures to fit the LD power in eye safety rule. LD BIST mode is enabled by pull-high (**3.3V ONLY**) the LDTEST pin. Once LDTEST pin is pulled high, the XA, YB, YA pin are changed to be input pin and become the LD test mode input [XA ,YB ,YA] , XA is MSB and YA is LSB. At this moment, XB is also changed to LD test fail output.

Pin Name	Description
LDTEST	LD Test Mode disable/enable 0 = Disable (Default) 1 = Enable
[XA , YB , YA]	“ 000 “ = Mode 0, Measure LD power, BIST if eye safety error detection function is fail in normal mode “ 001 “ = Mode 1, BIST if LD_P error detection function is fail “ 010 “ = Mode 2, BIST if LD_N error detection function is fail “ 011 “ = Mode 3, BIST if LDRES pin is short to GND
XB	0 = PASS 1 = FAIL

5. Specifications

5.1 Absolute Maximum Ratings

Stresses above those listed under "Absolute Maximum Rating" may cause permanent damage to the device. These are stress ratings only. Functional operation of this device at these or any other conditions above those indicated in the operational sections of this specification is not implied and exposure to absolute maximum rating conditions for extended periods may affect device reliability.

Symbol	Parameter	Min	Max	Unit	Notes
T _{STG}	Storage Temperature	-40	85	°C	
T _A	Operating Temperature	-15	55	°C	
V _{DC}	DC Supply Voltage	-0.5	V _{dd1} + 0.3	V	
		-0.5	V _{dd2} + 0.5	V	
V _{IN}	DC Input Voltage	-0.5	V _{DC}	V	All I/O pin except LDTEST pin (LDTEST high is 3.3V only)
	Lead Solder Temp		260	°C	For 10 seconds, 1.6mm below seating plane.
ESD			2	kV	All pins, human body model MIL 883 Method 3015

5.2 Recommend Operating Condition

Symbol	Parameter	Min.	Typ.	Max.	Unit	Notes
T _A	Operating Temperature	0		40	°C	
V _{dd1}	Power Supply Voltage	3.0	3.3	3.6	V	VDDD, VDDA short
V _{dd2}		4.25	5	5.5		VDD
V _N	Supply Noise			80	mV	Peak to peak within 0 - 80 MHz
Z	Distance from Lens Reference Plane to Surface	2.3	2.4	2.5	mm	
R	Resolution		800	1600	CPI	
SCLK	Serial Port Clock Frequency			10	MHz	
F _{CLK}	Clock Frequency		27		MHz	
FR	Frame Rate		6600		frames/s	
S	Speed		28		inches/s	

5.3 AC Operating Condition

Electrical Characteristics over recommended operating conditions. Typical values at 25 °C, $V_{dd1} = 3.3\text{ V}$, $F_{CLK} = 27\text{ MHz}$.

Symbol	Parameter	Min.	Typ.	Max.	Unit	Notes
t_{PDR}	PD Pulse Register			152	us	One frame time maximum after setting PD_enh bit in the Configuration register @6600frame/sec (refer to Figure 14).
t_{PD}	Power Down		500		us	From PD↑ (refer to Figure 10)
t_{PDW}	PD Pulse Width	700			us	Pulse width to reset the serial interface (refer to Figure 10).
t_{PUPD}	Power Up from PD↓	8		14.5	ms	From PD↓ to valid quad signals. After t_{PUPD} , all registers contain valid data from first image after PD↓. Note that an additional 90 frames for Auto-Exposure (AE) stabilization may be required if mouse movement occurred while PD was high (refer to Figure 10).
t_{PU}	Power Up from $V_{DD}\uparrow$	8		14.5	ms	From $V_{DD}\uparrow$ to valid quad signals. 500usec + 90 frames.
t_{HOLD}	SDIO Read Hold Time		3		us	Minimum hold time for valid data (refer to Figure 9).
t_{RESYNC}	Serial Interface RESYNC	1			us	@6600 frame/sec (refer to Figure 11)
t_{SIWTT}	Serial Interface Watchdog Timer Timeout	1.7			ms	@6600 frame/sec (refer to Figure 11)
t_r, t_f	Rise and Fall Times: SDIO		35, 25		ns	$C_L = 30\text{ pF}$
t_r, t_f	Rise and Fall Times: XA, XB, YA, YB		30, 25		ns	$C_L = 30\text{ pF}$
t_r, t_f	Rise and Fall Times: I_{LD}		80, 30		ns	LD bin grade: P64; $R1 = 13.2\text{ Kohm}$

5.4 DC Operating Condition

Electrical Characteristics over recommended operating conditions. Typical values at 25 °C, $V_{dd1} = 3.3\text{ V}$, $F_{CLK} = 27\text{ MHz}$.

Symbol	Parameter	Min.	Typ.	Max.	Unit	Notes
Type: PWR						
I_{DD}	Supply Current Mouse moving (Normal)		17		mA	Sensor + LD
I_{DD}	Supply Current Mouse not moving (sleep1)		5		mA	Sensor + LD
I_{DDPD}	Supply Current (Power Down)		200		uA	PD, SCLK, SDIO = high Sensor + LD
Type: SCLK, SDIO, PD						
V_{IH}	Input voltage HIGH	2.0				
V_{IL}	Input voltage LOW			0.7	V	
V_{OH}	Output voltage HIGH	2.4			V	@ $I_{OH} = 2\text{mA}$ (SDIO only)
V_{OL}	Output voltage LOW			0.6	V	@ $I_{OL} = 2\text{mA}$ (SDIO only)
Type: LDTEST						
V_{IH}	Input voltage HIGH	2.0			V	
V_{IL}	Input voltage LOW			0.7	V	
Type: XA, XB, YA, YB						
V_{OH}	Output voltage HIGH	2.4			V	@ $I_{OH} = 2\text{mA}$
V_{OL}	Output voltage LOW			0.6	V	@ $I_{OL} = 2\text{mA}$

6. Quadrature Mode

The quadrature state of the mouse sensor tells mouse controller which direction the mouse is moving in. The output format is two channels quadrature (X and Y direction), which emulates encoder phototransistors. The DSP generates the Δx and Δy relative displacement values that are converted into two channel quadrature signals. The following diagrams show the timing for positive X motion, to the right or positive Y motion, up.

6.1 Quadrature Output Timing

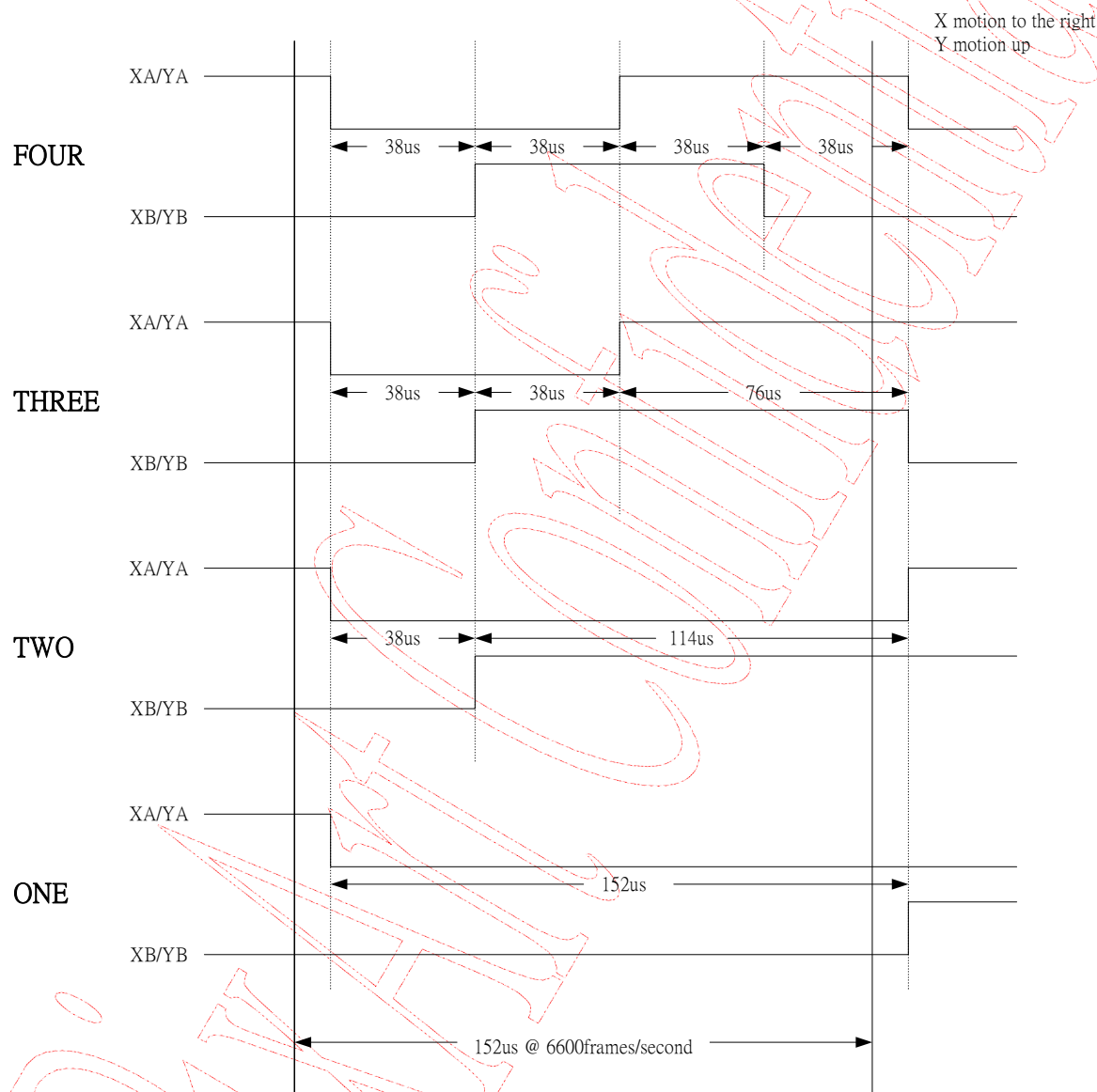


Figure 4. Quadrature output timing

6.2 Quadrature Output State Machine

The following state machine shows the states of the quadrature output pins. The three things to note are that state 0 is entered after a power on reset. While the PD pin is asserted, the state machine is halted. Once PD is de-asserted, the state machine picks up from where it left off. During times of mouse no movement will entry power saving mode, until mouse was moved.

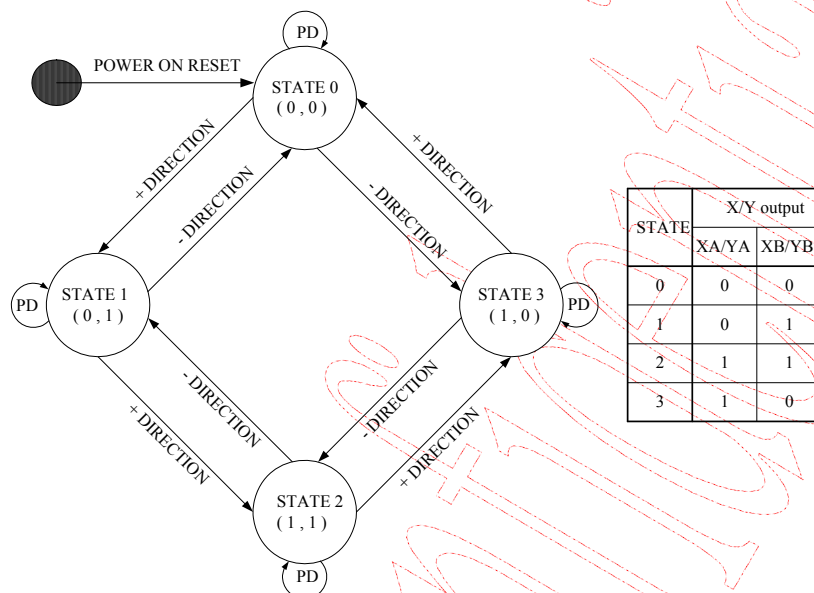


Figure 5. State machine

6.3 Quadrature Output Waveform

The following diagrams show the waveform of the two channel quadrature outputs. If the X, Y is motionless, the (XA, XB), (YA, YB) will keep in final state. Each state change (ex. STATE2 → STATE3) is one count.

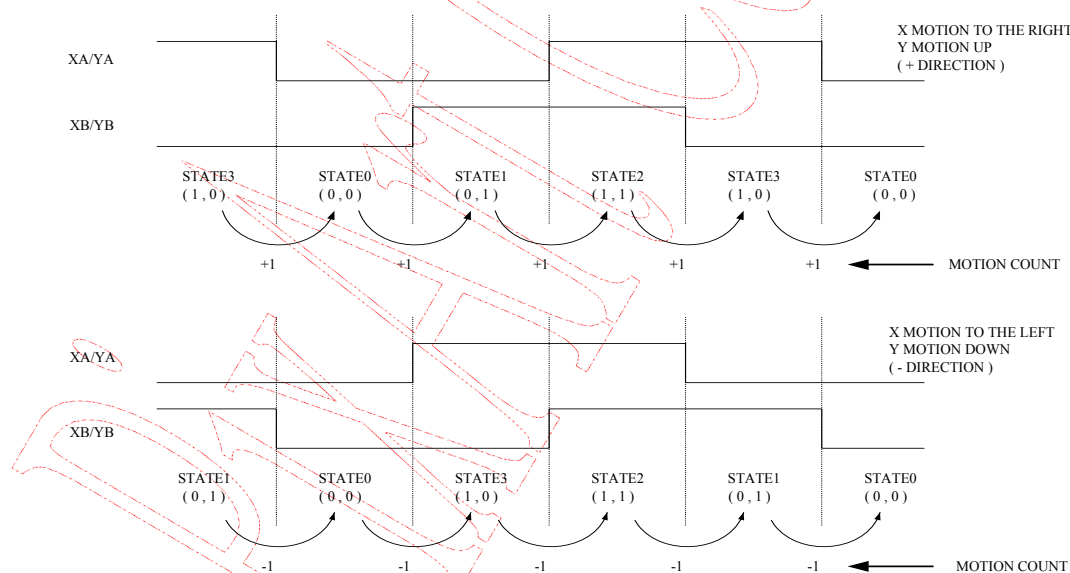


Figure 6. Quadrature output waveform

7. Serial Interface

The synchronous serial port is used to set and read parameters in the mouse sensor, and can be used to read out the motion information instead of the quadrature data pins.

SCLK: The serial clock line. It is always generated by the host micro-controller.

SDIO: The serial data line used for write and read data.

PD: A third line is sometimes involved. PD (Power Down pin) is usually used to place the mouse sensor in a low power mode to meet USB suspend specification. PD can also be used to force re-synchronization between the micro-controller and the mouse sensor in case of an error.

7.1 Transmission Protocol

The transmission protocol is a two-wire link, half duplex protocol between the micro-controller and mouse sensor. All data changes on SDIO are initiated by the falling edge on SCLK. The host micro-controller always initiates communication; the mouse sensor never initiates data transfers.

The transmission protocol consists of the two operation modes:

- Write Operation.
- Read Operation.

Both of the two operation modes consist of two bytes. The first byte contains the address (seven bits) and has a bit7 as its MSB to indicate data direction. The second byte contains the data.

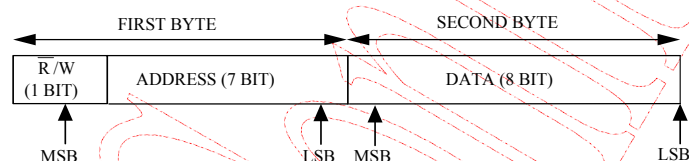


Figure 7. Transmission protocol

7.1.1 Write Operation

A write operation, which means that data is going from the micro-controller to the mouse sensor, is always initiated by the micro-controller and consists of two bytes. The first byte contains the address (seven bits) and has a "1" as its MSB to indicate data direction. The second byte contains the data. The transfer is synchronized by SCLK. The micro-controller changes SDIO on falling edges of SCLK. The mouse sensor reads SDIO on rising edges of SCLK.

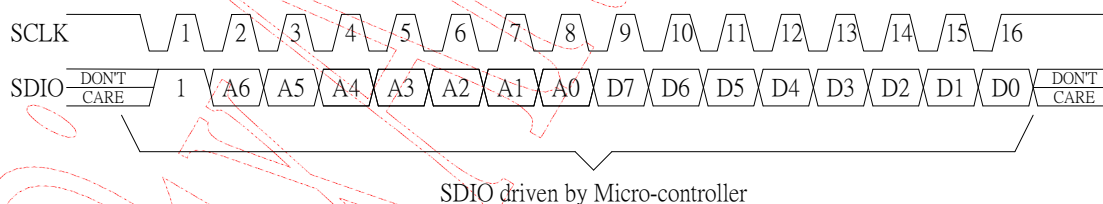


Figure 8. Write operation

7.1.2 Read Operation

A read operation, which means that data is going from the mouse sensor to the mouse controller, is always initiated by the mouse controller and consists of two bytes. The first byte contains the address, is written by the mouse controller, and has a “0” as its MSB to indicate data direction. The second byte contains the data and is driven by the mouse sensor. The transfer is synchronized by SCLK. SDIO is changed on falling edges of SCLK and read on every rising edge of SCLK. The mouse controller must go to a high Z state after the last address data bit. The mouse sensor will go to the high Z state after the last data bit.

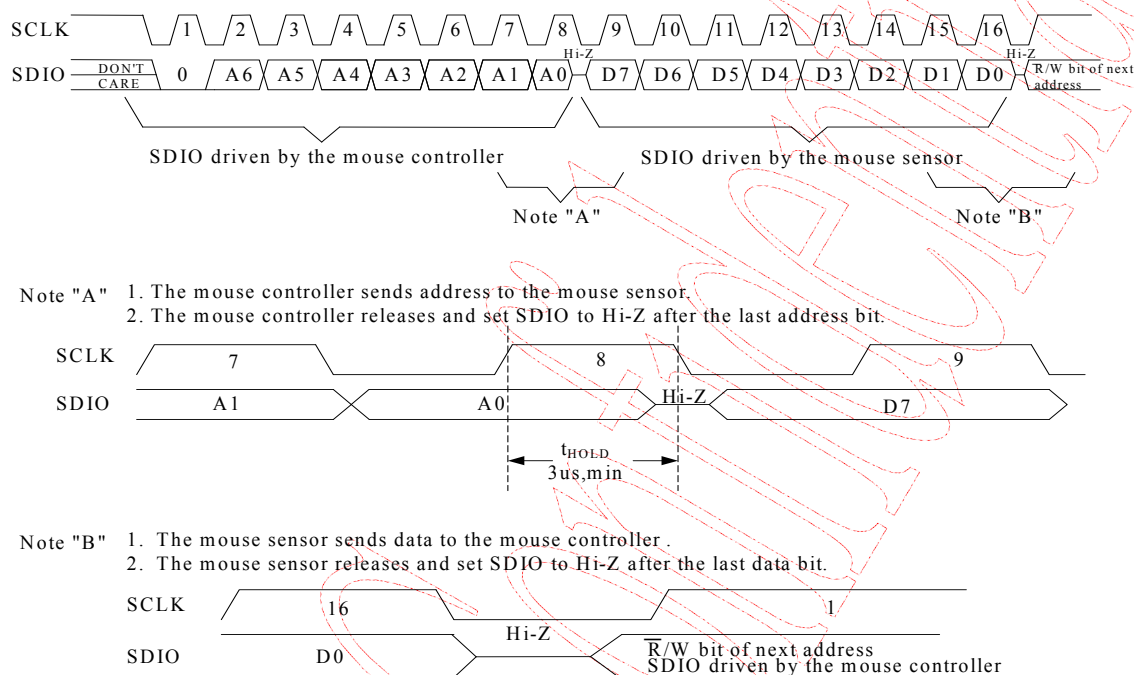


Figure 9. Read Operation

7.2 Re-Synchronous Serial Interface

If the mouse controller and the mouse sensor get out of synchronization, then the data either written or read from the registers will be incorrect. There are two different ways for re-synchronous serial interface.

- Re-synchronous serial interface using PD pin (see Section 7.2.1)
- Re-synchronous serial interface using watchdog timer timeout (see Section 7.2.2)

Note that “watchdog timer timeout” (see Section 7.2.2) function is disabled when the mouse sensor is in the power down mode. If the user uses this function during the power down mode, it will get out of synchronization. The mouse sensor and the mouse controller also might get out of synchronization due to following conditions.

- **Power On Problem** - The problem occurs if the mouse sensor powers up before the mouse controller sets the SCLK and SDIO lines to be output. The mouse sensor and the mouse controller might get out of synchronization due to power on problem. An easy way to solve this is to raise PD pin (see Section 7.2.1) or use watchdog timer timeout (see Section 7.2.2) for re-synchronous serial interface.
- **ESD Events** - The mouse sensor and the mouse controller might get out of synchronization due to ESD events. An easy way to solve this is to raise PD pin (see Section 7.2.1) or use watchdog timer timeout (see Section 7.2.2) for re-synchronous serial interface.
- **USB suspend** - Termination of a transmission by the mouse controller may be required sometimes (for example, due to a USB suspend interrupt during a read operation). An easy way to solve this is to raise PD pin (see Section 7.2.1) or use watchdog timer timeout (see Section 7.2.2) for re-synchronous serial interface.

7.2.1 Re-Synchronous Serial Interface Using PD Pin

The mouse controller raises PD line to reach re-synchronous serial interface after an incorrect read. The mouse sensor will reset the serial port but will not reset the registers and be prepared for the beginning of a new transmission. Note that using “PD pin” to reach re-synchronous is quicker than using “watchdog timer timeout”.

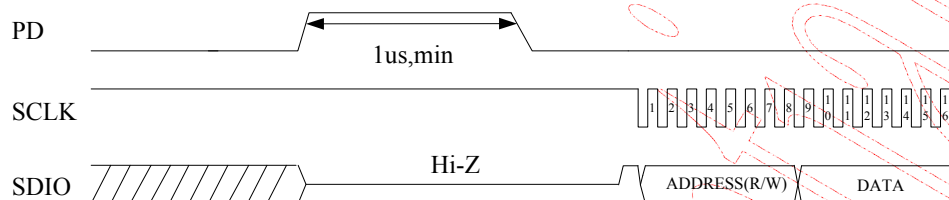


Figure 10. Re-synchronous Serial Interface Using PD Pin

7.2.2 Re-Synchronous Serial Interface Using Watchdog Timer Timeout

The mouse controller can toggle the SCLK line from high to low to high and wait at least t_{SIWTT} to reach re-synchronous serial interface after an incorrect read. The mouse sensor will reset the serial port but will not reset the registers and be prepared for the beginning of a new transmission.

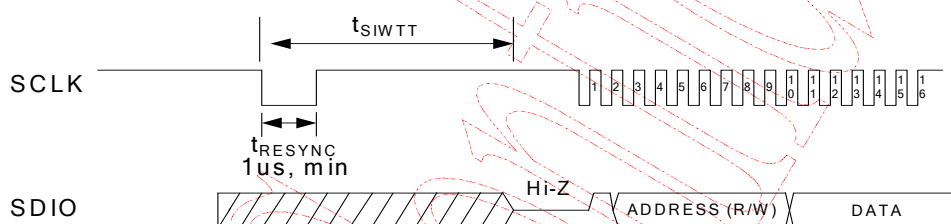


Figure 11. Re-synchronous Serial Interface Using Watchdog Timer Timeout

7.3 Collision Detection on SDIO

The only time that the mouse sensor drives the SDIO line is during a READ operation. To avoid data collisions, the micro-controller should release SDIO before the falling edge of SCLK after the last address bit. The mouse sensor begins to drive SDIO after the next falling edge of SCLK. The mouse sensor release SDIO of the rising SCLK edge after the last data bit. The micro-controller can begin driving SDIO any time after that. In order to maintain low power consumption in normal operation or when the PD pin is pulled high, the micro-controller should not leave SDIO floating until the next transmission (although that will not cause any communication difficulties).

7.4 Power Down Mode

There are two different ways to entry power down mode, using the PD line or register setting.

7.4.1 PD Line Power Down Mode

To place the mouse sensor in a low power mode to meet USB suspend specification, raise the PD line at least 700us. Then PD line can stay high, with the mouse sensor in the shutdown state, or the PD pin can be lowered, returning the mouse sensor to normal operation.

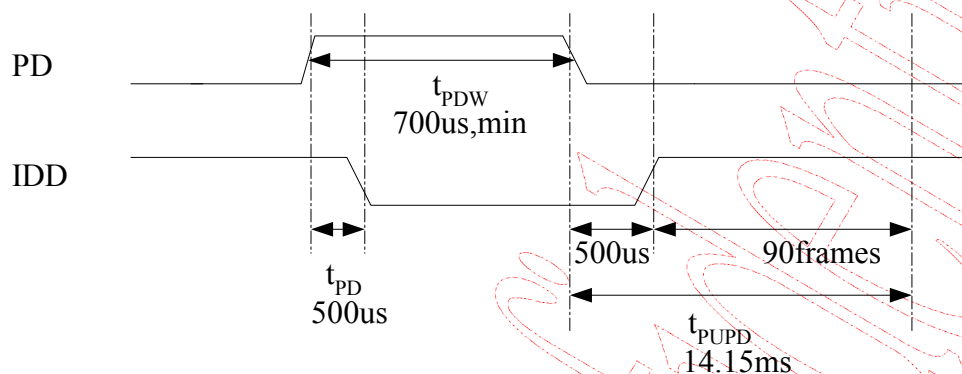


Figure 12. Power down minimum pulse width

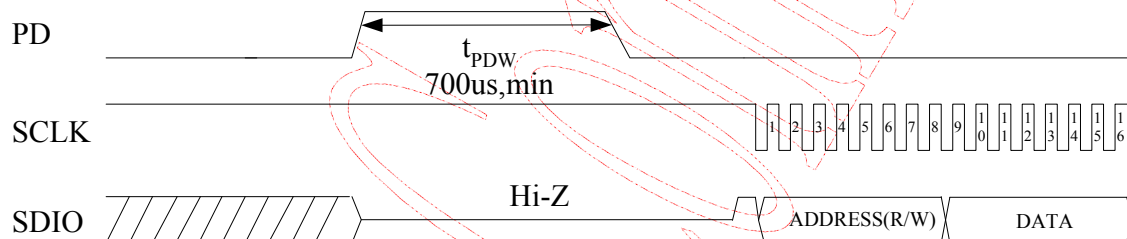


Figure 13. PD line power down mode

7.4.2 Register Power Down Mode

The mouse sensor can be placed in a power down mode by setting **PD_enh** bit in the **configuration** register via a serial port write operation. After setting the **configuration** register, wait at least 1 frame times. To get the chip out of the power down mode, clear **PD_enh** bit in the **configuration** register via a serial port write operation. In the power down mode, the serial interface watchdog timer is not available (see Section 7.2.2). But, the serial interface still can read/write normally. For an accurate report after leave the power down mode, wait about 3ms before the mouse controller is able to issue any write/read operation to the mouse sensor.

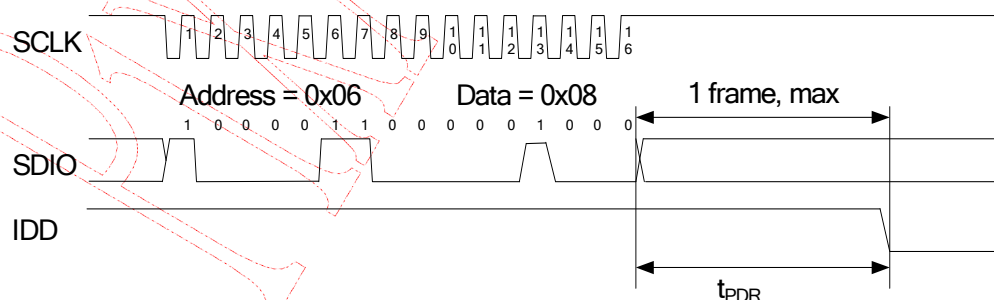


Figure 14. Power-down Configuration Register Writing Operation

7.4.3 Register Power Down Mode

The mouse sensor can be placed in a power-down mode by setting bit 3 in the configuration register via a serial port write operation. After setting the configuration register, wait at least 1 frame times. To get the chip out of the power-down mode, clear bit 3 in the configuration register via a serial port write operation. In power-down mode, the serial interface watchdog timer is not available. But, The serial interface still can read/write normally. For an accurate report after leave power down mode, wait about 3ms before the micro-controller is able to issue any write/read operation to the mouse sensor.

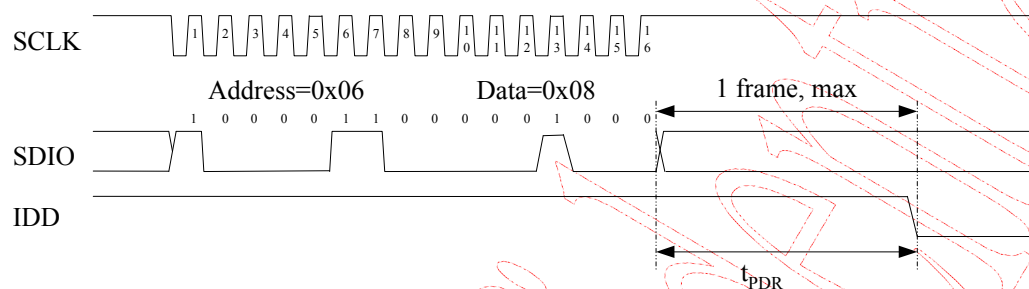


Figure 15. Power-down configuration register writing operation

7.5 Error Detection

1. The micro-controller can verify success of write operations by issuing a read command to the same address and comparing written data to read data.
2. The micro-controller can verify the synchronization of the serial port by periodically reading the product ID register

8. Referencing Application Circuit

8.1 Typical Application using Serial Interface for Full Speed USB Wire Mouse

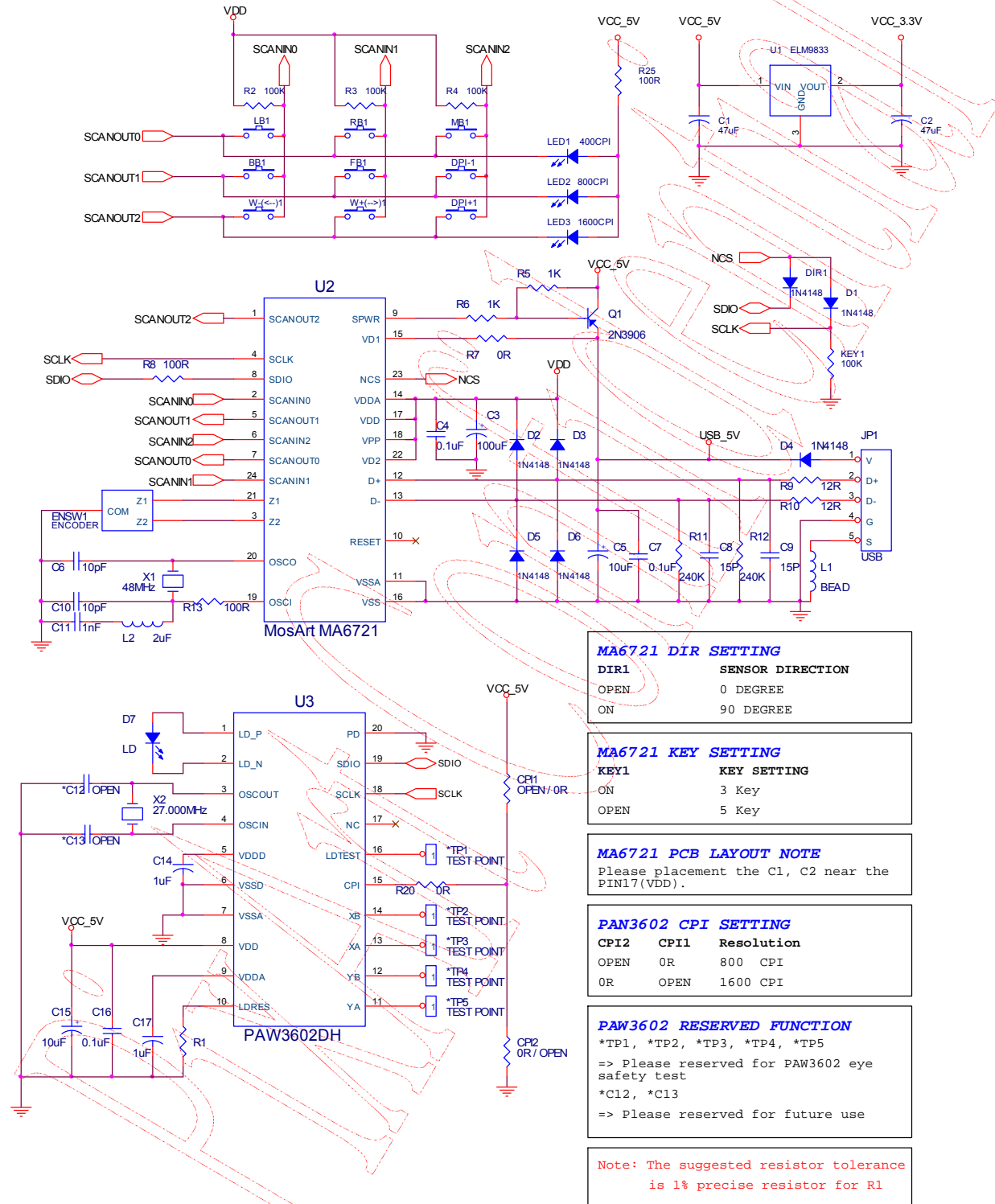


Figure 16. Application Circuit Using Serial Interface with MosArt MA6721 (Full Speed USB)

8.3 Typical Application for Wireless Laser Mouse, Power Source from Pin 5 & 9

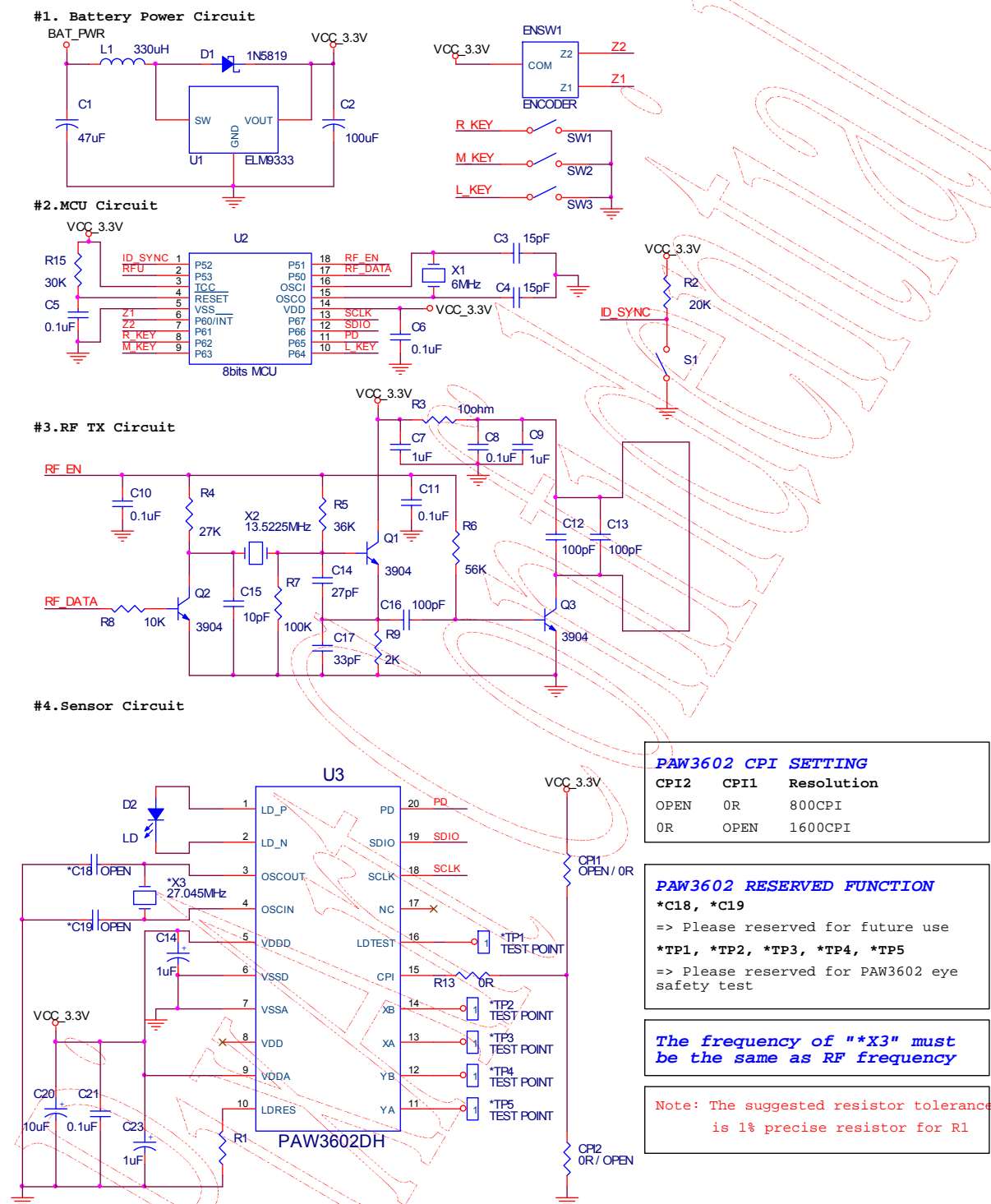


Figure 18. RF application circuit using pin 5 & 9 for power supply source

8.4 Typical Application for RF Receiver

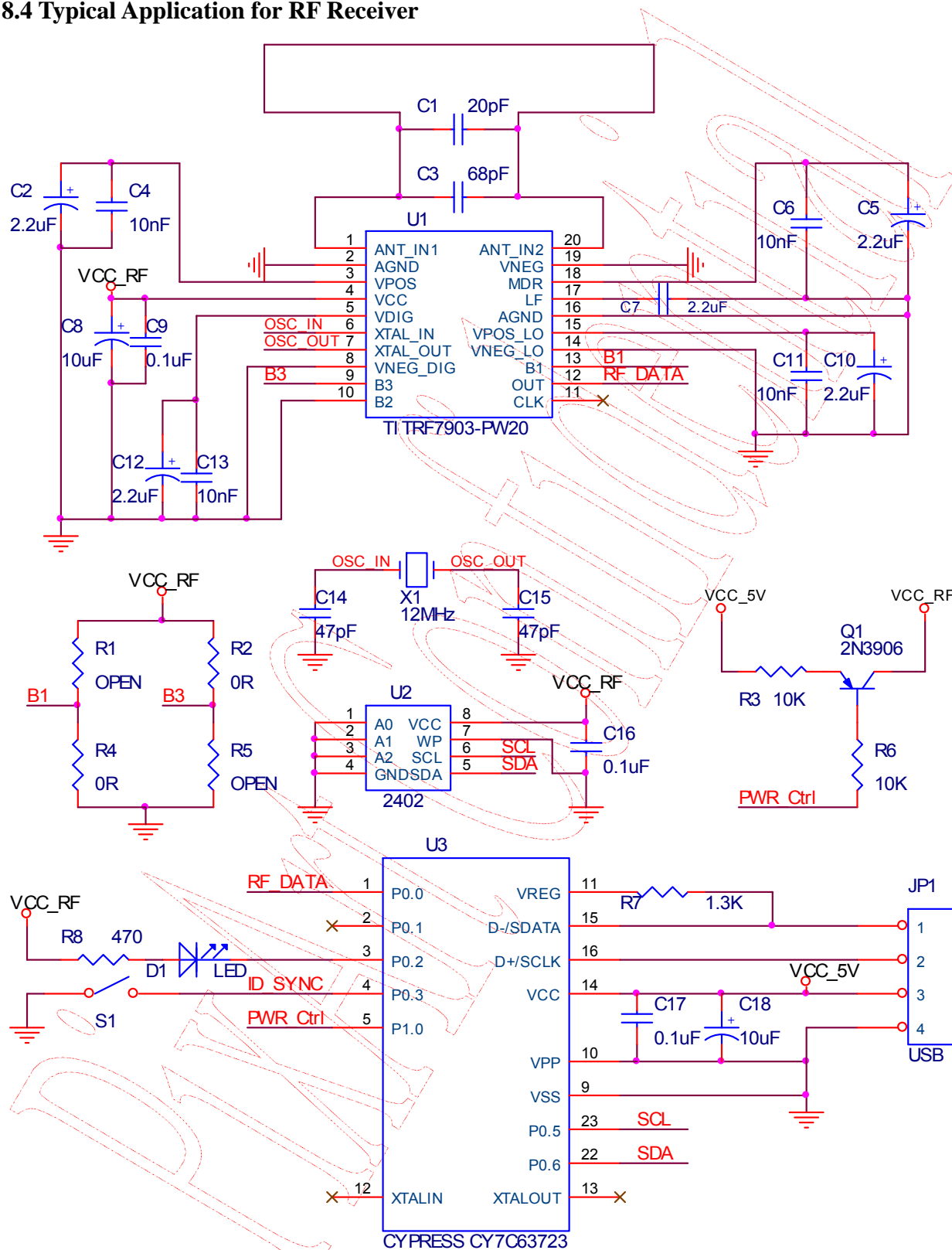
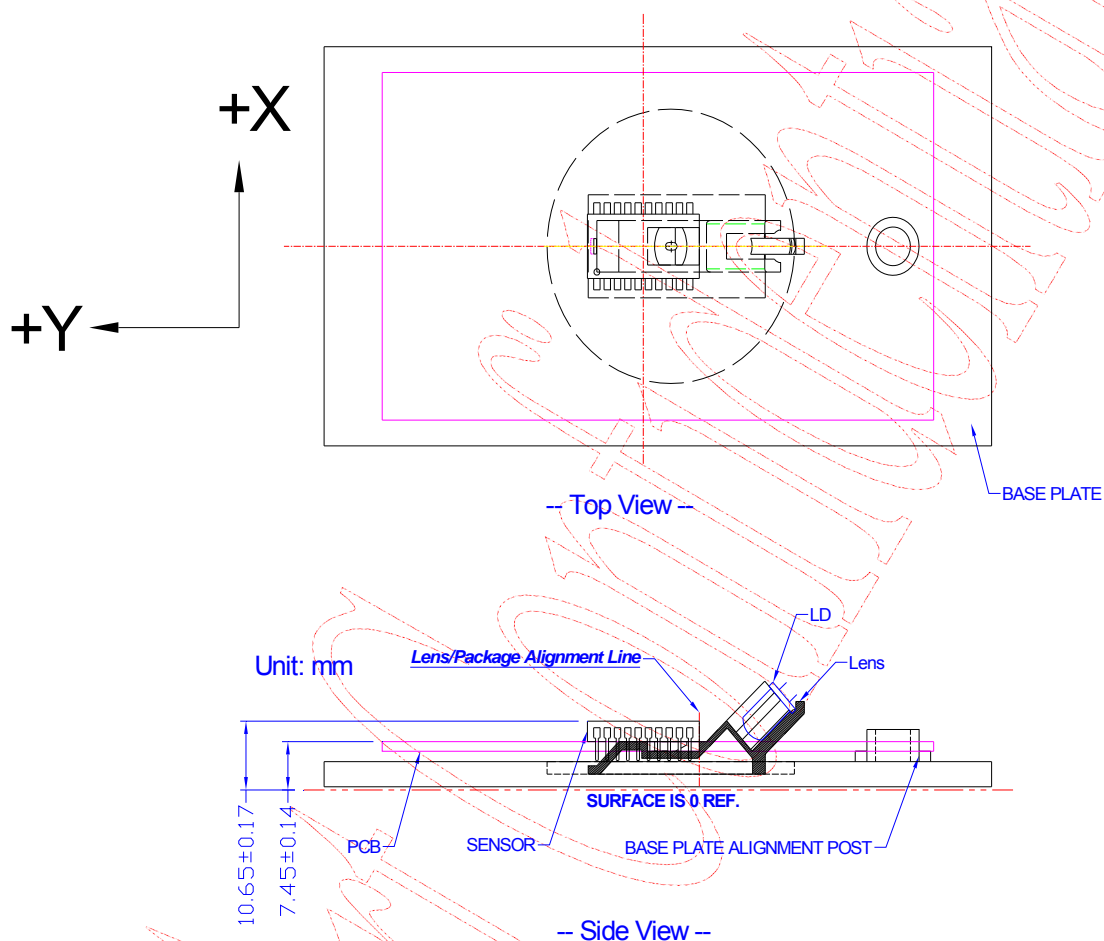


Figure 19. Application circuit with Cypress CY7C6313 (Low speed USB)

9. PCB Layout Consideration

1. Caps for pins 5, 8, 9 **MUST** have trace lengths **LESS** than **5mm**.
2. The trace lengths of OSCOUT, OSCIN must less than **6mm**.

10. Z and 2D Assembly



11. Package Information

11.1 Package Outline Drawing

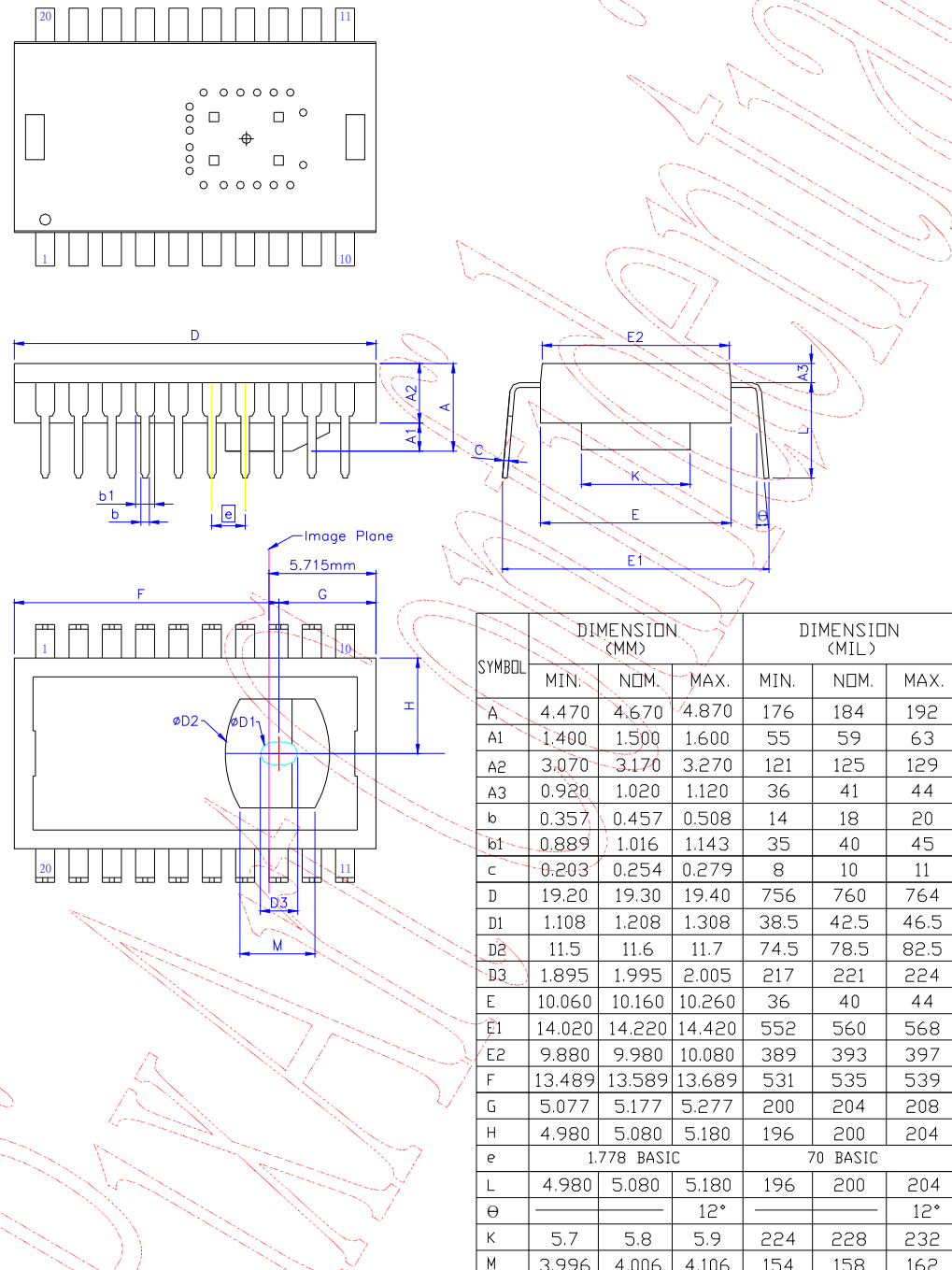


Figure 21. Package outline drawing

5.2 Base Plate Modeling Dimension

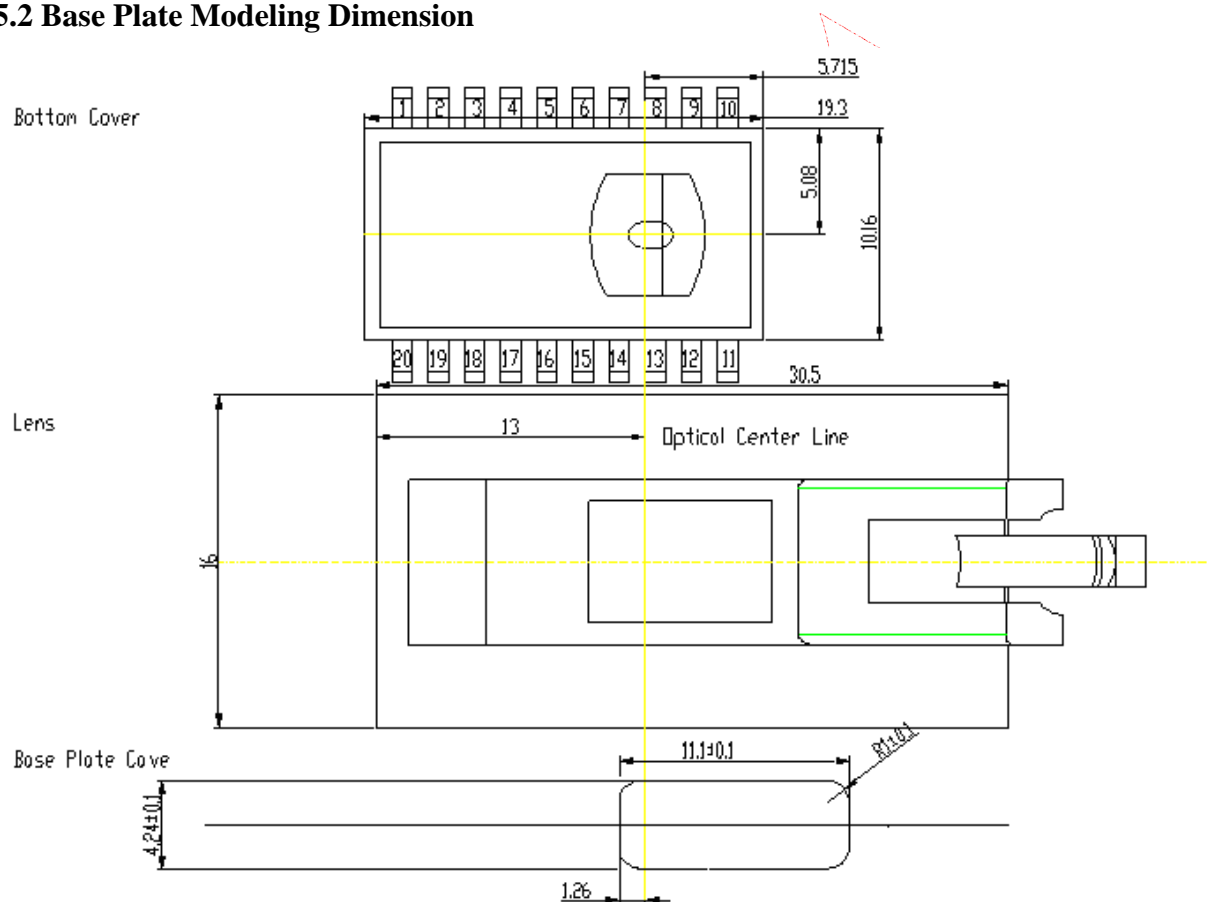


Figure 22. Base plate molding dimension

5.3 Recommended PCB Mechanical Cutouts and Spacing

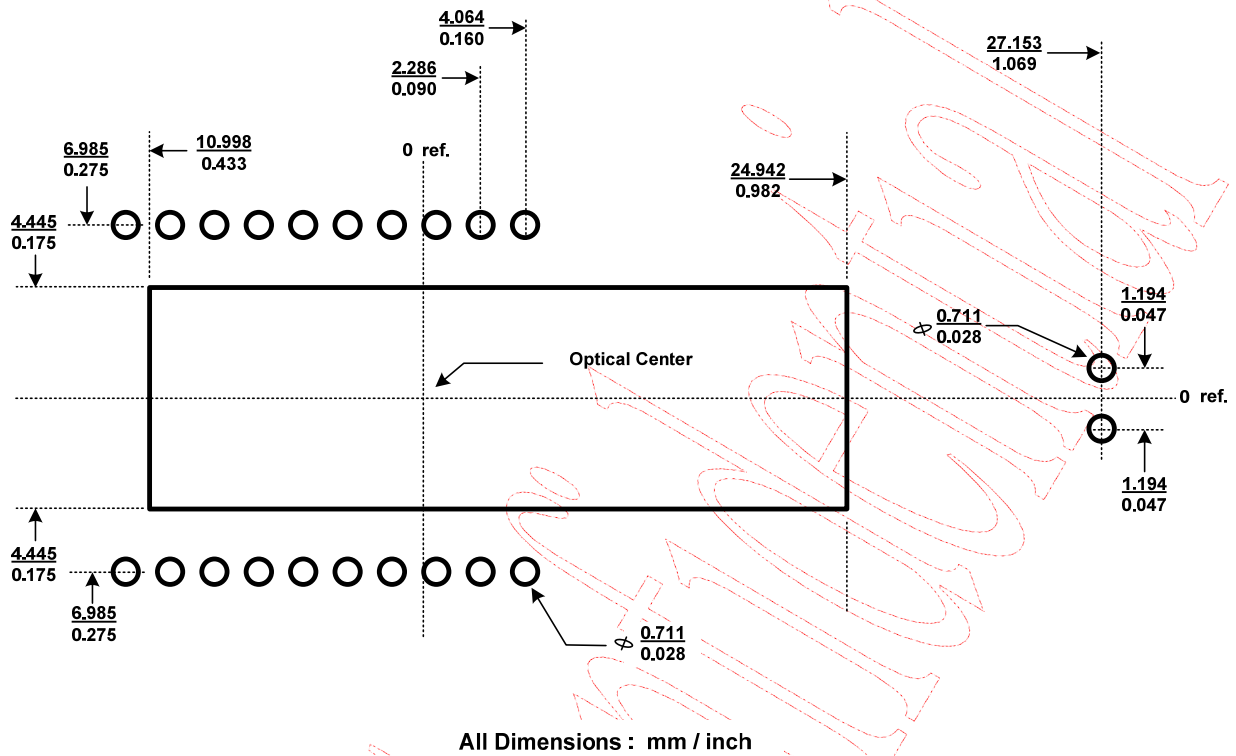


Figure 23. Recommended PCB Mechanical Cutouts and Spacing

6. Update History

Version	Update	Date
V1.0	Creation, Preliminary 1 st version	06/28/2007

Vertical Cavity Surface Emitting Laser (VCSEL)

Components Specification

Distribution

Internal Only

☐

External All

☐

External Restricted

☐ If restricted, specify restricted to whom:

Document No.: PNDR-00003

Revision: Rev 2.50

Date: 2007/06/15

Revision History

Revision	Author	Date	Description
1.0	M.H.Chien	2006/06/14	Initial version
1.5	Chadwick	2007/01/18	Add VDD=2.7V and delete VDD=5.0V constraint resistor table
2.0	Chadwick	2007/05/04	Revise resistor table for higher CW radiant power 300uW ~550uW on Mouse operation ; Delete P32/ P64/ P68/ P72/ P76/ P80 six Grades
2.5	Chadwick	2007/06/15	Note PAN/PAW 3601DH for constraint resistor table and add new constraint resistor table for PAN/PAW 3602-DH

PNDR-00003**850nm Epoxy molded VCSEL for Laser Mouse****FEATURES**

- Epoxy Molded with round emission surface.
- Small divergence angle.
- Constricted Beam profile.

**ELECTRO-OPTICAL CHARACTERISTICS**

PARAMETERS	SYMBOL	MIN	TYP	MAX	UNIT	TEST CONDITIONS
Output Power	P_o		0.475	0.7	mW	$I = I_F^{(1)}$
Wavelength	λ_P	830	850	860	nm	$I_F = 6 \text{ mA}$
Forward Voltage	V_F	1.6	1.75	1.9	V	$I_F = 6 \text{ mA}$
Series Resistance	R_S		40	60	Ω	$I_F = 6 \text{ mA}$
Breakdown voltage	V_{BD}	7	14		V	$I_r = 10 \mu\text{A}$
Beam Divergence($1/e^2$)	θ		8		degree	$I_F = 6 \text{ mA}$

Notes : (1) Binning

APPLY TO PAN3602DH/ PAW3602DH

Optical power at each of following nominal bin operating current and constrained resistor

Bin grade	LD current (mA)	Single Constrain resistor :R(Ω)	Bin grade	LD current (mA)	Single Constrain resistor :R(Ω)
P36	3.6	18K	P50	5.0	13K
P40	4.0	15K	P52	5.2	13K
P42	4.2	15K	P54	5.4	12K
P44	4.4	15K	P56	5.6	12K
P46	4.6	15K	P58	5.8	12K
P48	4.8	13K	P60	6.0	10K

Warning! For Single constrain resistor (R), please using the recommend value, if resistor value is less than recommend value, there will be eye safety issue.

Note: The suggested resistor tolerance is 1% precise resistor for constrained resistor R.

ABSOLUTE MAXIMUM RATINGS:

PARAMETERS	MIN	MAX	UNIT	Condition
Storage Temperature	-30	85	°C	
Operating Temperature	-10	60	°C	
Continuous Forward Current		12	mA	
Continuous Reverse Voltage		7	V	
Lead Solder Temperature		260	°C	10 seconds

Fig. 1 Typical Optical Characteristics

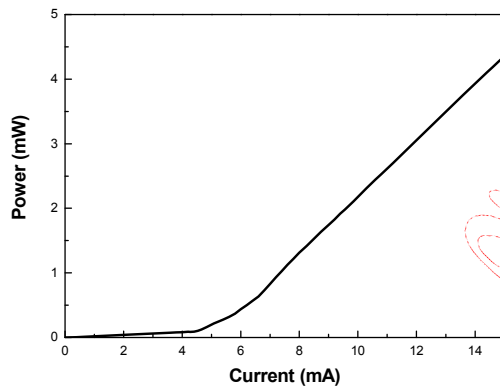
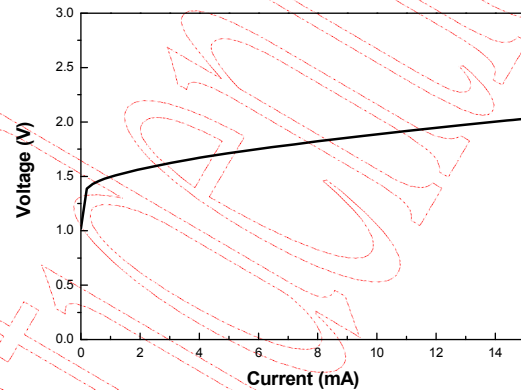
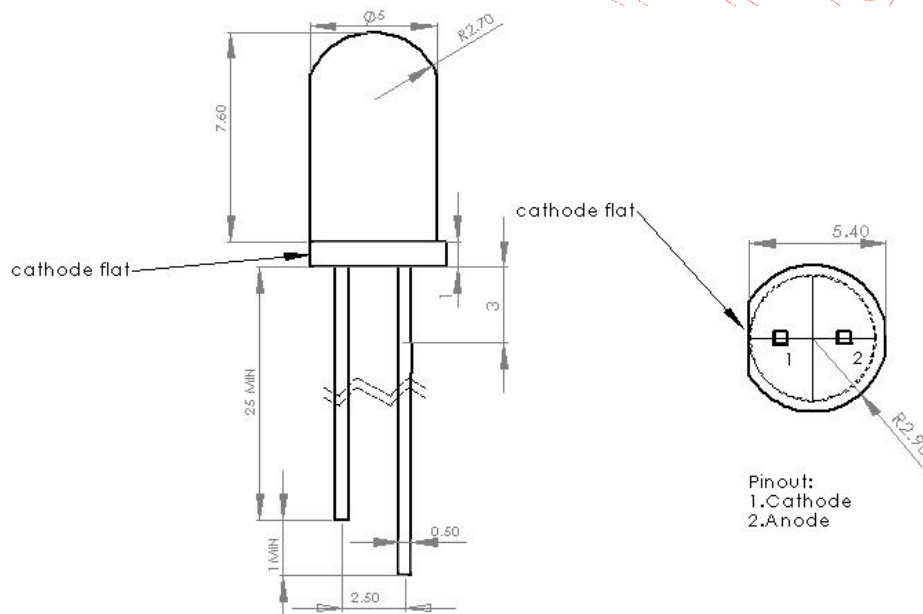


Fig. 2 Typical Electrical Characteristics

**OUTLINE DIMENSIONS:**

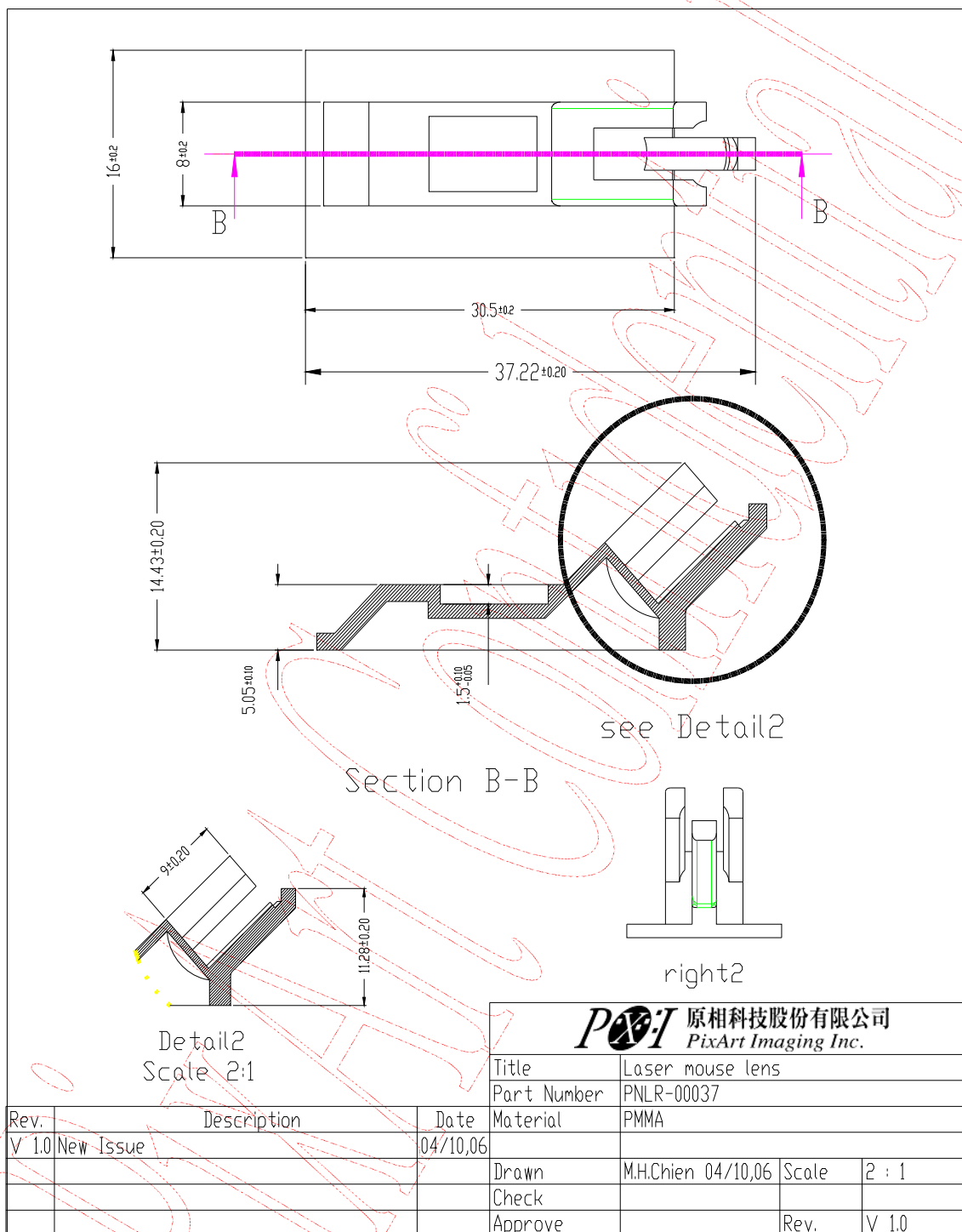
Note: Unit is millimeters and Tolerance is ± 0.2 mm unless otherwise notes

WARNING:

The VCSEL is a class IIIa laser in the safety standard ANSI Z136.1 and should be treated as a potential eye hazard.



PNLR-00037 Lens Dimensions



Note: The Part No. of the Mouse Product with Prefix "PAN" shall NOT be made, sold, offered to sell, imported or used in or into USA, Canada, Japan and EU. For "PAN", PixArt has only gained territory-limited patent license from Avago. Avago reserve right to take legal action against our customers who fails to comply the above term. PLEASE NOTE THAT PixArt will NOT defend, indemnify, or provide any assistance to our customers who fail to comply the term. IF YOU DO NOT AGREE THE TERM, PIXART WILL NOT DELIVER "PAN" PRODUCTS TO YOU.