

**TOSHIBA**

**32-bit TX System RISC  
TX03 Series**

**TMPM370FYDFG  
TMPM370FYFG**

**Tentative**

**TOSHIBA CORPORATION**

Semiconductor Company

## Revision History

Date	Revision	
2009/8/4	Tentative 1	First Release
2009/10/5	Tentative 2	Contents Revised

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ARM, ARM Powered, AMBA, ADK, ARM9TDMI, TDMI, PrimeCell, RealView, Thumb, Cortex, Coresight, ARM9, ARM926EJ-S, Embedded Trace Macrocell, ETM, AHB, APB, and KEIL are registered trademarks or trademarks of ARM Limited in the EU and other countries.  
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32-bit RISC microcontroller TX03 series

# TMPM370FYDFG

# TMPM370FYFG

TX03 series is a 32-bit RISC microcontroller series with an ARM® Cortex™-M3 microcontroller core.

Product No.	On chip Flash ROM	On chip RAM	Package
TMPM370FYDFG	256 Kbyte	10 Kbyte	QFP100-P-1420-0.65Q
TMPM370FYFG	256 Kbyte	10 Kbyte	LQFP100-P-1414-0.50H

## 1.1 Features

### (1) ARM Cortex-M3 microcontroller core

#### 1) Improved code efficiency has been realized through the use of Thumb®2 instruction

- New 16-bit Thumb® instructions for improved program flow
- New 32-bit Thumb instructions for improved performance
- Auto-switching between 32-bit instruction and 16-bit instruction is executed by compiler.

#### 2) Both high performance and low power consumption have been achieved

##### ■ High performance

- A 32-bit multiplication (32×32=32 bit) can be executed with one clock
- Division takes between 2 and 12 cycles depending on dividend and divisor

##### ■ Low power consumption

- Optimized design using a low power consumption library
- Standby function that stops the operation of the microcontroller core

#### 3) High-speed interrupt response suitable for real-time control

- An interruptible long instruction
- Stack push automatically handled by hardware

### (2) Interrupt source

- Internal: 62 factors...The order of precedence can be set over 7 levels (except the watchdog timer interrupt).
- External: 16 factors...The order of precedence can be set over 7 levels

### (3) Input/ output ports

- Input/Output: 74 pins    Input: 2pins

### (4) Watchdog timer(WDT): 1 channel

- 26 cycles of binary counter
- Watchdog timer out

### (5) Power\_On reset function(POR)

### (6) Voltage detect function(VLTD)

### (7) Oscillation frequency detect function(OFD)

- ( 8 ) Vector engine(VE): 1 unit
  - Calculation circuit for motor control
  - corresponding to 2 motors
- ( 9 ) Programmable motor driver(PMD): 2channel
  - 3phase complementary PWM generator
  - Synchronous A/D convert start trigger generator
  - Emergency protective function(EMG pin/comparator output)
- ( 10 ) Encoder input circuit(ENC): 2 channel
  - Correspond to incremental encoder(AB/ABZ)
  - Rotation direction detection
  - Counter for absolute position detection
  - Comparator for position detection
  - Noise filter
  - 3 phase sensor input
- ( 11 ) 16-bit timer(TMRB): 8 channel
  - 16-bit interval timer mode
  - 16-bit event counter mode
  - 16-bit PPG output
  - Input capture function
- ( 12 ) General-purpose serial interface(SIO): 4 channel
  - Either UART mode or synchronous mode can be selected (4byte FIFO equipped)
- ( 13 ) 12-bit A/D converter (ADC): 2unit( 22 channel for analog input)
  - Start by the internal trigger: TMRB interrupt / PMD trigger
  - Single/repeat mode
  - AD monitoring function(2ch)
  - Conversion speed 2 usec (@ ADC conversion clock = 40MHz)
- ( 14 ) OP-Amp(AMP): 4 channel
  - 8 gain can be select
- ( 15 ) comparator(CMP): 3+1 channel
  - Protection for motor emergence stop
  - 2 input type(OP-Amp output/analog input)
- ( 16 ) Standby mode
  - Standby mode: IDLE, STOP
- ( 17 ) Clock generator(CG)
  - On-chip PLL (8 times)
  - Clock gear function: The high-speed clock can be divided into 1/1, 1/2, 1/4, 1/8 or 1/16
- ( 18 ) Endian
  - Little endian
- ( 19 ) Maximum operating frequency
  - 80MHz
- ( 20 ) Operating voltage range
  - 4.5V~5.5V (with on-chip regulator)
- ( 21 ) Temperature range
  - -40°C~85°C (except during Flash writing/ erasing and debugging)
  - 0°C~70°C (during Flash writing/ erasing and degugging)

1.2 Block Diagram

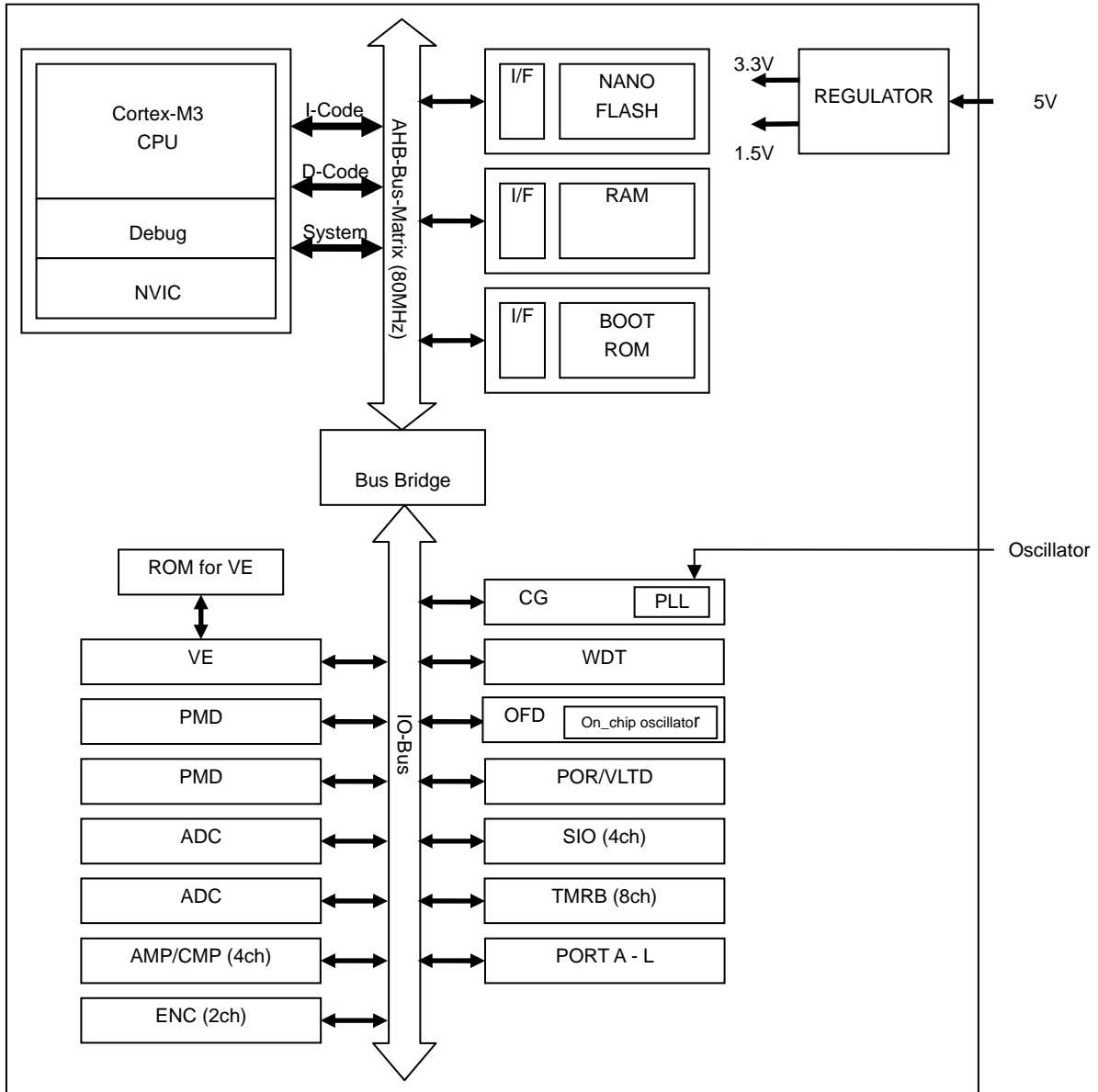


Fig1.1 TMPM370FYDFG/ FYFG block diagram

## 2. Pin Layout and Pin Functions

This chapter describes the pin layout, pin names and pin functions of TMPM370FYFG/TMPM370FYDFG.

### 2.1 Pin Layout (Top view)

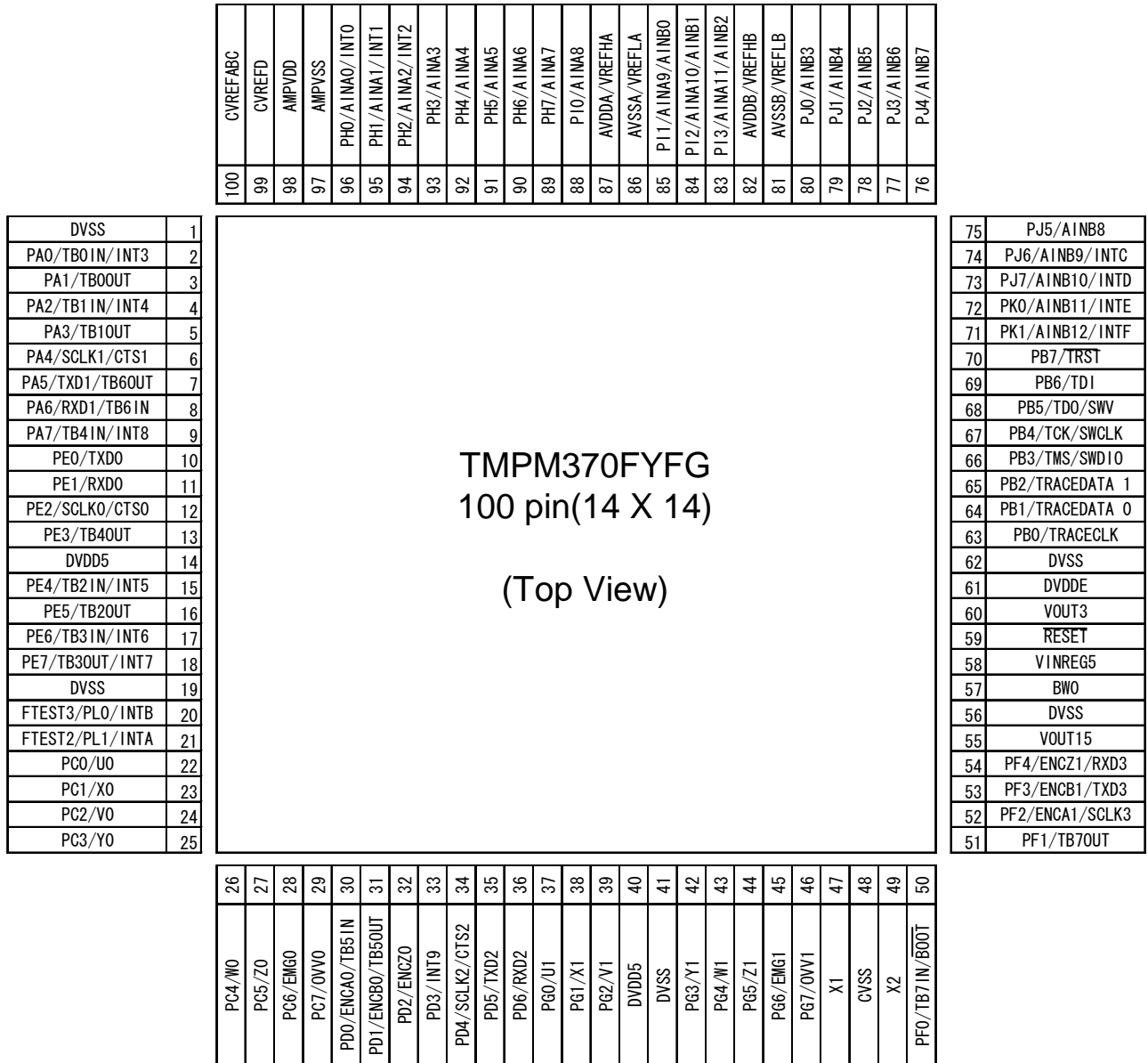


Fig 2-1 Pin layout (TMPM370FYFG)

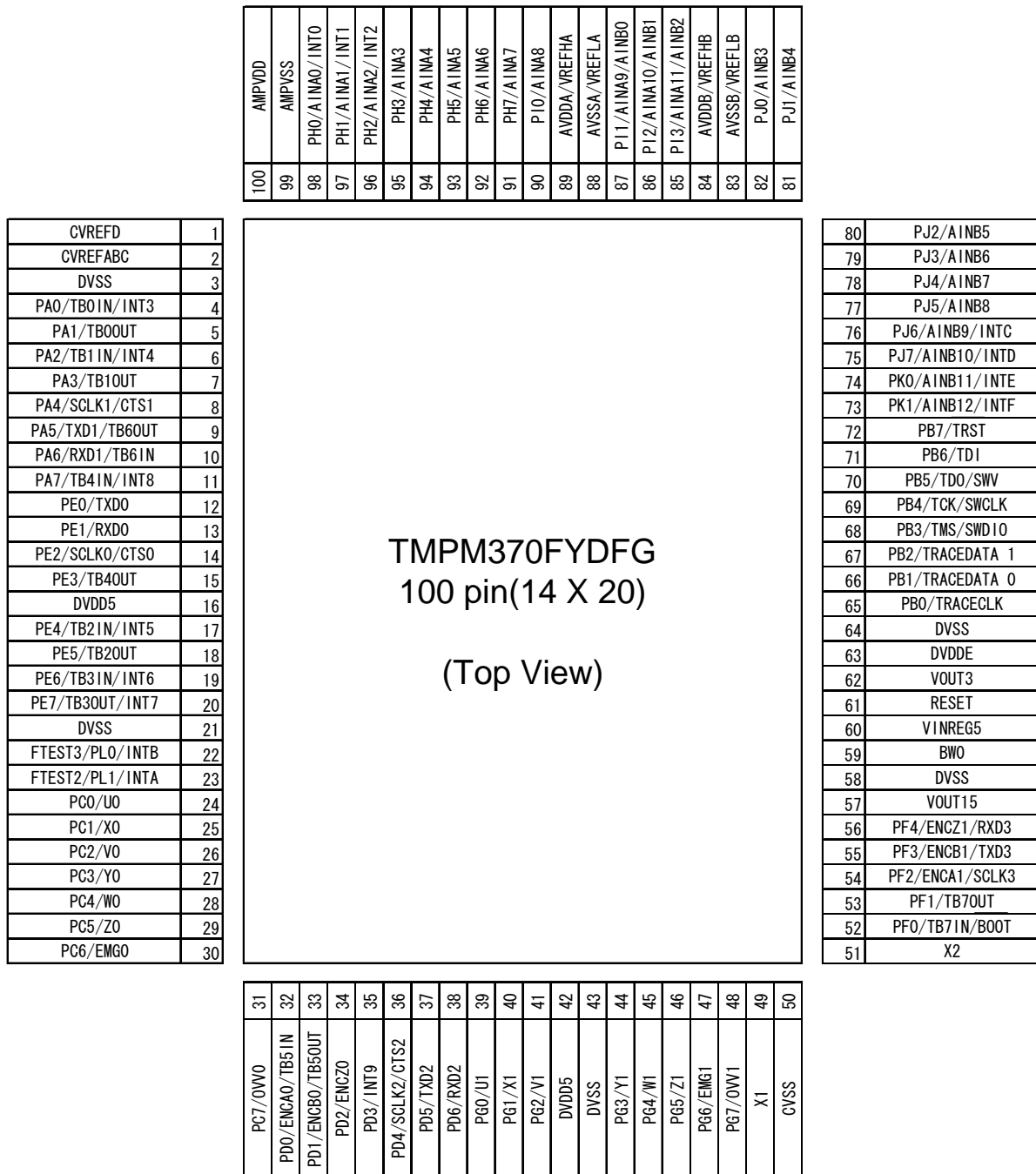


Fig 2-2 Pin layout (TMPM370FYDFG)



## 2.2 Pin function

Table 2.1 lists the pin functions of TMPM370FYFG/FYDFG. Table 2.2 shows the operating voltage of each pin, and table 2.3 shows the voltage range of every pin.

Table 2.1 Pin functions (1/5)

Pin name	Output during Reset	SCHMITT (O:Yes)	Open Drain mode	High Speed
CVREFD	Hi-Z			
CVREFABC	Hi-Z			
DVSS				
PA0 TB0IN/INT3	Hi-Z	O	O	
PA1 TB0OUT	Hi-Z	O	O	
PA2 TB1IN INT4	Hi-Z	O	O	
PA3 TB1OUT	Hi-Z	O	O	
PA4 SCLK1 CTS1	Hi-Z	O	O	
PA5 TXD1 TB6OUT	Hi-Z	O	O	
PA6 RXD1 TB6IN	Hi-Z	O	O	
PA7 TB4IN INT8	Hi-Z	O	O	
PE0 TXD0	Hi-Z	O	O	
PE1 RXD0	Hi-Z	O	O	
PE2 SCLK0 CTS0	Hi-Z	O	O	
PE3 TB4OUT	Hi-Z	O	O	
DVDD5				
PE4 TB2IN INT5	Hi-Z	O	O	
PE5 TB2OUT	Hi-Z	O	O	
PE6 TB3IN INT6	Hi-Z	O	O	
PE7 TB3OUT INT7	Hi-Z	O	O	
DVSS				

Table 2.1 Pin functions (2/5)

Pin name	Output during Reset	SCHMITT (O:Yes)	Open Drain mode	High Speed
PL0 INTB	Hi-Z	0		
PL1 INTA	Hi-Z	0		
PC0 U0	Hi-Z	0	0	
PC1 X0	Hi-Z	0	0	
PC2 V0	Hi-Z	0	0	
PC3 Y0	Hi-Z	0	0	
PC4 W0	Hi-Z	0	0	
PC5 Z0	Hi-Z	0	0	
PC6 EMG0	Hi-Z	0	0	
PC7 OVV0	Hi-Z	0	0	
PD0 ENCA0 TB5IN	Hi-Z	0	0	
PD1 ENCB0 TB5OUT	Hi-Z	0	0	
PD2 ENCZ0	Hi-Z	0	0	
PD3 INT9	Hi-Z	0	0	
PD4 SCLK2 CTS2	Hi-Z	0	0	
PD5 TXD2	Hi-Z	0	0	
PD6 RXD2	Hi-Z	0	0	
PG0 U1	Hi-Z	0	0	
PG1 X1	Hi-Z	0	0	
PG2 V1	Hi-Z	0	0	
DVDD5				
DVSS				

Table 2.1 Pin functions (3/5)

Pin name	Output during Reset	SCHMITT (O:Yes)	Open Drain mode	High Speed
PG3 Y1	Hi-Z	0	0	
PG4 W1	Hi-Z	0	0	
PG5 Z1	Hi-Z	0	0	
PG6 EMG1	Hi-Z	0	0	
PG7 OVV1	Hi-Z	0	0	
X1	Hi-Z	0		
CVSS	Hi-Z	0		
X2	Hi-Z	0		
PF0 TB7IN BOOT	Pull UP	0	0	
PF1 TB7OUT	Hi-Z	0	0	
PF2 ENCA1 SCLK3	Hi-Z	0	0	
PF3 ENCB1 TXD3	Hi-Z	0	0	
PF4 ENCZ1 RXD3	Hi-Z	0	0	
VOUT15				
DVSS				
BW0	Hi-Z	0		
VINREG5				
RESET	Pull UP	0		
VOUT3				
DVDDE				
DVSS				
PB0 TRACECLK	Hi-Z	0		0
PB1 TRACEDATA 0	Hi-Z	0		0
PB2 TRACEDATA 1	Hi-Z	0		0
PB3 TMS SWDIO	Pull UP	0		0
PB4 TCK SWCLK	Pull DOWN	0		0

Table 2.1 Pin functions (4/5)

Pin name	Output during Reset	SCHMITT (O:Yes)	Open Drain mode	High Speed
PB5 TDO SWV	Hi-Z	O		O
PB6 TDI	Pull UP	O		
PB7 $\overline{\text{TRST}}$	Pull UP	O		
PK1 AINB12 INTF	Hi-Z	O	O	
PK0 AINB11 INTE	Hi-Z	O	O	
PJ7 AINB10 INTD	Hi-Z	O	O	
PJ6 AINB9 INTC	Hi-Z	O	O	
PJ5 AINB8	Hi-Z	O	O	
PJ4 AINB7	Hi-Z	O	O	
PJ3 AINB6	Hi-Z	O	O	
PJ2 AINB5	Hi-Z	O	O	
PJ1 AINB4	Hi-Z	O	O	
PJ0 AINB3	Hi-Z	O	O	
AVSSB VREFLB				
AVDDB VREFHB				
PI3 AINA11 AINB2	Hi-Z	O	O	
PI2 AINA10 AINB1	Hi-Z	O	O	
PI1 AINA9 AINB0	Hi-Z	O	O	
AVSSA VREFLA				
AVDDA VREFHA				
PI0 AINA8	Hi-Z	O	O	

Table 2.1 Pin function (5/5)

Pin name	Output during Reset	SCHMITT (O:Yes)	Open Drain mode	High Speed
PH7 AINA7	Hi-Z	O	O	
PH6 AINA6	Hi-Z	O	O	
PH5 AINA5	Hi-Z	O	O	
PH4 AINA4	Hi-Z	O	O	
PH3 AINA3	Hi-Z	O	O	
PH2 AINA2 INT2	Hi-Z	O	O	
PH1 AINA1 INT1	Hi-Z	O	O	
PH0 AINA0 INT0	Hi-Z	O	O	
AMPVSS				
AMPVDD				

Table 2.2 Operating voltage of each Pin

Pin name	Operating voltage	
X1,X2	Internal 1.5V/CVSS	
RESET	DVDD5/DVSS	
BW0	DVDD5/DVSS	Need to connect GND
CVREFABC, CVREFD	AMPVDD/AMPVSS	Compare voltage input between comparator ABC and comparator D
I/O (PAx,PCx-PGx,PMx)	DVDD5/DVSS	
I/O(PBx)	DVDD5/DVSS	
AIN(PHx-PKx)	AVDDA/AVSSB AVddb/AVSSB	

Table 2.3 voltage range of each pin

Pin name	Voltage range	
DVDD5	4.5~5.5V	For I/O ports
VINREG5		For internal circuit
AVDDx		For ADCs
AMPVDD		For operational amp and comparator
DVDE		Need to connect DVDD5
VOUT15	1.35~1.65V	Output terminal of internal power supply. Connect to DVSS through 1~4.7uF capacitor
VOUT3	2.7~3.6V	Output terminal of internal power supply. Connect to DVSS through 1~4.7uF capacitor
DVSS	GND	
CVSS		
AVSSx		
AMPVSS		

## 3 Processor Core and Debug Interface

### 3.1 Processor Core

The TX03 series has a high-performance 32-bit processor core (the ARM Cortex-M3 processor core). For information on the operations of this processor core, please refer to the “Cortex-M3 Technical Reference Manual” issued by ARM Limited. This chapter describes the functions unique to the TX03 series that are not explained in that document.

The following table shows the revision of the processor core in the TMPM370FY. For further information on each revision, see the documents issued by ARM Limited.

Product Name	Core Revision
TMPM370FY	r2p0-00rel0

The Cortex-M3 core has the optional blocks. The optional blocks of the revision r2p0 are ETM™ and MPU. Not MPU but ETM is contained in the TMPM370FY.

### 3.2 Reset operation

#### 3.2.1 Initial state

The internal circuits, register settings and pin status are undefined right after the power-on. The state continues until the  $\overline{\text{RESET}}$  pin receives low level input after all the power supply voltage is applied.

#### 3.2.2 Reset operation

As the precondition, ensure that an internal high-frequency oscillator provides stable oscillation while power supply voltage is in the operating range. To reset the TMPM370, input  $\overline{\text{RESET}}$  signal at low level for a minimum duration of 12 system clocks (1.2 $\mu$ s with external 10MHz oscillator).

#### 3.2.3 After Reset

When the reset is released, the system control register and the internal I/O register of the Cortex-M3 processor core are initialized. Note that the PLL multiplication circuit stops after releasing the reset. Therefore, set the PLLSEL register to use PLL multiplication circuit once again.

After the reset exception handling is executed, the program branches off to the interrupt service routine. The address with which the interrupt service routine starts is stored in 0x0000\_0004H

(Note 1) Set the  $\overline{\text{RESET}}$  pin to "0" before turning the power on. Release the reset after the power supply voltage has stabilized sufficiently within the operating range.

(Note 2) The reset operation may alter the internal RAM state.

### 3.3 Debug Interface

#### 3.3.1 Specification Overview

The TMPM370 contains the Serial Wire JTAG Debug Port (SWJ-DP) unit for interfacing with the In-Circuit Emulator (ICE) and the Embedded Trace Macrocell™ (ETM) unit for instruction trace output. Trace data is output to the dedicated pins (TRACEDATA[0]-[1], SWV) via the on-chip Trace Port Interface Unit (TPIU).

For details about SWJ-DP, ETM and TPIU, refer to “Cortex-M3 Technical Reference Manual”.

#### 3.3.2 Features of SWJ-DP

SWJ-DP supports the two-pin Serial Wire Debug Port (SWDCK, SWDIO) and the JTAG Debug Port (TDI, TDO, TMS, TCK, TRST).

#### 3.3.3 Features of ETM

ETM supports two data signal pins (TRACEDATA[0]-[1]), one clock signal pin (TRACECLK) and trace output from SWV.

#### 3.3.4 Pin Functions

The debug interface pins can also be used as general-purpose ports. The PB3 and PB4 pins are shared between the JTAG debug port function and the serial wire debug port function. The PB5 pin is shared between the JTAG debug port function and the SWV trace output function.

After reset, the PB3, PB4, PB5, PB6 and PB7 pins are configured as debug port function pins. The functions of other debug interface pins need to be programmed as required.

When using a low power consumption mode, take note of the following points.

(Note 1) If PB3 and PB5 are configured as debug function pins, output continues to be enabled even in STOP mode regardless of the setting of the STBYCR2<DRVE> bit .

(Note 2) If PB4 is configured as a debug function pin, it prevents a low power consumption mode from being fully effective. Configure PB4 to function as a general-purpose port if the debug function is not used.

The table below summarizes the debug interface pin functions and related port settings after reset.

Pin Number	Port (Bit Name)	Debug Function	Port Settings after Reset				
			Function (PxFR)	Input (PxIE)	Output (PxCR)	Pull-up (PxPUP)	Pull-down (PxPDN)
63	PB0	TRACECLK	x	x	x	x	-
64	PB1	TARCEDATA[0]	x	x	x	x	-
65	PB2	TRACEDATA[1]	x	x	x	x	-
66	PB3	TMS/ SWDIO	o	o	o	o	-
67	PB4	TCK/ SWCLK	o	o	x	-	o
68	PB5	TDO/ SWV	o	x	o	x	-
69	PB6	TDI	o	o	x	o	-
70	PB7	TRST	o	o	x	o	-

o: Enabled x: Disabled

### 3.3.5 Connection with a Debug Tool

For how to connect a debug tool, refer to the method recommended by each manufacturer.



## 4 Memory Map

The memory maps for the TMPM370FY are based on the ARM Cortex-M3 processor core memory map. The internal ROM, internal RAM and internal I/O of the TMPM370FY are mapped to the code, SRAM and peripheral regions of the Cortex-M3 respectively. The SRAM and internal I/O regions are all included in the bit-band region.

The CPU register region is the processor core's internal register region.

For more information on each region, see the "Cortex-M3 Technical Reference Manual".

Note that access to regions indicated as "Fault" causes a memory fault if memory faults are enabled or a hard fault if memory faults are disabled. Do not access the vendor-specific region.

See Chapter 21 "Special Function Registers" for details on the internal I/O region.

### 4.1 Memory Map

Fig 4-1 shows the memory map of the TMPM370FY.

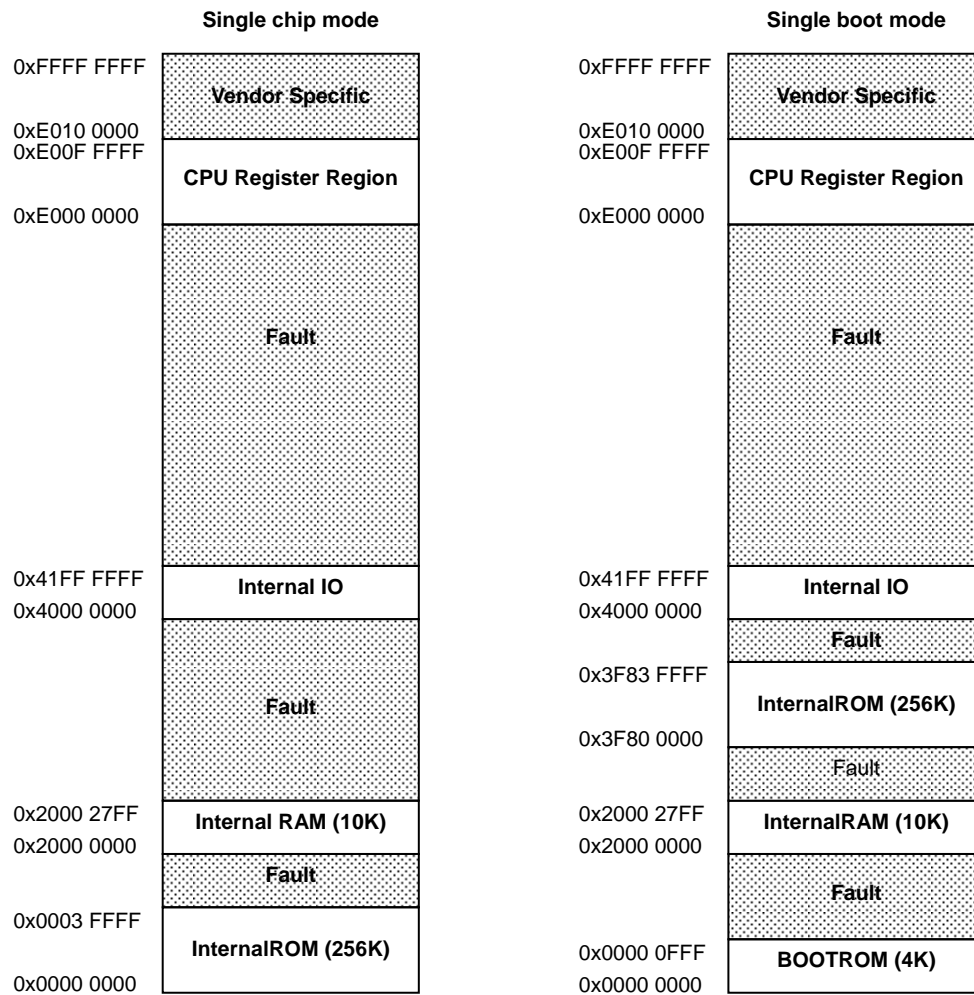


Fig 4-1 Memory Map

## 5 Clock/Mode Control

### 5.1 Features

The clock/mode control block enables to select clock gear, prescaler clock and warm-up of the PLL (including clock multiplication circuit) and oscillator.

The low power consumption mode can reduce power consumption.

This chapter describes how to control clocks, clock operating modes and mode transitions.

The clock/mode control block has the following functions:

- Controls the system clock.
- Controls the prescaler clock.
- Controls the PLL multiplication circuit.
- Controls the warm-up timer.

In addition to NORMAL mode, the TMPM370FY can operate in two types of low power mode to reduce power consumption according to its usage conditions.

## 5.2 Registers

### 5.2.1 Register List

Table 5-1 shows registers and addresses of the clock generator.

Table 5-1 Registers of Clock Generator

Register name		Address
System control register 0	SYSCR0	0x4004_0200
System control register 1	SYSCR1	0x4004_0201
System control register 2	SYSCR2	0x4004_0202
Oscillation control register 0	OSCCR0	0x4004_0204
Oscillation control register 1	OSCCR1	0x4004_0205
Oscillation control register 2	OSCCR2	0x4004_0206
Oscillation control register 3	OSCCR3	0x4004_0207
Standby control register 0	STBYCR0	0x4004_0208
Standby control register 1	STBYCR1	0x4004_0209
Standby control register 2	STBYCR2	0x4004_020A
PLL selection register	PLLSEL	0x4004_020C
System clock selection register	CKSEL	0x4004_0210

## 5.2.2 Detailed Description of Registers

### 5.2.2.1 System Control Register

		<b>7</b>	<b>6</b>	<b>5</b>	<b>4</b>	<b>3</b>	<b>2</b>	<b>1</b>	<b>0</b>
SYSCR0	Bit symbol	-	-	-	-	-	GEAR2	GEAR1	GEAR0
	Read/Write	R					R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.					High-speed clock (fc) gear 000: fc                   100: fc/2 001: reserved           101: fc/4 010: reserved           110: fc/8 011: reserved           111: fc/16		
		<b>15</b>	<b>14</b>	<b>13</b>	<b>12</b>	<b>11</b>	<b>10</b>	<b>9</b>	<b>8</b>
SYSCR1	Bit symbol	-	-	-	FPSEL	-	PRCK2	PRCK1	PRCK0
	Read/Write	R			R/W	R	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.			fperiph 0:fgear 1:fc	"0" is read.	Prescaler clock 000: fperiph           100: fperiph/16 001: fperiph/2       101: fperiph/32 010: fperiph/4       110: Reserved 011: fperiph/8       111: Reserved		
		<b>23</b>	<b>22</b>	<b>21</b>	<b>20</b>	<b>19</b>	<b>18</b>	<b>17</b>	<b>16</b>
SYSCR2	Bit symbol	-	-	-	-	-	-	-	-
	Read/Write	R						R/W	R/W
	After reset	0	0	0	0	0	0	0	1
	Function	"0" is read.						Reserved	

<Bit 2:0><GEAR 2:0> : Specifies the high-speed clock (fc) gear.

<Bit 10:8><PRCK 2:0> : Specifies the prescaler clock to peripheral I/O.

<Bit 12><FPSEL> : Specifies the source clock to fperiph.

## 5.2.2.2 Oscillation Control Register

		<b>7</b>	<b>6</b>	<b>5</b>	<b>4</b>	<b>3</b>	<b>2</b>	<b>1</b>	<b>0</b>
OSCCR0	Bit symbol	-	-	-	-	WUPSEL	PLLON	WUEF	WUEON
	Read/Write	R	-	-	-	R/W	R/W	R	W
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.				Warm-up counter 0: X1 1: Reserved	PLL operation 0: Stop 1: Oscillation	Status of Warm-up timer (WUP) 0: warm-up completed 1: Warm-up in operation	Operation of warm-up timer (WUP) 0: don't care 1: starting warm-up
		<b>15</b>	<b>14</b>	<b>13</b>	<b>12</b>	<b>11</b>	<b>10</b>	<b>9</b>	<b>8</b>
OSCCR1	Bit symbol	WUODR1	WUODR0	-	DRVOSCH	-	-	-	XEN
	Read/Write	R/W		R/W	R/W	R		R/W	R/W
	After reset	0	0	0	0	0	0	0	1
	Function	Bit1:0 for warm-up counter value. Write "00".		Write "0".	Current control for high_speed oscillator 0: Large current 1: Small current	"0" is read.		Write "0".	High-speed oscillator 0: Stop 1: Oscillation
		<b>23</b>	<b>22</b>	<b>21</b>	<b>20</b>	<b>19</b>	<b>18</b>	<b>17</b>	<b>16</b>
OSCCR2	Bit symbol	WUODR5	WUODR4	WUODR3	WUODR2	-	-	-	-
	Read/Write	R/W				R/W	R/W	R/W	R/W
	After reset	0	0	0	0	1	1	1	0
	Function	Bit5:2 for warm-up counter value.				Write "1".	Write "1".	Write "1".	Write "0".
		<b>15</b>	<b>14</b>	<b>13</b>	<b>12</b>	<b>11</b>	<b>10</b>	<b>9</b>	<b>8</b>
OSCCR3	Bit symbol	WUODR13	WUODR12	WUODR11	WUODR10	WUODR9	WUODR8	WUODR7	WUODR6
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	1	1
	Function	Bit13:6 for warm-up counter value.							

<Bit 0><WUEON> : Enables to start the warm-up timer.

<Bit 1><WUEF> : Enables to monitor the status of the warm-up timer.

<Bit 2><PLLON> : Specifies operation of the PLL.  
It stops after reset. Setting the bit is required.

<Bit 3><WUPSEL> : Write "0" to WUPSEL.

<Bit 8><XEN> : Specifies operation of the high-speed oscillator.

<Bit 12><DRVOSCH> : Specifies the current of high\_speed oscillator.

<Bit 31:24, 23:20, 15:14><WUODR 13:0> : Warm-up counter value.

(Note 1) Always write "0" to bit3, bit9 bit13 and bit16.

(Note 2) Always write "1" to bit17, bit18 and bit19.

(Note 3) Always write "0" to bit15 and bit14 in OSCCR1.

## 5.2.2.3 Standby Control Register

	7	6	5	4	3	2	1	0	
STBYCR0	Bit symbol	-	-	-	-	-	STBY2	STBY1	STBY0
	Read/Write	R					R/W	R/W	R/W
	After reset	0	0	0	0	0	1	1	
	Function	"0" is read.					Low power consumption mode  000: Reserved 001: STOP 010: Reserved 011: IDLE 100: Reserved 101: Reserved 110: Reserved 111: Reserved		
	15	14	13	12	11	10	9	8	
STBYCR1	Bit symbol	-	-	-	-	-	-	RXEN	
	Read/Write	R						R/W	R/W
	After reset	0	0	0	0	0	0	1	
	Function	"0" is read.						Write "0".	High-speed oscillator after releasing STOP mode  0: Stop 1: Oscillation
	23	22	21	20	19	18	17	16	
STBYCR2	Bit symbol	-	-	-	-	-	-	DRVE	
	Read/Write	R						R/W	R/W
	After reset	0	0	0	0	0	0	0	
	Function	"0" is read.						Write "0".	Pin status in STOP mode  0: Active 1: Inactive
	31	30	29	28	27	26	25	24	
	Bit symbol	-	-	-	-	-	-	-	
	Read/Write	R							
	After reset	0	0	0	0	0	0	0	
	Function	"0" is read.							

<Bit 2:0><STBY2:0> : Specifies the low power consumption mode.

<Bit 8><RXEN> : Specifies the high-speed oscillator operation after releasing the STOP mode.

<Bit 16><DRVE> : Specifies the pin status in the STOP mode.

## 5.2.2.4 PLL Selection Register

	<b>7</b>	<b>6</b>	<b>5</b>	<b>4</b>	<b>3</b>	<b>2</b>	<b>1</b>	<b>0</b>
PLLSEL	Bit symbol	-	-	-	-	-	-	PLLSEL
	Read/Write	R/W						R/W
	After reset	0	0	1	1	1	1	0
	Function	Reserved						Use of PLL 0: X1 1: Use PLL
	<b>15</b>	<b>14</b>	<b>13</b>	<b>12</b>	<b>11</b>	<b>10</b>	<b>9</b>	<b>8</b>
	Bit symbol	-	-	-	-	-	-	-
	Read/Write	R/W			R	R/W	R/W	R/W
	After reset	1	0	1	0	0	0	1
	Function	Reserved			"0" is read.	Reserved		Reserved

<Bit 0><PLLSEL> : Specifies use or disuse of the clock multiplied by the PLL.  
 "X1" is automatically set after reset. Resetting is required when using the PLL.



## 5.2.2.5 System Clock Selection Register

CKSEL		<b>7</b>	<b>6</b>	<b>5</b>	<b>4</b>	<b>3</b>	<b>2</b>	<b>1</b>	<b>0</b>
	Bit symbol	-	-	-	-	-	-	SYSCK	SYSCK FLG
	Read/Write	R						R/W	R
	After reset	0	0	0	0	0	0	0	0
Function	"0" is read.						System clock 0: High-speed (fc) 1: Reserved	System clock status 0: High-speed (fc) 1: Reserved	
		<b>15</b>	<b>14</b>	<b>13</b>	<b>12</b>	<b>11</b>	<b>10</b>	<b>9</b>	<b>8</b>
Bit symbol	-	-	-	-	-	-	-	-	-
Read/Write	R								
After reset	0	0	0	0	0	0	0	0	0
Function	"0" is read.								
		<b>23</b>	<b>22</b>	<b>21</b>	<b>20</b>	<b>19</b>	<b>18</b>	<b>17</b>	<b>16</b>
Bit symbol	-	-	-	-	-	-	-	-	-
Read/Write	R								
After reset	0	0	0	0	0	0	0	0	0
Function	"0" is read.								
		<b>31</b>	<b>30</b>	<b>29</b>	<b>28</b>	<b>27</b>	<b>26</b>	<b>25</b>	<b>24</b>
Bit symbol	-	-	-	-	-	-	-	-	-
Read/Write	R								
After reset	0	0	0	0	0	0	0	0	0
Function	"0" is read.								

<Bit 0><SYSCKFLG> : Shows the status of the system clock.

<Bit 1><SYSCK> : Write "0" to SYSCK.

## 5.3 Clock Control

### 5.3.1 Clock System Block Diagram

Fig.5-1 shows the clock system diagram. Each clock is defined as follows.

- fosc : Clock input from the X1 and X2 pins
- fpll : Clock octupled by PLL
- fc : Clock specified by PLLSEL<PLLSEL> (high-speed clock)
- fgear : Clock specified by SYSCR1<GEAR2:0>
- fsys : The same clock as fgear (system clock)
- fperiph : Clock specified by SYSCR1<FPSEL>
- $\Phi T0$  : Clock specified by SYSCR1<PRCK2:0> (prescaler clock)

The high-speed clock fc and the prescaler clock  $\Phi T0$  are dividable.

- High-speed clock: fc, fc/2, fc/4, fc/8, fc/16
- Prescaler clock: fperiph, fperiph/2, fperiph/4, fperiph/8, fperiph/16, fperiph/32

### 5.3.2 Initial Values after Reset

Reset initializes the clock configuration as follows.

- High-speed oscillator : ON (oscillating)
- PLL (phase locked loop circuit) : OFF (stop)
- High-speed clock gear : fc (no frequency dividing)

Reset causes all the clock configurations to be the same as fosc.

- fc = fosc
- fsys = fc (=fosc)
- fperiph = fc (=fosc)
- $\Phi T0$  = fperiph (=fosc)

For example, reset configures fsys as 10MHz when a 10MHz oscillator is connected to the X1 or X2 pin.

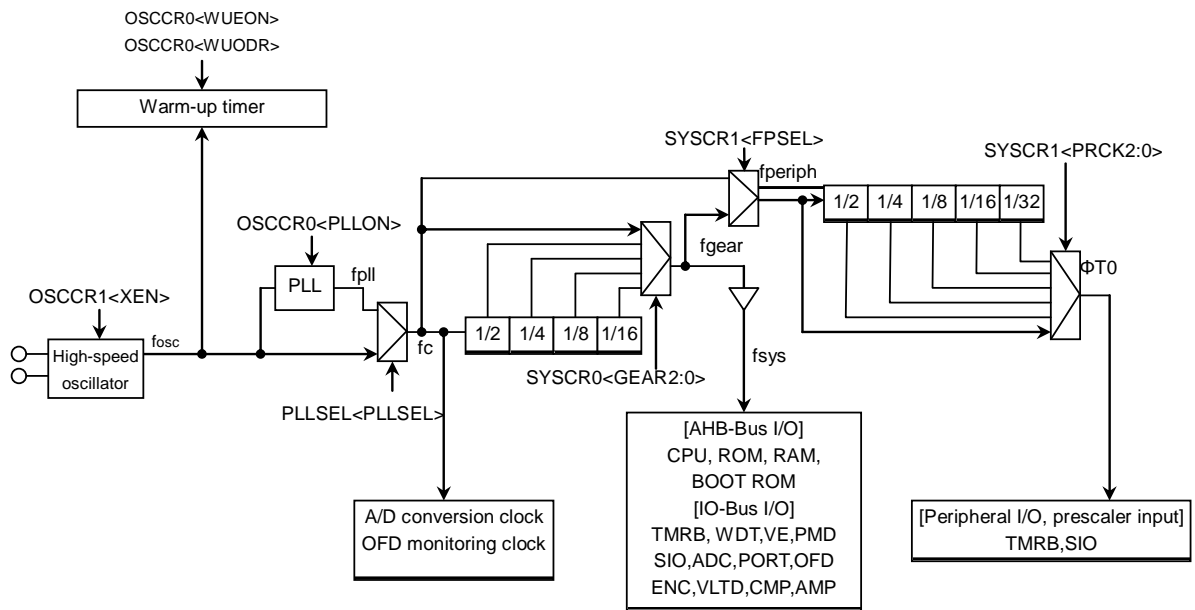


Fig.5-1 Clock Block Diagram

**(Note)** The input clocks to selector shown with an arrow are set as default after reset.

### 5.3.3 Clock Multiplication Circuit (PLL)

This circuit outputs the fpll clock that is octuple of the high-speed oscillator output clock, fosc. This lowers the oscillator input frequency while increasing the internal clock speed.

The PLL is disabled after reset is released. To enable the PLL, set "1" to the OSCCR0<WUEF> bit. The PLL requires a certain amount of time to be stabilized, which should be secured using the warm-up function.

**(Note)** It takes approx. 200μs for the PLL to be stabilized

### 5.3.4 Warm-up Function

The warm-up function secures the stability time for the oscillator and the PLL with the warm-up timer.

The warm-up function is used when returning from STOP mode. In this case, an interrupt for returning from the low power consumption mode triggers the automatic timer count. After the specified time is reached, the system clock is output and the CPU starts operation.

In STOP modes, the PLL is disabled. When returning from these modes, configure the warm-up time in consideration of the stability time of the PLL and the internal oscillator.

#### How to configure the warm-up function

Specify the count up clock for the warm-up counter in the OSCCR0<WUPSEL> bit. Write "0" to WUPSEL.

The warm-up time can be specified by setting the OSCCR<WUODR13:0>. The OSCCR0<WUEON><WUEF> is used to confirm the start and completion of warm-up through software (instruction).

**(Note)** The warm-up timer operates according to the oscillation clock, and it may contain errors if there is any fluctuation in the oscillation frequency. Therefore, the warm-up time should be taken as approximate time.

The following are the examples of the warm-up function configuration.

<Example Securing the stability time fro the PLL>

OSCCR0<WUPSEL>="0" : Specify the warm-up counter

OSCCR<WUPODR13:0>=<WUPODR 13:0> x (4/fosc)

: Specify the warm-up time

OSCCR0<WUEON>="1" : Start the warm-up timer (WUP)

OSCCR0<WUEF> Read : Wait until the state becomes "0" (warm-up is finished)

**(Note)** Always write "0" to bit15 and bit14 in OSCCR1.

### 5.3.5 System Clock

The TMPM370 offers high-speed clock as system clock. The high-speed clock is dividable.

- Input frequency from X1 and X2: 8MHz to 10MHz
- Clock gear: 1/1, 1/2, 1/4, 1/8, 1/16 (after reset: 1/1)

Table 5-2 Range of High-frequency (Unit:MHz)

Input freq. from X1 and X2	Min. operating freq.	Max. operating freq.	After reset (PLL=OFF, CG=1/1)	Clock gear (CG) @PLL=ON					Clock gear (CG) @PLL=OFF				
				1/1	1/2	1/4	1/8	1/16	1/1	1/2	1/4	1/8	1/16
8MHz	1MHz	80MHz	8MHz	64	32	16	8	4	8	4	2	1	0.5
10MHz			10MHz	80	40	20	10	5	10	5	2.5	1.25	0.625

\* PLL=ON/OFF setting: available in OSCCR0<PLLON>  
Clock gear setting: available in SYSCR0<GEAR2:0>

**(Note)** Switching of clock gear is executed when a value is written to the SYSCR0<GEAR2:0> register. The actual switching takes place after a slight delay.

### 5.3.6 Prescaler Clock Control

Each peripheral function (TMRB0-7 and SIO0-3) has a prescaler for dividing a clock. As the clock  $\phi T0$  to be input to each prescaler, the "fperiph" clock specified in the SYSCR1<FPSEL> can be divided according to the setting in the SYSCR1<PRCK2:0>. After the controller is reset, fperiph is selected as  $\phi T0$ .

**(Note)** To use the clock gear, ensure that you make the time setting such that prescaler output  $\phi Tn$  from each peripheral function is slower than fsys ( $\phi Tn < fsys$ ). Do not switch the clock gear while the timer counter or other peripheral function is operating.

## 5.4 Modes and Mode Transitions

### 5.4.1 Mode Transitions

The NORMAL mode uses the high-speed clock for system clock.

The IDLE and STOP modes can be used as the low power consumption mode that enables to reduce power consumption by halting processor core operation.

Fig.5-2 shows a mode transition diagram

For a description of sleep-on-exit, refer to “Cortex-M3 Technical Reference Manual”.

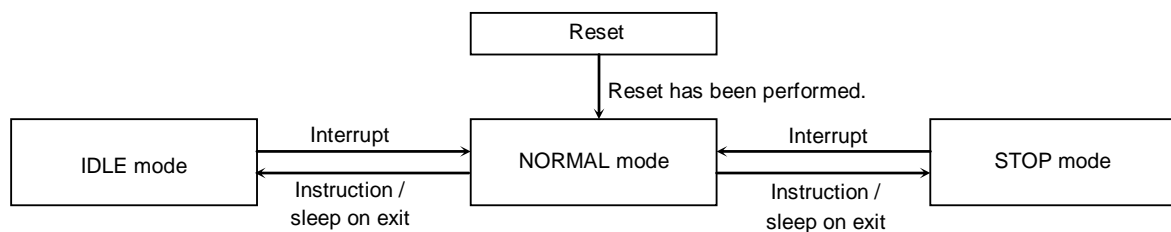


Fig.5-2 Mode Transition Diagram

## 5.5 Operation Modes

As an operation mode, NORMAL is available. The features of NORMAL mode are described below.

### 5.5.1 NORMAL Mode

This mode is to operate the CPU core and the peripheral hardware by using the high-speed clock. It is shifted to the NORMAL mode after reset.

## 5.6 Low Power Consumption Modes

The TMPM370 has two low power consumption modes: IDLE and STOP. To shift to the low power consumption mode, specify the mode in the system control register STBYCR0<STBY2:0> and execute the WFI (Wait For Interrupt) instruction. In this case, execute reset or generate the interrupt to release the mode. Releasing by the interrupt requires settings in advance. See chapter 6 for details.

**(Note 1)** Transition to the low power consumption mode by executing the WFE (Wait For Event) instruction is prohibited as the TMPM370 does not offer any event for releasing the low power consumption mode.

**(Note 2)** The TMPM370 does not support the low power consumption mode configured with the SLEEPDEEP bit in the Cortex-M3 core. Setting the SLEEPDEEP bit of the system control register is prohibited.

The features of each mode are described as follows.



### 5.6.1 IDLE Mode

Only the CPU is stopped in this mode.

Each peripheral function has one bit in its control register for enabling or disabling operation in the IDLE mode. When the IDLE mode is entered, peripheral functions for which operation in the IDLE mode is disabled stop operation and hold the state at that time.

The following peripheral functions can be enabled or disabled in the IDLE mode. For setting details, see the chapter on each peripheral function.

- 16-bit timer/event counter (TMRB)
- Serial channel (SIO)
- Watchdog timer (WDT)
- Vector Engine (VE)

### 5.6.2 STOP Mode

All the internal circuits including the internal oscillator are brought to a stop.

By releasing the STOP mode, the device returns to the preceding mode of the STOP mode and starts operation.

The STOP mode enables to select the pin status by setting the STBYCR2<DRVE>. Table 5-33 shows the pin status in the STOP mode.

**(Note)** When PB4 is configured as a debug function pin, it prevents the low power consumption mode from being fully effective. Configure PB4 to function as a general-purpose port when the debug function is not used.

Table 5-3 Pin States in STOP Mode

	Pin Name	I/O	<DRVE>=0	<DRVE>=1
Not Ports	X1	Input only	×	×
	X2	Output only	"H" level output	"H" level output
	RESET, BW0	Input only	○	○
Ports	PB3, PB5 [When used as a debug pin (PBFR<n>=1) and output is enabled (PBCR<n>=1)]	Input	×	Depends on PxIE<n>.
		Output	Enabled when data is valid. Disabled when data is invalid.	Enabled when data is valid. Disabled when data is invalid.
	PH0-2, PA0, PA2, PE4, PE6-7, PA7, PD3, PL0-1, PJ6-7, PK0-1 [When used as an interrupt pin (PxFR<n>=1) and input is enabled (PxIE<n>=1)]	Input	○	○
		Output	×	Depends on PxCR<n>.
	Other port pins	Input	×	Depends on PxIE<n>.
		Output	×	Depends on PxCR<n>.

○ : Input or output enabled

× : Input or output disabled.

### 5.6.3 Low power Consumption Mode Setting

The low power consumption mode is specified by the setting of the standby control register STBYCR<STBY2:0>.

Table 5-44 shows the mode setting in the <STBY2:0>.

Table 5-4 Low power consumption mode setting

Mode	STBYCR0 <STBY2:0>
STOP	001
IDLE	011

**(Note)** Do not set any value other than those shown above in <STBY2:0>.

### 5.6.4 Operational State in Each Mode

Table 5-55 show the operational state in each mode.

For I/O port, “o” and “x” indicate that input/output is enabled and disabled respectively. For other functions, “o” and “x” indicate that clock is supplied and is not supplied respectively.

Table 5-5 Operational State in Each Mode

Block	NORMAL	IDLE	STOP
Processor core	o	x	x
I/O port	o	o	* (Note 1)
PMD	o	o	x
ENC	o	o	x
ADC	o	o	x
VE	o	ON/OFF selectable for each module	x
SIO	o		x
TMRB	o		x
WDT	o		x
AMP/CMP	o	o	o
VLTD	o	o	o
POR	o	o	o
CG	o	o	x
PLL	o	o	x
High-speed oscillator (fc)	o	o	x

o: Operating, x: Stopped

**(Note 3)** The state depends on the SYSCR2<DRVE> bit.

## 5.6.5 Releasing the Low Power Consumption Mode

The low power consumption mode can be released by an interrupt request or reset. The release source that can be used is determined by the low power consumption mode selected. Details are shown in Table 5-66.

Table 5-6 Release Source in Each Mode

Low power consumption mode			IDLE	STOP
Release source	Interrupt	INTWDT	○	×
		INT0 to INTF (Note 1)	○	○
		INTRX0 to 3, INTTX0 to 3	○	×
		INTVCNA, INTVCNB	○	×
		INTEMG0 to 1	○	×
		INTOVV0 to 1	○	×
		INTTB0 to 7	○	×
		INTPMD0 to 1	○	×
		INTENC0 to 1	○	×
		INTCAP00, 01, 10, 11, 20, 21, 30, 31, 40, 41, 50, 51, 60, 61, 70, 71	○	×
		INTAD0PDA, INTAD1PDA, INTAD0PDB, INTAD1PDB	○	×
		INTAD0CPA, INTAD1CPA, INTAD0CPB, INTAD1CPB	○	×
		INTAD0SFT, INTAD1SFT	○	×
		INTAD0TMR, INTAD1TMR	○	×
		RESET (RESET pin)	○	○

○: Starts the interrupt handling after the mode is released. (The reset initializes the LSI).

×: Unavailable

**(Note 1)** To release the low power consumption mode by using the level mode interrupt, keep the level until the interrupt handling is started. Changing the level before then will prevent the interrupt handling from starting properly.

**(Note 2)** For shifting to the low power consumption mode, set the CPU to prohibit all the interrupts other than the release source. If not, releasing may be executed by an unspecified interrupt.

- Release by interrupt request

To release the low power consumption mode by an interrupt, the CPU must be set in advance to detect the interrupt. In addition to the setting in the CPU, the clock generator must be set to detect the interrupt to be used to release the STOP modes.

- Release by reset

Any low power consumption modes can be released by reset from the RESET pin. After that, the mode switches to NORMAL and all the registers are initialized as is the case with normal reset.

Note that returning to NORMAL mode by reset does not induce the automatic warm-up. Keep the reset signal valid until the oscillator operation becomes stable.

Refer to "Interrupts" for details.

### 5.6.6 Warm-up

Mode transition may require the warm-up so that the internal oscillator provides stable oscillation.

In the mode transition from STOP to NORMAL, the warm-up counter is activated automatically. And then the system clock output is started after the elapse of configured warm-up time. It is necessary to set the oscillator to be used for warm-up in the OCCR0<WUPSEL> and to set the warm-up time in the OSCCR<WUODR13:0> before executing the instruction to enter the STOP mode.

**(Note)** In STOP mode, the PLL is disabled. When returning from these modes, configure the warm-up time in consideration of the stability time of the PLL and the internal oscillator. It takes approx. 200 $\mu$ s for the PLL to be stabilized.

Table 5- shows whether the warm-up setting of each mode transition is required or not.

Table 5-7 Warm-up setting in mode transition

Mode transition	Warm-up setting
NORMAL→IDLE	Not required
NORMAL→STOP	Not required
IDLE→NORMAL	Not required
STOP→NORMAL	Auto-warm-up (Note 1)

**(Note 1)** Returning to NORMAL mode by reset does not induce the automatic warm-up. Keep the reset signal valid until the oscillator operation becomes stable.

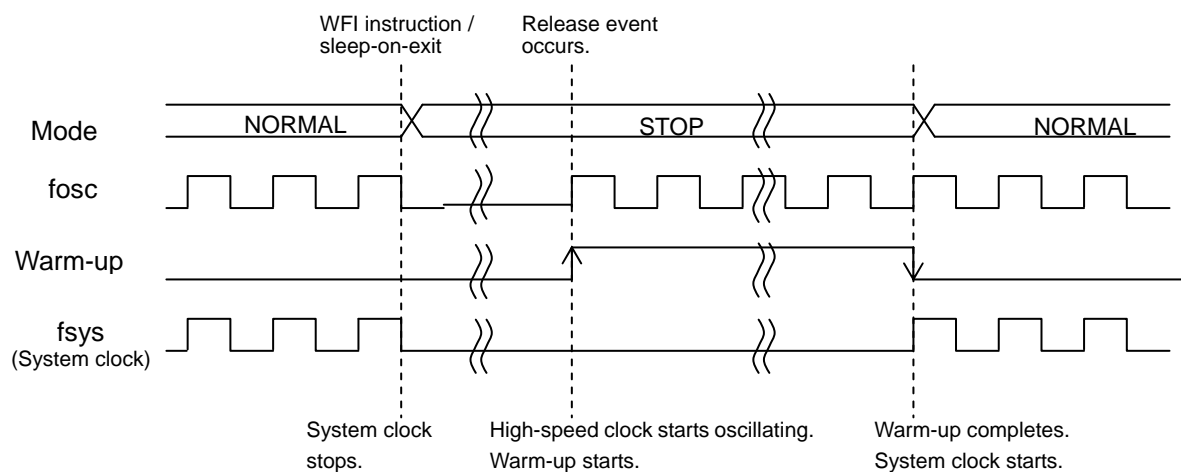
## 5.6.7 Clock Operations in Mode Transition

The clock operations in mode transition are described in the following section.

### 5.6.7.1 Transition of operation modes: NORMAL→STOP→NORMAL

When returning to NORMAL mode from STOP mode, the warm-up is activated automatically. It is necessary to set the warm-up time before entering the STOP mode.

Returning to NORMAL mode by reset does not induce the automatic warm-up. Keep the reset signal asserted until the oscillator operation becomes stable.



## 6. Exceptions

This chapter describes features, types and handling of exceptions.

Exceptions have close relation to the CPU core. Refer to “Cortex-M3 Technical Reference Manual” if needed.

### 6.1 Overview

An exception causes the CPU to stop the currently executing process and handle another process. There are two types of exceptions: those that are generated when some error condition occurs or when an instruction to generate an exception is executed; and those that are generated by hardware, such as an interrupt request signal from an external pin or peripheral function.

All exceptions are handled by the Nested Vectored Interrupt Controller (NVIC) in the CPU according to the respective priority levels. When an exception occurs, the CPU stores the current state to the stack and branches to the corresponding interrupt service routine (ISR). Upon completion of the ISR, the information stored to the stack is automatically restored.

#### 6.1.1 Exception Types



The following types of exceptions exist in the Cortex-M3.

For detailed descriptions on each exception, refer to “Cortex-M3 Technical Reference Manual”.

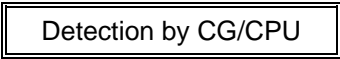

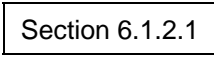
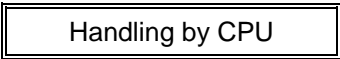

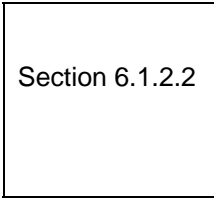
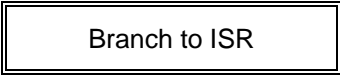

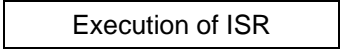

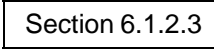
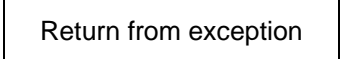
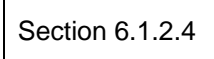
- Reset
- Non-Maskable Interrupt (NMI)
- Hard Fault
- Memory Management
- Bus Fault
- Usage Fault
- SVCcall (Supervisor Call)
- Debug Monitor
- PendSV
- SysTick
- External Interrupt

### 6.1.2 Handling Flowchart

The following shows how an exception/interrupt is handled.

 indicates hardware handling.  Indicates software handling.

Each step is described later in this chapter.

Processing	Description	See
 Detection by CG/CPU 	The CG/CPU detects the exception request.	 Section 6.1.2.1
 Handling by CPU 	The CPU handles the exception request.	 Section 6.1.2.2
 Branch to ISR 	The CPU branches to the corresponding interrupt service routine (ISR).	
 Execution of ISR 	Necessary processing is executed.	 Section 6.1.2.3
 Return from exception	The CPU branches to another ISR or returns to the previous program.	 Section 6.1.2.4

### 6.1.2.1 Exception Request and Detection

#### (1) Exception occurrence

Exception sources include instruction execution by the CPU, memory accesses, and interrupt requests from external interrupt pins or peripheral functions.

An exception by CPU instruction execution is caused when the CPU executes an instruction that generate an exception or when an error condition occurs during instruction execution.

An exception also occurs by an instruction fetch from the Execute Never (XN) region or an access violation to the Fault region.

An interrupt is generated from an external interrupt pin or peripheral function. For interrupts that are used for releasing a standby mode, relevant settings must be made in the clock generator. For details, refer to “6.5 Interrupts”.

#### (2) Exception detection

If multiple exceptions occur simultaneously, the CPU takes the exception with the highest priority. Table 6-1 shows the priority of exceptions. “Configurable” means that it is possible to assign a priority level to that exception. Memory Management, Bus Fault and Usage Fault exceptions can be enabled or disabled. If a disabled exception occurs, it is handled as Hard Fault.



Table 6-1 Exception Types and Priority

No	Exception type	Priority	Description
1	Reset	-3 (highest)	Reset pin, WDT or SYSRETRREQ
2	Non-Maskable Interrupt	-2	WDT or LTDV
3	Hard Fault	-1	Fault that cannot activate because a higher-priority fault is being handled or it is disabled
4	Memory Management	Configurable	Exception from the Memory Protection Unit (MPU) (Note 1) Instruction fetch from the Execute Never (XN) region
5	Bus Fault	Configurable	Access violation to the Hard Fault region of the memory map
6	Usage Fault	Configurable	Undefined instruction execution or other faults related to instruction execution
7-10	Reserved		
11	SVCa l l	Configurable	System service call with SVC instruction
12	Debug Monitor	Configurable	Debug monitor when the core is not halting
13	Reserved		
14	PendSV	Configurable	Pendable system service request
15	SysT ick	Configurable	Notification from system timer
16-	External Interrupt	Configurable	Configurable External interrupt pin or peripheral function (Note 2)

**(Note 1)** This product does not contain the MPU

**(Note 2)** External interrupts have different sources and numbers in each product. For details, see “List of Interrupt Factors”.

### (3) Priority setting

Use the Interrupt Priority Registers to assign a priority to each of the external interrupts. The priority of other exceptions can be set in the System Handler Priority Registers.

The priority registers are configurable, allowing the number of bits for setting priority levels to vary between three to eight bits. Therefore, the range of priority levels that can be assigned vary with each product.

In case of eight bits, a priority level can be set from 0 to 255. Priority level 0 is the highest priority level.

In case of the same priority level to multiple exceptions, the lowest-numbered exception has the highest priority.

**(Note)** In this product, three bits are used for assigning a priority level in the Interrupt Priority Registers and System Handler Priority Registers.

### 6.1.2.2 Exception Handling and Branch to the Interrupt Service Routine (Pre-emption)

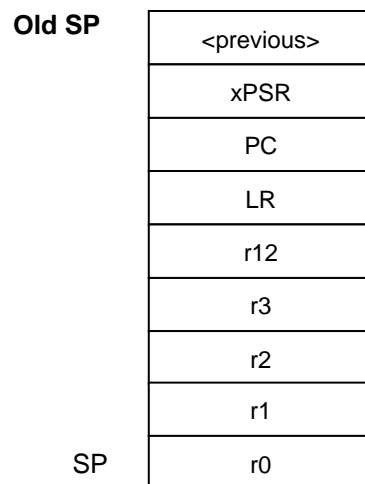
When an exception occurs, the CPU suspends the currently executing process and branches to the interrupt service routine. This is called “pre-emption”.

#### (1) Stacking

When the CPU detects an exception, it pushes the contents of the following eight registers to the stack in the following order:

- Program Counter (PC)
- Program Status Register (xPSR)
- r0 - r3
- r12
- Link Register (LR )

The SP is decremented by eight words by the completion of the stack push. The following shows the state of the stack after the register contents have been pushed.



#### (2) Fetching an ISR

At the same time as pushing the register contents to the stack, the CPU executes an instruction to fetch an ISR.

Prepare a vector table containing the top addresses of ISRs for each exception. After reset, the vector table is located at address 0x0000\_0000 in the code space. By setting the Vector Table Offset Register, it is possible to place the vector table at any address in the code or SRAM space.

The vector table should also contain the initial value of the main stack.

### (3) Late-arriving

If the CPU detects a higher priority exception before executing the ISR for a previous exception, the CPU handles the higher priority exception first. This is called "late-arriving".

A late-arriving exception causes the CPU to fetch a new vector address for branching to the corresponding ISR, but the CPU does not newly push the register contents to the stack.

### (4) Vector table

The vector table is configured as shown below.

It must always be set the first four words (stack top address, reset ISR address, NMI ISR address, and Hard Fault ISR address) .

ISR addresses for other exceptions are prepared in case if necessary.

Offset	Exception	Contents	Setting
0x00	Reset	Initial value of the main stack	Required
0x04	Reset	ISR address	Required
0x08	Non-Maskable Interrupt	ISR address	Required
0x0C	Hard Fault	ISR address	Required
0x10	Bus Fault	ISR address	Optional
0x14	Usage Fault	ISR address	Optional
0x18 ~ 0x24	Reserved		
0x28	SVCa l l	ISR address	Optional
0x2C	Debug Monitor	ISR address	Optional
0x30	Reserved		
0x34	PendSV	ISR address	Optional
0x38	SysT i c k	ISR address	Optional
0x3C	External Interrupt	ISR address	Optional

### 6.1.2.3 Executing an ISR

An ISR performs necessary processing for the corresponding exception. ISRs must be prepared by the user.

An ISR may need to include code for clearing the interrupt request so that the same interrupt will not occur again upon return to normal program execution.

For details about interrupt handling, see “6.5 Interrupts”.

If a higher priority exception occurs during ISR execution for the current exception, the CPU abandons the currently executing ISR and services the newly detected exception.

### 6.1.2.4 Exception exit

#### (1) Execution after returning from an ISR

When returning from an ISR, the CPU takes one of the following actions:

- Tail-chaining

If a pending exception exists and there are no stacked exceptions or the pending exception has higher priority than all stacked exceptions, the CPU returns to the ISR of the pending exception.

In this case, the CPU skips the pop of eight registers and push of eight registers when exiting one ISR and entering another. This is called “tail-chaining”.

- Returning to the last stacked ISR

If there are no pending exceptions or if the highest priority stacked exception is higher priority than the highest priority pending exception, the CPU returns to the last stacked ISR.

- Returning to the previous program

If there are no pending or stacked exceptions, the CPU returns to the previous program.

#### (2) Exception exit sequence

When returning from an ISR, the CPU performs the following operations:

- Pop eight registers

Pops the eight registers (PC, xPSR, r0 to r3, r12 and LR) from the stack and adjust the SP.

- Load current active interrupt number

Loads the current active interrupt number from the stacked xPSR. The CPU uses this to track which interrupt to return to.

- Select SP

If returning to an exception (Handler Mode), SP is SP\_main. If returning to Thread Mode, SP can be SP\_main or SP\_process.

## 6.2 Reset Exceptions

Reset exceptions are generated from the following three sources.

Use the Reset Flag (RSTFLG) Register of the Clock Generator to identify the source of a reset.

- External reset pin

A reset exception occurs when an external reset pin changes from “L” to “H”.

- Reset exception by WDT

The watchdog timer (WDT) has a reset generating feature. For details, see the chapter on the WDT.

- Reset exception by SYSRESETREQ

A reset can be generated by setting the SYSRESETREQ bit in the NVIC's Application Interrupt and Reset Control Register.

## 6.3 Non-Maskable Interrupts (NMIs)

Non-maskable interrupts are generated from the following two sources.

Use the NMI Flag (NMIFLG) Register of the clock generator to identify the source of a non-maskable interrupt.

- Non-maskable interrupt by WDT

The watchdog timer (WDT) has a non-maskable interrupt generating feature. For details, see the chapter on the WDT.

- Non-maskable interrupt by VLTD

The Voltage Level Detector (VLTD) has a non-maskable interrupt generating feature. For details, see the chapter on the VLTD.

## 6.4 SysTick

SysTick provides interrupt features using the CPU's system timer.

In case set a value in the SysTick Reload Value Register and enable the SysTick features in the SysTick Control and Status Register, the counter loads with the value set in the Reload Value Register and begins counting down. When the counter reaches "0", a SysTick exception occurs. It is also possible to pend exceptions and use a flag to know when the timer reaches "0".

The SysTick Calibration Value Register holds a reload value for counting 10 ms with the system timer. The count clock frequency varies with each product, and so the value set in the SysTick Calibration Value Register also varies with each product.

<p><b>(Note)</b> In this product, the system timer counts based on a clock obtained by dividing the clock input from the X1 pin by 32. The SysTick Calibration Value Register is set to 0x9C4, which provides 10 ms timing when the clock input from X1 is 8 MHz. In case of 10MHz clock input, 10 ms timing is made by setting 0xC35 to SysTick Reload Register.</p>
---

## 6.5 Interrupt

This chapter describes routes, factors and required settings of interrupts.

The CPU is notified of interrupts by each signal of interrupt factor. It sets priority on the interrupts and handles an interrupt request with the highest priority.

The CPU is notified of the interrupt factor, which is used for clearing the standby modes, via a clock generator. Therefore setting of the clock generator is required.

### 6.5.1 Interrupt factors

#### 6.5.1.1 Interrupt route

Fig6.1 shows an interrupt request route.

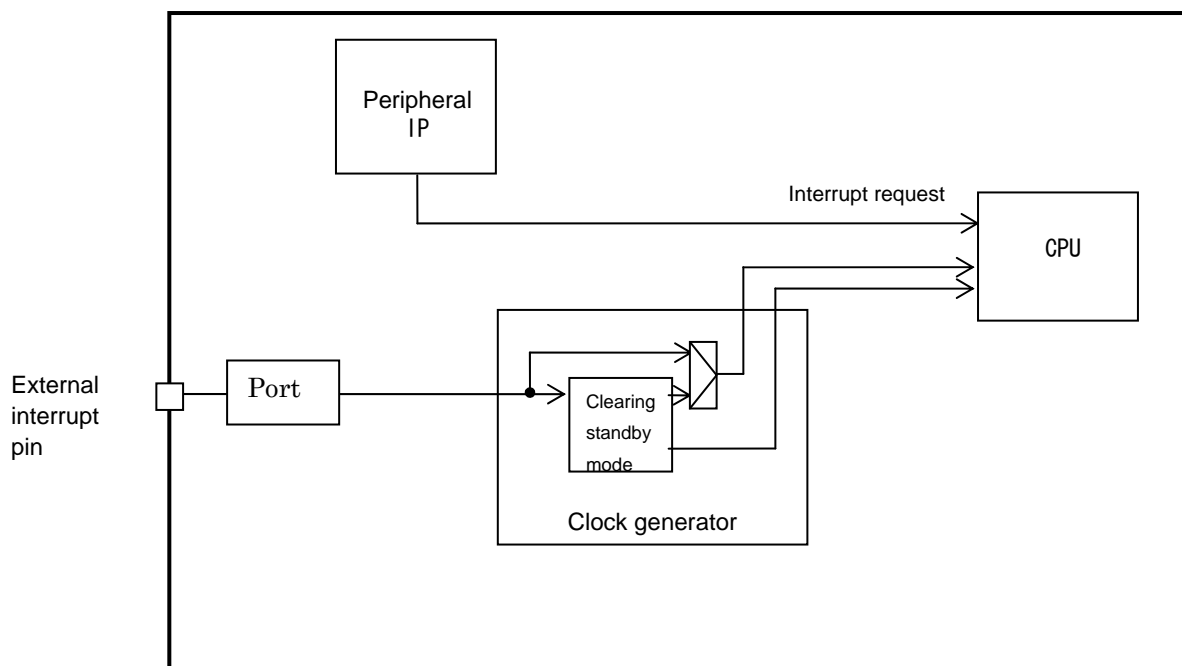


Fig 6.1 Interrupt Route



### 6.5.1.2 Interrupt signal generation

An interrupt request signal is generated from an external pin assigned as the interrupt factor or a peripheral IP.

- From external pin

Set the port control register so that the external pin can perform as an interrupt function pin.

- From peripheral IP

Set the peripheral IP to make it possible to output the interrupt.

See chapters of relevant IP for details.

### 6.5.1.3 Transmission of interrupt signal

An interrupt signal from an external pin or a peripheral IP is directly sent to the CPU unless it is used to clear the standby mode.

An interrupt that can be used to clear the standby mode is transmitted to the CPU via the clock generator. Therefore, it is necessary to set the clock generator in advance. An interrupt from an external pin can be used without setting the clock generator if it does not function as the clearing standby factor.

### 6.5.1.4 List of Interrupt Factors

Table 6.2 shows the list of interrupt factors.

Table6.2 List of Hardware Interrupt Factors (1/2)

INT No	Interrupt factors		Active level (Clearing standby)	CG interrupt mode control register		
0	INT0	Interrupt Pin (PH0/AINA0/96pin or 98pin)	High/Low Edge/Level Selectable	IMCGA		
1	INT1	Interrupt Pin (PH1/AINA1/95pin or 97pin)				
2	INT2	Interrupt Pin (PH2/AINA2/94pin or 96pin)				
3	INT3	Interrupt Pin (PA0/TB0IN/2pin or 4pin)				
4	INT4	Interrupt Pin (PA2/TB1IN/4pin or 6pin)				
5	INT5	Interrupt Pin (PE4/TB2IN//15pin or 17pin)		IMCGB		
6	INTRX0	Serial reception (channel.0)				
7	INTTX0	Serial transmit (channel.0)				
8	INTRX1	Serial reception (channel.1)				
9	INTTX1	Serial transmit (channel.1)				
10	INTVCNA	Vector Engine interrupt A				
11	INTVCNB	Vector Engine interrupt B				
12	INTEMG0	PMD0 EMG interrupt				
13	INTEMG1	PMD1 EMG interrupt				
14	INTOVV0	PMD0 OVV interrupt				
15	INTOVV0	PMD1 OVV interrupt				
16	INTADAPDA	ADC A conversion triggered by PMD0 is finished				
17	INTADBPDA	ADC B conversion triggered by PMD0 is finished				
18	INTADAPDB	ADC A conversion triggered by PMD1 is finished				
19	INTADBPDB	ADC B conversion triggered by PMD1 is finished				
20	INTTB00	16bit TMRB0 compare match detection 0/ Over flow				
21	INTTB01	16bit TMRB0 compare match detection 1				
22	INTTB10	16bit TMRB1 compare match detection 0/ Over flow				
23	INTTB11	16bit TMRB1 compare match detection 1				
24	INTTB40	16bit TMRB4 compare match detection 0/ Over flow				
25	INTTB41	16bit TMRB4 compare match detection 1				
26	INTTB50	16bit TMRB5 compare match detection 0/ Over flow				
27	INTTB51	16bit TMRB5 compare match detection 1				
28	INTPMD0	PMD0 PWM interrupt				
29	INTPMD1	PMD1 PWM interrupt				
30	INTCAP00	16bit TMRB0 input capture 0				
31	INTCAP01	16bit TMRB0 input capture 1				
32	INTCAP10	16bit TMRB1 input capture 0				
33	INTCAP11	16bit TMRB1 input capture 1				
34	INTCAP40	16bit TMRB4 input capture 0				
35	INTCAP41	16bit TMRB4 input capture 1				
36	INTCAP50	16bit TMRB5 input capture 0				
37	INTCAP51	16bit TMRB5 input capture 1				
38	INT6	Interrupt Pin (PE6/TB3IN//17pin or 19pin)			High/Low Edge/Level Selectable	IMCGB
39	INT7	Interrupt Pin (PE7/TB3OUT/18pin or 20pin)				
40	INTRX2	Serial reception (channel.2)				
41	INTTX2	Serial transmit (channel.2)				
42	INTAD0CPA	AD0 conversion monitoring function interrupt A				
43	INTAD1CPA	AD1 conversion monitoring function interrupt A				
44	INTAD0CPB	AD0 conversion monitoring function interrupt B				
45	INTAD1CPB	AD1 conversion monitoring function interrupt B				

Table 6.2 List of Hardware Interrupt Factors (2/2)

No.	Interrupt factors		Active trigger (Clearing standby)	CG interrupt mode control register		
46	INTTB20	16bit TMRB2 compare match detection 0/ Over flow				
47	INTTB21	16bit TMRB2 compare match detection 1				
48	INTTB30	16bit TMRB3 compare match detection 0/ Over flow				
49	INTTB31	16bit TMRB3 compare match detection 1				
50	INTCAP20	16bit TMRB2 input capture 0				
51	INTCAP21	16bit TMRB2 input capture 1				
52	INTCAP30	16bit TMRB3 input capture 0				
53	INTCAP31	16bit TMRB3 input capture 1				
54	INTAD0SFT	ADC0 conversion started by software is finished				
55	INTAD1SFT	ADC1 conversion started by software is finished				
56	INTAD0TMR	ADC0 conversion triggered by timer is finished				
57	INTAD1TMR	ADC1 conversion triggered by timer is finished				
58	INT8	Interrupt Pin (PA7/TB4IN/9pin or 11pin)			High/Low Edge/Level Selectable	IMCGC
59	INT9	Interrupt Pin (PD3/33pin or 35pin)				
60	INTA	Interrupt Pin (FTEST2/PL1/21pin or 23pin)				
61	INTB	Interrupt Pin (FTEST3/PL0/20pin or 22pin)				
62	INTENC0	Ender input0 interrupt				
63	INTENC1	Ender input1 interrupt				
64	INTRX3	Serial reception (channel.3)				
65	INTTX3	Serial transmit (channel.3)				
66	INTTB60	16bit TMRB6 compare match detection 0 / Over flow				
67	INTTB61	16bit TMRB6 compare match detection 1				
68	INTTB70	16bit TMRB7 compare match detection 0 / Over flow				
69	INTTB71	16bit TMRB7 compare match detection 1				
70	INTCAP60	16bit TMRB6 input capture 0				
71	INTCAP61	16bit TMRB6 input capture 1				
72	INTCAP70	16bit TMRB7 input capture 0				
73	INTCAP71	16bit TMRB7 input capture 1				
74	INTC	Interrupt Pin (PJ6/AINB9/74pin or 76 pin)	High/Low Edge/Level Selectable	IMCGD		
75	INTD	Interrupt Pin (PJ7/AINB10/73pin or 75pin)				
76	INTE	Interrupt Pin (PK0/AINB11/72pin or 74pin)				
77	INTF	Interrupt Pin (PK1/AINB12/71pin or 73pin)				

### 6.5.1.5 Active Level

The active level indicates which change in signal of an interrupt factor triggers an interrupt. The CPU recognize an interrupt signal as an interrupt factor when it is changed from “L” to “H”. A signal directly sent from the peripheral IP to the CPU is configured to output the “H” pulse as an interrupt request.

Only interrupt request from external pin have the option as the interrupt to clear the standby mode. The active level setting for Clock Generator is selectable from “H” level, “L” level, rising edge or falling edge.

If the interrupt is used for clearing the standby mode, setting the clock generator register is required.  
i.e. Enable the IMCGx<INTxEN> bit and specify the active level in the IMCGx<EMCG2:0> bits.

The interrupt detected by the clock generator is notified to the CPU as “H” level signal.



An interrupt from the external pin can be used without setting the clock generator in case it does not function as the standby clearing factor. However, inputting the “H” pulse or the “H” level signal is required

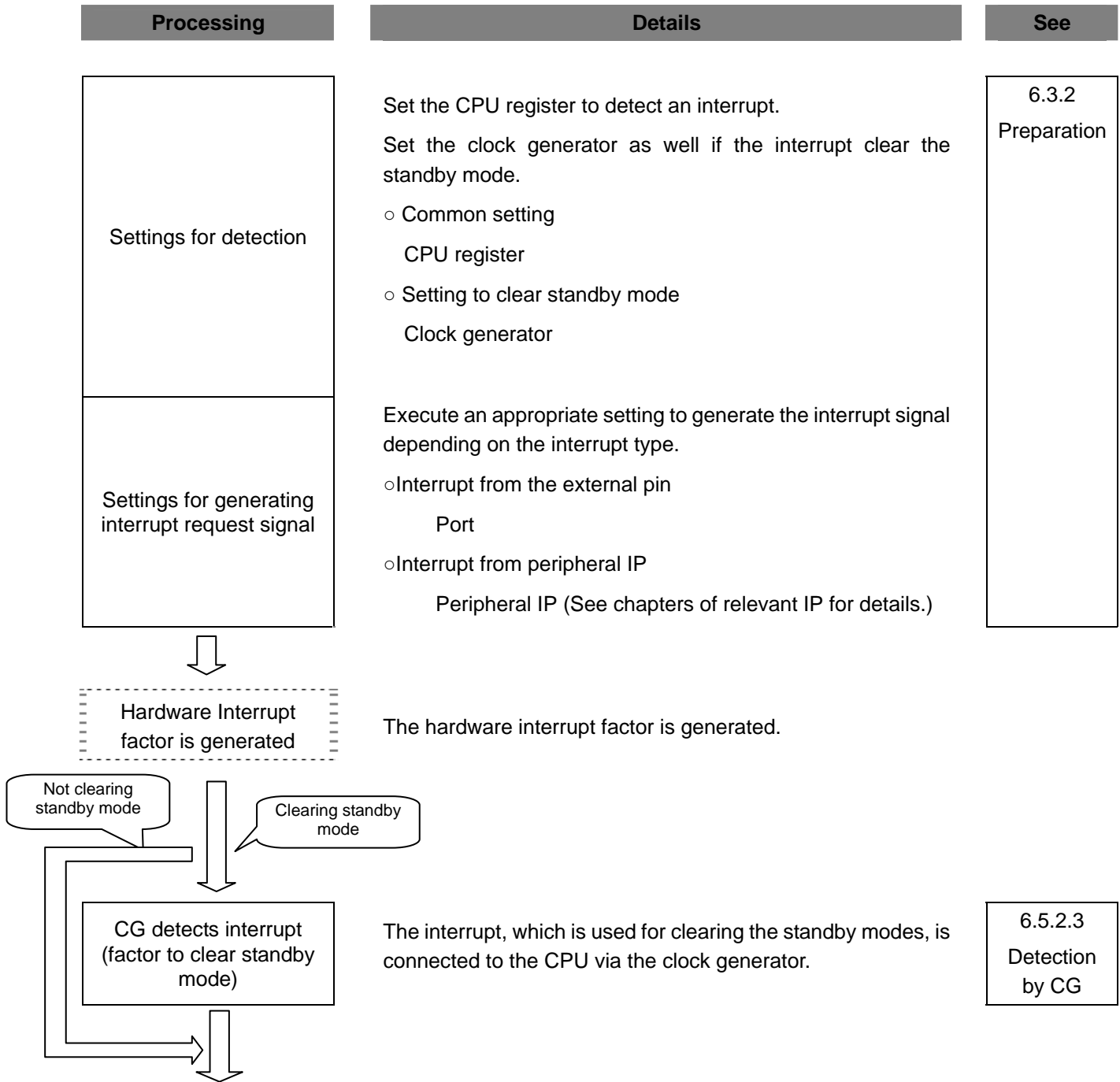
so that the CPU can detect it as an interrupt factor.

## 6.5.2 Interrupt handling

### 6.5.2.1 Flowchart

The following shows how an interrupt is handled.

 indicates hardware handling.  indicates software handling.



Processing	Details	See
<div style="text-align: center;">↓</div> <div style="border: 1px solid black; padding: 5px; text-align: center;">Detecting interrupt</div>	<p>The CPU detects the interrupt.</p> <p>In case several interrupt factor are detected, the interrupt factor with the highest priority is selected according to the priority order.</p>	<div style="border: 1px solid black; padding: 5px;">6.5.2.4 Detection by CPU</div>
<div style="text-align: center;">↓</div> <div style="border: 1px solid black; padding: 5px; text-align: center;">Handling interrupt</div>	<p>The CPU handles the interrupt.</p> <p>The CPU pushes register contents to the stack before entering the interrupt service routine</p>	<div style="border: 1px solid black; padding: 5px;">6.5.2.5 CPU processing</div>
<div style="text-align: center;">↓</div> <div style="border: 1px solid black; padding: 5px; text-align: center;">Executing interrupt service routine</div>	<p>Program for the interrupt service routine. Clear the interrupt factor if needed.</p>	<div style="border: 1px solid black; padding: 5px;">6.5.2.6 Interrupt service routine</div>
<div style="text-align: center;">↓</div> <div style="border: 1px solid black; padding: 5px; text-align: center;">Returning to preceding program</div>	<p>Configure to return to the preceding program from the interrupt service routine.</p>	

### 6.5.2.2 Preparation

When preparing for an interrupt, it is needed to pay attention to the order of configuration to avoid any unexpected interrupt on the way.

Initiating an interrupt or changing its configuration must be implemented in the following order basically. Disable the interrupt by the CPU. Configure from the farthest route from the CPU. Then enable the interrupt by the CPU.

In order not to generate unnecessary interrupt after condition setting, In case of setting the clock generator, it need to clear the interrupt related data in the clock generator before enable the interrupt.

The following shows the order of interrupt handling and describe how to configure them.

- (1) Disabling interrupt by CPU
- (2) CPU registers setting
- (3) Preconfiguration 1 (Interrupt from external pin)
- (4) Preconfiguration 2 (interrupt from peripheral IP)
- (5) Configuring the clock generator
- (6) Enabling interrupt by CPU

#### ( 1 ) Disabling interrupt by CPU

To make the CPU for not accepting any interrupt, write "1" to the corresponding bit of the Interrupt Clear-Enable register. Each bit of the register, of which default setting is "0" with interrupt disabled, is assigned to single interrupt factor.

●CPU register		
Interrupt Clear-Enable<m>	←	"1"(disable interrupt)

(Note) m: corresponding bit.

#### ( 2 ) CPU interrupt registers setting

assign a interrupt priority level from 0 to 255 by writing to the eight bit field in an Interrupt Priority Register.

Priority level 0 is the highest priority level.

●CPU register		
Interrupt Priority<m>	←	"Priority"

(Note) m: corresponding bit.

## (3) Preconfiguration 1 (Interrupt from external pin)

Set "1" to the port function register of the corresponding pin. Setting PnFRx[m] allows the pin to be used as the function pin. Setting PnIE[m] allows the pin to be used as the input port.

● Port register		
PnFRx<PnmFRx>	←	"1"
PnIE<PnmIE>	←	"1"

(Note)	n: port number m: corresponding bit x: function register number
--------	---

## (4) Preconfiguration 2 (interrupt from peripheral IP)

The setting varies depending on the IP to be used. See chapters of relevant IP for details.

## (5) Configuring the clock generator

For an interrupt to clear the standby mode, configure active level and enabling interrupt by the IMCG register of the clock generator. The IMCG registers are the registers for configuring each factor.

Before enabling an interrupt, clear the corresponding interrupt request already held. This can avoid unexpected interrupt. To clear corresponding interrupt request, write value corresponding to the interrupt to be used to the ICRCG register. See 6.3.5 ICRCG Interrupt Clear Register for each value.

An interrupt from the external pin can be used without setting the clock generator if it does not function as the standby clearing factor. However, inputting the "H" pulse or the signal in "H" level is required so that the CPU can detect it as an interrupt factor.

●Clock generator register		
IMCGn<EMCGm>	←	Active level
EICRCG<ICRCG>	←	Value corresponding to the interrupt to be used
IMCGn<INTmEN>	←	"1" (interrupt enabled)

(Note)	n: register number m: number assigned to each interrupt factor
--------	---



## (6) Enabling interrupt by CPU

Enable the interrupt by the CPU as shown below.

It is possible to clear the suspended interrupt by writing the Interrupt Clear-Pending register. Then, enable the intended interrupt with the Interrupt Set-Enable register. Each bit of the register is assigned to each interrupt factor.

Writing "1" to the corresponding bit of the Clear-Pending register clears the suspended interrupt. Writing "1" to the corresponding bit of the Set-Enable register enables the intended interrupt.

●CPU register		
Interrupt Clear-Pending<m>	←	"1"
Interrupt Set-Enable<m>	←	"1"

(Note) m: corresponding bit
-----------------------------

### 6.5.2.3 Detection by Clock Generator

If the interrupt is used for clearing the standby mode, the interrupt factor is detected by an active level specified in the clock generator, and notified to the CPU.

The interrupt active level triggered by a rising or falling edge is kept in the clock generator after detection. However, if "H" or "L" level signal is specified as the trigger to enter the active state, the CPU considers that the interrupt factor is cleared upon exiting from the active state. Therefore, the active state needs to be kept until the interrupt is detected.

The clock generator notified to the CPU the interrupt detected by "H" level signal. The CPU considers the interrupt signal as an interrupt factor when it is changed from "L" to "H". To generate an interrupt again, the factor held in the clock generator needs to be cleared with the ICRCG clear register.

### 6.5.2.4 Detection by CPU

The CPU detects an interrupt factor with the highest priority.

### 6.5.2.5 CPU processing

On detecting the interrupt, the CPU pushes the contents of PC, PSR, r0-r3, r12 and LR to the stack before entering the interrupt service routine.

### 6.5.2.6 Interrupt Service Routine

Interrupt service routine requires specific programming according to the application to be used. This section describes what is recommended at the service routine programming and how the factor is cleared.

#### ( 1 ) Pushing during interrupt service routine

Common interrupt service routine is accompanied with the interrupt handling and the pushing of the register contents. The Cortex-M3 core automatically pushes the contents of PC, PSR, r0-r3, r12 and LR to the stack. No extra programming is required for them.

Push the contents of other registers if needed.

An interrupt with the higher priority and faults such as NMI are accepted even when the interrupt service routine is being executed. Therefore, it is recommend to push the contents of the general purpose register that might be rewritten.

#### ( 2 ) Clearing interrupt factor

As for an interrupt factor clearing the standby mode, it need to clear the interrupt request with the ICRCG clear register of the clock generator.

If “H” or “L” level signal is specified as the trigger to enter the active state, the factor is held unless it is cleared. In this case, the factor needs to be cleared. Clearing the factor causes clearing the interrupt request signal from clock generator.

If a rising or falling edge is specified as the trigger to enter the active state, the factor is cleared by setting the value which corresponds to the interrupt, to the ICRCG clear register. The factor is detected again when the specified edge appears again.

## 6.6 Exception/Interrupt-related registers

The clock generator registers and their addresses are as shown below.

### 6.6.1 Register List

●NVIC Registers	
SysTick Control and Status Register	0xE000_E010
SysTick Reload Value Register	0xE000_E014
SysTick Current Value Register	0xE000_E018
SysTick Calibration Value Register	0xE000_E01C
Interrupt Set-Enable Register 1	0xE000_E100
Interrupt Set-Enable Register 2	0xE000_E104
Interrupt Set-Enable Register 3	0xE000_E108
Interrupt Clear-Enable Register 1	0xE000_E180
Interrupt Clear-Enable Register 2	0xE000_E184
Interrupt Clear-Enable Register 3	0xE000_E188
Interrupt Set-Pending Register 1	0xE000_E200
Interrupt Set-Pending Register 2	0xE000_E204
Interrupt Set-Pending Register 3	0xE000_E208
Interrupt Clear-Pending Register 1	0xE000_E280
Interrupt Clear-Pending Register 2	0xE000_E284
Interrupt Clear-Pending Register 3	0xE000_E288
Interrupt Priority Register	0xE000_E400-0xE000_E450
Vector Table Offset Register	0xE000_ED08
System Handler Priority Register	0xE000_ED18,0xE000_ED1C,0xE000_ED20
System Handler Control and State Register	0xE000_ED24

●Clock generator registers		
ICRCG	CG Interrupt Request Clear Register	0x4004_0214
NMIFLG	NMI Flag Register	0x4004_0218
RSTFLG	Reset Flag Register	0x4004_021C
IMCGA	CG Interrupt Mode Control Register A	0x4004_0220
IMCGB	CG Interrupt Mode Control Register B	0x4004_0224
IMCGC	CG Interrupt Mode Control Register C	0x4004_0228
IMCGD	CG Interrupt Mode Control Register D	0x4004_022C

6.6.2 NVIC Registers

6.6.2.1 SysTick Control and Status Register

	7	6	5	4	3	2	1	0
bit Symbol						CLK SOURCE	TICKINT	ENABLE
Read/Write	R					R/W	R/W	R/W
After reset	0					0	0	0
Function	"0" is read.					0: External reference clock 1: Core clock	0: Do not pend SysTick 1: Pend SysTick	0: Disable 1: Enable
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							
	23	22	21	20	19	18	17	16
bit Symbol								COUNT FLAG
Read/Write	R							R/W
After reset	0							0
Function	"0" is read.							0: Timer not counted to 0 1: Timer counted to 0
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							

- <bit0> <ENABLE> 1 = The counter loads with the Reload value and then begins counting down.  
0 = The timer is disabled.
- <bit1> <TICKINT> 1 = SysTick exceptions are pending.  
0 = SysTick exceptions are not pending.
- <bit2> <CLKSOURCE> 0 = External reference clock  
1 = Core clock
- <bit16> <COUNTFLAG> 1 = Indicates that the timer counted to 0 since last time this was read.  
Clears on read of any part of the SysTick Control and Status Register.

## 6.6.2.2 SysTick Reload Value Register

	7	6	5	4	3	2	1	0
bit Symbol	RELOAD							
Read/Write	R/W							
After reset	Undefined							
Function	Reload value							
	15	14	13	12	11	10	9	8
bit Symbol	RELOAD							
Read/Write	R/W							
After reset	Undefined							
Function	Reload value							
	23	22	21	20	19	18	17	16
bit Symbol	RELOAD							
Read/Write	R/W							
After reset	Undefined							
Function	Reload value							
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							

<bit23:0> <RELOAD> Set the value to load into the SysTick Current Value Register when the timer reaches "0".

**(Note)** In this product, the system timer counts based on a clock obtained by dividing the clock input from the X1 pin by 32.

## 6.6.2.3 SysTick Current Value Register

	7	6	5	4	3	2	1	0
bit Symbol	CURRENT							
Read/Write	R/W							
After reset	Undefined							
Function	[Read] Current SysTick timer value [Write] Clear							
	15	14	13	12	11	10	9	8
bit Symbol	CURRENT							
Read/Write	R/W							
After reset	Undefined							
Function	[Read] Current SysTick timer value [Write] Clear							
	23	22	21	20	19	18	17	16
bit Symbol	CURRENT							
Read/Write	R/W							
After reset	Undefined							
Function	[Read] Current SysTick timer value [Write] Clear							
	31	30	29	28	27	26	25	24
bit Symbol	/							
Read/Write	R							
After reset	0							
Function	"0" is read.							

<bit23:0> <CURRENT> [Read] Current SysTick timer value.

[Write] Writing to this register with any value clears it to 0. Clearing this register also clears the COUNTFLAG bit of the SysTick Control and Status Register.

## 6.6.2.4 SysTick Calibration Value Register

	7	6	5	4	3	2	1	0
bit Symbol	TENMS							
Read/Write	R							
After reset	1	1	0	0	0	1	0	0
Function	Calibration value (Note)							
	15	14	13	12	11	10	9	8
bit Symbol	TENMS							
Read/Write	R							
After reset	0	0	0	0	1	0	0	1
Function	Calibration value (Note)							
	23	22	21	20	19	18	17	16
bit Symbol	TENMS							
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	Calibration value (Note)							
	31	30	29	28	27	26	25	24
bit Symbol	NOREF	SKEW						
Read/Write	R	R	R					
After reset	0	0	0					
Function	0: Reference clock provided 1: No reference clock	0: Calibration value is 10 ms. 1: Calibration value is not 10 ms.	"0" is read.					

<bit23:0> <TENMS> Reload value to use for 10 ms timing (0x9C4). (Note)

<bit30> <SKEW> 1 = The calibration value is not exactly 10 ms.

<bit31> <NOREF> 1 = The reference clock is not provided.

**(Note)** In this product, the system timer counts based on a clock obtained by dividing the clock input from the X1 pin by 32.  
The SysTick Calibration Value Register is set to a value that provides 10 ms timing when the clock input from X1 is 8 MHz. In case of 10MHz clock input, 10 ms timing is made by setting 0xC35 to SysTick Reload Register.

## 6.6.2.5 Interrupt Set-Enable Register 1

	7	6	5	4	3	2	1	0
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 7 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 6 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 5 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 4 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 3 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 2 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 1 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 0 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 15 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 14 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 13 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 12 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 11 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 10 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 9 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 8 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 23 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 22 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 21 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 20 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 19 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 18 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 17 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 16 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	31	30	29	28	27	26	25	24
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 31 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 30 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 29 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 28 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 27 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 26 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 25 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 24 [Write] 1: Enable [Read] 0: Disabled 1: Enabled

<bit31:0> <SETENA> Use these bits to enable interrupts or determine which interrupts are currently enabled.

Writing “1” to a bit in this register enables the corresponding interrupt. Writing “0” has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Disabled  
1 = Enabled

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**



## 6.6.2.6 Interrupt Set-Enable Register 2

	7	6	5	4	3	2	1	0
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 39 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 38 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 37 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 36 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 35 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 34 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 33 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 32 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 47 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 46 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 45 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 44 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 43 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 42 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 41 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 40 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 55 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 54 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 53 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 52 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 51 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 50 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 49 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 48 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	31	30	29	28	27	26	25	24
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 63 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 62 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 61 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 60 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 59 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 58 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 57 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 56 [Write] 1: Enable [Read] 0: Disabled 1: Enabled

<bit31:0> <SETENA> Use these bits to enable interrupts or determine which interrupts are currently enabled.

Writing “1” to a bit in this register enables the corresponding interrupt. Writing “0” has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Disabled  
1 = Enabled

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**

6.6.2.7 Interrupt Set-Enable Register 3

	7	6	5	4	3	2	1	0
bit Symbol	SETENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 71 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 70 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 69 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 68 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 67 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 66 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 65 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 64 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	SETENA							
Read/Write	R		R/W					
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.		Interrupt number 77 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 76 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 75 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 74 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 73 [Write] 1: Enable [Read] 0: Disabled 1: Enabled	Interrupt number 72 [Write] 1: Enable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol	R							
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							
	31	30	29	28	27	26	25	24
bit Symbol	R							
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							

<bit13:0> <SETENA> Use these bits to enable interrupts or determine which interrupts are currently enabled.

Writing "1" to a bit in this register enables the corresponding interrupt. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

- 0 = Disabled
- 1 = Enabled

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**

6.6.2.8 Interrupt Clear-Enable Register 1

	7	6	5	4	3	2	1	0
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 7 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 6 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 5 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 4 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 3 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 2 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 1 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 0 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 15 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 14 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 13 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 12 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 11 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 10 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 9 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 8 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 23 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 22 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 21 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 20 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 19 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 18 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 17 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 16 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	31	30	29	28	27	26	25	24
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 31 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 30 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 29 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 28 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 27 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 26 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 25 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 24 [Write] 1: Disable [Read] 0: Disabled 1: Enabled

<bit31:0> <CLRENA> Use these bits to disable or determine which interrupts are currently disabled.

Writing “1” to a bit in this register disables the corresponding interrupt. Writing “0” has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

- 0 = Disabled
- 1 = Enabled

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**

## 6.6.2.9 Interrupt Clear-Enable Register 2

	7	6	5	4	3	2	1	0
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 39 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 38 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 37 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 36 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 35 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 34 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 33 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 32 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 47 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 46 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 45 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 44 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 43 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 42 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 41 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 40 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 55 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 54 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 53 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 52 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 51 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 50 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 49 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 48 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	31	30	29	28	27	26	25	24
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 63 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 62 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 61 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 60 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 59 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 58 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 57 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 56 [Write] 1: Disable [Read] 0: Disabled 1: Enabled

<bit31:0> <CLRENA> Use these bits to disable or determine which interrupts are currently disabled.

Writing “1” to a bit in this register disables the corresponding interrupt. Writing “0” has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Disabled  
1 = Enabled

**(Note)** For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.

6.6.2.10 Interrupt Clear-Enable Register 3

	7	6	5	4	3	2	1	0
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Interrupt number 71 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 70 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 69 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 68 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 67 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 66 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 65 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 64 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	15	14	13	12	11	10	9	8
bit Symbol	CLRENA							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.		Interrupt number 77 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 76 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 75 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 74 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 73 [Write] 1: Disable [Read] 0: Disabled 1: Enabled	Interrupt number 72 [Write] 1: Disable [Read] 0: Disabled 1: Enabled
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							

<bit13:0> <CLRENA> Use these bits to disable or determine which interrupts are currently disabled. Writing "1" to a bit in this register disables the corresponding interrupt. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Disabled  
1 = Enabled

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**

6.6.2.11 Interrupt Set-Pending Register 1

	7	6	5	4	3	2	1	0
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 7 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 6 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 5 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 4 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 3 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 2 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 1 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 0 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	15	14	13	12	11	10	9	8
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 15 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 14 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 13 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 12 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 11 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 10 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 9 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 8 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	23	22	21	20	19	18	17	16
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 23 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 22 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 21 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 20 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 19 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 18 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 17 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 16 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	31	30	29	28	27	26	25	24
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 31 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 30 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 29 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 28 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 27 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 26 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 25 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 24 [Write] 1: Pend [Read] 0: Not pending 1: Pending

<bit31:0> <SETPEND> Use these bits to force interrupts into the pending state or determine which interrupts are currently pending.

Writing "1" to a bit in this register pends the corresponding interrupt. However, writing "1" has no effect on an interrupt that is already pending or is disabled. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Not pending

1 = Pending

Each bit in this register can be cleared by writing "1" to the corresponding bit in the Interrupt Clear-Pending Register.

<b>C</b> For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.
---

6.6.2.12 Interrupt Set-Pending Register 2

	7	6	5	4	3	2	1	0
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 39 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 38 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 37 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 36 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 35 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 34 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 33 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 32 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	15	14	13	12	11	10	9	8
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 47 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 46 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 45 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 44 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 43 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 42 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 41 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 40 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	23	22	21	20	19	18	17	16
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 55 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 54 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 53 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 52 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 51 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 50 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 49 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 48 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	31	30	29	28	27	26	25	24
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 63 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 62 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 61 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 60 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 59 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 58 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 57 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 56 [Write] 1: Pend [Read] 0: Not pending 1: Pending



<bit31:0> <SETPEND> Use these bits to force interrupts into the pending state or determine which interrupts are currently pending.

Writing "1" to a bit in this register pends the corresponding interrupt. However, writing "1" has no effect on an interrupt that is already pending or is disabled. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Not pending

1 = Pending

Each bit in this register can be cleared by writing "1" to the corresponding bit in the Interrupt Clear-Pending Register.

<b>C</b> For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.
---

6.6.2.13 Interrupt Set-Pending Register 3

	7	6	5	4	3	2	1	0
bit Symbol	SETPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 71 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 70 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 69 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 68 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 67 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 66 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 65 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 64 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	15	14	13	12	11	10	9	8
bit Symbol	SETPEND							
Read/Write	R		R/W					
After reset	0		Undefined					
Function	"0" is read.		Interrupt number 77 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 76 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 75 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 74 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 73 [Write] 1: Pend [Read] 0: Not pending 1: Pending	Interrupt number 72 [Write] 1: Pend [Read] 0: Not pending 1: Pending
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							

<bit13:0> <SETPEND> Use these bits to force interrupts into the pending state or determine which interrupts are currently pending.

Writing "1" to a bit in this register pends the corresponding interrupt. However, writing "1" has no effect on an interrupt that is already pending or is disabled. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

- 0 = Not pending
- 1 = Pending

Each bit in this register can be cleared by writing "1" to the corresponding bit in the Interrupt Clear-Pending Register.

**(Note) For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.**

6.6.2.14 Interrupt Clear-Pending Register 1

	7	6	5	4	3	2	1	0
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 7 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 6 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 5 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 4 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 3 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 2 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 1 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 0 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	15	14	13	12	11	10	9	8
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 15 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 14 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 13 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 12 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 11 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 10 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 9 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 8 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	23	22	21	20	19	18	17	16
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 23 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 22 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 21 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 20 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 19 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 18 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 17 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 16 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	31	30	29	28	27	26	25	24
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 31 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 30 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 29 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 28 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 27 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 26 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 25 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 24 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending

<bit31:0> <CLRPEND> Use these bits to clear pending interrupts or determine which interrupts are currently pending.

Writing "1" to a bit in this register clears the corresponding pending interrupt. However, writing "1" has no effect on an interrupt that is already being serviced. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Not pending  
1 = Pending

<p><b>(Note)</b> For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.</p>
---

6.6.2.15 Interrupt Clear-Pending Register 2

	7	6	5	4	3	2	1	0
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number39 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 38 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 37 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 36 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 35 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 34 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 33 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 32 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	15	14	13	12	11	10	9	8
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 47 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 46 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 45 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 44 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 43 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 42 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 41 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 40 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	23	22	21	20	19	18	17	16
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 55 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 54 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 53 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 52 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 51 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 50 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 49 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 48 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending
	31	30	29	28	27	26	25	24
bit Symbol	CLRPEND							
Read/Write	R/W							
After reset	Undefined							
Function	Interrupt number 63 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 62 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 61 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 60 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 59 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number58 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 57 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 56 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending

<bit31:0> <CLRPEND> Use these bits to clear pending interrupts or determine which interrupts are currently pending.

Writing "1" to a bit in this register clears the corresponding pending interrupt. However, writing "1" has no effect on an interrupt that is already being serviced. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

0 = Not pending  
1 = Pending

<p><b>(Note)</b> For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.</p>
---

6.6.2.16 Interrupt Clear-Pending Register 3

	7	6	5	4	3	2	1	0	
bit Symbol	CLRPEND								
Read/Write	R/W								
After reset	Undefined								
Function	Interrupt number 39 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 38 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 37 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 36 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 35 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 34 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 33 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 32 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	
	15	14	13	12	11	10	9	8	
bit Symbol	CLRPEND								
Read/Write	R		R/W						
After reset	0		Undefined						
Function	"0" is read.		Interrupt number 45 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 44 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 43 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 42 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 41 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	Interrupt number 40 [Write] 1: Clear pending interrupt [Read] 0: Not pending 1: Pending	
	23	22	21	20	19	18	17	16	
bit Symbol									
Read/Write	R								
After reset	0								
Function	"0" is read.								
	31	30	29	28	27	26	25	24	
bit Symbol									
Read/Write	R								
After reset	0								
Function	"0" is read.								

<bit13:0> <CLRPEND> Use these bits to clear pending interrupts or determine which interrupts are currently pending.

Writing "1" to a bit in this register clears the corresponding pending interrupt. However, writing "1" has no effect on an interrupt that is already being serviced. Writing "0" has no effect.

Reading a bit in this register returns the current state of the corresponding interrupt as shown below.

- 0 = Not pending
- 1 = Pending

**(Note)** For descriptions of interrupts and interrupt numbers, see Section 6.5.1.4 List of Interrupt Factors.

### 6.6.2.17 Interrupt Priority Registers

Each interrupt is provided with eight bits of an Interrupt Priority Register.

The following shows the addresses of the Interrupt Priority Registers corresponding to interrupt numbers.

	31	24	23	16	15	8	7	0
0xE000_E400		PRI_3		PRI_2		PRI_1		PRI_0
0xE000_E404		PRI_7		PRI_6		PRI_5		PRI_4
0xE000_E408		PRI_11		PRI_10		PRI_9		PRI_8
0xE000_E40C		PRI_15		PRI_14		PRI_13		PRI_12
0xE000_E410		PRI_19		PRI_18		PRI_17		PRI_16
0xE000_E414		PRI_23		PRI_22		PRI_21		PRI_20
0xE000_E418		PRI_27		PRI_26		PRI_25		PRI_24
0xE000_E41C		PRI_31		PRI_30		PRI_29		PRI_28
0xE000_E420		PRI_35		PRI_34		PRI_33		PRI_32
0xE000_E424		PRI_39		PRI_38		PRI_37		PRI_36
0xE000_E428		PRI_43		PRI_42		PRI_41		PRI_40
0xE000_E42C		PRI_47		PRI_46		PRI_45		PRI_44
0xE000_E430		PRI_51		PRI_50		PRI_49		PRI_48
0xE000_E434		PRI_55		PRI_54		PRI_53		PRI_52
0xE000_E438		PRI_59		PRI_58		PRI_57		PRI_56
0xE000_E43C		PRI_63		PRI_62		PRI_61		PRI_60
0xE000_E440		PRI_67		PRI_66		PRI_65		PRI_64
0xE000_E444		PRI_71		PRI_70		PRI_69		PRI_68
0xE000_E448		PRI_75		PRI_74		PRI_73		PRI_72
0xE000_E44C		-		-		PRI_77		PRI_76

The number of bits to be used for assigning a priority varies with each product. This product uses three bits for assigning a priority.

The following shows the fields of the Interrupt Priority Registers for interrupt numbers 0 to 3. The Interrupt Priority Registers for all other interrupt numbers have the identical fields. Unused bits return "0" when read, and writing to unused bits has no effect.



	7	6	5	4	3	2	1	0
bit Symbol	PRI_0							
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of interrupt number 0			"0" is read.				
	15	14	13	12	11	10	9	8
bit Symbol	PRI_1							
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of interrupt number 1			"0" is read.				
	23	22	21	20	19	18	17	16
bit Symbol	PRI_2							
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of interrupt number 2			"0" is read.				
	31	30	29	28	27	26	25	24
bit Symbol	PRI_3							
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of interrupt number 3			"0" is read.				

<bit7:5>     <PRI\_0>   Priority of interrupt number 0  
 <bit15:13>   <PRI\_1>   Priority of interrupt number 1  
 <bit23:21>   <PRI\_2>   Priority of interrupt number 2  
 <bit31:29>   <PRI\_3>   Priority of interrupt number 3

## 6.6.2.18 Vector Table Offset Register

	7	6	5	4	3	2	1	0	
bit Symbol	TBLOFF								
Read/Write	R/W	R							
After reset	0	0							
Function	Offset value	"0" is read.							
	15	14	13	12	11	10	9	8	
bit Symbol	TBLOFF								
Read/Write	R/W								
After reset	0								
Function	Offset value								
	23	22	21	20	19	18	17	16	
bit Symbol	TBLOFF								
Read/Write	R/W								
After reset	0								
Function	Offset value								
	31	30	29	28	27	26	25	24	
bit Symbol			TBLBASE	TBLOFF					
Read/Write	R		R/W	R/W					
After reset	0		0	0					
Function	"0" is read.		Table base	Offset value					

- <bit28:7> <TBLOFF> Set the offset value from the top of the space specified in TBLBASE. The offset must be aligned based on the number of exceptions in the table. This means that the minimum alignment is 32 words that you can use for up to 16 interrupts. For more interrupts, it is necessary to adjust the alignment by rounding up to the next power of two.
- <bit29> <TBLBASE> The vector table is in:  
 0 = Code space  
 1 = SRAM space

**6.6.2.19 System Handler Priority Registers**

System Handler Priority Registers have eight bits per each exception.

The following shows the addresses of the System Handler Priority Registers corresponding to each exception.

	31	24	23	16	15	8	7	0
0xE000_ED18	PRI_7		PRI_6 (Usage Fault)		PRI_5 (Bus Fault)		PRI_4 (Memory Management)	
0xE000_ED1C	PRI_11 (SVCall)		PRI_10		PRI_9		PRI_8	
0xE000_ED20	PRI_15 (SysTick)		PRI_14 (PendSV)		PRI_13		PRI_12 (Debug Monitor)	

The number of bits to be used for assigning a priority varies with each product. This product uses three bits for assigning a priority.

The following shows the fields of the System Handler Priority Registers for Memory Management, Bus Fault and Usage Fault. The System Handler Priority Registers for all other exceptions have the identical fields. Unused bits return “0” when read, and writing to unused bits has no effect.

	7	6	5	4	3	2	1	0
bit Symbol	PRI_4			/	/	/	/	/
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of Memory Management			“0” is read.				
	15	14	13	12	11	10	9	8
bit Symbol	PRI_5			/	/	/	/	/
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of Bus Fault			“0” is read.				
	23	22	21	20	19	18	17	16
bit Symbol	PRI_6			/	/	/	/	/
Read/Write	R/W			R				
After reset	0			0				
Function	Priority of Usage Fault			“0” is read.				
	31	30	29	28	27	26	25	24
bit Symbol	PRI_7			/	/	/	/	/
Read/Write	R/W			R				
After reset	0			0				
Function	Reserved			“0” is read.				

6.6.2.20 System Handler Control and State Register

	7	6	5	4	3	2	1	0
bit Symbol	SVCALL ACT				USGFAU LT ACT		BUSFAU LT ACT	MEMFAU LT ACT
Read/Write	R/W	R			R/W	R	R/W	R/W
After reset	0	0			0	0	0	0
Function	SVCall 0: Inactive 1: Active	"0" is read.			Usage fault 0: Inactive 1: Active	"0" is read.	Bus fault 0: Inactive 1: Active	Memory Management 0: Inactive 1: Active
	15	14	13	12	11	10	9	8
bit Symbol	SVCALL PENDE	BUSFAU LT PENDE	MEMFAU LT PENDE	USGFAU LT PENDE	SYSTICK ACT	PENDSV ACT		MONITO R ACT
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R	R/W
After reset	0	0	0	0	0	0	0	0
Function	SVCall 0: Not pending 1: Pending	Bus Fault 0: Not pending 1: Pending	Memory Management 0: Not pending 1: Pending	Usage Fault 0: Not pending 1: Pending	SysTick 0: Inactive 1: Active	PendSV 0: Inactive 1: Active	"0" is read.	Debug Monitor 0: Inactive 1: Active
	23	22	21	20	19	18	17	16
bit Symbol						USGFAU LT ENA	BUSFAU LT ENA	MEMFAU LT ENA
Read/Write	R					R/W	R/W	R/W
After reset	0					0	0	0
Function	"0" is read.					Usage Fault 0: Disable 1: Enable	Bus Fault 0: Disable 1: Enable	Memory Management 0: Disable 1: Enable
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0							
Function	"0" is read.							

- <bit0> <MEMFAULTACT> Reads as "1" if Memory Management is active.
- <bit1> <BUSFAULTACT> Reads as "1" if Bus Fault is active.
- <bit3> <USGFALTACT> Reads as "1" if Usage Fault is active.
- <bit7> <SVCALLACT> Reads as "1" if SVCAll is active.
- <bit8> <MONITORACT> Reads as "1" if Debug Monitor is active.
- <bit10> <PENDSVACT> Reads as "1" if PendSV is active.
- <bit11> <SYSTICKACT> Reads as "1" if SysTick is active.
- <bit12> <USGFAULTPENDE> Reads as "1" if Usage Fault is pending.
- <bit13> <MEMFAULTPENDE> Reads as "1" if Memory Management is pending.
- <bit14> <BUSFAULTPENDE> Reads as "1" if Bus Fault is pending.
- <bit15> <SVCALLPENDE> Reads as "1" if SVCAll is pending.

<bit16>	<MEMFAULTENA>	Set to "0" to disable or "1" to enable Memory Management.
<bit17>	<BUSFAULTENA>	Set to "0" to disable or "1" to enable Bus Fault.
<bit18>	<USGFAULTENA>	Set to "0" to disable or "1" to enable Usage Fault.

**(Note) Extreme caution is needed to clear or set the active bits, because clearing and setting these bits does not repair stack contents.**

### 6.6.3 Clock Generator Registers

#### 6.6.3.1 CG Interrupt Mode Control Register A

This register set the clearing standby request active level of external interrupt INT0~INT3.

IMCGA  
0x4004\_0220

	7	6	5	4	3	2	1	0
bit Symbol		EMCG02	EMCG01	EMCG00	EMST01	EMST00	INT0F	INT0EN
Read/Write	R	R/W			R		R	R/W
After reset	0	0	1	0	0	0	0	0
Function	"0" is read	Active state setting of INT0 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT0 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT0 clear input 0: Disable 1: Enable
	15	14	13	12	11	10	9	8
bit Symbol		EMCG12	EMCG11	EMCG10	EMST11	EMST10	INT1F	INT1EN
Read/Write	R	R/W			R		R	R/W
After reset	0	0	1	0	0	0	0	0
Function	"0" is read	Active state setting of INT1 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT1 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT1 clear input 0: Disable 1: Enable
	23	22	21	20	19	18	17	16
bit Symbol		EMCG22	EMCG21	EMCG20	EMST21	EMST20	INT2F	INT2EN
Read/Write	R	R/W			R		R	R/W
After reset	0	0	1	0	0	0	0	0
Function	"0" is read	Active state setting of INT2 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT2 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT2 clear input 0: Disable 1: Enable
	31	30	29	28	27	26	25	24
bit Symbol		EMCG32	EMCG31	EMCG30	EMST31	EMST30	INT3F	INT3EN
Read/Write	R	R/W			R		R	R/W
After reset	0	0	1	0	0	0	0	0
Function	"0" is read	Active state setting of INT3 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT3 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT3 clear input 0: Disable 1: Enable

(Note1) Refer to EMSTxx bit to know the active condition which is used for clearing standby.

(Note2) Please specify the bit for the edge first and then specify the bit for the <INTxEN>. Setting them simultaneously is prohibited.

### 6.6.3.2 CG Interrupt Mode Control Register B

This register set the clearing standby request active level of external interrupt INT4~INT7.

IMCGB 0x4004_0224		7	6	5	4	3	2	1	0
	bit Symbol		EMCG42	EMCG41	EMCG40	EMST41	EMST40	INT4F	INT4EN
	Read/Write	R	R/W			R		R	R/W
	After reset	0	0	1	0	0	0	0	0
	Function	"0" is read	Active state setting of INT4 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT4 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT4 clear input 0: Disable 1: Enable
		15	14	13	12	11	10	9	8
bit Symbol		EMCG52	EMCG51	EMCG50	EMST51	EMST50	INT5F	INT5EN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INT5 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT5 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT5 clear input 0: Disable 1: Enable	
		23	22	21	20	19	18	17	16
bit Symbol		EMCG62	EMCG61	EMCG60	EMST61	EMST60	INT6F	INT6EN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INT6 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT6 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT6 clear input 0: Disable 1: Enable	
		31	30	29	28	27	26	25	24
bit Symbol		EMCG72	EMCG71	EMCG70	EMST71	EMST70	INT7F	INT7EN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INT7 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT7 standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0:No 1:happened	INT7 clear input 0: Disable 1: Enable	

(Note1) Refer to EMSTxx bit to know the active condition which is used for clearing standby.

(Note2) Please specify the bit for the edge first and then specify the bit for the <INTxEN>. Setting them simultaneously is prohibited.

### 6.6.3.3 CG Interrupt Mode Control Register C

This register sets the clearing standby request active level of external interrupt INT8~INTB.

IMCGC		7	6	5	4	3	2	1	0
	bit Symbol		EMCG82	EMCG81	EMCG80	EMST81	EMST80	INT8F	INT8EN
	Read/Write	R	R/W			R		R	R/W
	After reset	0	0	1	0	0	0	0	0
	Function	"0" is read	Active state setting of INT8 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT8 standby clear request 00: — 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0: No 1: happened	INT8 clear input 0: Disable 1: Enable
		15	14	13	12	11	10	9	8
bit Symbol		EMCG92	EMCG91	EMCG90	EMST91	EMST90	INT9F	INT9EN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INT9 standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INT9 standby clear request 00: — 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0: No 1: happened	INT9 clear input 0: Disable 1: Enable	
		23	22	21	20	19	18	17	16
bit Symbol		EMCGA2	EMCGA1	EMCGA0	EMSTA1	EMSTA0	INTAF	INTAEN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INTA standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTA standby clear request 00: — 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0: No 1: happened	INTA clear input 0: Disable 1: Enable	
		31	30	29	28	27	26	25	24
bit Symbol		EMCGB2	EMCGB1	EMCGB0	EMSTB1	EMSTB0	INTBF	INTBEN	
Read/Write	R	R/W			R		R	R/W	
After reset	0	0	1	0	0	0	0	0	
Function	"0" is read	Active state setting of INTB standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTB standby clear request 00: — 01: Rising edge 10: Falling edge 11: Both edges		Interrupt happened 0: No 1: happened	INTB clear input 0: Disable 1: Enable	

(Note1) Refer to EMSTxx bit to know the active condition which is used for clearing standby.

(Note2) Please specify the bit for the edge first and then specify the bit for the <INTxEN>. Setting them simultaneously is prohibited.



### 6.6.3.4 CG Interrupt Mode Control Register D

This register set the clearing standby request active level of external interrupt INTC~INTF.

IMCGD 0x4004_022C	bit Symbol	7	6	5	4	3	2	1	0	
	Read/Write	R	R/W			R			R/W	
	After reset	0	0	1	0	0	0	0	0	
	Function	"0" is read	Active state setting of INTC standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTC standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges			Interrupt happened 0:No 1:happened	INTC clear input 0: Disable 1: Enable
bit Symbol	15	14	13	12	11	10	9	8		
Read/Write	R	R/W			R			R/W		
After reset	0	0	1	0	0	0	0	0		
Function	"0" is read	Active state setting of INTD standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTD standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges			Interrupt happened 0:No 1:happened	INTD clear input 0: Disable 1: Enable	
bit Symbol	23	22	21	20	19	18	17	16		
Read/Write	R	R/W			R			R/W		
After reset	0	0	1	0	0	0	0	0		
Function	"0" is read	Active state setting of INTE standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTE standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges			Interrupt happened 0:No 1:happened	INTE clear input 0: Disable 1: Enable	
bit Symbol	31	30	29	28	27	26	25	24		
Read/Write	R	R/W			R			R/W		
After reset	0	0	1	0	0	0	0	0		
Function	"0" is read	Active state setting of INTF standby clear request. (101~111: setting prohibited) 000: "L" level 001: "H" level 010: Falling edge 011: Rising edge 100: Both edges			Active state of INTF standby clear request 00: – 01: Rising edge 10: Falling edge 11: Both edges			Interrupt happened 0:No 1:happened	INTF clear input 0: Disable 1: Enable	

(Note1) Refer to EMSTxx bit to know the active condition which is used for clearing standby.

(Note2) Please specify the bit for the edge first and then specify the bit for the <INTxEN>. Setting them simultaneously is prohibited.

Be sure to set active state of the Standby clear request, in case the interrupt is enabled for clearing the Standby modes.

(Note 1) When using interrupts, be sure to follow the sequence of actions shown below:

- 1) If the external interrupt request pin shared with other general ports, enable the port to receive the interrupt.
- 2) Set conditions such as active state upon initialization.
- 3) Clear interrupt requests.
- 4) Enable interrupts.

(Note 2) Each settings must be performed while interrupts are disabled.

(Note 3) For clearing the Standby modes , 16 interrupt factors (INT0 to INTF) are available. IMCGA~IMCGD Registers in CG are used for selecting edge/level of active state and which aforementioned factors are used for clearing the standby modes.

(Note 4) In case the standby mode clear is not required, INT0 to INTF can be used as a normal interrupt without setting IMCGA~IMCGD Registers in CG.



6.6.3.6 NMI Flag Register

NMI Flag register is a register for reading NMI generation status.

NMIFLG

	7	6	5	4	3	2	1	0
bit Symbol						NMIFLG2	-	NMIFLG0
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.					NMI factor generation flag 0: not applicable 1: generated from Voltage level detection	-	NMI factor generation flag 0: not applicable 1: generated from WDT
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							

(Note) <NMIFLG2:0> are cleared to "0" when they are read.

6.6.3.7 Reset Flag Register

Reset Flag Register is a register for reading internal Reset generation status per generation factors. Since this register is not cleared automatically, it is necessary to write "0" to clear the register.

RSTFLG

	7	6	5	4	3	2	1	0
bit Symbol			OFDRSTF	DBGRSTF		WDRSTF	PINRSTF	PONRSTF
Read/Write	R		R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	1
Function	"0" is read.		OFD reset flag 0 : "0" is written 1 : Reset from OFD	Debug reset flag 0 : "0" is written 1 : Reset from debugger	Write "0".	WDT reset flag 0 : "0" is written 1 : Reset from WDT	RESET 端子フラグ 0 : "0" is written 1 : Reset from RESET pin	Power On Reset フラグ 0 : "0" is written 1 : Reset from Power On Reset
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							
	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.							

(Note) The TMPM370FY has power-on reset circuit and this register is initialized only by power-on reset. Therefore, "1" is set to the <PONRSTF> bit in initial reset state right after power-on. Note that this bit is not set by the second and subsequent resets .

## 7 Input/Output Ports

### 7.1 Port registers

- Px** : **Port data register**  
To read/write port data.
- PxCR** : **Output control Register**  
To control enable/disable output.  
\* To enable/disable input, controlled by PxIE register.
- PxFRn** : **Function control Register**  
To set functions. An assigned function can be activated by setting "1".
- PxOD** : **Open Drain control register**  
To switch CMOS output or open drain output.
- PxPUP** : **Port Pull-Up control register**  
To enable/disable pull-up resister.
- PxPDN** : **Port Pull-Down control register**  
To enable/disable pull-down resister.
- PxIE** : **Input Enable control register**  
To enable/disable input. Default setting is disabled for avoiding through current.

## 7.2 Port Functions

### 7.2.1 Port States in Stop Mode

Input and output in Stop mode are enabled/disabled by the STBYCR2<DRVE> bit in the Standby Control Register

If PxIE or PxCR is enabled with <DRVE>=1, input or output is enabled respectively in STOP mode.

If <DRVE>=0, both input and output are disabled in STOP mode except for some ports even if PxIE and PxCR are enabled.

The differences are summarized in the table shown below.

Port	I/O	<DRVE>=0	<DRVE>=1
PB3,PB5 [When used for debug(PxFR<n>=1) and output is enabled(PxCR<n>=1)]	Input	x	Depends on PxIE<n>
	Output	Enable when data is valid. Disable when data is invalid.	
PH0-2,PA0,PA2,PE4,PE6-7,PA7,PD3,PL0-1,PJ6-7,PK0-1 [When used for interrupt(PxFR<n>=1) and input is enabled(PxIE<n>=1)]	Input	O	O
	Output	x	Depends on PxCR<n>
Other ports	Input	x	Depends on PxIE<n>
	Output	x	Depends on PxCR<n>

O : Input or Output enabled

x : Input or Output disabled

## 7.2.2 Port A (PA0 to PA7)

The port A is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port A performs the serial interface function and the external interrupt input and 16-bit timer input and 16-bit timer output.

Reset initializes all bits of the port A as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PAFR2 register and enable input in the PAIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

Port A circuit types

	7	6	5	4	3	2	1	0
Type	T12	T11	T13	T9	T2	T12	T2	T12

Port A register

	7	6	5	4	3	2	1	0
Bit Symbol	PA7	PA6	PA5	PA4	PA3	PA2	PA1	PA0
Read/Write	R/W							
After reset	"0"							

PA  
(0x4000\_0000)

Port A control register

	7	6	5	4	3	2	1	0
Bit Symbol	PA7C	PA6C	PA5C	PA4C	PA3C	PA2C	PA1C	PA0C
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Output 0: disabled 1: enabled							

PACR  
(0x4000\_0004)

Port A function register 1

	7	6	5	4	3	2	1	0
Bit Symbol	PA6F1	PA6F1	PA5F1	PA4F1	PA3F1	PA2F1	PA1F1	PA0F1
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	0:PORT 1:TB4IN	0:PORT 1:RXD1	0:PORT 1:TXD1	0:PORT 1:SCLK1	0:PORT 1:TB1OUT	0:PORT 1:TB1IN	0:PORT 1:TB0OUT	0:PORT 1:TB0IN

PAFR1  
(0x4000\_0008)



Port A function register 2

	7	6	5	4	3	2	1	0	
PAFR 2 (0x4000_000C)	Bit Symbol	PA7F2	PA6F2	PA5F2	PA4F2	—	PA2F2	—	PA0F2
	Read/Write	R/W				R	R/W	R	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	0:PORT 1:INT8	0:PORT 1:TB6IN	0:PORT 1:TB6OUT	0:PORT 1:CTS1	"0" is read.	0:PORT 1:INT4	"0" is read.	0:PORT 1:INT3

Port A open drain Control register

	7	6	5	4	3	2	1	0	
PAOD (0x4000_0028)	Bit Symbol	PA7OD	PA6OD	PA5OD	PA4OD	PA3OD	PA2OD	PA1OD	PA0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1: open drain							

Port A pull-up control register

	7	6	5	4	3	2	1	0	
PAPUP (0x4000_002C)	Bit Symbol	PA7UP	PA6UP	PA5UP	PA4UP	PA3UP	PA2UP	PA1UP	PA0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-up 0: disabled 1: enabled							

Port A pull-down control register

	7	6	5	4	3	2	1	0	
PAPDN (0x4000_0030)	Bit Symbol	PA7DN	PA6DN	PA5DN	PA4DN	PA3DN	PA2DN	PA1DN	PA0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-down 0: disabled 1: enabled							

Port A input enable control register

	7	6	5	4	3	2	1	0	
PAIE (0x4000_0038)	Bit Symbol	PA7IE	PA6IE	PA5IE	PA4IE	PA3IE	PA2IE	PA1IE	PA0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0: disabled 1: enabled							

### 7.2.3 Port B (PB0 to PB7)

The port B is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port B performs the debug communication function and the debug trace output function.

Reset initializes PB3, PB4, PB5, PB6 and PB7 to perform debug communication function. When PB3 functions as the TMS or SWDIO, input, output and pull-up are enabled. When PB4 functions as the TCK or SWCLK, input, pull-down are enabled. When PB5 functions as the TDO or SWV, output is enabled. When PB6 functions TDI, input, pull-up are enabled. When PB7 functions as  $\overline{\text{TRST}}$  input, pull-up is enabled. PB0, PB1, PB2 perform as the general-purpose ports with input, output and pull-up disabled.

- (Note 1)** The default setting for PB3 is function port. Input, output, and pull-up are enabled.
- (Note 2)** The default setting for PB4 is function port. Input, and pull-down are enabled.
- (Note 3)** The default setting for PB5 is function port. Output is enabled.
- (Note 4)** The default setting for PB6 and PB7 are function port. Input and pull-up are enabled.
- (Note 5)** If PB3 and PB5 are configured to function port for debug function, outputs are enabled even during Stop mode regardless of the STBYCR2<DRVE> bit setting.

Port B circuit types

	7	6	5	4	3	2	1	0
Type	T7	T7	T19	T8	T6	T18	T18	T18

Port B register

	7	6	5	4	3	2	1	0
Bit Symbol	PB7	PB6	PB5	PB4	PB3	PB2	PB1	PB0
Read/Write	R/W							
After reset	"0"							

PB  
(0x4000\_0040)

Port B control register

	7	6	5	4	3	2	1	0
Bit Symbol	PB7C	PB6C	PB5C	PB4C	PB3C	PB2C	PB1C	PB0C
Read/Write	R/W							
After reset	0	0	1	0	1	0	0	0
Function	Output 0: disabled 1: enabled							

PBCR  
(0x4000\_0044)

Port B function register 1

		7	6	5	4	3	2	1	0
PBF1 (0x4000_0048)	Bit Symbol	PB7F1	PB6F1	PB5F1	PB4F1	PB3F1	PB2F1	PB1F1	PB0F1
	Read/Write	R/W							
	After reset	1	1	1	1	1	0	0	0
	Function	0:PORT 1:TRST	0:PORT 1:TDI	0:PORT 1:TDO/ SWV	0:PORT 1:TCK/ SWCLK	0:PORT 1:TMS/ SWDIO	0:PORT 1:TRACE DATA1	0:PORT 1:TRACE DATA0	0:PORT 1:TRACE CLK

Port B pull-up control register

		7	6	5	4	3	2	1	0
PBPUP (0x4000_006C)	Bit Symbol	PB7UP	PB6UP	PB5UP	—	PB3UP	PB2UP	PB1UP	PB0UP
	Read/Write	R/W			R	R/W			
	After reset	1	1	0	0	1	0	0	0
	Function	Pull-up 0: disabled 1: enabled			"0" is read.	Pull-up 0: disabled 1: enabled			

Port B pull-down control register

		7	6	5	4	3	2	1	0
PBPDN (0x4000_0070)	Bit Symbol	—	—	—	PB4DN	—	—	—	—
	Read/Write	R			R/W	R			
	After reset	0	0	0	1	0	0	0	0
	Function	"0" is read.			Pull-down 0: disabled 1: enabled	"0" is read.			

Port B input enable control register

		7	6	5	4	3	2	1	0
PBIE (0x4000_0078)	Bit Symbol	PB7IE	PB6IE	PB5IE	PB4IE	PB3IE	PB2IE	PB1IE	PB0IE
	Read/Write	R/W							
	After reset	1	1	0	1	1	0	0	0
	Function	Input 0: disabled 1: enabled							

### 7.2.4 Port C (PC0 to PC7)

The port C is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the ports C perform the input/output port for three-phase moter control (PMD).

Reset initializes all bits of the port C as general-purpose ports with input, output, pull-up and pull-down disabled.

Port C circuit types

	7	6	5	4	3	2	1	0
Type	T3	T3	T1	T1	T1	T1	T1	T1

Port C register

PC  
(0x4000\_0080)

	7	6	5	4	3	2	1	0
Bit Symbol	PC7	PC6	PC5	PC4	PC3	PC2	PC1	PC0
Read/Write	R/W							
After reset	"0"							

Port C control register

PCCR  
(0x4000\_0084)

	7	6	5	4	3	2	1	0
Bit Symbol	PC7C	PC6C	PC5C	PC4C	PC3C	PC2C	PC1C	PC0C
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Output 0: disabled 1: enabled							

Port C function register 1

PCFR1  
(0x4000\_0088)

	7	6	5	4	3	2	1	0
Bit Symbol	PC7F1	PC6F1	PC5F1	PC4F1	PC3F1	PC2F1	PC1F1	PC0F1
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	0:port 1:OVV0	0:port 1:EMG0	0:port 1:Z0	0:port 1:W0	0:port 1:Y0	0:port 1:V0	0:port 1:X0	0:port 1:U0

Port C open drain Control register

		7	6	5	4	3	2	1	0
PCOD (0x4000_00A8)	Bit Symbol	PC7OD	PC6OD	PC5OD	PC4OD	PC3OD	PC2OD	PC1OD	PC0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1:open drain							

Port C pull-up control register

		7	6	5	4	3	2	1	0
PCPUP (0x4000_00AC)	Bit Symbol	PC7UP	PC6UP	PC5UP	PC4UP	PC3UP	PC2UP	PC1UP	PC0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-up 0: disabled 1: enabled							

Port C pull-down control register

		7	6	5	4	3	2	1	0
PCPDN (0x4000_00B0)	Bit Symbol	PC7DN	PC6DN	PC5DN	PC4DN	PC3DN	PC2DN	PC1DN	PC0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-down 0: disabled 1: enabled							

Port C input enable control register

		7	6	5	4	3	2	1	0
PCIE (0x4000_00B8)	Bit Symbol	PC7IE	PC6IE	PC5IE	PC4IE	PC3IE	PC2IE	PC1IE	PC0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0:disabled 1:enabled							

### 7.2.5 Port D (PD0 to PD6)

The port D is a general-purpose, 7-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port D performs the serial interface function, 16-bit timer input/output, the external interrupt input and encoder input.

Reset initializes all bits of the port D as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PDFR1 register and enable input in the PDIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

Port D circuit types

	7	6	5	4	3	2	1	0
Type	—	T3	T2	T9	T4	T3	T10	T11

Port D register

PD  
(0x4000\_00C0)

	7	6	5	4	3	2	1	0
Bit Symbol	-	PD6	PD5	PD4	PD3	PD2	PD1	PD0
Read/Write	R	R/W						
After reset	"0" is read.	"0"						

Port D control register

PDCR  
(0x4000\_00C4)

	7	6	5	4	3	2	1	0
Bit Symbol	—	PD6C	PD5C	PD4C	PD3C	PD2C	PD1C	PD0C
Read/Write	R	R/W						
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.	Output 0: disabled 1: enabled						

Port D function register 1

PDFR1  
(0x4000\_00C8)

	7	6	5	4	3	2	1	0
Bit Symbol	—	PD6F1	PD5F1	PD4F1	PD3F1	PD2F1	PD1F1	PD0F1
Read/Write	R	R/W						
After reset	0	0	0	0	0	0	0	0
Function	"0" is read.	0:PORT 1:RXD2	0:PORT 1:TXD2	0:PORT 1:SCLK2	0:PORT 1:INT9	0:PORT 1:ENCZ0	0:PORT 1:ENCB0	0:PORT 1:ENCA0

Port D function register 2

		7	6	5	4	3	2	1	0
PDFR 2 (0x4000_00CC)	Bit Symbol	—	—	—	PD4F2	—	—	PD1F2	PD0F2
	Read/Write	R			R/W	R		R/W	R/W
	After reset	0			0	0		0	0
	Function	"0" is read.			0:PORT 1:CTS2	"0" is read.		0:PORT 1:TB5OUT	0:PORT 1:TB5IN

Port D open drain control register

		7	6	5	4	3	2	1	0
PDOD (0x4000_00E8)	Bit Symbol	—	PD6OD	PD5OD	PD4OD	PD3OD	PD2OD	PD1OD	PD0OD
	Read/Write	R	R/W						
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.	0:CMOS 1: open drain						

Port D pull-up control register

		7	6	5	4	3	2	1	0
PDPUP (0x4000_00EC)	Bit Symbol	-	PD6UP	PD5UP	PD4UP	PD3UP	PD2UP	PD1UP	PD0UP
	Read/Write	R	R/W						
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.	Pull-up 0:disabled 1:enabled						

Port D pull-down control register

		7	6	5	4	3	2	1	0
PDPDN (0x4000_00F0)	Bit Symbol	-	PD6DN	PD5DN	PD4DN	PD3DN	PD2DN	PD1DN	PD0DN
	Read/Write	R	R/W						
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.	Pull-down 0:disabled 1:enabled						

Port D input enable control register

		7	6	5	4	3	2	1	0
PDIE (0x4000_00F8)	Bit Symbol	-	PD6IE	PD5IE	PD4IE	PD3IE	PD2IE	PD1IE	PD0IE
	Read/Write	R	R/W						
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read.	Input 0:disabled 1:enabled						

### 7.2.6 Port E (PE0 to PE7)

The port E is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port E performs the serial interface function, timer input/output and the external interrupt input.

Reset initializes all bits of the port E as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PEFR2 register and enable input in the PEIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

Port E circuit type

	7	6	5	4	3	2	1	0
Type	T14	T12	T2	T12	T2	T9	T3	T2

Port E register

PE  
(0x4000\_0100)

	7	6	5	4	3	2	1	0
Bit Symbol	PE7	PE6	PE5	PE4	PE3	PE2	PE1	PE0
Read/Write	R/W							
After reset	"0"							

Port E control register

PECR  
(0x4000\_0104)

	7	6	5	4	3	2	1	0
Bit Symbol	PE7C	PE6C	PE5C	PE4C	PE3C	PE2C	PE1C	PE0C
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Output 0: disabled 1: enabled							

Port E functions register 1

PEFR1  
(0x4000\_0108)

	7	6	5	4	3	2	1	0
Bit Symbol	PE7F1	PE6F1	PE5F1	PE4F1	PE3F1	PE2F1	PE1F1	PE0F1
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	0:PORT 1:TB3OUT.	0:PORT 1:TB3IN	0:PORT 1:TB2OUT	0:PORT 1:TB2IN	0:PORT 1:TB4OUT	0:PORT 1:SCLK0	0:PORT 1:RXD0	0:PORT 1:TXD0



Port E functions register 2

	7	6	5	4	3	2	1	0
PEFR2 (0x4000_010C)	Bit Symbol	PE7F2	PE6F2	—	PE4F2	—	PE2F2	—
	Read/Write	R/W	R/W	R	R/W	R	R/W	R
	After reset	0	0	0	0	0	0	0
	Function	0:PORT 1:INT7.	0:PORT 1:INT6	"0" is read.	0:PORT 1:INT5	"0" is read.	0:PORT 1:CTS0	"0" is read.

Port E open drain control register

	7	6	5	4	3	2	1	0	
PEOD (0x4000_0128)	Bit Symbol	PE7OD	PE6OD	PE5OD	PE4OD	PE3OD	PE2OD	PE1OD	PE0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1:Open drain							

Port E pull-up control register

	7	6	5	4	3	2	1	0	
PEPUP (0x4000_012C)	Bit Symbol	PE7UP	PE6UP	PE5UP	PE4UP	PE3UP	PE2UP	PE1UP	PE0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-up 0:disabled 1:enabled							

Port E pull-down control register

	7	6	5	4	3	2	1	0	
PEPDN (0x4000_0130)	Bit Symbol	PE7DN	PE6DN	PE5DN	PE4DN	PE3DN	PE2DN	PE1DN	PE0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-down 0:disabled 1:enabled							

Port E input enable control register

	7	6	5	4	3	2	1	0	
PEIE (0x4000_0138)	Bit Symbol	PE7IE	PE6IE	PE5IE	PE4IE	PE3IE	PE2IE	PE1IE	PE0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0:disabled 1:enabled							

### 7.2.7 Port F (PF0 to PF4)

The port F is a general-purpose, 5-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port F performs the functions of the serial interface, timer output and the operation mode setting.

While a reset signal is in “0” state, the PF0 input and pull-up are enabled. At the rising edge of the reset signal, if PF0 is “1”, the device enters single mode and boots from the on-chip flash memory. If PF0 is “0”, the device enters single boot mode and boots from the internal boot program. For details of single boot mode, refer to “Chapter 19 Flash Memory Operation”.

Reset initializes all bits of the port F as general-purpose ports with input, output and pull-down disabled. Pull-up is enabled for PF0 and disabled for PF1 through PF4.

Port F circuit type

	7	6	5	4	3	2	1	0
Type	—	—	—	T11	T10	T15	T2	T20

Port F register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	PF4	PF3	PF2	PF1	PF0
Read/Write	R			R/W				
After reset	“0” is read.			“0”				

PF  
(0x4000\_0140)

Port F control register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	PF4C	PF3C	PF2C	PF1C	PF0C
Read/Write	R			R/W				
After reset	0			0	0	0	0	0
Function	“0” is read.			Output 0: disabled 1: enabled				

PFCR  
(0x4000\_0144)

Port F function register 1

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	PF4F1	PF3F1	PF2F1	PF1F1	PF0F1
Read/Write	R			R/W				
After reset	0			0	0	0	0	0
Function	“0” is read.			0:PORT 1: ENCZ1	0:PORT 1: ENCB1	0:PORT 1: ENCA1	0:PORT 1:TB7OUT	0:PORT 1: TB7IN

PFFR1  
(0x4000\_0148)

Port F function register 2

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	PF4F2	PF3F2	PF2F2	—	—
Read/Write	R			R/W			R	
After reset	0			0	0	0	0	
Function	“0” is read.			0:PORT 1:RXD3	0:PORT 1:TXD3	0:PORT 1:SCLK3	“0” is read.	

PFFR2  
(0x4000\_014C)

Port F function register 3

		7	6	5	4	3	2	1	0	
PFFR3 (0x4000_0150)	Bit Symbol	—	—	—	—	—	PF2F3	—	—	
	Read/Write	R					R/W		R	
	After reset	0					0		0	
	Function	"0" is read.					0:PORT 1:CTS3		"0" is read.	

Port F open drain control register

		7	6	5	4	3	2	1	0	
PFOD (0x4000_0168)	Bit Symbol	—	—	—	PF4OD	PF3OD	PF2OD	PF1OD	PF0OD	
	Read/Write	R			R/W					
	After reset	0			0	0	0	0	0	
	Function	"0" is read			0:CMOS 1:Open drain					

Port F pull-up control register

		7	6	5	4	3	2	1	0	
PFPUP (0x4000_016C)	Bit Symbol	—	—	—	PF4UP	PF3UP	PF2UP	PF1UP	PF0UP	
	Read/Write	R			R/W					
	After reset	0			0	0	0	0	0	
	Function	"0" is read			Pull-up 0:disabled 1:enabled					

Port F pull-down control register

		7	6	5	4	3	2	1	0	
PFPDN (0x4000_0170)	Bit Symbol	—	—	—	PF4DN	PF3DN	PF2DN	PF1DN	PF0DN	
	Read/Write	R			R/W					
	After reset	0			0	0	0	0	0	
	Function	"0" is read			Pull-down 0:disabled 1:enabled					

Port F input enable control register

		7	6	5	4	3	2	1	0	
PFIE (0x4000_0178)	Bit Symbol	—	—	—	PF4IE	PF3IE	PF2IE	PF1IE	PF0IE	
	Read/Write	R			R/W					
	After reset	0			0	0	0	0	0	
	Function	"0" is read			Input 0:disabled 1:enabled					

### 7.2.8 Port G (PG0 to PG7)

The port G is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port G performs the input/output port for three-phase moter control (PMD).

Reset initializes all bits of the port G as general-purpose ports with input, output, pull-up and pull-down disabled.

Port G circuit type

	7	6	5	4	3	2	1	0
Type	T3	T3	T1	T1	T1	T1	T1	T1

Port G register

	7	6	5	4	3	2	1	0
Bit Symbol	PG7	PG6	PG5	PG4	PG3	PG2	PG1	PG0
Read/Write	R/W							
After reset	"0"							

PG  
(0x4000\_0180)

Port G control register

	7	6	5	4	3	2	1	0
Bit Symbol	PG7C	PG6C	PG5C	PG4C	PG3C	PG2C	PG1C	PG0C
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Output 0: disabled 1: enabled							

PGCR  
(0x4000\_0184)

Port G function register 1

	7	6	5	4	3	2	1	0
Bit Symbol	PG7F1	PG6F1	PG5F1	PG4F1	PG3F1	PG2F1	PG1F1	PG0F1
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	0:PORT 1: OV1	0:PORT 1: EM1	0:PORT 1: Z1	0:PORT 1: W1	0:PORT 1: Y1	0:PORT 1: V1	0:PORT 1: X1	0:PORT 1: U1

PGFR1  
(0x4000\_0188)

Port G open drain control register

		7	6	5	4	3	2	1	0
PGOD (0x4000_01A8)	Bit Symbol	PG7OD	PG6OD	PG5OD	PG4OD	PG3OD	PG2OD	PG1OD	PG0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1:Open drain							

Port G pull-up control register

		7	6	5	4	3	2	1	0
PGPUP (0x4000_01AC)	Bit Symbol	PG7UP	PG6UP	PG5UP	PG4UP	PG3UP	PG2UP	PG1UP	PG0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-up 0:disabled 1:enabled							

Port G pull-down control register

		7	6	5	4	3	2	1	0
PGPDN (0x4000_01B0)	Bit Symbol	PG7DN	PG6DN	PG5DN	PG4DN	PG3DN	PG2DN	PG1DN	PG0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-down 0:disabled 1:enabled							

Port G input enable control register

		7	6	5	4	3	2	1	0
PGIE (0x4000_01B8)	Bit Symbol	PG7IE	PG6IE	PG5IE	PG4IE	PG3IE	PG2IE	PG1IE	PG0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0:disabled 1:enabled							

### 7.2.9 Port H (PH0 to PH7)

The port H is a general-purpose 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port H performs the analog input of the A/D converter and the external interrupt input.

Reset initializes all bits of the port H as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PHFR1 register and enable input in the PHIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note 1)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

**(Note 2)** Unless you use all the bits of port H as analog input pins, conversion accuracy may be reduced. Be sure to verify that this causes no problem on your system.

Port H circuit type

	7	6	5	4	3	2	1	0
Type	T16	T16	T16	T16	T16	T17	T17	T17

Port H register

	7	6	5	4	3	2	1	0
Bit Symbol	PH7	PH6	PH5	PH4	PH3	PH2	PH1	PH0
Read/Write	R/W							
After reset	"0"							

PH  
(0x4000\_01C0)

Port H control register

	7	6	5	4	3	2	1	0
Bit Symbol	PH7C	PH6C	PH5C	PH4C	PH3C	PH2C	PH1C	PH0C
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Output 0: disabled 1: enabled							

PHCR  
(0x4000\_01C4)

Port H function register 1

	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	PH2F1	PH1F1	PH0F1
Read/Write	R					R/W		
After reset	0	0	0	0	0	0	0	0
Function	"0" is read					0:PORT 1:INT2	0:PORT 1:INT1	0:PORT 1:INT0

PHFR1  
(0x4000\_01C8)

Port H open drain control register

		7	6	5	4	3	2	1	0
PHOD (0x4000_01E8)	Bit Symbol	PH7OD	PH6OD	PH5OD	PH4OD	PH3OD	PH2OD	PH1OD	PH0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1:open drain							

Port H pull-up control register

		7	6	5	4	3	2	1	0
PHPUP (0x4000_01EC)	Bit Symbol	PH7UP	PH6UP	PH5UP	PH4UP	PH3UP	PH2UP	PH1UP	PH0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	1
	Function	Pull-up 0:disabled 1:enabled							

Port H pull-down control register

		7	6	5	4	3	2	1	0
PHPDN (0x4000_01F0)	Bit Symbol	PH7DN	PH6DN	PH5DN	PH4DN	PH3DN	PH2DN	PH1DN	PH0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Pull-down 0:disabled 1:enabled							

Port H input enable control register

		7	6	5	4	3	2	1	0
PHIE (0x4000_01F8)	Bit Symbol	PH7IE	PH6IE	PH5IE	PH4IE	PH3IE	PH2IE	PH1IE	PH0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0:disabled 1:enabled							

### 7.2.10 Port I (PI0 to PI3)

The port I is a general-purpose, 4-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port I performs the analog input of the A/D converter.

Reset initializes all bits of the port I as general-purpose ports with input, output, pull-up and pull-down disabled.

**(Note) Unless you use all the bits of port I as analog input pins, conversion accuracy may be reduced. Be sure to verify that this causes no problem on your system.**

Port I circuit type

	7	6	5	4	3	2	1	0
Type	—	—	—	—	T16	T16	T16	T16

Port I register

PI  
(0x4000\_0200)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3	PI2	PI1	PI0
Read/Write	R				R/W			
After reset	"0" is read				"0"			

Port I control register

PICR  
(0x4000\_0204)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3C	PI2C	PI1C	PI0C
Read/Write	R				R/W			
After reset	0	0	0	0	0	0	0	0
Function	"0" is read				Output 0: disabled 1: enabled			

Port I open drain control register

PIOD  
(0x4000\_0228)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3OD	PI2OD	PI1OD	PI0OD
Read/Write	R				R/W			
After reset	0	0	0	0	0	0	0	0
Function	"0" is read				0:CMOS 1:open drain			

Port I pull-up control register

PIPUP  
(0x4000\_022C)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3UP	PI2UP	PI1UP	PI0UP
Read/Write	R				R/W			
After reset	0	0	0	0	0	0	0	0
Function	"0" is read				Pull-up 0: disabled 1: enabled			



Port I pull-down control register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3DN	PI2DN	PI1DN	PI0DN
Read/Write	R				R/W			
After reset	0	0	0	0	0	0	0	0
Function	"0" is read				Pull-down 0:disabled 1:enabled			

PIPDN  
(0x4000\_0230)

Port I input enable control register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	PI3IE	PI2IE	PI1IE	PI0IE
Read/Write	R				R/W			
After reset	0	0	0	0	0	0	0	0
Function	"0" is read				Input 0:disabled 1:enabled			

PIIE  
(0x4000\_0238)

### 7.2.11 Port J (PJ0 to PJ7)

The port J is a general-purpose, 8-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port J performs the analog input of the A/D converter and external interrupt input.

Reset initializes all bits of the port J as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PJFR1 register and enable input in the PJIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note 1) In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.**

**(Note 2) Unless you use all the bits of port J as analog input pins, conversion accuracy may be reduced. Be sure to verify that this causes no problem on your system.**

Port J circuit type

	7	6	5	4	3	2	1	0
Type	T17	T17	T16	T16	T16	T16	T16	T16

Port J register

		7	6	5	4	3	2	1	0
PJ (0x4000_0240)	Bit Symbol	PJ7	PJ6	PJ5	PJ4	PJ3	PJ2	PJ1	PJ0
	Read/Write	R/W							
	After reset	"0"							

Port J control register

		7	6	5	4	3	2	1	0
PJCR (0x4000_0244)	Bit Symbol	PJ7C	PJ6C	PJ5C	PJ4C	PJ3C	PJ2C	PJ1C	PJ0C
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Output 0: disabled 1: enabled							

Port J function register 1

		7	6	5	4	3	2	1	0
PJFR1 (0x4000_0248)	Bit Symbol	PJ7F1	PJ6F1	—	—	—	—	—	—
	Read/Write	R/W		R					
	After reset	0	0	0	0	0	0	0	0
	Function	0:PORT 1:INTD	0:PORT 1:INTC	"0" is read					

Port J open drain control register

		7	6	5	4	3	2	1	0
PJOD (0x4000_0268)	Bit Symbol	PJ7OD	PJ6OD	PJ5OD	PJ4OD	PJ3OD	PJ2OD	PJ1OD	PJ0OD
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	0:CMOS 1:open drain							

Port J pull-up control register

		7	6	5	4	3	2	1	0
PJUP (0x4000_026C)	Bit Symbol	PJ7UP	PJ6UP	PJ5UP	PJ4UP	PJ3UP	PJ2UP	PJ1UP	PJ0UP
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	After reset	Pull-up 0:disabled 1:enabled							

Port J pull-down control register

		7	6	5	4	3	2	1	0
PJPDN (0x4000_0270)	Bit Symbol	PJ7DN	PJ6DN	PJ5DN	PJ4DN	PJ3DN	PJ2DN	PJ1DN	PJ0DN
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	After reset	Pull-down 0:disabled 1:enabled							

Port J input enable control register

		7	6	5	4	3	2	1	0
PJIE (0x4000_0278)	Bit Symbol	PJ7IE	PJ6IE	PJ5IE	PJ4IE	PJ3IE	PJ2IE	PJ1IE	PJ0IE
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	Input 0:disabled 1:enabled							

### 7.2.12 Port K (PK0 to PK1)

The port K is a general-purpose, 2-bit input/output port. For this port, inputs and outputs can be specified in units of bits. Besides the general-purpose input/output function, the port K performs the functions as the analog input of the A/D converter and the external interrupt input.

Reset initializes all bits of the port K as general-purpose ports with input, output, pull-up and pull-down disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PKFR1 register and enable input in the PKIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note 1)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

**(Note 2)** Unless you use all the bits of port K as analog input pins, conversion accuracy may be reduced. Be sure to verify that this causes no problem on your system.

Port K circuit type

	7	6	5	4	3	2	1	0
Type	—	—	—	—	—	—	T17	T17

Port K register

PK  
(0x4000\_0280)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PK1	PK0
Read/Write	R						R/W	
After reset	"0" is read						"0"	

Port K control register

PKCR  
(0x4000\_0284)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PK1C	PK0C
Read/Write	R						R/W	
After reset	0						0	0
Function	"0" is read.						Output 0: disabled 1: enabled	

Port K function register 1

PKFR1  
(0x4000\_0288)

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PK1F1	PK0F1
Read/Write	R						R/W	
After reset	0						0	0
Function	"0" is read						0:PORT 1: INTF	0:PORT 1: INTE

Port K open drain control register

		7	6	5	4	3	2	1	0
PKOD (0x4000_02A8)	Bit Symbol	—	—	—	—	—	—	PK1OD	PK0OD
	Read/Write	R						R/W	
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read						0:CMOS 1:open drain	

Port K pull-up control register

		7	6	5	4	3	2	1	0
PKPUP (0x4000_02AC)	Bit Symbol	—	—	—	—	—	—	PK1UP	PK0UP
	Read/Write	R						R/W	
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read						Pull-up 0:disabled 1:enabled	

Port K pull-down control register

		7	6	5	4	3	2	1	0
PKPDN (0x4000_02B0)	Bit Symbol	—	—	—	—	—	—	PK1DN	PK0DN
	Read/Write	R						R/W	
	After reset	0	0	0	0	0	0	0	0
	Function	"0" is read						Pull-down 0:disabled 1:enabled	

Port K input enable control register

		7	6	5	4	3	2	1	0
PKIE (0x4000_02B8)	Bit Symbol	—	—	—	—	—	—	PK1IE	PK0IE
	Read/Write	R						R/W	
	After reset	0						0	0
	Function	"0" is read						Input 0:disabled 1:enabled	

### 7.2.13 Port L(PL0 to PL1)

The port L is a general-purpose, 2-bit input port. For this port, inputs can be specified in units of bits. Besides the general-purpose input function, the port L performs the functions as the external interrupt input.

Reset initializes all bits of the port L as general-purpose input ports with input disabled.

To use the external interrupt input for releasing STOP mode, select this function in the PLFR1 register and enable input in the PLIE register. These settings enable the interrupt input even if the STBYCR2<DRVE> bit in the clock/mode control block is set to stop driving of pins during STOP mode.

**(Note)** In modes other than STOP mode, interrupt input is enabled regardless of the PxFR register setting as long as input is enabled in PxIE. Make sure to disable unused interrupts when programming the device.

Port L circuit type

	7	6	5	4	3	2	1	0
Type	—	—	—	—	—	—	T5	T5

Port L register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PL1	PL0
Read/Write	R						R	
After reset	"0" is read						"0"	

PL  
(0x4000\_02C0)

Port L function register 1

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PL1F1	PL0F1
Read/Write	R						R/W	
After reset	0						0	0
Function	"0" is read						0:PORT 1: INTA	0:PORT 1: INTB

PLFR1  
(0x4000\_02C8)

Port L input enable control register

	7	6	5	4	3	2	1	0
Bit Symbol	—	—	—	—	—	—	PL1IE	PL0IE
Read/Write	R						R/W	
After reset	0						0	0
Function	"0" is read						Input 0:disabled 1:enabled	

PLIE  
(0x4000\_02F8)

## 7.3 Block Diagrams of Ports

### 7.3.1 Port Types

The ports are classified into 20 types shown below. Please refer to the following pages for the block diagrams of each port type.

Type	Port	Function1	Function2	Function3	Analog	Pull-up	Pull-down	OD	Note
T1	i/o	o	-	-	-	R	R	○	Function output triggered by enable signal
T2	i/o	o	-	-	-	R	R	○	
T3	i/o	i	-	-	-	R	R	○	
T4	i/o	i(int)	-	-	-	R	R	○	
T5	i	i(int)	-	-	-	-	-	-	
T6	i/o	i/o	-	-	-	NoR	-	-	Function output triggered by enable signal
T7	i/o	i	-	-	-	NoR	-	-	
T8	i/o	i	-	-	-	-	NoR	-	
T9	i/o	i/o	i	-	-	R	R	○	
T10	i/o	i	o	-	-	R	R	○	
T11	i/o	i	i	-	-	R	R	○	
T12	i/o	i	i(int)	-	-	R	R	○	
T13	i/o	o	o	-	-	R	R	○	
T14	i/o	o	i(int)	-	-	R	R	○	
T15	i/o	i	i/o	i	-	R	R	○	
T16	i/o	-	-	-	○	R	R	○	
T17	i/o	i	-	-	○	R	R	○	
T18	i/o	o	-	-	-	R	-	-	
T19	i/o	o	-	-	-	NoR	-	-	Function output triggered by enable signal
T20	i/o	i	-	-	-	NoR	NoR	○	BOOT input enabled during reset

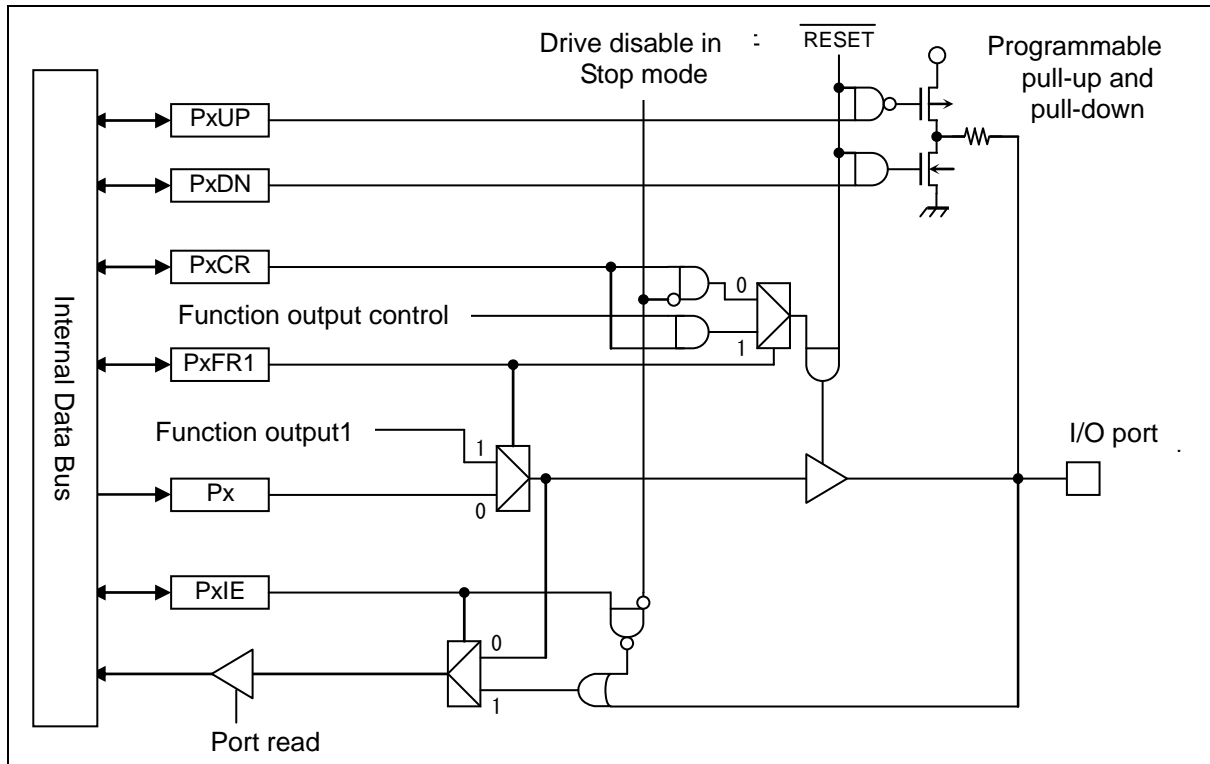
R : Forced disable during reset.

NoR : Unaffected by reset.

### 7.3.2 Type T1

Type T1 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data as well.

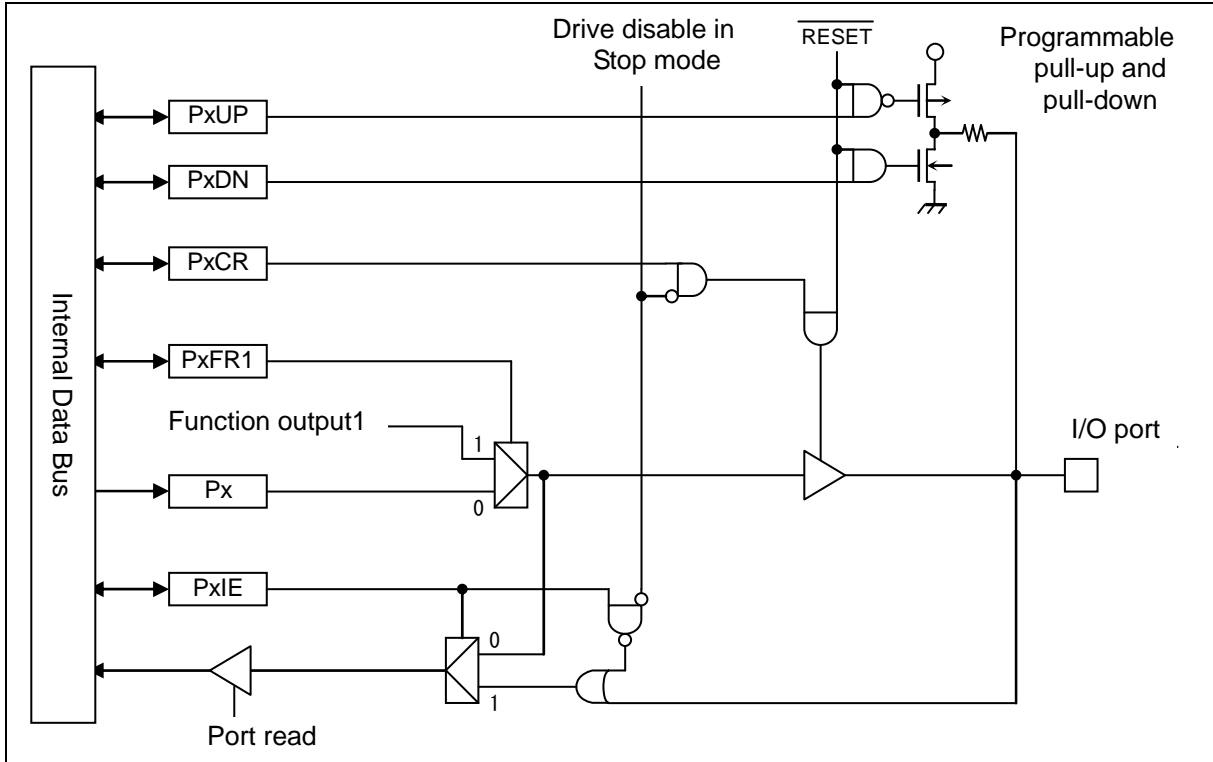
The function output is controlled by an enable signal. If enabled, the function data is output.





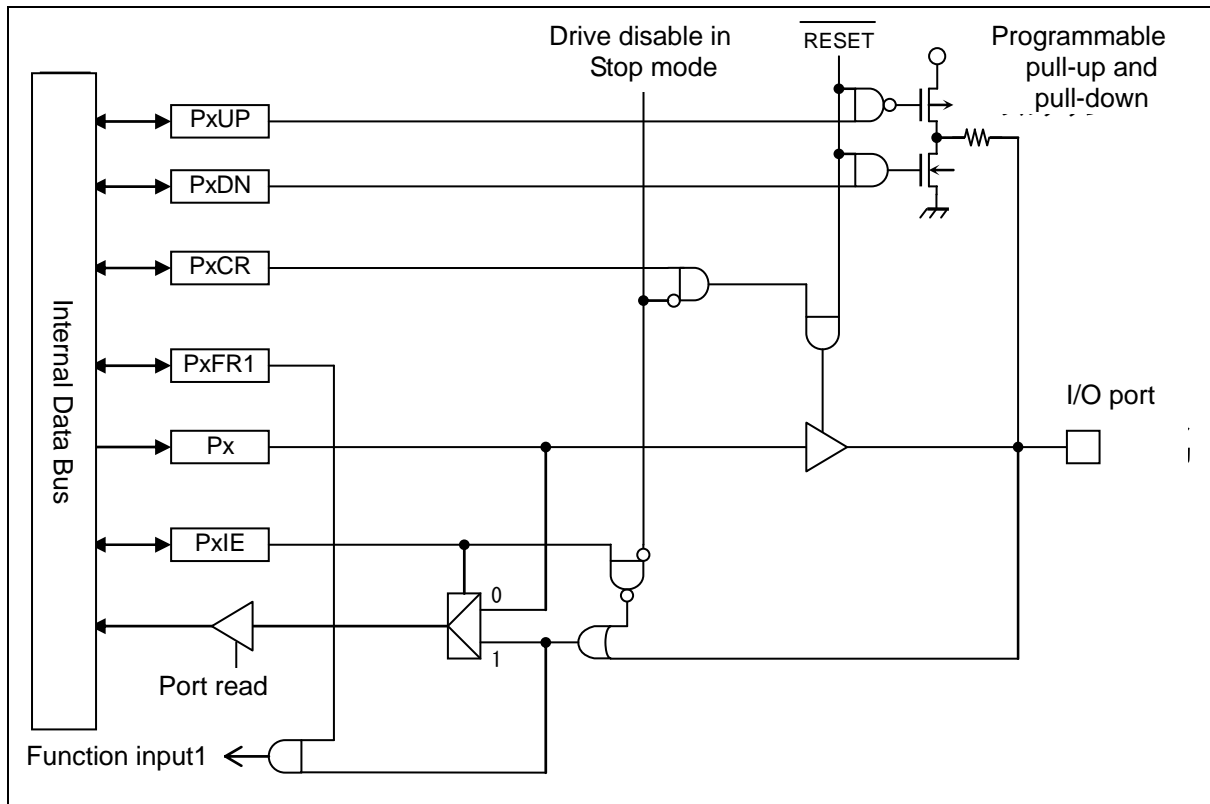
### 7.3.3 Type T2

Type T2 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data as well.



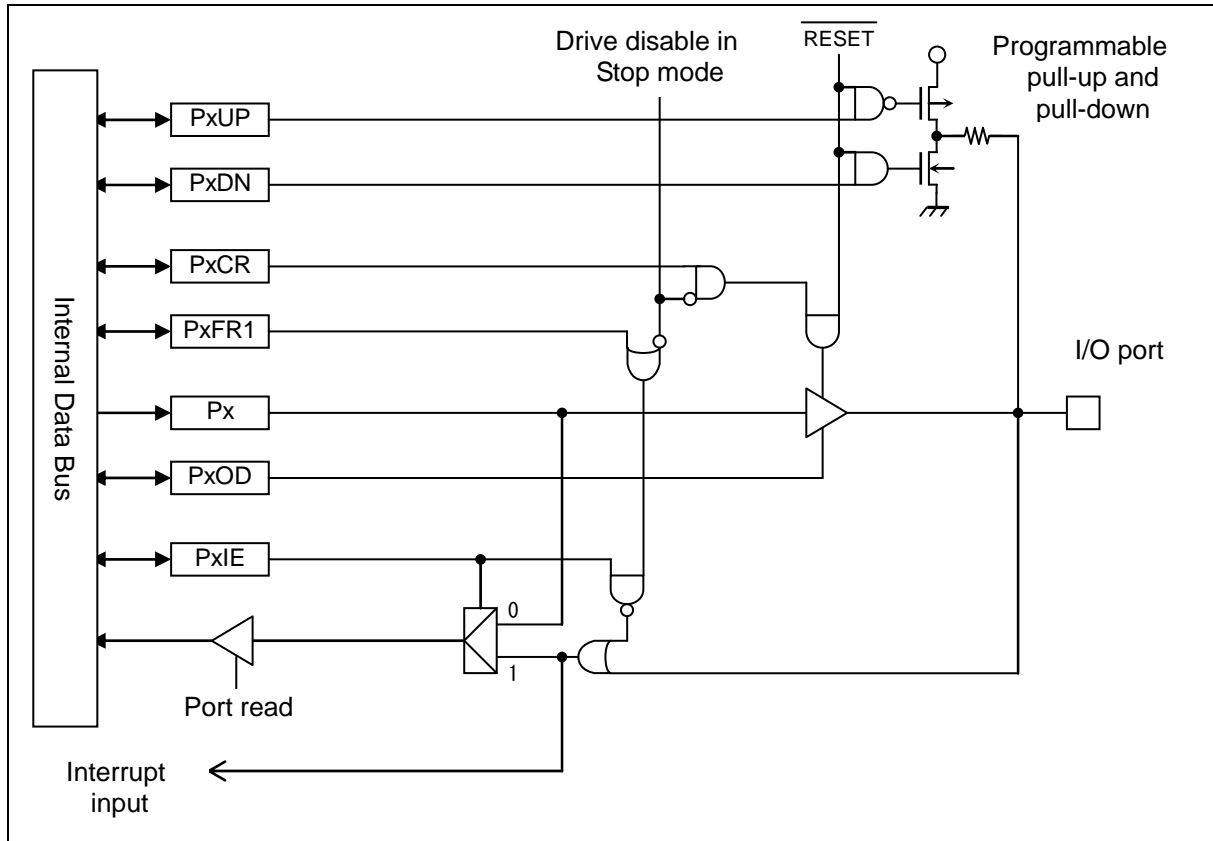
### 7.3.4 Type T3

Type T3 is a general-purpose input/output port with pull-up and pull-down. It is used to input function data as well.



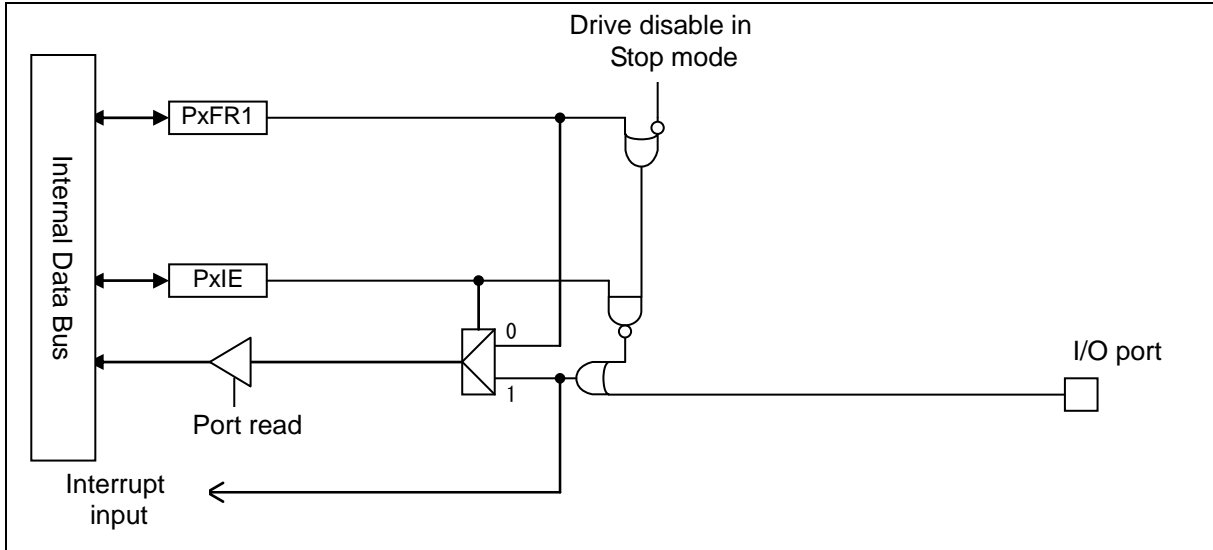
### 7.3.5 Type T4

Type T4 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data and interrupt input as well.



### 7.3.6 Type T5

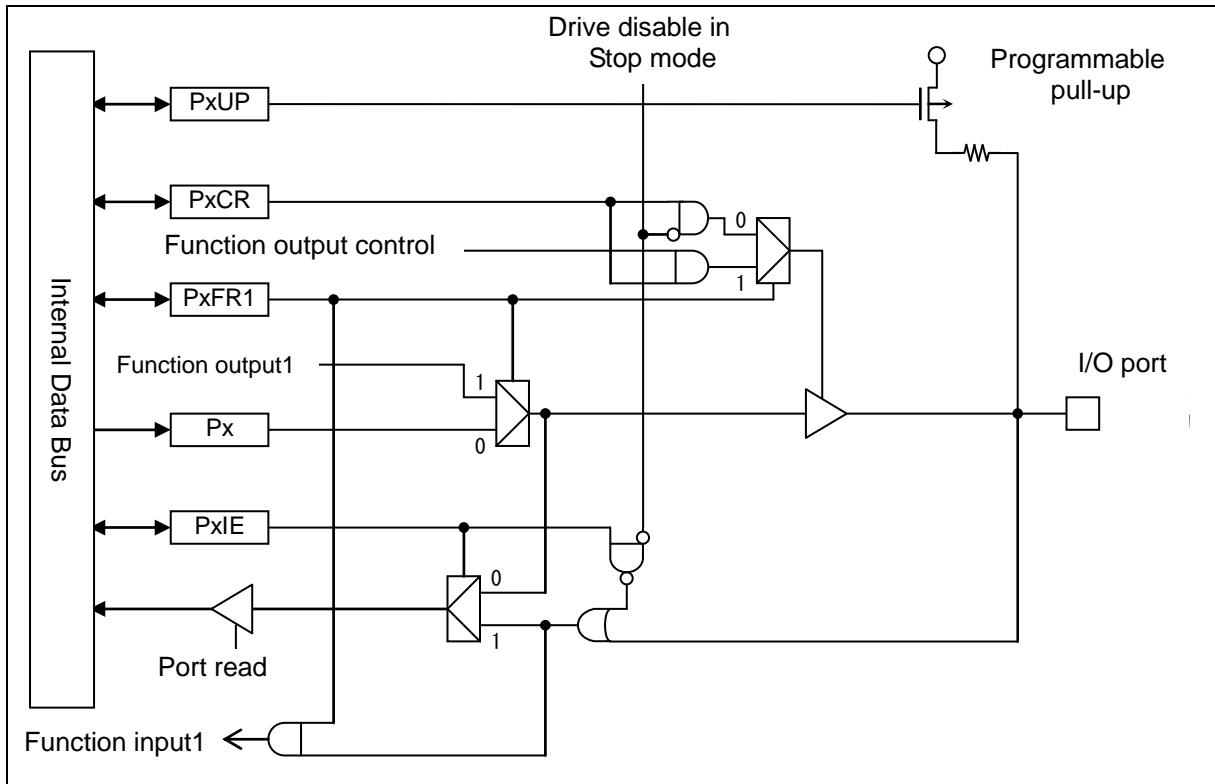
Type T5 is a general-purpose input/output port. It is used to interrupt input as well.



7.3.7 Type T6

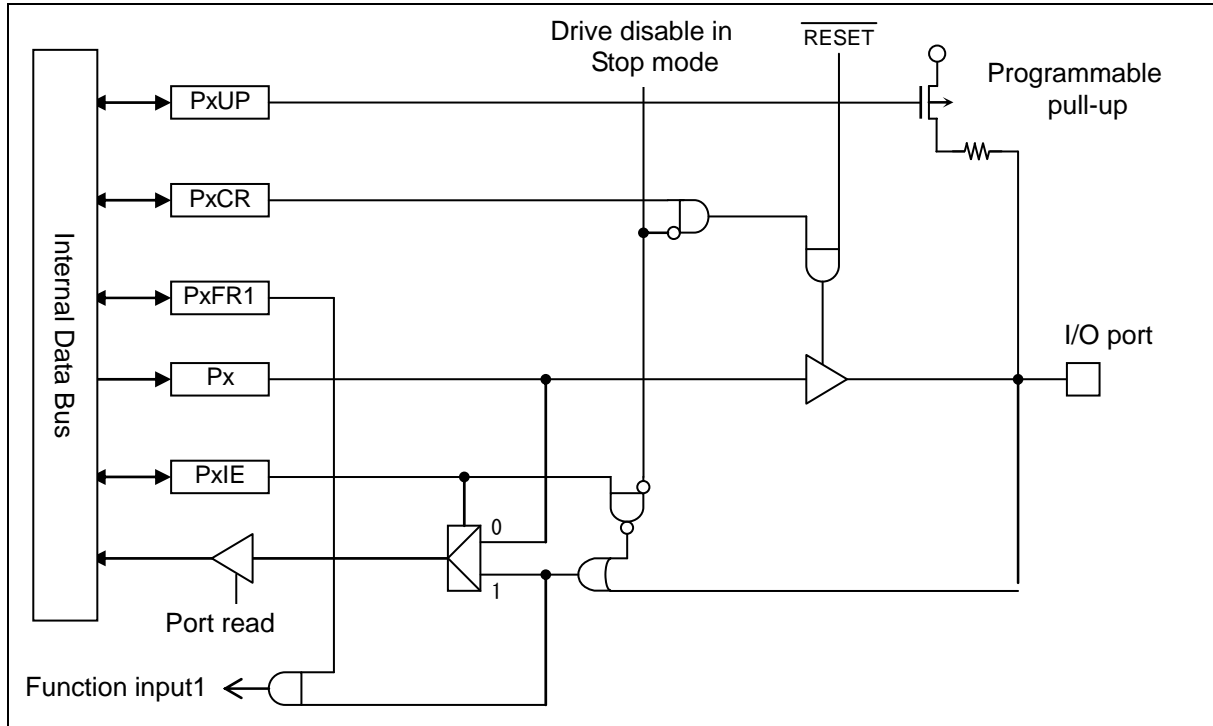
Type T6 is a general-purpose port with pull-up. It is used to output function data and input interrupt as well.

The function output is controlled by an enable signal. If enabled, the function data is output.



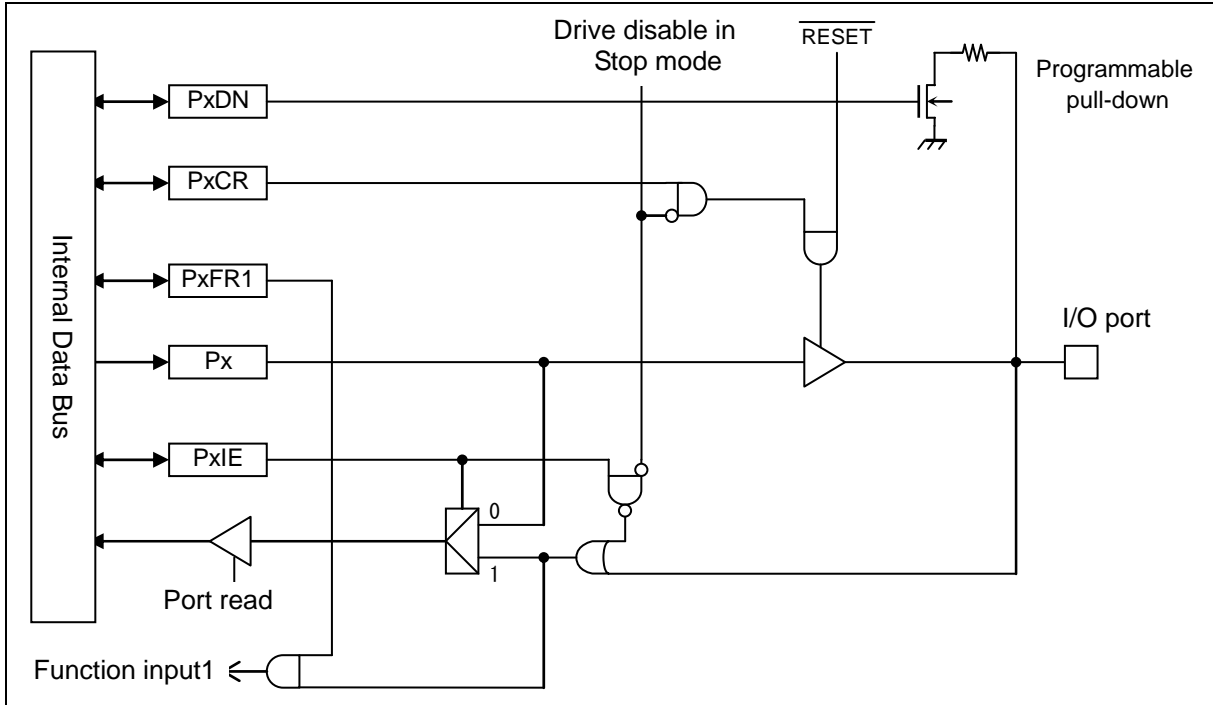
### 7.3.8 Type T7

Type T7 is a general-purpose input/output port with pull-up. It is used to input function data as well.



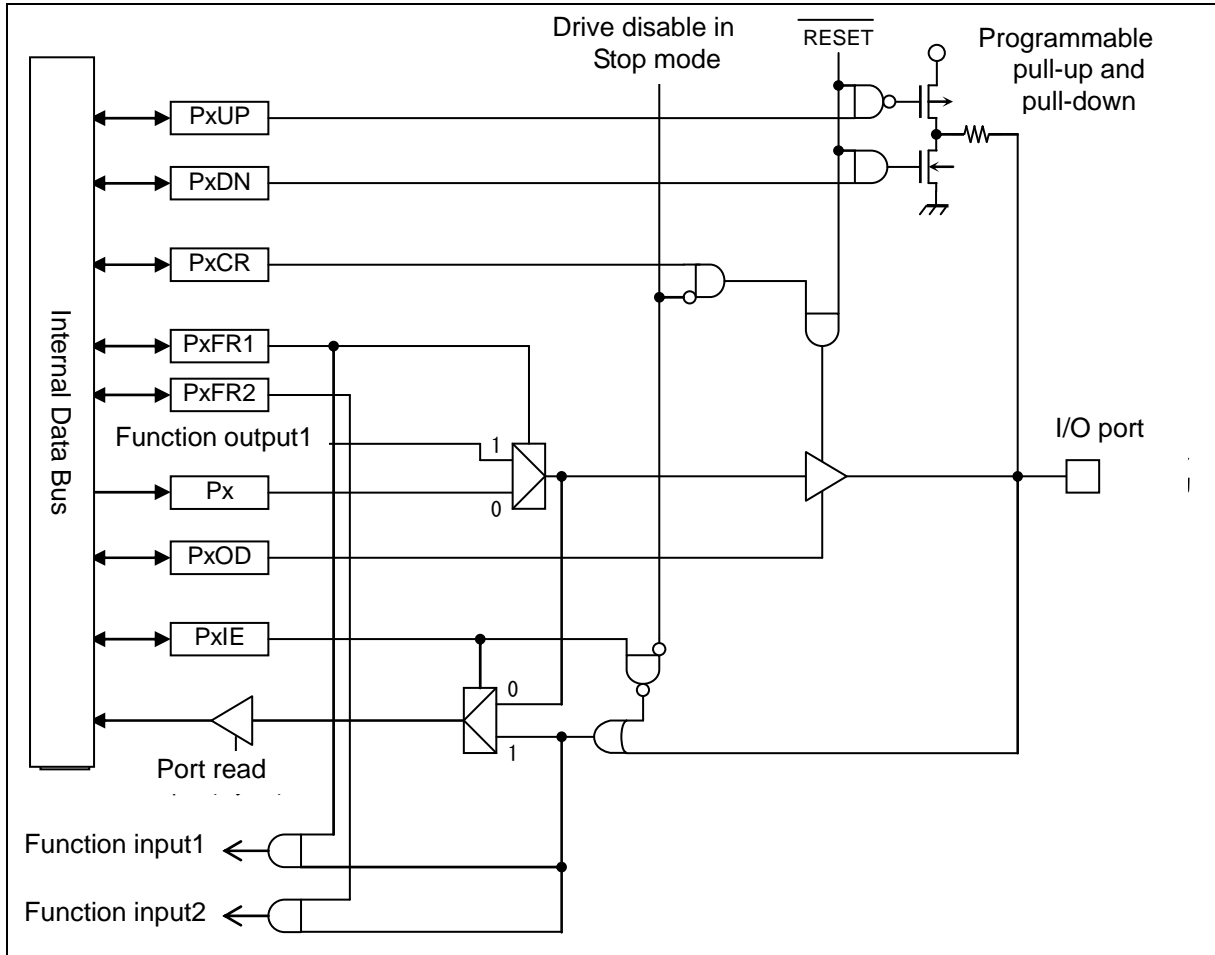
### 7.3.9 Type T8

Type T8 is a general-purpose input/output port with pull-down. It is used to input function data as well.



### 7.3.10 Type T9

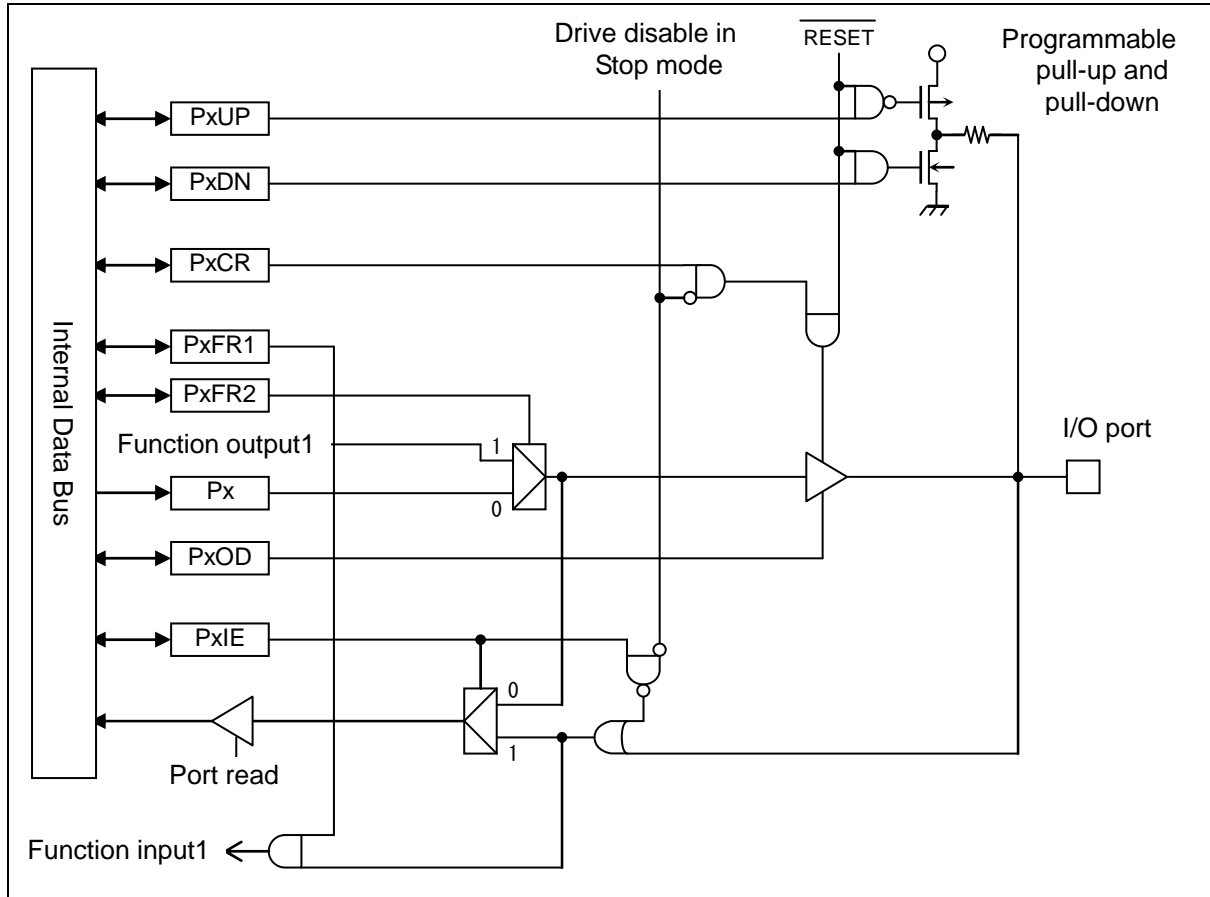
Type T9 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data and two input function data as well.





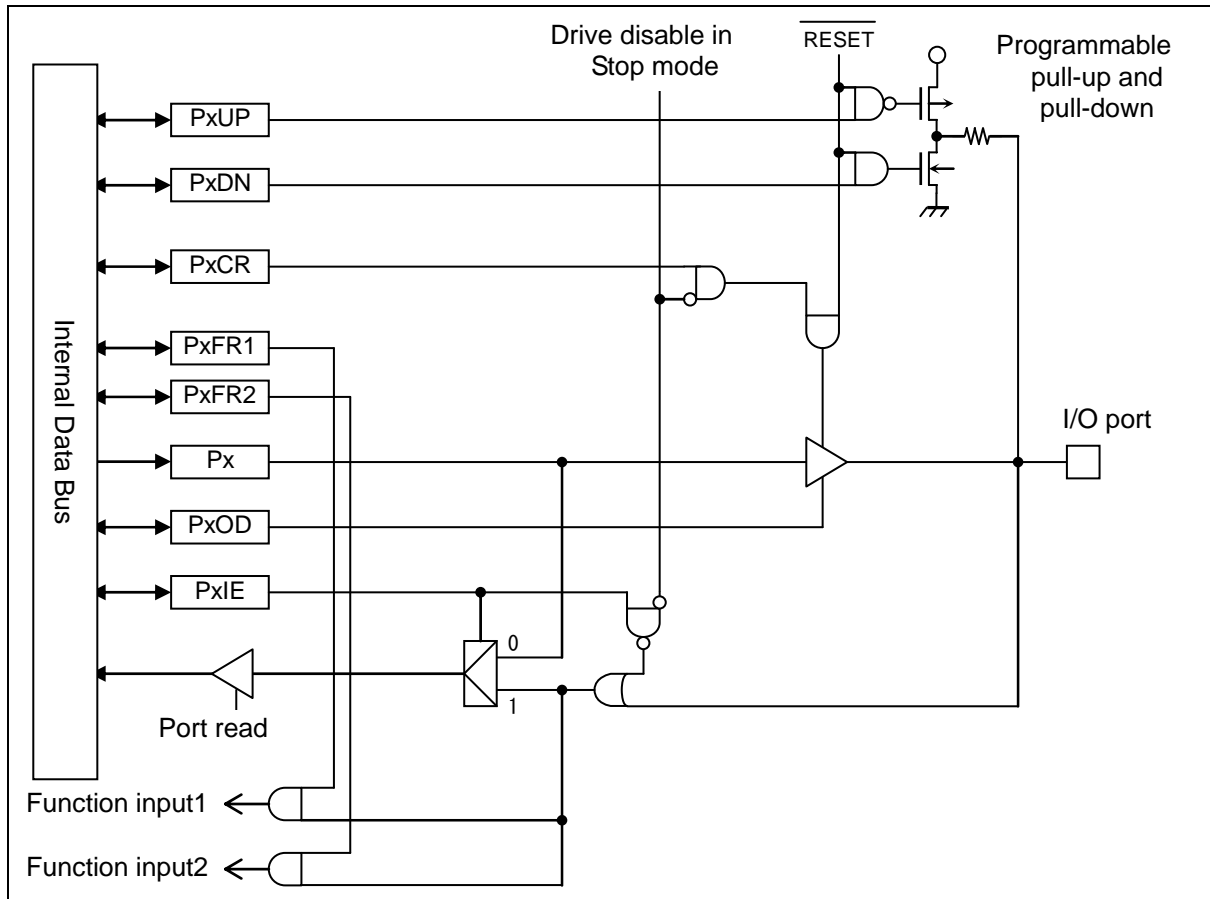
### 7.3.11 Type T10

Type T10 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data and input function data as well.



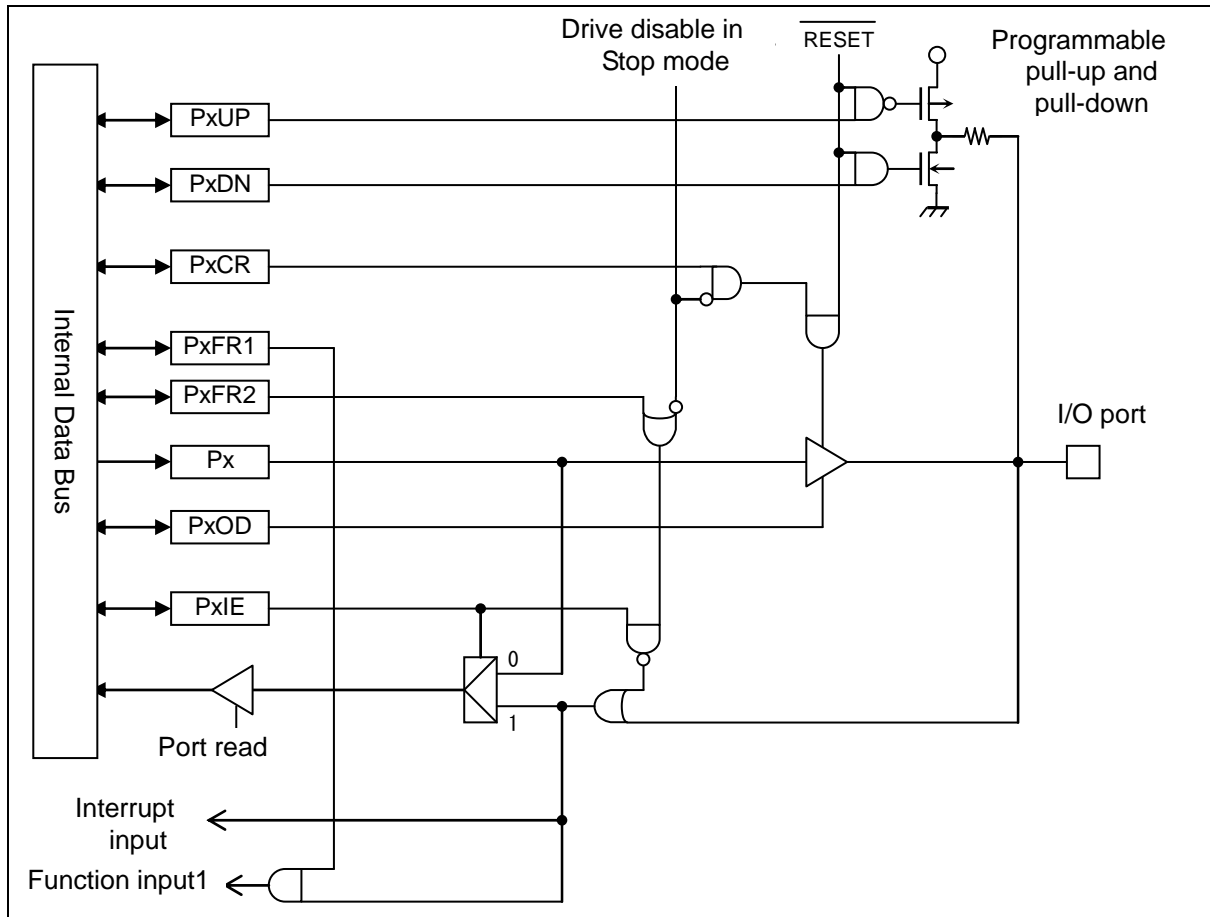
7.3.12 Type T11

Type T11 is a general-purpose input/output port with pull-up and pull-down. It is used to two input function data as well.



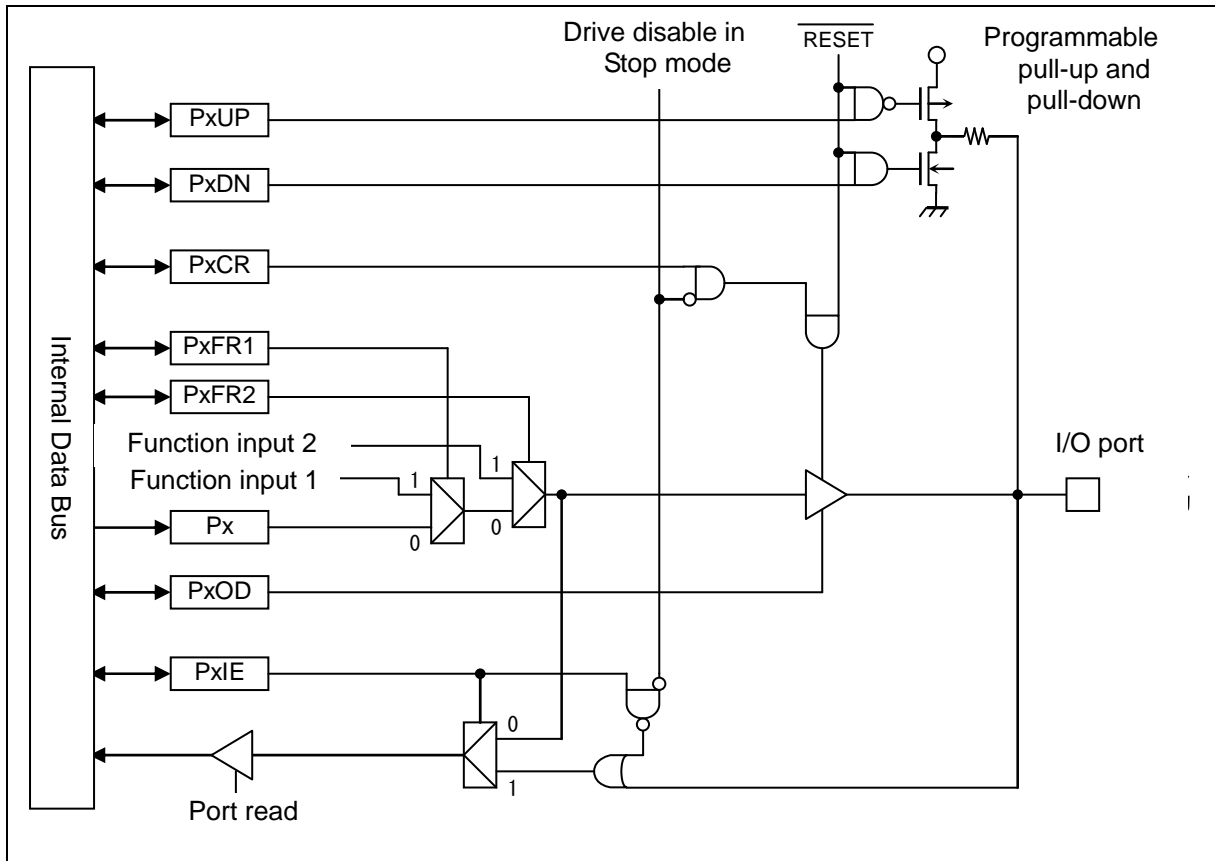
7.3.13 Type T12

Type T12 is a general-purpose input/output port with pull-up and pull-down. It is used to input function data and interrupt input as well.



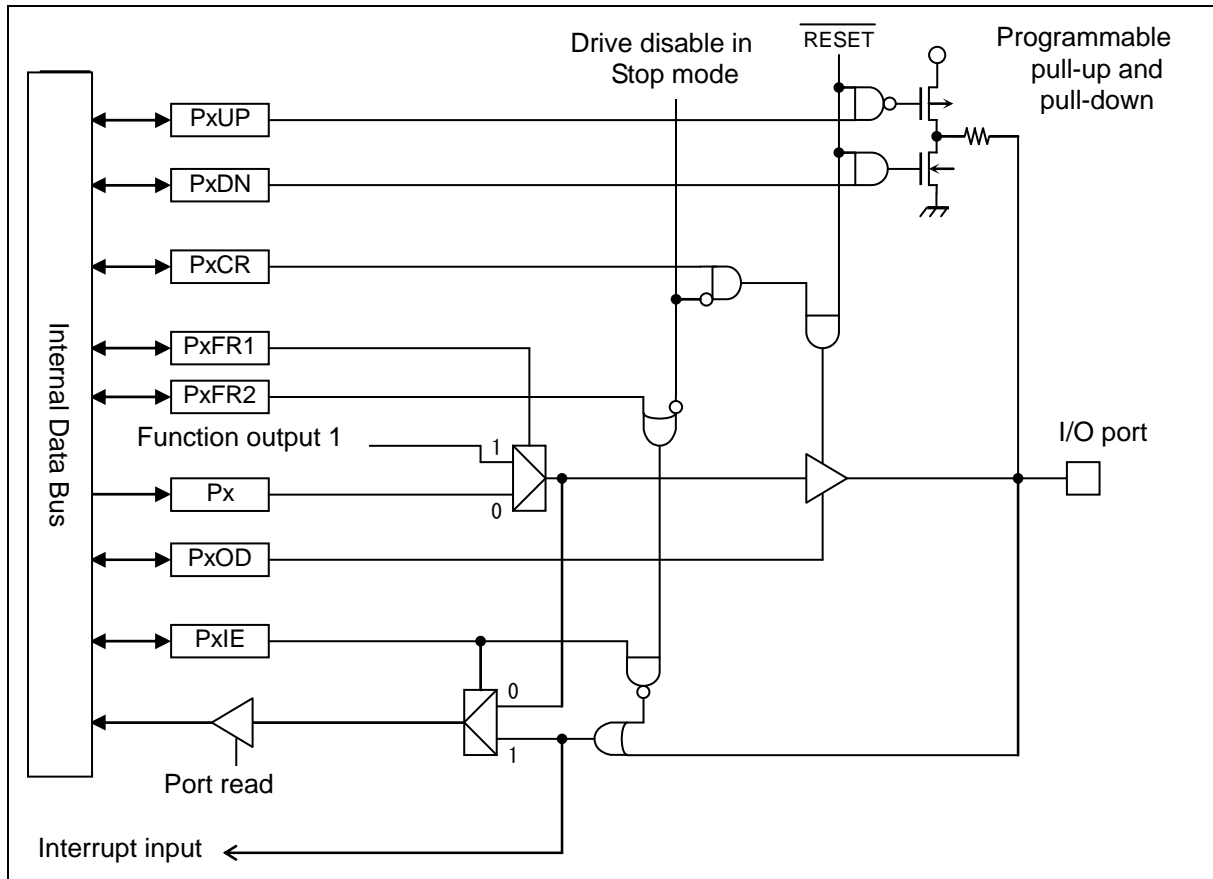
7.3.14 Type T13

Type T13 is a general-purpose input/output port with pull-up and pull-down. It is used to two output function data as well.



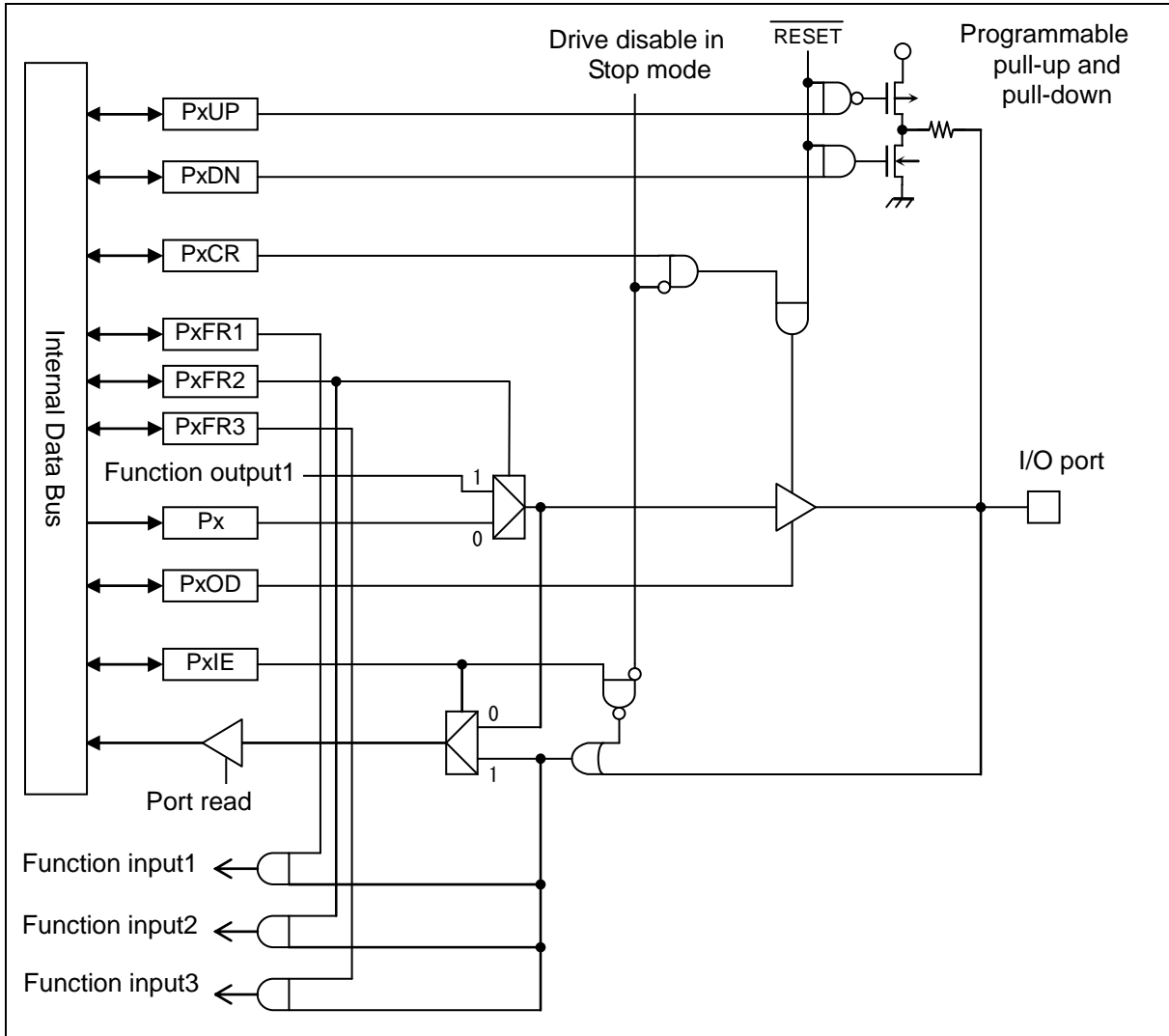
7.3.15 Type T14

Type T14 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data and interrupt input as well.



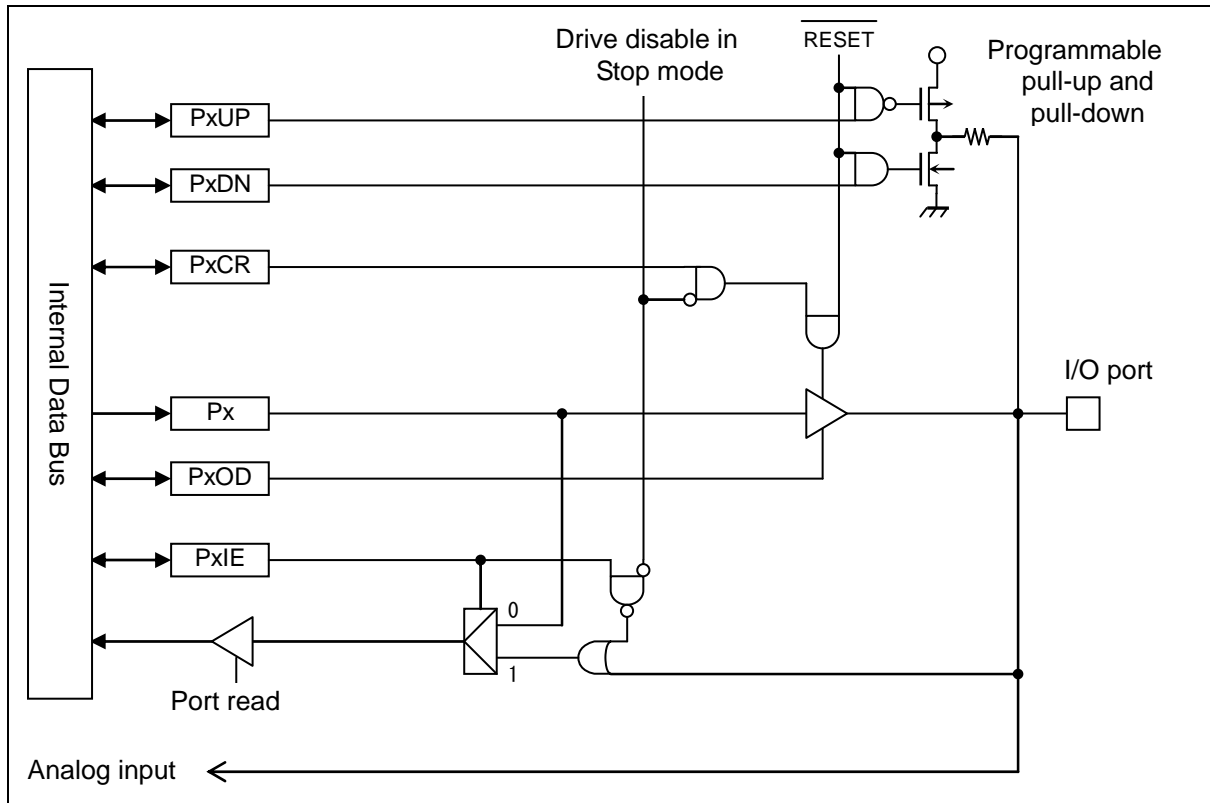
### 7.3.16 Type T15

Type T15 is a general-purpose input/output port with pull-up and pull-down. It is used to output function data and three input function data as well.



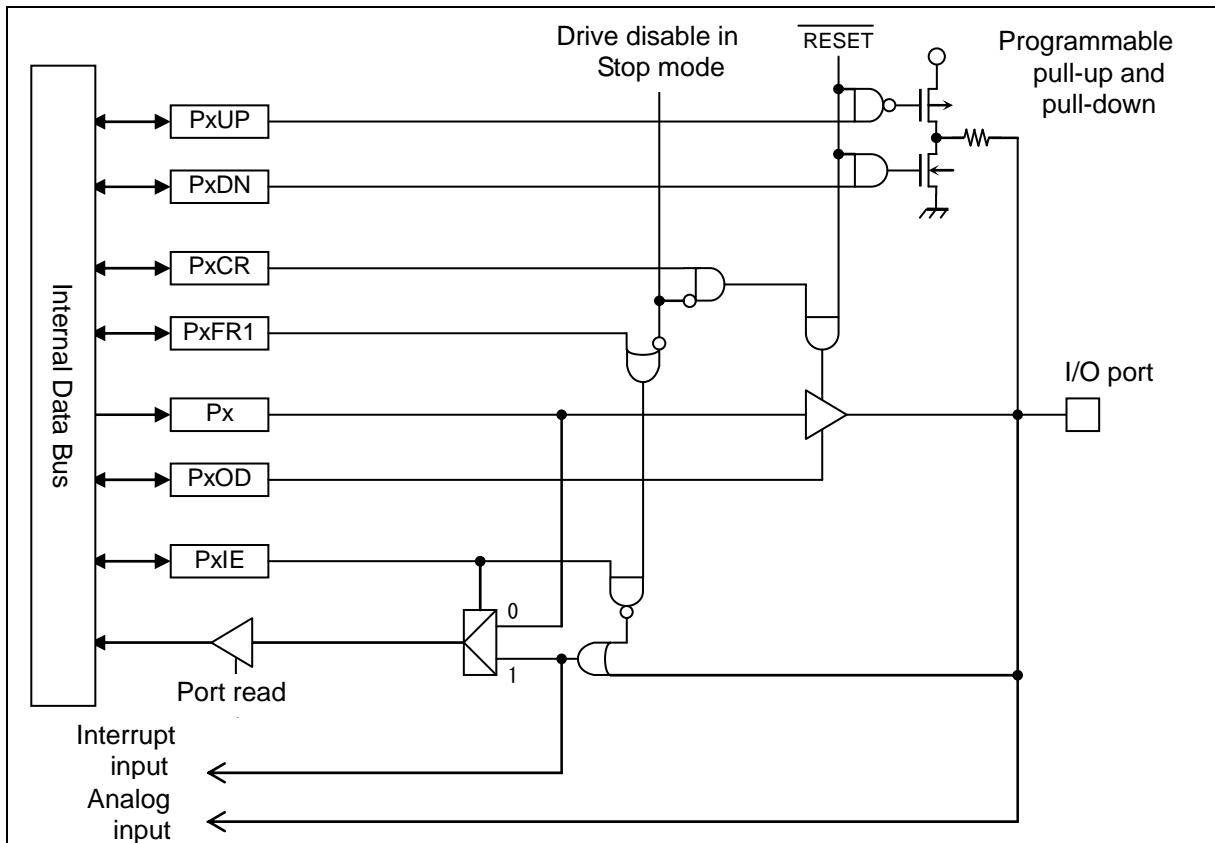
7.3.17 Type T16

Type T16 is a general-purpose input/output port with pull-up and pull-down. It is used to input analog signals for A/D converter as well.



7.3.18 Type T17

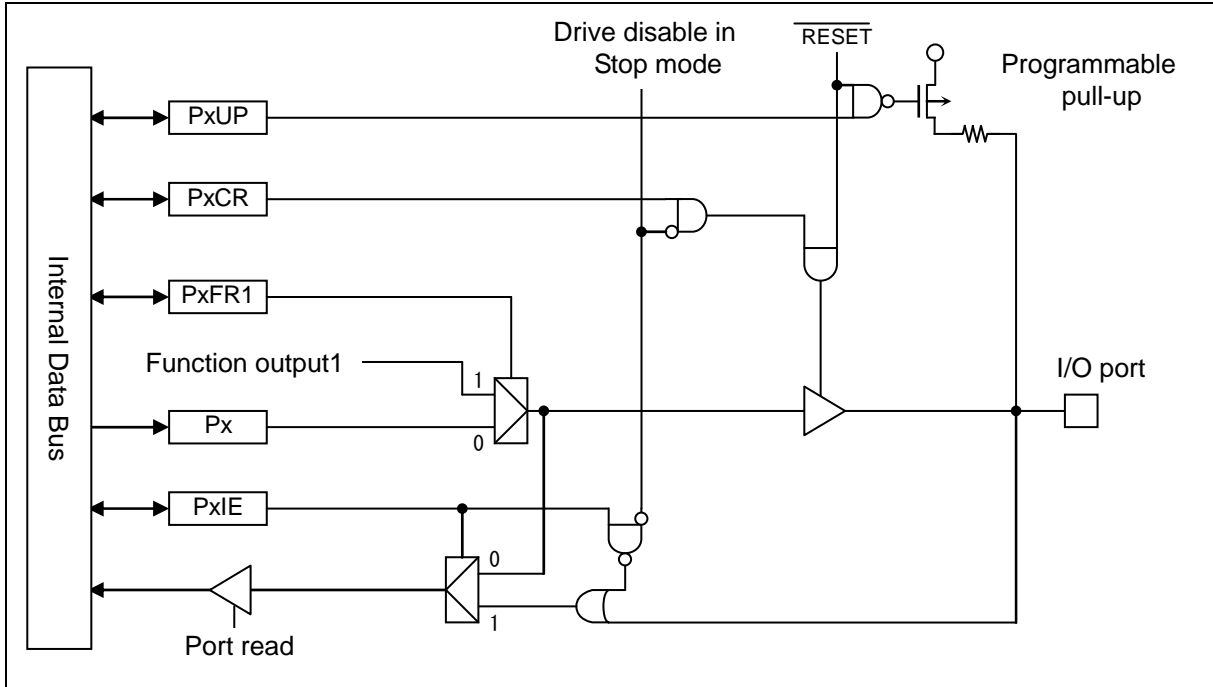
Type T17 is a general-purpose input/output port with pull-up and pull-down. It is used to input analog signals for A/D converter and interrupt input as well.





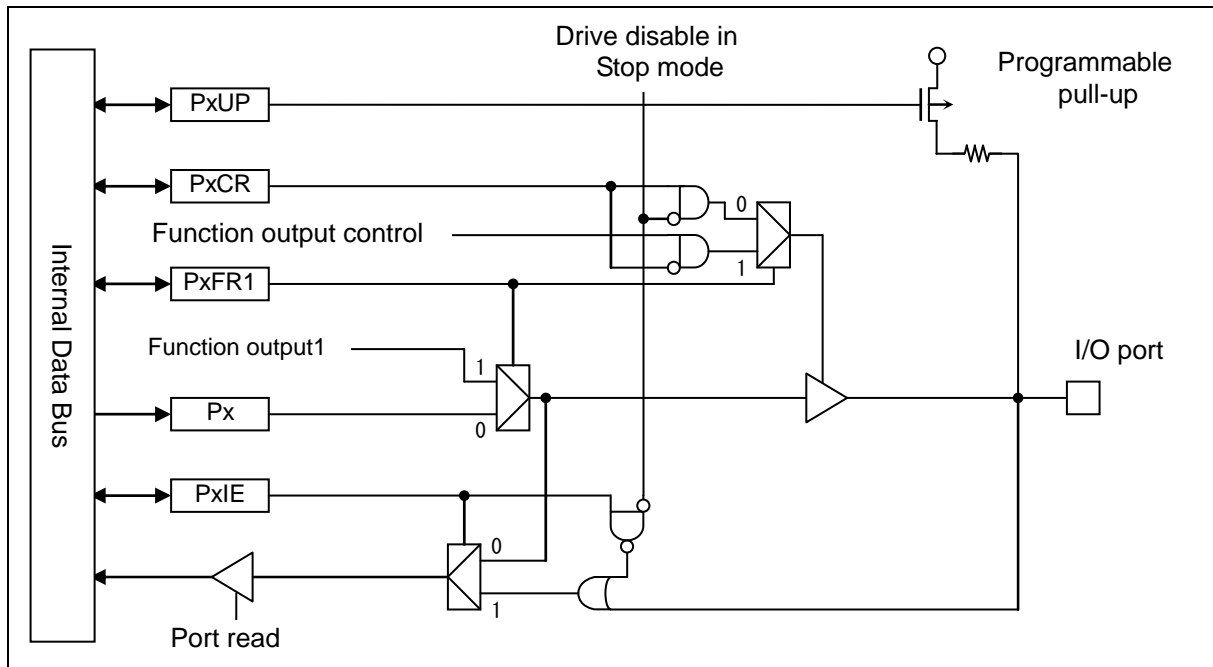
### 7.3.19 Type T18

Type T18 is a general-purpose input/output port with pull-up. It is used to output function data as well.



### 7.3.20 Type T19

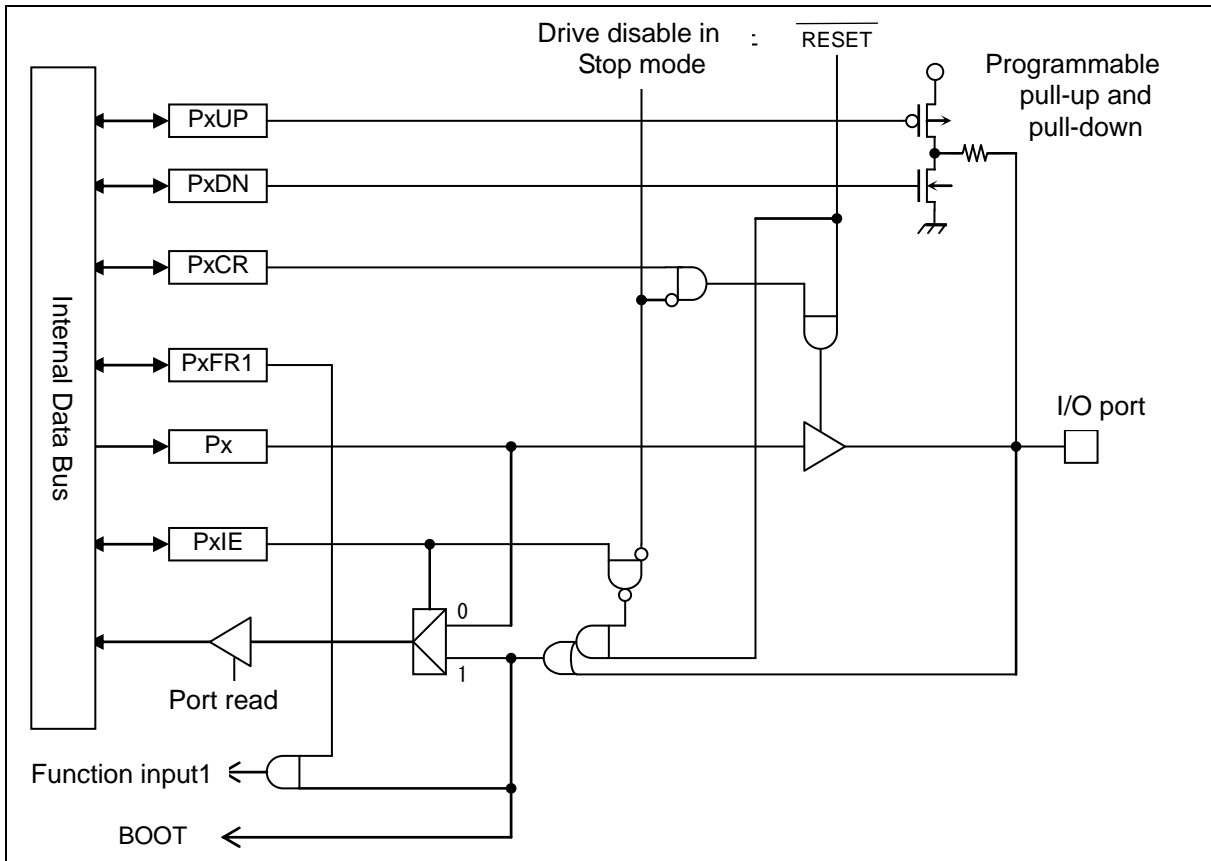
Type T19 is a general-purpose port with pull-up. It is used to output function data as well. The function output is controlled by an enable signal. If enabled, the function data is output.



7.3.21 Type T20

Type T20 is a general-purpose input/output port with pull-up and pull-down. It is used to input function data as well.

During reset, it functions as an input port for a BOOT signal.



## 8. 16-bit Timer/Event Counters (TMRBs)

### 8.1 Outline

TMPM370 have the eight channels multi-functional 16-bit timer/event counter. (TMRB0 through TMRB7) TMRBs operate in the following five operation modes:

- 16-bit interval timer mode
- 16-bit event counter mode
- 16-bit programmable square-wave output mode (PPG)

The use of the capture function allows TMRBs to perform the following two measurements

- Pulse width measurement
- One-shot pulse generation from an external trigger pulse

## 8.2 Specification differences among channels

Channels (TMRB0 through TMRB7) operate independently and the functions are same except the differences as shown in Table 8-1 and Table 8-2. Therefore, the operational descriptions here are explained only for TMRB0.

Table 8-1 Differences in the Specifications of TMRB Modules (1)

Specification Channel	External pins	
	External clock/ capture trigger input pin	Timer flip-flop output pin
TMRB0	TB0IN (shared with PA0)	TB0OUT (shared with PA1)
TMRB1	TB1IN (shared with PA2)	TB1OUT (shared with PA3)
TMRB2	TB2IN (shared with PE4)	TB2OUT (shared with PE5)
TMRB3	TB3IN (shared with PE6)	TB3OUT (shared with PE7)
TMRB4	TB4IN (shared with PA7)	TB4OUT (shared with PE3)
TMRB5	TB5IN (shared with PD0)	TB5OUT (shared with PD1)
TMRB6	TB6IN (shared with PA6)	TB6OUT (shared with PA5)
TMRB7	TB7IN (shared with PF0)	TB7OUT (shared with PF1)

Table 8-2 Differences in the Specifications of TMRB Modules (2)

Specification Channel	Interrupt	
	Capture interrupt	TMRB interrupt
TMRB0	INTCAP00 INTCAP01	INTTB00 INTTB01
TMRB1	INTCAP10 INTCAP11	INTTB10 INTTB11
TMRB2	INTCAP20 INTCAP21	INTTB20 INTTB21
TMRB3	INTCAP30 INTCAP31	INTTB30 INTTB31
TMRB4	INTCAP40 INTCAP41	INTTB40 INTTB41
TMRB5	INTCAP50 INTCAP51	INTTB50 INTTB51
TMRB6	INTCAP60 INTCAP61	INTTB60 INTTB61
TMRB7	INTCAP70 INTCAP71	INTTB70 INTTB71

### 8.3 Configuration

Each channel consists of a 16-bit up-counter, two 16-bit timer registers (one of which is double-buffered), two 16-bit capture registers, two comparators, a capture input control, a timer flip-flop and its associated control circuit.

Timer operation modes and the timer flip-flop are controlled by registers.

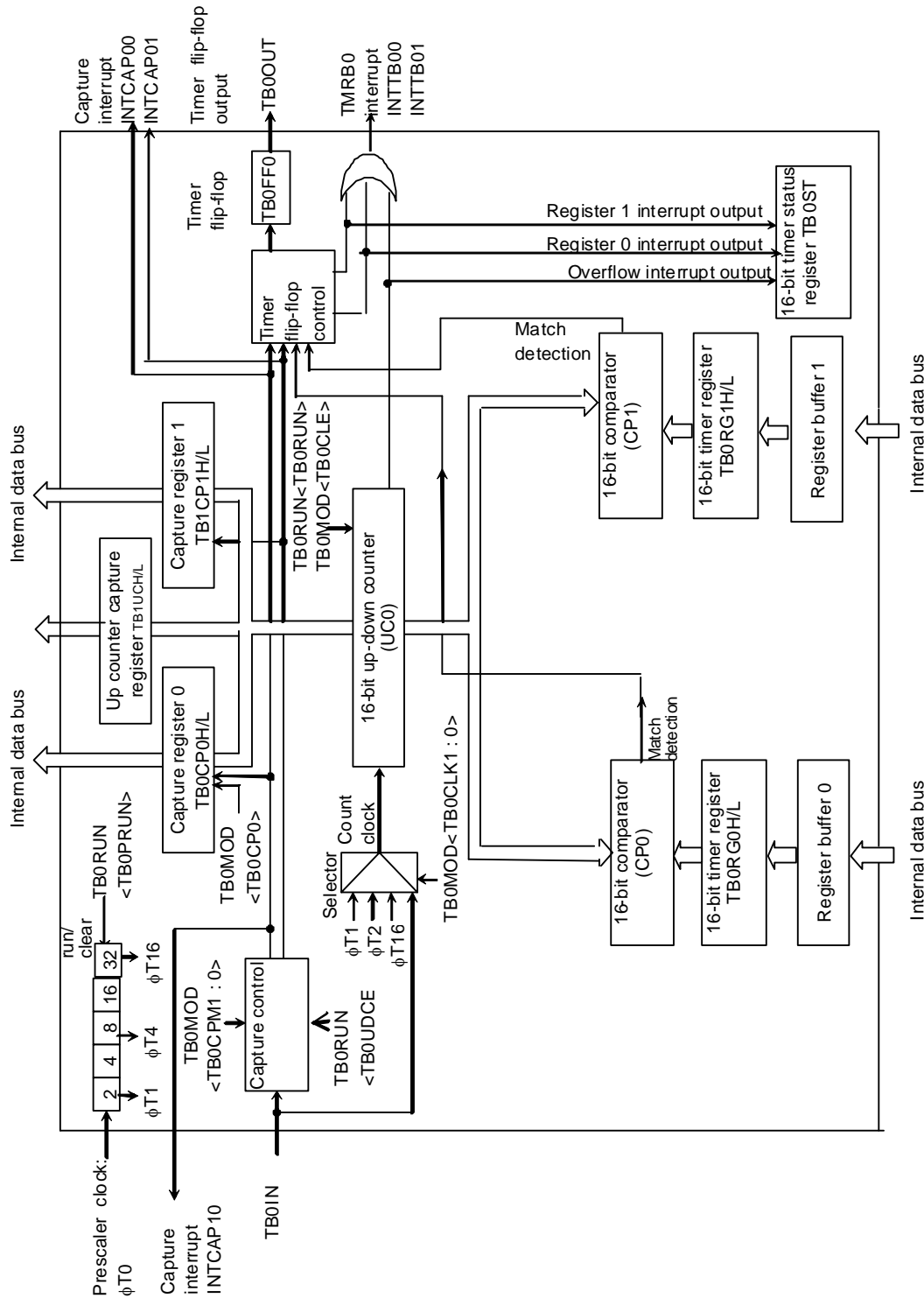


Fig. 8-1 TMRB0 Block Diagram (the same applies to channels 1 through 7)

## 8.4 Registers

### 8.4.1 TMRB registers

Table 8-3 shows the register names and addresses of each channel.

Table 8-3 TMRB registers

Channel		TMRB0		TMRB1		TMRB2		TMRB3	
Specification									
Register names (addresses)	Timer enable register	TB0EN	0x4001_0000	TB1EN	0x4001_0040	TB2EN	0x4001_0080	TB3EN	0x4001_00C0
	Timer RUN register	TB0RUN	0x4001_0004	TB1RUN	0x4001_0044	TB2RUN	0x4001_0084	TB3RUN	0x4001_00C4
	Timer control register	TB0CR	0x4001_0008	TB1CR	0x4001_0048	TB2CR	0x4001_0088	TB3CR	0x4001_00C8
	Timer mode register	TB0MOD	0x4001_000C	TB1MOD	0x4001_004C	TB2MOD	0x4001_008C	TB3MOD	0x4001_00CC
	Timer flip-flop control register	TB0FFCR	0x4001_0010	TB1FFCR	0x4001_0050	TB2FFCR	0x4001_0090	TB3FFCR	0x4001_00D0
	Timer status register	TB0ST	0x4001_0014	TB1ST	0x4001_0054	TB2ST	0x4001_0094	TB3ST	0x4001_00D4
	Interrupt mask register	TB0IM	0x4001_0018	TB1IM	0x4001_0058	TB2IM	0x4001_0098	TB3IM	0x4001_00D8
	Timer up counter register	TB0UC	0x4001_001C	TB1UC	0x4001_005C	TB2UC	0x4001_009C	TB3UC	0x4001_00DC
	Timer register	TB0RG0	0x4001_0020	TB1RG0	0x4001_0060	TB2RG0	0x4001_00A0	TB3RG0	0x4001_00E0
		TB0RG1	0x4001_0024	TB1RG1	0x4001_0064	TB2RG1	0x4001_00A4	TB3RG1	0x4001_00E4
Capture register	TB0CP0	0x4001_0028	TB1CP0	0x4001_0068	TB2CP0	0x4001_00A8	TB3CP0	0x4001_00E8	
	TB0CP1	0x4001_002C	TB1CP1	0x4001_006C	TB2CP1	0x4001_00AC	TB3CP1	0x4001_00EC	

Channel		TMRB4		TMRB5		TMRB6		TMRB7	
Specification									
Register names (addresses)	Timer enable register	TB4EN	0x4001_0100	TB5EN	0x4001_0140	TB6EN	0x4001_0180	TB7EN	0x4001_01C0
	Timer RUN register	TB4RUN	0x4001_0104	TB5RUN	0x4001_0144	TB6RUN	0x4001_0184	TB7RUN	0x4001_01C4
	Timer control register	TB4CR	0x4001_0108	TB5CR	0x4001_0148	TB6CR	0x4001_0188	TB7CR	0x4001_01C8
	Timer mode register	TB4MOD	0x4001_010C	TB5MOD	0x4001_014C	TB6MOD	0x4001_018C	TB7MOD	0x4001_01CC
	Timer flip-flop control register	TB4FFCR	0x4001_0110	TB5FFCR	0x4001_0150	TB6FFCR	0x4001_0190	TB7FFCR	0x4001_01D0
	Timer status register	TB4ST	0x4001_0114	TB5ST	0x4001_0154	TB6ST	0x4001_0194	TB7ST	0x4001_01D4
	Interrupt mask register	TB4IM	0x4001_0118	TB5IM	0x4001_0158	TB6IM	0x4001_0198	TB7IM	0x4001_01D8
	Timer up counter register	TB4UC	0x4001_011C	TB5UC	0x4001_015C	TB6UC	0x4001_019C	TB7UC	0x4001_01DC
	Timer register	TB4RG0	0x4001_0120	TB5RG0	0x4001_0160	TB6RG0	0x4001_01A0	TB7RG0	0x4001_01E0
		TB4RG1	0x4001_0124	TB5RG1	0x4001_0164	TB6RG1	0x4001_01A4	TB7RG1	0x4001_01E4
Capture register	TB4CP0	0x4001_0128	TB5CP0	0x4001_0168	TB6CP0	0x4001_01A8	TB7CP0	0x4001_01E8	
	TB4CP1	0x4001_012C	TB5CP1	0x4001_016C	TB6CP1	0x4001_01AC	TB7CP1	0x4001_01EC	

8.4.1.1 TMRBn enable register (channels 0 through 7)

TMRBn enable register (n=0~7)

		31	30	29	28	27	26	25	24
TbEnEN (0x4001_0xx0)	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		23	22	21	20	19	18	17	16
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		15	14	13	12	11	10	9	8
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		7	6	5	4	3	2	1	0
	bit Symbol	TbEnEN							
	Read/Write	R/W							
	After reset	0							
	Function	TMRBn operation 0: Disabled 1: Enabled							

<TbEnEN>: Specifies the TMRBn operation. When the operation is disabled, no clock is supplied to the other registers in the TMRBn module. This can reduce power consumption. (This disables reading from and writing to the other registers.)

To use the TMRBn, enable the TMRBn operation (set to “1”) before programming each register in the TMRBn module.

After the TMRBn operation is executed and then disabled, the settings will be maintained in each registers.



## 8.4.1.2 TMRB RUN register (channels 0 through 7)

TMRBn RUN register (n=0~7)

	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
bit Symbol						TBnPRUN		TBnRUN
Read/Write	R					R/W	R	R/W
After reset	0					0	0	0
Function	"0" is read.					Timer Run/Stop Control 0: Stop & clear 1: Count * The bit 1 can be read as "0."		

<TBnRUN> :Controls the TMRBn count operation.

- 0: Stop counting and the counter is cleared to "0".
- 1: Start counter

<TBnPRUN> :Controls the TMRBn prescaler operation.

- 0: Stop prescaler operation and the prescaler is cleared to "0".
- 1: Start prescaler operation.

## 8.4.1.3 TMRB control register (channels 0 through 7)

TMRBn control register (n=0~7)

	31	30	29	28	27	26	25	24
TnCR (0x4001_0xx8)	bit Symbol							
	Read/Write	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
bit Symbol	TnWBF				I2Tn		TRGSELn	CSSELn
Read/Write	R/W	R/W	R/W	R	R/W	R	R/W	R/W
After reset	0	0	0	0	0	0	0	0
Function	Double Buffer 0: Disabled 1: Enabled	Write "0".	Write "0".	"0" is read.	IDLE 0: Stop 1: Operation	"0" is read.	External Trigger select 0: Rising edge 1: Falling edge	Counter Start select 0: Software start 1: External trigger

<CSSELn>: Selects how the timer starts counting.

0: Select software for timer count start.

1: Select external trigger for timer count start.

<TRGSELn>: Selects the active edge of the external trigger signal.

0: Select rising edge of external trigger.

1: Select falling edge of external trigger.

<I2Tn>: Controls the clock keep/ stop operation during the IDLE mode.

0: Stop the clock.

1: Keep clock operation during IDLE mode.

<TnWBF>: Controls the enabling/disabling of double buffering.

0: Disable Double Buffer.

1: Enable Double Buffer.

(Note) TnCR register must not be changed during Timer operation (TnRUN=1)

## 8.4.1.4 TMRB mode register (channels 0 thorough 7)

TMRBn mode register(n=0~7)

	31	30	29	28	27	26	25	24
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
bit Symbol								
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
bit Symbol		TBnRSWR	TBnCP0	TBnCPM1	TBnCPM0	TBnCLE	TBnCLK1	TBnCLK0
Read/Write	R	R/W	W	R/W				
After reset	0	0	1	0	0	0	0	0
Function	"0" is read.	Writes to timer registers 0 and 1 (when double buffering is enabled)  0: Can be written separately 1: Must be written simultaneously	Software capture control  0: Software capture 1: Don't care	Capture timing 00: Disable 01: TBnIN ↑ 10: TBnIN ↑ TBnIN ↓ 11: Disable		Up-counter clear control  0: Clear/disable 1: clear/enable	Source clock select 00: TBnIN pin input 01: φT1 10: φT4 11: φT16	

<TBnCLK1:0>:Selects the TMRBn timer count clock.

- 00: select TBnIN input pin
- 01: select φT1 (1/2φT0)
- 10: select φT4 (1/8φT0)
- 11: select φT16 (1/32φT0)

<TBnCLE>:Clears and controls the TMRBn up-counter.

- "0": Disables clearing of the up-counter.
- "1": Clears up-counter if there is a match with timer register 1 (TBnRG1).

<TBnCPM1:0>:Specifies TMRBn capture timing.

- "00": Capture disable
- "01": Takes count values into capture register 0 (TBnCP0) upon rising of TBnIN pin input.
- "10": Takes count values into capture register 0 (TBnCP0) upon rising of TBnIN pin input. Takes count values into capture register 1 (TBnCP1) upon falling of TBnIN pin input.
- "11": Capture disable

<TBnCP0>:Captures count values by software and takes them into capture register 0 (TBnCP0).

<TBnRSWR>: Controls the timing to write to timer registers 0 and 1 when double buffering is enabled.

“0”: Timer registers 0 and 1 can be written separately, even in case writing preparation is ready for only one register.

“1”: In case both registers are not ready to be written, Timer registers 0 and 1 can not be written

**(Note 1)** The value read from bit 5 of TBnMOD is “1”.

**(Note 2)** TBnMOD register must not be changed during Timer operation (TBnRUN=1”)

8.4.1.5 TMRB flip-flop control register (channels 0 through 7)

TMRBn flip-flop control register (n=0~7)

	31	30	29	28	27	26	25	24	
TnFFCR (0x4001_0xx0)	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	23	22	21	20	19	18	17	16	
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	15	14	13	12	11	10	9	8	
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	7	6	5	4	3	2	1	0	
	bit Symbol			TBnC1T1	TBnC0T1	TBnE1T1	TBnE0T1	TBnFF0C1	TBnFF0C0
	Read/Write	R		R/W				R/W	
	After reset	1	1	0	0	0	0	1	1
	Function	"11" is read.		TBnFF0 reverse trigger 0: Disable trigger 1: Enable trigger				TBnFF0 control 00: Invert 01: Set 10: Clear 11: Don't care * This is always read as "11."	
				When the up-counter value is taken into TBnCP1	When the up-counter value is taken into TBnCP0	When the up-counter matches TBnRG1	When the up-counter matches TBnRG0		

<TBnFF0C1:0>:Controls the timer flip-flop.

- 00 : Reverses the value of TBnFF0
- 01 : Sets TBnFF0 to "1".
- 10 : Clears TBnFF0 to "0".
- 11 :Don't care

<TBnE0>:Reverses the timer flip-flop when the up-counter matches the timer register 0 (TBnRG0).

- 0: TBnFF0 not reverse
- 1: TBnFF0 reverse

<TBnE1>:Reverses the timer flip-flop when the up-counter matches the timer register 1 (TBnRG1).

- 0: TBnFF0 not reverse
- 1: TBnFF0 reverse

<TBnC0>:Reverses the timer flip-flop when the up-counter value is taken into the capture register 0 (TBnCP0).

- 0: TBnFF0 not reverse
- 1: TBnFF0 reverse

<TBnC1>:Reverses the timer flip-flop when the up-counter value is taken into the capture register 1 (TBnCP1).

- 0: TBnFF0 not reverse
- 1: TBnFF0 reverse

(Note) TBnFFCR register must not be changed during Timer operation (TBnRUN=1")

## 8.4.1.6 TMRB status register (channels 0 through 7)

TMRBn status register (n=0~7)

	31	30	29	28	27	26	25	24	
TnST (0x4001_0xx4)	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	23	22	21	20	19	18	17	16	
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	15	14	13	12	11	10	9	8	
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	
	After reset	0	0	0	0	0	0	0	
	7	6	5	4	3	2	1	0	
	bit Symbol					INTTBOFn	INTTBn1	INTTBn0	
	Read/Write	R				R			
	After reset	0				0	0	0	
	Function	"0" is read.				0: Interrupt not generated 1: Interrupt generated	0: Interrupt not generated 1: Interrupt generated	0: Interrupt not generated 1: Interrupt generated	

<INTTBn0>:Interrupt generated status for a match with timer register 0 (TnRG0)

- 0: No interrupt generated
- 1: Interrupt generated

<INTTBn1>:Interrupt generated status for a match with timer register 1 (TnRG1)

- 0: No interrupt generated
- 1: Interrupt generated

<INTTBOFn>:Interrupt generated status for an up-counter overflow occurs

- 0: No interrupt generated
- 1: Interrupt generated

**(Note) If any interrupt is generated, the flag that corresponds to the interrupt is set to TnST and the generation of interrupt is notified to the CPU.  
The flag is cleared by reading the TnST register.**

8.4.1.7 TMRB interrupt mask register (channels 0 through 7)

TMRBn interrupt mask register (n=0~7)

TBnIM  
(0x4001\_0xx8)

	31	30	29	28	27	26	25	24
bit Symbol	/							
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
bit Symbol	/							
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
bit Symbol	/							
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
bit Symbol	/					TBIMOFn	TBIMn1	TBIMn0
Read/Write	R					R/W		
After reset	0					0	0	0
Function	"0" is read					0: No Interrupt mask 1: Interrupt is masked	0: No Interrupt mask 1: Interrupt is masked	0: No Interrupt mask 1: Interrupt is masked

<TBIMn0>: Interrupt mask for a match with timer register 0 (TBnRG0)

- 0: No interrupt mask
- 1: Interrupt is masked

<TBIMn1>: Interrupt mask for a match with timer register 1 (TBnRG1).

- 0: No interrupt mask
- 1: Interrupt is masked

<TBIMOFn>: Interrupt mask for an up counter overflow.

- 0: No interrupt mask
- 1: Interrupt is masked

(Note) Even in case TBnIM set interrupt Mask, TBnST status register have a interrupt requested status.

8.4.1.8 TMRB read capture register (channels 0 through 7)

TBnUC read capture register (n=0~7)

	31	30	29	28	27	26	25	24
TBnUC (0x4001_0xxC)	/							
bit Symbol	/							
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
bit Symbol	/							
Read/Write	R	R	R	R	R	R	R	R
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
bit Symbol	UCn15	UCn14	UCn13	UCn12	UCn11	UCn10	UCn9	UCn8
Read/Write	R							
After reset	0							
Function	Data obtained by read capture: 15-8 bit data							
	7	6	5	4	3	2	1	0
bit Symbol	UCn7	UCn6	UCn5	UCn4	UCn3	UCn2	UCn1	UCn0
Read/Write	R							
After reset	0							
Function	Data obtained by read capture: 7-0 bit							

<UCn15-0> : Captured Up-counter value.



8.4.1.9 TMRB timer register (channels 0 through 7)

TBnRG0 timer register (n=0~7)

TBnRG0 (0x4001_0xx0)		31	30	29	28	27	26	25	24
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		23	22	21	20	19	18	17	16
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		15	14	13	12	11	10	9	8
	bit Symbol	TBnRG 015	TBnRG 014	TBnRG 013	TBnRG 012	TBnRG 011	TBnRG 010	TBnRG09	TBnRG08
	Read/Write	R/W							
	After reset	0							
Function	Timer count value: 15-8 bit data								
	7	6	5	4	3	2	1	0	
bit Symbol	TBnRG07	TBnRG06	TBnRG05	TBnRG04	TBnRG03	TBnRG02	TBnRG01	TBnRG00	
Read/Write	R/W								
After reset	0								
Function	Timer count value: 7-0 bit data								

<TBnRG015-000> : 16bit Compare value0 with Up- counter

TBnRG1 timer register (n=0~7)

TBnRG1 (0x4001_0xx4)		31	30	29	28	27	26	25	24
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		23	22	21	20	19	18	17	16
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		15	14	13	12	11	10	9	8
	bit Symbol	TBnRG 115	TBnRG 114	TBnRG 113	TBnRG 112	TBnRG 111	TBnRG 110	TBnRG19	TBnRG18
	Read/Write	R/W							
	After reset	0							
Function	Timer count value: 15-8 bit data								
	7	6	5	4	3	2	1	0	
bit Symbol	TBnRG17	TBnRG16	TBnRG15	TBnRG14	TBnRG13	TBnRG12	TBnRG11	TBnRG10	
Read/Write	R/W								
After reset	0								
Function	Timer count value: 7-0 bit data								

<TBnRG115-100> : 16bit Compare value1 with Up- counter

8.4.1.10 TMRB capture register (channels 0 through 7)

TBnCP0capture register (n=0~7)

TBnCP0 (0x4001_0xx8)		31	30	29	28	27	26	25	24
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		23	22	21	20	19	18	17	16
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		15	14	13	12	11	10	9	8
	bit Symbol	TBnCP 015	TBnCP 014	TBnCP 013	TBnCP 012	TBnCP 011	TBnCP 010	TBnCP09	TBnCP08
	Read/Write	R							
	After reset	0							
	Function	Timer capture value: 15-8 bit data							
		7	6	5	4	3	2	1	0
	bit Symbol	TBnCP07	TBnCP06	TBnCP05	TBnCP04	TBnCP03	TBnCP02	TBnCP01	TBnCP00
	Read/Write	R							
	After reset	0							
	Function	Timer capture value: 7-0 bit data							

<TBnCP015-000>: 16bit up-counter capture value0

TBnCP1 capture register (n=0~7)

TBnCP1 (0x4001_0xxC)		31	30	29	28	27	26	25	24
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		23	22	21	20	19	18	17	16
	bit Symbol								
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
		15	14	13	12	11	10	9	8
	bit Symbol	TBnCP 115	TBnCP 114	TBnCP 113	TBnCP 112	TBnCP 111	TBnCP 110	TBnCP19	TBnCP18
	Read/Write	R							
	After reset	0							
	Function	Timer capture value: 15-8 bit data							
		7	6	5	4	3	2	1	0
	bit Symbol	TBnCP17	TBnCP16	TBnCP15	TBnCP14	TBnCP13	TBnCP12	TBnCP11	TBnCP10
	Read/Write	R							
	After reset	0							
	Function	Timer capture value: 7-0 bit data							

<TBnCP115-100>: 16bit up-counter capture value1

## 8.5 Description of Operations for Each Circuit

The channels operate in the same way, except for the differences in their specifications as shown in Table 8-1 and Table 8-2. Therefore, the operational descriptions here are only for channel 0.

### 8.5.1 Prescaler

There is a 4-bit prescaler to generate the source clock for up-counter UC0. The prescaler input clock  $\phi T0$  is  $f_{\text{periph}}$ ,  $f_{\text{periph}}/2$ ,  $f_{\text{periph}}/4$ ,  $f_{\text{periph}}/8$ ,  $f_{\text{periph}}/16$  or  $f_{\text{periph}}/32$  selected by SYSCR1<PRCLK2:0> in the CG. The peripheral clock,  $f_{\text{periph}}$ , is either  $f_{\text{gear}}$ , a clock selected by SYSCR1<FPSEL> in the CG, or  $f_c$ , which is a clock before it is divided by the clock gear.

The operation or the stop of a prescaler is set with TBORUN<TB0PRUN> where writing "1" starts counting and writing "0" clears and stops counting. Table 8-4 show prescaler output clock resolutions.

Table 8-4 Prescaler Output Clock Resolutions @fc = 80MHz

Clear peripheral clock <FPSEL>	Clock gear value <GEAR2:0>	Prescaler clock selection <PRCK2:0>	Prescaler output clock resolution		
			$\phi T1$	$\phi T4$	$\phi T16$
0 (fgear)	000 (fc)	000 (fper iph/1)	$fc/2^1 (0.025\mu s)$	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$
		001 (fper iph/2)	$fc/2^2 (0.05\mu s)$	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		010 (fper iph/4)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		011 (fper iph/8)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		100 (fper iph/16)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		101 (fper iph/32)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
	100(fc/2)	000 (fper iph/1)	$fc/2^2 (0.05\mu s)$	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		001 (fper iph/2)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		010 (fper iph/4)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		011 (fper iph/8)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		100 (fper iph/16)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
		101 (fper iph/32)	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$	$fc/2^{11} (25.6\mu s)$
	101(fc/4)	000 (fper iph/1)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		001 (fper iph/2)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		010 (fper iph/4)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		011 (fper iph/8)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
		100 (fper iph/16)	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$	$fc/2^{11} (25.6\mu s)$
		101 (fper iph/32)	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$	$fc/2^{12} (51.2\mu s)$
	110(fc/8)	000 (fper iph/1)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		001 (fper iph/2)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		010 (fper iph/4)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
		011 (fper iph/8)	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$	$fc/2^{11} (25.6\mu s)$
		100 (fper iph/16)	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$	$fc/2^{12} (51.2\mu s)$
		101 (fper iph/32)	$fc/2^9 (6.4\mu s)$	$fc/2^{11} (25.6\mu s)$	$fc/2^{13} (102.4\mu s)$
1 (fc)	000 (fc)	000 (fper iph/1)	$fc/2^1 (0.025\mu s)$	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$
		001 (fper iph/2)	$fc/2^2 (0.05\mu s)$	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		010 (fper iph/4)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		011 (fper iph/8)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		100 (fper iph/16)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		101 (fper iph/32)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
	100(fc/2)	000 (fper iph/1)	—	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$
		001 (fper iph/2)	$fc/2^2 (0.05\mu s)$	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		010 (fper iph/4)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		011 (fper iph/8)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		100 (fper iph/16)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		101 (fper iph/32)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
	101(fc/4)	000 (fper iph/1)	—	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$
		001 (fper iph/2)	—	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		010 (fper iph/4)	$fc/2^3 (0.1\mu s)$	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		011 (fper iph/8)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		100 (fper iph/16)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		101 (fper iph/32)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$
	110(fc/8)	000 (fper iph/1)	—	—	$fc/2^5 (0.4\mu s)$
		001 (fper iph/2)	—	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$
		010 (fper iph/4)	—	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$
		011 (fper iph/8)	$fc/2^4 (0.2\mu s)$	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$
		100 (fper iph/16)	$fc/2^5 (0.4\mu s)$	$fc/2^7 (1.6\mu s)$	$fc/2^9 (6.4\mu s)$
		101 (fper iph/32)	$fc/2^6 (0.8\mu s)$	$fc/2^8 (3.2\mu s)$	$fc/2^{10} (12.8\mu s)$

- |          |   |
|----------|---|
| (Note 1) | The prescaler output clock $\phi T_n$ must be selected as $\phi T_n < f_{sys}$ . ( $\phi T_n$ is slower than $f_{sys}$ ). |
| (Note 2) | Do not change the clock gear while the timer is operating.  |
| (Note 3) | “—“ denotes a setting prohibited.   |

### 8.5.2 Up-counter (UC0)

UC0 is a 16-bit binary counter.

- Source clock

UC0 source clock, specified by TB0MOD<TB0CLK1:0>, can be selected from either three types  $\phi T1$ ,  $\phi T4$  and  $\phi T16$  of prescaler output clock or the external clock of the TB0IN pin.

- Count start/ stop

Counter operation is specified by TB0RUN<TB0RUN>. UC0 starts counting if <TB0RUN> = "1", and stops counting and clears counter value if <TB0RUN> = "0".

- Timing to clear UC0

- 1) When a compare match is detected

By setting TB0MOD<TB0CLE> = "1", UC0 is cleared in case the comparator detects a match between counter value and the value set in TB0RG1. UC0 operates as a free-running counter if TB0MOD<TB0CLE> = "0".

- 2) When UC0 stops

UC0 stops counting and clears counter value if TB0RUN <TB0RUN> = "0".

- UC0 overflow

If UC0 overflow occurs, the INTTB00 overflow interrupt is generated.

### 8.5.3 Timer registers (TB0RG0, TB0RG1)

TB0RG0 and TB0RG1 are registers for setting values to compare with up-counter values and two registers are built into each channel. If the comparator detects a match between a value set in this timer register and that in a UC0 up-counter, it outputs the match detection signal.

- Configuration

TB0RG0 and TB0RG1 of this timer registers are paired with register buffer - the double-buffered configuration. The two registers use TB0CR<TB0WBF> to control the enabling/disabling of double buffering. If <TB0WBF> = "0", double buffering is disabled and if <TB0WBF> = "1", it is enabled. If double buffering is enabled, data is transferred from register buffer to the TB0RG0 and TB0RG1 timer registers when there is a match between UC0 and TB0RG1.

- Default setting

The values of TB0RG0 and TB0RG1 become undefined after a reset. A reset disables the double buffer.

- Register setting

- 1) When not using double-buffering

To write data to the timer registers, either a 2-byte data transfer instruction or a 1-byte data transfer instruction written twice in the order of low-order 8 bits followed by high-order 8 bits can be used.

- 2) When using double-buffering

TB0RG0/ TB0RG1 and the register buffers are assigned to the same address. If <TB0WBF> = "0," the same value is written to TB0RG0, TB0RG1 and each register buffer; if <TB0WBF> = "1," the value is only written to each register buffer. Therefore, in order to write an initial value to the timer register, the register buffers must be set to "disable". Then set <TB0WBF> = "1" and write the following data to the register.

- Interrupt

INTTB00 is generated by UP0 count value matching with TB0RG0 value.

INTTB01 is generated by UP0 count value matching with TB0RG1 value.

### 8.5.4 Capture Control

This is a circuit that controls the timing to latch UC0 up-counter values into the TB0CP0 and TB0CP1 capture registers. The timing to latch data is specified by TB0MOD <TB0CPM1:0>.

Software can also be used to capture values from the UC0 up-counter into the capture register; specifically, UC0 values are taken into the TB0CP0 capture register each time "0" is written to TB0MOD<TB0CP0>. To use this capability, the prescaler must be running (TB0RUN<TB0PRUN> = "1").

### 8.5.5 Capture Registers (TB0CP0H/L, TB0CP1H/L)

These are 16-bit registers for latching values from the UC0 up-counter. To read data from the capture register, use a 16-bit data transfer instruction or read in the order of low-order bits followed by high-order bits.

### 8.5.6 Up-counter capture register (TB0UCH/L)

Other than the capturing functions shown above, the current count value of the UC0 can be captured by reading the TB0UC registers.

### 8.5.7 Comparators (CP0,CP1)

These are 16-bit comparators for detecting a match by comparing set values of the UC0 up-counter with set values of the TB0RG0 and TB0RG1 timer registers. If a match is detected, INTTB00 and INTTB01 are generated.

### 8.5.8 Timer Flip-flop (TB0FF0)

The timer flip-flop (TB0FF0) is reversed by a match signal from the comparator and a latch signal to the capture registers. It can be enabled or disabled to reverse by setting the TB0FFCR<TB0C1T1, TB0C0T1, TB0E1T1, TB0E0T1>.

The value of TB0FF0 becomes undefined after a reset. The flip-flop can be reversed by writing "00" to TB0FFCR<TB0FF0C1:0>. It can be set to "1" by writing "01," and can be cleared to "0" by writing "10."

The TB0FF0 value can be output to the timer output pin:TB0OUT (shared with PA0). To enable timer output, the port A related registers PACR and PAFR1 must be programmed beforehand.

### 8.5.9 Capture interrupt (INTCAP00, INTCAP01)

Interrupts INTCAP00 and INTCAP01 can be generated at the timing of latching values from the UC0 up-counter into the TB0CP0 and TB0CP1 capture registers. The interrupt setting is specified by the CPU.



## 8.6 Description of Operations for Each Mode

### 8.6.1 16-bit Interval Timer Mode

#### -Generating interrupts at periodic cycles

To generate the INTTB01 interrupt, specify a time interval in the TB0RG1 timer register. Same as TB0RG0, INTTB01 interrupt is generated by setting different interval time value to TB0RG1 timer register,

### 8.6.2 16-bit Event Counter Mode

It is possible to make it the event counter by using an input clock as an external clock (TB0IN pin input).

The up-counter counts up on the rising edge of TB0IN pin input. It is possible to read the count value by capturing value using software and reading the captured value.

To use it as an event counter, put the prescaler in a "RUN" state (TB0RUN<TB0PRUN> = "1").

### 8.6.3 16-bit Programmable Square Wave Output Mode (PPG)

Square waves with any frequency and any duty (programmable square waves) can be output. The output pulse can be either low-active or high-active.

Programmable square waves can be output from the TB0OUT pin by triggering the timer flip-flop (TB0FF) to reverse when the set value of the up-counter (UCO) matches the set values of the timer registers (TB0RG0 and TB0RG1). Note that the set values of TB0RG0 and TB0RG1 must satisfy the following requirement:

$$(\text{Set value of TB0RG0}) < (\text{Set value of TB0RG1})$$

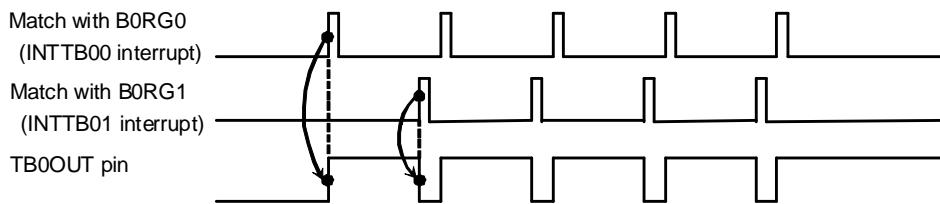


Fig. 8-2 Example of Output of Programmable Square Wave (PPG)

In this mode, by enabling the double buffering of TB0RG0 and TB0RG1, the value of register buffers are shifted into TB0RG0 and TB0RG1 when the set value of the up-counter matches the set value of TB0RG1. Since software writing time is secured by double buffer, this facilitates handling of small duties pulse.

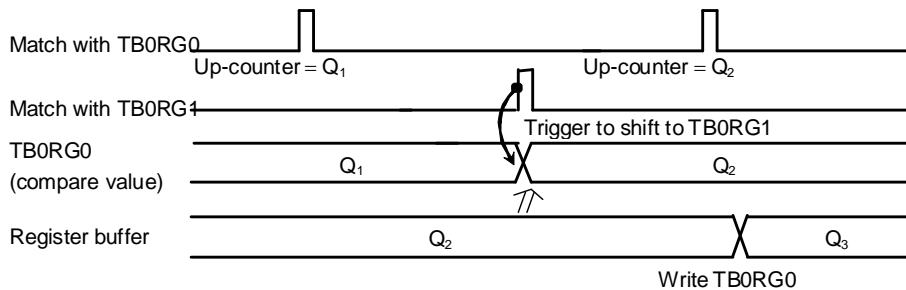


Fig. 8-3 Register Buffer Operation

The block diagram of this mode is shown below.

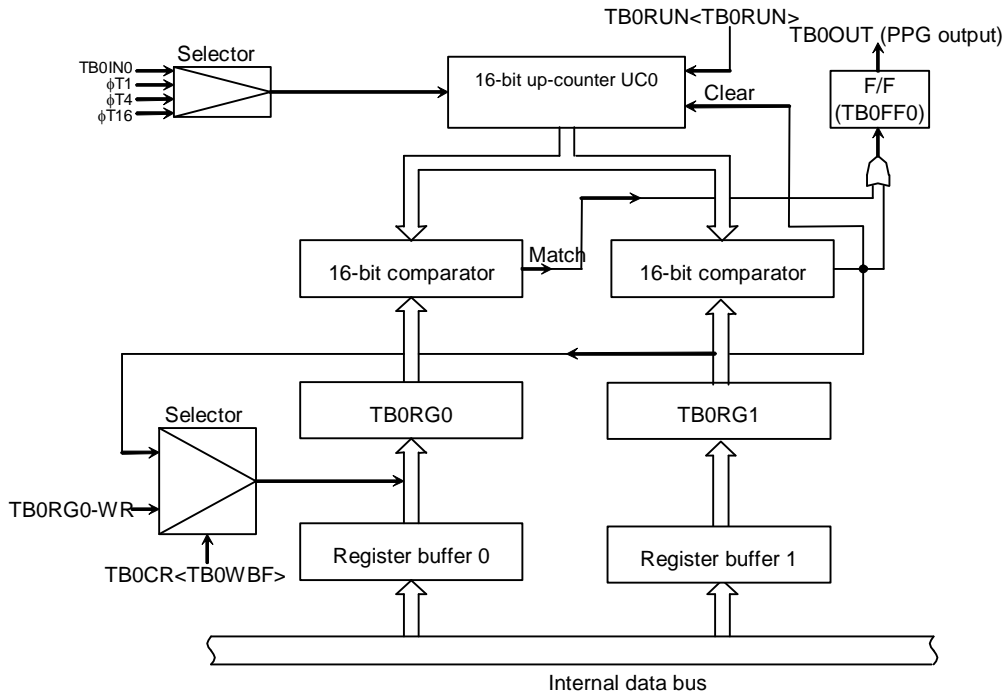


Fig. 8-4 Block Diagram of 16-bit PPG Mode

Each register in the 16-bit PPG output mode must be programmed as listed below.

	7	6	5	4	3	2	1	0	
TB0EN	← 1	X	X	X	X	X	X	X	Starts the TMRB0 module.
TB0RUN	← X	X	X	X	X	0	X	0	Stops the TMRB0
TBORG0	← *	*	*	*	*	*	*	*	Specifies a duty. (16 bits *32-bits register length)
TBORG1	← *	*	*	*	*	*	*	*	Specifies a cycle. (16 bits *32-bits register length)
TB0CR	← 1	0	X	0	0	0	0	0	Enables the TBORG0 double buffering. (Changes the duty/cycle when the INTTB0 interrupt is generated)
TB0FFCR	← X	X	0	0	1	1	1	0	Specifies to trigger TB0FF0 to reverse when a match with TBORG0 or TBORG1 is detected, and sets the initial value of TB0FF0 to "0."
TB0MOD	← 0	0	1	0	0	1	*	*	Designates the prescaler output clock as the input clock, and disables the capture function.
PACR	← -	-	-	-	-	-	1	-	} Assigns PA0 to output and TB0OUT
PAFR1	← -	-	-	-	-	-	1	-	
TB0RUN	← *	*	*	*	*	1	X	1	

X; Don't care -; no change

### 8.7 Application example using the Capture Function

The capture function can be used to develop many applications, including those described below:

- ① One-shot pulse output triggered by an external pulse
- ② Pulse width measurement

① One-shot pulse output triggered by an external pulse

One-shot pulse output triggered by an external pulse is carried out as follows:

The 16-bit up-counter is made to count up by putting it in a free-running state using the prescaler output clock. An external pulse is input through the TB0IN pin. A trigger is generated at the rising of the external pulse by using the capture function and the value of the up-counter is taken into the capture registers (TB0CP0).

The CPU must be programmed so that an interrupt INTCAP00 is generated at the rising of an external trigger pulse. This interrupt is used to set the timer registers (TB0RG0) to the sum of the TB0CP0 value (c) and the delay time (d), (c + d), and set the timer registers (TB0RG1) to the sum of the TB0RG0 values and the pulse width (p) of one-shot pulse, (c + d + p).

TB0RG1 change must be completed before the next match.

In addition, the timer flip-flop control registers (TB0FFCR<TB0E1T1, TB0E0T1>) must be set to “11.” This enables triggering the timer flip-flop (TB0FF0) to reverse when UC0 matches TB0RG0 and TB0RG1. This trigger is disabled by the INTTB01 interrupt after a one-shot pulse is output.

Symbols (c), (d) and (p) used in the text correspond to symbols c, d and p in Fig. 8-5 One-shot Pulse Output (With Delay).”

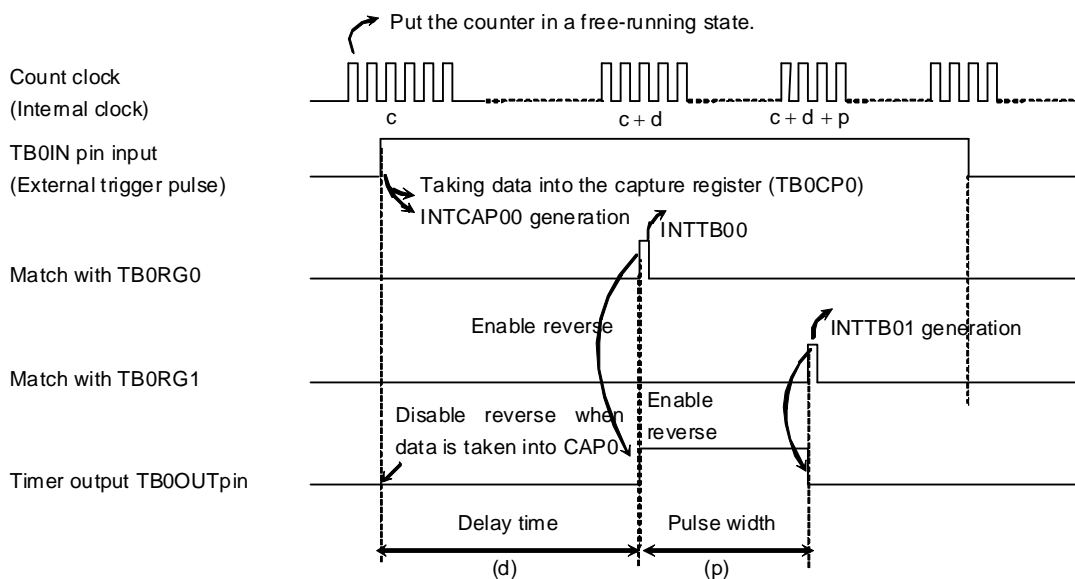


Fig. 8-5 One-shot Pulse Output (With Delay)

If a delay is not required, TB0FF0 is reversed when data is taken into TB0CP0, and TB0RG1 is set to the sum of the TB0CPO value ( $c$ ) and the one-shot pulse width ( $p$ ), ( $c + p$ ), by generating the INTTB00 interrupt. TB0RG1 change must be completed before the next match. TB0FF0 is enabled to reverse when UC0 matches with TB0RG1, and is disabled by generating the INTTB01 interrupt.

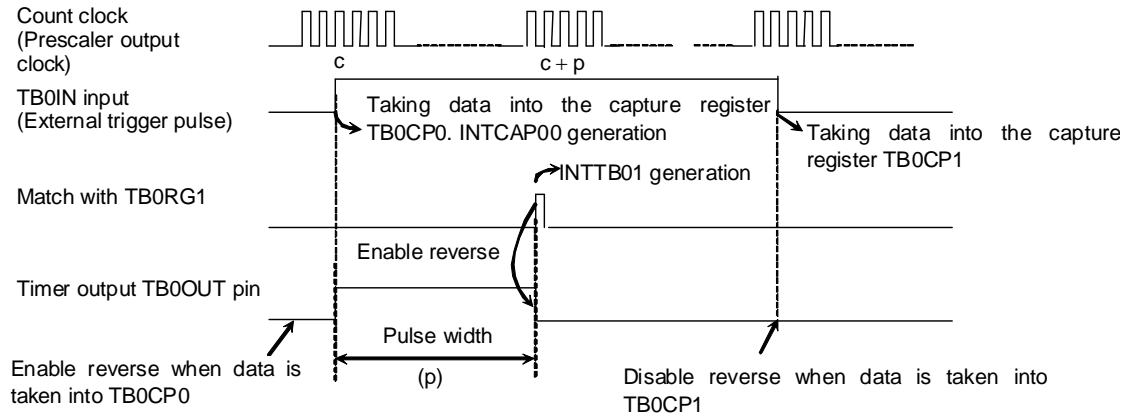


Fig. 8-6 One-shot Pulse Output Triggered by an External Pulse (Without Delay)

② Pulse width measurement

By using the capture function, the “H” level width of an external pulse can be measured. Specifically, by putting it in a free-running state using the prescaler output clock, an external pulse is input through the TB0IN pin and the up-counter (UC0) is made to count up. A trigger is generated at each rising and falling edge of the external pulse by using the capture function and the value of the up-counter is taken into the capture registers (TB0CP0, TB0CP1). The CPU must be programmed so that INTCAP01 is generated at the falling edge of an external pulse input through the TB0IN pin.

The “H” level pulse width can be calculated by multiplying the difference between TB0CP0 and TB0CP1 by the clock cycle of an internal clock.

For example, if the difference between TB0CP0 and TB0CP1 is 100 and the cycle of the prescaler output clock is 0.5 *us*, the pulse width is  $100 \times 0.5 \text{ us} = 50 \text{ us}$ .

Caution must be exercised when measuring pulse widths exceeding the UC0 maximum count time which is dependant upon the source clock used. The measurement of such pulse widths must be made using software.

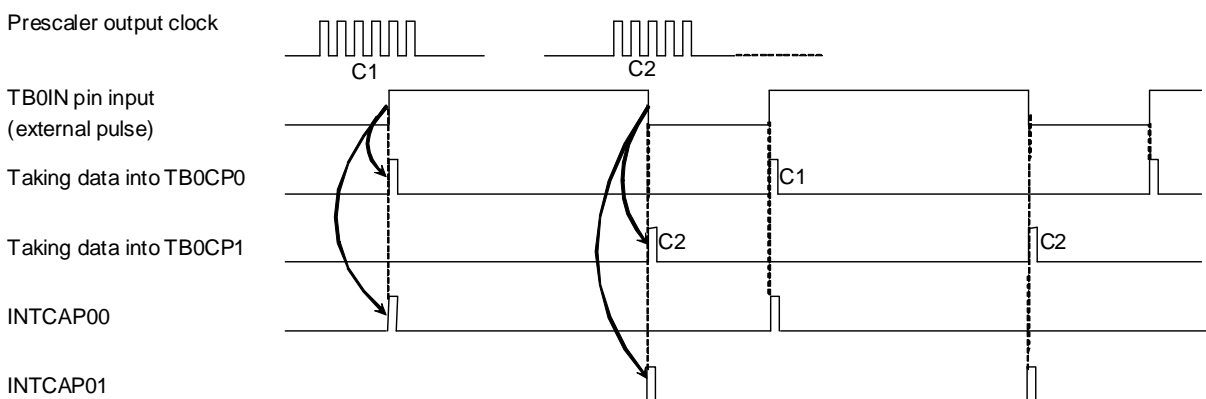


Fig. 8-7 Pulse Width Measurement

The “L” level width of an external pulse can also be measured. In such cases, the difference between C2 generated the first time and C1 generated the second time is initially obtained by performing the second stage of INTCAP00 interrupt processing as shown in “Fig. 8-7 Pulse Width Measurement” and this difference is multiplied by the cycle of the prescaler output clock to obtain the “L” level width.

## 9. Serial Channel (SIO)

### 9.1 Features

This device has four serial I/O channels: SIO0 to SIO3. Each channel operates in either the UART mode (asynchronous communication) or the I/O interface mode (synchronous communication) which is selected by the user.

I/O interface mode	——	Mode 0: This is the mode to transmit and receive I/O data and associated synchronization signals (SCLK) to extend I/O.
Asynchronous (UART) mode:	—	Mode 1: TX/RX Data Length: 7 bits
		Mode 2: TX/RX Data Length: 8 bits
		Mode 3: TX/RX Data Length: 9 bits

In the above modes 1 and 2, parity bits can be added. The mode 3 has a wakeup function in which the master controller can start up slave controllers via the serial link (multi-controller system). Fig. 9-2 shows the block diagram of SIO0.

Each channel consists of a prescaler, a serial clock generation circuit, a receive buffer, its control circuit, a transmit buffer and its control circuit. Each channel functions independently.

As the SIOs 0 to 3 operate in the same way, only SIO0 is described here.

Table 9-1 Difference in the Specifications of SIO Modules

	Channel 0	Channel 1	Channel 2	Channel 3	
Pin name	TXD0 (PE0) RXD0 (PE1) $\overline{\text{CTS0}}/\text{SCLK0}$ (PE2)	TXD1 (PA5) RXD1 (PA6) $\overline{\text{CTS1}}/\text{SCLK1}$ (PA4)	TXD2 (PD5) RXD2 (PD6) $\overline{\text{CTS2}}/\text{SCLK2}$ (PD4)	TXD3 (PF3) RXD3 (PF4) $\overline{\text{CTS3}}/\text{SCLK3}$ (PF2)	
Interrupt	INTRX0 INTTX0	INTRX1 INTTX1	INTRX2 INTTX2	INTRX3 INTTX3	
In the UART mode, TMRB output to use for the serial transfer clock	TB4OUT (TMRB4)	TB4OUT (TMRB4)	TB7OUT (TMRB7)	TB7OUT (TMRB7)	
Register name (address)	Enable register	SC0EN 0x4002_0080	SC1EN 0x4002_00C0	SC2EN 0x4002_0100	SC3EN 0x4002_0140
	Transmit/ receive buffer register	SC0BUF 0x4002_0084	SC1BUF 0x4002_00C4	SC2BUF 0x4002_0104	SC3BUF 0x4002_0144
	Control register	SC0CR 0x4002_0088	SC1CR 0x4002_00C8	SC2CR 0x4002_0108	SC3CR 0x4002_0148
	Mode control register 0	SC0MOD0 0x4002_008C	SC1MOD0 0x4002_00CC	SC2MOD0 0x4002_010C	SC3MOD0 0x4002_014C
	Baud rate generator control	SC0BRCR 0x4002_0090	SC1BRCR 0x4002_00D0	SC2BRCR 0x4002_0110	SC3BRCR 0x4002_0150
	Baud rate generator control 2	SC0BRADD 0x4002_0094	SC1BRADD 0x4002_00D4	SC2BRADD 0x4002_0114	SC3BRADD 0x4002_0154
	Mode control register 1	SC0MOD1 0x4002_0098	SC1MOD1 0x4002_00D8	SC2MOD1 0x4002_0118	SC3MOD1 0x4002_0158
	Mode control register 2	SC0MOD2 0x4002_009C	SC1MOD2 0x4002_00DC	SC2MOD2 0x4002_011C	SC3MOD2 0x4002_015C
	Receive FIFO configuration register	SC0RFC 0x4002_00A0	SC1RFC 0x4002_00E0	SC2RFC 0x4002_0120	SC3RFC 0x4002_0160
	Transmit FIFO configuration register	SC0TFC 0x4002_00A4	SC1TFC 0x4002_00E4	SC2TFC 0x4002_0124	SC3TFC 0x4002_0164
	Receive FIFO status register	SC0RST 0x4002_00A8	SC1RST 0x4002_00E8	SC2RST 0x4002_0128	SC3RST 0x4002_0168
	Transmit FIFO status register	SC0TST 0x4002_00AC	SC1TST 0x4002_00EC	SC2TST 0x4002_012C	SC3TST 0x4002_016C
	FIFO configuration register	SC0FCNF 0x4002_00B0	SC1FCNF 0x4002_00F0	SC2FCNF 0x4002_0130	SC3FCNF 0x4002_0170



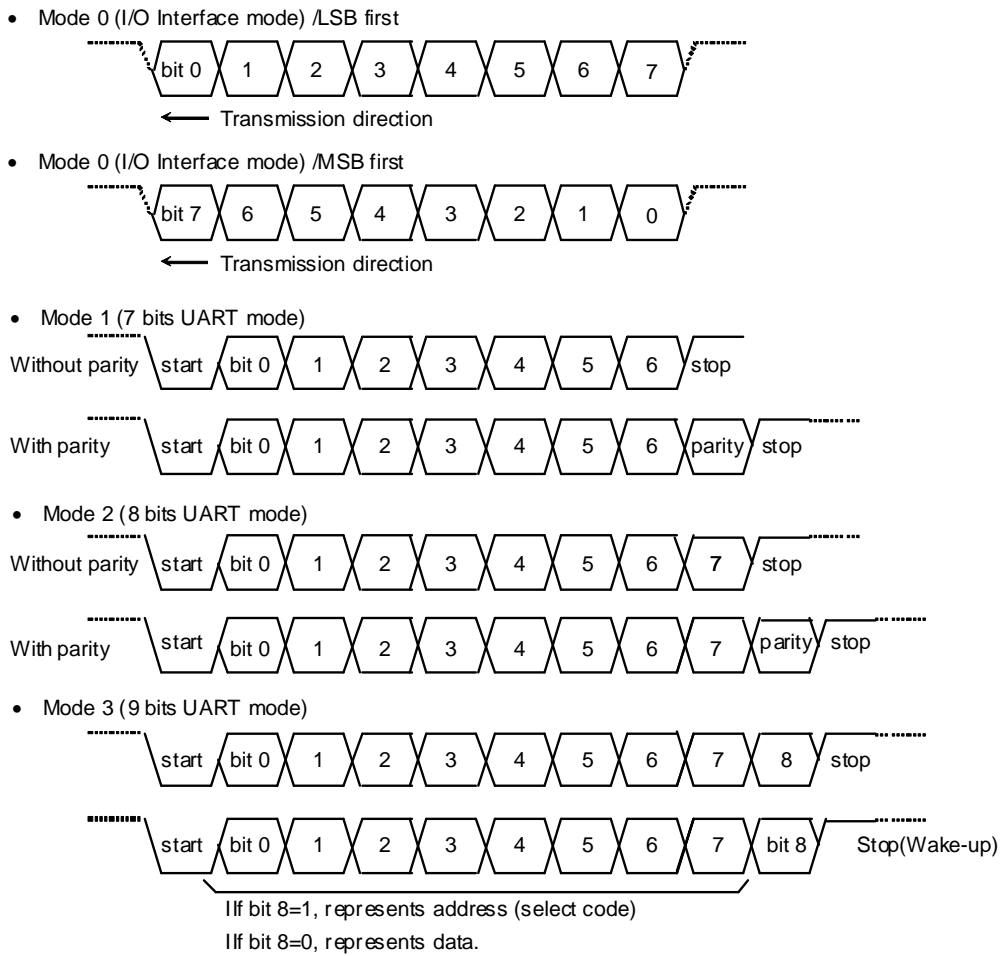


Fig. 9-1 Data Format

9.2 Block Diagram (Channel 0)

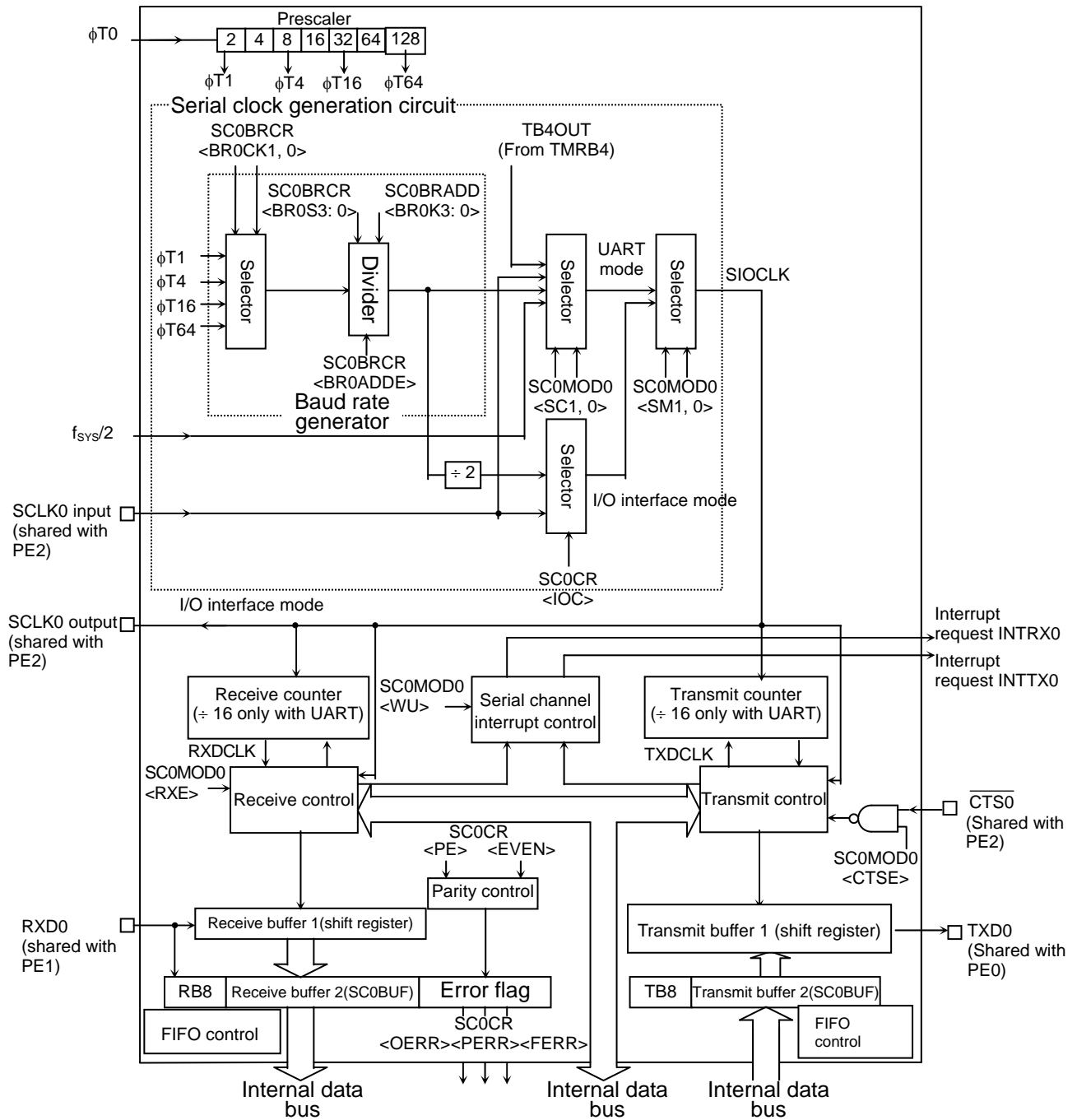


Fig. 9-2 SIO0 Block Diagram

## 9.3 Operation of Each Circuit (Channel 0)

### 9.3.1 Prescaler

The device includes a 7-bit prescaler to generate necessary clocks to drive SIO0. The input clock  $\phi T0$  to the prescaler is selected by SYSCR1 of CG <PRCK2:0> to provide the frequency of either  $f_{\text{periph}}/1$ ,  $f_{\text{periph}}/2$ ,  $f_{\text{periph}}/4$ ,  $f_{\text{periph}}/8$ ,  $f_{\text{periph}}/16$  or  $f_{\text{periph}}/32$ .

The clock frequency  $f_{\text{periph}}$  is either the clock “fgear,” to be selected by SYSCR1<FPSEL> of CG, or the clock “fc” before it is divided by the clock gear.

The prescaler becomes active only when the baud rate generator is selected for generating the serial transfer clock. Table 9-2 list the prescaler output clock resolution.

**Table 9-2 Clock Resolution to the Baud Rate Generator @ = 80MHz**

Clear peripheral clock <FPSEL>	Clock gear value <GEAR2:0>	Prescaler clock selection <PRCK2:0>	Prescaler output clock resolution			
			$\phi T1$	$\phi T4$	$\phi T16$	$\phi T64$
0 (fgear)	000 (fc)	000 (fper iph/1)	$f_c/2^1$ (0.025 $\mu$ s)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)
		001 (fper iph/2)	$f_c/2^2$ (0.05 $\mu$ s)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		010 (fper iph/4)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		011 (fper iph/8)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		100 (fper iph/16)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		101 (fper iph/32)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
	100(fc/2)	000 (fper iph/1)	$f_c/2^2$ (0.05 $\mu$ s)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		001 (fper iph/2)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		010 (fper iph/4)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		011 (fper iph/8)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		100 (fper iph/16)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
		101 (fper iph/32)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)	$f_c/2^{13}$ (102.4 $\mu$ s)
	101(fc/4)	000 (fper iph/1)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		001 (fper iph/2)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		010 (fper iph/4)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		011 (fper iph/8)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
		100 (fper iph/16)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)	$f_c/2^{13}$ (102.4 $\mu$ s)
		101 (fper iph/32)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)	$f_c/2^{14}$ (204.8 $\mu$ s)
	110(fc/8)	000 (fper iph/1)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		001 (fper iph/2)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		010 (fper iph/4)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
		011 (fper iph/8)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)	$f_c/2^{13}$ (102.4 $\mu$ s)
		100 (fper iph/16)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)	$f_c/2^{14}$ (204.8 $\mu$ s)
		101 (fper iph/32)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)	$f_c/2^{13}$ (102.4 $\mu$ s)	$f_c/2^{15}$ (409.6 $\mu$ s)
1 (fc)	000 (fc)	000 (fper iph/1)	$f_c/2^1$ (0.025 $\mu$ s)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)
		001 (fper iph/2)	$f_c/2^2$ (0.05 $\mu$ s)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		010 (fper iph/4)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		011 (fper iph/8)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		100 (fper iph/16)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		101 (fper iph/32)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
	100(fc/2)	000 (fper iph/1)	—	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)
		001 (fper iph/2)	$f_c/2^2$ (0.05 $\mu$ s)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		010 (fper iph/4)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		011 (fper iph/8)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		100 (fper iph/16)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		101 (fper iph/32)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
	101(fc/4)	000 (fper iph/1)	—	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)
		001 (fper iph/2)	—	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		010 (fper iph/4)	$f_c/2^3$ (0.1 $\mu$ s)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		011 (fper iph/8)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		100 (fper iph/16)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		101 (fper iph/32)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)
	110(fc/8)	000 (fper iph/1)	—	—	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)
		001 (fper iph/2)	—	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)
		010 (fper iph/4)	—	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)
		011 (fper iph/8)	$f_c/2^4$ (0.2 $\mu$ s)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)
		100 (fper iph/16)	$f_c/2^5$ (0.4 $\mu$ s)	$f_c/2^7$ (1.6 $\mu$ s)	$f_c/2^9$ (6.4 $\mu$ s)	$f_c/2^{11}$ (25.6 $\mu$ s)
		101 (fper iph/32)	$f_c/2^6$ (0.8 $\mu$ s)	$f_c/2^8$ (3.2 $\mu$ s)	$f_c/2^{10}$ (12.8 $\mu$ s)	$f_c/2^{12}$ (51.2 $\mu$ s)

**(Note 1) The prescaler output clock  $\phi T_n$  must be selected so that the relationship " $\phi T_n < f_{sys}$ " is satisfied (so that  $\phi T_n$  is slower than  $f_{sys}$ ).**

**(Note 2) Do not change the clock gear while SIO is operating.**

**(Note 3) The horizontal lines in the above table indicate that the setting is prohibited.**

The serial interface baud rate generator uses four different clocks, i.e.,  $\phi T_1$ ,  $\phi T_4$ ,  $\phi T_{16}$  and  $\phi T_{64}$ , supplied from the prescaler output clock.

### 9.3.2 Baud Rate Generator

The baud rate generator generates transmit and receive clocks to determine the serial channel transfer rate.

The baud rate generator uses either the  $\phi T1$ ,  $\phi T4$ ,  $\phi T16$  or  $\phi T64$  clock supplied from the 7-bit prescaler. This input clock selection is made by setting the baud rate generator control register, SC0BRCCR <BR0CK1:0>.

The baud rate generator contains built-in dividers for divide by 1,  $N + m/16$  ( $N=2\sim 15$ ,  $m=0\sim 15$ ), and 16. The division is performed according to the settings of the baud rate generator control registers SC0BRCCR <BR0ADDE> <BR0S3:0> and SC0BRADD <BR0K3:0> to determine the resulting transfer rate.

The highest baud rate of each mode is limited.

- UART mode

- 1) If SC0BRCCR <BR0ADDE> = 0,

The setting of SC0BRADD <BR0K3:0> is ignored and the counter is divided by N where N is the value set to SC0BRCCR <BR0S3:0>. (N = 1 to 16).

- 2) If SC0BRCCR <BR0ADDE> = 1,

The  $N + (16 - K)/16$  division function is enabled and the division is made by using the values N (set in SC0BRCCR <BR0S3:0>) and K (set in SC0BRADD <BR0K3:0>). (N = 2 to 15, K = 1 to 15)

**(Note) For the N values of 1 and 16, the above  $N+(16-K)/16$  division function is inhibited. So, be sure to set SC0BRCCR<BR0ADDE> to "0."**

- I/O interface mode

The  $N + (16 - K)/16$  division function cannot be used in the I/O interface mode. Be sure to divide by N, by setting SC0BRCCR <BR0ADDE> to "0".

- Baud rate calculation to use the baud rate generator:

- 1) UART mode

$$\text{Baud rate} = \frac{\text{Baud rated generator input clock}}{\text{Frequency divided by the divide ratio}} / 16$$

The highest baud rate out of the baud rate generator is 1.25 Mbps.

The  $f_{\text{sys}}$  frequency, which is independent of the baud rate generator, can be used as the serial clock. In this case, the highest baud rate will be 2.5 Mbps.

- 2) I/O interface mode

$$\text{Baud rate} = \frac{\text{Baud rated generator input clock}}{\text{Frequency divided by the divide ratio}} / 2$$

When it uses a double buffer, the highest baud rate generated with the baud rate generator becomes 10Mbps. (If double buffering is not used, the highest baud rate will be 5.0 Mbps).

- Example baud rate setting:

- 1) Division by an integer (divide by N):

Selecting  $f_c = 78.642$  MHz for  $f_{\text{periph}}$ , setting  $\phi T0$  to  $f_{\text{periph}}/16$ , using the baud rate generator input clock  $\phi T1$ , setting the divide ratio N (SC0BRCCR<BR0S3:0>) = 4, and setting SC0BRCCR<BR0ADDE> = "0," the resulting baud rate in the UART mode is calculated as follows:

\* Clocking conditions

System clock	:	High-speed ( $f_c$ )
High speed clock gear	:	$\times 1$ ( $f_c$ )
Prescaler clock	:	$f_{\text{periph}}/16$ ( $f_{\text{periph}} = f_{\text{sys}}$ )

$$\text{Baud rate} = \frac{f_c/32}{4} /16$$

$$= 78.642 \times 10^6 \div 32 \div 4 \div 16 \doteq 38400 \text{ (bps)}$$

**(Note) The divide by (N + (16-K)/16) function is inhibited and thus SC0BRADD <BR0K3:0> is ignored.**

- 2) For divide by N + (16-K)/16 (only for UART mode):

Selecting  $f_c = 9.6$  MHz for  $f_{\text{periph}}$ , setting  $\phi T0$  to  $f_{\text{periph}}/8$ , using the baud rate generator input clock  $\phi T1$ , setting the divide ratio N (SC0BRCCR<BR0S3:0>) = 7, setting K (SC0BRADD<BR0K3:0>) = 3, and selecting SC0BRCCR<BR0ADDE> = 1, the resulting baud rate is calculated as follows:

\* Clocking conditions

{	System clock	:	High-speed ( $f_c$ )
	High-speed clock gear	:	$\times 1$ ( $f_c$ )
	Prescaler clock	:	$f_{\text{periph}}/4$ ( $f_{\text{periph}} = f_{\text{sys}}$ )

$$\text{Baud rate} = \frac{f_c/16}{7 + \frac{(16-3)}{16}} /16$$

$$= 9.6 \times 10^6 \div 16 \div \left(7 + \frac{13}{16}\right) \div 16 = 4800 \text{ (bps)}$$

Also, an external clock input may be used as the serial clock. The resulting baud rate calculation is shown below:

- Baud rate calculation for an external clock input:

- 1) UART mode

Baud Rate = external clock input / 16

In this, the period of the external clock input must be equal to or greater than  $2/f_{sys}$ .

Moreover, please set to become it to the highest baud rate 1.25 (Mbps) as follows.

- 2) I/O interface mode

Baud Rate = external clock input

When double buffering is used, it is necessary to satisfy the following relationship:

External clock input period >  $6/f_{sys}$

Moreover, it is necessary to adjust the highest baud rate to less than 6.66 (Mbps).

When double buffering is not used, it is necessary to satisfy the following relationship:

External clock input period >  $8/f_{sys}$

Moreover, it is necessary to adjust the highest baud rate to less than 5.0 (Mbps).

The baud rate examples for the UART mode are shown in Table 9-3 and Table 9-4.



**Table 9-3 Selection of UART Baud Rate**

(Using the baud rate generator with SC0BRCR <BR0ADDE> = 0)

Unit: (kbps)

fc [MHz]	Input clock				
	Divide ratio N (Set to SC0BRCR <BR0S3 : 0>)	$\phi T1$ (fc/4)	$\phi T4$ (fc/16)	$\phi T16$ (fc/64)	$\phi T64$ (fc/256)
9.830400	2	76.800	19.200	4.800	1.200
↑	4	38.400	9.600	2.400	0.600
↑	8	19.200	4.800	1.200	0.300
↑	0	9.600	2.400	0.600	0.150

**(Note)** This table shows the case where the system clock is set to fc, the clock gear is set to fc/1, and the prescaler clock is set to  $f_{periph}/2$ .

**Table 9-4 Selection of UART Baud Rate**

(The TMRB4 timer output (internal TB4OUT) is used with the timer input clock set to  $\phi T1$ .)

Unit: (Kbbs)

TB4RG	fc	80 MHz	9.8304 MHz	8 MHz
	1H		625.0	76.8
2H		312.5	38.4	31.25
3H			25.6	
4H		156.25	19.2	15.625
5H		125.0	15.36	12.5
6H			12.8	
8H		78.125	9.6	
AH		62.5	7.68	6.25
10H		39.0625	4.8	
14H		31.25	3.84	3.125

Baud rate calculation to use the TMRB4 timer:

$$\text{Transfer rate} = \frac{\text{Clock frequency selected by SYSCR0<PRCK2:0>}}{\text{TB4RG} \times 2 \times 2 \times 16}$$

↑ (When input clock to the timer TMRB4 is  $\phi T1$ )

**(Note 1)** In the I/O interface mode, the TMRB4 timer output signal cannot be used internally as the transfer clock.

**(Note 2)** This table shows the case where the system clock is set to fc, the clock gear is set to fc, and the prescaler clock is set to  $f_{periph}/2$ .

### 9.3.3 Serial Clock Generation Circuit

This circuit generates basic transmit and receive clocks.

- I/O interface mode

In the SCLK output mode with the SC0CR <IOC> serial control register set to “0,” the output of the previously mentioned baud rate generator is divided by 2 to generate the basic clock.

In the SCLK input mode with SC0CR <IOC> set to “1,” rising and falling edges are detected according to the SC0CR <SCLKS> setting to generate the basic clock.

- Asynchronous (UART) mode :

According to the settings of the serial control mode register SC0MOD0 <SC1:0>, either the clock from the baud rate register, the system clock ( $f_{SYS}$ ), the internal output signal of the TMRB4 timer, or the external clock (SCLKO pin) is selected to generate the basic clock, SIOCLK.

### 9.3.4 Receive Counter

The receive counter is a 4-bit binary counter used in the asynchronous (UART) mode and is up-counted by SIOCLK. Sixteen SIOCLK clock pulses are used in receiving a single data bit while the data symbol is sampled at the seventh, eighth, and ninth pulses. From these three samples, majority logic is applied to decide the received data.

### 9.3.5 Receive Control Unit

- I/O interface mode:

In the SCLK output mode with SC0CR <IOC> set to “0,” the RXD0 pin is sampled on the rising edge of the shift clock output to the SCLK0 pin.

In the SCLK input mode with SC0CR <IOC> set to “1,” the serial receive data RXD0 pin is sampled on the rising or falling edge of SCLK input depending on the SC0CR <SCLKS> setting.

- Asynchronous (UART) mode:

The receive control unit has a start bit detection circuit, which is used to initiate receive operation when a normal start bit is detected.

### 9.3.6 Receive Buffer

The receive buffer is of a dual structure to prevent overrun errors. The first receive buffer (a shift register) stores the received data bit-by-bit. When a complete set of bits have been stored, they are moved to the second receive buffer (SC0BUF). At the same time, the receive buffer full flag (SC0MOD2 “RBFL”) is set to “1” to indicate that valid data is stored in the second receive buffer. However, if the receive FIFO is set enabled, the receive data is moved to the receive FIFO and this flag is immediately cleared.

If the receive FIFO has been disabled (SC0FCNF <CNFG> = 0 and SC0MOD1<FDPX1:0> = 01), the INTRX0 interrupt is generated at the same time. If the receive FIFO has been enabled (SCNFCNF <CNFG> = 1 and SC0MOD1<FDPX1:0> = 01), an interrupt will be generated according to the SC0RFC <RIL1:0> setting.

The CPU will read the data from either the second receive buffer (SC0BUF) or from the receive FIFO (the address is the same as that of the receive buffer). If the receive FIFO has not been enabled, the receive buffer full flag <RBFL> is cleared to "0" by the read operation. The next data received can be stored in the first receive buffer even if the CPU has not read the previous data from the second receive buffer (SC0BUF) or the receive FIFO.

If SCLK is set to generate clock output in the I/O interface mode, the double buffer control bit SC0MOD2 <WBUF> can be programmed to enable or disable the operation of the second receive buffer (SC0BUF).

By disabling the second receive buffer (i.e., the double buffer function) and also disabling the receive FIFO (SC0FCNF <CNFG> = 0 and <FDPX1:0> = 01), handshaking with the other side of communication can be enabled and the SCLK output stops each time one frame of data is transferred. In this setting, the CPU reads data from the first receive buffer. By the read operation of CPU, the SCLK output resumes.

If the second receive buffer (i.e., double buffering) is enabled but the receive FIFO is not enabled, the SCLK output is stopped when the first receive data is moved from the first receive buffer to the second receive buffer and the next data is stored in the first buffer filling both buffers with valid data. When the second receive buffer is read, the data of the first receive buffer is moved to the second receive buffer and the SCLK output is resumed upon generation of the receive interrupt INTRX0. Therefore, no buffer overrun error will be caused in the I/O interface SCLK output mode regardless of the setting of the double buffer control bit SC0MOD2 <WBUF>.

If the second receive buffer (double buffering) is enabled and the receive FIFO is also enabled (SC0FCNF <CNFG> = 1 and <FDPX1:0> = 01/11), the SCLK output will be stopped when the receive FIFO is full (according to the setting of SC0FCNF <RFST>) and both the first and second receive buffers contain valid data. Also in this case, if SC0FCNF <RXTXCNT> has been set to "1," the receive control bit RXE will be automatically cleared upon suspension of the SCLK output. If it is set to "0," automatic clearing will not be performed.

**(Note) In this mode, the SC0CR <OEER> flag is insignificant and the operation is undefined. Therefore, before switching from the SCLK output mode to another mode, the SC0CR register must be read to initialize this flag.**

In other operating modes, the operation of the second receive buffer is always valid, thus improving the performance of continuous data transfer. If the receive FIFO is not enabled, an overrun error occurs when the data in the second receive buffer (SC0BUF) has not been read before the first receive buffer is full with the next receive data. If an overrun error occurs, data in the first receive buffer will be lost while data in the second receive buffer and the contents of SC0CR <RB8> remain intact. If the receive FIFO is enabled, the FIFO must be read before the FIFO is full and the second receive buffer is written by the next data through the first buffer. Otherwise, an overrun error will be generated and the receive FIFO overrun error flag will be set. Even in this case, the data already in the receive FIFO remains intact.

The parity bit to be added in the 8-bit UART mode as well as the most significant bit in the 9-bit UART mode will be stored in SC0CR <RB8>.

In the 9-bit UART mode, the slave controller can be operated in the wake-up mode by

setting the wake-up function SC0MOD0 <WU> to “1.” In this case, the interrupt INTRX0 will be generated only when SC0CR <RB8> is set to “1.”

### 9.3.7 Receive FIFO Buffer

In addition to the double buffer function already described, data may be stored using the receive FIFO buffer. By setting <CNFG> of the SC0FCNF register and <FDPX1:0> of the SC0MOD1 register, the 4-byte receive buffer can be enabled. Also, in the UART mode or I/O interface mode, data may be stored up to a predefined fill level. When the receive FIFO buffer is to be used, be sure to enable the double buffer function.

If data with parity bit is to be received in the UART mode, parity check must be performed each time a data frame is received.

### 9.3.8 Receive FIFO Operation

- ① I/O interface mode with SCLK output:

The following example describes the case a 4-byte data stream is received in the half duplex mode:

SC0RFC<7:6>=01: Clears receive FIFO and sets the condition of interrupt generation.

SC0RFC<1:0>=00: Sets the interrupt to be generated at fill level 4.

SC0FCNF <4:0>=10111: Automatically inhibits continued reception after reaching the fill level. The number of bytes to be used in the receive FIFO is the same as the interrupt generation fill level.

In this condition, 4-byte data reception may be initiated by setting the half duplex transmission mode and writing “1” to the RXE bit. After receiving 4 bytes, the RXE bit is automatically cleared and the receive operation is stopped (SCLK is stopped).

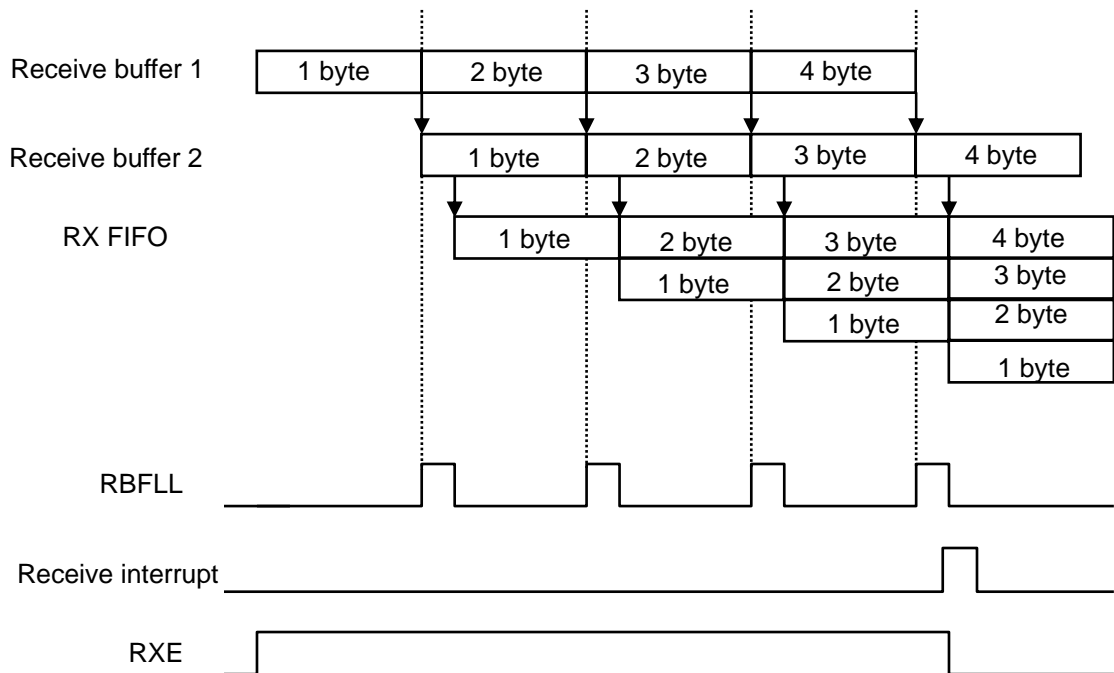


Fig. 9-3 Receive FIFO Operation

② I/O interface mode with SCLK input:

The following example describes the case a 4-byte data stream is received:

SC0RFC <7:6> = 10: Clears receive FIFO and sets the condition of interrupt generation

SC0RFC <1:0> = 00: Sets the interrupt to be generated at fill level 4.

SC0FCNF <1:0> = 10101: Automatically allows continued reception after reaching the fill level. The number of bytes to be used in the receive FIFO is the maximum allowable number.

In this condition, 4-byte data reception may be initiated by setting the half duplex transmission mode and writing "1" to the RXE bit. After receiving 4 bytes, receive FIFO interrupt is generated. This setting enables the next data reception as well. The next 4 bytes can be received before all the data is read from FIFO.

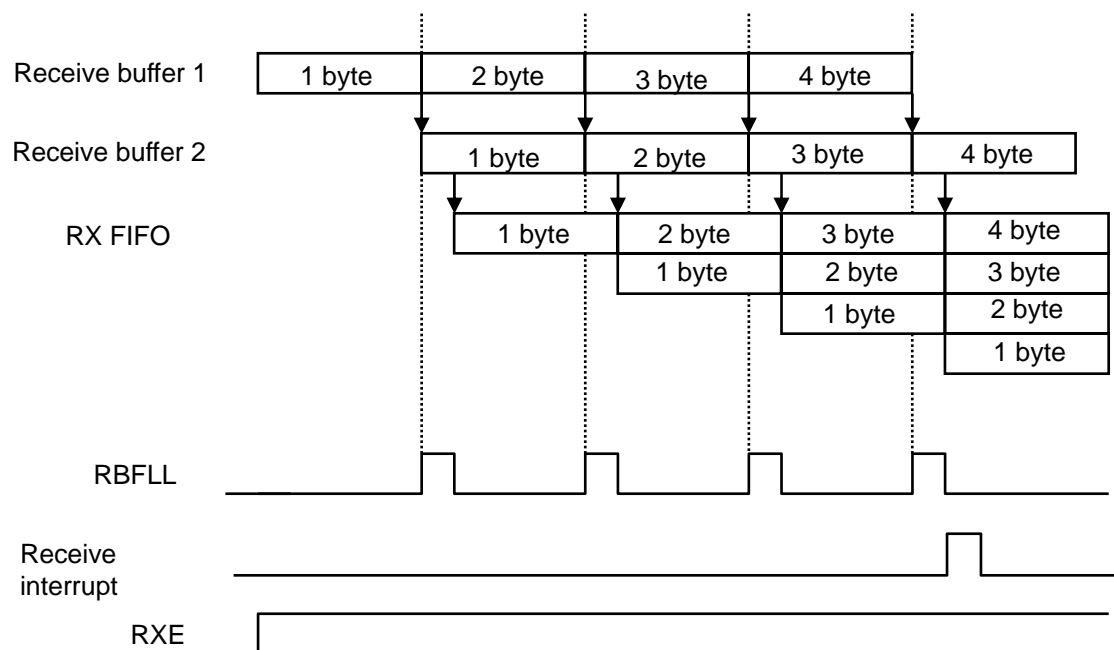


Fig. 9-4 Receive FIFO Operation

### 9.3.9 Transmit Counter

The transmit counter is a 4-bit binary counter used in the asynchronous communication (UART) mode. It is counted by SIOCLK as in the case of the receive counter and generates a transmit clock (TXDCLK) on every 16th clock pulse.

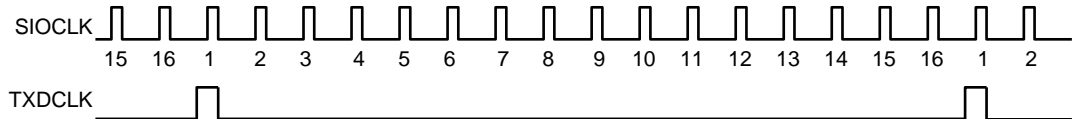


Fig. 9-5 Transmit Clock Generation

### 9.3.10 Transmit Control Unit

- I/O interface mode:

In the SCLK output mode with SC0CR <IOC> set to "0," each bit of data in the transmit buffer is output to the TXD0 pin on the rising edge of the shift clock output from the SCLK0 pin.

In the SCLK input mode with SC0CR <IOC> set to "1," each bit of data in the transmit buffer is output to the TXD0 pin on the rising or falling edge of the input SCLK signal according to the SC0CR <SCLKS> setting.

- Asynchronous (UART) mode:

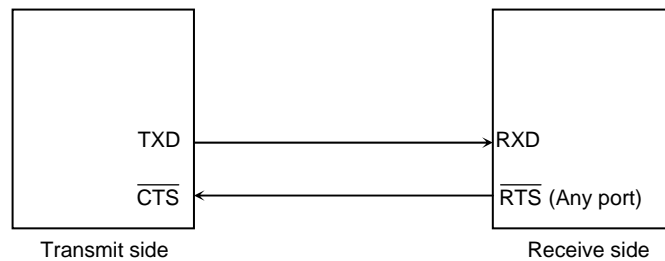
When the CPU writes data to the transmit buffer, data transmission is initiated on the rising edge of the next TXDCLK and the transmit shift clock (TXDSFT) is also generated.

- Handshake function

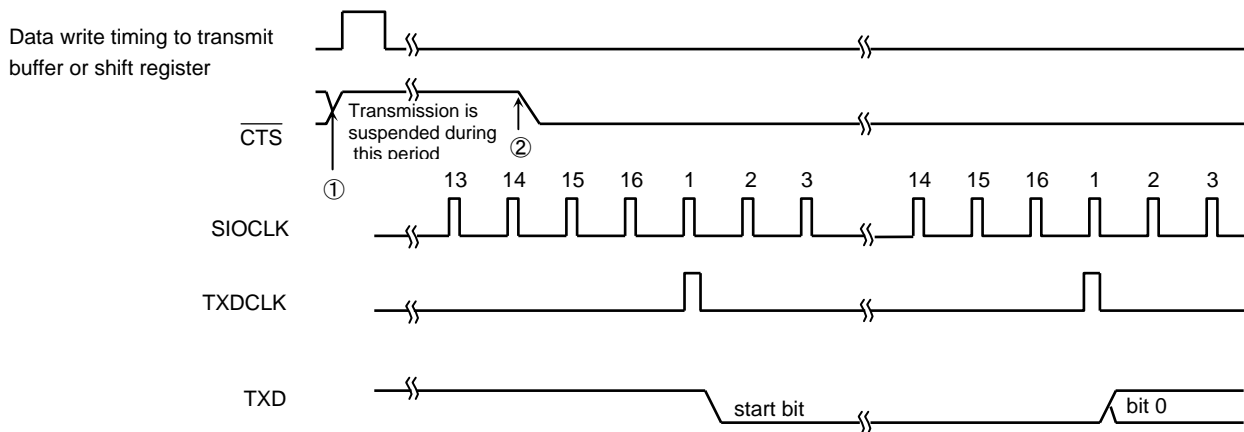
The  $\overline{\text{CTS}}$  pin enables frame by frame data transmission so that overrun errors can be prevented. This function can be enabled or disabled by SC0MOD0 <CTSE>.

When the  $\overline{\text{CTS0}}$  pin is set to the “H” level, the current data transmission can be completed but the next data transmission is suspended until the  $\overline{\text{CTS0}}$  pin returns to the “L” level. However in this case, the INTTX0 interrupt is generated, the next transmit data is requested to the CPU, data is written to the transmit buffer, and it waits until it is ready to transmit data.

Although no  $\overline{\text{RTS}}$  pin is provided, a handshake control function can be easily implemented by assigning a port for the  $\overline{\text{RTS}}$  function. By setting the port to “H” level upon completion of data reception (in the receive interrupt routine), the transmit side can be requested to suspend data transmission.



**Fig. 9-6 Handshake Function**



**Fig. 9-7 CTS (Clear to Transmit) Signal Timing**

**(Note 1)** If the  $\overline{\text{CTS}}$  signal is set to “H” during transmission, the next data transmission is suspended after the current transmission is completed.

**(Note 2)** Data transmission starts on the first falling edge of the TXDCLK clock after  $\overline{\text{CTS}}$  is set to “L.”

### 9.3.11 Transmit Buffer

The transmit buffer (SC0BUF) is in a dual structure. The double buffering function may be enabled or disabled by setting the double buffer control bit <WBUF> in serial mode control register 2 (SC0MOD2). If double buffering is enabled, data written to Transmit Buffer 2 (SC0BUF) is moved to Transmit Buffer 1 (shift register).

If the transmit FIFO has been disabled (SC0FCNF <CNFG> = 0 or 1 and SC0MOD1<FDPX1:0> = 01), the INTTX0 interrupt is generated at the same time and the transmit buffer empty flag <TBEMP> of SC0MOD2 is set to "1." This flag indicates that Transmit Buffer 2 is now empty and that the next transmit data can be written. When the next data is written to Transmit Buffer 2, the <TBEMP> flag is cleared to "0."

If the transmit FIFO has been enabled (SCNFCNF <CNFG> = 1 and SC0MOD1<FDPX1:0> = 10/11), any data in the transmit FIFO is moved to the Transmit Buffer 2 and <TBEMP> flag is immediately cleared to "0." The CPU writes data to Transmit Buffer 2 or to the transmit FIFO.

If the transmit FIFO is disabled in the I/O interface SCLK input mode and if no data is set in Transmit Buffer 2 before the next frame clock input, which occurs upon completion of data transmission from Transmit Buffer 1, an under-run error occurs and a serial control register (SC0CR) <PERR> parity/under-run flag is set.

If the transmit FIFO is enabled in the I/O interface SCLK input mode, when data transmission from Transmit Buffer 1 is completed, the Transmit Buffer 2 data is moved to Transmit Buffer 1 and any data in transmit FIFO is moved to Transmit Buffer 2 at the same time.

If the transmit FIFO is disabled in the I/O interface SCLK output mode, when data in Transmit Buffer 2 is moved to Transmit Buffer 1 and the data transmission is completed, the SCLK output stops. So, no under-run errors can be generated.

If the transmit FIFO is enabled in the I/O interface SCLK output mode, the SCLK output stops upon completion of data transmission from Transmit Buffer 1 if there is no valid data in the transmit FIFO.

**Note) In the I/O interface SCLK output mode, the SC0CR <PEER> flag is insignificant. In this case, the operation is undefined. Therefore, to switch from the SCLK output mode to another mode, SC0CR must be read in advance to initialize the flag.**

If double buffering is disabled, the CPU writes data only to Transmit Buffer 1 and the transmit interrupt INTTX0 is generated upon completion of data transmission.

If handshaking with the other side is necessary, set the double buffer control bit <WBUF> to "0" (disable) to disable Transmit Buffer 2; any setting for the transmit FIFO should not be performed.



### 9.3.12 Transmit FIFO Buffer

In addition to the double buffer function already described, data may be stored using the transmit FIFO buffer. By setting <CNFG> of the SC0FCNF register and <FDPX1:0> of the SC0MOD1 register, the 4-byte transmit buffer can be enabled. In the UART mode or I/O interface mode, up to 4 bytes of data may be stored.

If data is to be transmitted with a parity bit in the UART mode, parity check must be performed on the receive side each time a data frame is received.

### 9.3.13 Transmit FIFO Operation

- ① I/O interface mode with SCLK output (normal mode):

The following example describes the case a 4-byte data stream is transmitted:

SC0TFC <7:6> = 01: Clears transmit FIFO and sets the condition of interrupt generation

SC0TFC <1:0> = 00: Sets the interrupt to be generated at fill level 0.

SC0FCNF <4:0> = 01011: Inhibits continued transmission after reaching the fill level.

In this condition, data transmission can be initiated by setting the transfer mode to half duplex, writing 4 bytes of data to the transmit FIFO, and setting the <TXE> bit to "1." When the last transmit data is moved to the transmit buffer, the transmit FIFO interrupt is generated. When transmission of the last data is completed, the clock is stopped and the transmission sequence is terminated.

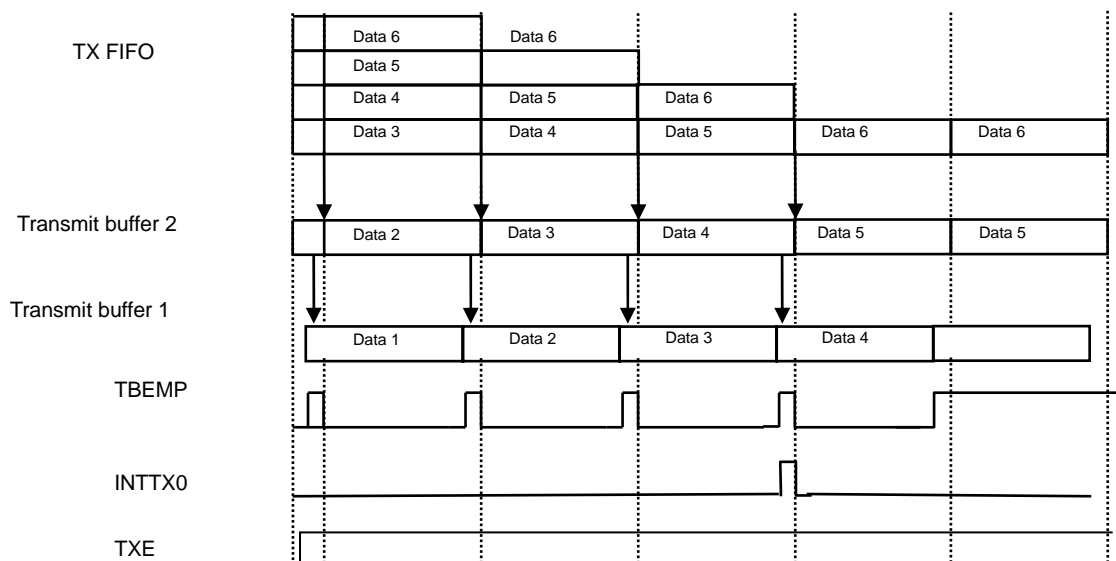


Fig. 9-8 Transmit FIFO Operation

② I/O interface mode with SCLK input (normal mode):

The following example describes the case a 4-byte data stream is transmitted:

SC0TFC <1:0> = 01: Clears the transmit FIFO and sets the condition of interrupt generation.

SC0TFC <7:6> = 000000: Sets the interrupt to be generated at fill level 0.

SC0FCNF <4:0> = 01001: Allows continued transmission after reaching the fill level.

In this condition, data transmission can be initiated along with the input clock by setting the transfer mode to half duplex, writing 4 bytes of data to the transmit FIFO, and setting the <TXE> bit to "1." When the last transmit data is moved to the transmit buffer, the transmit FIFO interrupt is generated.

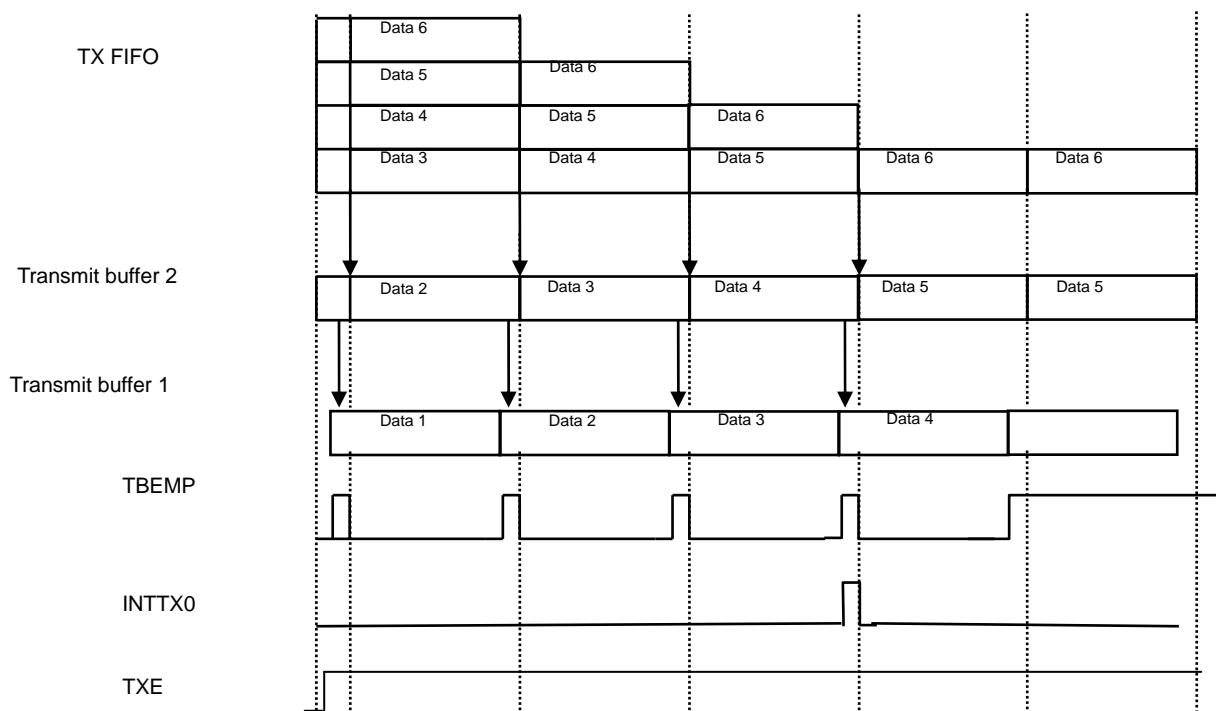


Fig. 9-9 Transmit FIFO Operation

### 9.3.14 Parity Control Circuit

If the parity addition bit <PE> of the serial control register SC0CR is set to “1,” data is sent with the parity bit. Note that the parity bit may be used only in the 7- or 8-bit UART mode. The <EVEN> bit of SC0CR selects either even or odd parity.

Upon data transmission, the parity control circuit automatically generates the parity with the data written to the transmit buffer (SC0BUF). After data transmission is complete, the parity bit will be stored in SC0BUF bit 7 <TB7> in the 7-bit UART mode and in bit 7 <TB8> in the serial mode control register SC0MOD in the 8-bit UART mode. The <PE> and <EVEN> settings must be completed before data is written to the transmit buffer.

Upon data reception, the parity bit for the received data is automatically generated while the data is shifted to receive buffer 1 and moved to receive buffer 2 (SC0BUF). In the 7-bit UART mode, the parity generated is compared with the parity stored in SC0BUF <RB7>, while in the 8-bit UART mode, it is compared with the bit 7 <RB8> of the SC0CR register. If there is any difference, a parity error occurs and the <PERR> flag of the SC0CR register is set.

In the I/O interface mode, the SC0CR <PERR> flag functions as an under-run error flag, not as a parity flag.

### 9.3.15 Error Flag

Three error flags are provided to improve the reliability of received data.

1. Overrun error <OERR>: Bit 4 of the serial control register SC0CR

In both UART and I/O interface modes, this bit is set to “1” when an error is generated by completing the reception of the next frame receive data before the receive buffer has been read. If the receive FIFO is enabled, the received data is automatically moved to the receive FIFO and no overrun error will be generated until the receive FIFO is full (or until the usable bytes are fully occupied). This flag is set to “0” when it is read. In the I/O interface SCLK output mode, no overrun error is generated and therefore, this flag is inoperative and the operation is undefined.

2. Parity error/under-run error <PERR>: Bit 3 of the SC0CR register

In the UART mode, this bit is set to “1” when a parity error is generated. A parity error is generated when the parity generated from the received data is different from the parity received. This flag is set to “0” when it is read.

In the I/O interface mode, this bit indicates an under-run error. When the double buffer control bit <WBUF> of the serial mode control register SC0MOD2 is set to “1” in the SCLK input mode, if no data is set to the transmit double buffer before the next data transfer clock after completing the transmission from the transmit shift register, this error flag is set to “1” indicating an under-run error. If the transmit FIFO is enabled, any data content in the transmit FIFO will be moved to the buffer. When the transmit FIFO and the double buffer are both empty, an under-run error will be generated. Because no under-run errors can be generated in the SCLK output mode, this flag is inoperative and the operation is undefined. If Transmit Buffer 2 is disabled, the under-run flag <PERR> will not be set. This flag is set to “0” when it is read.

### 3. Framing error <FERR>: Bit 2 of the SC0CR register

In the UART mode, this bit is set to “1” when a framing error is generated. This flag is set to “0” when it is read. A framing error is generated if the corresponding stop bit is determined to be “0” by sampling the bit at around the center. Regardless of the <SBLN> (stop bit length) setting of the serial mode control register 2, SC0MOD2, the stop bit status is determined by only 1 bit on the receive side.

Operation mode	Error flag	Function
UART	OERR	Overrun error flag
	PERR	Parity error flag
	FERR	Framing error flag
I/O Interface (SCLK input)	OERR	Overrun error flag
	PERR	Underrun error flag (WBUF = 1)
		Fixed to 0 (WBUF = 0)
FERR	Fixed to 0	
I/O Interface (SCLK output)	OERR	Operation undefined
	PERR	Operation undefined
	FERR	Fixed to 0

#### 9.3.16 Direction of Data Transfer

In the I/O interface mode, the direction of data transfer can be switched between “MSB first” and “LSB first” by the data transfer direction setting bit <DRCHG> of the SC0MOD2 serial mode control register 2. Don't switch the direction when data is being transferred.

#### 9.3.17 Stop Bit Length

In the UART transmission mode, the stop bit length can be set to either 1 or 2 bits by bit 4 <SBLN> of the SC0MOD2 register.

#### 9.3.18 Status Flag

If the double buffer function is enabled (SC0MOD2 <WBUF> = “1”), the bit 6 flag <RBFLL> of the SC0MOD2 register indicates the condition of receive buffer full. When one frame of data has been received and transferred from buffer 1 to buffer 2, this bit is set to “1” to show that buffer 2 is full (data is stored in buffer 2). When the receive buffer is read by CPU/DMAC, it is cleared to “0.” If <WBUF> is set to “0,” this bit is insignificant and must not be used as a status flag. When double buffering is enabled (SC0MOD2 <WBUF> = “1”), the bit 7 flag <TBEMP> of the SC0MOD2 register indicates that Transmit Buffer 2 is empty. When data is moved from Transmit Buffer 2 to Transmit Buffer 1 (shift register), this bit is set to “1” indicating that Transmit Buffer 2 is now empty. When data is set to the transmit buffer by CPU/DMAC, the bit is cleared to “0.” If <WBUF> is set to “0,” this bit is insignificant and must not be used as a status flag.

### 9.3.19 Configurations of Transmit/Receive Buffer

		<WBUF> = 0	<WBUF> = 1
UART	Transmit buffer	Single	Double
	Receive buffer	Double	Double
I/O Interface (SCLK input)	Transmit buffer	Single	Double
	Receive buffer	Double	Double
I/O Interface (SCLK output)	Transmit buffer	Single	Double
	Receive buffer	Single	Double

### 9.3.20 Software reset

Software reset is generated by writing the bits 1 and 0 of SC0MOD2 <SWRST1:0> as "10" followed by "01". As a result, SC0MOD0<RXE>, SC0MOD1<TXE>, SC0MOD2<TBEMP>,<RBFL>,<TXRUN> of mode registers and SC0CR<OERR>, <PERR>, <FERR> of control registers and internal circuit is initialized. Other states are maintained.

9.3.21 Signal Generation Timing

① UART Mode:

Receive Side

Mode	9-bit	8-bit with parity	8-bit, 7-bit, and 7-bit with parity
Interrupt generation timing	Around the center of the 1st stop bit	Around the center of the 1st stop bit	Around the center of the 1st stop bit
Framing error generation timing	Around the center of the stop bit	Around the center of the stop bit	Around the center of the stop bit
Parity error generation timing	—	Around the center of the last (parity) bit	Around the center of the last (parity) bit
Overrun error generation timing	Around the center of the stop bit	Around the center of the stop bit	Around the center of the stop bit

Transmit Side

Mode	9-bit	8-bit with parity	8-bit, 7-bit, and 7-bit with parity
Interrupt generation timing (<WBUF> = 0)	Just before the stop bit is sent	Just before the stop bit is sent	Just before the stop bit is sent
Interrupt generation timing (<WBUF> = 1)	Immediately after data is moved to transmit buffer 1 (just before start bit transmission)	Immediately after data is moved to transmit buffer 1 (just before start bit transmission).	Immediately after data is moved to transmit buffer 1 (just before start bit transmission)

② I/O interface mode:

Receive Side

Interrupt generation timing (<WBUF> = 0)	SCLK output mode	Immediately after the rising edge of the last SCLK
	SCLK input mode	Immediately after the rising or falling edge of the last SCLK (for rising or falling edge mode, respectively).
Interrupt generation timing (<WBUF> = 1)	SCLK output mode	Immediately after the rising edge of the last SCLK (just after data transfer to receive buffer 2) or just after receive buffer 2 is read.
	SCLK input mode	Immediately after the rising edge or falling edge of the last SCLK (right after data is moved to receive buffer 2).
Overrun error generation timing	SCLK input mode	Immediately after the rising or falling edge of the last SCLK (for rising or falling edge mode, respectively)

Transmit Side

Interrupt generation timing (<WBUF> = 0)	SCLK output mode	Immediately after the rising edge of the last SCLK
	SCLK input mode	Immediately after the rising or falling edge of the last SCLK (for rising or falling edge mode, respectively)
Interrupt generation timing (<WBUF> = 1)	SCLK output mode	Immediately after the rising edge of the last SCLK or just after data is moved to Transmit Buffer 1
	SCLK input mode	Immediately after the rising or falling edge of the last SCLK or just after data is moved to Transmit Buffer 1
Under-run error generation timing	SCLK input mode	Immediately after the falling or rising edge of the next SCLK

**(Note 1) Do not modify any control register when data is being sent or received (in a state ready to transmit or receive).**  
**(Note 2) Do not stop the receive operation (by setting SC0MOD0 <RXE> = "0") when data is being received.**  
**(Note 3) Do not stop the transmit operation (by setting SC0MOD1 <TXE> = "0") when data is being transmitted.**

## 9.4 Register Description (Only for Channel 0)

The channel 0 registers are described here. Each register for all the channels operates in the same way.

### 9.4.1 Enable register

	7	6	5	4	3	2	1	0	
SC0EN	bit Symbol								SIOE
	Read/Write								R/W
	After reset								0
	Function								SIO operation 0:disabled 1:enabled

<SIOE>: Specified the SIO operation.  
 To use the SIO, enable the SIO operation.  
 When the operation is disabled, no clock is supplied to the other registers in the SIO module.  
 This can reduce the power consumption.  
 If the SIO operation is executed and then disabled, the settings will be maintained in each register.

### 9.4.2 Buffer register



SC0BUF works as a transmit buffer for WR operation and as a receive buffer for RD operation.

	7	6	5	4	3	2	1	0	
SC0BUF	bit Symbol	TB7/RB7	TB6/RB6	TB5/RB5	TB4/RB4	TB3/RB3	TB2/RB2	TB1/RB1	TB0/RB0
	Read/Write	R/W							
	After reset	0	0	0	0	0	0	0	0
	Function	TB7~0 : Transmit buffer/FIFO RB7~0 : Receive buffer/FIFO							

<TB7:0> Transmit buffer (at WR operation).

<RB7:0> Receive buffer (at RD operation).

### 9.4.3 Control register

	7	6	5	4	3	2	1	0
bit Symbol	RB8	EVEN	PE	OERR	PERR	FERR	SCLKS	IOC
Read/Write	R	R/W		R (Cleared to "0" when read)			R/W	
After reset	0	0	0	0	0	0	0	0
Function	Receive data bit 8 (For UART)	Parity (For UART) 0: Odd 1: Even	Add parity (For UART) 0: Disabled 1: Enabled	0: Normal operation 1: Error			0: SCLK0  1: SCLK0 	(For I/O interface) 0: Baud rate generator 1: SCLK0 pin input
				Overrun	Parity/underrun	Framing		

<RB8>: 9<sup>th</sup> bit of the received data in the 9 bits UART mode.

<EVEN>: Selects even or odd parity.  
 "0": odd parity.  
 "1": even parity.  
 The parity bit may be used only in the 7- or 8-bit UART mode.

<PE>: Controls enabling/ disabling parity.  
 The parity bit may be used only in the 7- or 8-bit UART mode.

<OERR>: Error flag (see note)

<PERR>: Indicate overrun error, parity error, underrun error and framing error.

<FERR>:

<SCLKS>: Selects edge for data transmission and reception.  
 "0": Data transmit/receive at rising edges of SCLK0  
 "1": Data transmit/receive at falling edges of SCLK0

<IOC>: Selects input clock in the I/O interface mode.  
 "0": baud rate generator  
 "1": SCLK0 pin input.

**(Note) Any error flag is cleared when read.**



### 9.4.4 Mode control register 0

	7	6	5	4	3	2	1	0
bit Symbol	TB8	CTSE	RXE	WU	SM1	SM0	SC1	SC0
Read/Write	R/W							
SC0MOD0 After reset	0	0	0	0	0	0	0	0
Function	Transmit data bit 8	Handshake function control 0: CTS disable 1: CTS enable	Receive control 0: Reception disabled 1: Reception enabled	Wake-up function 0: Reception disabled 1: Reception enabled	Serial transfer mode 00: I/O interface mode 01: 7-bit length UART mode 10: 8-bit length UART mode 11: 9-bit length UART mode		Serial transfer clock (for UART) 00: TMRB output 01: Baud rate generator 10: Internal clock f <sub>sys</sub> 11: External clock (SCLK0 input)	

<TB8>: Writes the 9<sup>th</sup> bit of transmit data in the 9 bits UART mode.

<CTSE>: Controls handshake function.  
Setting "1" enables handshake function using  $\overline{\text{CTS}}$  pin.

<RXE>: Controls reception (**see note**).  
Set <RXE> after setting each mode register (SC0MOD0, SC0MOD1 and SC0MOD2).

<WU>: Controls wake-up function.  
This function is available only at 9-bit UART mode.

	9-bit UART mode	Other modes
0	Interrupt when received	don't care
1	Interrupt only when RB9=1	

<SM1:0>: Specifies transfer mode.

<SC1:0>: Selects the serial transfer clock in the UART mode.  
As for the I/O interface mode, the serial transfer clock can be set in the control register SC0CR. When TMRB output is used for the serial transfer clock, TB4OUT is used in SIO0,1, and TB7OUT is used in SIO2,3.

**(Note)** With <RXE> set to "0," set each mode register (SC0MOD0, SC0MOD1 and SC0MOD2). Then set <RXE> to "1."

## 9.4.5 Mode control register 1

	7	6	5	4	3	2	1	0
bit Symbol	I2S0	FDPX1	FDPX0	TXE	SINT2	SINT1	SINT0	-
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0
Function	IDLE 0: Stop 1: Start	Transfer mode setting 00: Transfer prohibited 01: Half duplex(RX) 10: Half duplex(TX) 11: Full duplex		Transmit control 0: Disabled 1: Enabled	Interval time of continuous transmission <b>(for I/O interface)</b> 000: None 100: 8SCLK 001: 1SCLK 101: 16SCLK 010: 2SCLK 110: 32SCLK 011: 4SCLK 111: 64SCLK			Write "0".

<I2S0>: Specifies the IDLE mode operation.

<FDPX1:0>: Configures the transfer mode in the I/O interface mode. Also configures the FIFO if it is enabled. In the UART mode, it is used only to specify the FIFO configuration.

<TXE>: This bit enables transmission and is valid for all the transfer modes (**see note**). If disabled while transmission is in progress, transmission is inhibited only after the current frame of data is completed for transmission.

<SINT2:0>: Specifies the interval time of continuous transmission when double buffering or FIFO is enabled in the I/O interface mode. This parameter is valid only for the I/O interface mode when SCLK0 pin input is not selected.

**(Note) Specify the mode first and then specify the <TXE> bit.**

## 9.4.6 Mode control register 2

	7	6	5	4	3	2	1	0
bit Symbol	TBEMP	RBFL	TXRUN	SBLN	DRCHG	WBUF	SWRST1	SWRST0
Read/Write	R			R/W				
After reset	1	0	0	0	0	0	0	0
Function	Transmit buffer empty flag 0: full 1: Empty	Receive Buffer full flag 0: Empty 1: full	In transmission flag 0: Stop 1: Start	STOP bit (for UART) 0: 1-bit 1: 2-bit	Setting transfer direction 0: LSB first 1: MSB first	W-buffer 0: Disabled 1: Enabled	SOFT RESET Overwrite "01" on "10" to reset.	

<TBEMP>: This flag shows that the transmit double buffers are empty. When data in the transmit double buffers is moved to the transmit shift register and the double buffers are empty, this bit is set to "1." Writing data again to the double buffers sets this bit to "0." If double buffering is disabled, this flag is insignificant.

<RBFL>: This is a flag to show that the receive double buffers are full. When a receive operation is completed and received data is moved from the receive shift register to the receive double buffers, this bit changes to "1" while reading this bit changes it to "0." If double buffering is disabled, this flag is insignificant.

<TXRUN>: This is a status flag to show that data transmission is in progress.  
<TXRUN> and <TBEMP> bits indicate the following status.

<TXRUN>	<TBEMP>	Status
1	-	Transmission in progress
0	1	Transmission completed
	0	Wait state with data in TX buffer

<SBLN>: This specifies the length of stop bit transmission in the UART mode. On the receive side, the decision is made using only a single bit regardless of the <SBLN> setting.

<DRCHG>: Specifies the direction of data transfer in the I/O interface mode. In the UART mode, it is fixed to LSB first.

<WBUF>: This parameter enables or disables the transmit/receive buffers to transmit (in both SCLK output/input modes) and receive (in SCLK output mode) data in the I/O interface mode and to transmit data in the UART. When receiving data in the I/O interface mode (I SCLK input) and UART mode, double buffering is enabled in both cases that 0 or 1 is set to <WBUF> bit.

<SWRST1:0>: Overwriting "01" in place of "10" generates a software reset. When this software reset is executed, the following bits and their internal circuits are initialized (**see note 1, 2 and 3**).

Register	Bit
SC0MOD0	RXE
SC0MOD1	TXE
SC0MOD2	TBEMP, RBFL, TXRUN,
SC0CR	OERR, PERR, FERR

- (Note 1)** While data transmission is in progress, any software reset operation must be executed twice in succession.
- (Note 2)** A software reset requires 2 clocks-duration at the time between the end of recognition and the start of execution of software reset instruction.
- (Note 3)** A software reset initializes other bits. Resetting a mode register and a control register are needed.

**9.4.7 Baud rate generator control register(SC0BRCR)  
Baud rate generator control register 2(SC0BRADD)**

		7	6	5	4	3	2	1	0
	bit Symbol	-	BR0ADDE	BR0CK1	BR0CK0	BR0S3	BR0S2	BR0S1	BR0S0
	Read/Write	R/W							
SC0BRCR	After reset	0	0	0	0	0	0	0	0
	Function	Write "0":	N + (16 - K)/16 divider function 0: disabled 1: enabled	Select input clock to the baud rate generator 00: φT1 01: φT4 10: φT16 11: φT64	Division ratio "N" 0000: 16 0001: 1 0010: 2 : 1111: 15				

		7	6	5	4	3	2	1	0
	bit Symbol					BR0K3	BR0K2	BR0K1	BR0K0
	Read/Write	R				R/W			
SC0BRADD	After reset	0				0	0	0	0
	Function	"0" is read.				Specify K for the "N + (16 - K)/16" division 0000: Prohibited 0001: K=1 0010: K=2 : 1111: K=15			

- <RB0ADDE>: Specifies N + (16-K)/16 division function.  
N + (16-K)/16 division function can only be used in the UART mode.
- <RB0CK1:0>: Specifies the baud rate generator input clock.
- <RB0S3:0>: Specifies division ratio "N".
- <RB0K3:0>: Specifies K for the "N+(16-K)/16" division.

The division ratio of the baud rate generator can be specified in the registers shown above. Table 9-5 lists the settings of baud rate generator division ratio.

Table 9-5 Setting division ratio

	BR0ADDE=0	BR0ADDE=1 (Note 1) (Only UART)
BR0S	Specify "N" (Note 2) (Note 3)	
BR0K	No setting required	Setting "K" (Note 4)
Division ratio	Divide by N	$N + \frac{(16-K)}{16}$ division

- (Note 1) To use the “ $N + (16 - K)/16$ ” division function, be sure to set BR0K <BR0ADDE> to “1” after setting the K value to BR0K. The “ $N + (16 - K)/16$ ” division function can only be used in the UART mode.
- (Note 2) The division ratio “1” of the baud rate generator can be specified only when
- the “ $N + (16 - K)/16$ ” division function is not used in the UART mode.
  - double buffering is used in the I/O interface mode.
- (Note 3) As a division ratio, 1 (“0001”) or 16 (“0000”) cannot be applied to N when using the “ $N + (16 - K)/16$ ” division function.
- (Note 4) Specifying “K = 0” is prohibited.

## 9.4.8 FIFO configuration register

	7	6	5	4	3	2	1	0
bit Symbol	Reserved	Reserved	Reserved	RFST	TFIE	RFIE	RXTXCNT	CNFG
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
Function	Be sure to write "000".			Bytes used in RX FIFO 0: Maximum 1: Same as FILL level of RX FIFO	TX interrupt for TX FIFO 0: Disabled 1: Enabled	RX interrupt for RX FIFO 0: Disabled 1: Enabled	Automatic disable of RXE/TXE 0: None 1: Auto disable	FIFO enable 0: Disabled 1: Enabled

<RFST>: When RX FIFO is enabled, the number of RX FIFO bytes to be used is selected (**see note**).

0: The maximum number of bytes of the FIFO configured (see also <CNFG>).

1: Same as the fill level for receive interrupt generation specified by SC0RFC <RIL1:0>.

<TFIE>: When TX FIFO is enabled, transmit interrupts are enabled or disabled by this parameter.

<RFIE>: When RX FIFO is enabled, receive interrupts are enabled or disabled by this parameter.

<RXTXCNT>: Controls automatic disabling of transmission and reception.

The mode control register SCOMOD1 <FDPX1:0> is used to set the types of TX/RX. Setting "1" enables to operate as follows.

Half duplex RX	When the RX FIFO is filled up to the specified number of valid bytes, SC0MOD0<RXE> is automatically set to "0" to inhibit further reception.
Half duplex TX	When the TX FIFO is empty, SC0MOD1<TXE> is automatically set to "0" to inhibit further transmission.
Full duplex	When either of the above two conditions is satisfied, TXE/RXE are automatically set to "0" to inhibit further transmission and reception.

<CNFG>: Enables FIFO.

If enabled, the SCOMOD1 <FDPX1:0> setting automatically configures FIFO as follows: (The type of TX/RX can be specified in the mode control register 1 SCOMOD1<FDPX1:0>).

Half duplex RX	RX FIFO 4byte
Half duplex TX	TX FIFO 4byte
Full duplex	RX FIFO 2byte + TX FIFO 2byte

**(Note) Regarding TX FIFO, the maximum number of bytes being configured is always available. The available number of bytes is the bytes already written to the TX FIFO.**

9.4.9 RX FIFO configuration register

		7	6	5	4	3	2	1	0
bit Symbol		RFCS	RFIS					RIL1	RIL0
Read/Write		W	R/W	R				R/W	
After reset		0	0	0				0	0
Function		RX FIFO clear 1: Clear "0" is read.	Select interrupt generation condition 0: when the data reaches to the specified fill level. 1: when the data reaches to the specified fill level or the data exceeds the specified fill level at the time data is read.	"0" is read.				FIFO fill level to generate RX interrupts 00:4byte (2 Byte at full duplex) 01:1byte 10:2byte 11:3byte	

<RFCS>: Clears RX FIFO  
Setting "1" clears RX FIFO and "0" is always read.

<RFIS>: Specifies the condition of interrupt generation.  
0: An interrupt is generated when it reaches to the specified fill level.  
An interrupt is generated when it is reaches to the specified fill level or if it exceeds the specified fill level at the time data is read.

<RIL1:0>: Specifies FIFO fill level(see note).

	Other than full duplex	Full duplex
00	4byte	2byte
01	1byte	1byte
10	2byte	2byte
11	3byte	1byte

**(Note) RIL1 is ignored when FDPX1:0 = 11 (full duplex)**



9.4.10 TX FIFO configuration register

	7	6	5	4	3	2	1	0
bit Symbol	TFCS	TFIS					TIL1	TIL0
Read/Write	W	R/W	R				R/W	
After reset	0	0	0				0	0
Function	TX FIFO clear 1:Clear Always reads "0".	Select interrupt generation condition 0: when the data reaches to the specified fill level. 1: when the data reaches to the specified fill level or the data cannot reach the specified fill level at the time new data is read.	"0" is read.				FIFO fill level to generate TX interrupts. 00:Empty 01:1byte 10:2byte 11:3byte Note: TIL1 is ignored when FDPX1:0=11 (full duplex).	

<TFCS>: Clears TX FIFO.  
Setting "1" clears TX FIFO and "0" is always read.

<TFIS>: Selects interrupt generation condition.  
0: An interrupt is generated when the data reaches to the specified fill level.  
1: An interrupt is generated when the data reaches to the specified fill level or the data cannot reach the specified fill level at the time new data is read.

<TIL1:0>: Selects FIFO fill level (see note).

	Other than full duplex	Full duplex
00	Empty	Empty
01	1byte	1byte
10	2byte	Empty
11	3byte	1byte

**(Note) TIL1 is ignored when FDPX1:0 = 11 (full duplex).**

### 9.4.11 RX FIFO status register

		7	6	5	4	3	2	1	0
SC0RST	bit Symbol	ROR					RLVL2	RLVL1	RLVL0
	Read/Write	R	R				R		
	After reset	0	0				0	0	0
	Function	RX FIFO Overflow  1: Generated	"0" is read.				Status of RX FIFO fill level 000:Empty 001:1Byte 010:2Byte 011:3Byte 100:4Byte		

<ROR>: Flags for RX FIFO overrun. When the overrun occurs, these bits are set to "1" (see note).

<RLVL2:0>: Shows the fill level of RX FIFO.

**(Note)** The <ROR> bit is cleared to "0" when receive data is read from the SC0BUF register.

### 9.4.12 TX FIFO status register

		7	6	5	4	3	2	1	0
SC0TST	bit Symbol	TUR					TLVL2	TLVL1	TLVL0
	Read/Write	R	R				R		
	After reset	1	0				0	0	0
	Function	TX FIFO Under run 1:Generated Cleared by writing FIFO	"0" is read.				Status of TX FIFO fill level 000:Empty 001:1Byte 010:2Byte 011:3Byte 100:4Byte		

<TUR>: Flags for TX FIFO underrun. When the underrun occurs, these bits are set to "1" (see note).

<TLVL2:0>: Shows the fill level of TX FIFO.

**(Note)** The <TUR> bit is cleared to "0" when transmit data is written to the SC0BUF register.

## 9.5 Operation in Each Mode

### 9.5.1 Mode 0 (I/O interface mode)

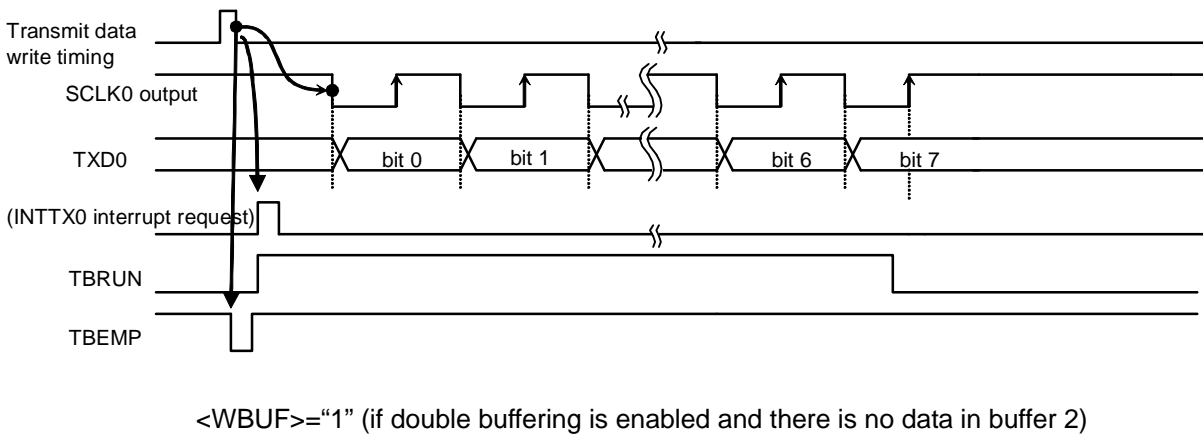
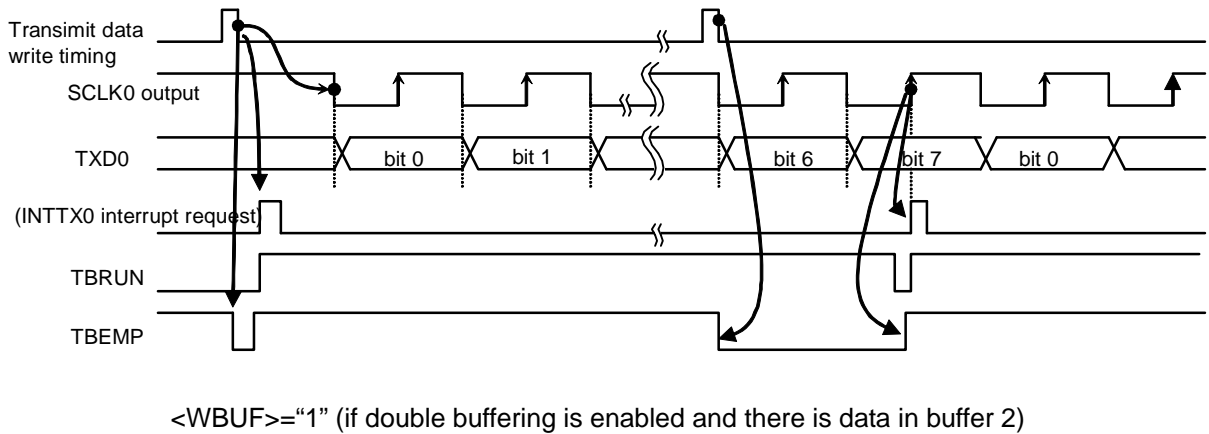
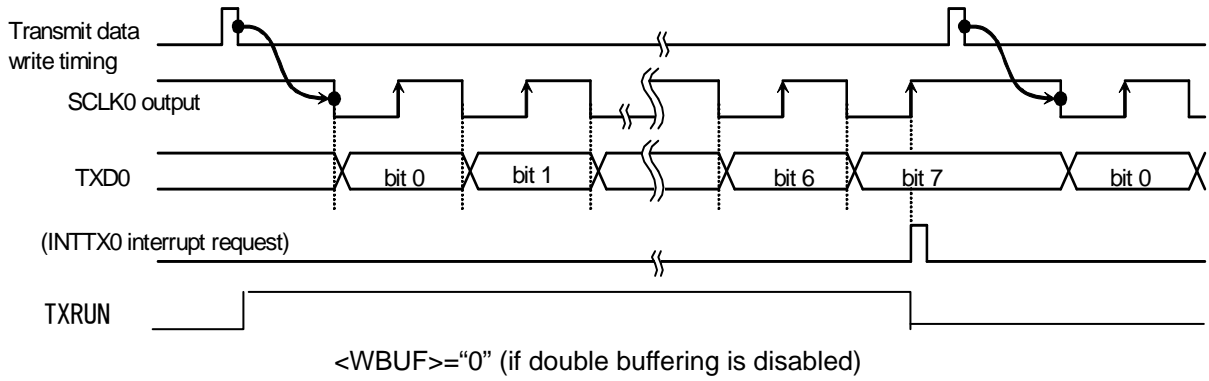
Mode 0 consists of two modes, the “SCLK output” mode to output synchronous clock and the “SCLK input” mode to accept synchronous clock from an external source. The following operational descriptions are for the case use of FIFO is disabled. For details of FIFO operation, refer to the previous sections describing receive/transmit FIFO functions.

① Transmitting data

SCLK output mode

In the SCLK output mode, if SC0MOD2<WBUF> is set to “0” and the transmit double buffers are disabled, 8 bits of data are output from the TXD0 pin and the synchronous clock is output from the SCLK0 pin each time the CPU writes data to the transmit buffer. When all data is output, the INTTX0 interrupt is generated.

If SC0MOD2 <WBUF> is set to “1” and the transmit double buffers are enabled, data is moved from Transmit Buffer 2 to Transmit Buffer 1 when the CPU writes data to Transmit Buffer 2 while data transmission is halted or when data transmission from Transmit Buffer 1 (shift register) is completed. When data is moved from Transmit Buffer 2 to Transmit Buffer 1, the transmit buffer empty flag SC0MOD2 <TBEMP> is set to “1,” and the INTTX0 interrupt is generated. If Transmit Buffer 2 has no data to be moved to Transmit Buffer 1, the INTTX0 interrupt is not generated and the SCLK0 output stops.

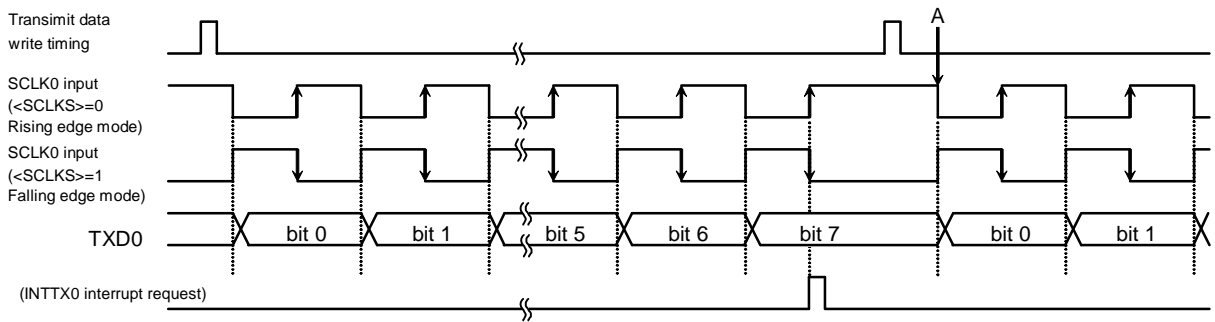


**Fig. 9-10 Transmit Operation in the I/O Interface Mode (SCLK0 Output Mode)**

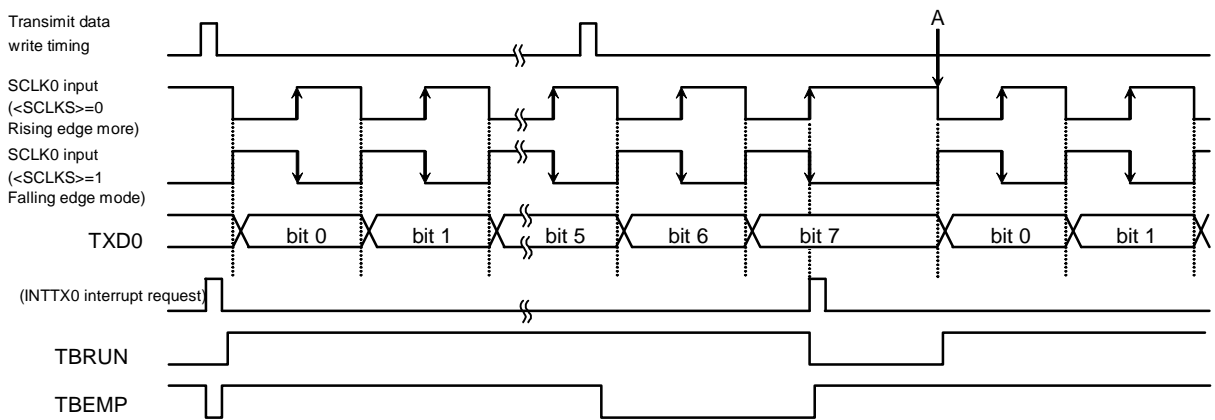
SCLK input mode

In the SCLK input mode, if SC0MOD2 <WBUF> is set to “0” and the transmit double buffers are disabled, 8-bit data that has been written in the transmit buffer is output from the TXD0 pin when the SCLK0 input becomes active. When all 8 bits are sent, the INTTX0 interrupt is generated. The next transmit data must be written before the timing point “A” as shown in Fig. 9-11.

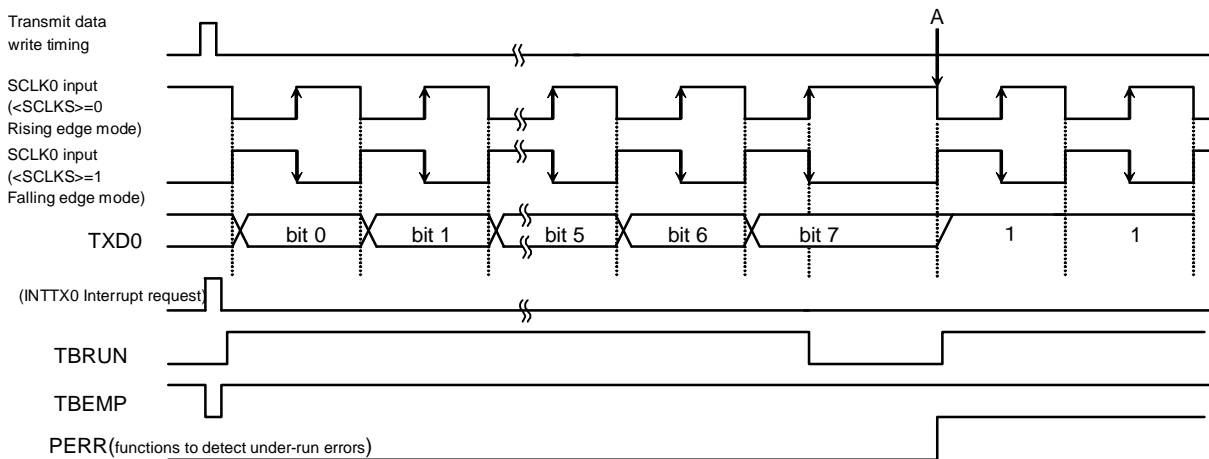
If SC0MOD2 <WBUF> is set to “1” and the transmit double buffers are enabled, data is moved from Transmit Buffer 2 to Transmit Buffer 1 when the CPU writes data to Transmit Buffer 2 before the SCLK0 becomes active or when data transmission from Transmit Buffer 1 (shift register) is completed. As data is moved from Transmit Buffer 2 to Transmit Buffer 1, the transmit buffer empty flag SC0MOD2 <TBEMP> is set to “1” and the INTTX0 interrupt is generated. If the SCLK0 input becomes active while no data is in Transmit Buffer 2, although the internal bit counter is started, an under-run error occurs and 8-bit dummy data (FFh) is sent.



<WBUF>="0" (if double buffering is disabled)



<WBUF>="1" (if double buffering is enabled and there is data in buffer 2)



<WBUF>="1" (if double buffering is enabled and there is no data in buffer 2)

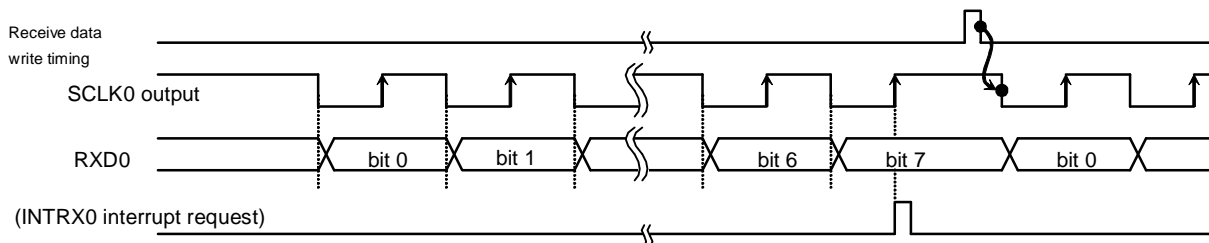
Fig. 9-11 Transmit Operation in the I/O Interface Mode (SCLK0 Input Mode)

② Receiving data  
SCLK output mode

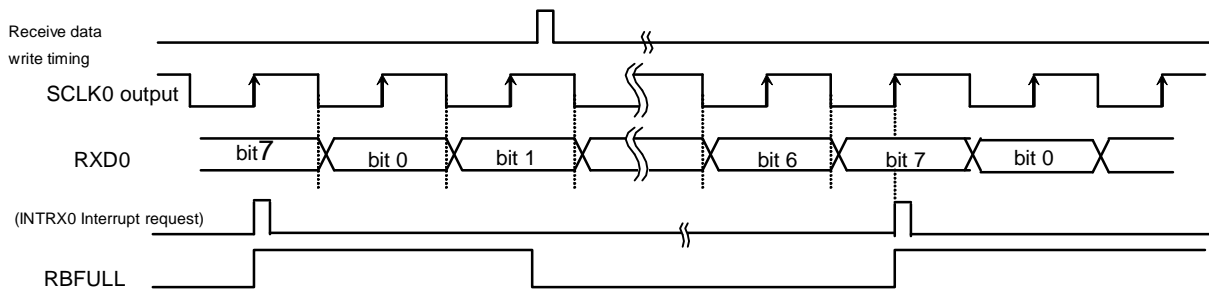
In the SCLK output mode, if SC0MOD2 <WBUF> = "0" and receive double buffering is disabled, a synchronous clock pulse is output from the SCLK0 pin and the next data is shifted into receive buffer 1 each time the CPU reads received data. When all the 8 bits are received, the INTRX0 interrupt is generated.

The first SCLK output can be started by setting the receive enable bit SC0MOD0 <RXE> to "1." If the receive double buffering is enabled with SC0MOD2 <WBUF> set to "1," the first frame received is moved to receive buffer 2 and receive buffer 1 can receive the next frame successively. As data is moved from receive buffer 1 to receive buffer 2, the receive buffer full flag SC0MOD2 <RBFULL> is set to "1" and the INTRX0 interrupt is generated.

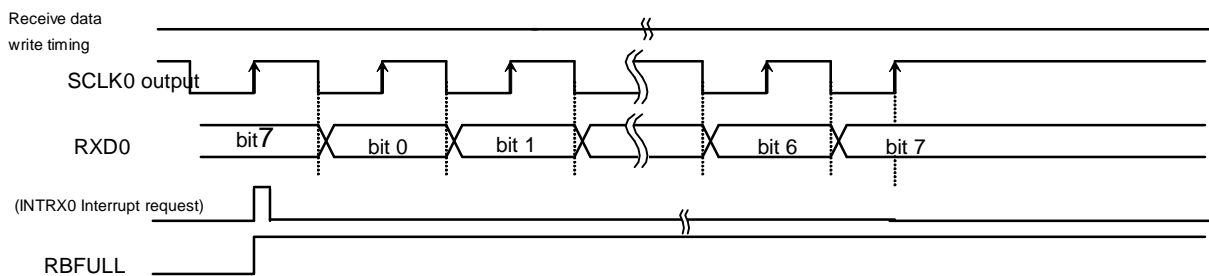
While data is in receive buffer 2, if CPU/DMAC cannot read data from receive buffer 2 before completing reception of the next 8 bits, the INTRX0 interrupt is not generated and the SCLK0 clock stops. In this state, reading data from receive buffer 2 allows data in receive buffer 1 to move to receive buffer 2 and thus the INTRX0 interrupt is generated and data reception resumes.



<WBUF>="0" (if double buffering is disabled)



<WBUF>="1" (if double buffering is enabled and data is read from buffer 2)



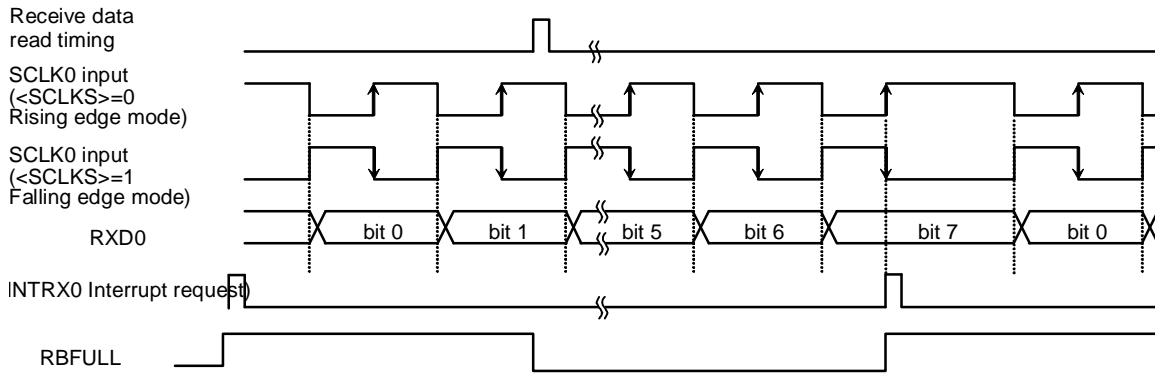
<WBUF>="1" (if double buffering is enabled and data cannot be read from buffer 2)

**Fig. 9-12 Receive Operation in the I/O Interface Mode (SCLK0 Output Mode)**

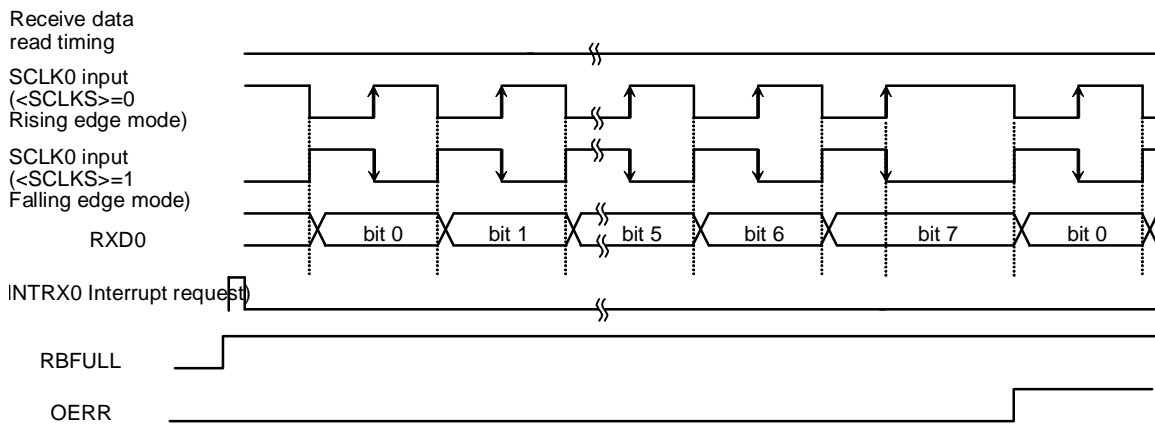
SCLK input mode

In the SCLK input mode, receiving double buffering is always enabled, the received frame can be moved to receive buffer 2 and receive buffer 1 can receive the next frame successively.

The INTRX0 receive interrupt is generated each time received data is moved to received buffer 2.



If data is read from buffer 2



If data cannot be read from buffer 2

**Fig. 9-13 Receive Operation in the I/O Interface Mode (SCLK0 Input Mode)**

**(Note) To receive data, SC0MOD <RXE> must always be set to "1" (receive enable) in the SCLK output / SCLK input mode.**



③ Transmit and receive (full-duplex)

The full-duplex mode is enabled by setting bit 6 <FDPX0> of the serial mode control register 1 (SC0MOD1) to "1".

SCLK output mode

In the SCLK output mode, if SC0MOD2 <WBUF> is set to "0" and both the transmit and receive double buffers are disabled, SCLK is output when the CPU writes data to the transmit buffer. Subsequently, 8 bits of data are shifted into receive buffer 1 and the INTRX0 receive interrupt is generated. Concurrently, 8 bits of data written to the transmit buffer are output from the TXD0 pin, the INTTX0 transmit interrupt is generated when transmission of all data bits has been completed. Then, the SCLK output stops. In this, the next round of data transmission and reception starts when the data is read from the receive buffer and the next transmit data is written to the transmit buffer by the CPU. The order of reading the receive buffer and writing to the transmit buffer can be freely determined. Data transmission is resumed only when both conditions are satisfied.

If SC0MOD2 <WBUF> = "1" and double buffering is enabled for both transmission and reception, SCLK is output when the CPU writes data to the transmit buffer. Subsequently, 8 bits of data are shifted into receive buffer 1, moved to receive buffer 2, and the INTRX0 interrupt is generated. While 8 bits of data is received, 8 bits of transmit data is output from the TXD0 pin. When all data bits are sent out, the INTTX0 interrupt is generated and the next data is moved from the Transmit Buffer 2 to Transmit Buffer 1. If Transmit Buffer 2 has no data to be moved to Transmit Buffer 1 (SC0MOD2 <TBEMP> = 1) or when receive buffer 2 is full (SC0MOD2 <RBFULL> = 1), the SCLK clock is stopped. When both conditions, receive data is read and transmit data is written, are satisfied, the SCLK output is resumed and the next round of data transmission is started.

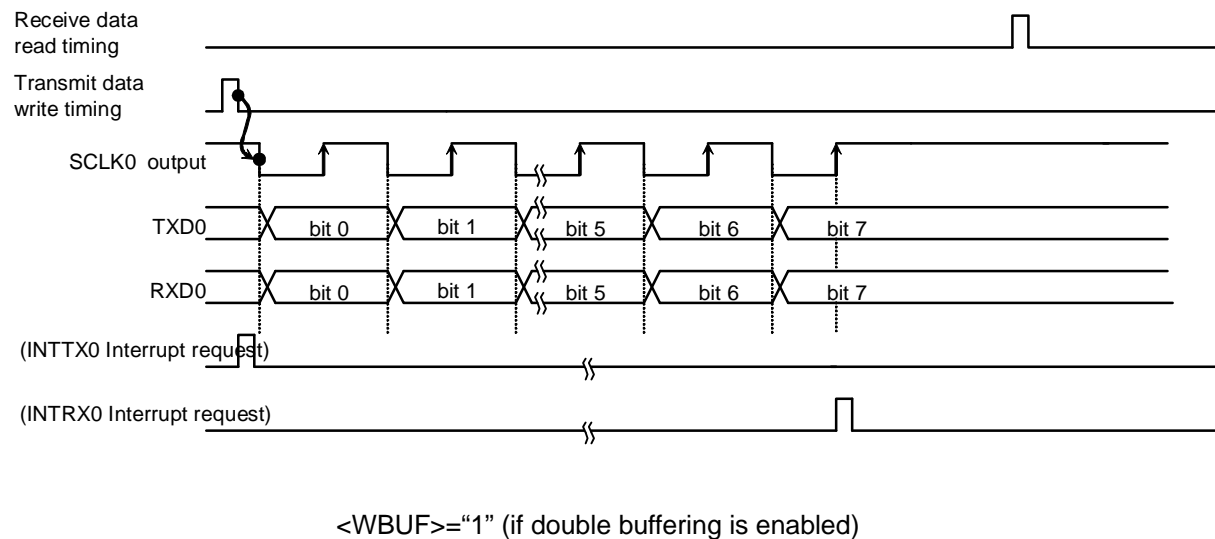
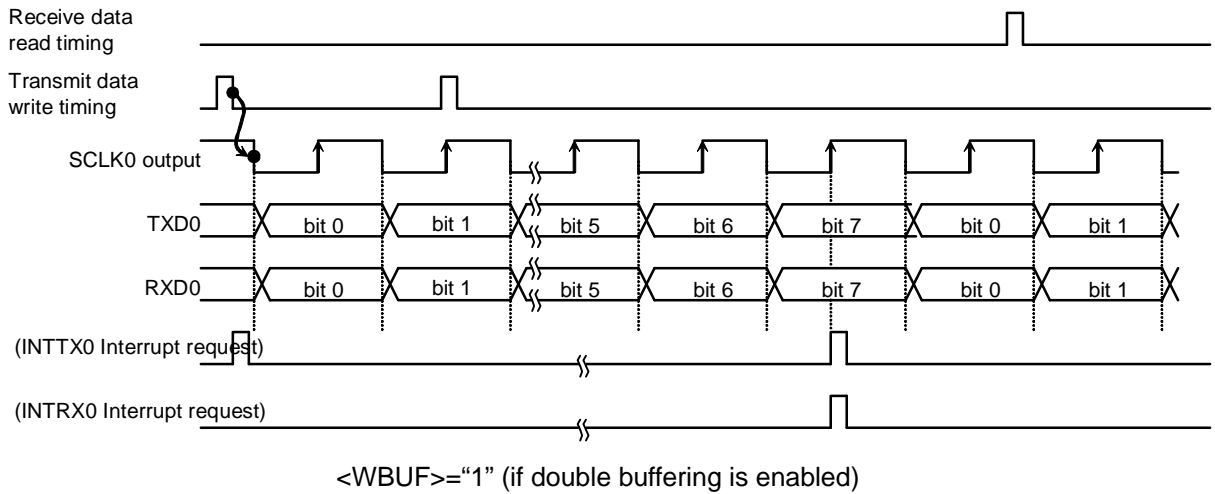
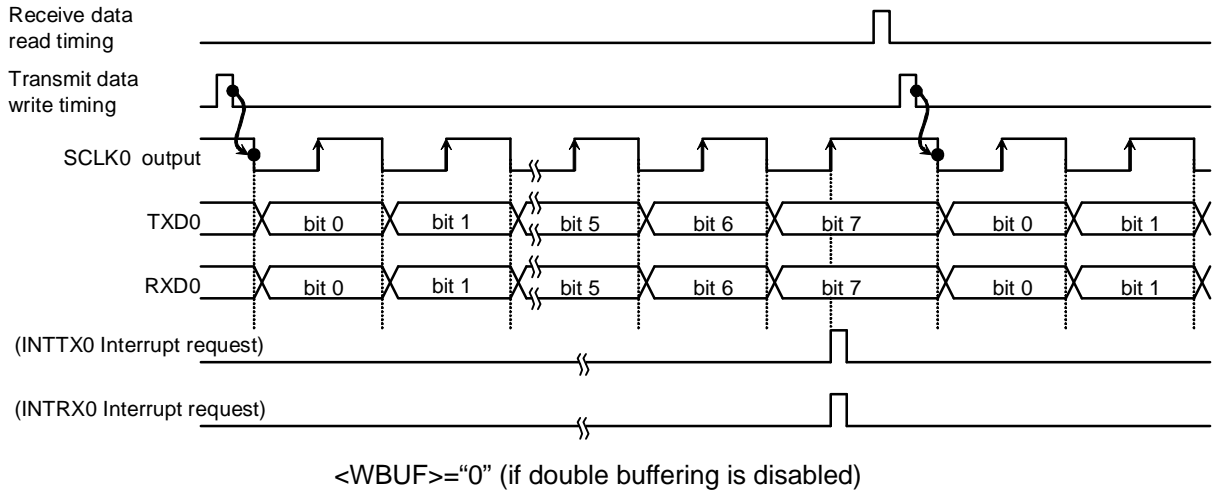
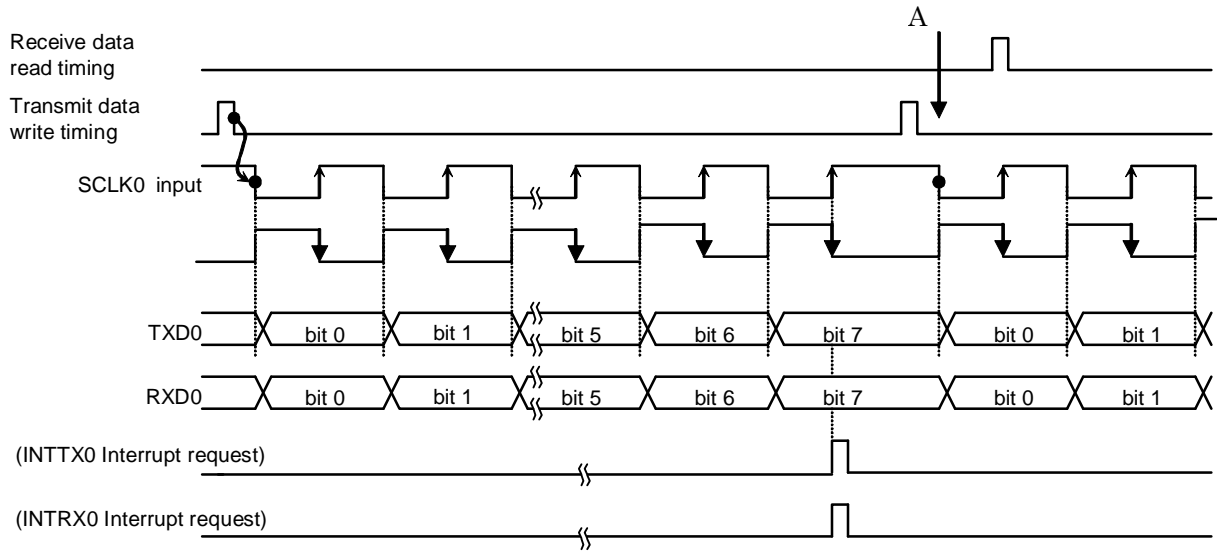


Fig. 9-14 Transmit/Receive Operation in the I/O Interface Mode (SCLK0 Output Mode)

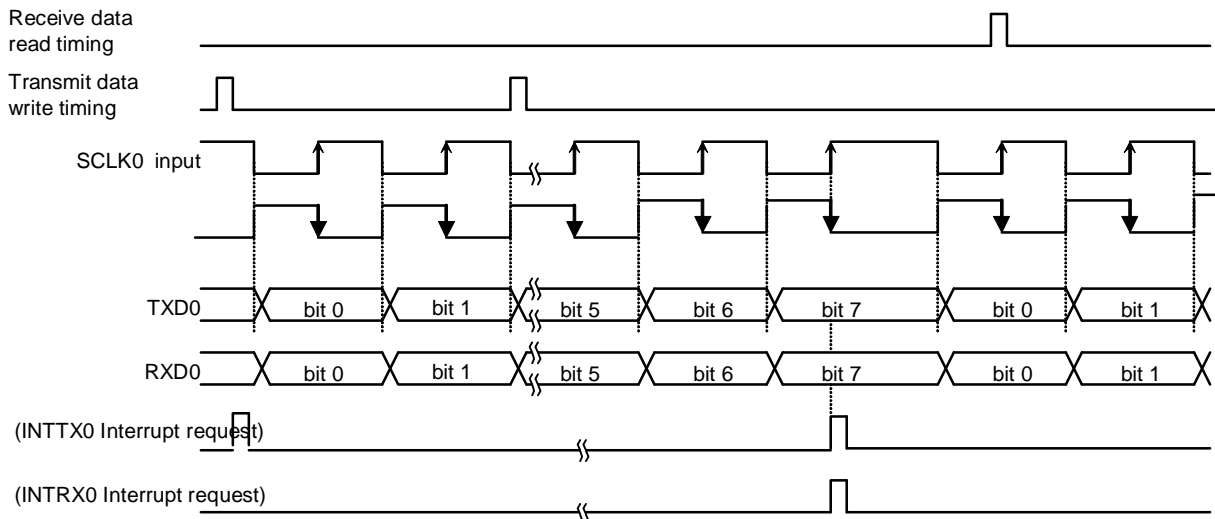
### SCLK input mode

In the SCLK input mode with SC0MOD2 <WBUF> set to "0" and the transmit double buffers are disabled (double buffering is always enabled for the receive side), 8-bit data written in the transmit buffer is output from the TXD0 pin and 8 bits of data is shifted into the receive buffer when the SCLK input becomes active. The INTTX0 interrupt is generated upon completion of data transmission and the INTRX0 interrupt is generated at the instant the received data is moved from receive buffer 1 to receive buffer 2. Note that transmit data must be written into the transmit buffer before the SCLK input for the next frame (data must be written before the point A in Fig. 9-15). As double buffering is enabled for data reception, data must be read before completing reception of the next frame data.

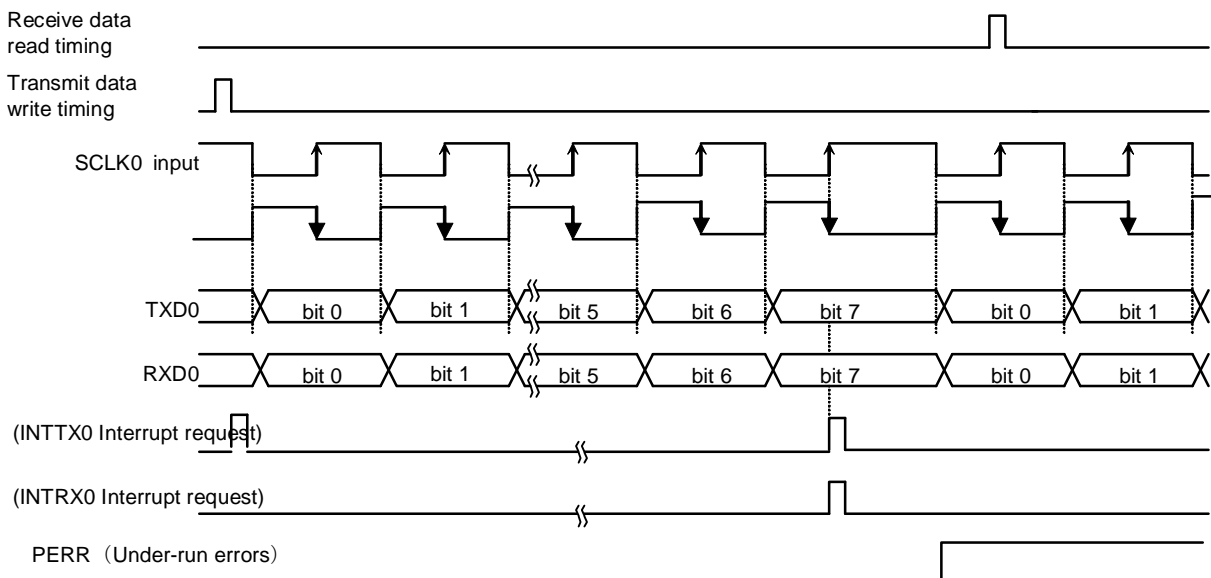
If SC0MOD2 <WBUF> = "1" and double buffering is enabled for both transmission and reception, the interrupt INTRX0 is generated at the timing Transmit Buffer 2 data is moved to Transmit Buffer 1 after completing data transmission from Transmit Buffer 1. At the same time, the 8 bits of data received is shifted to buffer 1, it is moved to receive buffer 2, and the INTRX0 interrupt is generated. Upon the SCLK input for the next frame, transmission from Transmit Buffer 1 (in which data has been moved from Transmit Buffer 2) is started while receive data is shifted into receive buffer 1 simultaneously. If data in receive buffer 2 has not been read when the last bit of the frame is received, an overrun error occurs. Similarly, if there is no data written to Transmit Buffer 2 when SCLK for the next frame is input, an under-run error occurs.



<WBUF>="0" (if double buffering is disabled)



<WBUF>="1" (if double buffering is enabled with no errors)



<WBUF>="1" (if double buffering is enabled with error generation)

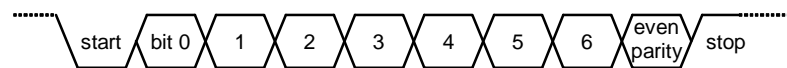
**Fig. 9-15 Transmit/Receive Operation in the I/O Interface Mode (SCLK0 Input Mode)**

### 9.5.2 Mode 1 (7-bit UART Mode)

The 7-bit UART mode can be selected by setting the serial mode control register (SCOMOD <SM1, 0>) to "01".

In this mode, parity bits can be added to the transmit data stream; the serial mode control register (SC0CR <PE>) controls the parity enable/disable setting. When <PE> is set to "1" (enable), either even or odd parity may be selected using the SC0CR <EVEN> bit. The length of the stop bit can be specified using SCOMOD2<SBLLEN>.

The following table shows the control register settings for transmitting in the following data format.



← Transmission direction (Transmission rate of 2400 bps @  $f_c = 9.8304$  MHz)

* Clocking conditions	{	System clock	: high- speed ( $f_c$ )
		High-speed clock gear	: x1 ( $f_c$ )
		Prescaler clock	: $f_{\text{periph}}/2$ ( $f_{\text{periph}} = f_{\text{sys}}$ )

### 9.5.3 Mode 2 (8-bit UART Mode)

The 8-bit UART mode can be selected by setting SC0MOD0 <SM1:0> to "10." In this mode, parity bits can be added and parity enable/disable is controlled using SC0CR <PE>. If <PE> = "1" (enabled), either even or odd parity can be selected using SC0CR <EVEN>.

The control register settings for receiving data in the following format are as follows:



* Clocking conditions	{ System clock	: High-speed ( $f_c$ )
	{ High-speed clock gear	: x1 ( $f_c$ )
	{ Prescaler clock	: $f_{\text{periph}}/4$ ( $f_{\text{periph}} = f_{\text{sys}}$ )

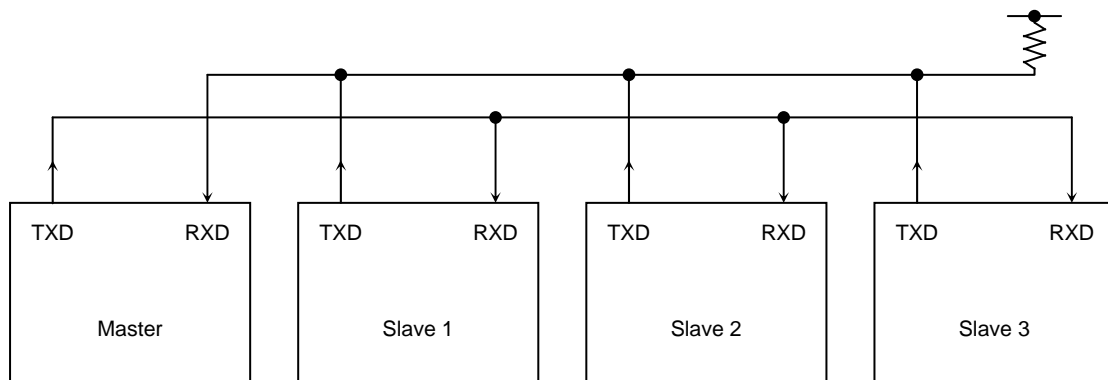
### 9.5.4 Mode 3 (9-bit UART)

The 9-bit UART mode can be selected by setting SC0MOD0 <SM1:0> to "11." In this mode, parity bits must be disabled (SC0CR <PE> = "0").

The most significant bit (9th bit) is written to bit 7 <TB8> of the serial mode control register 0 (SC0MOD0) for transmitting data. The data is stored in bit 7 <RB8> of the serial control register SC0CR. When writing or reading data to/from the buffers, the most significant bit must be written or read first before writing or reading to/from SC0BUF. The stop bit length can be specified using SC0MOD2 <SBLEN>.

#### Wakeup function

In the 9-bit UART mode, slave controllers can be operated in the wake-up mode by setting the wake-up function control bit SC0MOD0 <WU> to "1." In this case, the interrupt INTRX0 will be generated only when SC0CR <RB8> is set to "1".

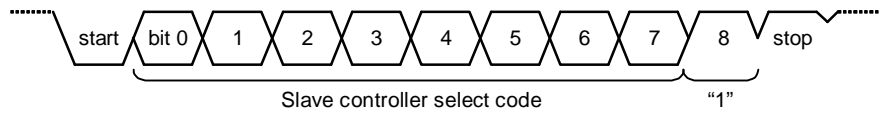


**(Note)** The TXD pin of the slave controller must be set to the open drain output mode using the ODE register.

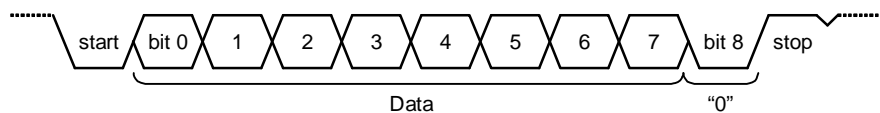
Fig. 9-16 Serial Links to Use Wake-up Function

Protocol

- ① Select the 9-bit UART mode for the master and slave controllers.
- ② Set SC0MOD <WU> to "1" for the slave controllers to make them ready to receive data.
- ③ The master controller is to transmit a single frame of data that includes the slave controller select code (8 bits). In this, the most significant bit (bit 8) <TB8> must be set to "1".

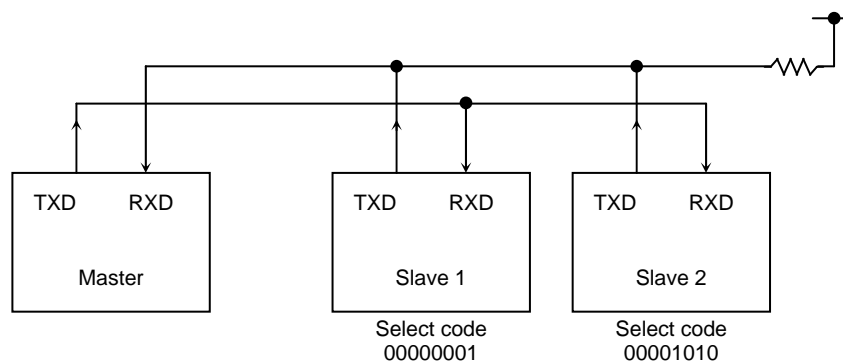


- ④ Each slave controller receives the above data frame; if the code received matches with the controller's own select code, it clears the WU bit to "0".
- ⑤ The master controller transmits data to the designated slave controller (the controller of which SC0MOD <WU> bit is cleared to "0"). In this, the most significant bit (bit 8) <TB8> must be set to "0".



- ⑥ The slave controllers with the <WU> bit set to "1" ignore the receive data because the most significant bit (bit 8) <RB8> is set to "0" and thus no interrupt (INTRX0) is generated. Also, the slave controller with the <WU> bit set to "0" can transmit data to the master controller to inform that the data has been successfully received.

An example: Using the internal clock  $f_{SYS}$  as the transfer clock, two slave controllers are serially linked as follows.





## 10. Watchdog Timer (Runaway Detection Timer)

The watchdog timer (WDT) is for detecting malfunctions (runaways) of the CPU caused by noises or other disturbances and remedying them to return the CPU to normal operation. If the timer detects a runaway, it generates a non-maskable interrupt or an internal reset to notify the CPU. The watchdog timer starts immediately after reset release.

### 10.1 Configuration

Fig. 10-1 shows the block diagram of the watchdog timer

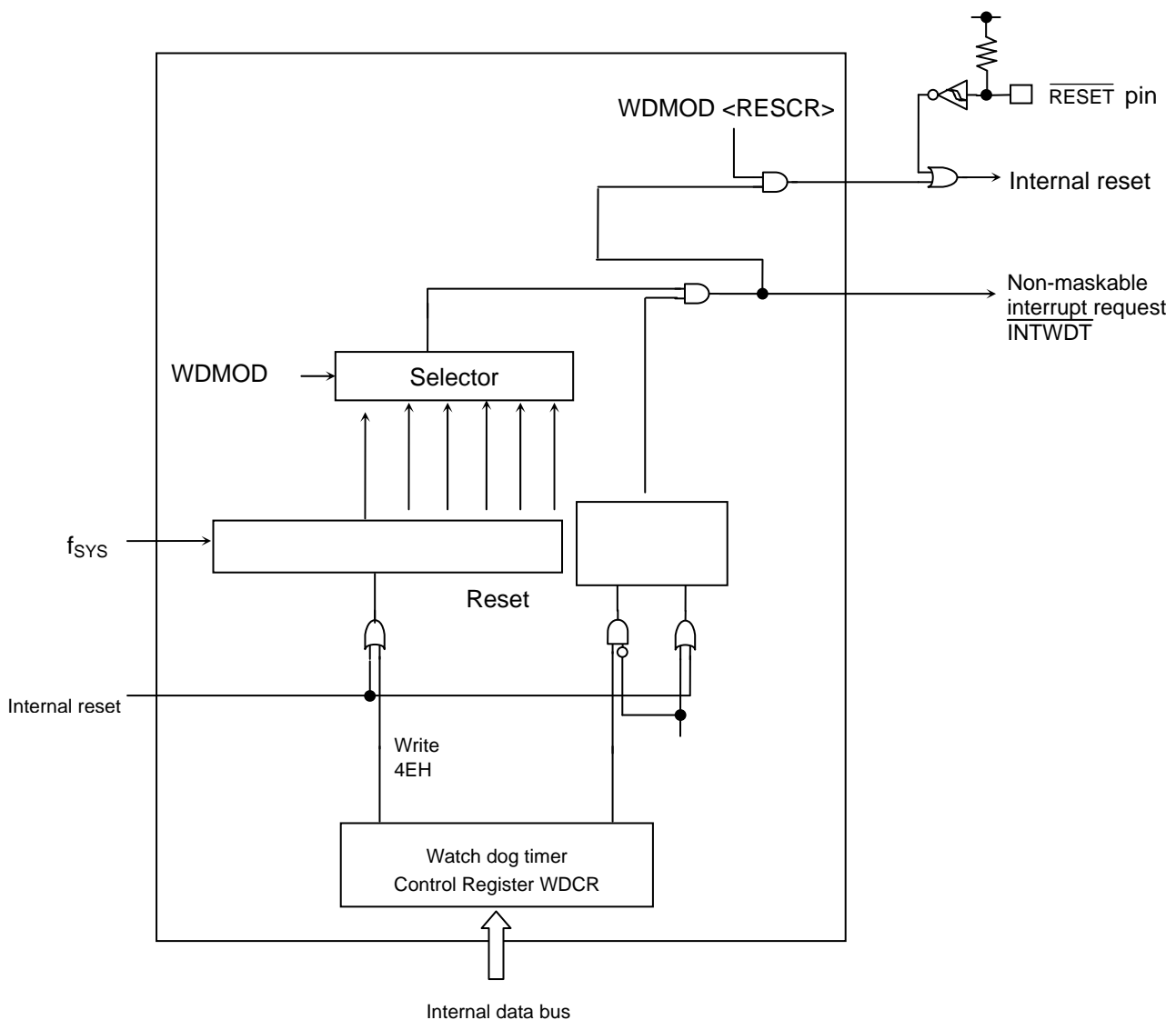


Fig. 10-1 Block Diagram of the Watchdog Timer

## 10.2 Outline

The watchdog timer consists of the binary counters that are arranged in 26 stages and work using the  $f_{SYS}$  system clock as an input clock. The outputs produced by these binary counters are  $2^{16}$ ,  $2^{18}$ ,  $2^{20}$ ,  $2^{22}$ ,  $2^{24}$  are  $2^{26}$ . By selecting one of these outputs with  $WDMOD <WDTP2:0>$ , a watchdog timer interrupt  $\overline{INTWDT}$  can be generated when an overflow occurs, as shown in Fig. 10-2.

### 10.2.1 Watchdog Timer Interrupt ( $WDMOD <RESCR> = 0$ )

When an overflow occurs, the watchdog timer generates a watchdog timer interrupt to the CPU.

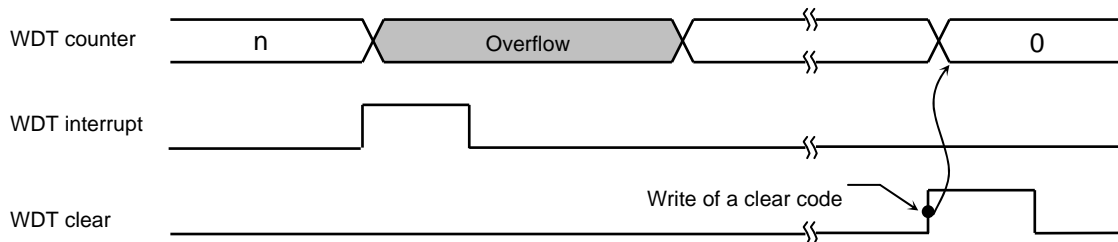


Fig. 10-2 Normal Mode

### 10.2.2 Reset Mode ( $WDMOD <RESCR> = 1$ )

When an overflow occurs, resetting the chip itself is an option to choose. If the chip is reset, a reset is affected for a 32-state time, as shown in Fig. 10-3. If this reset is affected, the clock  $f_{SYS}$  that the clock gear generates by dividing the clock  $f_C$  of the high-speed oscillator by 1 is used as an input clock  $f_{SYS}$ .

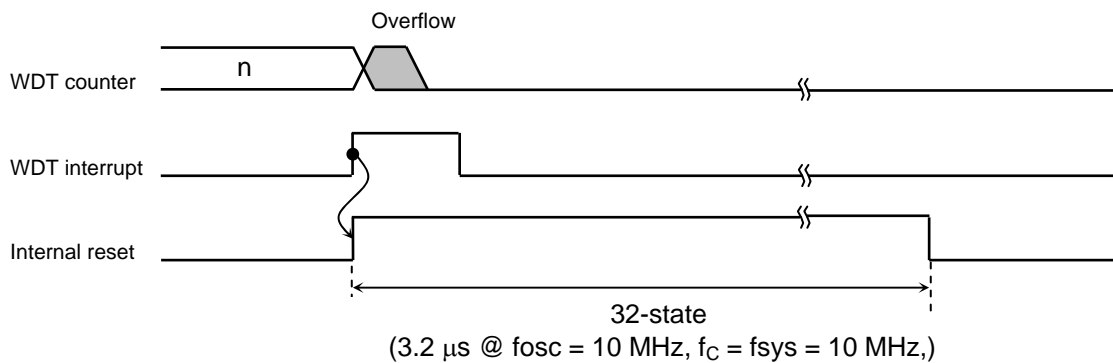


Fig. 10-3 Reset Mode

## 10.3 Control Registers

The watchdog timer (WDT) is controlled by two control registers WDMOD and WDCR.

### 10.3.1 Watchdog Timer Mode Register (WDMOD)

#### 1. Enabling/disabling the watchdog timer <WDTE>

When resetting, WDMOD <WDTE> is initialized to "1" and the watchdog timer is enabled.

To disable the watchdog timer, this bit must be set to "0" and, at the same time, the disable code (B1H) must be written to the WDCR register. This dual setting is intended to minimize the probability that the watchdog timer may inadvertently be disabled if a runaway occurs.

To change the status of the watchdog timer from "disable" to "enable," set the <WDTE> bit to "1".

#### 2. Specifying the detection time of the watchdog timer <WDTP2: 0>

This is a 3-bit register for specifying the watchdog timer interrupt time for runaway detection. When a reset is effected, this register is initialized to WDMOD <WDTP2: 0> = "000." Fig. 10-4 shows the detection time of the watchdog timer.

#### 3. Enabling/disabling the watchdog timer in IDLE mode <I2WDT>

Enabling/disabling the watchdog timer in IDLE mode is controlled by this bit. Writing "0" to this bit enables the watchdog timer and writing "1" to this bit disables the watchdog timer in IDLE mode.

#### 4. Watchdog timer out reset connection <RESCR>

Setting this bit to "1" enables the watch dog timer to be reset when a runaway is detected. Since a reset initializes this bit to "1," a counter overflow causes a reset.

### 10.3.2 Watchdog Timer Control Register (WDCR)

This is a register for disabling the watchdog timer function and controlling the clearing function of the binary counter.

- Disabling control

By writing the disable code (B1H) to this WDCR register after setting WDMOD <WDTE> to "0," the watchdog timer can be disabled.

WDMOD	← 0 - - - - -	Clears WDTE to "0."
WDCR	← 1 0 1 1 0 0 0 1	Writes the disable code (B1H).

- Enabling control

Set WDMOD <WDTE> to "1".

- Watchdog timer clearing control

Writing the clear code (4EH) to the WDCR register clears the binary counter and allows it to resume counting.

WDCR	← 0 1 0 0 1 1 1 0	Writes the clear code (4EH)
------	-------------------	-----------------------------

**(Note) Writing the disable code (B1H) clears the binary counter.**

Watchdog Timer Mode Register

WDMOD  
(0x4004\_0000)

	7	6	5	4	3	2	1	0
bit Symbol	WDTE	WDTP2	WDTP1	WDTP0		I2WDT	RESCR	
Read/Write	R/W	R/W			R	R/W		R/W
After reset	1	0	0	0		0	1	0
Function	WDT control 1: enable	Selects WDT detection time 000: $2^{16}/f_{SYS}$ 001: $2^{18}/f_{SYS}$ 010: $2^{20}/f_{SYS}$ 011: $2^{22}/f_{SYS}$ 100: $2^{24}/f_{SYS}$ 101: $2^{26}/f_{SYS}$ 110: Setting prohibited 111: Setting prohibited			"0" is read.	IDLE 0: Stop 1: Start	0: Generates NMI interrupt 1: Generates reset	Write "0."

Watchdog timer out control

0	Generates NMI interrupt
1	Generates reset

Detection time of watchdog timer

@  $f_c = 80 \text{ MHz}$

SYSCR1 clock gear value <GEAR2:0>	Detection time of watchdog timer					
	WDMOD<WDTP2:0>					
	000	001	010	011	100	101
000 (fc)	0.82 ms	3.28 ms	13.11 ms	52.43 ms	209.72 ms	838.86 ms
100 (fc/2)	1.64 ms	6.55 ms	26.21 ms	104.86 ms	419.43 ms	1.68 s
101 (fc/4)	3.28 ms	13.11 ms	52.43 ms	209.72 ms	838.86 ms	3.36 s
110 (fc/8)	6.55 ms	26.21 ms	104.86 ms	419.43 ms	1.68 s	6.71 s
111 (fc/16)	13.11 ms	52.43 ms	209.72 ms	838.86 ms	3.36 s	13.42 s

Enable/disable control of the watchdog timer

0	Disable
1	Enable

Watchdog Timer Control Register

WDCR  
(0x4004\_0004)

	7	6	5	4	3	2	1	0
bit Symbol	-							
Read/Write	W							
After reset	-							
Function	B1H : WDT disable code 4EH : WDT clear code							

Disable & clear of WDT

B1H	WDT disable code
4EH	WDT clear code
Others	-

Fig. 10-4 Watchdog Timer Registers

## 10.4 Operation

The watchdog timer generates the  $\overline{\text{INTWDT}}$  interrupt or an internal reset after a lapse of the detection time specified by the WDMOD <WDTP2: 0> register. Before generating the  $\overline{\text{INTWDT}}$  interrupt or an internal reset, the binary counter for the watchdog timer must be cleared to "0" using software (instruction). If the CPU malfunctions (runaways) due to noise or other disturbances and cannot execute the instruction to clear the binary counter, the binary counter overflows and the non-maskable interrupt by the  $\overline{\text{INTWDT}}$  interrupt or an internal reset is generated. The CPU is able to recognize the occurrence of a malfunction (runaway) by identifying the non-maskable interrupt and to restore the faulty condition to normal by using a malfunction (runaway) countermeasure program.

The watchdog timer begins operation immediately after a reset is cleared.

In STOP mode, the watchdog timer is reset and in an idle state. In IDLE mode, its operation depends on the WDMOD <I2WDT> setting. Before putting it in IDLE mode, WDMOD <I2WDT> must be set to an appropriate setting, as required.

Example:

1. To clear the binary counter

```

      7 6 5 4 3 2 1 0
WDCR ← 0 1 0 0 1 1 1 0   Writes the clear code (4EH)

```

2. To set the detection time of the watchdog timer to  $2^{18}/f_{\text{SYS}}$ .

```

      7 6 5 4 3 2 1 0
WDMOD ← 1 0 1 - - - - -

```

3. To disable the watchdog timer.

```

      7 6 5 4 3 2 1 0
WDMOD ← 0 - - - - - - -   Clears WDTE to "0"
WDCR ← 1 0 1 1 0 0 0 1   Writes the disable code (B1H)

```

**(Note 1) The counter of the watchdog timer stops at the debug mode.**

# 11. Oscillation Frequency Detector (OFD)

## 11.1 Configuration

The oscillation frequency detector generates a reset for I/O if the oscillation of high frequency for CPU clock exceeds the detection frequency range.

The oscillation frequency detection is controlled by CLKSCR1, CLKSCR2 registers and the detection frequency range is specified by CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLLOFF/CLKSMXPLLON which are the detection frequency setting registers. The lower detection frequency is specified by CLKSMNPLLOFF/CLKSMNPLLON registers and the higher detection frequency is specified by CLKSMXPLLOFF/CLKSMXPLLON registers. An initial value of detection frequency is shown in Figure 11-1.

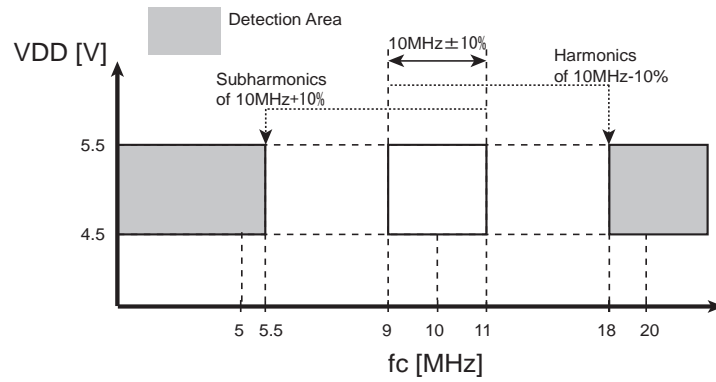
When the oscillation frequency detection is enabled, writing to CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLLOFF/CLKSMXPLLON registers is disabled. Therefore, the setting the detection frequency to these registers should be done when the oscillation frequency detection is disabled. And writing to CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLLOFF/CLKSMXPLLON registers is controlled by CLKSCR1 register. To write CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLLOFF/CLKSMXPLLON registers, the write enable code "0xF9" should be set to CLKSCR1 beforehand. To enable the oscillation frequency detector, set "0xE4" to CLKSCR2 after setting "0xF9" to CLKSCR1. Since the oscillation frequency detection is disabled after an external reset input, write "0xF9" to CLKSCR1 and write "0xE4" to CLKSCR2 register to enable its function.

When the TMPM370 detects the out of frequency by lower and higher detection frequency setting registers, all I/Os become high impedance by reset. In case of PLOFF, CLKSMNPLLOFF and CLKSMXPLLOFF registers are valid for detection and the setting value of CLKSMNPLLON/CLKSMXPLLON registers are ignored. In case of PLLON, CLKSMNPLLON and CLKSMXPLLON registers are valid for detection and the setting value of CLKSMNPLLOFF/CLKSMXPLLOFF registers are ignored. By the oscillation frequency detection reset, all I/Os except power supply pins, RESET, X1 and X2 become high impedance. If oscillation frequency detection reset is generated by detecting the stopping of high frequency, the internal circuitries such as registers hold the condition at the timing of oscillation stop. To initialize these internal circuitries, an external re-starting of oscillation is needed.

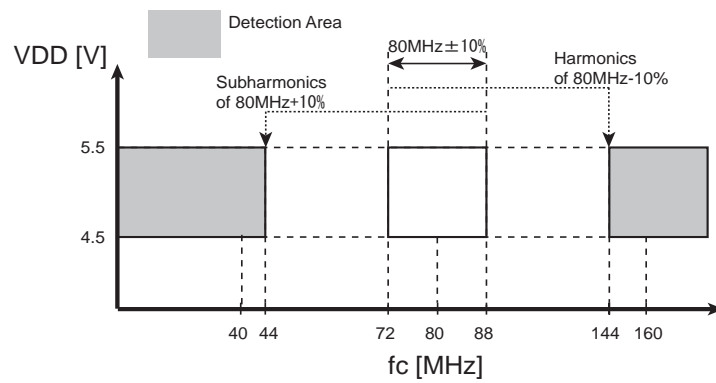
Since all registers for oscillation frequency detector (CLKSCR1/CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLLOFF/CLKSMXPLLON) are not initialized by the reset generated from oscillation frequency detector, the detection of oscillation is keeps its function during the reset period of oscillation frequency detection. Therefore, if the oscillation frequency detection reset occurs, the reset is not released unless the CPU clock resumes its normal frequency.

Note 1: The oscillation frequency detection reset is available only in NORMAL and IDLE modes. In STOP mode, the oscillation frequency detection reset is disabled automatically.

Note 2: CLKSMNPLLOFF/CLKSMXPLLOFF and CLKSMNPLLON/CLKSMXPLLON are automatically switched over by the setting of PLLON.



(a) In case of PLLOFF



(b) In case of PLLON

Figure 11-1 Detection frequency range (Initial value)

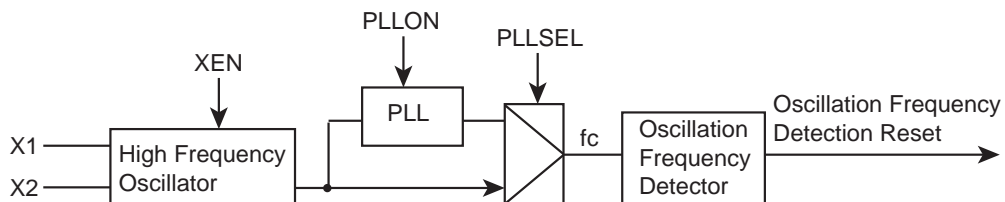


Figure 11-2 Oscillation Frequency Detector

## 11.2 Control

The oscillation frequency detection is controlled by oscillation frequency detection control register 2 (CLKSCR2). The detection frequency is specified by lower/higher detection frequency setting registers (CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPLLON). Writing to CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLOFF/CLKSMXPLLON/CLKSMX is controlled by oscillation frequency control register 1 (CLKSCR1).

### Oscillation frequency detection control register 1

	31-8								
CLKSCR1	Bit Symbol	-							
(0x4004_0800)	Read/Write	R							
	After reset	0							
		7	6	5	4	3	2	1	0
	Bit Symbol	CLKWEN7	CLKWEN6	CLKWEN5	CLKWEN4	CLKWEN3	CLKWEN2	CLKWEN1	CLKWEN0
	Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	1	1	0
	Function	0x06: Disabling of writing to CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLOFF/CLKSMXPLLON (Write disable code) 0xF9: Enabling of writing to CLKSCR2/CLKSMNPLLOFF/CLKSMNPLLON/CLKSMXPLOFF/CLKSMXPLLON (Write enable code) Others: Reserved (Note 1)							

Note 1: Only "0x06" and "0xF9" is valid to CLKSCR1. If other value than "0x06" and "0xF9" is written to CLKSCR1, "0x06" is written to CLKSCR1 automatically.

Note 2: CLKSCR1 is not initialized by an internal factor reset including oscillation frequency detection reset. To initialize this registers, set the RESET pin (external factor reset) to the low level.

### Oscillation frequency detection control register 2

	31-8								
CLKSCR2	Bit Symbol	-							
(0x4004_0804)	Read/Write	R							
	After reset	0							
		7	6	5	4	3	2	1	0
	Bit Symbol	CLKSEN7	CLKSEN6	CLKSEN5	CLKSEN4	CLKSEN3	CLKSEN2	CLKSEN1	CLKSEN0
	Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	0x00: Disabling of oscillation frequency detection 0xE4: Enabling of oscillation frequency detection Others: Reserved (Note 1)							

Note 1: Only "0x00" and "0xE4" is valid to CLKSCR2. Writing other value than "0x00" and "0xE4" to CLKSCR2 is ignored.

Note 2: Writing to CLKSCR2 is protected by setting "0x06" to CLKSCR1 but reading from CLKSCR2 is always enabled without setting of CLKSCR1.

Note 3: CLKSCR2 is not initialized by an internal factor reset including oscillation frequency detection reset. To initialize this registers, set the RESET pin (external factor reset) to the low level.



## Lower detection frequency setting register (In case of PLL OFF)

	31-9						8	
CLKSMNPLLOFF (0x4004_0808)	Bit Symbol						CLKSMNPLLOFF	
	Read/Write						R/W	
	After reset						0	
	7	6	5	4	3	2	1	0
	Bit Symbol							
	CLKSMNPLLOFF							
	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	0	0	0	1	1	1	1	1

## Lower detection frequency setting register (In case of PLL ON)

	31-9						8	
CLKSMNPLLON (0x4004_080C)	Bit Symbol						CLKSMNPLLON	
	Read/Write						R/W	
	After reset						0	
	7	6	5	4	3	2	1	0
	Bit Symbol							
	CLKSMNPLLON							
	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	1	1	1	1	0	0	0	1

## Higher detection frequency setting register (In case of PLL OFF)

	31-9						8	
CLKSMXPLOFF (0x4004_0810)	Bit Symbol						CLKSMXPLOFF	
	Read/Write						R/W	
	After reset						0	
	7	6	5	4	3	2	1	0
	Bit Symbol							
	CLKSMXPLOFF							
	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	0	0	1	1	0	1	1	1

## Higher detection frequency setting register (In case of PLL ON)

	31-9						8	
CLKSMXPPLON (0x4004_0814)	Bit Symbol						CLKSMXPPLON	
	Read/Write						R/W	
	After reset						0	
	7	6	5	4	3	2	1	0
	Bit Symbol							
	CLKSMXPPLON							
	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	1	1	0	0	0	0	0	0

Note 1: CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPPLON can not be written when the oscillation frequency detection circuit is enabled (CLKSCR2="0xE4") or writing is disabled with CLKSCR1="0x06". An attempt to write CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPPLON can not complete a write operation.

Note 2: Writing to CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPPLON is protected by setting "0x06" to CLKSCR1 but reading from CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPPLON is always enabled without setting of CLKSCR1.

Note 3: Specify an appropriate value to CLKSMNPLLOFF and CLKSMXPLOFF depending on the clock frequency to be used under the condition of CLKSMNPLLOFF < CLKSMXPLOFF. For how to calculate the value, refer to " 11.3.2 Setting the Lower and Higher Frequency for Detection ".

Note 4: Specify an appropriate value to CLKSMNPLLON and CLKSMXPLLON depending on the clock frequency to be used under the condition of CLKSMNPLLON<CLKSMXPLLON. For how to calculate the value, refer to " 11.3.2 Setting the Lower and Higher Frequency for Detection ".

Note 5: CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLOFF and CLKSMXPLLON are not initialized by an internal factor reset including oscillation frequency detection reset. To initialize these registers, set the RESET pin (external factor reset) to the low level.

Note 6: CLKSMNPLLOFF/CLKSMXPLOFF and CLKSMNPLLON/CLKSMXPLLON are automatically switched over by the setting of PLLON.

### 11.3 Function

#### 11.3.1 Enabling and Disabling the Oscillation Frequency Detection

Writing "0xE4" to CLKSCR2 with CLKSCR1="0xF9" enables the oscillation frequency detection, and writing "0x00" to CLKSCR2 with CLKSCR1="0xF9" disables the oscillation frequency detection.

Setting "0xF9" to CLKSCR1 enables writing to CLKSCR2 and setting "0x06" to CLKSCR1 disables writing to CLKSCR2. Reading from CLKSCR2 is always enabled without setting of CLKSCR1. CLKSCR1 is initialized to "0x06" by external reset and CLKSCR2 is initialized to "0x00" by external reset. However, CLKSCR1 and CLKSCR2 are not initialized by internal reset which are SYSRESETREQ reset, watchdog timer reset and oscillation frequency detection reset.

Note: After writing data to CLKSCR2, set "0x06" to CLKSCR1 to protect CLKSCR2 register.

When STOP mode is executed with CLKSCR2=0xE4, the oscillation frequency detection is automatically disabled. After releasing STOP and warming up period, the oscillation frequency detection is enabled. The oscillation frequency detection is available only in NORMAL and IDLE mode. Table 11-1 shows the availability of oscillation frequency detector.

Table 11-1 Availability of oscillation frequency detector

Operating Mode	Oscillation Frequency Detection (CLKSCR2=0xE4)	All I/Os condition after Oscillation Frequency Detection RESET (Except power supply, RESET, X1, X2 pins)
NORMAL	Available	High impedance
IDLE	Available	High impedance
STOP (Including warming up period)	Oscillation Frequency Detection is disabled automatically.	
RESET by oscillation frequency detection reset	Available	High impedance
RESET by internal reset (Note 1)	Available	High impedance
RESET by external reset	Disable	-

Note 1: Internal reset; Watchdog timer reset, SYSRESETREQ reset

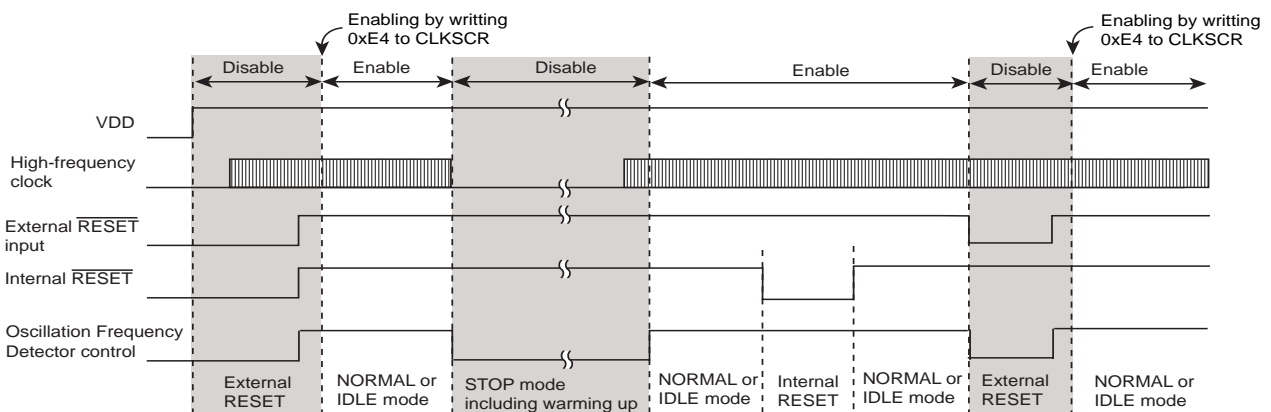


Figure 11-3 Availability of Oscillation Frequency Detection

### 11.3.2 Setting the Lower and Higher Frequency for Detection

The detection frequency is specified by CLKSMNPLLOFF, CLKSMNPLLON, CLKSMXPLLOFF and CLKSMXPLLON registers. The relation between the setting value to these registers and the detection frequency is shown in Table 11-2.

Table 11-2 High frequency and Setting value for detection frequency

High frequency	Range	Detection frequency range [MHz]	Non detection frequency range [MHz]	Setting value
8MHz (PLL OFF)	Lower	≤ 4	≥ 7.2	CLKSMNPLLOFF 25
	Upper	≥ 16	≤ 8.8	CLKSMXPLLOFF 44
10MHz (PLL OFF)	Lower	≤ 5	≥ 9	CLKSMNPLLOFF 31
	Upper	≥ 20	≤ 11	CLKSMXPLLOFF 55
64MHz (PLL ON)	Lower	≤ 32	≥ 57.6	CLKSMNPLLON 193
	Upper	≥ 128	≤ 70.4	CLKSMXPLLON 358
80MHz (PLL ON)	Lower	≤ 40	≥ 72	CLKSMNPLLON 241
	Upper	≥ 160	≤ 88	CLKSMXPLLON 448

### 11.3.3 Oscillation Frequency Detection Reset

If the TMPM370 detects lower frequency specified by CLKSMNPLLOFF/CLKSMNPLLON or higher frequency specified by CLKSMXPLLOFF/CLKSMXPLLON, the oscillation frequency detector outputs a reset signal for all I/Os.

a. When the high frequency oscillation becomes abnormal

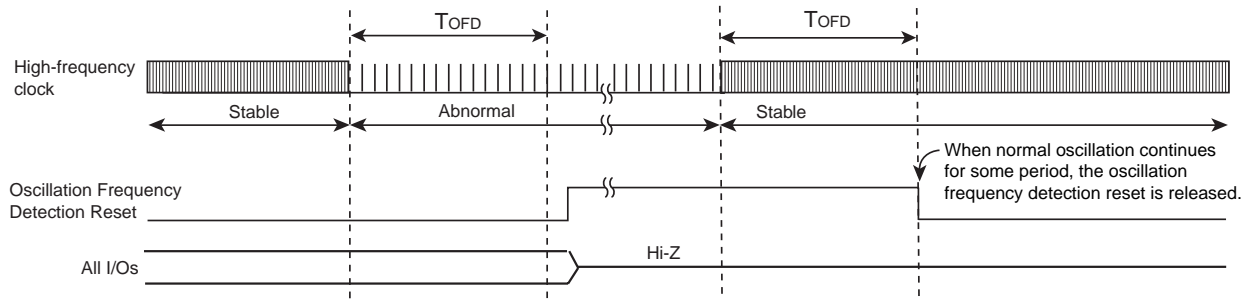
When an abnormal (lower or higher) frequency oscillation continues for some period ( $T_{OFD}$ ), the oscillation frequency detection reset is generated. By oscillation frequency detection reset initializes all I/Os except power supply pins, RESET, X1 and X2 become high impedance.

b. When the high frequency oscillation stops

When the high frequency oscillation stops for some period ( $T_{OFD}$ ), the oscillation frequency detection reset is generated. By oscillation frequency detection reset initializes all I/Os except power supply pins, RESET, X1 and X2 become high impedance. However, since the internal circuitries such as CPU are initialized by a reset signal latched by high frequency, the internal circuitries hold the state at the oscillation frequency detection.

When the oscillation resumes its normal frequency and continues for some period ( $T_{OFD}$ ), the oscillation frequency detection reset is released.

· When the high-frequency clock becomes abnormal



· When the high-frequency clock stops

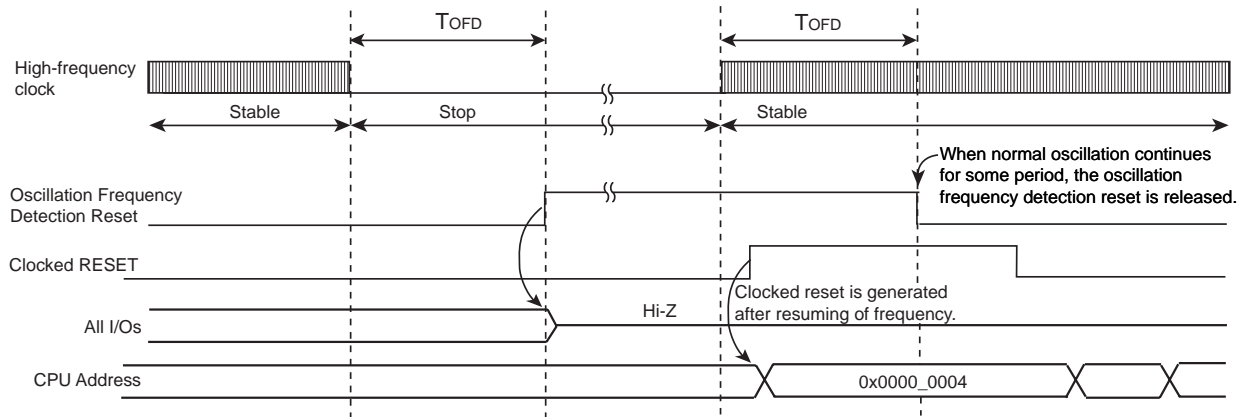


Figure 11-4 Oscillation Frequency Detection Reset Timing



## 12. Power-on Reset Circuit (POR)

The power-on reset circuit generates a reset when the power is turned on. When the supply voltage is lower than the detection voltage of the power-on reset circuit, a power-on reset signal is generated.

### 12.1 Configuration

The power-on reset circuit consists of a reference voltage generation circuit and a comparator.

The supply voltage divided by ladder resistor is compared with the voltage generated by the reference voltage generation circuit by the comparator.

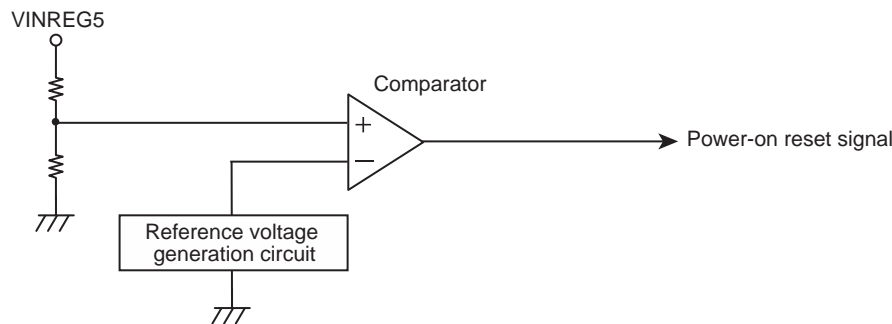


Figure 12-1 Power-on Reset Circuit

### 12.2 Function

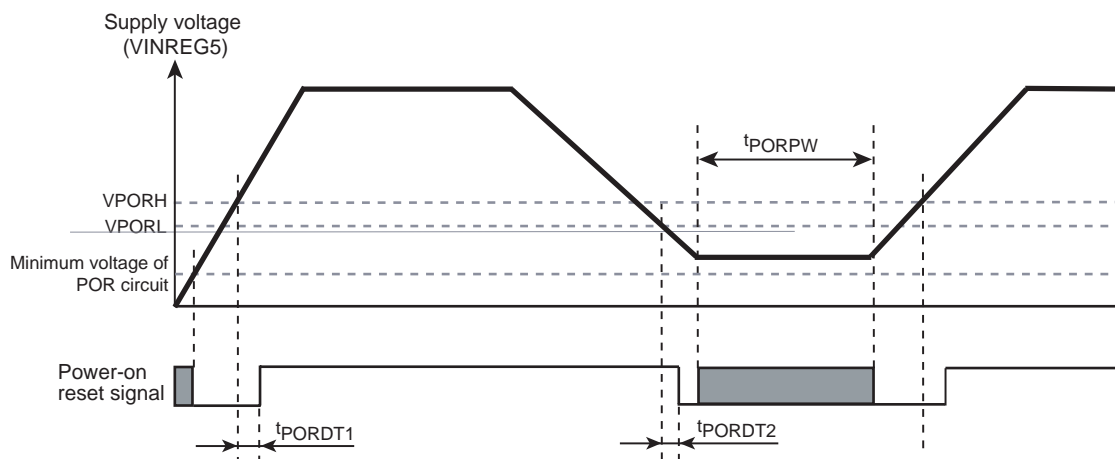
When power supply voltage goes on, if the supply voltage is equal to or lower than the releasing voltage of the power-on reset circuit, a power-on reset signal is generated and if it is higher than the releasing voltage of the power-on reset circuit, a power-on reset signal is released.

When power supply voltage goes down, if the supply voltage is equal to or lower than the detecting voltage of the power-on reset circuit, a power-on reset signal is generated.

During the generating power-on reset, warm-up circuit and CPU are reset.

When the power-on reset signal is released, the warm-up circuit is activated. The reset of the CPU and peripheral circuits is released after the warm-up time that follows reset release has elapsed.

The supply voltage should be increased up to the operating range during the period of warm-up. If not, the TMPM370 cannot operate properly.



Note 1: The power-on reset circuit may operate improperly, depending on fluctuations in the supply voltage (VINREG5). Refer to the electrical characteristics and take them into consideration when designing equipment.

Note 2: If the supply voltage is lower than the minimum voltage of Power-on Reset circuit in which the circuit cannot operate properly, the Power-on Reset signal becomes undefined value.

Figure 12-2 Operation Timing of Power-on Reset

Symbol	Parameter	Min.	Typ.	Max.	Unit
$T_{PORH}$	Power-on Reset releasing time	2.8	3	3.2	V
$T_{PORL}$	Power-on Reset detection time	2.6	2.8	3.0	V
$t_{PORDT1}$	Power-on Reset release response time		T.B.D		ms
$t_{PORDT2}$	Power-on Reset detection response time		T.B.D		ms
$t_{PORPW}$	Power-on Reset minimum pulse width	T.B.D			ms

## 13. Voltage Detection Circuit (VLTD)

The voltage detection circuit detects any decrease in the supply voltage and generates NMI signal.

Note: The voltage detection circuit may operate improperly, depending on fluctuations in the supply voltage (VINREG5). Refer to the electrical characteristics and take them into consideration when designing equipment.

### 13.1 Configuration

The voltage detection circuit consists of a reference voltage generation circuit, a detection voltage level selection circuit, a comparator and control registers.

The supply voltage (VINREG5) is divided by the ladder resistor and input to the detection voltage selection circuit. The detection voltage selection circuit selects a voltage according to the specified detection voltage (VDLVL), and the comparator compares it with the reference voltage. When the comparator detects the selected voltage, NMI signal can be generated.

When the supply voltage (VINREG5) becomes lower than the detection voltage (VDLVL), a voltage detection reset signal is generated.

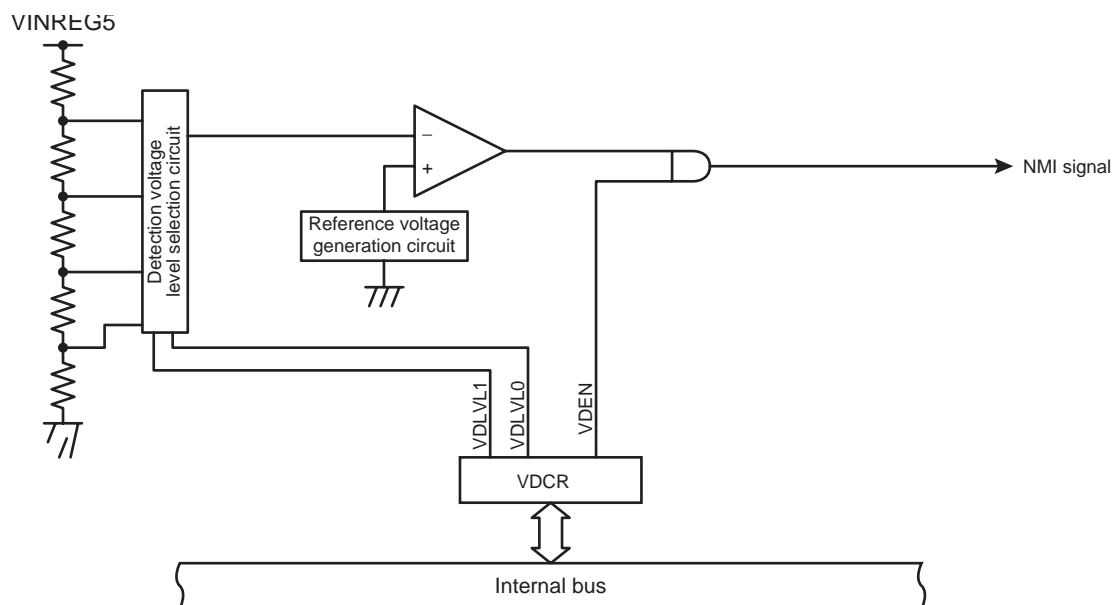


Figure 13-1 Voltage Detection Circuit



## 13.2 Control

The voltage detection circuit is controlled by voltage detection control registers 1 and 2.

### Voltage detection control register

VDCR (0x4004_0900)		7	6	5	4	3	2	1	0
Bit Symbol		-	-	-	-	-	VDLVL1	VDLVL0	VDEN
Read/Write		R	R	R	R	R	R/W	R/W	R/W
After reset		0	0	0	0	0	0	0	0

VDLVL[1:0]	Selection for detection voltage	00:	3.8 +0.1 / -0.1V
		01:	4.1 +0.1 / -0.1V
		10:	4.4 +0.1 / -0.1V
		11:	4.6 +0.1 / -0.1V
V DEN	Enables/disables the operation of voltage detection	0:	Disables the operation of voltage detection
		1:	Enables the operation of voltage detection

Note 1: VDCR is initialized by a power-on reset or an external reset input.

### Voltage detection status register

VDSR (0x4004_0904)		7	6	5	4	3	2	1	0
Bit Symbol		-	-	-	-	-	-	-	VDSR
Read/Write		R	R	R	R	R	R	R	R
After reset		0	0	0	0	0	0	0	0

VDSR	Voltage detection status flag	0:	Power supply voltage is higher than the detection voltage specified by VDLVL.
		1:	Power supply voltage is lower than the detection voltage specified by VDLVL.

### 13.3 Function

The detection voltage can be selected by VDCR<VDLVL>. Enabling/disabling the voltage detection can be programmed by VDCR<VDEN>.

#### 13.3.1 Enabling/disabling the voltage detection operation

Setting VDCR<VDEN> to "1" enables the voltage detection operation. Setting it to "0" disables the operation.

VDCR<VDEN> is cleared to "0" immediately after a power-on reset or a reset by an external reset input is released.

Note: When the supply voltage (VINREG5) is lower than the detection voltage (VDLVL), setting VDCR<VDEN> to "1" generates NMI signal at the time.

#### 13.3.2 Selecting the detection voltage level

Select a detection voltage at VDCR<VDLVL>.

When VDCR<VDEN> = "1", NMI signal is generated when the supply voltage (VINREG5) becomes lower than the detection voltage specified by VDCR<VDLVL>.

VDCR is initialized by a power-on reset or an external reset input only. NMI signal is generated continuously as long as the supply voltage (VINREG5) is lower than the detection voltage specified by VDCR<VDLVL>.

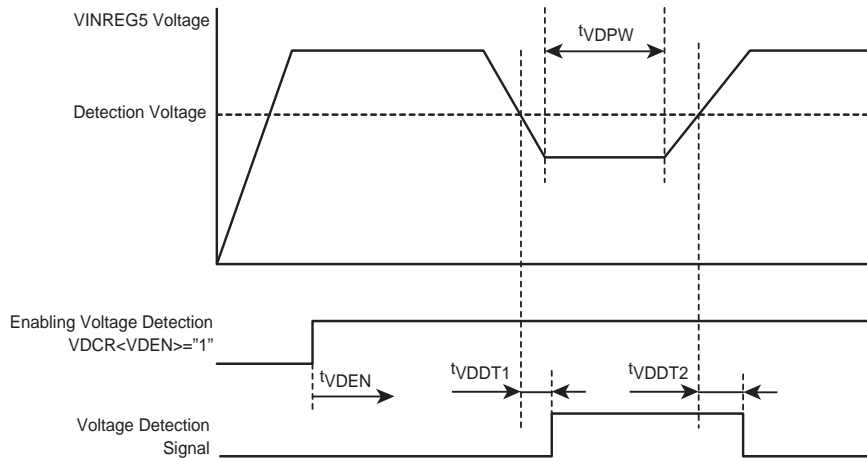


Figure 13-2 Voltage Detection Timing

Symbol	Parameter	Min.	Typ.	Max.	Unit
t <sub>VDEN</sub>	Setup time after enabling voltage detection		T.B.D		ms
t <sub>VDDT1</sub>	Voltage detection response time		T.B.D		ms
t <sub>VDDT2</sub>	Voltage detection releasing time		T.B.D		ms
t <sub>VDPW</sub>	Voltage detection minimum pulse width	T.B.D			ms



## 14. Vector Engine (VE)

### 14.1 Overview

#### 14.1.1 Features

The Vector Engine provides the following features:

- 1) Executes basic tasks for vector control (coordinate conversion, phase conversion and SIN/COS computation).
  - Uses fixed-point format data.
    - No need for software to manage the decimal point alignment.
- 2) Enables interface (output control, trigger generation, input processing) with the motor control circuit (PMD: Programmable Motor Driver) and AD converter (ADC).
  - Converts computation results from fixed-point format to data format usable in the PMD.
  - Generates timing data for interactive operation with the PMD and ADC.
  - Converts AD conversion results into fixed-point format.
- 3) Calculates current, voltage and rotation speed by using normalized values with respect to their maximum values in fixed-point format.
- 4) Implements PI control in current control.
- 5) Implements phase interpolation (integration of rotation speed).

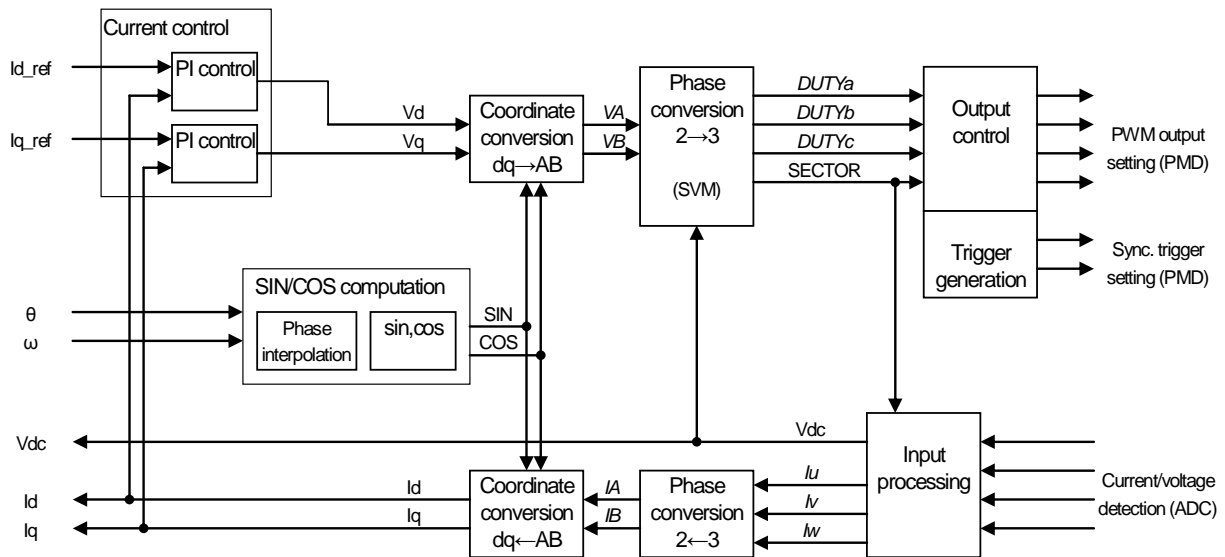


Figure 14-1 Block Diagram of Vector Control

### 14.1.2 Key Specifications

- 1) Space vector conversion is used for 2-phase-to-3-phase conversion. Both 2-phase modulation and 3-phase modulation are supported.
  - 2) ADC sampling timing can be generated for sensorless current detection. Current detection can be performed by the 1-shunt, 3-shunt and 2-sensor methods.
  - 3) In current control, PI control is implemented independently for d-axis and q-axis. It is also possible to directly supply reference voltage information without using current control.
  - 4) SIN/COS computations are performed with approximations using series values.  
Phase information can be directly specified or computed from rotation speed by using phase interpolation.
- \* For using the Vector Engine, the PMD must be set to the VE mode through the mode select register (MODESEL).  
It is also necessary to make appropriate settings in the ADC (enabling trigger and selecting AIN and result registers to be used) for each synchronizing trigger from the PMD.

## 14.2 Configuration

Figure 14-2 shows the configuration of the Vector Engine.

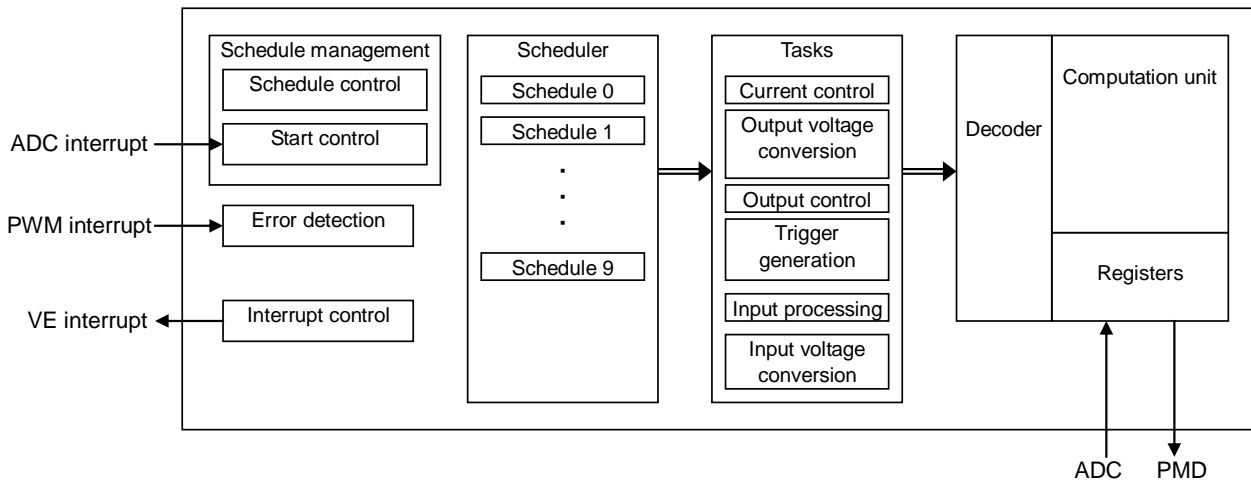


Figure 14-2 Configuration of the Vector Engine

The Vector Engine can control two motors by interacting with two channels of motor control circuit (PMD) and two units of AD converter (ADC). Channel 0 of the Vector Engine controls PMD channel 0, and channel 1 of the Vector Engine controls PMD channel 1.

As shown in Figure 14-3, the Vector Engine allows direct interaction with the PMD and ADC.

When the MODESEL register is set to the VE mode, the PMD channel 0 registers CMPU, CMPV, CMPW, MDOUT, TRGCMP0, TRGCMP1 and TRGSEL are switched to the Vector Engine registers VCMPU0, VCMPV0, VCMPW0, OUTCR0, VTRGCMP00, VTRGCMP10 and VTRGSEL0 respectively. Likewise, the PMD channel 1 registers are switched to Vector Engine registers VCMPU1, VCMPV1, VCMPW1, OUTCR1, VTRGCMP01, VTRGCMP11 and VTRGSEL1. In this case, these registers can only be controlled from the Vector Engine, and cannot be written from the PMD. Other PMD registers have no read/write restrictions.

The ADC unit A registers ADREG0, ADREG1, ADREG2, ADREG3, UVWIS0, UVWIS1, UVWIS2 and UVWIS3 are read into the Vector Engine as the Vector Engine registers ADREG0A, ADREG1A, ADREG2A, ADREG3A, PHNUM0A, PNNUM1A, PHNUM2A and PHNUM3A respectively. (These registers cannot be accessed from the CPU.) Likewise, the ADC unit B registers are read into the Vector Engine as the Vector Engine registers ADREG0B, ADREG1B, ADREG2B, ADREG3B, PHNUM0B, PNNUM1B, PHNUM2B and PHNUM3B. (These registers cannot be accessed from the CPU.) These ADC registers can be written and read from the ADC.

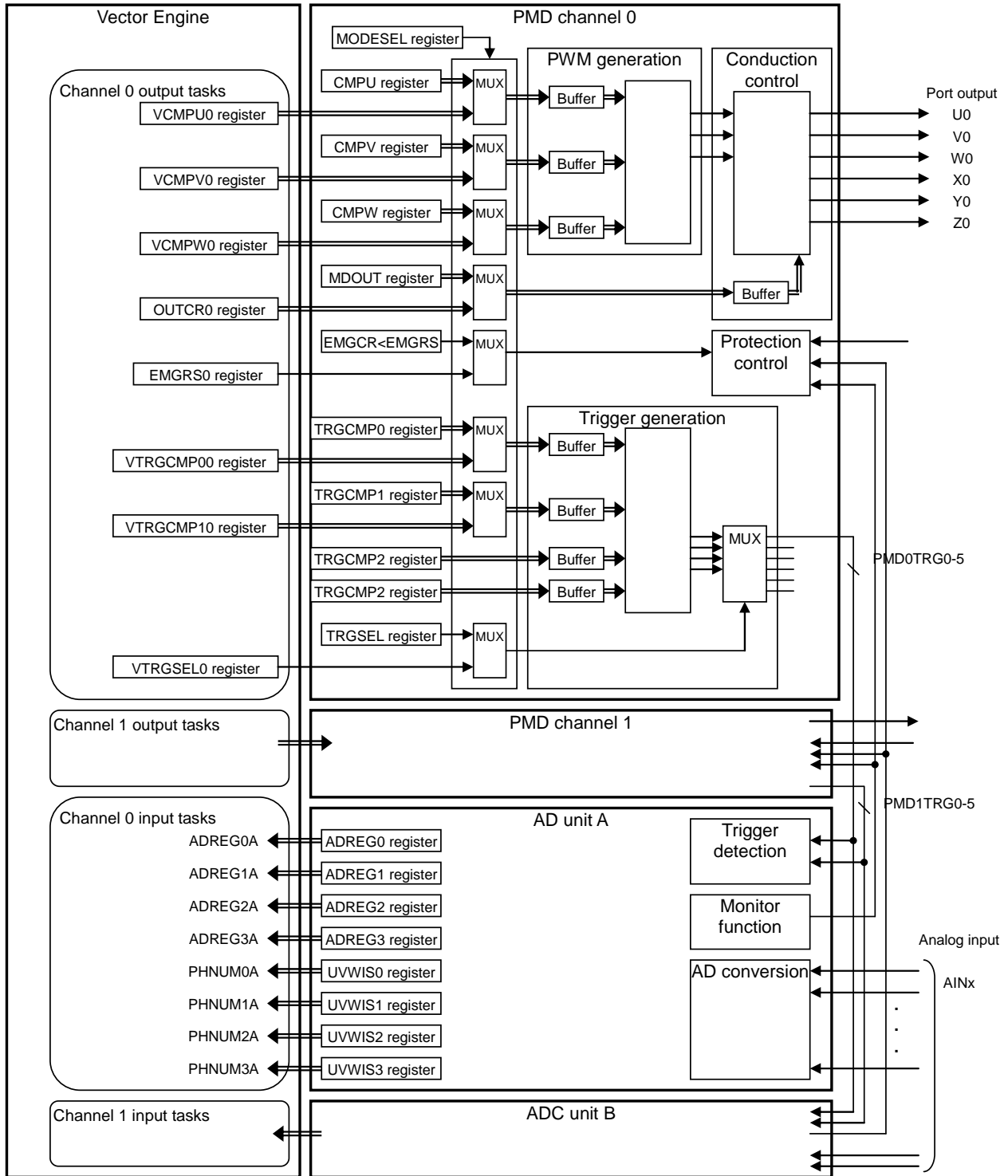


Figure 14-3 Interaction among Vector Engine, PMD and ADC

### 14.3 List of Registers

The Vector Engine registers are divided into the following three types:

VE control registers : Vector Engine control registers and temporary registers

Common registers : Registers common to both channels

Channel-specific registers : Computation data and control registers for each channel

Table 14-1 List of Registers (1) – VE Control Registers

Address	Register Name	Channel	Description	Read/Write
0x4005-0000	VEEN	-	VE enable/disable	R/W
0x4005-0004	CPURUNTRG	-	CPU start trigger selection	W
0x4005-0008	TASKAPP	-	Task selection	R/W
0x4005-000C	ACTSCH	-	Operation schedule selection	R/W
0x4005-0010	REPTIME	-	Schedule repeat count	R/W
0x4005-0014	TRGMODE	-	Start trigger mode	R/W
0x4005-0018	ERRINTEN	-	Error interrupt enable/disable	R/W
0x4005-001C	COMPEND	-	VE forced termination	W
0x4005-0020	ERRDET	-	Error detection	R
0x4005-0024	SCHTASKRUN	-	Schedule executing flag/executing task	R
0x4005-0028	-	-	Reserved	R
0x4005-002C	TMPREG0	-	Temporary register	R/W
0x4005-0030	TMPREG1	-	Temporary register	R/W
0x4005-0034	TMPREG2	-	Temporary register	R/W
0x4005-0038	TMPREG3	-	Temporary register	R/W
0x4005-003C	TMPREG4	-	Temporary register	R/W
0x4005-0040	TMPREG5	-	Temporary register	R/W
0x4005-01BC	-	-	Reserved	R

Table 14-2 List of Registers (2) – Common Registers

Address	Register Name	Channel	Description	Read/Write
0x4005-0174	—	Common	Reserved	R/W
0x4005-0178	TADC	Common	ADC conversion time (based on PWM clock)	R/W



Table 14-3 List of Registers (3) – Channel-Specific Registers for Channel 0

Address	Register Name	Channel	Description	Read/Write
0x4005-0044	MCTLF0	0	Status flags	R/W
0x4005-0048	MODE0	0	Task control mode	R/W
0x4005-004C	FMODE0	0	Flow control	R/W
0x4005-0050	TPWM0	0	PWM period rate (PWM period [s] × maximum speed <sup>*1</sup> × 2 <sup>16</sup> )	R/W
0x4005-0054	OMEGA0	0	Rotation speed (speed [Hz] ÷ maximum speed *1 <sup>*1</sup> × 2 <sup>15</sup> )	R/W
0x4005-0058	THETA0	0	Motor phase (motor phase [deg]/360 × 2 <sup>16</sup> )	R/W
0x4005-005C	IDREF0	0	d-axis reference value (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>15</sup> )	R/W
0x4005-0060	IQREF0	0	q-axis reference value (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>15</sup> )	R/W
0x4005-0064	VD0	0	d-axis voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>31</sup> )	R/W
0x4005-0068	VQ0	0	q-axis voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>31</sup> )	R/W
0x4005-006C	CIDKI0	0	Integral coefficient for PI control of d-axis	R/W
0x4005-0070	CIDKP0	0	Proportional coefficient for PI control of d-axis	R/W
0x4005-0074	CIQKI0	0	Integral coefficient for PI control of q-axis	R/W
0x4005-0078	CIQKP0	0	Proportional coefficient for PI control of q-axis	R/W
0x4005-007C	VDIH0	0	Upper 32 bits of integral term (VDI ) of d-axis voltage	R/W
0x4005-0080	VDLH0	0	Lower 32 bits of integral term (VDI) of d-axis voltage	R/W
0x4005-0084	VQIH0	0	Upper 32 bits of integral term (VQI) of q-axis voltage	R/W
0x4005-0088	VQLH0	0	Lower 32 bits of integral term (VQI) of q-axis voltage	R/W
0x4005-008C	FPWMCHG0	0	Switching speed (for 2-phase modulation and shift PWM)	R/W
0x4005-0090	MDPRD0	0	PWM period (to be set identically with PMD's PWM period)	R/W
0x4005-0094	MINPLS0	0	Minimum pulse width	R/W
0x4005-0098	TRGCRC0	0	Synchronizing trigger correction value	R/W
0x4005-009C	—	0	Reserved	R/W
0x4005-00A0	COS0	0	Cosine value at THETA for output conversion (Q15 data)	R/W
0x4005-00A4	SIN0	0	Sine value at THETA for output conversion (Q15 data)	R/W
0x4005-00A8	COSM0	0	Previous cosine value for input processing (Q15 data)	R/W
0x4005-00AC	SINM0	0	Previous sine value for input processing (Q15 data)	R/W
0x4005-00B0	SECTOR0	0	Sector information (0-11)	R/W
0x4005-00B4	SECTORM0	0	Previous sector information for input processing (0-11)	R/W
0x4005-00B8	IA00	0	AD conversion result of a-phase zero-current <sup>*4</sup>	R/W
0x4005-00BC	IB00	0	AD conversion result of b-phase zero-current <sup>*4</sup>	R/W
0x4005-00C0	IC00	0	AD conversion result of c-phase zero-current <sup>*4</sup>	R/W
0x4005-00C4	IAADC0	0	AD conversion result of a-phase current <sup>*4</sup>	R/W
0x4005-00C8	IBADC0	0	AD conversion result of b-phase current <sup>*4</sup>	R/W
0x4005-00CC	ICADC0	0	AD conversion result of c-phase current <sup>*4</sup>	R/W
0x4005-00D0	VDC0	0	DC supply voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>15</sup> )	R/W
0x4005-00D4	ID0	0	d-axis current (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>31</sup> )	R/W
0x4005-00D8	IQ0	0	q-axis current (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>31</sup> )	R/W
0x4005-017C	VCMPU0	0	PMD control: CMPU setting	R/W
0x4005-0180	VCMPV0	0	PMD control: CMPV setting	R/W
0x4005-0184	VCMPW0	0	PMD control: CMPW setting	R/W
0x4005-0188	OUTCR0	0	PMD control: Output control (MDOUT)	R/W
0x4005-018C	VTRGCMP00	0	PMD control: TRGCMP0 setting	R/W
0x4005-0190	VTRGCMP10	0	PMD control: TRGCMP1 setting	R/W
0x4005-0194	VTRGSEL0	0	PMD control: Trigger selection	R/W
0x4005-0198	EMGRS0	0	PMD control: EMG return (EMGCR[EMGRS])	W

\*1) Maximum speed: Maximum rotation speed [Hz] that can be controlled or operated

\*2) Maximum current: Phase current value [A] that results in 0x7FF0 after AD conversion and zero-level correction

\*3) Maximum voltage: Supply voltage (VDC) value [V] that results in 0xFFFF0 after AD conversion

\*4) AD conversion results are stored in the upper 12 bits of each 16-bit register.

Table 14-4 List of Registers (4) – Channel-Specific Registers for Channel 1

Address	Register Name	Channel	Description	Read/Write
0x4005-00DC	MCTLF1	1	Status flags	R/W
0x4005-00E0	MODE1	1	Task control mode	R/W
0x4005-00E4	FMODE1	1	Flow control	R/W
0x4005-00E8	TPWM1	1	PWM period rate (PWM period [s] × maximum speed <sup>*1</sup> × 2 <sup>16</sup> )	R/W
0x4005-00EC	OMEGA1	1	Rotation speed (speed [Hz] ÷ maximum speed <sup>*1</sup> × 2 <sup>15</sup> )	R/W
0x4005-00F0	THETA1	1	Motor phase (motor phase [deg]/360 × 2 <sup>16</sup> )	R/W
0x4005-00F4	IDREF1	1	d-axis reference value (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>15</sup> )	R/W
0x4005-00F8	IQREF1	1	q-axis reference value (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>15</sup> )	R/W
0x4005-00FC	VD1	1	d-axis voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>31</sup> )	R/W
0x4005-0100	VQ1	1	q-axis voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>31</sup> )	R/W
0x4005-0104	CIDK1	1	Integral coefficient for PI control of d-axis	R/W
0x4005-0108	CIDKP1	1	Proportional coefficient for PI control of d-axis	R/W
0x4005-010C	CIQK1	1	Integral coefficient for PI control of q-axis	R/W
0x4005-0110	CIQKP1	1	Proportional coefficient for PI control of q-axis	R/W
0x4005-0114	VDIH1	1	Upper 32 bits of integral term (VDI) of d-axis voltage	R/W
0x4005-0118	VDILH1	1	Lower 32 bits of integral term (VDI) of d-axis voltage	R/W
0x4005-011C	VQIH1	1	Upper 32 bits of integral term (VQI) of q-axis voltage	R/W
0x4005-0120	VQILH1	1	Lower 32 bits of integral term (VQI) of q-axis voltage	R/W
0x4005-0124	FPWMCHG1	1	Switching speed (for 2-phase modulation and shift PWM)	R/W
0x4005-0128	MDPRD1	1	PWM period (to be set identically with PMD's PWM period)	R/W
0x4005-012C	MINPLS0	1	Minimum pulse width	R/W
0x4005-0130	TRGCRC1	1	Synchronizing trigger correction value	R/W
0x4005-0134	—	1	Reserved	R/W
0x4005-0138	COS1	1	Cosine value at THETA for output conversion (Q15 data)	R/W
0x4005-013C	SIN1	1	Sine value at THETA for output conversion (Q15 data)	R/W
0x4005-0140	COSM1	1	Previous cosine value for input processing (Q15 data)	R/W
0x4005-0144	SINM1	1	Previous sine value for input processing (Q15 data)	R/W
0x4005-0148	SECTOR1	1	Sector information (0-11)	R/W
0x4005-014C	SECTORM1	1	Previous sector information for input processing (0-11)	R/W
0x4005-0150	IAO1	1	AD conversion result of a-phase zero-current <sup>*4</sup>	R/W
0x4005-0154	IBO1	1	AD conversion result of b-phase zero-current <sup>*4</sup>	R/W
0x4005-0158	ICO1	1	AD conversion result of c-phase zero-current <sup>*4</sup>	R/W
0x4005-015C	IAADC1	1	AD conversion result of a-phase current <sup>*4</sup>	R/W
0x4005-0160	IBADC1	1	AD conversion result of b-phase current <sup>*4</sup>	R/W
0x4005-0164	ICADC1	1	AD conversion result of c-phase current <sup>*4</sup>	R/W
0x4005-0168	VDC1	1	DC supply voltage (voltage [V] ÷ maximum voltage <sup>*3</sup> × 2 <sup>15</sup> )	R/W
0x4005-016C	ID1	1	d-axis current (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>31</sup> )	R/W
0x4005-0170	IQ1	1	q-axis current (current [A] ÷ maximum current <sup>*2</sup> × 2 <sup>31</sup> )	R/W
0x4005-019C	VCMPU1	1	PMD control: CMPU setting	R/W
0x4005-01A0	VCMPV1	1	PMD control: CMPV setting	R/W
0x4005-01A4	VCMPW1	1	PMD control: CMPW setting	R/W
0x4005-01A8	OUTCR1	1	PMD control: Output control (MDOUT)	R/W
0x4005-01AC	VTRGCMP01	1	PMD control: TRGCMP0 setting	R/W
0x4005-01B0	VTRGCMP11	1	PMD control: TRGCMP1 setting	R/W
0x4005-01B4	VTRGSEL1	1	PMD control: Trigger selection	R/W
0x4005-01B8	EMGRS1	1	PMD control: EMG return (EMGCR[EMGRS])	W

\*1) Maximum speed: Maximum rotation speed [Hz] that can be controlled or operated

\*2) Maximum current: Phase current value [A] that results in 0x7FF0 after AD conversion and zero-level correction

\*3) Maximum voltage: Supply voltage (VDC) value [V] that results in 0xFFFF after AD conversion

\*4) AD conversion results are stored in the upper 12 bits of each 16-bit register.

## 14.4 Description of Registers

### 14.4.1 VE Control Registers

#### 14.4.1.1 VEEN Register

	31	...				9	8
VEEN (0x4005_0000)	bit Symbol						
	Read/Write						
	After reset						
	Function						
	7	...		3	2	1	0
	bit Symbol				VEIDLEN		VEEN
	Read/Write				R/W		R/W
	After reset				0		0
	Function				Operation in IDLE mode 0: Inactive 1: Active		VE enable 0: Disable 1: Enable

<VEEN> Disables or enables the Vector Engine.

<VEIDLEN> Controls whether or not the clock is supplied to the Vector Engine in IDLE mode.

#### 14.4.1.2 CPURUNTRG Register

	31	...				9	8
CPURUNTRG (0x4005_0004)	bit Symbol						
	Read/Write						
	After reset						
	Function						
	7	...		3	2	1	0
	bit Symbol				VCPURTB		VCPURTA
	Read/Write				W		W
	After reset				0		0
	Function				Channel 1 start command 0: — 1: Start		Channel 0 start command 0: — 1: Start

<VCPURTA> Starts channel 0 by programming.

<VCPURTB> Start channel 1 by programming.

- \* When "1" is written to these bits, it is cleared in the next cycle. These bits always read as 0.
- \* The task to be performed is determined by the settings of the ACTSCH and TASKAPP registers.
- \* If a channel under executing will be restarted, it must be terminated by COMPEND register before a start command executed.

14.4.1.3 TASKAPP Register

	31	...				9	8	
TASKAPP (0x4005_0008)	bit Symbol							
	Read/Write	R						
	After reset	0x000000						
	Function	-						
	7	6	5	4	3	2	1	0
bit Symbol	VTASKB				VTASKA			
Read/Write	R/W				R/W			
After reset	0x0				0x0			
Function	Channel 1 task selection 0x0: Output control 0x1: Trigger control 0x2: Input processing 0x3: Input phase conversion 0x4: Input coordinate axis conversion 0x5: Current control 0x6: SIN/COS computation 0x7: Output coordinate axis conversion 0x8: Output phase conversion 0x9-0xF: -				Channel 0 task selection 0x0: Output control 0x1: Trigger control 0x2: Input processing 0x3: Input phase conversion 0x4: Input coordinate axis conversion 0x5: Current control 0x6: SIN/COS computation 0x7: Output coordinate axis conversion 0x8: Output phase conversion 0x9-0xF: -			

<VTASKA> Specifies the task to be performed when channel 0 is started by programming.  
 <VTASKB> Specifies the task to be performed when channel 1 is started by programming.

\* Only those tasks that are included in schedules can be specified.

14.4.1.4 ACTSCH Register

	31	...				9	8	
ACTSCH (0x4005_000C)	bit Symbol							
	Read/Write	R						
	After reset	0x000000						
	Function	-						
	7	6	5	4	3	2	1	0
bit Symbol	VACTB				VACTA			
Read/Write	R/W				R/W			
After reset	0x0				0x0			
Function	Channel 1 schedule 0x0: Task execution 0x1: Schedule 1 0x4: Schedule 4 0x9: Schedule 9 Other: Reserved				Channel 0 schedule 0x0: Task execution 0x1: Schedule 1 0x4: Schedule 4 0x9: Schedule 9 Other: Reserved			

<VACTA> Specifies a schedule for channel 0.  
 <VACTB> Specifies a schedule for channel 1.

14.4.1.5 REPTIME Register

	31	...				9	8	
REPTIME (0x4005_0010)	bit Symbol							
	Read/Write							
	After reset							
	Function							
	7	6	5	4	3	2	1	0
	bit Symbol				bit Symbol			
	Read/Write				Read/Write			
	After reset				After reset			
	Function				Function			

<VREPA> Specifies the repeat times a schedule is to be executed in channel 0.  
 <VREP B> Specifies the repeat times a schedule is to be executed in channel 1.  
 \* When "0" is set, no schedule is executed.

14.4.1.6 TRGMODE Register

	31	...				9	8	
TRGMODE (0x4005_0014)	bit Symbol							
	Read/Write							
	After reset							
	Function							
	7	6	5	4	3	2	1	0
	bit Symbol				bit Symbol		bit Symbol	
	Read/Write				Read/Write		Read/Write	
	After reset				After reset		After reset	
	Function				Function		Function	

<VTRGA> Specifies the AD conversion end interrupt that triggers input processing in channel 0.  
 <VTRGB> Specifies the AD conversion end interrupt that triggers input processing in channel 1.

14.4.1.7 ERRINTEN Register

ERRINTEN (0x4005_0018)	31	...				9	8
	bit Symbol						
	Read/Write	R					
	After reset	0x000000					
	Function	-					
	7	...		3	2	1	0
bit Symbol					VERRENB	VERRENA	
Read/Write	R				R/W	R/W	
After reset	000000				0	0	
Function	-				Channel 1 error interrupt enable 0: Disable 1: Enable	Channel 0 error interrupt enable 0: Disable 1: Enable	

<VERRENA> Enables or disables the error detection interrupt in channel 0.

<VERRENB> Enables or disables the error detection interrupt in channel 1.

14.4.1.8 COMPEND Register

COMPEND (0x4005_001C)	31	...				9	8
	bit Symbol						
	Read/Write	R					
	After reset	0x000000					
	Function	-					
	7	...		3	2	1	0
bit Symbol					VCENDB	VCENDA	
Read/Write	R				W	W	
After reset	000000				0	0	
Function	-				Channel 1 forced termination 0: - 1: Terminate	Channel 0 forced termination 0: 1: Terminate	

<VCENDA> Forcefully terminates the currently executing schedule in channel 0.

<VCENDB> Forcefully terminates the currently executing schedule in channel 1.

\* When "1" is written to these bits, it is cleared in the next cycle. These bits always read as "0".

14.4.1.9 ERRDET Register

ERRDET (0x4005_0020)	31	...				9	8
	bit Symbol						
	Read/Write	R					
	After reset	0x000000					
	Function	-					
	7	...		3	2	1	0
bit Symbol					VERRDB	VERRDA	
Read/Write	R				R	R	
After reset	000000				0	0	
Function	-				Channel 1 error flag 0: No error detected 1: Error detected		Channel 0 error flag 0: No error detected 1: Error detected

<VERRDA> Channel 0 error flag

<VERRDB> Channel 1 error flag

The error flags are set when a PWM interrupt is detected during execution of a schedule (excluding standby periods waiting for a start trigger).

\* The error flags are cleared by a read of this register.

14.4.1.10 SHTASKRUN Register

SHTASKRUN (0x4005_0024)	31	...				25	24
	bit Symbol						
	Read/Write	R					
	After reset	0x0000					
	Function	-					
	15	...				11	10
bit Symbol							
Read/Write	R						
After reset	000000						
Function	-						
	9	6	5	4	1	0	
bit Symbol	VRTASKB		VRSCHB	VRTASKA		VRSCHA	
Read/Write	R		R	R		R	
After reset	0x0		0	0x0		0	
Function	Task executing in channel 1 0x0: Output control 0x1: Trigger generation 0x2: Input processing 0x3: Input phase conversion 0x4: Input coordinate axis conversion 0x5: Current control 0x6: SIN/COS computation 0x7: Output coordinate axis conversion 0x8: Output phase conversion 0x9-0xF: -		Channel 1 schedule status 0: Not executing 1: Executing	Task executing in channel 0 0x0: Output control 0x1: Trigger generation 0x2: Input processing 0x3: Input phase conversion 0x4: Input coordinate axis conversion 0x5: Current control 0x6: SIN/COS computation 0x7: Output coordinate axis conversion 0x8: Output phase conversion 0x9-0xF: -		Channel 0 schedule status 0: Not executing 1: Executing	

<VRSCHA> Schedule execution status in channel 0

<VRTASKA> Task Number currently executing in channel 0

<VRSCHB> Schedule execution status in channel 1

<VRTASKB> Task Number currently executing in channel 1

## 14.4.1.11 Temporary Registers

		31	...	2	1
TMPREG0 (0x4005_002C)	bit Symbol	TMPREG0			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				
		31	...	2	1
TMPREG1 (0x4005_0030)	bit Symbol	TMPREG1			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				
		31	...	2	1
TMPREG2 (0x4005_0034)	bit Symbol	TMPREG2			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				
		31	...	2	1
TMPREG3 (0x4005_0038)	bit Symbol	TMPREG3			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				
		31	...	2	1
TMPREG4 (0x4005_003C)	bit Symbol	TMPREG4			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				
		31	...	2	1
TMPREG5 (0x4005_0040)	bit Symbol	TMPREG5			
	Read/Write	R/W			
	After reset	0x00000000			
	Function				

<TMPREG0> Temporary register 0

<TMPREG1> Temporary register 1

<TMPREG2> Temporary register 2

<TMPREG3> Temporary register 3

<TMPREG4> Temporary register 4

<TMPREG5> Temporary register 5



14.4.2 Common Registers

14.4.2.1 TADC Register

	31	...	17	16
TADC (0x4005_0178)	bit Symbol			
	Read/Write	R		
	After reset	0x0000		
	Function	-		
	15	...	1	0
bit Symbol	TADC			
Read/Write	R/W			
After reset	0x0000			
Function	ADC conversion time 0x0000-0xFFFF			

<TADC> The value to be set is:

$$\text{ADC conversion time [s]} \div \text{PWM counter clock frequency [s]}$$

- \* This register is effective when the 1-shunt current detection mode is selected and PWM shift is enabled.

### 14.4.3 Channel-Specific Registers

#### 14.4.3.1 MODE Register

	31	...				9	8	
MODE0 (0x4005_0048)	bit Symbol							
	Read/Write							
	R							
MODE1 (0x4005_00E0)	After reset							
	0x000000							
	Function							
	-							
	7	6	5	4	3	2	1	0
	bit Symbol				OCRMD		ZIEN	PVIEN
	Read/Write				R/W		R/W	R/W
	After reset				00		0	0
	Function				Output control 00: Output OFF 01: Output enable 10: - 11: EMG return		Zero-current detection 0: Disable 1: Enable	Phase interpolation 0: Disable 1: Enable

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<PVIEN> Enables or disables phase interpolation.

<ZIEN>:Enables or disables zero-current detection.

<OCRMD> Controls output operation (output OFF, output enable or EMG return).

## 14.4.3.2 FMODE Register

	31	...					17	16
FMODE0 (0x4005_004C)	bit Symbol							
	Read/Write							
	After reset							
FMODE1 (0x4005_00E4)	Function							
	15	14	13	12	11	10	9	8
	bit Symbol						MREGDIS	—
	Read/Write						R/W	R/W
	After reset						0	0
	Function						Keep the previous value of SIN/COS/SECTOR 0: effective 1: no_effective	Reserved
	7	6	5	4	3	2	1	0
	bit Symbol		—	PMDSEL	IDMODE		SPWMEN	C2PEN
	Read/Write		R/W	R/W	R/W		R/W	R/W
	After reset		00	0	00		0	0
	Function		ADC unit 00: Unit A 01: Unit B 10: Unit A,B 11: Unit A,B	Reserved	PMD channel 0: Channel 0 1: Channel 1	Current detection mode 00: 3-shunt 01: 2-sensor 10: 1-shunt 11: 1-shunt	PWM shift enable 0: Disable 1: Enable	Modulation mode 0: 3-phase modulation 1: 2-phase modulation

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<C2PEN>: Selects 3-phase or 2-phase modulation.

<SPWMEN>: Enables or disables PWM shift.

<IDMODE>: Selects the 3-shunt, 2-sensor or 1-shunt current detection mode.

<PMDSEL>: Selects PMD channel 0 or channel 1.

\* Select PMD channel 0 when Vector Engine channel 0 is used .

Select PMD channel 1 when Vector Engine channel 1 is used .

<ADCSEL>: Selects the ADC unit to be used.

\* Select unit A or unit A/unit B when Vector Engine channel 0 is used .

Select unit B or unit A/unit B when Vector Engine channel 1 is used

<MREGDIS>: Keep or Not\_keep the previous value of SIN/COS/SECTOR.

\* In case of no\_effective, SINM=SIN, COSM=COS, SECTORM=SECTOR.

14.4.3.3 TPWM Register

	31	...	17	16
TPWM0 (0x4005_0050)	bit Symbol			
	Read/Write	R		
TPWM1 (0x4005_00E8)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	TPWM		
	Read/Write	R/W		
	After reset	0x0000		
	Function	PWM period rate 0x0000 to 0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<TPWM> Set a PWM period rate (integral factor for phase interpolation) as follows:  
 $PWM\ period\ [s] \times Max\_Hz \times 2^{16}$

\* Max\_Hz: Maximum rotation speed

14.4.3.4 OMEGA Register

	31	...	17	16
OMEGA0 (0x4005_0054)	bit Symbol			
	Read/Write	R		
OMEGA1 (0x4005_00EC)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	OMEGA		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Rotation speed 0x0000 to 0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<OMEGA> Set a rotation speed (16-bit fixed-point data: -1.0 to 1.0) as follows:  
 $Rotation\ speed\ [Hz] \div Max\_Hz \times 2^{15}$

\* Max\_Hz: Maximum rotation speed [Hz]

14.4.3.5 THETA Register

	31	...	17	16
THETA0 (0x4005_0058)	bit Symbol			
	Read/Write	R		
THETA1 (0x4005_00F0)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	THETA		
	Read/Write	R/W		
	After reset	0x0000		
	Function			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<THETA> Set phase data (16-bit fixed-point data: 0.0 to 1.0) as follows:  
 $Phase\ [deg] \div 360 \times 2^{16}$

14.4.3.6 SIN/COS Registers

	31	...	17	16
COS0 (0x4005_00A0)	bit Symbol			
	Read/Write			
	R			
COS1 (0x4005_0138)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	COS			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Cosine value: 0x0000-0xFFFF			
	31	...	17	16
SIN0 (0x4005_00A4)	bit Symbol			
	Read/Write			
	R			
SIN1 (0x4005_013C)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	SIN			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Sine value: 0x0000-0xFFFF			
	31	...	17	16
COSM0 (0x4005_00A8)	bit Symbol			
	Read/Write			
	R			
COSM1 (0x4005_0140)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	COSM			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Cosine value (previous value): 0x0000-0xFFFF			
	31	...	17	16
SINM0 (0x4005_00AC)	bit Symbol			
	Read/Write			
	R			
SINM1 (0x4005_0144)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	SINM			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Sine value (previous value): 0x0000-0xFFFF			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

- <COS> Cosine value based on the THETA value (16-bit fixed-point data: -1.0 to 1.0)
- <SIN> Sine value based on the THETA value (16-bit fixed-point data: -1.0 to 1.0)
- <COSM> Previous value of the COS register
- <SINM> Previous value of the SIN register

14.4.3.7 dq Current Reference Registers

	31	...	17	16
IDREF0 (0x4005_005C)	bit Symbol	IDREF0		
	Read/Write	R		
IDREF1 (0x4005_00F4)	After reset	0x0000		
	Function	—		
	15	...	1	0
	bit Symbol	IDREF		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Reference value of d-axis current: 0x0000 to 0xFFFF		

	31	...	17	16
IQREF0 (0x4005_0060)	bit Symbol	IQREF0		
	Read/Write	R		
IQREF1 (0x4005_00F8)	After reset	0x0000		
	Function	—		
	15	...	1	0
	bit Symbol	IQREF		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Reference value of q-axis current: 0x0000 to 0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<ID\_REF> Reference value of d-axis current (16-bit fixed-point data: -1.0 to 1.0)  
 <IQ\_REF> Reference value of q-axis current (16-bit fixed-point data: -1.0 to 1.0)

The value to be set is:  
 Axis current reference [A] ÷ Max\_I × 2<sup>15</sup>

\* Max\_I: Maximum current [A] that can be detected in the ADC

14.4.3.8 dq Voltage Registers

	31	...	1	0
VD0 (0x4005_0064)	bit Symbol	VD		
	Read/Write	R/W		
VD1 (0x4005_00FC)	After reset	0x00000000		
	Function	d-axis voltage: 0x00000000-0xFFFFFFFF		

	31	...	1	0
VQ0 (0x4005_0068)	bit Symbol	VQ		
	Read/Write	R/W		
VQ1 (0x4005_0100)	After reset	0x00000000		
	Function	q-axis voltage: 0x00000000-0xFFFFFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VD> d-axis voltage (32-bit fixed-point data: -1.0 to 1.0)  
 <VQ> q-axis voltage (32-bit fixed-point data: -1.0 to 1.0)

The value to be set is as follows:  
 Axis voltage ÷ Max\_V × 2<sup>31</sup>

\* Max\_V: Maximum voltage [V] that can be detected in the ADC

14.4.3.9 PI Control Coefficient Registers

	31	...	17	16
CIDKI0 (0x4005_006C)	bit Symbol			
	Read/Write	R		
CIDKI1 (0x4005_0104)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	CIDKI		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Integral coefficient for PI control of d-axis: 0x0000-0xFFFF		
	31	...	17	16
CIDKP0 (0x4005_0070)	bit Symbol			
	Read/Write	R		
CIDKP1 (0x4005_0108)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	CIDKP		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Proportional coefficient for PI control of d-axis: 0x0000-0xFFFF		
	31	...	17	16
CIQKI0 (0x4005_0074)	bit Symbol			
	Read/Write	R		
CIQKI1 (0x4005_010C)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	CIQKI		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Integral coefficient for PI control of q-axis: 0x0000-0xFFFF		
	31	...	17	16
CIQKP0 (0x4005_0078)	bit Symbol			
	Read/Write	R		
CIQKP1 (0x4005_0110)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	CIQKP		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Proportional coefficient for PI control of q-axis: 0x0000-0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

- <CIDKI> Integral coefficient for PI control of d-axis
- <CIDKP> Proportional coefficient for PI control of d-axis
- <CIQKI> Integral coefficient for PI control of q-axis
- <CIQKP> Proportional coefficient for PI control of q-axis

14.4.3.10 PI Control Integral Term Registers

		31	...	1	0
VDIH0 (0x4005_007C)	bit Symbol	VDIH			
	Read/Write	R/W			
VD_H1 (0x4005_0114)	After reset	0x00000000			
	Function	Upper 32 bits of VDI			

		31	...	17	16
VDILH0 (0x4005_0080)	bit Symbol	VDILH			
	Read/Write	R/W			
VDILH1 (0x4005_0118)	After reset	0x0000			
	Function				

		15	...	1	0
	bit Symbol				
	Read/Write	R			
	After reset	0x0000			
	Function	-			

		31	...	1	0
VQIH0 (0x4005_0084)	bit Symbol	VQIH			
	Read/Write	R/W			
VQIH1 (0x4005_011C)	After reset	0x00000000			
	Function				

		31	...	17	16
VQILH0 (0x4005_0088)	bit Symbol	VQILH			
	Read/Write	R/W			
VQILH1 (0x4005_0120)	After reset	0x0000			
	Function				

		15	...	1	0
	bit Symbol				
	Read/Write	R			
	After reset	0x0000			
	Function	-			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VDIH> Upper 32 bits of the integral term (VDI) for PI control of d-axis

<VDILH> Lower 32 bits of the integral term (VDI) for PI control of d-axis (The lower 16 bits are fixed to 0x0000.)

VDI: 64-bit fixed-point data with 63 fractional bits (-1.0 to 1.0)

<VQIH> Upper 32 bits of the integral term (VQI) for PI control of q-axis

<VQILH> Lower 32 bits of the integral term (VQI) for PI control of q-axis (The lower 16 bits are fixed to 0x0000.)

VQI: 64-bit fixed-point data with 63 fractional bits (-1.0 to 1.0)





**14.4.3.13 PWM Period Register**

		31	...	17	16
VMDPRD0 (0x4005_0090)	bit Symbol				
	Read/Write	R			
VMDPRD1 (0x4005_0128)	After reset	0x0000			
	Function	-			
		15	...	1	0
	bit Symbol	VMDPRD			
	Read/Write	R/W			
	After reset	0x0000			
	Function	PWM period			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VMDPRD> PWM period. Set the value of the PMD's MDPRD register.

**14.4.3.14 MINPLS Register**

		31	...	17	16
MINPLS0 (0x4005_0094)	bit Symbol				
	Read/Write	R			
MINPLS1 (0x4005_012C)	After reset	0x0000			
	Function	-			
		15	...	1	0
	bit Symbol	MINPLS			
	Read/Write	R/W			
	After reset	0x0000			
	Function	Minimum disparity of pulse width			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<MINPLS> Set the minimum disparity of pulse width between the duty of VCMPU, VCMPV, VCMPW.

$$\text{Disparity of pulse width [s]} \div \text{PWM counter clock period [s]}$$

14.4.3.15 Sector Registers

		31	...				9	8	
SECTOR0 (0x4005_00B0)	bit Symbol								
	Read/Write	R							
SECTOR1 (0x4005_0148)	After reset	0x000000							
	Function	-							
		7	6	5	4	3	2	1	0
	bit Symbol					SECTOR			
	Read/Write	R				R/W			
	After reset	0x0				0x0			
	Function	-				Sector information 0x0-0xF:			
		31	...				9	8	
SECTORM0 (0x4005_00B4)	bit Symbol								
	Read/Write	R							
SECTORM1 (0x4005_014C)	Function	-							
	After reset	0x000000							
		7	6	5	4	3	2	1	0
	bit Symbol					SECTORM			
	Read/Write	R				R/W			
	After reset	0x0				0x0			
	Function	-				Sector information 0x0-0xF:			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<SECTOR> Sector information. Indicates the rotation position at the time of output by 12 sectors each having 30 degrees.

<SECTORM> Previous sector information. Used in input processing.

14.4.3.16 Zero-Current Registers

	31	...	17	16
IA00 (0x4005_00B8)	bit Symbol			
	Read/Write			
IA01 (0x4005_0150)	After reset			
	Function			
	15	...	1	0
	bit Symbol			
	Read/Write			
	After reset			
	Function			
	31	...	17	16
IB00 (0x4005_00BC)	bit Symbol			
	Read/Write			
IB01 (0x4005_0154)	After reset			
	Function			
	15	...	1	0
	bit Symbol			
	Read/Write			
	After reset			
	Function			
	31	...	17	16
IC00 (0x4005_00C0)	bit Symbol			
	Read/Write			
IC01 (0x4005_0158)	After reset			
	Function			
	15	...	1	0
	bit Symbol			
	Read/Write			
	After reset			
	Function			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

- <IA0> Stores the AD conversion result of U-phase current when the motor is at stop.
- <IB0> Stores the AD conversion result of V-phase current when the motor is at stop
- <IC0> Stores the AD conversion result of W-phase current when the motor is at stop

\* AD conversion results are stored in the 15--4 bits, with the 3--0 bits always "0".

14.4.3.17 Current ADC Result Registers

		31	...	17	16
IAADC0 (0x4005_00C4)	bit Symbol				
	Read/Write	R			
	After reset	0x0000			
	Function	-			
IAADC1 (0x4005_015C)		15	...	1	0
	bit Symbol	IAADC			
	Read/Write	R/W			
	After reset	0x0000			
Function	AD conversion result of U-phase current : 0x0000-0xFFFF				
		31	...	17	16
IBADC0 (0x4005_00C8)	bit Symbol				
	Read/Write	R			
	After reset	0x0000			
	Function	-			
IBADC1 (0x4005_0160)		15	...	1	0
	bit Symbol	IBADC			
	Read/Write	R/W			
	After reset	0x0000			
Function	AD conversion result of V-phase current: 0x0000-0xFFFF				
		31	...	17	16
ICADC0 (0x4005_00CC)	bit Symbol				
	Read/Write	R			
	After reset	0x0000			
	Function	-			
ICADC1 (0x4005_0164)		15	...	1	0
	bit Symbol	ICADC			
	Read/Write	R/W			
	After reset	0x0000			
Function	AD conversion result of W-phase current: 0x0000-0xFFFF				

The upper and lower register names correspond to channel 0 and channel 1 respectively.

- <IAADC> Stores the AD conversion result of U-phase current.
- <IBADC> Stores the AD conversion result of V-phase current.
- <ICADC> Stores the AD conversion result of W-phase current.

\* AD conversion results are stored in the 15--4 bits, with the 3--0 bits always "0".

14.4.3.18 Supply Voltage Register

	31	...	17	16
VDC0 (0x4005_00D0)	bit Symbol			
	Read/Write	R		
VDC1 (0x4005_0168)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	VDC		
	Read/Write	R/W		
	After reset	0x0000		
	Function	Supply voltage: 0x0000-0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VDC> Supply voltage (16-bit fixed-point data: 0 to 1.0)

The actual voltage value is:

$$\text{VDC value} \times \text{Max\_V value} \div 2^{15}$$

\* Max\_V: Maximum voltage that can be detected in the ADC

14.4.3.19 dq Current Registers

	31	...	1	0
ID0 (0x4005_00D4)	bit Symbol	ID		
	Read/Write	R/W		
ID1 (0x4005_016C)	After reset	0x00000000		
	Function	d-axis current: 0x00000000-0xFFFFFFFF		

	31	...	1	0
IQ0 (0x4005_00D8)	bit Symbol	IQ		
	Read/Write	R/W		
IQ1 (0x4005_0170)	After reset	0x00000000		
	Function	q-axis current: 0x00000000-0xFFFFFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<ID> d-axis current (32-bit fixed-point data: -1.0 to 1.0)

<IQ> q-axis current (32-bit fixed-point data: -1.0 to 1.0)

The actual current value is:

$$\text{ID (or IQ) value} \times \text{Max\_I value} \div 2^{31}$$

\* Max\_I: Maximum current that can be detected in the ADC

14.4.3.20 PWM Duty Register

	31	...	17	16
VCMPU0 (0x4005_017C)	bit Symbol			
	Read/Write	R		
VCMPU1 (0x4005_019C)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	VCMPU		
	Read/Write	R/W		
	After reset	0x0000		
	Function	PWM pulse width of U-phase: 0-0xFFFF		
	31	...	17	16
VCMPV0 (0x4005_0180)	bit Symbol			
	Read/Write	R		
VCMPV1 (0x4005_01A0)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	VCMPV		
	Read/Write	R/W		
	After reset	0x0000		
	Function	PWM pulse width of V-phase: 0-0xFFFF		
	31	...	17	16
VCMPW0 (0x4005_0184)	bit Symbol			
	Read/Write	R		
VCMPW1 (0x4005_01A4)	After reset	0x0000		
	Function	-		
	15	...	1	0
	bit Symbol	VCMPW		
	Read/Write	R/W		
	After reset	0x0000		
	Function	PWM pulse width of W-phase: 0-0xFFFF		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

- <VCMPU> PMD setting: PWM setting of U-phase
- <VCMPV> PMD setting: PWM setting of V-phase
- <VCMPW> PMD setting: PWM setting of W-phase

14.4.3.21 6-Phase Output Control Register

	31	...						17	16
OUTCR0 (0x4005_0188)	bit Symbol								
	Read/Write								
	R								
OUTCR1 (0x4005_01A8)	After reset								
	0x0000								
	Function								
	-								
	15	14	13	12	11	10	9	8	
	bit Symbol								
	Read/Write								
	R								
	After reset								
	0000000								
	Function								
	-								
	WPWM								
	R/W								
	0								
	PWM of W-phase 0: ON/OFF output 1: PWM output								
	7	6	5	4	3	2	1	0	
	VPWM		UPWM		WOC		VOC		UOC
	R/W		R/W		R/W		R/W		R/W
	0		0		00		00		00
	Function		Function		Function		Function		Function
	PWM of V-phase 0: ON/OFF output 1: PWM output		PWM of U-phase 0: ON/OFF output 1: PWM output		Output control of W-phase 00: W0 OFF, Z0 OFF <sup>(*)</sup> 01: W0 ON, Z0 OFF 10: W0 OFF, Z0 ON 11: W0 ON, Z0 ON *W0 and Z0 are both ON when WPWM=1.		Output control of V-phase 00: V0 OFF, Y0 OFF <sup>(*)</sup> 01: V0 ON, Y0 OFF 10: V0 OFF, Y0 ON 11: V0 ON, Y0 ON *V0 and Y0 are both ON when VPWM=1.		Output control of U-phase 00: U0 OFF, X0 OFF <sup>(*)</sup> 01: U0 ON, X0 OFF 10: U0 OFF, X0 ON 11: U0 ON, X0 ON *U0 and X0 are both ON when UPWM=1.

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<UPWM>, <U0C> PMD setting: Output control of U-phase (U0,X0)

Setting		Output	
UPWM	U0C	U0	X0
0	00	OFF output	OFF output
1	00	PWMU inverted output	PWMU output
1	11	PWMU output	PWMU inverted output

\*The table shows only those combinations that are used in the VE.

<VPWM>,<V0C> PMD setting: Output control of V-phase (V0,Y0)

Setting		Output	
VPWM	V0C	V0	Y0
0	00	OFF output	OFF output
1	00	PWMV inverted output	PWMV output
1	11	PWMV output	PWMV inverted output

\*The table shows only those combinations that are used in the VE.



---

<WPWM>,<W0C> PMD setting: Output control of W-phase (W0,Z0)

Setting		Output	
WPWM	W0C	W0	Z0
0	00	OFF output	OFF output
1	00	PWMW inverted output	PWMW output
1	11	PWMW output	PWMW inverted output

\* The table shows only those combinations that are used in the VE.

14.4.3.22 TRGCRC Register

	31	...	17	16
TRGCRC0 (0x4005_0098)	bit Symbol			
	Read/Write			
	R			
TRGCRC1 (0x4005_0130)	After reset			
	0x0000			
	Function			
	-			
	15	...	2	1
	bit Symbol			
	TRGCRC			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Trigger correction			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<TRGCRC>: Used to correct the synchronizing trigger timing. The value to be set is:  
Correction time [s] ÷ PWM counter clock frequency [s]

14.4.3.23 VTRGCMP Register

	31	...	17	16
VTRGCMP00 (0x4005_018C)	bit Symbol			
	Read/Write			
	R			
VTRGCMP01 (0x4005_01AC)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	VTRGCMP0			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Trigger timing setting 0x0000: Prohibited 0x0001 to (MDPRD value -1): Trigger timing MDPRD value to 0xFFFF: Prohibited			

	31	...	17	16
VTRGCMP10 (0x4005_0190)	bit Symbol			
	Read/Write			
	R			
VTRGCMP11 (0x4005_01B0)	After reset			
	0x0000			
	Function			
	-			
	15	...	1	0
	bit Symbol			
	VTRGCMP1			
	Read/Write			
	R/W			
	After reset			
	0x0000			
	Function			
	Trigger timing setting 0x0000: Prohibited 0x0001 to (MDPRD value-1): Trigger timing MDPRD value to 0xFFFF: Prohibited			

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VTRGCMP0> PMD setting: Specifies the trigger timing for sampling ADC in synchronization with PMD.

<VTRGCMP1> PMD setting: Specifies the trigger timing for sampling ADC in synchronization with PMD.

\* These registers are effective when one of the following PMD trigger modes is selected:  
count-down match, count-up match, count-up/-down match

\* These registers are ineffective when the PMD trigger output mode is set to trigger select output (TRGOUT=1).

14.4.3.24 VTRGSEL Register

	31	...				9	8	
VTRGSEL0 (0x4005_0194)	bit Symbol							
	Read/Write							
	R							
VTRGSEL1 (0x4005_01B4)	After reset							
	0x000000							
	Function							
	-							
	7	6	5	4	3	2	1	0
	bit Symbol					VTRGSEL		
	Read/Write					R/W		
	R					R/W		
	After reset					000		
	00000					000		
	Function					Synchronizing trigger		
	-					0-5: Output trigger number		
						6-7: Prohibited		

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<VTRGSEL> PMD setting: Specifies the synchronizing trigger number to be output at the timing specified in the VTRGCMP0 register.

\* These registers are effective when the PMD trigger output mode is set to trigger select output (TRGOUT= 1).

14.4.3.25 EMGRS Register

	31	...				9	8
EMGRS0 (0x4005_0198)	bit Symbol						
	Read/Write						
	R						
EMGRS1 (0x4005_01B8)	After reset						
	0x000000						
	Function						
	-						
	7	...			2	1	0
	bit Symbol					EMGRS	
	Read/Write					R/W	
	R					R/W	
	After reset					0	
	0000000					0	
	Function					EMG return	
	-					0: Nop	
						1: EMG return command	

The upper and lower register names correspond to channel 0 and channel 1 respectively.

<EMGRS> PMD setting : EMG return command for returning from the EMG state

## 14.5 Description of Operations

### 14.5.1 Schedule Management

Figure 14-4 shows a flowchart for motor control. The Vector Engine makes state transitions according to the schedule and mode settings which are programmed through the relevant registers.

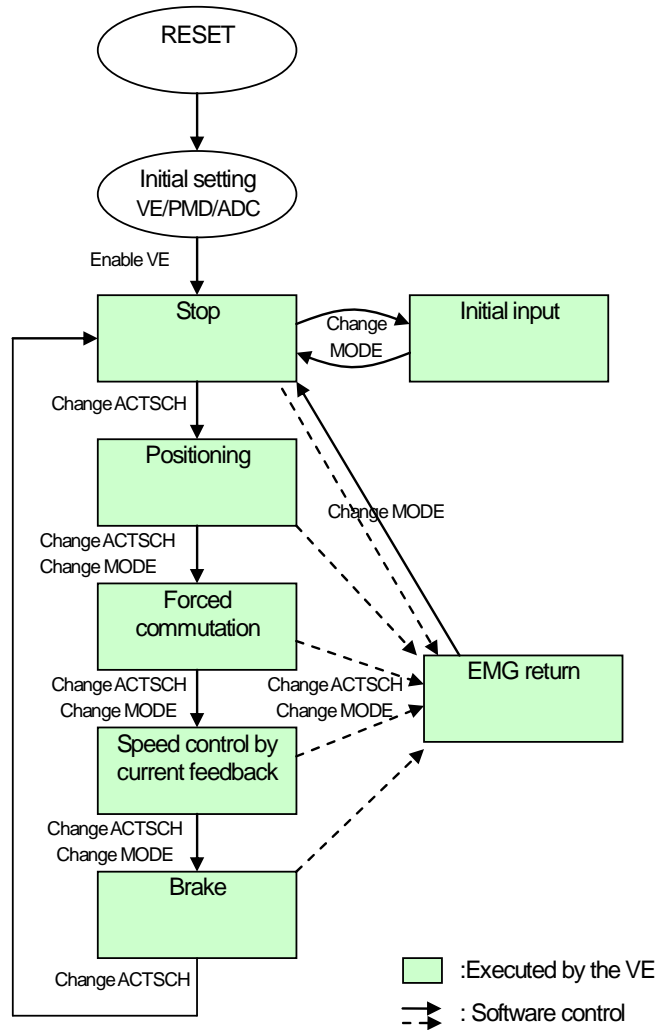


Figure 14-4 Example of Motor Control Flow

RESET	: Microcontroller reset
Initial setting	: Initial setting by a user-created program
Stop	: Stop the motor.
Initial input	: Sample and store zero-current data when the motor is at stop
Positioning	: Determine the initial motor position.
Forced commutation	: Start the motor. For a specified period, the motor is rotated at a specified speed, not controlled by current feedback.
Speed control by current feedback	: Control motor rotation by current feedback.
Brake	: Deceleration control
EMG return	: Return from the EMG state.

14.5.1.1 Schedule Control

The ACTSCH register is used to select the schedule to be executed. A schedule is comprised of an output schedule handling output-related tasks and an input schedule handling input-related tasks. Table 14-5 shows the tasks that are executed in each schedule.

The MODE register is used to enable or disable phase interpolation, control output operation, and enable or disable zero-current detection as appropriate for each step of the motor control flow (see Table 14-6).

Table 14-5 Tasks To Be Executed in Each Schedule

Schedule Selection (ACTSCH)	Output Schedule						Input Schedule		
	Current control	SIN/COS computation	Output coordinate axis conversion	Output phase conversion	Output control	Trigger generation	Input processing	Input phase conversion	Input coordinate axis conversion
0 Individual execution	*1	*1	*1	*1	*1	*1	*1	*1	*1
1 Schedule 1	✓	✓*2	✓	✓	✓*3	✓	✓*4	✓	✓
4 Schedule 4	—	✓*2	✓	✓	✓*3	✓	✓*4	✓	✓
9 Schedule 9	—	—	—	—	✓*3	✓	✓*4	—	—

\*1: Each task is executed only when it is specified.

\*2: Phase interpolation

\*3: Output OFF/EMGRS

\*4: Task operation to be switched by zero-current detection

Table 14-6 Typical Setting Example

Motor Control Flow	Register Setting				
	Schedule selection (ACTSCH)	Task specification (TASKAPP)	Phase interpolation (MODE)	Output control (MODE)	Zero-current detection (MODE)
Stop	9	0	x	00	0
Initial input	9	0	x	00	1
Positioning	1	5	0	01	0
Forced commutation	1	5	1	01	0
Speed control by current feedback	1	5	1	01	0
Brake	4	6	0	01	0
EMG return	9	0	x	11	0

An output schedule begins executing by the CPURUNTRG command. When all output-related tasks are completed, the Vector Engine enters a standby state and waits for a start trigger for input-related tasks. At this time, schedules of the other channel can be executed.

An input schedule begins executing by a start trigger. When all input-related tasks are completed, the Vector Engine generates an interrupt to the CPU and enters a halt state. However, if the schedule has its repeat count (REPTIME) set to "2" or more, an interrupt is not generated until the schedule is executed the specified number of times.

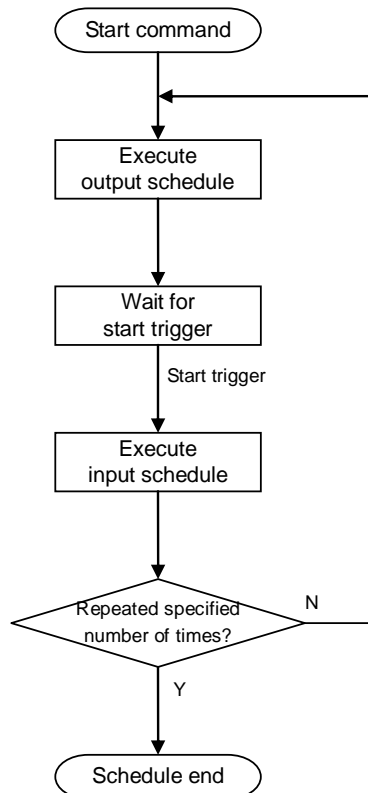


Figure 14-5 Schedule Execution Flow

### 14.5.1.2 Start Control

Enable the Vector Engine with the VEEN register. Specify a schedule (ACTSCH register), task to be executed (TASKAPP register) and repeat count (REPTIME register).

A schedule of the Vector Engine is comprised of an output schedule and an input schedule. Typically, the Vector Engine executes an output schedule first, enters a standby state, and then starts executing an input schedule by a start trigger.

An output schedule is started:

- i) By the CPURUNTRG command. In this case, the task specified in the TASKAPP register is executed.
- ii) On a repeat start (when REPTIME  $\geq$  2) after the corresponding input schedule is completed.

An input schedule is started:

- i) By a start trigger (selected in the TRGMODE register) after the corresponding output schedule is completed.
- ii) By the CPURUNTRG command. In this case, the task specified in the TASKAPP register is executed.

### 14.5.2 Summary of Tasks

Table 14-7 gives a summary of tasks executed in output and input schedules. When each task is to be executed individually or specified as a startup task, use the task number shown in this table.

Table 14-7 List of Tasks

	Task	Description	Task Number
Output schedule	Current control	Controls dq currents.	5
	SIN/COS computation	Performs sine/cosine computation and phase interpolation.	6
	Output coordinate axis conversion	Converts dq coordinates to $\alpha\beta$ coordinates.	7
	Output phase conversion	Converts 2-phase to 3-phase.	8
	Output control	Converts data to PMD setting format. Switches PWM shift.	0
	Trigger generation	Generates synchronization trigger timing.	1
Input schedule	Input processing	Captures AD conversion results and converts them into fixed-point format	2
	Input phase conversion	Converts 2-phase to 3-phase.	3
	Input coordinate axis conversion	Converts $\alpha\beta$ coordinates to dq coordinates.	4

### 14.5.2.1 Current Control

The current control unit is comprised of a PI control unit for d-axis and a PI control unit for q-axis, and calculates d-axis and q-axis voltages.

#### i) PI control of d-axis current

[Equations]

$\Delta ID = IDREF \times 2^{16} - ID$  : Difference between current reference value and current feedback

$VDI = CIDKI \times \Delta ID \times 2 + VDI$  : Integral term computation

$VD = (CIDKP \times \Delta ID \times 2 + VDI) / 2^{32}$  : Voltage calculation using proportional term

	Register Name	Description	
Input	IDn	d-axis current	32-bit fixed-point data (31 fractional bits)
	IDREFn	Reference value of d-axis current	16-bit fixed-point data (15 fractional bits)
	CIDKPn	Proportional coefficient	16-bit data
	CIDKIn	Integral coefficient	16-bit data
Output	VDn	d-axis voltage	32-bit fixed-point data (31 fractional bits)
Internal	VDIn	Integral term of d-axis voltage	64-bit fixed-point data (63 fractional bits)

n = channel number

#### ii) PI control of q-axis current

[Equations]

$\Delta IQ = IQREF \times 2^{16} - IQ$  : Difference between current reference value and current feedback

$VQI = CIQKI \times \Delta IQ \times 2 + VQI$  : Integral term computation

$VQ = (CIQKP \times \Delta IQ \times 2 + VQI) / 2^{32}$  : Voltage calculation using proportional term

	Register Name	Description	
Input	IQn	q-axis current	32-bit fixed-point data (31 fractional bits)
	IQREFn	Reference value of q-axis current	16-bit fixed-point data (15 fractional bits)
	CIQKPn	Proportional coefficient	16-bit data
	CIQKIn	Integral coefficient	16-bit data
Output	VQn	q-axis voltage	32-bit fixed-point data (31 fractional bits)
Internal	VQIn	Integral term of q-axis voltage	64-bit fixed-point data (63 fractional bits)

n = channel number



### 14.5.2.2 SIN/COS Computation

The SIN/COS computation unit is comprised of a phase interpolation unit and a SIN/COS computation unit.

Phase interpolation calculates the rotation speed by integrating with the PWM period. It is executed only when phase interpolation is enabled.

#### i) Phase interpolation

[Equations]

$THEATA = (OMEGA \times TPWM + THEATA \times 2^{31}) / 2^{31}$  : Integration of rotation speed.  
Only when phase interpolation is enabled.

	Register Name	Description	
Input	THETAn	Phase $\theta$	16-bit fixed-point data (0.0 to 1.0, 16 fractional bits)
	OMEGAn	Rotation speed	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	TPWM	PWM period rate	16-bit data
	MODEn	Phase interpolation enable	Mode settings
Output	THETAn	Phase $\theta$	16-bit fixed-point data (0.0 to 1.0, 16 fractional bits)

n = channel number

#### ii) SIN/COS computation

[Equations]

$SINM = SIN$  : Saves previous value (for input processing).

$COSM = COS$  : Saves previous value (for input processing).

$SIN = \sin(THETA \times \pi / 2^{15}) \times 2^{15}$  : SIN/COS computation

$COS = \sin((THETA + 0x4000) \times \pi / 2^{15}) \times 2^{15}$

	Register Name	Description	
Input	THETAn	Phase $\theta$	16-bit fixed-point data (0.0 to 1.0, 16 fractional bits)
Output	SINn	Sine value at $\theta$	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	COSn	Cosine value at $\theta$	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	SINMn	Previous sine value	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	COSMn	Previous cosine value	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)

n = channel number

**14.5.2.3 Output Voltage Conversion (Coordinate axis Conversion/Phase Conversion)**

Output voltage conversion is comprised of dq-to-αβ coordinate axis conversion and 2-phase-to-3-phase conversion.

The dq-to-αβ coordinate axis conversion calculates  $V_\alpha$  and  $V_\beta$  from  $V_d$ ,  $V_q$  in SIN and COS.

The 2-phase-to-3-phase conversion performs segmentation by using  $V_\alpha$  and  $V_\beta$  and performs space vector conversion to calculate  $V_a$ ,  $V_b$  and  $V_c$ .

For the 2-phase-to-3-phase conversion, either 2-phase modulation or 3-phase modulation can be selected.

(1) dq-to-αβ coordinate conversion

[Equations]

$TMPREG0 = (\text{COS} \times VD - \text{SIN} \times VQ) / 2^{15}$  : Calculates  $V_\alpha$ .

$TMPREG1 = (\text{SIN} \times VD + \text{COS} \times VQ) / 2^{15}$  : Calculates  $V_\beta$ .

	Register Name	Description	
Input	VDn	d-axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	VQn	q-axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	SINn	Sine value at $\theta$	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	COSn	Cosine value at $\theta$	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
Output	TMPREG3	$\alpha$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG4	$\beta$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)

n = channel number

(2) 2-phase-to-3-phase conversion (space vector conversion)

i) Segmentation

[Equations]

SECTORM = SECTOR : Saves previous sector.

```

if( $V_\alpha \geq 0$  &  $V_\beta \geq 0$ )
  if( $|V_\alpha| \geq |V_\beta| \div \sqrt{3}$ )
    if( $|V_\alpha| \div \sqrt{3} \geq |V_\beta|$ ) SECTOR=0
    else SECTOR=1
  else SECTOR=2
else if( $V_\alpha < 0$  &  $V_\beta \geq 0$ )
  if( $|V_\alpha| < |V_\beta| \div \sqrt{3}$ ) SECTOR=3
  else if( $|V_\alpha| \div \sqrt{3} < |V_\beta|$ ) SECTOR=4
  else SECTOR=5
else if( $V_\alpha < 0$  &  $V_\beta < 0$ )
  if( $|V_\alpha| \geq |V_\beta| \div \sqrt{3}$ )
    if( $|V_\alpha| \div \sqrt{3} \geq |V_\beta|$ ) SECTOR=6
    else SECTOR=7
  else SECTOR=8
else if( $V_\alpha \geq 0$  &  $V_\beta < 0$ )
  if( $|V_\alpha| < |V_\beta| \div \sqrt{3}$ ) SECTOR=9
  else if( $|V_\alpha| \div \sqrt{3} < |V_\beta|$ ) SECTOR=10
  else SECTOR=11
    
```

	Register Name	Description	
Input	TMPREG3	$\alpha$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG4	$\beta$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
Output	SECTORn	Sector	4-bit data
	SECTORMn	Previous sector	4-bit data

n = channel number

ii) 3-phase voltage calculation (when 3-phase modulation is selected and SECTOR=0 )

[Equations]

$$t1 = \sqrt{3}/VDC \times (\sqrt{3}/2 \times V\alpha - 1/2 \times V\beta) \quad : \text{Calculates } V1 \text{ period.}$$

$$t2 = \sqrt{3}/VDC \times V\beta \quad : \text{Calculates } V2 \text{ period.}$$

$$t3 = 1 - t1 - t2 \quad : \text{Calculates } V0+V7 \text{ period.}$$

$$TMPREG0 = t1 + t2 + t3 \div 2 \quad : \text{Calculates } Va.$$

$$TMPREG1 = t1 + t3 \div 2 \quad : \text{Calculates } Vb.$$

$$TMPREG2 = t3 \div 2 \quad : \text{Calculates } Vc.$$

	Register Name	Description	
Input	TMPREG3	$\alpha$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG4	$\beta$ -axis voltage	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	VDCn	Supply voltage	16-bit fixed-point data (0.0 to 1.0, 15 fractional bits)
	SECTORn	Sector	4-bit data
	FMODEn	Modulation mode	Mode settings
Output	TMPREG0	a-phase voltage	32-bit fixed-point data (0.0 to 1.0, 31 fractional bits)
	TMPREG1	b-phase voltage	32-bit fixed-point data (0.0 to 1.0, 31 fractional bits)
	TMPREG2	c-phase voltage	32-bit fixed-point data (0.0 to 1.0, 31 fractional bits)

n = channel number

#### 14.5.2.4 Output Control

The output control unit converts 3-phase voltage values into PWM setting format (CMPU, CMPV and CMPW ), and sets the OUTCR register to control output operation.

When 1-shunt current detection and 2-phase modulation are selected and PWM is enabled, if the rotation speed is slower than the PWM shift switching reference value, output is switched to shift PWM output.

	Register Name	Description	
Input	TMPREG0	a-phase voltage	32-bit fixed-point data (0.0 to 1.0, 31 fractional bits)
	TMPREG1	b-phase voltage	32-bit fixed-point data (0.0 to 1.0, 31 fractional bits)
	TMPREG2	c-phase voltage	16-bit fixed-point data (0.0 to 1.0, 15 fractional bits)
	MDPRDn	PWM period	16-bit data (PMD PWM period )
	SECTORn	Sector	4-bit data
	OMEGAn	Rotation speed	16-bit fixed-point data (-1.0 to 1.0, 15 fractional bits)
	FPWMCHGn	PWM shift switching reference	16-bit fixed-point data (0 to 1.0, 15 fractional bits)
	FMODEn	Output control operation	Mode settings
Output	CMPUn	PMD U-phase PMW setting	16-bit data (0 to MDPRD value)
	CMPVn	PMD V-phase PWM setting	16-bit data (0 to MDPRD value)
	CMPWn	PMD W-phase PWM setting	16-bit data (0 to MDPRD value)
	OUTCRn	PMD output control setting	9-bit setting
	EMGRSn	PMD EMG return	1-bit setting
	MCTLFn	Shift switching flag	Status

n = channel number

### 14.5.2.5 Trigger Generation

The trigger generation unit calculates the trigger timing from the PWM setting values (CMPU, CMPV and CMPW) as appropriate to the current detection method, and sets the TRGCMP0 and TRGCMP1 registers.

	Register Name	Description	
Input	CMPUn	PMD U-phase PWM setting	16-bit data (0 to MDPRD value)
	CMPVn	PMD V-phase PWM setting	16-bit data (0 to MDPRD value)
	CMPWn	PMD W-phase PWM setting	16-bit data (0 to MDPRD value)
	MDPRDn	PWM period setting	16-bit data (PMD PWM period)
	TADC	AD conversion time	16-bit data (0 to MDPRD value)
	TRGCRCn	Trigger correction value	16-bit data (0 to MDPRD value)
	SECTORn	Sector	4-bit data
	MODEn	Output control operation	Mode settings
	FMODEn	PMD channel/ shift enable/ modulation mode/ detection mode	Mode settings
	MCTLFn	Shift switching flag	Status
Output	TRGCMP0	PMD trigger 0 timing	16-bit data (0 to MDPRD value)
	TRGCMP1	PMD trigger 1 timing	16-bit data (0 to MDPRD value)
	TRGSELn	PMD trigger selection	3-bit data

n = channel number

### 14.5.2.6 Input Processing

The input processing unit saves segmented 3-phase current conversion results, and converts the current and voltage conversion results into fixed-point data.

It saves zero-current conversion results in the initial input processing..

	Register Name	Description	
Input	ADREG0A	ADC unit A conversion result 0	16-bit data (The upper 12 bits are used.)
	ADREG1A	ADC unit A conversion result 1	16-bit data (The upper 12 bits are used.)
	ADREG2A	ADC unit A conversion result 2	16-bit data (The upper 12 bits are used.)
	ADREG3A	ADC unit A conversion result 3	16-bit data (The upper 12 bits are used.)
	ADREG0B	ADC unit B conversion result 0	16-bit data (The upper 12 bits are used.)
	ADREG1B	ADC unit B conversion result 1	16-bit data (The upper 12 bits are used.)
	ADREG2B	ADC unit B conversion result 2	16-bit data (The upper 12 bits are used.)
	ADREG3B	ADC unit B conversion result 3	16-bit data (The upper 12 bits are used.)
	PHNUM0A	ADREG0A detected phase information	2-bit data
	PHNUM1A	ADREG1A detected phase information	2-bit data
	PHNUM2A	ADREG2A detected phase information	2-bit data
	PHNUM3A	ADREG3A detected phase information	2-bit data
	PHNUM0B	ADREG0B detected phase information	2-bit data
	PHNUM1B	ADREG1B detected phase information	2-bit data
	PHNUM2B	ADREG2B detected phase information	2-bit data
	PHNUM3B	ADREG3B detected phase information	2-bit data
	SECTORMn	Sector information	4-bit data
	MODEn	Zero-current detection	Mode settings
	FMODEn	PMD channel /current detection mode / ADC unit /shift enable	Mode settings
	MCTLFn	Shift switching flag	Status
Output	VDCn	Supply voltage	16-bit fixed-point data (0.0 to 1.0, 15 fractional bits)
	TMPREG0	a-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG1	b-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG2	c-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
Internal	IA0n	a-phase zero-current conversion result	16-bit data (The upper 12 bits are used.)
	IB0n	b-phase zero-current conversion result	16-bit data (The upper 12 bits are used.)
	IC0n	c-phase zero-current conversion result	16-bit data (The upper 12 bits are used.)
	IAADCn	a-phase current conversion result	16-bit data (The upper 12 bits are used.)
	IBADCn	b-phase current conversion result	16-bit data (The upper 12 bits are used.)
	ICADCn	c-phase current conversion result	16-bit data (The upper 12 bits are used.)

n = channel number

### 14.5.2.7 Input Current Conversion (Phase Conversion/Coordinate axis Conversion)

Input current conversion is comprised of 3-phase-to-2-phase conversion and  $\alpha\beta$ -to-dq coordinate axis conversion.

The 3-phase-to-2-phase conversion calculates  $I_\alpha$  and  $I_\beta$  from  $I_a$ ,  $I_b$  and  $I_c$ .

The  $\alpha\beta$ -to-dq coordinate axis conversion calculates  $I_d$  and  $I_q$  from  $I_\alpha$ ,  $I_\beta$ ,  $SINM$  and  $COSM$ .

#### (1) 3-phase-to-2-phase conversion

[Equations]

$$TMPREG0 = TMPREG0 \quad : \text{Calculates } I_\alpha.$$

$$TMPREG1 = 1/\sqrt{3} \times TMPREG1 - 1/\sqrt{3} \times TMPREG2 \quad : \text{Calculates } I_\beta.$$

	Register Name	Description	
Input	TMPREG0	a-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG1	b-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG2	c-phase current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
Output	TMPREG3	$\alpha$ -axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG4	$\beta$ -axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)

n = channel number

#### (2) $\alpha\beta$ -to-dq coordinate conversion

[Equations]

$$ID = COSM \times TMPREG0 + SINM \times TMPREG1 \quad : \text{Calculates } I_d.$$

$$IQ = -SINM \times TMPREG0 + COSM \times TMPREG1 \quad : \text{Calculates } I_q.$$

	Register Name	Description	
Input	TMPREG3	$\alpha$ -axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	TMPREG4	$\beta$ -axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	SINMn	Sine value at $\theta$	16-bit fixed-point data (-1.0~1.0, 15 fractional bits)
	COSMn	Cosine value at $\theta$	16-bit fixed-point data (-1.0~1.0, 15 fractional bits)
Output	IDn	d-axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)
	IQn	q-axis current	32-bit fixed-point data (-1.0 to 1.0, 31 fractional bits)

n = channel number

## 14.6 Combinations of VE Channel, ADC Unit and PMD Channel

Table 14-8 shows the combinations of AD unit and PMD channel that can be used with each Vector Engine channel depending on the current detection mode to be used.

Table 14-8 Possible Combinations of VE Channel, ADC Unit and PMD Channel for Motor Control

Vector Engine Channel	Current Detection Mode	ADC Unit	PMD Channel	ADC	
				Unit	Registers Used
0	3-shunt	Unit A	Channel 0	Unit A	ADREG0-3
		Unit A, B	Channel 0	Unit A	ADREG0,1,3
	Unit B			ADREG0	
	1-shunt	Unit A	Channel 0	Unit A	ADREG0-3
	2sensor	Unit A	Channel 0	Unit A	ADREG0-3
		Unit A, B	Channel 0	Unit A	ADREG0,1,3
Unit B	ADREG0				
1	3-shunt	Unit B	Channel 1	Unit B	ADREG0-3
		Unit A, B	Channel 1	Unit A	ADREG0
	Unit B			ADREG0,1,3	
	1-shunt	Unit B	Channel 1	Unit B	ADREG0-3
	2-sensor	Unit B	Channel 1	Unit B	ADREG0-3
		Unit A, B	Channel 1	Unit A	ADREG0
Unit B	ADREG0,1,3				

### 15. Motor Control Circuit (PMD: Programmable Motor Driver)

The TMPM370 contains a two-channel programmable motor driver (PMD). The PMD of this product has newly added features of conduction output control and DC overvoltage detection to realize sensorless motor control and supports interaction with the AD converter.

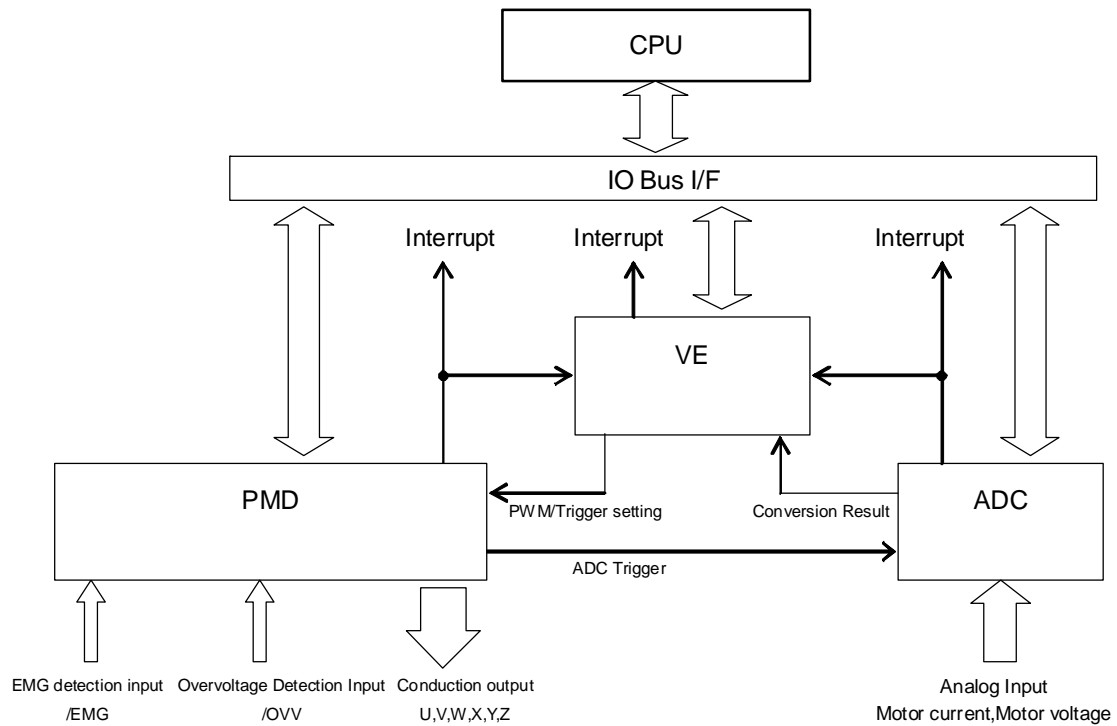


Figure 15-1 Motor Control-related Block Constitution



## 15.1 PMD Input/Output Signals

The table below shows the signals that are input to and output from each PMD.

Table 15-1 Input/Output Signals

Channel	Pin Name	PMD Signal Name	Description
CH 0	PC7/OVV0	OVV 0	OVV state signal
	PC6/EMG0	EMG 0	EMG state signal
	PC0/U0	U 0	U-phase output
	PC1/X0	X 0	X-phase output
	PC2/V0	V 0	V-phase output
	PC3/Y0	Y 0	Y- phase output
	PC4/W0	W 0	W-phase output
	PC5/Z0	Z 0	Z-phase output
CH 1	PG7/OVV1	OVV 1	OVV state signal
	PG6/EMG1	EMG 1	EMG state signal
	PG0/U1	U 1	U-phase output
	PG1/X1	X 1	X-phase output
	PG2/V1	V 1	V-phase output
	PG3/Y1	Y 1	Y-phase output
	PG4/W1	W 1	W-phase output
	PG5/Z1	Z 1	Z-phase output

## 15.2 PMD Registers

The table below shows the registers related to the PMD. (The Address column shows a PMD0 address first followed by a PMD1 address on the next line.)

Table 15-2 PMD Registers

Address	Mnemonic	Register Name
0x4005 0400 0x4005 0480	MDEN0 MDEN1	PMD Enable Register
0x4005 0404 0x4005 0484	PORTMD0 PORTMD1	Port Output Mode Register
0x4005 0408 0x4005 0488	MDCR0 MDCR1	PMD Control Register
0x4005 040C 0x4005 048C	CNTSTA0 CNTSTA1	PWM Counter Status Register
0x4005 0410 0x4005 0490	MDCNT0 MDCNT1	PWM Counter Register
0x4005 0414 0x4005 0494	MDPRD0 MDPRD1	PWM Period Register
0x4005 0418 0x4005 0498	CMPU0 CMPU1	PMD Compare U Register
0x4005 041C 0x4005 049C	CMPV0 CMPV1	PMD Compare V Register
0x4005 0420 0x4005 04A0	CMPW0 CMPW1	PMD Compare W Register
0x4005 0424 0x4005 04A4	MODESEL0 MODESEL1	Mode Select Register
0x4005 0428 0x4005 04A8	MDOUT0 MDOUT1	PMD Output Control Register
0x4005 042C 0x4005 04AC	MDPOT0 MDPOT1	PMD Output Setting Register
0x4005 0430 0x4005 04B0	EMGREL0 EMGREL1	EMG Release Register
0x4005 0434 0x4005 04B4	EMGCR0 EMGCR1	EMG Control Register
0x4005 0438 0x4005 04B8	EMGSTA0 EMGSTA1	EMG Status Register
0x4005 043C 0x4005 04BC	OVVCR0 OVVCR1	OVV Control Register
0x4005 0440 0x4005 04C0	OVVSTA0 OVVSTA1	OVV Status Register
0x4005 0444 0x4005 04C4	DTR0 DTR1	Dead Time Register
0x4005 0448 0x4005 04C8	TRGCMP00 TRGCMP01	Trigger Compare 0 Register
0x4005 044C 0x4005 04CC	TRGCMP10 TRGCMP11	Trigger Compare 1 Register
0x4005 0450 0x4005 04D0	TRGCMP20 TRGCMP21	Trigger Compare 2 Register
0x4005 0454 0x4005 04D4	TRGCMP30 TRGCMP31	Trigger Compare 3 Register
0x4005 0458 0x4005 04D8	TRGCR0 TRGCR1	Trigger Control Register
0x4005 045C 0x4005 04DC	TRGMD0 TRGMD1	Trigger Output Mode Setting Register
0x4005 0460 0x4005 04E0	TRGSEL0 TRGSEL1	Trigger Output Select Register
0x4005 047C 0x4005 04FC	Reserved	-

15.3 PMD Circuit

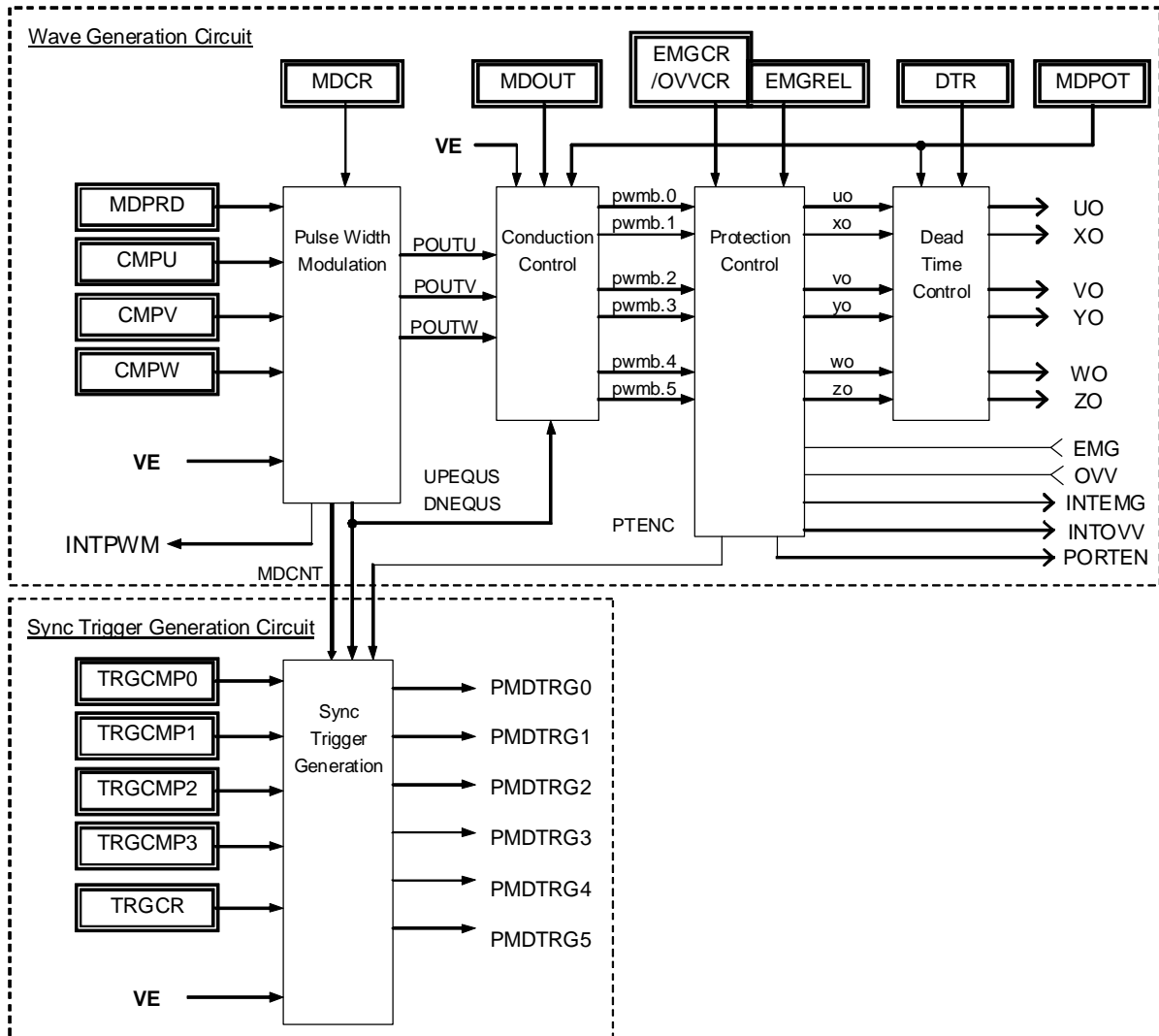


Figure 15-2 Block diagram of PMD Circuit

The PMD circuit consists of two blocks of a wave generation circuit and a sync trigger generation circuit. The wave generation circuit includes a pulse width modulation circuit, a conduction control circuit, a protection control circuit, a dead time control circuit.

- The pulse width modulation circuit generates independent 3-phase PWM waveforms with the same PWM frequency.
- The conduction control circuit determines the output pattern for each of the upper and lower sides of the U, V and W phases.
- The protection control circuit controls emergency output stop by EMG input and OVV input.
- The dead time control circuit prevents a short circuit which may occur when the upper side and lower side are switched.
- The sync trigger generation circuit generates sync trigger signals to the AD converter.

- PMD Enable Register (MDEN)  
0x4005 0400, 0x4005 0480

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	-	PWMEN
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R/W
After reset	0	0	0	0	0	0	0	0

<PWMEN>: Enables or disables waveform synthesis.

- 0: Disable
- 1: Enable

Output ports that are used for the PMD become high impedance when the PMD is disabled. Before enabling the PMD, configure other relevant settings, such as output port polarity.

- Port Output Mode Register (PORTMD)  
0x4005 0404, 0x4005 0484

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	PORTMD	
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R/W	
After reset	0	0	0	0	0	0	0	0

<PORTMD>: Port control setting

- 00: Upper phases = High-Z, lower phases = High-Z
- 01: Upper phases = High-Z, lower phases = PMD output
- 10: Upper phases = PMD output, lower phases = High-Z
- 11: Upper phases = PMD output, lower phases = PMD output

The <PORTMD> setting controls external port outputs of the upper phases (U, V and W phases) and the lower phases (X, Y and Z phases). When a tool break occurs while “High-Z” is selected, the upper and lower phases of external output ports are set to high impedance. In other cases, external port outputs depend on PMD outputs.

- \* When PWMEN=0, output ports are set to high impedance regardless of the output port setting.
- \* When an EMG input occurs, external port outputs are controlled depending on the EMGMD setting.

- Mode Select Register (MODESEL)  
0x4005 0424, 0x4005 04A4

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	-	MDESEL
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R/W
After reset	0	0	0	0	0	0	0	0

<MDESEL>: Mode select register

0: Bus mode

1: VE mode

This bit selects whether to load the second buffer of each double-buffered register with the register value set via the bus (bus mode) or the value supplied from the Vector Engine (VE mode). The PWM compare registers (CMPU, CMPV, CMPW), trigger compare registers (TRGCMP0, TRGCMP1) and MDOUT register are double-buffered, and the second buffers are loaded in synchronization with the PMD's internal update timing.

15.3.1 Pulse Width Modulation Circuit

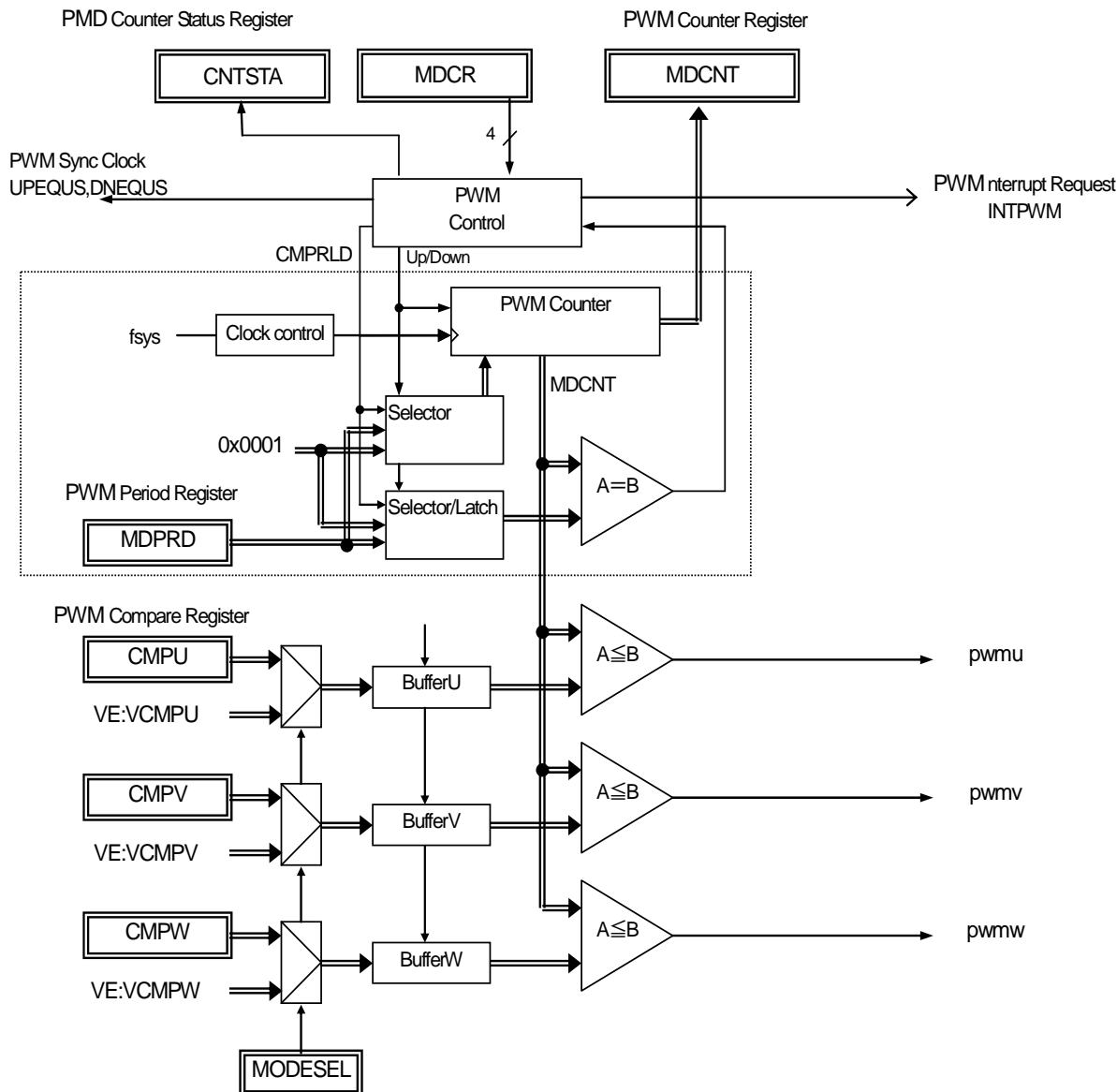


Figure 15-3 Pulse Width Modulation Circuit

The pulse width modulation circuit has a 16-bit PMD up-/down-counter and generates PWM carrier waveforms with a resolution of 12.5 nsec at 80 MHz. The PWM carrier waveform mode can be selected from mode 0 (edge-aligned PWM, sawtooth wave modulation) and mode 1 (center-aligned PWM, triangular wave modulation).

The PWM period extension mode (MDCR<PWMCK> = 1) is also available. When this mode is selected, the PWM counter generates PWM carrier waveforms with a resolution of 50 nsec.

(1) Setting the PWM period

The PWM period is determined by the MDPRD register. This register is double-buffered. Comparator input is updated at every PWM period. It is also possible to update comparator input at every half PWM period.

$$\text{Sawtooth wave PWM: MDPRD register value} = \frac{\text{Oscillation frequency [Hz]}}{\text{PWM frequency [Hz]}}$$

$$\text{Triangular wave PWM: MDPRD register value} = \frac{\text{Oscillation frequency [Hz]}}{\text{PWM frequency [Hz]} \times 2}$$

(2) Compare function

The pulse width modulation circuit compares the PWM compare registers of the 3 phases (CMPU, CMPV, CMPW) and the carrier wave generated by the PWM counter (MDCNT) to determine which is larger to generate PWM waveforms with the desired duty.

The PWM compare register of each phase has a double-buffered compare register. The PWM compare register value is loaded at every PWM period (when the internal counter value matches the MDPRD value). It is also possible to update the compare register at every 0.5 PWM period.

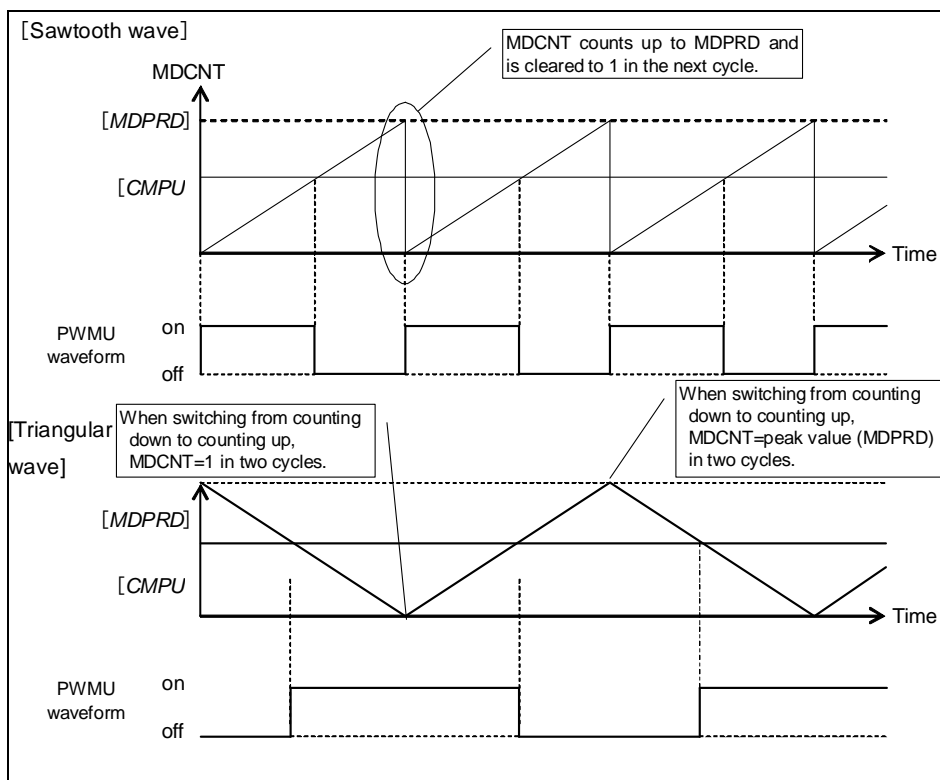


Figure 15-4 PWM Waveforms

(3) Waveform mode

Three-phase PWM waveforms can be generated in the following two modes:

i) 3-phase independent mode:

Each of the PWM compare registers for the three phases is set independently to generate independent PWM waveforms for each phase. This mode is used to generate drive waveforms such as sinusoidal waves.

ii) 3-phase common mode:

Only the U-phase PWM compare register is set to generate identical PWM waveforms for all the three phases. This mode is used for rectangular wave drive of brushless DC motors.

(4) Interrupt processing

The pulse width modulation circuit generates PWM interrupt requests in synchronization with PWM waveforms. The PWM interrupt period can be set to half a PWM period, one PWM period, two PWM periods or four PWM periods.



- PMD Control Register (MDCR)

0x4005 0408, 0x4005 0488

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	PWMCK	SYNTMD	DTYMD	PINT	INTPRD		PWMMD
Read/Write	R→0				R/W			
After reset	0	0	0	0	0	0	0	0

<PWMMD>: PWM carrier waveform

0: PWM mode 0 (edge-aligned PWM, sawtooth wave)

1: PWM mode 1 (center-aligned PWM, triangular wave)

This bit selects the PWM mode. PWM mode 0 is edge-aligned PWM and PWM mode 1 is center-aligned PWM.

<INTPRD>: PWM interrupt period

00: Interrupt request at every 0.5 PWM period (PWM mode 1 only)

01: Interrupt request at every PWM period

10: Interrupt request at every 2 PWM periods

11: Interrupt request at every 4 PWM periods

This field selects the PWM interrupt period from 0.5 PWM period, one PWM period, two PWM periods and four PWM periods.

When <INTPRD>=00, the contents of the compare registers (CMPU, CMPV, CMPW) and period register (MDPRD) are updated into their respective buffers when the internal counter equals 1 or the MDPRD value.

<PINT>: PWM interrupt timing

0: Interrupt request when PWM counter = 1

1: Interrupt request when PWM counter = MDPRD

This bit selects whether to generate an interrupt request when the PWM counter equals its minimum or maximum value. When the edge-aligned PWM mode is selected, an interrupt request is generated when the PWM counter equals the MDPRD value. When the PWM interrupt period is set to every 0.5 PWM period, an interrupt request is generated when the PWM counter equals 1 or MDPRD.)

<DTYMD>: Duty mode

0: 3-phase common mode

1: 3-phase independent mode

This bit selects whether to make duty setting independently for each phase or to use the CMPU register for all three phases.

<SYNTMD>: Port output mode

This bit specifies the port output setting of the U, V and W phases. (See Table 15-3.)

<PWMCK>: PWM period extension mode

0: Normal period

1: 4x period

When <PWMCK>=0, the PWM counter operates with a resolution of 12.5 ns at fsys=80 MHz.

\* Sawtooth wave: 12.5 ns, triangular wave: 25 ns

When <PWMCK>=1, the PWM counter operates with a resolution of 50 ns at fsys=80 MHz.

\* Sawtooth wave: 50 ns, triangular wave: 100 ns

- PWM Counter Status Register (CNTSTA)

0x4005 040C, 0x4005 048C

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	-	UPDWN
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R
After reset	0	0	0	0	0	0	0	0

&lt;UPDWN&gt;: PWM counter flag

0: Up-counting

1: Down-counting

This bit indicates whether the PWM counter is up-counting or down-counting.

When the edge-aligned PWM mode is selected, this bit is always read as 0.

- PWM Counter Register (MDCNT)

0x4005 0410, 0x4005 0490

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	MDCNT							
Read/Write	R							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	MDCNT							
Read/Write	R							
After reset	0	0	0	0	0	0	0	0

&lt;MDCNT&gt;: PWM counter

PMD counter value (resolution: 12.5 ns at  $f_{sys} = 80$  MHz)

\* Sawtooth wave: 12.5 ns, triangular wave: 25 ns

\* When  $MDCR<PWMCK>=1$ , the counter resolution becomes 50 ns.

A16-bit counter for reading the PWM period count value. It is read-only.

- PWM Period Register (MDPRD)  
0x4005 0414, 0x4005 0494

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	MDPRD							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	MDPRD							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

<MDPRD>: PWM period

MDPRD 0x0010

A 16-bit register for specifying the PWM period. This register is double-buffered and can be changed even when the PWM counter is operating. The buffer is loaded at every PWM period. (That is, when the PWM counter matches the MDPRD value. When 0.5 PWM period is selected, loading is performed when the PWM counter matches 1 or MDPRD. The least significant bit must be set as 0.)

If <MDPRD> is set to a value less than 0x0010, it is automatically assumed to be 0x0010. (The register retains the actual value that is written.)

\* Do not write to this register in byte units. If the upper 8 bits [15:8] and the lower 8 bits [7:0] are written separately, operation cannot be guaranteed.

- PWM Compare Registers (CMPU, CMPV, CMPW)  
PMD1(0x4005 0418-041B),PMD2( 0x4005 0498-049B)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	CMPU0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	CMPU0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

PMD1(0x4005 041C-041F),PMD2( 0x4005 049C-049F)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	CMPV0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	CMPV0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

PMD1(0x4005 0420-0423),PMD2( 0x4005 04A0-04A3)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	CMPW0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	CMPW0,1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

<CMPU, CMPV, CMPW>: PWM pulse width

Compare registers (resolution : 12.5 ns at  $f_{\text{sys}} = 80$  MHz)

\* Sawtooth wave: 12.5 ns, triangular wave: 25 ns

\* When  $\text{MDCR} < \text{PWMCK} > = 1$ , the counter resolution becomes 50 ns.

CMPU, CMPV and CMPW are compare registers for determining the output pulse width of the U, V and W phases. These registers are double-buffered. Pulse width is determined by comparing the buffer and the PWM counter to evaluate which is larger. (To be loaded when the PWM counter value matches the MDPRD value. When 0.5 PWM period is selected, loading is performed when the PWM counter matches 1 or MDPRD.) When this register is read, the value of the first buffer (data set via the bus) is returned.

\* To load the second buffer with the value in the compare register updated via the bus, select the bus mode (default) by setting  $\text{MODESEL} < \text{MDSEL} >$  to 0.

\* Do not write to these registers in byte units. If the upper 8 bits [15:8] and the lower 8 bits [7:0] are written separately, operation cannot be guaranteed.

15.3.2 Conduction Control Circuit

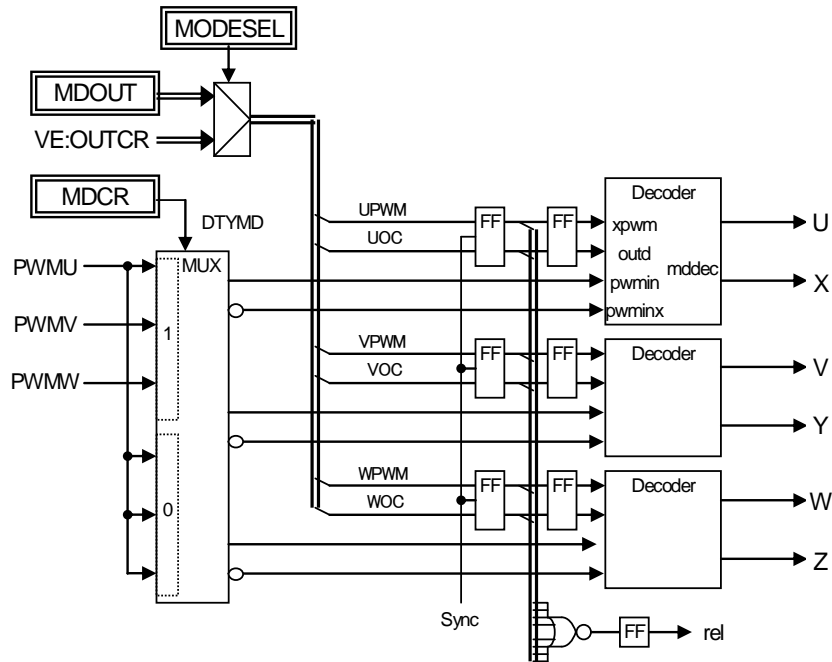


Figure 15-5 Conduction Control Circuit

The conduction control circuit performs output port control according to the settings made in the PMD output register (MDOUT). The MDOUT register bits are divided into two parts: settings for the synchronizing signal for port output and settings for port output. The latter part is double-buffered and update timing can be set as synchronous or asynchronous to PWM.

The output settings for six port lines are made independently for each of the upper and lower phases through the bits 10 to 8 of the MDOUT register and bits 3 and 2 of the MDPO register. In addition, bits 10 to 8 of the MDOUT register select PWM or H/L output for each of the U, V and W phases. When PWM output is selected, PWM waveforms are output. When H/L output is selected, output is fixed to either a high or low level. Table 15-3 shows a summary of port outputs according to port output settings in the MDOUT register and polarity settings in the MDCR register.

• PMD Output Setting Register (MDPOT)  
0x4005 042C, 0x4005 04AC

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	POLH	POLL	PSYNCS	
Read/Write	R→0	R→0	R→0	R→0	R/W	R/W	R/W	
After reset	0	0	0	0	0	0	0	0

<PSYNCS>: MDOUT transfer timing

00: Async to PWM

01: Load when PWM counter = 1

10: Load when PWM counter= MDPRD

11: Load when PWM counter = 1 or MDPRD

PSYNCS selects the timing when the U-, V- and W-phase output settings are reflected in port outputs (sync or async to the PWM counter peak, bottom or peak/bottom).

\* This field must be set while MDEN<PWMEN>=0.

<POLL>: Lower phase port polarity

0: Active low

1: Active high

POLL selects the output port polarity of the lower phases.

\* This bit must be set while MDEN<PWMEN>=0.

<POLH>: Upper phase port polarity

0: Active low

1: Active high

POLH selects the output port polarity of the upper phases.

\* This bit must be set while MDEN<PWMEN>=0.

• PMD Output Control Register (MDOUT)

0x4005 0428, 0x4005 04A8

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	WPWM	VPWM	UPWM
Read/Write	R→0	R→0	R→0	R→0	R→0	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	WOC		VOC		UOC	
Read/Write	R→0	R→0	R/W		R/W		R/W	
After reset	0	0	0	0	0	0	0	0

<UOC, VOC, WOC>, <UPWM, VPWM, WPWM>: U-, V-, and W-phase output control

The MDOUT register controls the port outputs of the U, V and W phases (see Table 15-3 below.)

\* To load the second buffer of MDOUT with a value updated via the bus, select the bus mode (default) by setting MODESEL<MDESEL> to 0.

\* Do not write to this register in byte units. If the upper 8 bits [15:8] and the lower 8 bits [7:0] are written separately, operation cannot be guaranteed.

OMDCR<SYNTMD>=0

Polarity: Active high (MDPOT bits 4, 3=1)

MDOUT Output Control		MDOUT Bits 10, 9, 8 H/L or PWM Output Select			
Bits 5, 3, 1	Bits 4, 2, 0	0: H/L output		1: PWM output	
Upper phase	Lower phase	Upper phase output	Lower phase output	Upper phase output	Lower phase output
0	0	L	L	/PWM	PWM
0	1	L	H	L	PWM
1	0	H	L	PWM	L
1	1	H	H	PWM	/PWM

Polarity: Active low (MDPOT bits 4, 3=0)

MDOUT Output Control		MDOUT Bits 10, 9, 8 H/L or PWM Output Select			
Bits 5,3,1	Bits 4,2,0	0: H/L output		1: PWM output	
Upper phase	Lower phase	Upper phase output	Lower phase output	Upper phase output	Lower phase output
0	0	H	H	PWM	/PWM
0	1	H	L	H	/PWM
1	0	L	H	/PWM	H
1	1	L	L	/PWM	PWM

OMDCR<SYNTMD>=1

Polarity: Active high (MDPOT bits 4, 3=1)

MDOUT Output Control		MDOUT Bits 10, 9, 8 H/L or PWM Output Select			
Bits 5, 3, 1	Bits 4, 2, 0	0: H/L output		1: PWM output	
Upper phase	Lower phase	Upper phase output	Lower phase output	Upper phase output	Lower phase output
0	0	L	L	/PWM	PWM
0	1	L	H	L	/PWM
1	0	H	L	PWM	L
1	1	H	H	PWM	/PWM

Polarity: Active low (MDPOT bits 4, 3=0)

MDOUT Output Control		MDOUT Bits 10, 9, 8 H/L or PWM Output Select			
Bits 5,3,1	Bits 4,2,0	0: H/L output		1: PWM output	
Upper phase	Lower phase	Upper phase output	Lower phase output	Upper phase output	Lower phase output
0	0	H	H	PWM	/PWM
0	1	H	L	H	PWM
1	0	L	H	/PWM	H
1	1	L	L	/PWM	PWM

Table 15-3 Port Outputs according to the UOC, VOC, WOC, UPWM, VPWM and WPWM Settings



## Output Settings for Center-off PWM

Center-off PWM can be supported by the following settings.

Table 15-4 Register Settings for Center-off PWM

	Normal PWM center on	U-Phase PWM center off	V-Phase PWM center off	W-Phase PWM center off
CMPU	duty_U	MDPRD-duty_U	duty_U	duty_U
CMPV	duty_V	duty_V	MDPRD-duty_V	duty_V
CMPW	duty_W	duty_W	duty_W	MDPRD-duty_W
UOC	11	00	11	11
VOC	11	11	00	11
WOC	11	11	11	00

### 15.3.3 Protection Control Circuit

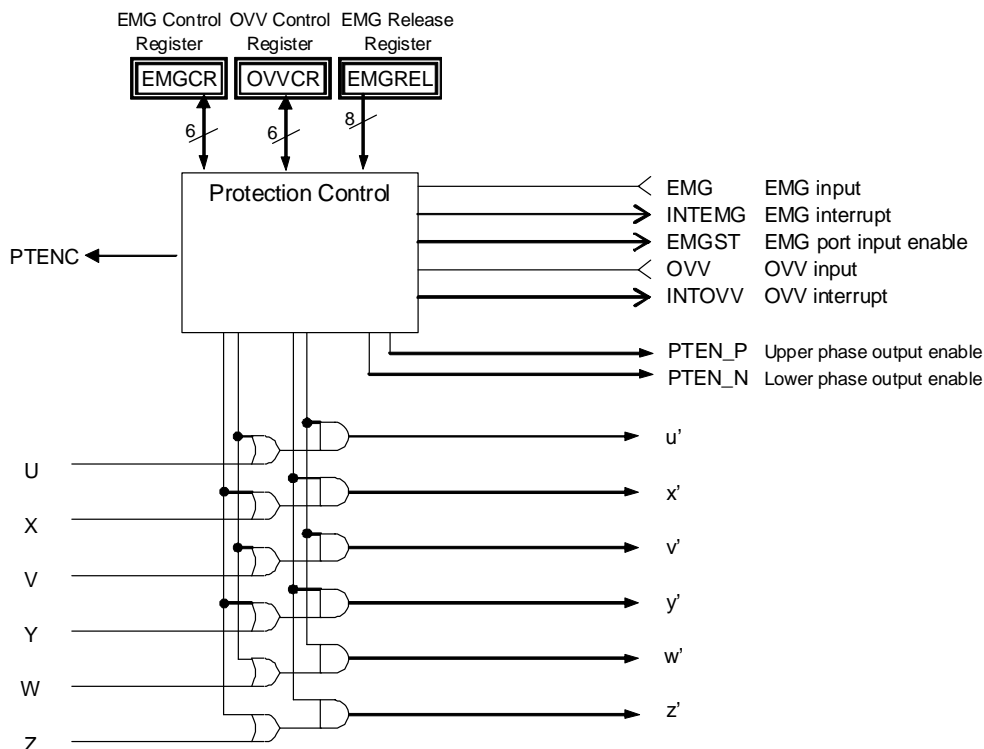


Figure 15-6 Protection Control Circuit

The protection control circuit consists of an EMG protection control circuit and an OVV protection control circuit.

#### (1)EMG Protection Circuit

The EMG protection circuit consists of an EMG protection control unit and a port output disable unit. This circuit is activated when the EMG input becomes low. The EMG protection circuit offers an emergency stop mechanism: when the EMG input is asserted (H → L), all six port outputs are immediately disabled (depending on the EMGCR<EMGMD> setting) and an EMG interrupt (INTEMG) is generated. EMGCR<EMGMD> can be set to output a control signal that sets external output ports to high impedance in case of an emergency.

A tool break also disables all six PWM output lines depending on the EMGCR<EMGMD> setting. When a tool break occurs, external output ports can be set to high impedance through the setting of the PORTMD register.

EMG protection is set through the EMG Control Register (EMGCR). A read value of 1 in EMGSTA<EMGST> indicates that the EMG protection circuit is active. In this state, EMG protection can be released by setting all the port output lines inactive (MDOUT[10:8][5:0]) and then setting EMGCR<EMGRS> to 1.

To disable the EMG protection function, write 0x5A and 0xA5 in this order to the EMGREL register and then clear EMGCR<EMGEN> to 0. (These three instructions must be executed consecutively.) While the EMG protection input is low, any attempt to release the EMG protection state is ignored. Before setting EMGCR<EMGRS> to 1 to release EMG protection, make sure that EMGST<EMGI> is high.

The EMG protection circuit can be disabled only after the specified key codes (0x5A, 0xA5) are written in the EMGREL register to prevent it from being inadvertently disabled.

- EMG Release Register (EMGREL)

0x4005 0430, 0x4005 04B0

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	EMGREL							
Read/Write	W							
After reset	0	0	0	0	0	0	0	0

<EMGREL>: EMG disable code

The EMG and OVV protection functions can be disabled by setting 5A and A5 in this order to bits 7 to 0 of the EMGREL register.

When disabling these functions, EMGCR<EMGEN> and OVVCr<OVVEN> must be cleared to 0.

\* This register is used for both the EMG and OVV functions.

- EMG Control Register (EMGCR)

0x4005 0434, 0x4005 04B4

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	EMGCNT			
Read/Write	R→0	R→0	R→0	R→0	R/W			
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	INHEN	EMGMD		EMGMD	EMGRS	EMGEN
Read/Write	R→0	R→0	R/W	R/W		R/W	W	R/W
After reset	0	0	1	1	1	0	0	1

<EMGEN>: EMG protection circuit enable/disable

0: Disable

1: Enable

The EMG protection circuit is enabled by setting this bit to 1. In the initial state, the EMG protection circuit is enabled.

To disable this circuit, write 5A and A5 in this order to the EMGREL register and then clear the EMGEN bit to 0.

<EMGRS>: EMG protection release

0: -

1: Release protection

EMG protection can be released by setting the MDOUT register to 0 and then setting the EMGRS bit to 1.

This bit is always read as 0.

\* Be sure to write 0 to both the upper bits [10:8] and lower bits [5:0].

\* Before releasing EMG protection, make sure that the EMG input has returned to high.

<EMGISEL>: EMG input select

0: Port input

1: Comparator output

This bit selects whether to use port input or comparator output as the EMG signal to be input to the protection circuit.

<EMGMD>: EMG protection mode select

00: PWM output control disabled / Port output = All phases High-Z

01: All upper phases ON, all lower phases OFF / Port output = Lower phases High-Z

10: All upper phases OFF, all lower phases ON / Port output = Upper phases High-Z

11: All phases OFF / Port output = All phases High-Z

\* ON = PWM output (no output control), OFF = Low [when <POLL>,<POLH>=1 (active high)]

This field controls PWM output and port output of the upper and lower phases in case of an emergency.

<INHEN>: Tool break enable/disable

0: Disable

1: Enable

This bit selects whether or not to stop the PMD when the PMD stop signal is input from the tool. In the initial state, tool breaks are enabled.

<EMGCNT>: EMG input detection time

0 to 15 (When <EMGCNT=0, the noise filter is bypassed.)

EMGCNT×16/fsys (resolution: 200[nsec] at 80 MHz)

• EMG Status Register (EMGSTA)

0x4005 0438, 0x4005 04B8

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	EMGI	EMGST
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R	R
After reset	0	0	0	0	0	0	-	0

<EMGST>: EMG protection state

0: Normal operation

1: Protected

The EMG protection state can be known by reading this bit.

<EMGI>: EMG input

EMG protection state

The EMG input state can be known by reading this bit.

## (2) OVV Protection Control Circuit

The OVV protection control circuit consists of an OVV protection control unit and a port output disable unit. This circuit is activated when the OVV input port is asserted.

When the OVV input is asserted (H → L) for a specified period (set in OVVCNT<OVVCNT>), the OVV protection circuit fixes the six port output lines in the conduction control circuit to high or low. At this time, an OVV interrupt (INTOV) is generated. It is possible to turn off only the upper or lower phases or all phases.

OVV protection is set through the OVV Control Register (OVVCR). A read value of 1 in OVVSTA<OVVST> indicates that the OVV protection circuit is active.

The release of the OVV protection state is enabled by setting OVVCNT<OVVEN> to 1. Then, OVV protection is automatically released after the OVV protection circuit completes its operation.

\* The OVV protection state is not released while the OVV protection input is low. The state of this port input can be checked by reading OVVSTA<OVVI>.

The OVV protection state is released in synchronization with the PWM period (when the PWM count matches the MDPRD value). (When 0.5 PWM period is selected, the release timing is when the PWM counter equals 1 or MDPRD.)

To disable the OVV protection function, write 0x5A and 0xA5 in this order to the EMGREL register and then clear OVVCNT<OVVEN> to 0. (These three instructions must be executed consecutively.)

The OVV protection circuit can be disabled only after the specified key codes (0x5A, 0xA5) are written in the EMGREL register to prevent it from being inadvertently disabled.

- OVV Control Register (OVVCR)

0x4005 043C, 0x4005 04BC

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	OVVCNT			
Read/Write	R→0	R→0	R→0	R→0	R/W			
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	ADIN1EN	ADIN0EN	OVVMD		OVVISEL	OVVRS	OVVEN
Read/Write	R→0	R/W	R/W	R/W		R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

<OVVEN>: OVV protection circuit enable/disable

0: Disable

1: Enable

The OVV protection circuit is enabled by setting this bit to 1. In the initial state, the OVV protection circuit is disabled.

To disable this circuit, write 5A and A5 in this order to the EMGREL register and then clear this bit to 0. (These three instructions must be executed consecutively.)

<OVVRS>: OVV protection release

0: Disable automatic release of OVV protection

1: Disable automatic release of OVV protection

The OVV protection state is entered when the overvoltage detection signal makes a high-to-low transition. After the overvoltage detection signal returns high, the OVV protection state can be automatically released by a match between the PWM counter and the MDPRD register by setting this bit to 1.

\* When 0.5 PWM period is selected (MDCR<INTPRD>=00), the OVV protection state is released when the PWM counter equals 1 or MDPRD.

<OVVISEL>: OVV input select

0: Port input

1: ADC monitor signal

This bit selects whether to use port input or the monitor signal from the ADC as the OVV signal to be input to the protection circuit.

When the ADC monitor signal is selected, <OVVCNT> becomes invalid.

<OVVMD>: OVV protection mode

00: No output control

01: All upper phases ON, all lower phases OFF

10: All upper phases OFF, all lower phases ON

11: All phases OFF

\* ON=High, OFF=Low [when <POLL>,<POLH>=1 (active high)]

This field controls the outputs of the upper and lower phases when an OVV condition occurs.

\* If OVV and EMG conditions occur simultaneously, the protection mode settings in the EMGCR register become effective.

<ADIN0EN>: ADC A monitor interrupt input enable

0: Disable

1: Enable

This bit selects whether to enable or disable the monitor signal input from ADC A.

When this bit is set to enable and <OVVISEL>=1, the PMD is placed in a protection state (if OVV protection is enabled) by an interrupt signal from ADC A that is generated by a match between an AD conversion result and the specified compare value.

\* For details, see the chapter on the ADC.

<ADIN1EN>: ADC B monitor interrupt input enable

0: Disable input

1: Enable input

This bit selects whether to enable or disable the monitor signal input from ADC B.

When this bit is set to enable and <OVVISEL>=1, the PMD is placed in a protection state (if OVV protection is enabled) by an interrupt signal from ADC B that is generated by a match between an AD conversion result and the specified compare value.

\* For details, see the chapter on the ADC.

<OVVCNT>: OVV input detection time

1-15 (If 0 is set, it is handled as 1.)

$OVVCNT \times 16 / f_{sys}$  (resolution: 200[nsec] at 80 MHz)

\* OVVCNT is effective only when port input is selected as the OVV signal (<OVVISEL>=1).

- OVV Status Register (OVVSTA)

0x4005 0440, 0x4005 04C0

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	OVVI	OVVST
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R	R
After reset	0	0	0	0	0	0	-	0

<OVVST>: OVV protection state

0: Normal operation

1: Protected

The OVV state can be known by reading this bit.

<OVVI>: OVVI input

OVVI state

The OVV input state (selected by OVVCR<OVVISEL>) can be known by reading this bit.

15.3.4 Dead Time Circuit

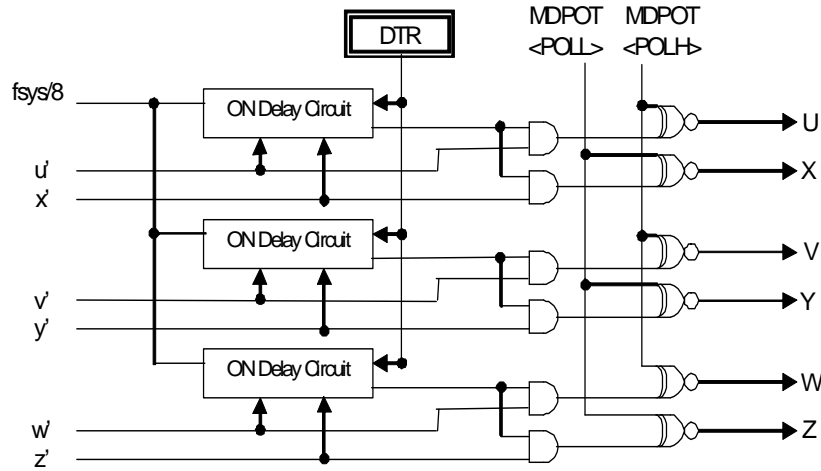


Figure 15-7 Dead Time Circuit

The dead time circuit consists of a dead time unit and an output polarity switching unit.

For each of the U, V and W phases, the ON delay circuit introduces a delay (dead time) when the upper and lower phases are switched to prevent a short circuit. The dead time is set to the Dead Time Register (DTR) as an 8-bit value with a resolution of 100 ns at 80 MHz.

The output polarity switching circuit allows the polarity (active high or active low) of the upper and lower phases to be independently set through MDPOT<POLH> and <POLL>.

- Dead Time Register (DTR)  
0x4005 0444, 0x4005 04C4

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	DTR							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

<DTR>: Dead time

100 nsec × 8 bits (up to 25.5 μsec at fsys = 80 MHz)

\* Do not change this register while MDEN<PWMEN>=1.



15.3.5 Sync Trigger Generation Circuit

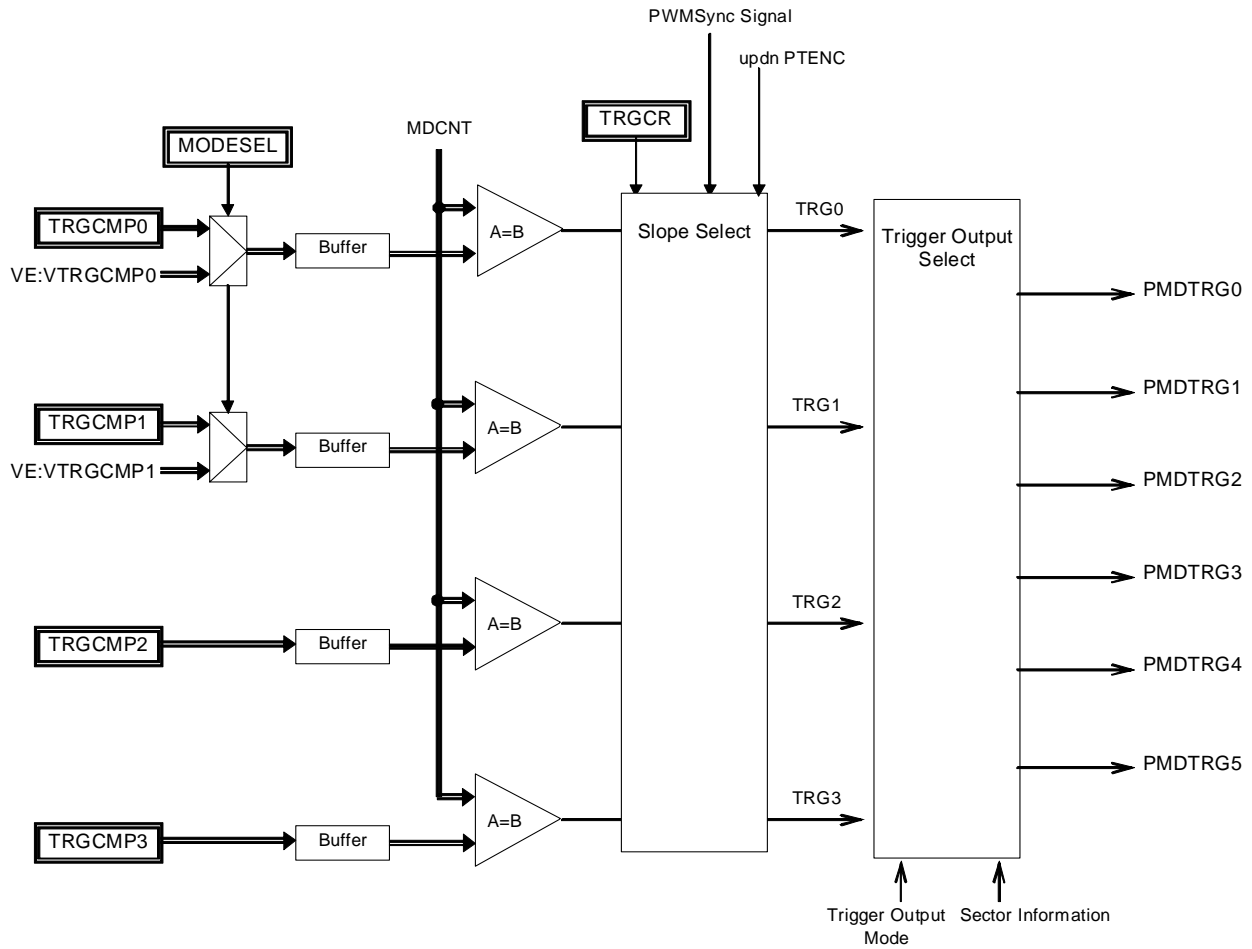


Figure 15-8 Sync Trigger Generation Circuit

The sync trigger generation circuit generates trigger signals for starting ADC sampling in synchronization with PWM. The ADC trigger signal (PMDTRG) is generated by a match between MDCNT and TRGCMP. The signal generation timing can be selected from up-count match, down-count match and up-/down-count match. When the edge-aligned PWM mode is selected, the ADC trigger signal is generated on an up-count match. When PWM output is disabled ( $MDEN < PWMEN = 0$ ), trigger output is also disabled.

When the trigger select output mode is selected, the trigger output port is switched according to the TRGSEL register setting or sector information from the Vector Engine.

• Trigger Compare Registers (TRGCMP0 ~TRGCMP3)

PMD0 (0x4005 0448-044B) , PMD1 (0x4005 04C8-04CB)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	TRGCMP0							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	TRGCMP0							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

PMD0 (0x4005 044C-044F) , PMD1 (0x4005 04CC-04CF)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	TRGCMP1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	TRGCMP1							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

PMD0 (0x4005 0450-0453) , PMD1 (0x4005 04D0-04D3)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	TRGCMP2							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	TRGCMP2							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

PMD0 (0x4005 0454-0458) , PMD1 (0x4005 04D4-04D7)

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	TRGCMP3							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	TRGCMP3							
Read/Write	R/W							
After reset	0	0	0	0	0	0	0	0

<TRGCMP0-3>: Trigger output compare registers

When the PMD counter value (MDCNT) matches the value set in TRGCMPx, PMDTRG is output. When TRGCMPx is read, the value in the first buffer of the double buffers (data set via the bus) is returned.

TRGCMPx should be set in a range of 1 to [MDPRD set value – 1].

- \* It is prohibited to set TRGCMPx to 0 or the MDPRD value.
- \* To load the data in TRGCMP0 and TRGCMP1 to the second buffers, select the bus mode (default) by setting MODESEL<MSEL> to 0.
- \* Do not write to these registers in byte units. If the upper 8 bits [15:8] and the lower 8 bits [7:0] are written separately, operation cannot be guaranteed.
- \* When TRGCMPx is set to 0x0001, no trigger output is made only in the first cycle after PWM start (MDEN<PWMEN>1).

Update Timing of the Trigger Compare Register (TRGCMPx)

The Trigger Compare Register (TRGCMPx) is double-buffered. The timing at which the data written to TRGCMPx is loaded to the second buffer depends on the setting of TRGCR<TRGxMD>. When TRGCR<TRGxBE> is set to 1, data written to TRGCMPx is immediately loaded to the second buffer.

Table 15-5 TRGCMPx Buffer Update Timing according to Trigger Output Mode Setting

TRGxMD	TBUFx Update Timing
000:Trigger output disabled	Always updated
001:Trigger output on down-count match	Updated when PWM counter equals MDPRD (PWM carrier peak)
010:Trigger output on up-count match	Updated when PWM counter equals 1 (PWM carrier bottom)
011:Trigger output on up-/down-count match	Updated when PWM counter equals 1 or MDPRD (PWM carrier peak/bottom)
100:Trigger output at PWM carrier peak	Always updated
101:Trigger output at PWM carrier bottom	
110:Trigger output at PWM carrier peak/bottom	
111:Trigger output disabled	

• Trigger Control Register (TRGCR)  
0x4005 0458, 0x4005 04D8

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	TRG3BE	TRG3MD			TRG2BE	TRG2MD		
Read/Write	R/W	R/W			R/W	R/W		
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	TRG1BE	TRG1MD			TRG0BE	TRG0MD		
Read/Write	R/W	R/W			R/W	R/W		
After reset	0	0	0	0	0	0	0	0

<TRG0MD, TRG1MD, TRG2MD, TRG3MD>: PMDTRG0 to PMDTRG3 mode setting

- 000: Trigger output disabled
- 001: Trigger output at down-count match
- 010: Trigger output at up-count match
- 011: Trigger output at up-/down-count match
- 100: Trigger output at PWM carrier peak
- 101: Trigger output at PWM carrier bottom
- 110: Trigger output at PWM carrier peak/bottom
- 111: Trigger output disabled

This register selects trigger output timing.

When the PMD is set to the edge-aligned mode, trigger outputs are made on up-count match or at PWM carrier peak even if down-count match or PWM carrier bottom is selected.

\* When <TRGxMD>=011, TRGCMPx=0x0001 and MDCR<PWMMMD>=1 (triangular wave), one trigger output is made per period.

< TRG0BE, TRG1BE, TRG2BE, TRG3BE >: PMDTRG0 to PMDTRG3 buffer update timing

- 0: Sync
- 1: Async (The value written to PMDTRGx is immediately reflected.)

This bit enables asynchronous updating of the PMDTRG0 to PMDTRG3 buffers.

• Trigger Output Mode Setting Register (TRGMD)  
0x4005 045C, 0x4005 04DC

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	-	TRGOUT	EMGTGE
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R/W	R/W
After reset	0	0	0	0	0	0	0	0

<EMGTGE>: Output enable in EMG protection state  
 0: Disable trigger output in the protection state  
 1: Enable trigger output in the protection state

This bit enables or disables trigger output in the EMG protection state.

<TRGOUT>: Trigger output mode  
 0: Fixed trigger output  
 1: Variable trigger output

When <TRGOUT>=0, trigger outputs PMDTRG0 to PMDTRG3 output the trigger signals generated by a match with TRGCMP0 to TRGCMP3 respectively. PMDTRG4 and PMDTRG5 are fixed to a low level. When <TRGOUT>=1, trigger output by TRGCMP0 is switched according to the TRGSEL register setting or sector information from the Vector Engine. For details, see the table below.

Table 15-6 Trigger Output Patterns

TRGOUT Setting	TRGSEL Setting	Compare Register	Trigger Output
TRGOUT=0	x	TRGCMP0	PMDTRG0
		TRGCMP1	PMDTRG1
		TRGCMP2	PMDTRG2
		TRGCMP3	PMDTRG3
TRGOUT=1	TRGSEL = 0	TRGCMP0	PMDTRG0
	TRGSEL = 1		PMDTRG1
	TRGSEL = 2		PMDTRG2
	TRGSEL = 3		PMDTRG3
	TRGSEL = 4		PMDTRG4
	TRGSEL = 5		PMDTRG5
	x	TRGCMP1	No trigger output
	x	TRGCMP2	No trigger output
x	TRGCMP3	No trigger output	

- Trigger Output Select Register (TRGSEL)

0x4005 0460 , 0x4005 04E0

	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	15	14	13	12	11	10	9	8
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R→0	R→0	R→0	R→0	R→0	R→0	R→0	R→0
After reset	0	0	0	0	0	0	0	0
	7	6	5	4	3	2	1	0
Bit Symbol	-	-	-	-	-	TRGSEL		
Read/Write	R→0	R→0	R→0	R→0	R→0	R/W		
After reset	0	0	0	0	0	0	0	0

<TRGSEL>: Trigger output select

- 000: Output from PMDTRG0
- 001: Output from PMDTRG1
- 010: Output from PMDTRG2
- 011: Output from PMDTRG3
- 100: Output from PMDTRG4
- 101: Output from PMDTRG5
- 110: No trigger output
- 111: No trigger output

This field is effective when the variable trigger output mode is selected (TRGMD<TRGOUT>=1). The selected trigger is output by a match between the PMD counter and the TRGCMP0 value. (See Table 15-5.)

## 16 12-Bit Analog-to-Digital Converters

The TMPM370 FY contains two 12-bit successive-approximation analog-to-digital converters (ADCs).

The ADC unit A (ADC A) has 15 analog inputs. Six inputs are able to use for shunt resistor currents of motor 0. Three of six inputs are connected with operational amp/ comparator outputs. Thus twelve inputs can use for external input.

The ADC unit B (ADC B) has 17 analog inputs. Six inputs are able to use for shunt resistor currents of motor 0. And two inputs are able to use for shut resistor currents of motor 1. four of eight inputs are connected with operational amp/ comparator outputs. Thus thirteen inputs can use for external input.

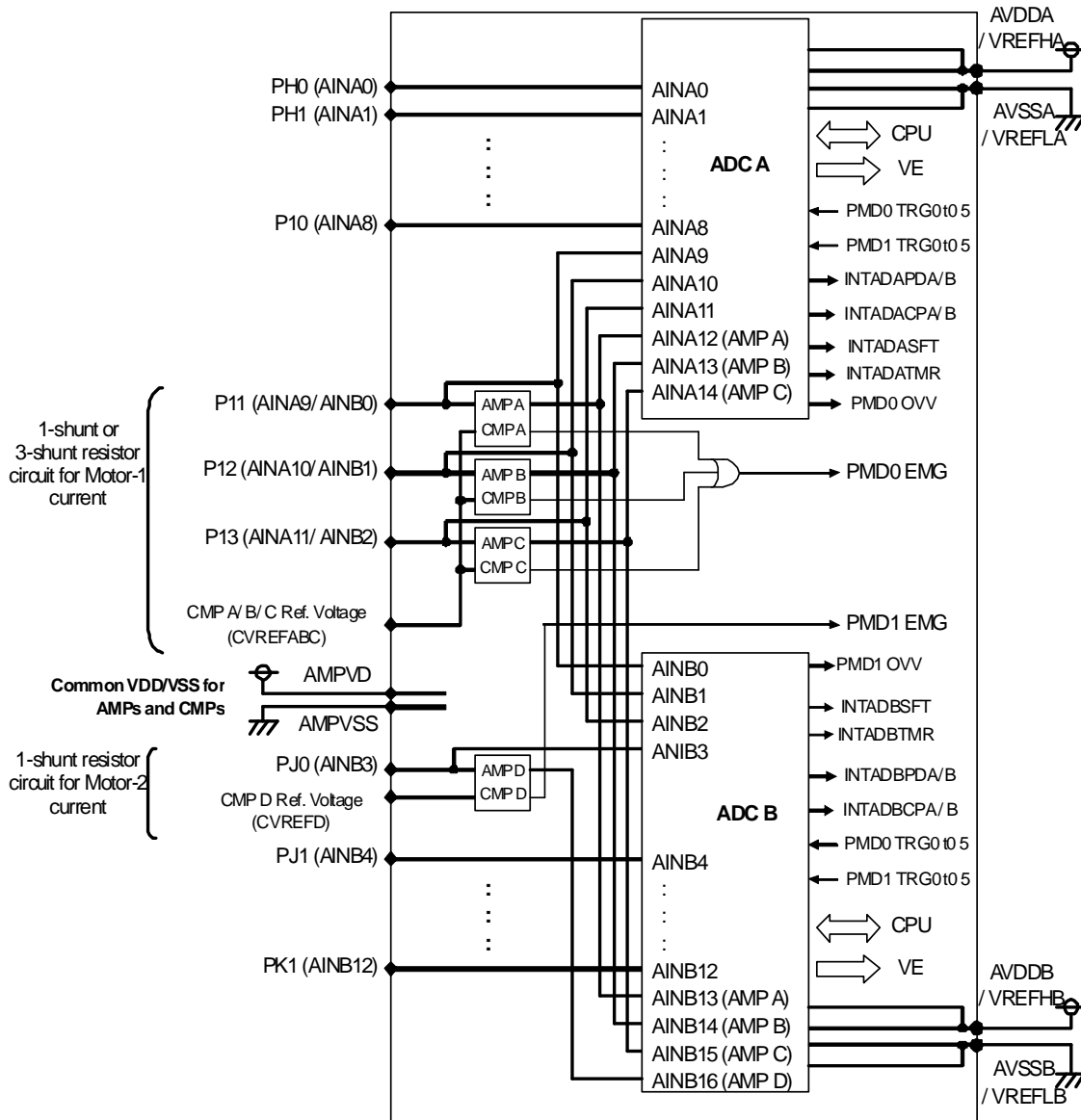
Twenty two external analog input pins (AINA0 to AINA8, AINA9/AINB0, AINA10/AINB1, AINA11/AINB2, AINB3 to AINB12) can also be used as input/output ports.

### Functions and features

- (1) It can select analog input and start AD conversion when receiving trigger signal from PMD or TMRB(interrupt).
- (2) It can select analog input, in the Software Trigger Program and the Constant Trigger Program.
- (3) The ADCs has twelve register for AD conversion result.
- (4) The ADCs generate interrupt signal at the end of the program which was started by PMD trigger and TMRB trigger.
- (5) The ADCs generate interrupt signal at the end of the program which are the Software Trigger Program and the Constant Trigger Program.
- (6) The ADCs have the AD conversion monitoring function. When this function is enabled, an interrupt is generated when a conversion result matches the specified comparison value.

### 16.1 Block Diagram

The following shows a block diagram of the ADCs.





## 16.2 List of Registers

The ADCs have the following registers. (Only the addresses of the registers of ADC A are shown below. The registers of ADC B are located starting from address 4003 0200).

Address	Register Name	Description
4003_00_00	ADCLK	ADC Clock Setting Register
4003_00_04	ADMOD0	ADC Mode Setting Register 0
4003_00_08	ADMOD1	ADC Mode Setting Register 1
4003_00_0C	ADMOD2	ADC Mode Setting Register 2
4003_00_10	ADCMPCR0	Monitoring Setting Register 0
4003_00_14	ADCMPCR1	Monitoring Setting Register 1
4003_00_18	ADCMP0	AD Conversion Result Compare Register 0
4003_00_1C	ADCMP1	AD Conversion Result Compare Register 1
4003_00_20	ADREG0	AD Conversion Result Register 0
4003_00_24	ADREG1	AD Conversion Result Register 1
4003_00_28	ADREG2	AD Conversion Result Register 2
4003_00_2C	ADREG3	AD Conversion Result Register 3
4003_00_30	ADREG4	AD Conversion Result Register 4
4003_00_34	ADREG5	AD Conversion Result Register 5
4003_00_38	ADREG6	AD Conversion Result Register 6
4003_00_3C	ADREG7	AD Conversion Result Register 7
4003_00_40	ADREG8	AD Conversion Result Register 8
4003_00_44	ADREG9	AD Conversion Result Register 9
4003_00_48	ADREG10	AD Conversion Result Register 10
4003_00_4C	ADREG11	AD Conversion Result Register 11
4003_00_50	ADPSEL0	PMD Trigger Program Number Select Register 0
4003_00_54	ADPSEL1	PMD Trigger Program Number Select Register 1
4003_00_58	ADPSEL2	PMD Trigger Program Number Select Register 2
4003_00_5C	ADPSEL3	PMD Trigger Program Number Select Register 3
4003_00_60	ADPSEL4	PMD Trigger Program Number Select Register 4
4003_00_64	ADPSEL5	PMD Trigger Program Number Select Register 5
4003_00_68	ADPSEL6	PMD Trigger Program Number Select Register 6
4003_00_6C	ADPSEL7	PMD Trigger Program Number Select Register 7
4003_00_70	ADPSEL8	PMD Trigger Program Number Select Register 8
4003_00_74	ADPSEL9	PMD Trigger Program Number Select Register 9
4003_00_78	ADPSEL10	PMD Trigger Program Number Select Register 10
4003_00_7C	ADPSEL11	PMD Trigger Program Number Select Register 11
4003_00_80	ADPINTS0	PMD Trigger Interrupt Select Register 0
4003_00_84	ADPINTS1	PMD Trigger Interrupt Select Register 1
4003_00_88	ADPINTS2	PMD Trigger Interrupt Select Register 2
4003_00_8C	ADPINTS3	PMD Trigger Interrupt Select Register 3
4003_00_90	ADPINTS4	PMD Trigger Interrupt Select Register 4
4003_00_94	ADPINTS5	PMD Trigger Interrupt Select Register 5
4003_00_98	ADPSET0_REG	PMD Trigger Program Register 0
4003_00_9C	ADPSET1_REG	PMD Trigger Program Register 1
4003_00_A0	ADPSET2_REG	PMD Trigger Program Register 2
4003_00_A4	ADPSET3_REG	PMD Trigger Program Register 3
4003_00_A8	ADPSET4_REG	PMD Trigger Program Register 4
4003_00_AC	ADPSET5_REG	PMD Trigger Program Register 5
4003_00_B0	ADTSET_REG03	Timer Trigger Program Registers 0 to 3
4003_00_B4	ADTSET_REG47	Timer Trigger Program Registers 4 to 7
4003_00_B8	ADTSET_REG811	Timer Trigger Program Registers 8 to 11
4003_00_BC	ADSSET_REG03	Software Program Registers 0 to 3
4003_00_C0	ADSSET_REG47	Software Program Registers 4 to 7
4003_00_C4	ADSSET_REG811	Software Program Registers 8 to 11
4003_00_C8	ADASET_REG03	Constant Conversion Program Registers 0 to 3

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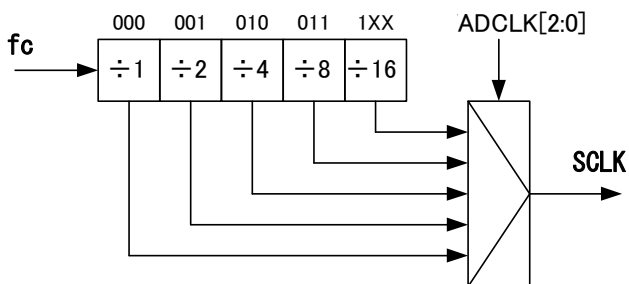
Address	Register Name	Description
4003_00_CC	ADASET_REG47	Constant Conversion Program Registers 4 to 7
4003_00_D0	ADASET_REG811	Constant Conversion Program Registers 8 to 11

### 16.3 Register Descriptions

AD conversion is performed at the clock frequency selected in the ADC Clock Setting Register.

#### 16.3.1 ADC Clock Setting Register (ADCLK)

	7	6	5	4	3	2	1	0
Bit symbol	-	TSH3	TSH2	TSH1	TSH0	ADCLK2	ADCLK1	ADCLK0
Read/Write	R	R/W				R/W		
After reset	0	1	000		000			
Function	Always read as 0.	Extend AIN sampling period 1000: 6*(1/SCLK)    1001: 12*(1/SCLK) 1010: 18*(1/SCLK)    1011: 24*(1/SCLK) 1100: 96*(1/SCLK)    1101: 384*(1/SCLK) 1110: 1536*(1/SCLK)    1111: 6144*(1/SCLK) Others : reserved				AD prescaler output (SCLK) select 000: fc            001: fc/2 010: fc/4            011: fc/8 1XX: fc/16		
ADACLK 0x4003_0000								
ADBCLK 0x4003_0200								



Note 1: AD conversion is performed at the clock frequency selected in this register. The conversion clock frequency must be selected to ensure the guaranteed accuracy.

Note 2: The conversion clock must not be changed while AD conversion is in progress.

#### 16.3.2 Mode Setting Registers

The ADC Mode Setting Registers (ADMOD0, ADMOD1 and ADMOD2) are used to select how AD conversion is started.

##### 16.3.2.1 ADMOD0

	7	6	5	4	3	2	1	0
Bit symbol							DACON	ADSS
Read/Write	R						R/W	W
After reset	0						0	0
Function	Always read as 0.						DAC control 0: off 1: On	Software triggered conversion 0: Don't care 1: Start
ADAMOD0 0x4003_0004								
ADBMOD0 0x4003_0204								

Setting <DACON> to “1”, when using the ADC.

Setting <ADSS> to “1” starts AD conversion (software triggered conversion). Receiving trigger signal from PMD or TMRB(interrupt) starts AD conversion also.

For detail setting, please read the chapter about PMD and TMRB.

**16.3.2.2 ADMOD1**

		7	6	5	4	3	2	1	0
ADAMOD1 0x4003_0008	Bit symbol	ADEN	-						ADAS
	Read/Write	R/W	R						R/W
	After reset	0	0						0
ADBMOD1 0x4003_0208	Function	AD conversion control 0: Disable 1: Enable	Always read as 0.						Constant AD conversion control 0: Disable 1: Enable

Setting <ADEN> to “1”, when using the ADC. After Setting <ADEN> to “1”, setting <ADAS> to “1” starts AD conversion and repeat conversion.

**16.3.2.3 ADMOD2**

		7	6	5	4	3	2	1	0	
ADMOD2 0x4003_000C	Bit symbol	-							ADSFN	ADBFN
	Read/Write	R							R	R
	After reset	0							0	0
ADMOD2 0x4003_020C	Function	Always read as 0.							Software conversion busy flag 0: Conversion completed 1: Conversion in progress	AD conversion busy flag 0: Conversion not in progress 1: Conversion in progress

The <ADBFN> is an AD conversion busy flag. When AD conversion is started regardless of conversion factor (PMD, Timer, Software, Constant), <ADBFN> is set to “1”. When finished AD conversion, <ADBFN> is cleared to “0”.

The <ADSFN> is a software AD conversion busy flag. After <ADSS> was set to “1”, when AD conversion is actually started, <ADSFN> is set to “1”. When finished AD conversion, <ADSFN> is cleared to “0”.

### 16.3.3 Monitoring Setting Registers

The ADCs have the AD conversion result monitoring function.

#### 16.3.3.1 ADCMPCR0,ADCMPCR1

The ADCMPCR0 and ADCMPCR1 registers are used to enable or disable comparison between an AD conversion result and the specified comparison value, to select the register to be compared with an AD conversion result and to set how many times comparison should be performed to determine the result.

After fixing the conversion result, The interrupt signal(INTADxCPA,INTADxCPB) is generated.  
(x=A , B : ADC unit)

#### ADCMPCR0

		7	6	5	4	3	2	1	0
ADACMPCR0LL 0x0043_0010	Bit symbol	CMP0EN	-	-	ADBIG0	REGS03	REGS02	REGS01	REGS00
	Read/Write	R/W	R	R	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
ADBCMPCR0LL 0x0043_0210	Function	Monitoring function  0: Disable 1: Enable	Always read as 0.	Always read as 0.	Comparison condition 0: Larger than compare register 1: Smaller than compare register	AD conversion result register to be compared 0000: ADREG0 0100: ADREG4 1000: ADREG8 0001: ADREG1 0101: ADREG5 1001: ADREG9 0010: ADREG2 0110: ADREG6 1010: ADREG10 0011: ADREG3 0111: ADREG7 1011: ADREG11			
			15	14	13	12	11	10	9
ADACMPCR0LH 0x4003_0011	Bit symbol	-	-	-	-	CMPCNT03	CMPCNT02	CMPCNT01	CMPCNT00
	Read/Write	R	R	R	R	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
ADBCMPCR0 0x4003_0211	Function	Always read as 0.	Always read as 0.	Always read as 0.	Always read as 0.	Comparison count for determining the result 0000: After every comparison 0001: After two comparisons . . 1111: After 16 comparisons			

#### ADCMPCR1

		7	6	5	4	3	2	1	0
ADACMPCR1LL 0x4003_0014	Bit symbol	CMP1EN	-	-	ADBIG1	REGS13	REGS12	REGS11	REGS10
	Read/Write	R/W	R	R	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
ADBCMPCR1LL 0x0043_0214	Function	Monitoring function  0: Disable 1: Enable	Always read as 0.	Always read as 0.	Comparison condition 0: Larger than compare register 1: Smaller than compare register	AD conversion result register to be compared 0000: ADREG0 0100: ADREG4 1000: ADREG8 0001: ADREG1 0101: ADREG5 1001: ADREG9 0010: ADREG2 0110: ADREG6 1010: ADREG10 0011: ADREG3 0111: ADREG7 1011: ADREG11			
			15	14	13	12	11	10	9
ADACMPCR1LH 0x4003_0015	Bit symbol	-	-	-	-	CMPCNT13	CMPCNT12	CMPCNT11	CMPCNT10
	Read/Write	R	R	R	R	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
ADBCMPCR1LH 0x4003_0215	Function	Always read as 0.	Always read as 0.	Always read as 0.	Always read as 0.	Comparison count for determining the result 0000: After every comparison 0001: After two comparisons . . 1111: After 16 comparisons			

### 16.3.3.2 Conversion Result Compare Register

The ADCMP0 and ADCMP1 registers specify the value to be compared with an AD conversion result. The upper 12 bits (bits 4 to 15) are used.

#### ADCMP0

		7	6	5	4	3	2	1	0
	Bit symbol	AD0CMP03	AD0CMP02	AD0CMP01	AD0CMP00	-	-	-	-
ADACMP0LL 0x4003_0018	Read/Write	R/W	R/W	R/W	R/W	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
	Function	Bits 0 to 3 of the value to be compared with an AD conversion result				Always read as 0.			
		15	14	13	12	11	10	9	8
	Bit symbol	AD0CMP11	AD0CMP10	AD0CMP09	AD0CMP08	AD0CMP07	AD0CMP06	AD0CMP05	AD0CMP04
AADCMP0LH 0x4003_0019	Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	Bits 4 to 11 of the value to be compared with an AD conversion result							
ADCMP0LH 0x4003_0219									

#### ADCMP1

		7	6	5	4	3	2	1	0
	Bit symbol	AD1CMP03	AD1CMP02	AD1CMP01	AD1CMP00	-	-	-	-
ADACMP1LL 0x4003_001C	Read/Write	R/W	R/W	R/W	R/W	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
	Function	Bits 0 to 3 of the value to be compared with an AD conversion result				Always read as 0.			
		15	14	13	12	11	10	9	8
	Bit symbol	AD1CMP11	AD1CMP10	AD1CMP09	AD1CMP08	AD1CMP07	AD1CMP06	AD1CMP05	AD1CMP04
ADACMP1LH 0x4003_001D	Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
	After reset	0	0	0	0	0	0	0	0
	Function	Bits 4 to 11 of the value to be compared with an AD conversion result							
AADCMP1LH 0x4003_021D									

### 16.3.4 AD Conversion Result Registers

#### 16.3.4.1 ADREG0 to ADREG11

The ADREGn (n = 0 to 11) register is used to store the result of an AD conversion. Bit 0 (ADRnRF) is a flag that is set when an AD conversion result is stored in the ADREGn register and is cleared when the low-order byte of ADREGn is read. Bit 1 (OVRn) is an overrun flag. This flag is set when a new AD conversion result is stored before the low-order byte of ADREGn is read and is cleared when the low-order byte of ADREGn is read.

There are twelve ADREGn registers, which are all functionally equivalent. Only the ADREG0 register is explained here.

AD Conversion Result Register

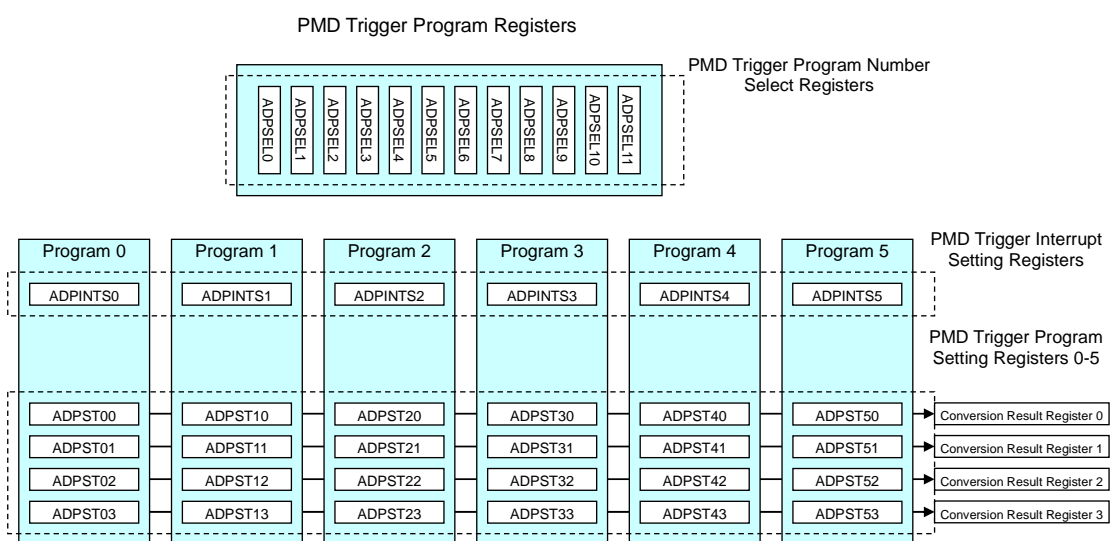
		7	6	5	4	3	2	1	0
ADAREG0LL 0x4003_0020	Bit symbol	ADR003	ADR002	ADR001	ADR000	-	-	OVR0	ADR0RF
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
ADBREG0LL 0x4003_0220	Function	Bits 0 to 3 of an AD conversion result				Always read as 0.	Always read as 0.	Overrun flag 0: No overrun occurred 1: Overrun occurred	AD conversion result store flag 0: No result stored 1: Result stored
			15	14	13	12	11	10	9
ADAREG0LH 0x4003_0021	Bit symbol	ADR011	ADR010	ADR009	ADR008	ADR007	ADR006	ADR005	ADR004
	Read/Write	R	R	R	R	R	R	R	R
	After reset	0	0	0	0	0	0	0	0
ADBREG0LH 0x4003_0221	Function	Bits 4 to 11 of an AD conversion result							

### 16.3.5 PMD Trigger Program Registers

AD conversion can be started by a trigger from the PMD (programmable motor driver).

The PMD trigger program registers are used to specify the program to be started by each of twelve triggers generated by the PMD, to select the interrupt to be generated upon completion of the program and to select the AIN input to be used.

The PMD trigger program registers include three types of registers: PMD Trigger Program Number Select Register (ADPSEL<sub>p</sub>), PMD Trigger Interrupt Select Register (ADPINTS<sub>n</sub>) and PMD Trigger Program Setting Register (ADPSET<sub>nm</sub>). (p=0 to 11, n=0 to 5, m=0 to 3)



The PMD Trigger Program Number Select Register (ADPSEL<sub>n</sub>) specifies the program to be started by each of twelve AD conversion start signals corresponding to twelve triggers generated by the PMD. Programs 0 to 5 are available.

The PMD Trigger Interrupt Select Register (ADPINT<sub>n</sub>) selects the interrupt to be generated upon completion of each program, and enables or disables the interrupt.

The PMD Trigger Program Setting Register (ADPSET<sub>nm</sub>) specifies the settings for each of programs 0 to 5. Each PMD Trigger Program Register is comprised of four registers for specifying the AIN input to be converted. The conversion results corresponding to the ADPSET<sub>n0</sub> to ADPSET<sub>n3</sub> registers are stored in the Conversion Result Registers 0 to 3 (ADREG0 to ADREG3).



**16.3.5.1 PMD Trigger Program Number Select Registers**

The PMD Trigger Program Number Select Registers (ADPSEL0 to ADPSEL11) select the program to be started (from among programs 0 to 5) by each of trigger inputs PMD0 to PMD11.

**PMD Trigger Program Number Select Register 0 (ADPSEL0)**

	7	6	5	4	3	2	1	0
ADAPSEL0 0x4003_0050	Bit symbol PENS0					PMDS02	PMDS01	PMDS00
	Read/Write R/W	R	R	R	R	R/W	R/W	R/W
	After reset 0	0	0	0	0	0	0	0
ADBSEL0 0x4003_0250	Function PMD Trigger Program Select Register 0 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	Always read as 0.	Always read as 0.	Program number select  000: Program 0    100: Program 4 001: Program 1    101: Program 5 010: Program 2    110,111: Reserved 011: Program 3		



**PMD Trigger Program Select Register 11 (ADPSEL11)**

	7	6	5	4	3	2	1	0
ADAPSEL11 0x4003_007C	Bit symbol PENS11					PMDS112	PMDS111	PMDS110
	Read/Write R/W	R	R	R	R	R/W	R/W	R/W
	After reset 0	0	0	0	0	0	0	0
ADBSEL11 0x4003_027C	Function PMD Trigger Program Select Register 11 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	Always read as 0.	Always read as 0.	Program number select  000: Program 0    100: Program 4 001: Program 1    101: Program 5 010: Program 2    110, 111: Reserved 011: Program 3		

**16.3.5.2 PMD Trigger Interrupt Select Registers**

The PMD Trigger Interrupt Select Registers (ADPINTS0 to ADPINTS5) select the interrupt to be generated for each of programs 0 to 5.

ADPINTS0 (for program 0)

		7	6	5	4	3	2	1	0
ADAPINTS0 0x4003_0080	Bit symbol							INTSEL01	INTSEL00
	Read/Write	R						R/W	
	After reset	0						0	
ADBPINTS0 0x4003_0280	Function	Always read as 0.						Interrupt select 00: No interrupt output 01: INTADA 10: INTADB 11: Reserved	

Note: When <INTSEL> = 11, no interrupt is generated.



ADINTS5 (for program 5)

		7	6	5	4	3	2	1	0
ADAPINS5 0x4003_0094	Bit symbol							INTSEL51	INTSEL50
	Read/Write	R						R/W	
	After reset	0						0	
ADBPINS5 0x4003_0294	Function	Always read as 0.						Interrupt select 00: No interrupt output 01: INTADA 10: INTADB 11: Reserved	

Note: When <INTSEL> = 11, no interrupt is generated.

### 16.3.5.3 PMD Trigger Program Setting Registers 0 to 5

Each of the PMD Trigger Program Registers (ADPSET0 to 5) are comprised of four registers. These four registers are used to select the AD conversion input pin (AINA0 to AINA14, AINB0 to AINB16) to be used and select phase of the Vector Engine. The numbers of these registers correspond to those of the Conversion Result Registers.

Setting the <ENSPnm> to 1 enables the ADPSETnm register. The <UWISnm> bits are used to select phase-U, phase-V or phase-W. The <AINSPnm> bits are used to select the AIN pin to be used. The numbers of the PMD Trigger Program Setting Registers correspond to those of the Conversion Result Registers. (n= 0 to 5 , m= 0 to 3)

PMD Trigger Program Register 0 (ADPSET0)

	7	6	5	4	3	2	1	0
ADAPSET00 0x4003_0098	Bit symbol ENSP00	UVWIS001	UVWIS000	AINSP004	AINSP003	AINSP002	AINSP001	AINSP000
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET00 0x4003_0298	Function REG0 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	15	14	13	12	11	10	9	8
ADAPSET01 0x4003_0099	Bit symbol ENSP01	UVWIS011	UVWIS010	AINSP014	AINSP013	AINSP012	AINSP011	AINSP010
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET01 0x4003_0299	Function REG1 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	23	22	21	20	19	18	17	16
ADAPSET02 0x4003_009A	Bit symbol ENSP02	UVWIS021	UVWIS020	AINSP024	AINSP023	AINSP022	AINSP021	AINSP020
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET02 0x4003_029A	Function REG2 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	31	30	29	28	27	26	25	24
ADAPSET03 0x4003_009B	Bit symbol ENSP03	UVWIS031	UVWIS030	AINSP034	AINSP033	AINSP032	AINSP031	AINSP030
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET03 0x4003_029B	Function REG3 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

PMD Trigger Program Register 1 (ADPSET1)

	7	6	5	4	3	2	1	0
ADAPSET10 0x4003_009C	Bit symbol ENSP10	UVWIS101	UVWIS100	AINSP104	AINSP103	AINSP102	AINSP101	AINSP100
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET10 0x4003_029C	Function REG0 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	15	14	13	12	11	10	9	8
ADAPSET11 0x4003_009D	Bit symbol ENSP11	UVWIS111	UVWIS110	AINSP114	AINSP113	AINSP112	AINSP111	AINSP110
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0 0				
ADBPSET11 0x4003_00#20D	Function REG1 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	23	22	21	20	19	18	17	16
ADAPSET12 0x4003_009E	Bit symbol ENSP12	UVWIS121	UVWIS120	AINSP124	AINSP123	AINSP122	AINSP121	AINSP120
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET12 0x4003_029E	Function REG2 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
	31	30	29	28	27	26	25	24
ADAPSET13 0x4003_009F	Bit symbol ENSP13	UVWIS131	UVWIS130	AINSP134	AINSP133	AINSP132	AINSP131	AINSP130
	Read/Write R/W	R/W		R/W				
	After reset 0	0		0				
ADBPSET13 0x4003_029F	Function REG3 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN selection (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

PMD Trigger Program Register 2(ADPSET2)

		7	6	5	4	3	2	1	0
	Bit symbol	ENSP20	UVWIS201	UVWIS200	AINSP204	AINSP203	AINSP202	AINSP201	AINSP200
ADAPSET20 0x4003_00A0	Read/Write	R/W	R/W		R/W				
	After reset	0	0		00				
ADBPSET20 0x4003_02A0	Function	REG0 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		15	14	13	12	11	10	9	8
	Bit symbol	ENSP21	UVWIS211	UVWIS210	AINSP214	AINSP213	AINSP212	AINSP211	AINSP210
ADAPSET21 0x4003_00A1	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET21 0x4003_02A1	Function	REG1 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		23	22	21	20	19	18	17	16
	Bit symbol	ENSP22	UVWIS221	UVWIS220	AINSP224	AINSP223	AINSP222	AINSP221	AINSP220
ADAPSET22 0x4003_00A2	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET22 0x4003_02A2	Function	REG2 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		31	30	29	28	27	26	25	24
	Bit symbol	ENSP23	UVWIS231	UVWIS230	AINSP234	AINSP233	AINSP232	AINSP231	AINSP230
ADAPSET23 0x4003_00A3	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET23 0x4003_02A3	Function	REG3 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

PMD Trigger Program Register 3(ADPSET3)

		7	6	5	4	3	2	1	0
	Bit symbol	ENSP30	UVWIS301	UVWIS300	AINSP304	AINSP303	AINSP302	AINSP301	AINSP300
ADAPSET30 0x4003_00A4	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET30 0x4003_02A4	Function	REG0 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 0000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		15	14	13	12	11	10	9	8
	Bit symbol	ENSP31	UVWIS311	UVWIS310	AINSP314	AINSP313	AINSP312	AINSP311	AINSP310
ADAPSET31 0x4003_00A5	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET31 0x4003_02A5	Function	REG1 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		23	22	21	20	19	18	17	16
	Bit symbol	ENSP32	UVWIS321	UVWIS320	AINSP324	AINSP323	AINSP322	AINSP321	AINSP320
ADAPSET32 0x4003_00A6	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET32 0x4003_02A6	Function	REG2 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		31	30	29	28	27	26	25	24
	Bit symbol	ENSP33	UVWIS331	UVWIS330	AINSP334	AINSP333	AINSP332	AINSP331	AINSP330
ADAPSET33 0x4003_00A7	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET33 0x4003_02A7	Function	REG3 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

PMD Trigger Program Register 4(ADPSET4)

		7	6	5	4	3	2	1	0
ADAPSET40 0x4003_00A8	Bit symbol	ENSP40	UVWIS401	UVWIS400	AINSP404	AINSP403	AINSP402	AINSP401	AINSP400
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
	Function	REG0 enable 0: Disable 1: Enable	Phase select (for Vector Engine) 00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
ADAPSET41 0x4003_00A9	Bit symbol	ENSP41	UVWIS411	UVWIS410	AINSP414	AINSP413	AINSP412	AINSP411	AINSP410
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
	Function	REG1 enable 0: Disable 1: Enable	Phase select (for Vector Engine) 00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
ADAPSET42 0x4003_00AA	Bit symbol	ENSP42	UVWIS421	UVWIS420	AINSP424	AINSP423	AINSP422	AINSP421	AINSP4_0
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
	Function	REG2 enable 0: Disable 1: Enable	Phase select (for Vector Engine) 00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
ADAPSET43 0x4003_00AB	Bit symbol	ENSP43	UVWIS431	UVWIS430	AINSP434	AINSP433	AINSP432	AINSP431	AINSP430
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
	Function	REG3 enable 0: Disable 1: Enable	Phase select (for Vector Engine) 00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.



PMD Trigger Program Register 5(ADPSET5)

		7	6	5	4	3	2	1	0
ADAPSET50 0x4003_00AC	Bit symbol	ENSP50	UVWIS501	UVWIS500	AINSP504	AINSP503	AINSP502	AINSP501	AINSP500
	Read/Write	R/W	R/W	R	R/W				
	After reset	0	0		0				
ADBPSET50 0x4003_02AC	Function	REG0 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit ) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		15	14	13	12	11	10	9	8
ADAPSET51 0x4003_00AD	Bit symbol	ENSP51	UVWIS511	UVWIS510	AINSP514	AINSP513	AINSP512	AINSP511	AINSP510
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET51 0x4003_02AD	Function	REG1 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		23	22	21	20	19	18	17	16
ADAPSET52 0x4003_00AE	Bit symbol	ENSP52	UVWIS521	UVWIS520	AINSP524	AINSP523	AINSP522	AINSP521	AINSP520
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET52 0x4003_02AE	Function	REG2 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		31	30	29	28	27	26	25	24
ADDPSET53 0x4003_00AF	Bit symbol	ENSP53	UVWIS531	UVWIS530	AINSP534	AINSP533	AINSP532	AINSP531	AINSP530
	Read/Write	R/W	R/W		R/W				
	After reset	0	0		0				
ADBPSET53 0x4003_02AF	Function	REG3 enable  0: Disable 1: Enable	Phase select (for Vector Engine)  00: Not specified 01: U 10: V 11: W		AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

### 16.3.6 Timer Trigger Program Registers

AD conversion can be started by trigger from Timer5(TMRB5). There are twelve 8-bit registers for programming timer triggers. Setting the <ENST<sub>m</sub>> to "1" enables the ADTSET<sub>m</sub> register. The <AINST<sub>m</sub><sub>n</sub>> are used to select the AIN pin to be used. The numbers of the Timer Trigger Program Registers correspond to those of the AD Conversion Result Registers.

When finished this AD conversion, interrupt:INTADxTMR(x=A,B:ADC unit) is generated.

(m= 0 to 11, n= 0 to 4)

Timer Trigger Program Register 04 (ADTSET04)

		7	6	5	4	3	2	1	0
	Bit symbol	ENST0	-	-	AINST04	AINST03	AINST02	AINST01	AINST00
ADATSET0 0x4003_00B0	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBTSET0 0x4003_02B0	Function	REG0 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		15	14	13	12	11	10	9	8
	Bit symbol	ENST1	-	-	AINST14	AINST13	AINST12	AINST11	AINST10
ADATSET1 0x4003_00B1	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBTSET1 0x4003_02B1	Function	REG01 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		23	22	21	20	19	18	17	16
	Bit symbol	ENST2	-	-	AINST24	AINST23	AINST22	AINST21	AINST20
ADATSET2 0x4003_00B2	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBTSET2 0x4003_02B2	Function	REG02 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		31	30	29	28	27	26	25	24
	Bit symbol	ENST3	-	-	AINST34	AINST33	AINST32	AINST31	AINST30
ADATSET3 0x4003_00B3	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBTSET3 0x4003_02B3	Function	REG3 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.



	31	30	29	28	27	26	25	24
ADATSET11 0x4003_00BB	ENST11			AINST114	AINST113	AINST112	AINST111	AINST110
	R/W	R	R	R/W				
	After reset	0	0	0				
ADBTSET11 0x4003_02BB	Function REG11 enable 0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

### 16.3.7 Software Trigger Program Registers

AD conversion can be started by software. There are twelve 8-bit registers for programming software triggers. Setting the <ENSSn> to “1” enables the ADSSETn register. The <AINSSnm> are used to select the AIN pin to be used. The numbers of the Software Trigger Program Registers correspond to those of the Conversion Result Registers.

When finished this AD conversion, interrupt:INTADxSFT(x=A,B:ADC unit) is generated.

(n= 0 to 11, m= 0 to 4)

Software Trigger Program Register 04 (ADSSET04)

		7	6	5	4	3	2	1	0
	Bit symbol	ENSS0	-	-	AINSS_04	AINSS_03	AINSS_02	AINSS_01	AINSS_00
ADASSET0 0x4003_00BC	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBSSET0 0x4003_02BC	Function	REG0 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		15	14	13	12	11	10	9	8
	Bit symbol	ENSS1	-	-	AINSS14	AINSS13	AINSS12	AINSS11	AINSS10
ADASSET1 0x4003_00BD	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBSSET1 0x4003_02BD	Function	REG1 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		23	22	21	20	19	18	17	16
	Bit symbol	ENSS2	-	-	AINSS24	AINSS23	AINSS22	AINSS21	AINSS20
ADASSET2 0x4003_00BE	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBSSET2 0x4003_02BE	Function	REG2 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				
		31	30	29	28	27	26	25	24
	Bit symbol	ENSS3	-	-	AINSS34	AINSS33	AINSS32	AINSS31	AINSS30
ADASSET3 0x4003_00BF	Read/Write	R/W	R	R	R/W				
	After reset	0	0	0	0				
ADBSSET3 0x4003_02BF	Function	REG3 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.



	31	30	29	28	27	26	25	24
ADASSET11	ENSS11			AINSS114	AINSS113	AINSS112	AINSS111	AINSS110
0x4003_00C7	R/W	R	R	R/W				
	0	0	0	0				
ADBSSET11	Function	REG11 enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A)			
0x4003_02C7		0: Disable 1: Enable			00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved)			
					AIN select (ADC unit B)			
					00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)			

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

### 16.3.8 Constant Trigger Program Registers

The ADCs allow conversion triggers to be constantly enabled. There are twelve 8-bit registers for programming constant triggers. Setting the <ENSA<sub>m</sub>> to “1” enables the ADASET<sub>m</sub> register. The <AINSA<sub>n</sub>> are used to select the AIN pin to be used. The numbers of the Constant Trigger Program Registers correspond to those of the Conversion Result Registers.

(m= 0 to 11, n= 0 to 4)

Constant Trigger Program Register 0

	7	6	5	4	3	2	1	0
Bit symbol	ENSA0	-	-	AINSA04	AINSA03	AINSA02	AINSA01	AINSA00
Read/Write	R/W	R	R	R/W				
After reset	0	0	0	0				
Function	REG0 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.



Constant Trigger Program Register 11

	31	30	29	28	27	26	25	24
Bit symbol	ENSA11	-	-	AINSA114	AINSA113	AINSA112	AINSA111	AINSA110
Read/Write	R/W	R	R	R/W				
After reset	0	0	0	0				
Function	REG11 enable  0: Disable 1: Enable	Always read as 0.	Always read as 0.	AIN select (ADC unit A) 00000: AINA0 00001: AINA1 : 01110: AINA14 (01111 to 11111: Reserved) AIN select (ADC unit B) 00000: AINB0 00001: AINB1 : 10000: AIN16 (10001 to 11111: Reserved)				

Note: When AIN24 to AIN 31 (set value: 11000 to 11111) are set in the AIN select field, AIN0 is selected.

## 16.4 Operation Descriptions

### 16.4.1 Analog Reference Voltages

For the High-level and Low-level analog reference voltages, the AVDDA and AVSSA pins are used in ADC A and the AVDDB and AVSSB pins are used in ADC B. There are no registers for controlling current between AVDDx and AVSSx. Inputs to these pins are fixed. (x=A,B:ADC unit)

The internal amplifiers and comparators share the power supply and GND, which are connected to AMPVDD and AMPVSS respectively.

### 16.4.2 Starting AD Conversion

AD conversion is started by software or one of the following three trigger signals.

- PMD trigger (See “16.3.5 PMD Trigger Program Setting Registers.”)
- Timer trigger (TMRB5) (See “16.3.6 Timer Trigger Program Setting Registers.”)
- Software trigger (See “16.3.7 Software Trigger Program Registers.”)

These start triggers are given priorities as shown below.

PMD trigger 0 > ••• > PMD trigger 5 > Timer trigger > Software trigger > constant trigger

If the PMD trigger occurs while an AD conversion is in progress, the PMD trigger is handled stop the ongoing program and start AD conversion correspond to PMD trigger number.

If a higher-priority trigger occurs while an AD conversion is in progress, the higher-priority trigger is handled after the ongoing program is completed.

### 16.4.3 AD Conversion Monitoring Function

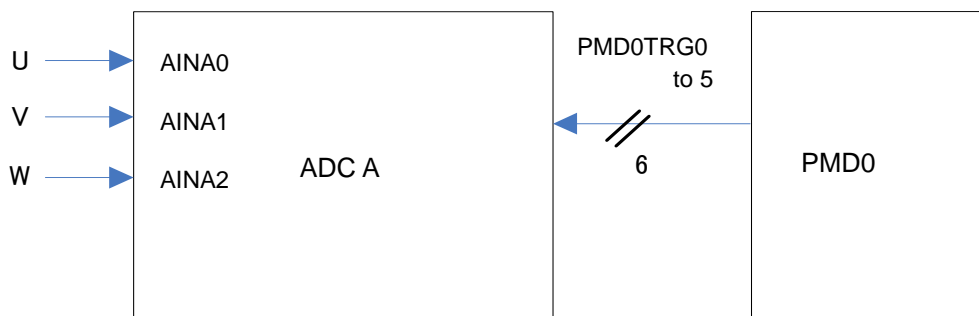
The ADCs have the AD conversion monitoring function. When this function is enabled, an interrupt is generated when a conversion result matches the specified comparison value.



## 16.5 Usage Examples

### 16.5.1 Successive Conversion Using PMD A (Three Shunts) and One ADC

The following shows a circuit diagram for AD conversion using one PMD for three shunts and one ADC.



Example ADC settings are shown below.

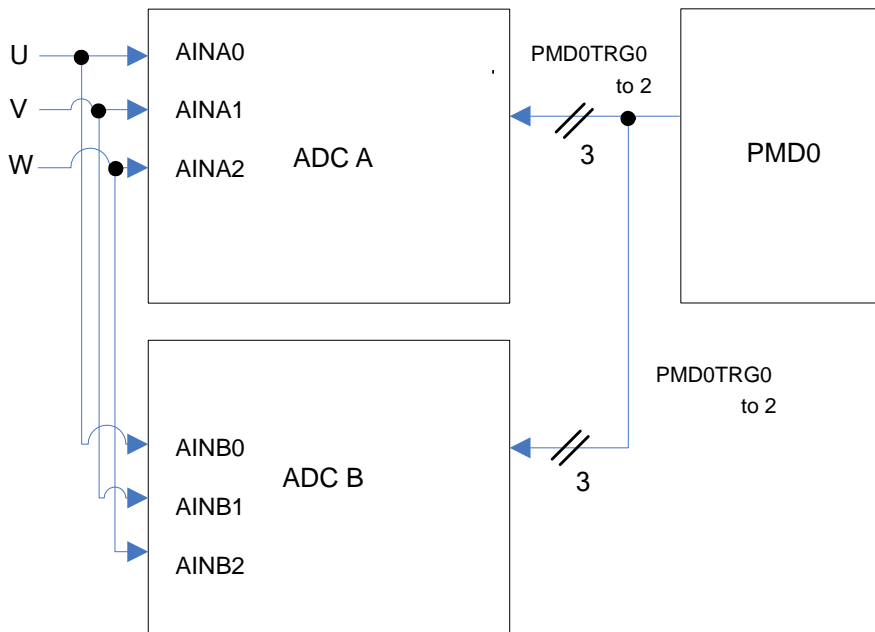
Program	0	1	2	3	4	5
reg0	U	V	W	V	W	U
reg1	V	W	U	U	V	W
INT	A	A	A	A	A	A

Programs 0 to 5 are assigned to trigger inputs PMD0TRG0 to 5. “reg0” and “reg1” indicate the PMD Trigger Program Registers ADPSETn0 and ADPSETn1. “U”, “V” and “W” indicate the phases of a motor. AIN inputs are selected to obtain these phases.

When a trigger input occurs, AD conversion is performed based on reg0 and reg1 sequentially, and then the interrupt signal (INTADAPDA) is generated.

### 16.5.2 Simultaneous Conversion Using One PMD (Three Shunts) and Two ADCs

The following shows a block diagram for AD conversion using one PMD for three shunts and two ADCs.



Example ADC settings are shown below.

#### ADC A

Program	0	1	2
reg0	U	V	W
INT	A	A	A

#### ADC B

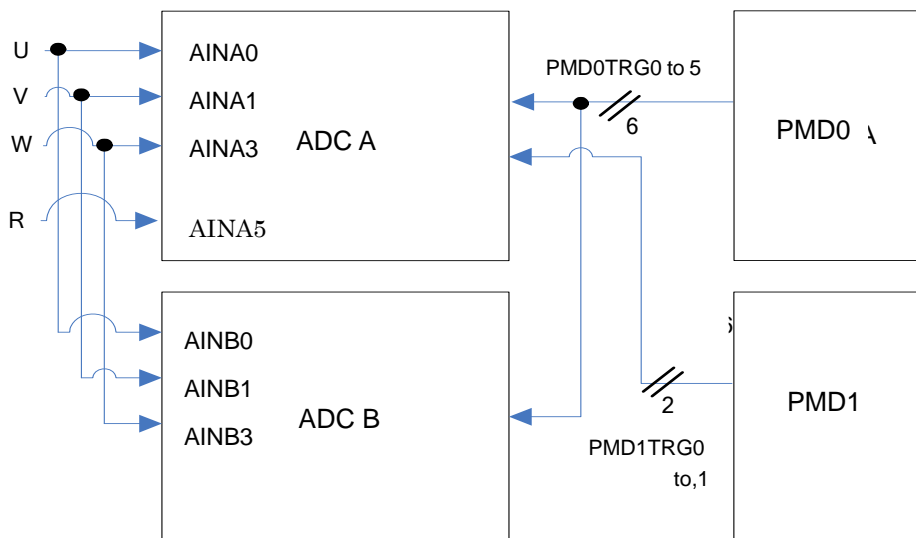
Program	0	1	2
reg0	V	W	U
INT	A	A	A

Programs 0 to 2 are assigned to three trigger inputs to ADC A and ADC B. “reg0” indicates the PMD Trigger Program Register ADPSETn0. “U”, “V” and “W” indicate the phases of a motor. AIN inputs are selected to obtain these phases.

When a trigger input occurs, ADC A and ADC B are started simultaneously to perform AD conversion based on reg0, and the interrupt signals (INTADAPDA , INTADBPDA) are output to ADC A and ADC B.

### 16.5.3 Successive Conversion Using PMD A (Three Shunts), PMD B (One Shunt) and Two ADCs

The following shows a circuit diagram for AD conversion using one PMD for three shunts, one PMD for one shunt and two ADCs.



Example ADC settings are shown below.

ADC A

Trigger	PMD0 0,3	PMD0 1,4	PMD0 2,5	PMD1 6	PMD1 7
Program	0	1	2	3	4
reg0	PMD0 U	PMD0 V	PMD0 W		
reg1				R	
reg2					R
INT	A	A	A	-	B

ADC B

Trigger	PMD0 0,3	PMD0 1,4	PMD0 2,5
Program	0	1	2
reg0	PMD0 V	PMD0 W	PMD0 U
INT	-	-	-

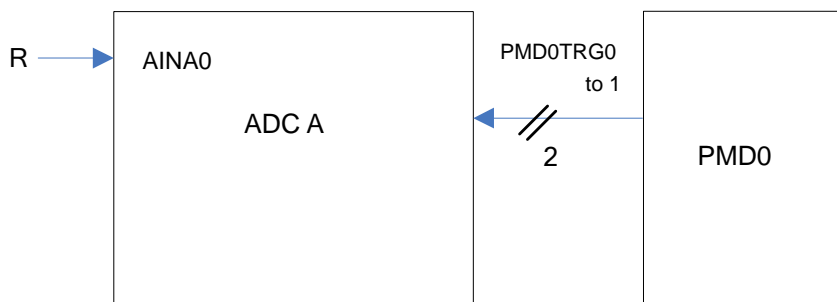
In ADC A, programs 0 to 2 are assigned to six trigger signals from PMD0 and programs 3 and 4 are assigned to two trigger signals from PMD1. In ADC B, programs 0 to 2 are assigned to six trigger signals from PMD0. “reg0”, “reg1” and “reg2” indicate the PMD Trigger Program Registers ADPSETn0, ADPSETn1 and ADPSETn2. “U”, “V” and “W” indicate the phases of a motor. AIN inputs are selected to obtain these phases. “R” indicates a resistor, where the AIN that is connected

to that resistor is set.

When a trigger input occurs, ADC A or ADC B is started to perform AD conversion. In ADC A, the interrupt (INTADAPDA) is generated for a trigger from PMD 0 and the interrupt (INTADAPDB) is generated for a trigger from PMD1. In ADC B, interrupt generation is disabled in this example.

### 16.5.4 Successive Conversion Using One PMD (One Shunt) and One ADC

The following shows a circuit diagram for AD conversion using one PMD for one shunt and one ADC.



Example ADC settings are shown below.

Trigger	PMD0	PMD0
	0	1
Program	0	1
reg0	R	-
reg1	-	R
INT	-	A

Programs 0 and 1 are assigned to two trigger signals from PMD0. “reg0” and “reg1” indicate the PMD Trigger Program Registers ADPSETn0 and ADPSETn1. “R” indicates a resistor, where the AIN input that is connected to that resistor is set.

When a trigger input occurs, the ADC is started to execute programs 0 and 1 sequentially. When program 1 is completed, the interrupt (INTADAPDA) is generated.

### 17. Op-Amps/Analog Comparators

The TMPM370 has four op-amps and analog comparators. Each op-amp amplifies a voltage received via an input port and feeds its output voltage into a 12-bit successive-approximation analog-to-digital (A/D) converter(s). These op-amps are used to amplify voltage differentials across shunt resistors for motor current measurement. The output of each op-amp is also fed into an analog comparator and compared to the corresponding reference voltage derived from an external resistor. The comparator provides an abnormal current indication to the EMG logic.

Figure 17-1 shows the block diagram of the op-amps/analog converters.

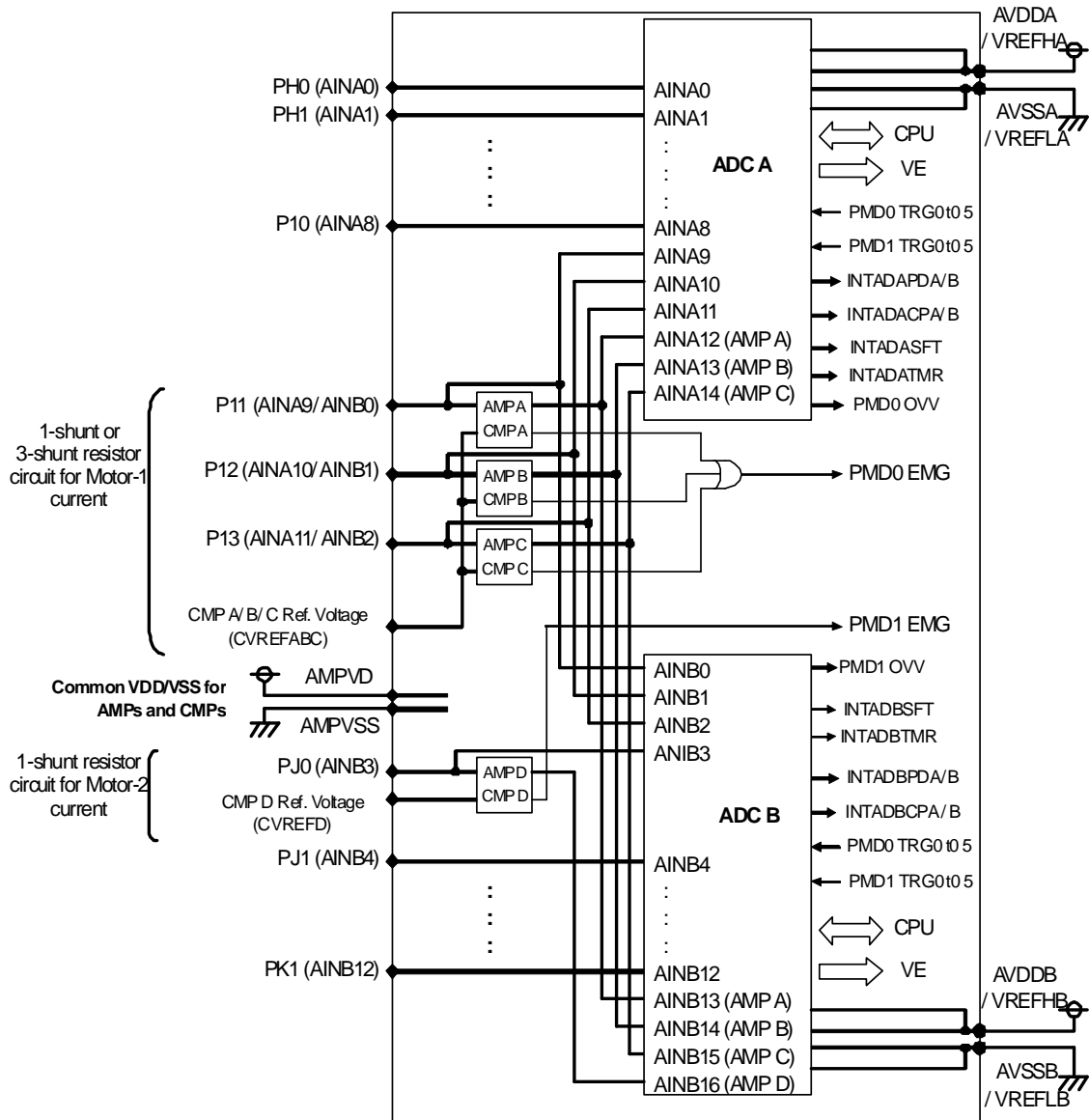


Figure 17-1 Op-Amps/Analog Converters Block Diagram

Op-amps A, B and C (AMP A/B/C) are intended to be used for 3-shunt current sensing. The amplified voltages from AMP A/B/C are fed into two A/D converters to allow simultaneous conversions of two shunt voltages out of three corresponding to the U, V and W phases of a motor.

The inputs of AMP A/B/C are also connected with the A/D converters directly; thus, even if AMP A/B/C are disabled, two shunt voltages can be converted into digital values at a time.

Op-amp D (AMP D) only supports 1-shunt current sensing. The amplified voltage from AMP D is fed into one A/D converter (AINB16).

See the block diagram of the op-amps/analog converters shown in Figure 17-1.

Analog comparators A/B/C/D are all connected to op-amps A/B/C/D; thus the comparators can compare an amplified voltage against the reference voltage. Each op-amp can be individually disabled by software; if disabled, the corresponding comparator takes as input a shunt voltage from an input port.

Analog comparators A/B/C, designed to be connected to a 3-shunt resistor circuit, have a common reference voltage (CMPREFABC).

Analog comparator D is designed to be connected to a 1-shunt resistor circuit; it has an independent reference voltage (CMPREFD).

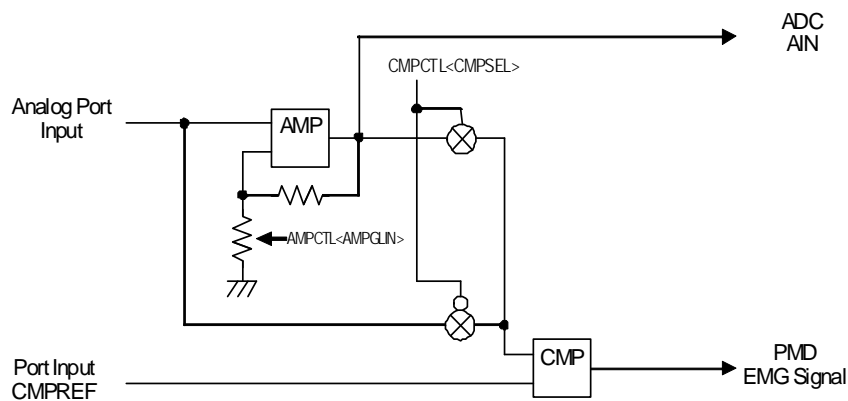


Figure 17-2 Op-Amp/Analog Comparator

## 17.1 Register List

The following table lists the control registers and their addresses for the op-amps and analog comparators.

Register		Address
Amp A Control Register	AMPCTLA	0x4003_0400
Amp B Control Register	AMPCTLB	0x4003_0408
Amp C Control Register	AMPCTLC	0x4003_0410
Amp D Control Register	AMPCTLD	0x4003_0418
Comparator A Control Register	CMPCTLA	0x4003_0420
Comparator B Control Register	CMPCTLB	0x4003_0428
Comparator C Control Register	CMPCTLC	0x4003_0430
Comparator D Control Register	CMPCTLD	0x4003_0438

## 17.2 Register Description

The op-amps are individually programmable through the Amp A/B/C/D Control Registers (AMPCTLA/AMPCTLB/AMPCTLC/AMPCTLD), which allow software to enable and disable each op-amp and select a voltage gain from eight levels.

The comparators are individually programmable through the Comparator A/B/C/D Control Registers (CMPCTLA/CMPCTLB/CMPCTLC/CMPCTLD), which allow software to enable and disable each comparator and select its input source (a port input or an op-amp output).

If an external op-amp is used instead of an on-chip op-amp, the on-chip op-amp should be disabled ( $AMPENx = 0$ ) and the comparator should be configured to accept the input port voltage, bypassing the associated op-amp ( $CMPSELx = 0$ ).

The following describes each control register.

Amp A/B/C/D Control Registers

AMPCTLx  
(x: A,B,C,D)

	7	6	5	4	3	2	1	0
Bit Symbol	/				AMPGLIN2	AMPGLIN1	AMPGLIN0	AMPEN
Read/Write	R	R	R	R	R/W			R/W
Default	0	0	0	0	000			0
Description	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Gain Select 000: 1.5x 100: 4.0x 001: 2.5x 101: 6.0x 010: 3.0x 110: 8.0x 011: 3.5x 111: 10.0x			AMP Enable 0: Standby 1: Enables AMP.

Comparator A/B/C/D Control Registers

CMPCTLx  
(x: A,B,C,D)

	7	6	5	4	3	2	1	0
Bit Symbol	/						CMPSEL	CMPEN
Read/Write	R	R	R	R	R	R	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Reading this bit returns a 0.	Input Select 0: Input port 1: Op-amp output	CMP Enable 0: Standby 1: Enables CMP.



## 18 Encoder Input Circuit (ENC)

The TMPM370FYFG/TMPM370FYDFG has a two-channel incremental encoder interface (ENC0/1), which can determine the direction and the absolute position of a motor, based on input signals from an incremental encoder.

The discussions in this chapter apply to ENC0. For ENC1, the names of registers, interrupt signals and pins in the following text should be replaced as appropriate, as shown in Table 18.1 to Table 18.3.

Table 18.1 List of the ENC Registers

Register	ENC0		ENC1	
	Register Symbol	Address	Register Symbol	Address
Encoder Input Control Register	EN0TNCR	0x4001_0400	EN1TNCR	0x4001_0500
Encoder Counter Reload Register	EN0RELOAD	0x4001_0404	EN1RELOAD	0x4001_0504
Encoder Compare Register	EN0INT	0x4001_0408	EN1INT	0x4001_0508
Encoder Counter	EN0CNT	0x4001_040C	EN1CNT	0x4001_050C

Table 18.2 Interrupt Sources

Interrupt Source	ENC0	ENC1
ENC interrupt	INTENC0	INTENC1

Table 18.3 Pin Names

Pin	ENC0	ENC1
Channel A input pin	PD0/ENCA0	PF2/ENCA1
Channel B input pin	PD1/ENCB0	PF3/ENCB1
Channel Z input pin	PD2/ENCZ0	PF4/ENCZ1

## 18.1 Outline

The ENC can be configured to operate in one of four different modes: Encoder mode, two Sensor modes (Event count mode, Timer count mode) and Timer mode. And it also has some functions as below.

- Supports incremental encoders and Hall sensor ICs. (signals of Hall sensor IC can be input directly)
- 24-bit general-purpose timer mode
- Multiply-by-4 (multiply-by-6) logic
- Direction discriminator
- 24-bit counter
- Comparator enable/disable
- Interrupt request output
- Digital noise filters for input signals

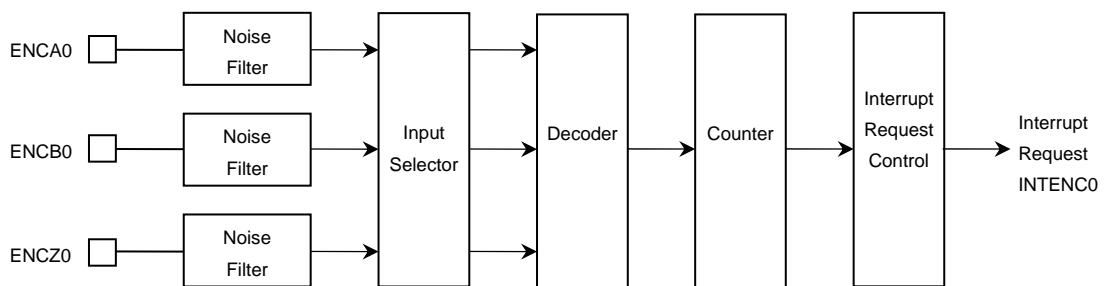


Figure 18.1 ENC Block Diagram

### 18.1.1 Encoder Mode

In Encoder mode, the ENC provides high-speed position tracking, based on the A/B or A/B/Z input signals from an incremental encoder.

- Event (rotation pulse) sensing: Programmable to generate an interrupt on each event.
- Event counter: Programmable to generate an interrupt at a preset count (for positional displacement calculation).
- Direction discrimination
- Up/down counting (dynamically selectable)
- Programmable counter period

### 18.1.2 Sensor Modes

In Sensor modes, the ENC provides low-speed position (zero-cross) tracking, based on either the U/V or U/V/W input signals from a Hall sensor.

There are two operating modes: Event Count mode and Timer Count mode (which runs with fsys).

#### 18.1.2.1 Event Count Mode

- Event (rotation pulse) sensing: Programmable to generate an interrupt on each event.
- Event counter: Programmable to generate an interrupt at a preset count (for positional displacement calculation).
- Direction discrimination

#### 18.1.2.2 Timer Count Mode

- Event (rotation pulse) sensing: Programmable to generate an interrupt on each event.
- Timer counting operation
- Direction discrimination
- Input capture functions
  - Event capture (event interval measurement): Programmable to generate an interrupt.
  - Software capture
- Event timeout error (timer compare): Programmable to generate an interrupt at a preset count.
- Revolution error: Error flag that indicates a change of the rotation direction

### 18.1.3 Timer Mode

The ENC can serve as a 24-bit general-purpose timer.

- 24-bit up-counter
- Counter clear: via a software clear bit, or at a preset count, or by an external trigger input, or on overflow of the free-running counter.
- Timer compare: Programmable to generate an interrupt at a preset count.
- Input capture functions
  - External trigger capture: Programmable to generate an interrupt.
  - Software capture

## 18.2 Control Registers

### Encoder 0 Input Control Register

EN0TNCR  
(0x4001\_0400)

	31	30	29	28	27	26	25	24	
Bit Symbol	-	-	-	-	-	-	-	-	
Read/Write	R	R	R	R	R	R	R	R	
Default	0	0	0	0	0	0	0	0	
Description	Reading these bits returns a 0.								
	23	22	21	20	19	18	17	16	
Bit Symbol	-	-	-	-	-	MODE1	MODE0	P3EN	
Read/Write	R	R	R	R	R	R/W	R/W	R/W	
Default	0	0	0	0	0	0	0	0	
Description	Reading these bits returns a 0.					ENC Operating Mode 00: Encoder mode 01: Sensor Event Count mode 10: Sensor Timer Count mode 11: Timer mode		[In Sensor mode] 2/3-Phase Input Select 0: 2-phase 1: 3-phase	
	15	14	13	12	11	10	9	8	
Bit Symbol	CMP	REVERR	U/D	ZDET	SFTCAP	ENCLR	ZESSEL	CMPEN	
Read/Write	R	R	R	R	W	W	R/W	R/W	
Default	0	0	0	0	0	0	0	0	
Description	Compare Flag 0: — 1: Counter compared  This bit is cleared on a read.	[In Sensor Timer Count mode] Revolution Error 0: — 1: Error occurred.  This bit is cleared on a read.	Rotation Direction 0: CCW 1: CW	Z_Detected 0: Not detected 1: Z phase detected	[In Sensor Timer Count and Timer modes] Software Capture 0: — 1: Software capture	Encoder Counter Clear 0: — 1: Clears the counter.	[In Timer mode] Z Trigger Edge Select 0: Rising edge 1: Falling edge	Compare Enable 0: Compare disabled 1: Compare enabled	
	7	6	5	4	3	2	1	0	
Bit Symbol	ZEN	ENRUN	NR1	NR0	INTEN	ENDEV2	ENDEV1	ENDEV0	
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W	
Default	0	0	0	0	0	0	0	0	
Description	Z Phase Enable 0: Disabled 1: Enabled	ENC Run 0: Disabled 1: Enabled	Noise Filter 00: No filtering 01: Filters out pulses narrower than 31/fsys (387.5 ns@80 MHz). 10: Filters out pulses narrower than 63/fsys(787.5 ns@80 MHz). 11: Filters out pulses narrower than 127/fsys(1587 ns@80 MHz).		ENC Interrupt Enable 0: Disabled 1: Enabled	Encoder Pulse Division Factor 000: +1 001: +2 010: +4 011: +8 100: +16 101: +32 110: +64 111: +128			

Description:

<MODE1:0>: ENC Operating Mode

- 00: Encoder mode
- 01: Sensor Event Count mode
- 10: Sensor Timer Count mode
- 11: Timer mode

<MODE1:0> selects an operating mode for the ENC.

Operating modes are defined by <MODE1:0>, <P3EN> and <ZEN> as shown in the following table. There are a total of eight operating modes.

<MODE1>	<MODE0>	<ZEN>	<P3EN>	Input signal Used	Operating Mode
0	0	0	0	A, B	Encoder mode
		1		A, B, Z	Encoder mode (using Z)
0	1	0	0	U, V	Sensor Event Count mode (2 phase inputs)
			1	U, V, W	Sensor Event Count mode (3 phase inputs)
1	0	0	0	U, V	Sensor Timer Count mode (2 phase inputs)
			1	U, V, W	Sensor Timer Count mode (3 phase inputs)
1	1	0	0	-	Timer mode
		1		Z	Timer mode (using Z)

<P3EN>: 2/3-Phase Input Select

0: 2-phase  
1: 3-phase

<P3EN> selects the number of phase input pins used.  
If <P3EN> is cleared to 0, the ENC decodes two phase inputs.  
If <P3EN> is set to 1, the ENC decodes three phase inputs.  
In Timer mode, this bit has no effect.

**Note:** <P3EN> must always be cleared in Encoder mode, irrespective of the number of phase input pins used.

<CMP>: Compare Flag

0: —  
1: Counter compared

<CMP> is set to 1 when the counter value has been compared to the value programmed in the EN0INT register.  
<CMP> is cleared to 0 on a read. <CMP> remains cleared when <ENRUN> = 0. Writing to <CMP> has no effect.

<REVERR>: Revolution Error

0: —  
1: Error occurred.

In Sensor Timer Count mode, <REVERR> is set to 1 when a change in the rotation direction has been detected. <REVERR> is cleared to 0 on a read. <REVERR> remains cleared when <ENRUN> = 0. Writing to <REVERR> has no effect.  
This bit has an effect only in Sensor Timer Count mode.

**Note:** Once software has changed the operating mode of the ENC, <REVERR> must be cleared by reading it.

<U/D>: Rotation Direction

0: Counterclockwise (CCW)  
1: Clockwise (CW)

The quadrature signals A and B identify the motor rotation direction. <U/D> is set to 1 when the CW direction is indicated (signal A of the incremental encoder signal is ahead of signal B). <U/D> is cleared to 0 when the CCW direction is indicated (signal A is behind signal B). <U/D> remains cleared while <ENRUN> = 0.

<ZDET>: Z Detected  
0: Not detected  
1: Detected

<ZDET> is set to 1 on the first edge of Z input signal (ENCZ) after <ENRUN> is written from 0 to 1. This occurs on a rising edge of the signal Z during CW rotation or on a falling edge of Z during CCW rotation. <ZDET> remains cleared while <ENRUN> = 0. <ZEN> has no influence on the value of <ZDET>. <ZDET> remains cleared in Sensor Event Count and Sensor Timer Count modes.

<SFTCAP>: Software Capture  
0: —  
1: Software capture

If <SFTCAP> is set to 1, the value of the encoder counter is captured into the ENOCNT register. Writing a 0 to <SFTCAP> has no effect. Reading <SFTCAP> always returns a 0. In Encoder and Sensor Event Count modes, <SFTCAP> has no effect; a write of a 1 to this bit is ignored.

<ENCLR>: Encoder Counter Clear  
0: —  
1: Clears the encoder counter.

Writing a 1 to <ENCLR> clears the encoder counter to 0. Once cleared, the encoder counter restarts counting from 0. Writing a 0 to <ENCLR> has no effect. Reading <ENCLR> always returns a 0.

<ZESEL>: Z Trigger Edge Select  
0: Uses a rising edge of the ENCZ as an external trigger input.  
1: Uses a falling edge of the ENCZ as an external trigger input.

<ZESEL> selects the edge of the ENCZ that should be used as an external trigger in Timer mode. In the other operating modes, <ZESEL> has no effect.

<CMPEN>: Compare Enable  
0: Compare disabled  
1: Compare enabled

If <CMPEN> is set to 1, the value of the encoder counter is compared to the value programmed in the ENOINT register. If <CMPEN> is cleared to 0, this comparison is not done.

<ZEN>: Z Phase Enable  
0: Disabled  
1: Enabled

- In Encoder mode  
<ZEN> controls whether to clear the encoder counter (ENOCNT) on the rising or falling edge of Z. When <ZEN> = 1, the encoder counter is cleared on the rising edge of the ENCZ input if the motor is rotating in the CW direction; the encoder counter is cleared on the falling edge of ENCZ if the motor is rotating in the CCW direction. If the edges of ENCLK (multiply\_by\_4 clock derived from the decoded A and B signals) and the edge of ENCZ coincide, the encoder counter is cleared to 0 without incrementing or decrementing (i.e., the clear takes precedence).

- In Timer mode  
<ZEN> controls whether to use the ENCZ signal as an external trigger input.  
When <ZEN> = 1, the value of the encoder counter is captured into the ENOINT register and cleared to 0 on the edge of ENCZ selected by <ZESEL>.

In the other operating modes, <ZEN> has no effect.

<ENRUN>: ENC Run

- 0: Disabled
- 1: Enabled

Setting <ENRUN> to 1 and clearing <ZDET> to 0 enables the encoder operation.  
Clearing <ENRUN> to 0 disables the encoder operation.

There are counters and flags that are and are not cleared even if the <ENRUN> bit is cleared to 0.

The following table shows the states of the counters and flags, depending on the value of <ENRUN>.

Internal Counter / Flag	When <ENRUN> = 0 (After reset)	When <ENRUN> = 1 (During active operation)	When <ENRUN> = 0 (During idle mode)	How to clear a counter or flag when <ENRUN> = 0
Encoder counter	0x000000	Counting	Keeps the current value.	Software clear (Write a 1 to <ENCLR>.)
Noise filter counter	0y0000000	Counting up	Counting up (Continues with noise filtering.)	Cleared only by reset.
Encoder pulse division counter	0x00	Counting down	Stopped and cleared	Cleared when <ENRUN> = 0.
Compare flag <CMP>	0	Set to 1 upon comparison; cleared to 0 on a read.	Cleared	Cleared when <ENRUN> = 0.
Revolution Error flag <REVERR>	0	Set to 1 upon an error; cleared to 0 on a read.	Cleared	Cleared when <ENRUN> = 0.
Z Detected flag <ZDET>	0	Set to 1 on detection of Z.	Cleared	Cleared when <ENRUN> = 0.
Rotation Direction Bit <U/D>	0	Set or cleared according to rotation direction.	Cleared	Cleared when <ENRUN> = 0.

<NR1:0>: Noise Filter

- 00: No filtering
- 01: Filters out pulses narrower than 31/fsys as noises.
- 10: Filters out pulses narrower than 63/fsys as noises.
- 11: Filters out pulses narrower than 127/fsys as noises.

The digital noise filters remove pulses narrower than the width selected by <NR1:0>.

<INTEN>: ENC Interrupt Enable

- 0: Disabled
- 1: Enabled

<INTEN> enables and disables the ENC interrupt.  
Setting <INTEN> to 1 enables interrupt generation. Clearing <INTEN> to 0 disables interrupt generation.



<ENDEV2:0>: Encoder Pulse Division Factor

000: ÷1  
 001: ÷2  
 010: ÷4  
 011: ÷8  
 100: ÷16  
 101: ÷32  
 110: ÷64  
 111: ÷128

The frequency of the encoder pulse is divided by the factor specified by <ENDEV2:0>.  
 The divided signal determines the interval of the event interrupt.

### Encoder 0 Counter Reload Register

ENORELOAD (0x4001_0404)	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R	R	R	R	R	R	R	R
Default	0	0	0	0	0	0	0	0
Description	Reading these bits returns a 0.							
	23	22	21	20	19	18	17	16
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R	R	R	R	R	R	R	R
Default	0	0	0	0	0	0	0	0
Description	Reading these bits returns a 0.							
	15	14	13	12	11	10	9	8
Bit Symbol	RELOAD15	RELOAD14	RELOAD13	RELOAD12	RELOAD11	RELOAD10	RELOAD9	RELOAD8
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	(See the description below.)							
	7	6	5	4	3	2	1	0
Bit Symbol	RELOAD7	RELOAD6	RELOAD5	RELOAD4	RELOAD3	RELOAD2	RELOAD1	RELOAD0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	Setting the Encoder Counter Period (Multiplied by 4 (or 6)) 0x0000 thru. 0xFFFF When Z is used: Specifies the number of counter pulses per revolution. When Z is not used: Specifies the number of counter pulses per revolution minus 1.							

Description:

<RELOAD15:0>: setting the Encoder Counter Period

- In Encoder mode  
 <RELOAD15:0> defines the encoder counter period multiplied by 4.  
 If the encoder counter is configured as an up-counter, it increments up to the value programmed in <RELOAD15:0> and then wraps around to 0 on the next ENCLK. If the encoder counter is configured as a down-counter, it decrements to 0 and then is reloaded with the value of <RELOAD15:0> on the next ENCLK.

The ENORELOAD register is only used in Encoder mode.

## Encoder 0 Compare Register

EN0INT (0x4001_0408)	31	30	29	28	27	26	25	24
Bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R	R	R	R	R	R	R	R
Default	0	0	0	0	0	0	0	0
Description	Reading these bits returns a 0.							
	23	22	21	20	19	18	17	16
Bit Symbol	INT23	INT22	INT21	INT20	INT19	INT18	INT17	INT16
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	See the description below. <INT23:16> are used only in Sensor Timer Count mode and Timer mode							
	15	14	13	12	11	10	9	8
Bit Symbol	INT15	INT14	INT13	INT12	INT11	INT10	INT9	INT8
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	See the description below.							
	7	6	5	4	3	2	1	0
Bit Symbol	INT7	INT6	INT5	INT4	INT3	INT2	INT1	INT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default	0	0	0	0	0	0	0	0
Description	In Encoder mode: Generates an interrupt at the programmed encoder pulse count (0x0000 thru. 0xFFFF). In Sensor Event Count mode: Generates an interrupt at the programmed encoder pulse count (0x0000 thru. 0xFFFF). In Sensor Timer Count mode: Generates an interrupt when the counter has reached the programmed value without detecting a pulse (0x000000 thru. 0xFFFFFF). In Timer mode: Generates an interrupt when the counter value has reached the programmed value (0x000000 thru. 0xFFFFFF).							

Description:

<INT15:0>: Counter Compare Value

- In Encoder mode  
 <CMP> is set to 1 when the value of the encoder counter has reached the value of <INT15:0>, provided <CMPEN> is set to 1. At this time, the event counter interrupt (INTENC) is asserted if <INTEN> is set to 1.  
 However, when <ZEN> = 1, INTENC is not asserted until <ZDET> is set to 1. In Encoder mode, <INT23:16> are not used (and are ignored even if programmed).
- In Sensor Event Count mode  
 <CMP> is set to 1 when the value of the encoder counter has reached the value of <INT15:0>, provided <CMPEN> is set to 1. At this time, the interrupt request (INTENC) is asserted if <INTEN> is set to 1. The value of <ZEN> has no effect on this interrupt generation.  
 In Sensor Event Count mode, <INT23:16> are not used (and are ignored even if programmed).
- In Sensor Timer Count mode  
 <CMP> is set to 1 when the value of the encoder counter has reached the value of <INT23:0>, provided <CMPEN> is set to 1. This indicates the absence of a pulse for an abnormally long period. At this time, the interrupt request (INTENC) is asserted if <INTEN> is set to 1. The value of <ZEN> has no effect on this interrupt generation.
- In Timer mode  
 <CMP> is set to 1 when the value of the encoder counter has reached the value of <INT23:0>, provided <CMPEN> is set to 1. At this time, the timer compare interrupt (INTENC) is asserted if <INTEN> is set to 1. The value of <ZEN> has no effect on this interrupt generation.

## Encoder 0 Counter Register

EN0CNT (0x4001_040C)		31	30	29	28	27	26	25	24
Bit Symbol		-	-	-	-	-	-	-	-
Read/Write		R	R	R	R	R	R	R	R
Default		0	0	0	0	0	0	0	0
Description	Reading these bits returns a 0.								
		23	22	21	20	19	18	17	16
Bit Symbol		CNT23	CNT22	CNT21	CNT20	CNT19	CNT18	CNT17	CNT16
Read/Write		R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default		0	0	0	0	0	0	0	0
Description	See the description below. <CNT23:16> are used only in Sensor Timer Count mode and Timer mode. In Encoder mode and Sensor Event Count mode, reading these bits returns a 0.								
		15	14	13	12	11	10	9	8
Bit Symbol		CNT15	CNT14	CNT13	CNT12	CNT11	CNT10	CNT9	CNT8
Read/Write		R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default		0	0	0	0	0	0	0	0
Description	See the description below.								
		7	6	5	4	3	2	1	0
Bit Symbol		CNT7	CNT6	CNT5	CNT4	CNT3	CNT2	CNT1	CNT0
Read/Write		R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
Default		0	0	0	0	0	0	0	0
Description	In Encoder mode: Number of encoder pulses 0x0000 thru. 0xFFFF In Sensor mode: Pulse detection time or the encoder counter value captured under software control 0x000000 thru. 0xFFFFF In Timer mode: Encoder counter value captured by hardware signaling or under software control 0x000000 thru. 0xFFFFF								

## Description:

## &lt;CNT15:0&gt;: Encoder Counter/Captured Value

- In Encoder mode  
The value of encoder count can be read out from <CNT15:0>.  
In Encoder mode, the encoder counter counts up or down on each encoder pulse (ENCLK).  
During CW rotation, encoder counter counts up; when it has reached the value of <RELOAD15:0>, it wraps around to 0 on the next ENCLK.  
During CCW rotation, encoder counter counts down; when it has reached 0, it is reloaded with the value of <RELOAD15:0> on the next ENCLK.
- In Sensor Event Count mode  
The value of encoder count can be read out from <CNT15:0>.  
In Sensor Event Count mode, the encoder counter counts up or down on each encoder pulse (ENCLK).  
During CW rotation, encoder counter counts up; when it has reached 0xFFFF, it wraps around to 0 on the next ENCLK.  
During CCW rotation, encoder counter counts down; when it has reached 0, it wraps around to 0xFFFF on the next ENCLK.

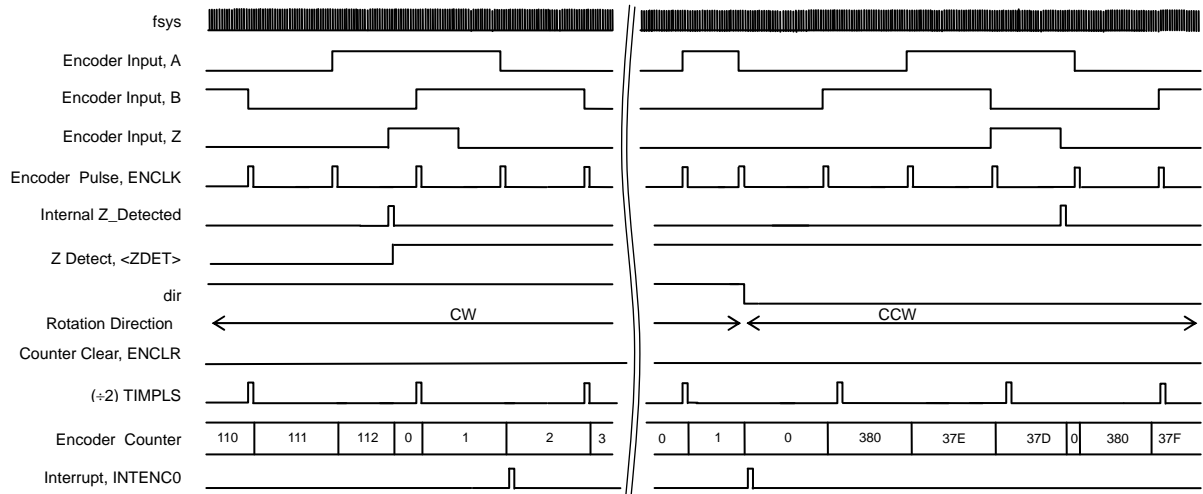
- In Sensor Timer Count mode
  - <CNT23:0> contains the value of the encoder counter captured by either the encoder pulse (ENCLK) or software setting <SFTCAP> to 1. The captured value in <CNT23:0> is cleared to 0 on system reset. It can also be cleared by clearing the counter via setting <ENCLR> to 1 and then setting <SFTCAP> to 1.
  - In Sensor Timer Count mode, the encoder counter is configured as a free-running counter that counts up with fsys. The encoder counter is cleared to 0 when the encoder pulse (ENCLK) is detected. When it has reached 0xFFFFFFFF, it wraps around to 0 automatically.
- In Timer mode
  - <CNT23:0> contains the value of the encoder counter captured by software setting <SFTCAP> to 1. When <ZEN> = 1, the value of the encoder counter is also captured into <CNT23:0> on the Z ENCZ edge selected by <ZESEL>.
  - In Timer mode, the encoder counter is configured as a free-running counter that counts up with fsys. When it has reached 0xFFFFFFFF, it wraps around to 0 automatically.

### 18.3 Functional Description

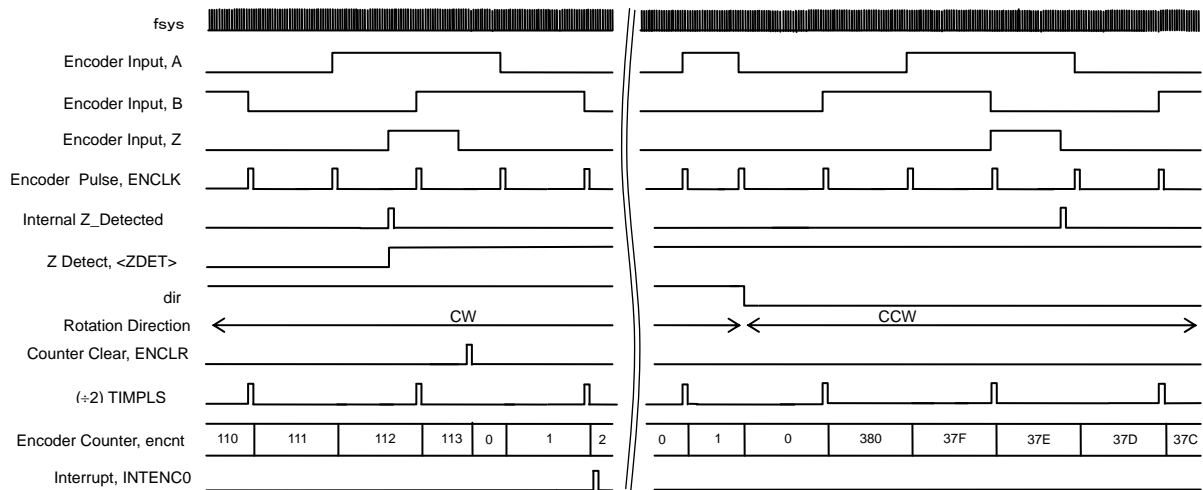
#### 18.3.1 Operating Modes

##### 18.3.1.1 Encoder Mode

(1) When <ZEN> = 1 (<RELOAD> = 0x0380, <EN0INT> = 0x0002)



(2) When <ZEN> = 0 (<RELOAD> = 0x0380, <EN0INT> = 0x0002)



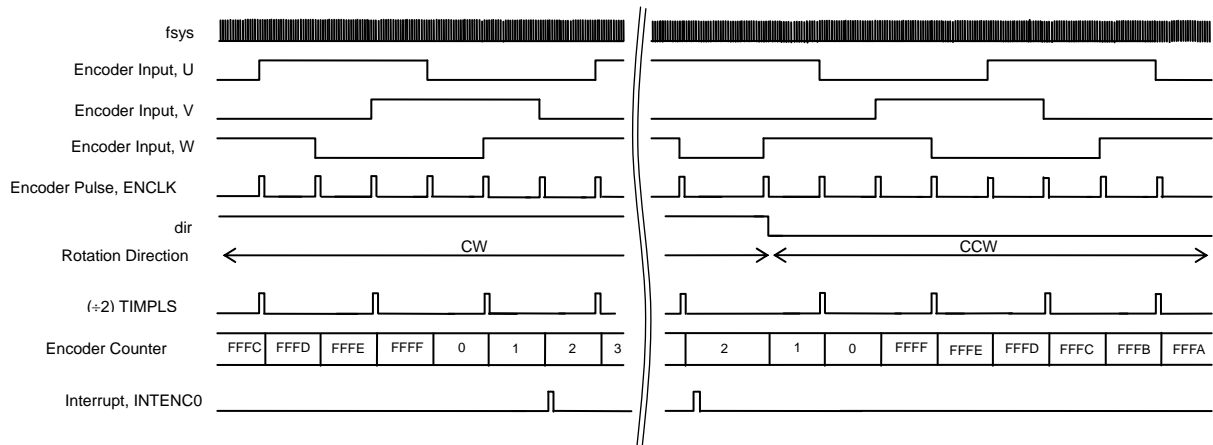
- In Encoder mode, the incremental encoder inputs of the TMPM370 should be connected to the A, B and Z channels. The encoder counter counts pulses of ENCLK, which is multiplied\_by\_4 clock derived from the decoded A and B quadrature signals.
- During CW rotation (i.e., when A leads B), the encoder counter counts up; when it has reached the value of <RELOAD>, it wraps around to 0 on the next ENCLK.
- During CCW rotation (i.e., when A lags B), the encoder counter counts down; when it has reached 0x0000, it is reloaded with the value of <RELOAD> on the next ENCLK.
- Additionally, when <ZEN> = 1, the encoder counter is cleared to 0 on the rising edge of Z during

CW rotation and on the falling edge of Z during CCW rotation (at the internal Z\_Detected timing). If the ENCLK and Z edges coincide, the encoder counter is cleared to 0 without incrementing or decrementing.

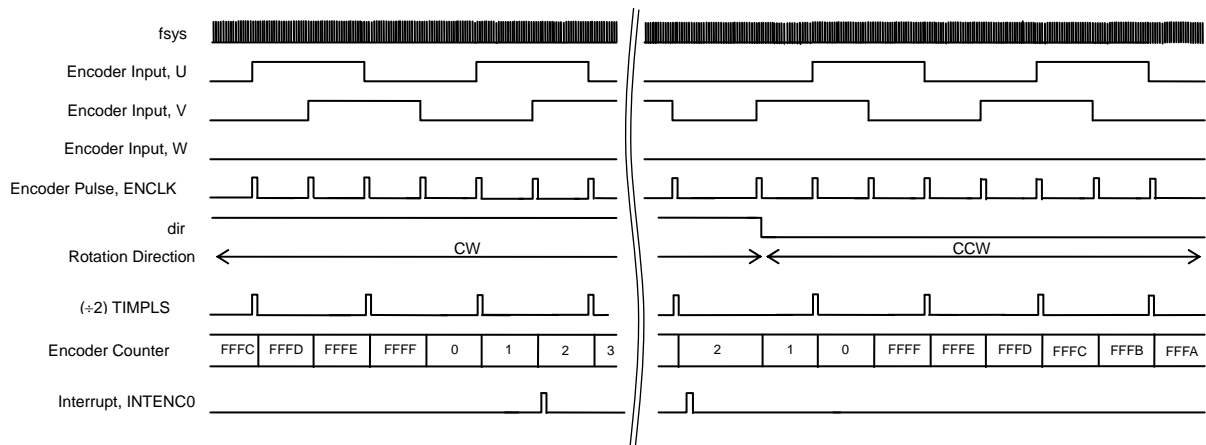
- When <ENCLR> is set to 1, causing the encoder counter to be cleared to 0.
- <U/D> is set to 1 during CW rotation and cleared to 0 during CCW rotation.
- TIMPLS, which is derived by dividing ENCLK by a programmed factor, can be driven out externally.
- If <CMPEN> is set to 1, an interrupt is generated when the value of the encoder counter has reached the value of <EN0INT>. When <ZEN> = 1, however, an interrupt does not occur while <ZDET> = 0.
- Clearing <ENRUN> to 0 clears <ZDET> and <U/D> to 0.

### 18.3.1.2 Sensor Event Count Mode

(1) When <P3EN> = 1 (<EN0INT> = 0x0002)



(2) When <P3EN> = 0 (<EN0INT> = 0x0002)

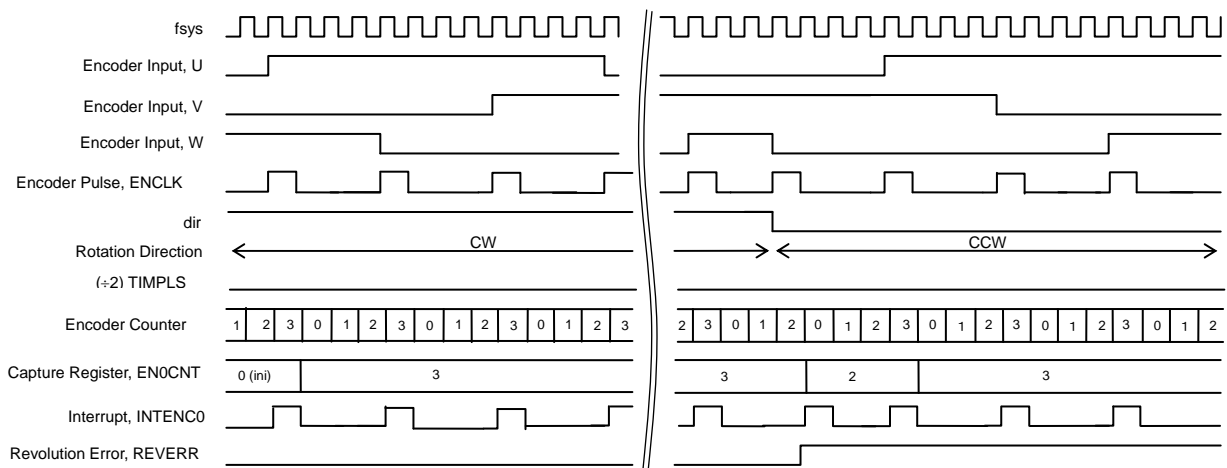


- In Sensor Event Count mode, the Hall sensor inputs of the TMPM370 should be connected to the U, V and W channels. The encoder counter counts the pulses of ENCLK, which is either multiplied\_by\_4 clock (when <P3EN> = 0) derived from the decoded U and V signals or multiplied\_by\_6 clock (when <P3EN> = 1) derived from the decoded U, V and W signals.
- During CW rotation, the encoder counter counts up; when it has reached 0xFFFF, it wraps around to 0 on the next ENCLK.

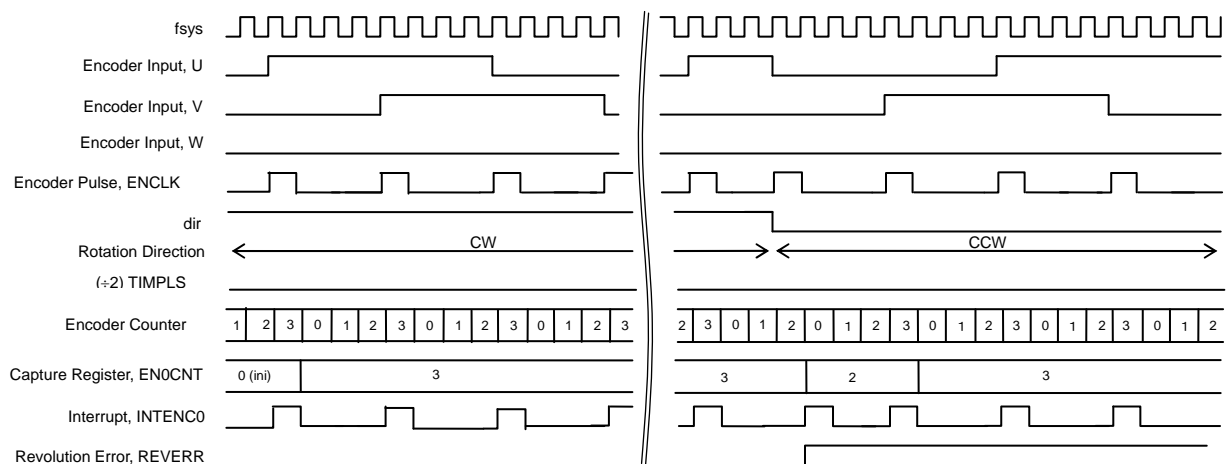
- During CCW rotation, the encoder counter counts down; when it has reached 0x0000, it wraps around to 0xFFFF on the next ENCLK.
- When <ENCLR> is set to 1, causing the internal counter to be cleared to 0.
  - <U/D> is set to 1 during CW rotation and cleared to 0 during CCW rotation.
  - TIMPLS, which is derived by dividing ENCLK by a programmed factor, can be driven out externally.
  - If <CMPEN> is set to 1, an interrupt is generated when the value of the internal counter has reached the value of <EN0INT>.
  - Clearing <ENRUN> to 0 clears <U/D> to 0.

### 18.3.1.3 Sensor Timer Count Mode

(1) When <P3EN> = 1 (<EN0INT> = 0x0002)



(2) When <P3EN> = 0 (<EN0INT> = 0x0002)



- In Sensor Timer Count mode, the Hall sensor inputs of the TMPM370 should be connected to the U, V and W channels. The encoder counter measures the interval between two contiguous pulses of ENCLK, which is either multiplied\_by\_4 clock (when <P3EN> = 0) derived from the decoded U and V signals or multiplied\_by\_6 clock (when <P3EN> = 1) derived from the decoded U, V and W signals.
- The encoder counter always counts up; it is cleared to 0 on ENCLK. When the encoder counter

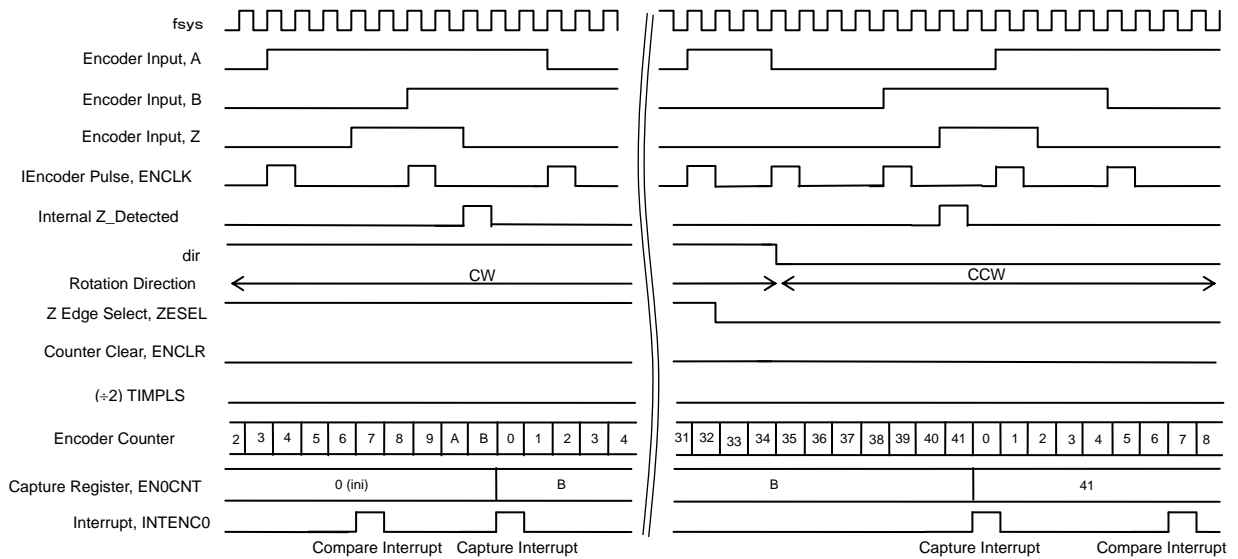
has reached 0xFFFFFFFF, it wraps around to 0.

- When <ENCLR> is set to 1, causing the encoder counter to be cleared to 0.
- ENCLK causes the value of the encoder counter to be captured into the EN0CNT register. The captured counter value can be read out of EN0CNT.
- Setting the software capture bit, <SFTCAP>, to 1 causes the value of the encoder counter to be captured into the ENCNT register. This capture operation can be performed at any time. The captured counter value can be read out of ENCNT.
- Clearing <ENRUN> to 0 clears <U/D> to 0.
- If <CMPEN> is set to 1, an interrupt is generated when the value of the encoder counter has reached the value of <EN0INT>.
- <U/D> is set to 1 during CW rotation and cleared to 0 during CCW rotation.
- <REVERR> is set to 1 when the rotation direction has changed. This bit is cleared to 0 on a read.
- The value of the ENCNT register (the captured value) is retained, regardless of the value of <ENRUN>. The ENCNT register is only cleared by a reset.

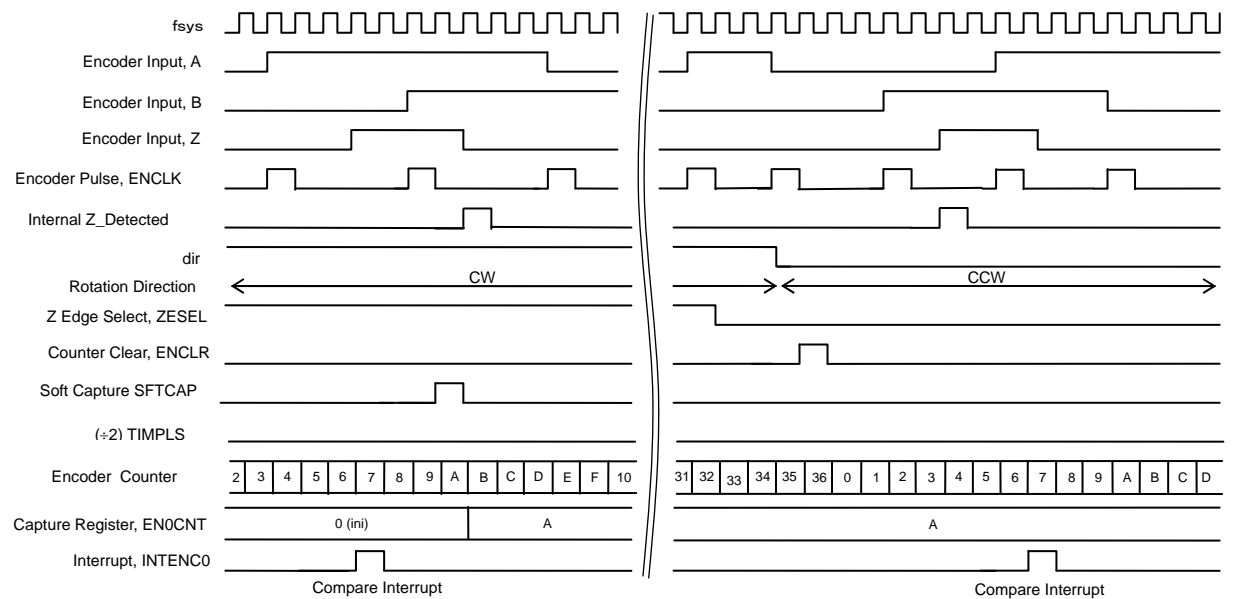


### 18.3.1.4 Timer Mode

(1) When  $\langle ZEN \rangle = 1$  ( $\langle EN0INT \rangle = 0x0006$ )



(2) When  $\langle ZEN \rangle = 0$  ( $\langle EN0INT \rangle = 0x0006$ )



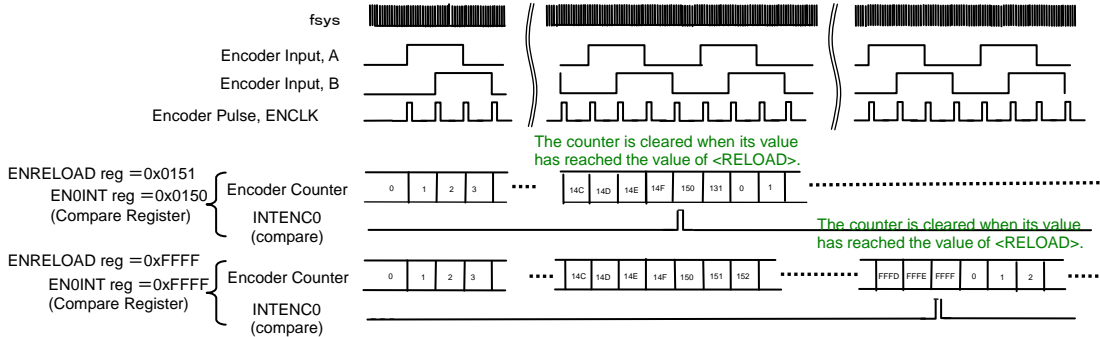
- When  $\langle ZEN \rangle = 1$ , the Z input pin is used as an external trigger. When  $\langle ZEN \rangle = 0$ , no external input is used to trigger the timer.
- The encoder counter always counts up. If  $\langle ZEN \rangle = 1$ , the counter is cleared to 0 on the selected edge of Z (at the internal Z\_Detected timing): a rising edge when  $\langle ZESSEL \rangle = 0$  and a falling edge when  $\langle ZESSEL \rangle = 1$ . When the encoder counter has reached 0xFFFFF, it wraps around to 0.
- When  $\langle ENCLR \rangle$  is set to 1, causing the encoder counter to be cleared to 0.
- Z\_Detected causes the value of the encoder counter to be captured into the ENCNT register. The captured counter value can be read out of ENCNT.
- Setting the software capture bit,  $\langle SFTCAP \rangle$ , to 1 causes the value of the encoder counter to be

captured into the ENCNT register. This capture operation can be performed at any time. The captured counter value can be read out of ENCNT.

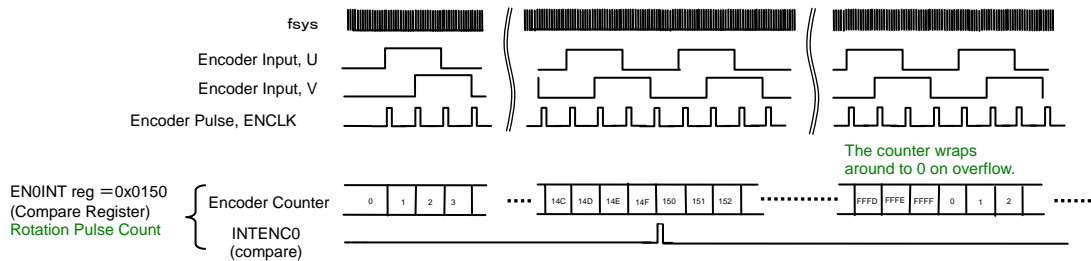
- <U/D> is set to 1 during CW rotation and cleared to 0 during CCW rotation.
- If <CMPEN> is set to 1, an interrupt is generated when the value of the encoder counter has reached the value of <ENINT>.
- Clearing <ENRUN> to 0 clears <U/D> to 0.
- The value of the ENCNT register (the captured value) is retained, regardless of the value of <ENRUN>. The ENCNT register is only cleared by a reset.

### 18.3.2 Counter Operation and Interrupt Generation When <CMPEN> = 1

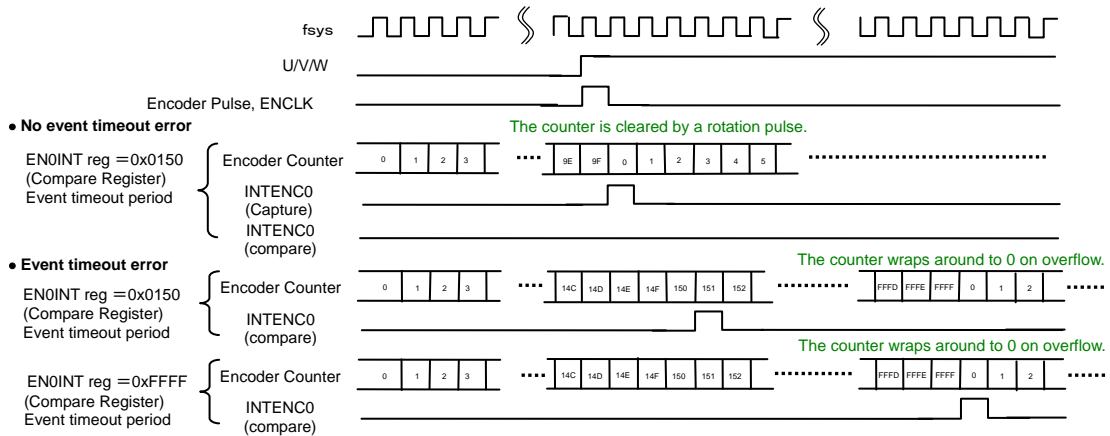
#### 18.3.2.1 Encoder Mode



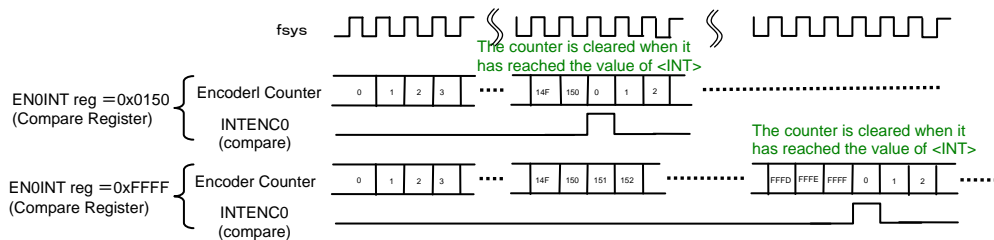
#### 18.3.2.2 Sensor Event Count Mode



#### 18.3.2.3 Sensor Timer Count Mode

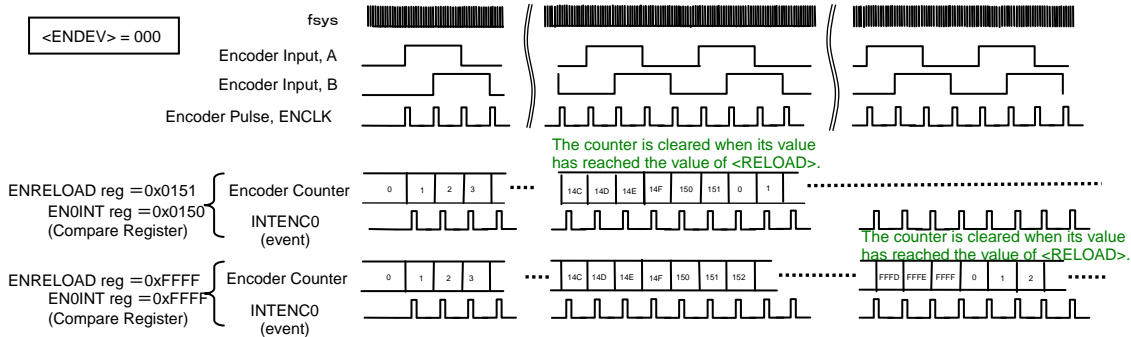


#### 18.3.2.4 Timer Mode

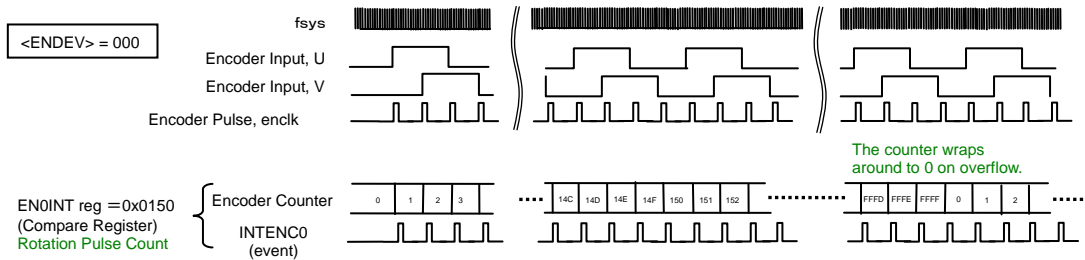


### 18.3.3 Counter Operation and Interrupt Generation When <CMPEN> = 0

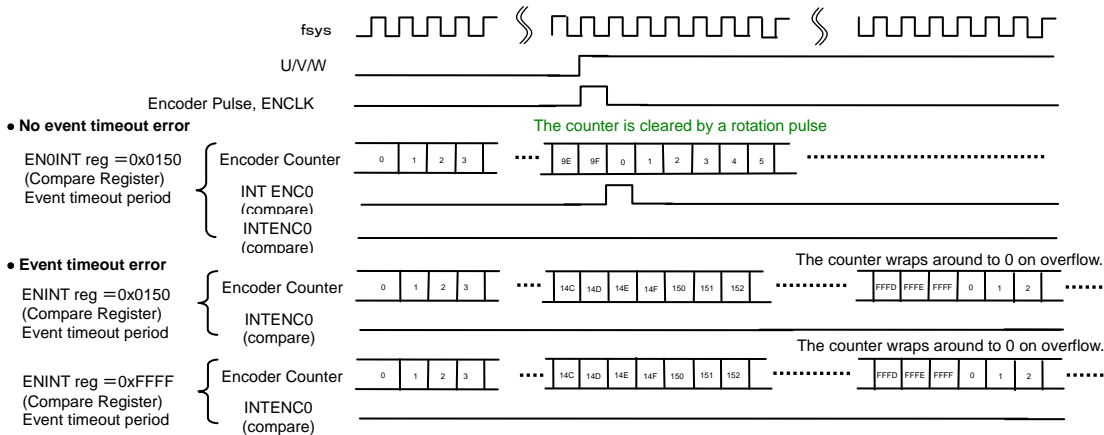
#### 18.3.3.1 Encoder Mode



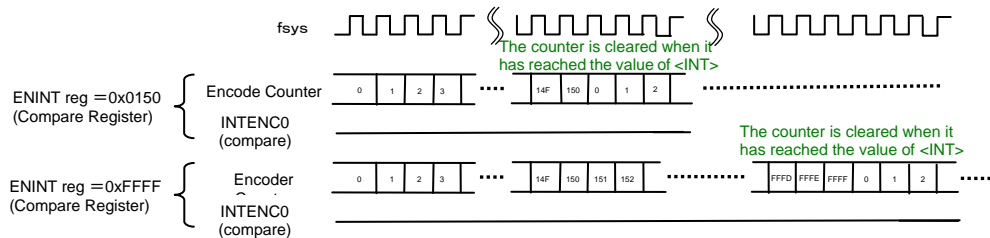
#### 18.3.3.2 Sensor Event Count Mode



#### 18.3.3.3 Sensor Timer Count Mode



#### 18.3.3.4 Timer Mode



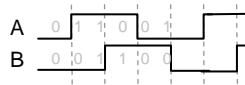
### 18.3.4 Encoder Rotation Direction

The following diagrams illustrate the phase shifting of the A, B and Z channels.

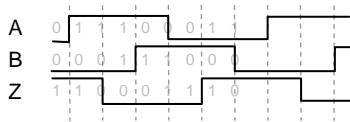
The ENC can interface with both two-phase (A/B) and three-phase (A/B/Z) encoder inputs. For three-phase encoder inputs, <P3EN> should be set to 1.

( 1 ) Here are possible combinations of values of the A (U), B (V) and Z (W) signals during CW rotation.

- For two-phase inputs

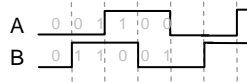


- For three-phase inputs

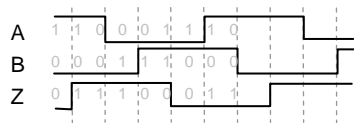


( 2 ) Here are possible combinations of values of the A (U), B (V) and Z (W) signals during CCW rotation.

- For two-phase inputs



- For three-phase inputs



### 18.3.5 Counter Block

The counter block consists of a 24-bit up/down counter and its control logic.

#### 18.3.5.1 Overview

The counter is configured as an up-counter or a down-counter, cleared and reloaded with a programmed value, according to the selected operating mode.

Table 18.4 summarizes how the counter is controlled.

Table 18.4 Counter Control

Operating Mode <MODE1:0>	<ZEN>	<REN>	Input Pins	Count	Up/Down	Counter Clear Conditions	Counter Reload Conditions	Counter Range (Reload Value)
Encoder Mode 00	0	0	A, B	Encoder pulse (ENCLK)	Up	[1] <ENCLR> is set to 1. [2] counter=<RELOAD>	-	0x0000 thru. <RELOAD>
					Down	[1] <ENCLR> is set to 1.	[1] counter=0x0000	
	1		A, B, Z	Encoder pulse (ENCLK)	Up	[1] <ENCLR> is set to 1. [2] counter=<RELOAD> [3] Z trigger	-	
					Down	[1] <ENCLR> is set to 1.	[1] counter=0x0000	
Sensor Event Count Mode 01	0	0	U, V	Encoder pulse (ENCLK)	Up	[1] <ENCLR> is set to 1. [2] counter=16'hFFFF	-	0x0000 thru. 0xFFFF
					Down	[1] <ENCLR> is set to 1.	[1] counter=0x0000	
	1		U, V, W	Encoder pulse (ENCLK)	Up	[1] <ENCLR> is set to 1. [2] counter=0xFFFF	-	
					Down	[1] <ENCLR> is set to 1.	[1] counter=0x0000	
Sensor Timer Count Mode 10	0	0	U, V	fsys	Up	[1] <ENCLR> is set to 1. [2] counter=0xFFFFF [3] Encoder pulse (ENCLK)		0x000000 thru. 0xFFFFF
	1		U, V, W	fsys	Up			
Timer Mode 11	0	X	-	fsys	Up	[1] <ENCLR> is set to 1. [2] counter=0xFFFFF [3] counter=<EN0INT>		0x000000 thru. 0xFFFFF
	1		Z	fsys	Up	[1] <ENCLR> is set to 1. [2] counter=0xFFFFF [3] counter=<EN0INT> [4] Z trigger		

**Note:** Clearing <ENRUN> to 0 does not clear the counter.

Setting <ENRUN> to 1 again causes the counter to restart from the current count.

The counter should be cleared by software setting <ENCLR> to 1.

### 18.3.6 Interrupts

The ENC has these interrupts: event (divided-clock/capture) interrupt, event timeout interrupt, timer compare interrupt and capture interrupt.

#### 18.3.6.1 Overview

When <INTEN> = 1, the ENC generates interrupt requests, based on the counter value and the detection of an encoder pulse.

There are six interrupt sources, depending on the operating mode, and the settings of <CMPEN> and <ZEN>, as shown in Table 18.5.

Table 18.5 Interrupt Sources

	Interrupt Source	Description	Operating Mode	Interrupt Generation	Status Flag
1	Event counter interrupt	When <CMPEN> = 1, the encoder counter counts events (encoder pulses). When it has reached the value programmed in <ENOINT>, an interrupt occurs.	Encoder mode and Sensor Event Count modes	When <INTEN> = 1 and <CMPEN> = 1	<CMP>
2	Event interrupt (Divided clock pulse)	An interrupt occurs on each divided clock pulse, which is derived by dividing the encoder pulse by a factor programmed in <ENDEV>.		When <INTEN> = 1	None
3	Event interrupt (Capture interrupt)	An interrupt occurs to indicate that an event (encoder pulse) has occurred, causing the counter value to be captured.	Sensor Timer Count mode	When <INTEN> = 1	None
4	Event timeout interrupt	When <CMPEN> = 1, the ENC uses a counter that counts up with fsys and is cleared by an event (encoder pulse). If no event occurs for a period of time programmed in <ENOINT>, an interrupt occurs.		When <INTEN> = 1 and <CMPEN> = 1	<CMP>
5	Timer compare interrupt	When <CMPEN> = 1, an interrupt occurs when the timer has reached the value programmed in <ENOINT>.	Timer mode	When <INTEN> = 1 and <CMPEN> = 1	<CMP>
6	Capture interrupt	An interrupt occurs when the counter value has been captured on an external trigger (Z input).		When <INTEN> = 1	None

In Sensor Timer Count mode and Timer mode, the value of the encoder counter can be captured into the ENCNT register.

The captured counter value can be read out of the ENCNT register.

In Sensor Timer Count mode, the value of the encoder counter is captured into the ENCNT register upon occurrence of an event (encoder pulse). The counter value can also be captured by writing a 1 to <SFTCAP>.

In Timer mode, the counter value can be captured by writing a 1 to <SFTCAP>. If <ZEN> is set to 1, the counter value can also be captured by an edge of the Z signal input selected via <ZESEL>.

## 19. Flash Memory Operation

This section describes the hardware configuration and operation of the flash memory.

### 19.1 Flash Memory

#### 19.1.1 Features

1) Memory capacity

The TMPM370FY contains flash memory. The memory sizes and configurations are shown in the table below. Independent write access to each block is available. When the CPU is to access the internal flash memory, 32-bit data bus width is used.

2) Write/erase time

Writing is executed per page. The TMPM370FY contains 64 words in a page.

Page writing requires 1.25ms (typical) regardless of number of words.

A block erase requires 0.1 sec. (typical).

The following table shows write and erase time per chip.

Product Name	Memory Size	Block Configuration				# of Words	Write Time	Erase Time
		128KB	64KB	32KB	16KB			
TMPM370FY	256KB	0	3	1	2	64	1.28sec	0.4sec

**(Note) The above values are theoretical values not including data transfer time. The write time per chip depends on the write method to be used by the user.**

3) Programming method

The onboard programming mode is available for the user to program (rewrite) the device while it is mounted on the user's board.

- The onboard programming mode

3-1) User boot mode

The user's original rewriting method can be supported.

3-2) Single boot mode

The rewriting method to use serial data transfer (Toshiba's unique method) can be supported.

#### Rewriting method

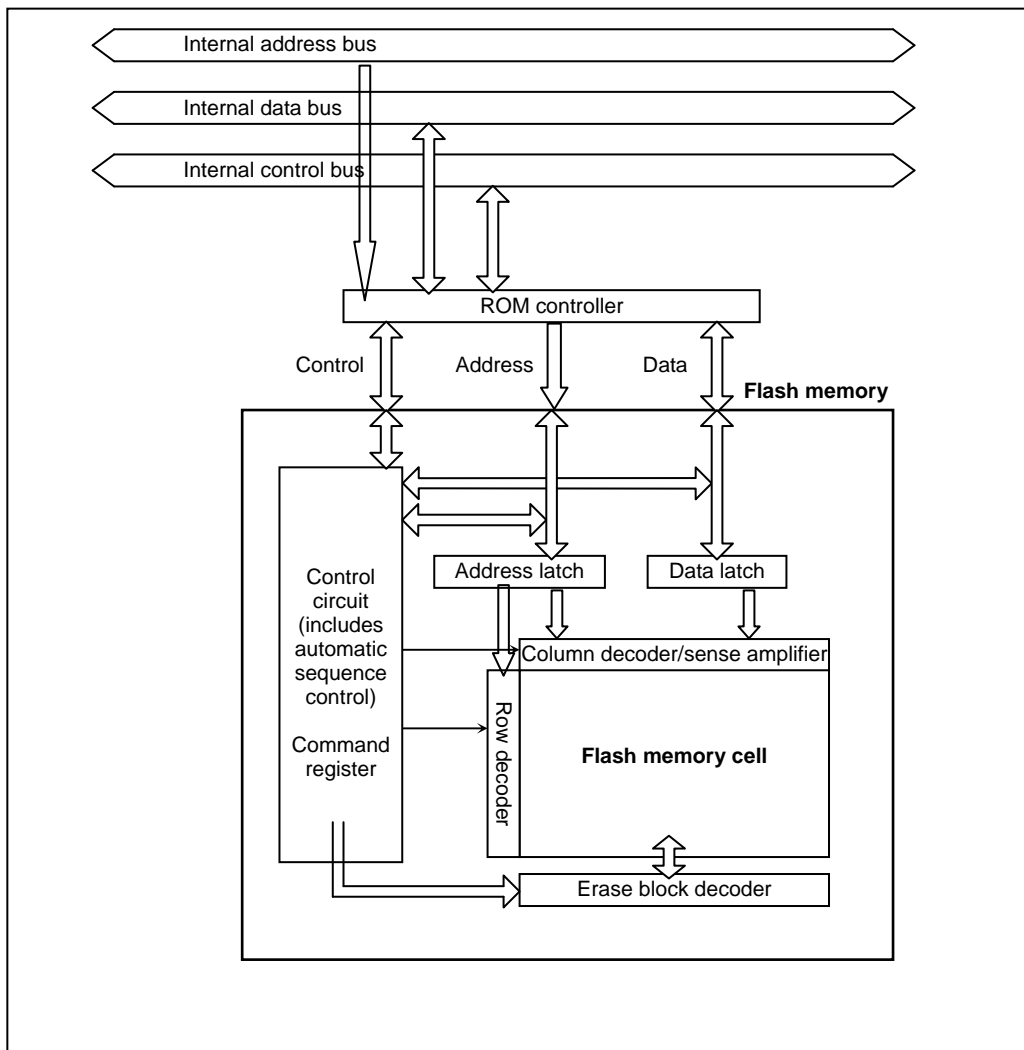
The flash memory included in this device is generally compliant with the applicable JEDEC standards except for some specific functions. Therefore, if the user is currently using an external flash memory device, it is easy to implement the functions into this device. Furthermore, the user is not required to build his/her own programs to realize complicated write and erase functions because such functions are automatically performed using the circuits already built-in the flash memory chip.

This device is also implemented with a read-protect function to inhibit reading flash memory data from any external writer device. On the other hand, rewrite protection is available only through command-based software programming; any hardware setting method to apply +12VDC is not supported. See chapter 20 for details of ROM protection and security function.



JEDEC compliant functions	Modified, added, or deleted functions
<ul style="list-style-type: none"> <li>• Automatic programming</li> <li>• Automatic chip erase</li> <li>• Automatic block erase</li> </ul>	<Modified> Block protect (only software protection is supported) <Deleted> Erase resume - suspend function
<ul style="list-style-type: none"> <li>• Data polling/toggle bit</li> </ul>	

**19.1.2 Block Diagram of the Flash Memory Section**



**Fig. 19-1 Block Diagram of the Flash Memory Section**

## 19.2 Operation Mode

This device has three operation modes including the mode not to use the internal flash memory.

**Table 19-1 Operation Modes**

Operation mode	Operation details
Single chip mode	After reset is cleared, it starts up from the internal flash memory.
Normal mode	In this operation mode, two different modes, i.e., the mode to execute user application programs and the mode to rewrite the flash memory onboard the user's card, are defined. The former is referred to as "normal mode" and the latter "user boot mode."  The user can uniquely configure the system to switch between these two modes. For example, the user can freely design the system such that the normal mode is selected when the port "A0" is set to "1" and the user boot mode is selected when it is set to "0." The user should prepare a routine as part of the application program to make the decision on the selection of the modes.
User boot mode	
Single boot mode	After reset is cleared, it starts up from the internal Boot ROM (Mask ROM). In the Boot ROM, an algorithm to enable flash memory rewriting on the user's set through the serial port of this device is programmed. By connecting to an external host computer through the serial port, the internal flash memory can be programmed by transferring data in accordance with predefined protocols.

Among the flash memory operation modes listed in the above table, the User Boot mode and the Single Boot mode are the programmable modes. These two modes, the User Boot mode and the Single Boot mode, are referred to as "Onboard Programming" modes where onboard rewriting of internal flash memory can be made on the user's card.

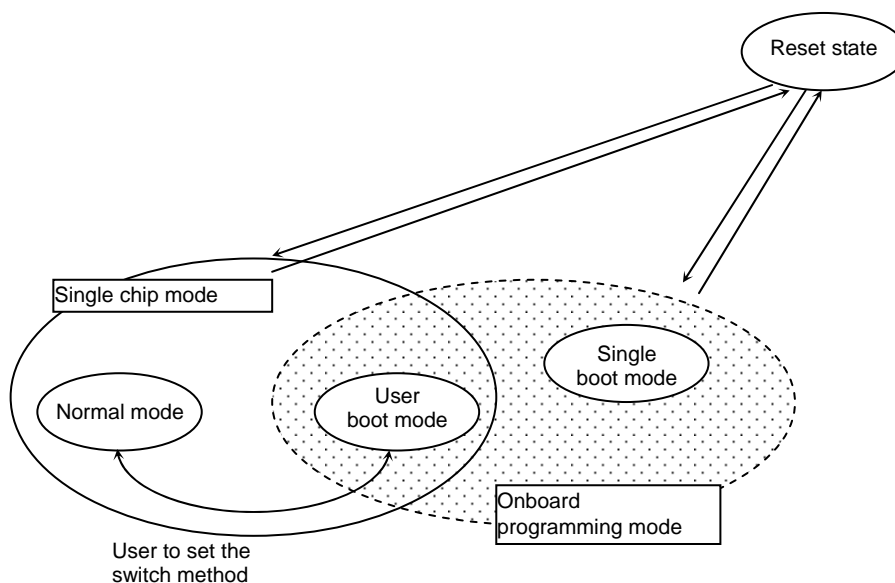
Either the Single Chip or Single Boot operation mode can be selected by externally setting the level of the  $\overline{\text{BOOT}}$  (PF0) pin while the device is in reset status.

After the level is set, the CPU starts operation in the selected operation mode when the reset condition is removed. Regarding the  $\overline{\text{BOOT}}$  (PF0) pin, be sure not to change the levels during operation once the mode is selected.

The mode setting method and the mode transition diagram are shown below:

**Table 19-2 Operation Mode Setting**

Operation mode	Pin	
	$\overline{\text{RESET}}$	$\overline{\text{BOOT}}$ (PF0)
Single chip mode	0 → 1	1
Single boot mode	0 → 1	0



**Fig. 19-2 Mode Transition Diagram**

**19.2.1 Reset Operation**

To reset the device, ensure that the power supply voltage is within the operating voltage range, that the internal oscillator has been stabilized, and that the  $\overline{\text{RESET}}$  input is held at "0" for a minimum duration of 12 system clocks (0.15  $\mu\text{s}$  with 80MHz operation; the "1/1" clock gear mode is applied after reset).

**(Note 1) Regarding power-on reset of devices with internal flash memory;**  
 for devices with internal flash memory, it is necessary to apply "0" to the  $\overline{\text{RESET}}$  inputs upon power on for a minimum duration of 300 microseconds regardless of the operating frequency.

**(Note 2) While flash auto programming or deletion is in progress, at least 0.5 microseconds of reset period is required regardless of the system clock frequency. In this condition, it takes approx. 2 ms to enable reading after reset.**

### 19.2.2 User Boot Mode (Single chip mode)

User Boot mode is to use flash memory programming routine defined by users. It is used when the data transfer buses for flash memory program code on the old application and for serial I/O are different. It operates at the single chip mode; therefore, a switch from normal mode in which user application is activated at the single chip mode to User Boot Mode for programming flash is required. Specifically, add a mode judgment routine to a reset program in the old application.

The condition to switch the modes needs to be set by using the I/O of TMPM370 in conformity with the user's system setup condition. Also, flash memory programming routine that the user uniquely makes up needs to be set in the new application. This routine is used for programming after being switched to User Boot Mode. The execution of the programming routine must take place while it is stored in the area other than the flash memory since the data in the internal flash memory cannot be read out during delete/ writing mode. Once re-programming is complete, it is recommended to protect relevant flash blocks from accidental corruption during subsequent Single-Chip (Normal mode) operations. All the interruption including a non-maskable are inhibited at User Boot Mode.

(1-A) and (1-B) are the examples of programming with routines in the internal flash memory and in the external memory. For a detailed description of the erase and program sequence, refer to 19.3 On-board Programming of Flash Memory (Rewrite/Erase).

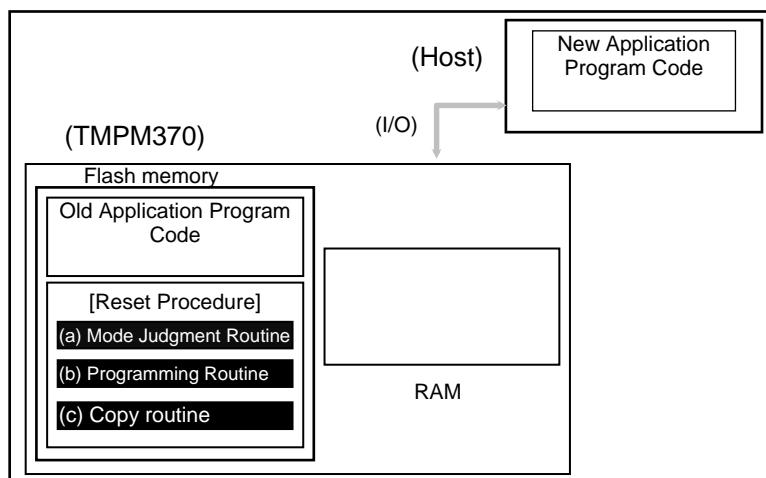
**User Boot Mode**

(1-A) Method 1: Storing a Programming Routine in the Flash Memory

**(Step-1)**

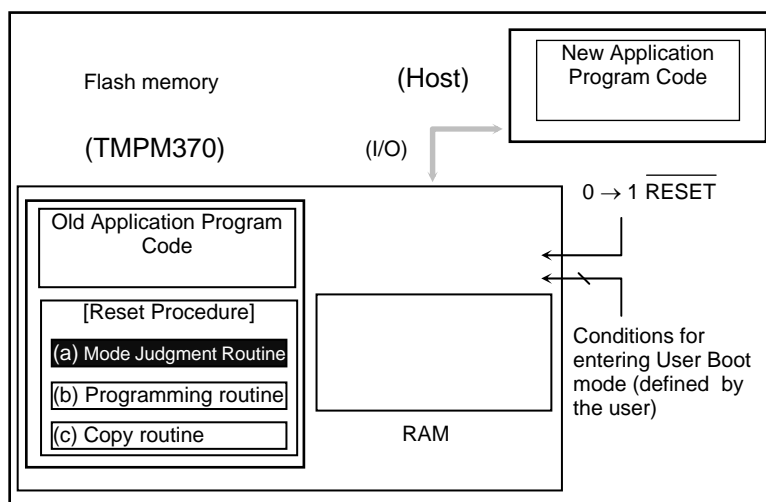
Determine the conditions (e.g., pin states) required for the flash memory to enter User Boot mode and the I/O bus to be used to transfer new program code. Create hardware and software accordingly. Before installing the TMPM370 on a printed circuit board, write the following program routines into an arbitrary flash block using programming equipment.

- (a) Mode judgment routine: Code to determine whether or not to switch to User Boot mode
- (b) Programming routine: Code to download new program code from a host controller and re-program the flash memory
- (c) Copy routine: Code to copy the data described in (b) from the TMPM370 flash memory to either the TMPM370 on-chip RAM or external memory device.



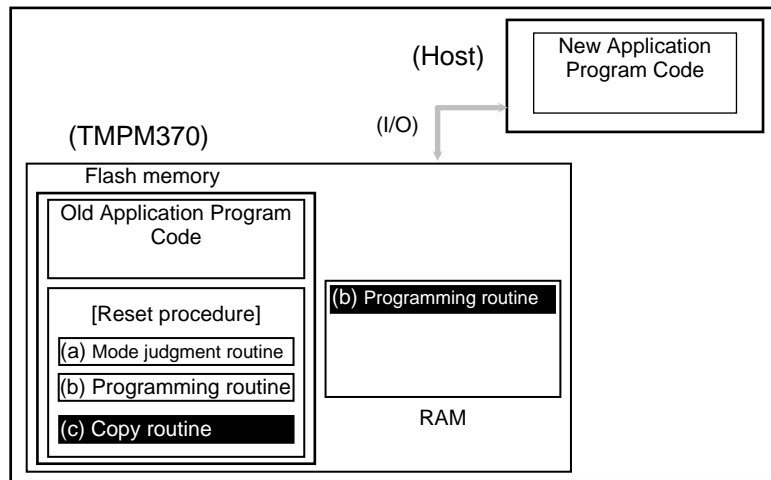
**(Step-2)**

After  $\overline{\text{RESET}}$  is released, the reset procedure determines whether to put the TMPM370 flash memory in User Boot mode. If mode switching conditions are met, the flash memory enters User Boot mode. (All interrupts including NMI must be disabled while in User Boot mode.)



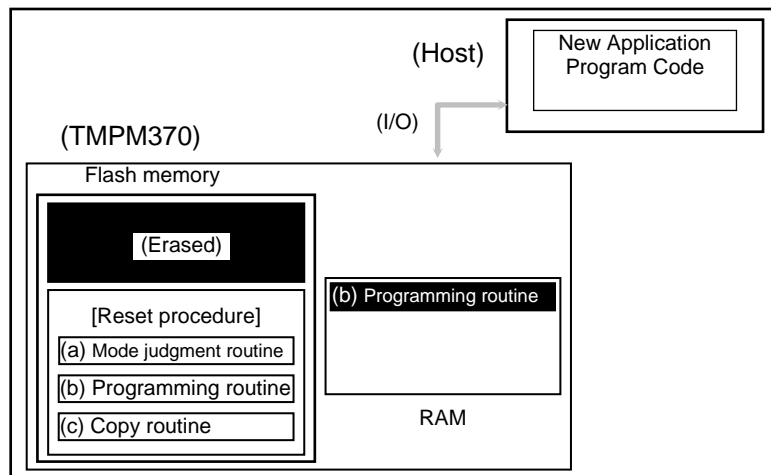
**(Step-3)**

Once transition to User Boot mode is occurred, execute the copy routine (c) to copy the flash programming routine (b) to the TMPM370 on-chip RAM.



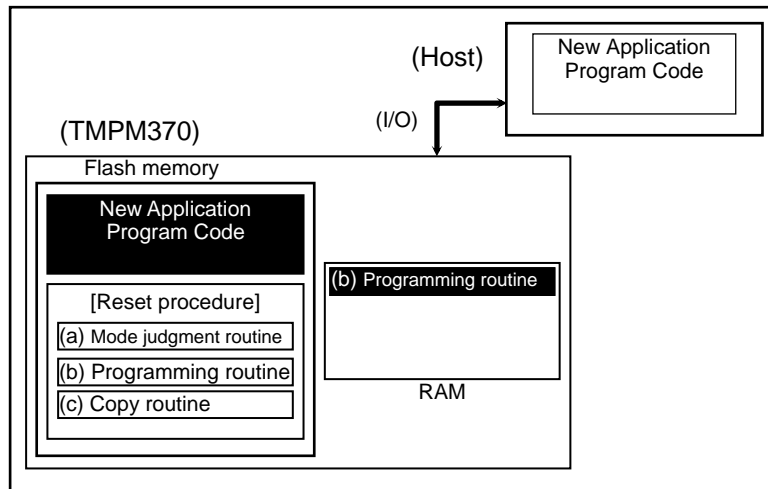
**(Step-4)**

Jump program execution to the flash programming routine in the on-chip RAM to erase a flash block containing the old application program code.



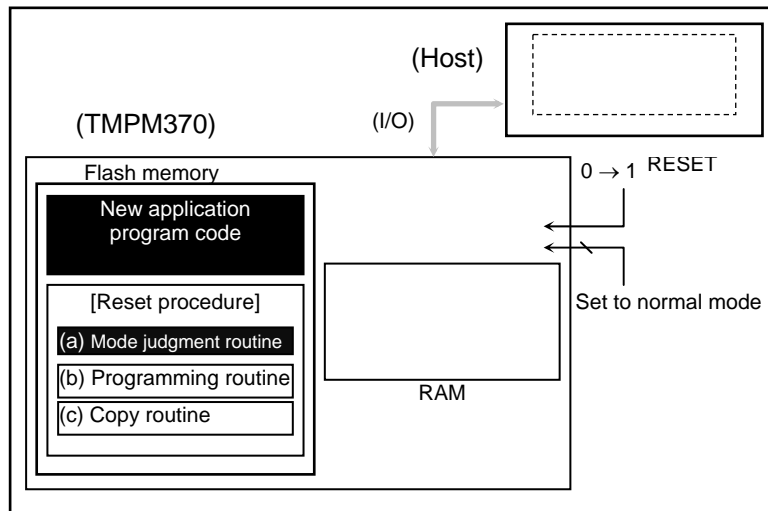
**(Step-5)**

Continue executing the flash programming routine to download new program code from the host controller and program it into the erased flash block. Once programming is complete, turn on the protection of that flash block.



**(Step-6)**

Set  $\overline{\text{RESET}}$  to "0" to reset the TMPM370. Upon reset, the on-chip flash memory is put in Normal mode. After  $\overline{\text{RESET}}$  is released, the CPU will start executing the new application program code.



(1-B) Method 2: Transferring a Programming Routine from an External Host

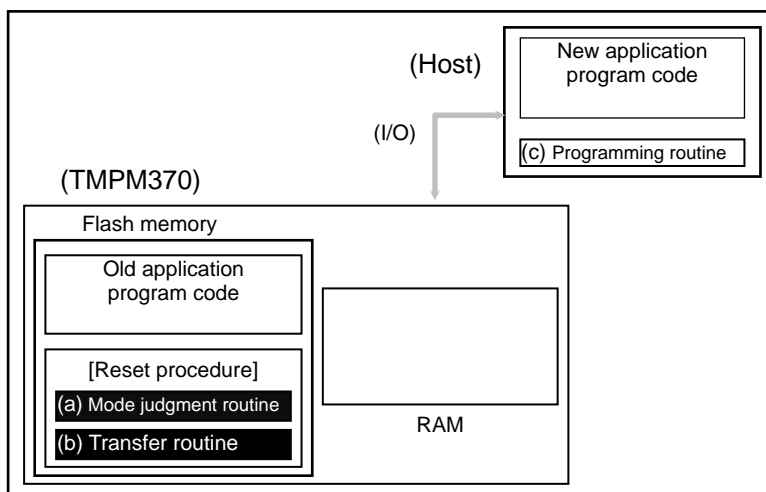
**(Step-1)**

Determine the conditions (e.g., pin states) required for the flash memory to enter User Boot mode and the I/O bus to be used to transfer new program code. Create hardware and software accordingly. Before installing the TMPM370 on a printed circuit board, write the following program routines into an arbitrary flash block using programming equipment.

- (a) Mode judgment routine: Code to determine whether or not to switch to User Boot mode
- (b) Transfer routine: Code to download new program code from a host controller

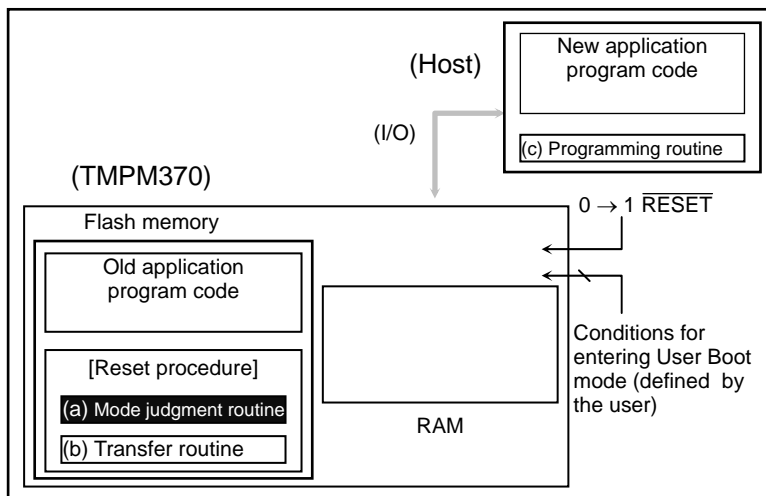
Also, prepare a programming routine shown below on the host controller:

- (c) Programming routine: Code to download new program code from an external host controller and re-program the flash memory



**(Step-2)**

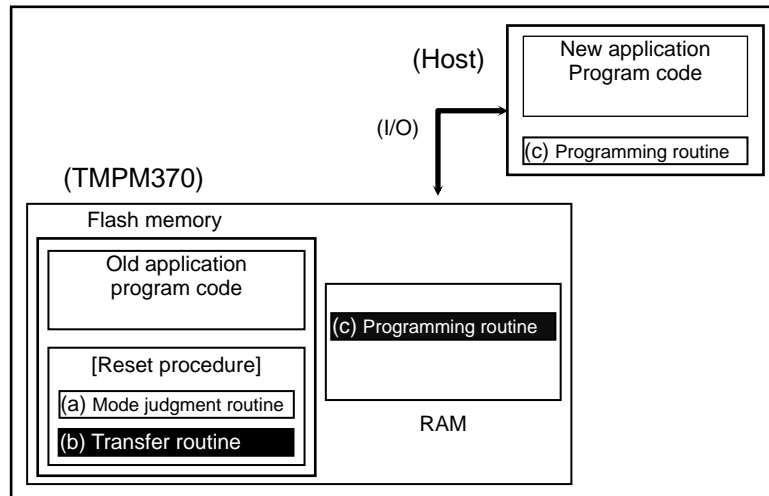
After  $\overline{\text{RESET}}$  is released, the reset procedure determines whether to put the TMPM370 flash memory in User Boot mode. If mode switching conditions are met, the flash memory enters User Boot mode. (All interrupts including NMI must be disabled while in User Boot mode).





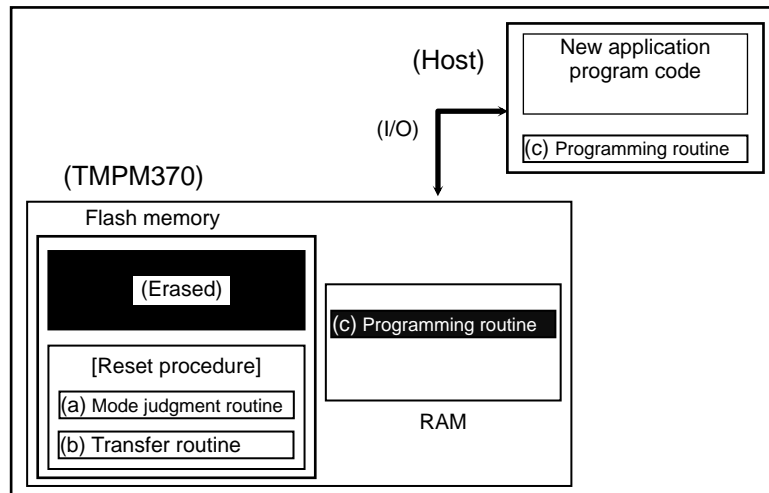
**(Step-3)**

Once User Boot mode is entered, execute the transfer routine (b) to download the flash programming routine (c) from the host controller to the TMPM370 on-chip RAM.



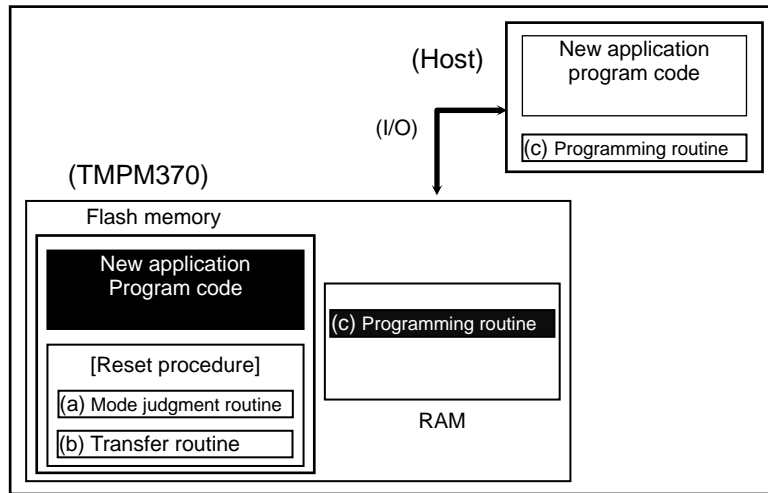
**(Step-4)**

Jump program execution to the flash programming routine in the on-chip RAM to erase a flash block containing the old application program code.



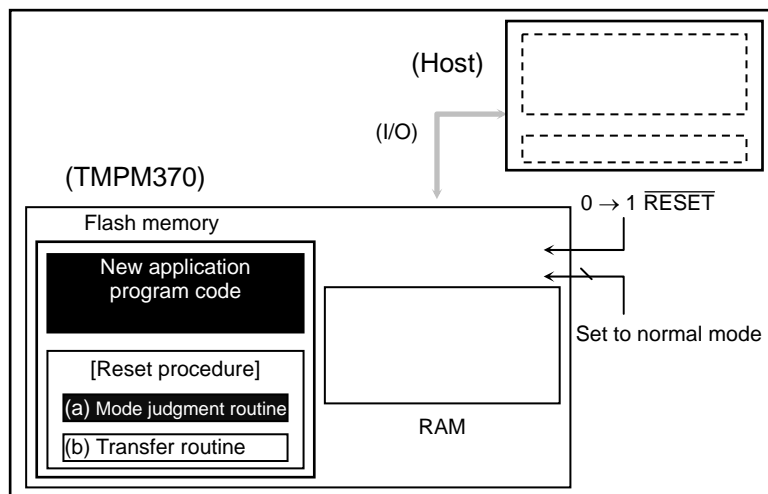
**(Step-5)**

Continue executing the flash programming routine to download new program code from the host controller and program it into the erased flash block. Once programming is complete, turn on the protection of that flash block.



**(Step-6)**

Set  $\overline{\text{RESET}}$  to "0" low to reset the TMPM370. Upon reset, the on-chip flash memory is put in Normal mode. After  $\overline{\text{RESET}}$  is released, the CPU will start executing the new application program code.



### 19.2.3 Single Boot Mode

In Single Boot mode, the flash memory can be re-programmed by using a program contained in the TMPM370 on-chip boot ROM. This boot ROM is a masked ROM. When Single Boot mode is selected upon reset, the boot ROM is mapped to the address region including the interrupt vector table while the flash memory is mapped to an address region different from it.

Single Boot mode allows for serial programming of the flash memory. Channel 0 of the SIO (SIO0) of the TMPM370 is connected to an external host controller. Via this serial link, a programming routine is downloaded from the host controller to the TMPM370 on-chip RAM. Then, the flash memory is re-programmed by executing the programming routine. The host sends out both commands and programming data to re-program the flash memory.

Communications between the SIO0 and the host must follow the protocol described later. To secure the contents of the flash memory, the validity of the application's password is checked before a programming routine is downloaded into the on-chip RAM. If password matching fails, the transfer of a programming routine itself is aborted.

As in the case of User Boot mode, all interrupts including the non-maskable interrupt (NMI) must be disabled in Single Boot mode while the flash memory is being erased or programmed. In Single Boot mode, the boot-ROM programs are executed in Normal mode.

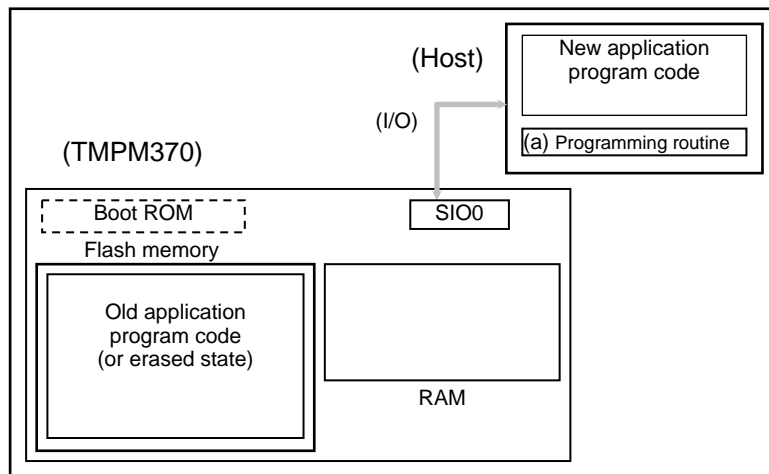
Once re-programming is complete, it is recommended to protect relevant flash blocks from accidental corruption during subsequent Single-Chip (Normal mode) operations.

**Single Boot Mode**

(2-A) Using the Program in the On-Chip Boot ROM

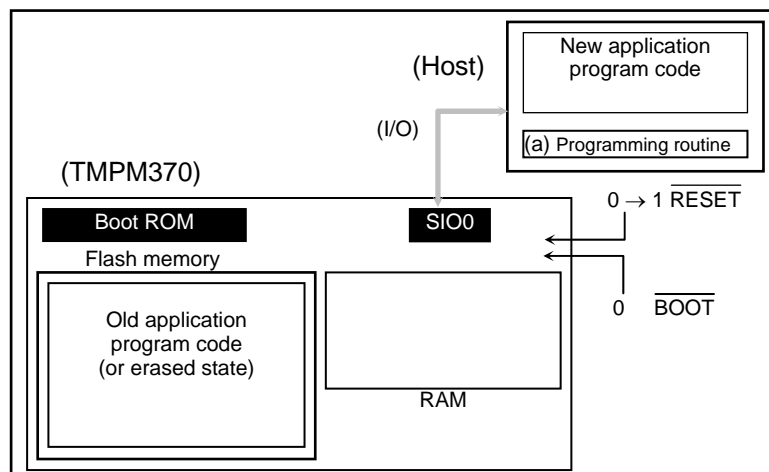
**(Step-1)**

The flash block containing the older version of the program code need not be erased before executing the programming routine. Since a programming routine and programming data are transferred via the SIO (SIO0), the SIO0 must be connected to a host controller. Prepare a programming routine (a) on the host controller.



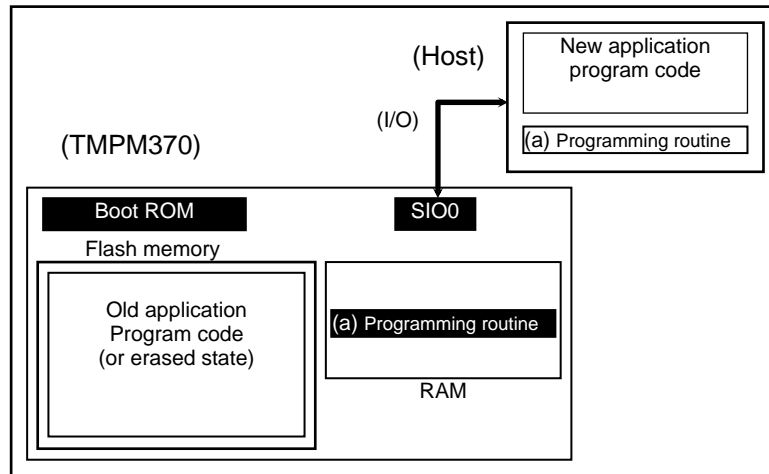
**(Step-2)**

Cancel the reset of the TMPM370 by setting the Single Boot mode pin to "0", so that the CPU re-boots from the on-chip boot ROM. The 12-byte password transferred from the host controller via SIO0 is first compared to the contents of the special flash memory locations. (If the flash block has already been erased, the password is 0xFFFF).



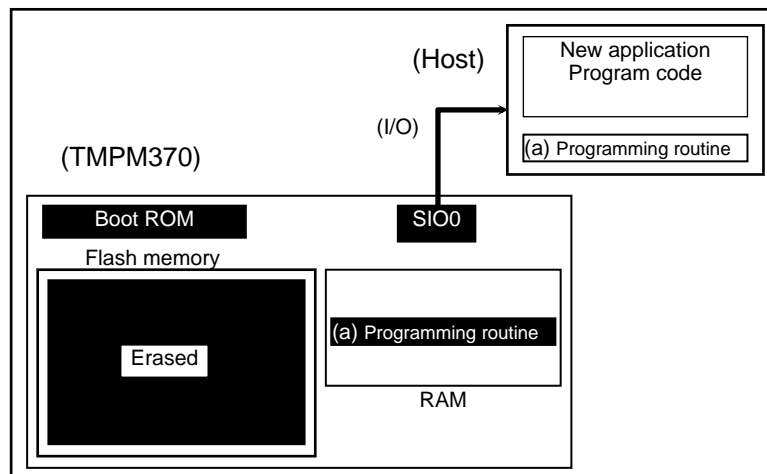
**(Step-3)**

If the password was correct, the boot program downloads, via the SIO0, the programming routine (a) from the host controller into the on-chip RAM of the TMPM370. The programming routine must be stored in the address range 0x2000\_0400 to the end address of RAM.



**(Step-4)**

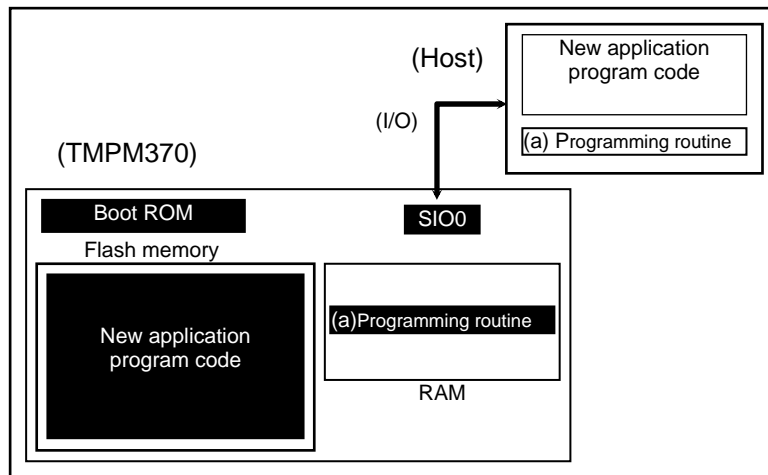
The CPU jumps to the programming routine (a) in the on-chip RAM to erase the flash block containing the old application program code. The Block Erase or Chip Erase command may be used.



**(Step-5)**

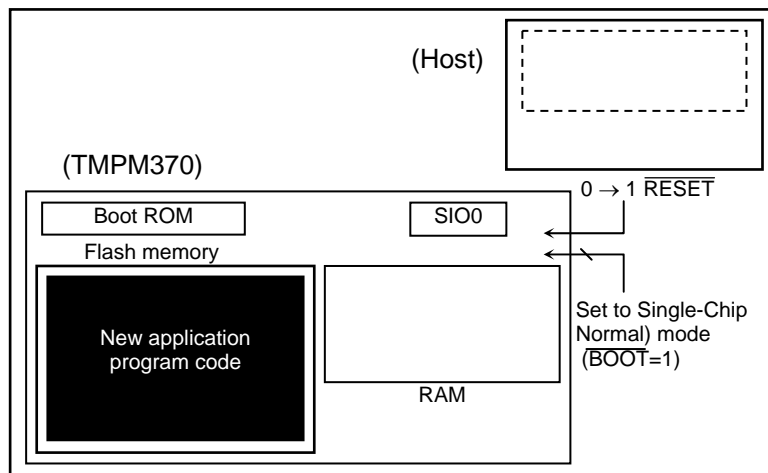
Next, the programming routine (a) downloads new application program code from the host controller and programs it into the erased flash block. Once programming is complete, protection of that flash block is turned on. It is not allowed to move program control from the programming routine (a) back to the boot ROM.

In the example below, new program code comes from the same host controller via the same SIO0 channel as for the programming routine. However, once the programming routine has begun to execute, it is free to change the transfer path and the source of the transfer. Create board hardware and a programming routine to suit your particular needs.



**(Step-6)**

When programming of the flash memory is complete, power off the board and disconnect the cable leading from the host to the target board. Turn on the power again so that the TMPM370 re-boots in Single-Chip (Normal) mode to execute the new program.



## (1) Configuration for Single Boot Mode

To execute the on-board programming, boot the TMPM370 with Single Boot mode following the configuration shown below.

$$\overline{\text{BOOT}} \text{ (PF0)} = 0$$

$$\overline{\text{RESET}} = 0 \rightarrow 1$$

Set the  $\overline{\text{RESET}}$  input to 0, and set the each  $\overline{\text{BOOT}}$  (PF0) pins to values shown above, and then release RESET (high).

## (2) Memory Map

Fig. 17-3 shows a comparison of the memory maps in Normal and Single Boot modes. In Single Boot mode, the internal flash memory is mapped to 0x3F80\_0000 through 0x3F83\_FFFF, and the Internal boot ROM (Mask ROM) is mapped to 0x0000\_0000 through 0x0000\_0FFF.

Product Name	Flash Size	RAM Size	Flash Address (Single Chip/ Single Boot Mode)	RAM Address
TMPM370FY	256KB	10KB	0x0000_0000 - 0x0003_FFFF 0x3F80_0000 - 0x3F83_FFFF	0x2000_0000 - 0x2000_27FF

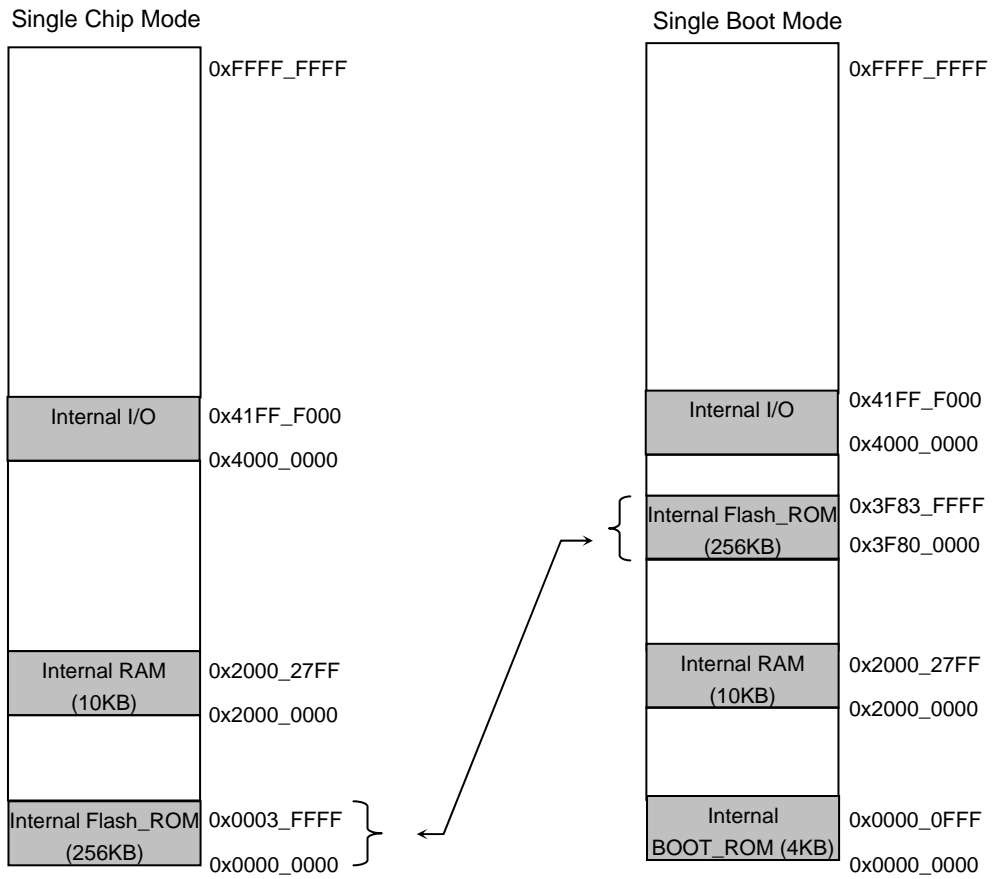


Fig. 19-3 Memory Maps for TMPM370FY



## (3) Interface specification

In Single Boot mode, an SIO channel is used for communications with a programming controller. The same configuration is applied to a communication format on a programming controller to execute the on-board programming. Both UART (asynchronous) and I/O Interface (synchronous) modes are supported. The communication formats are shown below.

- UART communication

Communication channel : SIO channel 0  
 Serial transfer mode : UART (asynchronous), half -duplex, LSB fast  
 Data length : 8 bit  
 Parity bits : None  
 STOP bits : 1 bit  
 Baud rate : Arbitrary baud rate

- I/O interface mode

Communication channel : SIO channel 0  
 Serial transfer mode : I/O interface mode, full -duplex, LSB fast  
 Synchronization clock (SCLK0) : Input mode  
 Handshaking signal : PE4 configured as an output mode  
 Baud rate : Arbitrary baud rate

- 

**Table 19-3 Required Pin Connections**

Pins		Interface	
		UART	I/O Interface Mode
Power supply pins	REGVCC	○	○
	AVCC	○	○
	DVCC	○	○
	CVCC	○	○
	REGVSS	○	○
	AVSS	○	○
	DVSS	○	○
	CVSS	○	○
Mode-setting pin	$\overline{\text{BOOT}}$ (PF0)	○	○
Reset pin	$\overline{\text{RESET}}$	○	○
Communication pins	TXD0(PE0)	○	○
	RXD0(PE1)	○	○
	SCLK0(PE2)	x	○ (Input mode)
	PE4	x	○ (Output mode)

## (4) Data Transfer Format

Table 19-4 and Table 19-6 to Table 19-10 illustrate the operation commands and data transfer formats at each operation mode. In conjunction with this section, refer to (6) Operation of Boot Program.

**Table 19-4 Single Boot Mode Commands**

Code	Command
0x10	RAM transfer
0x20	Show Flash Memory SUM
0x30	Show Product Information
0x40	Chip and protection bit erase

## (5) Restrictions on internal memories

Single Boot Mode places restrictions on the internal RAM and ROM as shown in Table 19-5.

**Table 19-5 Restrictions in Single Boot Mode**

Memory	Details
Internal RAM	BOOT ROM is mapped from 0x2000_0000 to 0x2000_03FF. Store the RAM transfer program from 0x2000_0400 through the end address of RAM.
Internal ROM	The following addresses are assigned for storing software ID information and passwords. Storing program in these addresses is not recommendable. TMPM370FY : 0x3F83_FFF0 to 0x3F83_FFFF

Table 19-6 Transfer Format for the RAM Transfer Command

	Byte	Data Transferred from the Controller to the TMPM370FY	Baud rate	Data Transferred from the TMPM370FY to the Controller
Boot ROM	1 byte	Serial operation mode and baud rate For UART mode 0x86 For I/O Interface mode 0x30	Desired baud rate (Note 1)	-
	2 byte	-		ACK for the serial operation mode byte For UART mode -Normal acknowledge 0x86 (The boot program aborts if the baud rate can not be set correctly.) For I/O Interface mode -Normal acknowledge 0x30
	3 byte	Command code (0x10)		-
	4 byte	-		ACK for the command code byte (Note 2) -Normal acknowledge 0x10 -Negative acknowledge 0xN1 -Communication error 0xN8
	5 byte - 16 byte	Password sequence (12 bytes) 0x3F83_FFF4 to 0x3F83_FFFF		-
	17 byte	Check SUM value for bytes 5 - 16		-
	18 byte	-		ACK for the checksum byte (Note 2) -Normal acknowledge 0x10 -Negative acknowledge 0xN1 -Communication error 0xN8
	19 byte	RAM storage start address 31 - 24		-
	20 byte	RAM storage start address 23 - 16		-
	21 byte	RAM storage start address 15 - 8		-
	22 byte	RAM storage start address 7 - 0		-
	23 byte	RAM storage byte count 15 - 8		-
	24 byte	RAM storage byte count 7 - 0		-
	25 byte	Check SUM value for bytes 19 - 24		-
	26 byte	-		ACK for the checksum byte (Note 2) -Normal acknowledge 0x10 -Negative acknowledge 0xN1 -Communication error 0xN8
	27 byte ~ m byte	RAM storage data		-
	m + byte	Checksum value for bytes 27 - m		-
m + byte	-	ACK for the checksum byte (Note 2) -Normal acknowledge 0x10 -Negative acknowledge 0xN1 -Communication error 0xN8		
RAM	m + byte	-	Jump to RAM storage start address	

**(Note 1)** In I/O Interface mode, the baud rate for the transfers of the first and second bytes must be 1/16 of the desired baud rate.

**(Note 2)** In case of any negative acknowledge, the boot program returns to a state in which it waits for a command code (3rd byte). In I/O Interface mode, if a communication error occurs, a negative acknowledge does not occur.

**(Note 3)** The 19th to 25th bytes must be within the RAM address range from 0x2000\_0400 through the end address of RAM.

Table 19-7 Transfer Format for the Show Flash Memory Sum Command

	Byte	Data Transferred from the Controller to the TMPM370FY	Baud rate	Data Transferred from the TMPM370FY to the Controller
Boot ROM	1 byte	Serial operation mode and baud rate For UART mode           0x86 For I/O Interface mode   0x30	Desired baud rate (Note 1)	-
	2 byte	-		ACK for the serial operation mode byte For UART mode -Normal acknowledge       0x86 (The boot program aborts if the baud rate can not be set correctly.) For I/O Interface mode -Normal acknowledge       0x30
	3 byte	Command code           (0x20)		-
	4 byte	-		ACK for the command code byte (Note 2) -Normal acknowledge       0x20 -Negative acknowledge      0xN1 -Communication error       0xN8
	5 byte	-		SUM (upper byte)
	6 byte	-		SUM (lower byte)
	7 byte	-		Checksum value for bytes 5 and 6
	8 byte	(Wait for the next command code.)		-

**(Note 1)** In I/O Interface mode, the baud rate for the transfers of the first and second bytes must be 1/16 of the desired baud rate.

**(Note 2)** In case of any negative acknowledge, the boot program returns to a state in which it waits for a command code (3rd byte). In I/O Interface mode, if a communication error occurs, a negative acknowledge does not occur.

Table 19-8 Transfer Format for the Show Product Information Command (1/2)

	Byte	Data Transferred from the Controller to the TMPM370FY	Baud rate	Data Transferred from the TMPM370FY to the Controller
Boot ROM	1 byte	Serial operation mode and baud rate For UART mode 0x86 For I/O Interface mode 0x30	Desired baud rate (Note 1)	-
	2 byte	-		ACK for the serial operation mode byte For UART mode -Normal acknowledge 0x86 (The boot program aborts if the baud rate can not be set correctly.) For I/O Interface mode -Normal acknowledge 0x30
	3 byte	Command code (0x30)		-
	4 byte	-		ACK for the command code byte (Note 2) -Normal acknowledge 0x30 -Negative acknowledge 0xN1 -Communication error 0xN8
	5 byte	-		Flash memory data at address 0x3F83_FFF0
	6 byte	-		Flash memory data at address 0x3F83_FFF1
	7 byte	-		Flash memory data at address 0x3F83_FFF2
	8 byte	-		Flash memory data at address 0x3F83_FFF3
	9 byte - 20 byte	-		Product name (12-byte ASCII code) From the 9th byte: 'TMPM370FY_[]_' (where [] is a space)
	21 byte - 24 byte	-		Password comparison start address (4 bytes) From the 21 <sup>st</sup> byte: 0xF4, 0xFF, 0x83, 0x3F
	25 byte - 28 byte	-		RAM start address (4 bytes) 0x00, 0x00, 0x00 and 0x20 from the 25 <sup>th</sup> byte
	29 byte - 32 byte	-		Dummy data (4 bytes) 0x00, 0x00, 0x00 and 0x00 from the 29 <sup>th</sup> byte
	33 byte - 36 byte	-		RAM end address (4 bytes) From the 33 <sup>rd</sup> byte: 0xFF, 0x27, 0x00, 0x20 (Note 3)
	37 byte - 40 byte	-		Dummy data (4 bytes) 0x00, 0x00, 0x00 and 0x00 from the 37 <sup>th</sup> byte.
	41 byte - 44 byte	-		Dummy data (4 bytes) 0x00, 0x00, 0x00 and 0x00 from the 41 <sup>st</sup> byte
	45 byte - 46 byte	-		Fuse information (2 bytes) 0x00 and 0x00 from the 45 <sup>th</sup> byte.
	47 byte - 50 byte	-		Flash memory start address (4 bytes) 0x00, 0x00, 0x80 and 0x3F from the 47 <sup>th</sup> byte
51 byte - 54 byte	-		Flash memory end address (4 bytes) From the 51 <sup>st</sup> byte: 0xFF, 0xFF, 0x83, 0x3F (Note 4)	
55 byte - 56 byte	-		Flash memory block count (2 bytes) From the 55 <sup>th</sup> byte: 0x06, 0x00	

Table 19-8 Transfer Format for the Show Product Information Command (2/2)

	Byte	Data Transferred from the Controller to the TMPM370FY	Baud rate	Data Transferred from the TMPM370FY to the Controller
Boot ROM	57 byte - 60 byte	-		Start address of a group of the same-size (16K) flash blocks (4 bytes) From 57 <sup>th</sup> byte: 0x00, 0x00, 0x80, 0x3F
	61 byte - 64 byte	-		Size (in halfwords) of the same-size (16K) flash blocks (4 bytes) 0x00, 0x20, 0x00 and 0x00 from the 61 <sup>st</sup> byte
	65 byte	-		Number of flash blocks of the same size (16K) (1 byte) 0x02
	66 byte - 69 byte	-		Start address of a group of the same-size (32K) flash blocks (4 bytes) From 66 <sup>th</sup> byte: 0x00, 0x80, 0x80, 0x3F
	70 byte - 73 byte			Size (in halfwords) of the same-size (32K) flash blocks (4 bytes) 0x00, 0x40, 0x00 and 0x00 from the 70 <sup>th</sup> byte
	74 byte			Number of flash blocks of the same size (32K) (1 byte) 0x01
	75 byte - 78 byte			Start address of a group of the same-size (64K) flash blocks (4 bytes) 0x00, 0x00, 0x81 and 0x3F from 75 <sup>th</sup> byte
	79 byte - 82 byte			Size (in halfwords) of the same-size (64K) flash blocks (4 bytes) 0x00, 0x80, 0x00 and 0x00 from the 79 <sup>th</sup> byte
	83 byte			Number of flash blocks of the same size (64K) (1 byte) From 83 <sup>rd</sup> byte: 0x03
	84 byte - 87 byte			Start address of a group of the same-size (128K) flash blocks (4 bytes) From 84 <sup>th</sup> byte: 0x00, 0x00, 0x82, 0x3F
	88 byte - 91 byte			Size (in halfwords) of the same-size (128K) flash blocks (4 bytes) 0x00, 0x00, 0x00 and 0x00 from the 88 <sup>th</sup> byte
	92 byte			Number of flash blocks of the same size (128K) (1 byte) 0x00 (Note 5)
	93 byte			Checksum value for bytes 5 - 92
94 byte		(Wait for the next command code.)		-

**(Note 1)** In I/O Interface mode, the baud rate for the transfers of the first and second bytes must be 1/16 of the desired baud rate.

**(Note 2)** In case of any negative acknowledge, the boot program returns to a state in which it waits for a command code (3rd byte). In I/O Interface mode, if a communication error occurs, a negative acknowledge does not occur.

Table 19-9 Transfer Format for the Chip and Protection Bit Erase Command

	Byte	Data Transferred from the Controller to the TMPM370FY	Baud rate	Data Transferred from the TMPM370FY to the Controller
Boot ROM	1 byte	Serial operation mode and baud rate For UART mode                   0x86 For I/O Interface mode       0x30	Desired baud rate (Note 1)	—
	2 byte	—		ACK for the serial operation mode byte For UART mode -Normal acknowledge           0x86 For I/O Interface mode -Normal acknowledge           0x30 (The boot program aborts if the baud rate can not be set correctly.)
	3 byte	Command code                   (0x40)		—
	4 byte	—		ACK for the command code byte (Note 2) -Normal acknowledge           0x40 -Negative acknowledge        0xN1 -Communication error         0xN8
	5 byte	Chip erase command code   (0x54)		—
	6 byte	—		ACK for the command code byte (Note 2) -Normal acknowledge           0x54 -Negative acknowledge        0xN1 -Communication error         0xN8
	7 byte	—		ACK for the chip erase command code byte  -Normal acknowledge           0x4F -Negative acknowledge        0x4C
	8 byte	(Wait for the next command code.)		—

**(Note 1)** In I/O Interface mode, the baud rate for the transfers of the first and second bytes must be 1/16 of the desired baud rate.

**(Note 2)** In case of any negative acknowledge, the boot program returns to a state in which it waits for a command code (3rd byte). In I/O Interface mode, if a communication error occurs, a negative acknowledge does not occur.

## (6) Operation of Boot Program

When Single Boot mode is selected, the boot program is automatically executed on startup. The boot program offers these three commands, of which the details are provided on the following subsections. The addresses described in this section are the virtual unless otherwise noted.

## 1. RAM Transfer command

The RAM Transfer command stores program code transferred from a host controller to the on-chip RAM and executes the program once the transfer is successfully completed. The user program RAM space can be assigned to the range from 0x2000\_0400 to the end address of RAM, whereas the boot program area (0x2000\_0000 ~ 0x2000\_03FF) is unavailable. The user program starts at the assigned RAM address.

The RAM Transfer command can be used to download a flash programming routine of your own; this provides the ability to control on-board programming of the flash memory in a unique manner. The programming routine must utilize the flash memory command sequences described in Section 19.3.

Before initiating a transfer, the RAM Transfer command verifies a password sequence coming from the controller against that stored in the flash memory.

## 2. Show Flash Memory Sum command

The Show Flash Memory Sum command adds the entire contents of the flash memory together. The boot program does not provide a command to read out the contents of the flash memory. Instead, the Flash Memory Sum command can be used for software revision management.

## 3. Show Product Information command

The Show Product Information command provides the product name, on-chip memory configuration and the like. This command also reads out the contents of the flash memory locations at addresses shown below. In addition to the Show Flash Memory Sum command, these locations can be used for software revision management.

Product name	Area
TMPM370FY	0x3F83_FFF0 - 0x3F87_FFF3

## 4. Chip and Protection Bit Erase command

This command erases the entire area of the flash memory automatically without verifying a password. All the blocks in the memory cell and their protection conditions are erased even when any of the blocks are prohibited from writing and erasing. When the command is completed, the SECBIT <SECBIT> bit is set to "1".

This command serves to recover boot programming operation when a user forgets the password. Therefore password verification is not executed.



- 1) RAM Transfer Command (See Table 19-6)
  1. The 1st byte specifies which one of the two serial operation modes is used. For a detailed description of how the serial operation mode is determined, see Determination of a Serial Operation Mode described later. If it is determined as UART mode, the boot program then checks if the SIO0 is programmable to the baud rate at which the 1st byte was transferred. During the first-byte interval, the RXE bit in the HSC0MOD register is cleared.
    - To communicate in UART mode  
Send, from the controller to the target board, 86H in UART data format at the desired baud rate. If the serial operation mode is determined as UART, then the boot program checks if the SIO0 can be programmed to the baud rate at which the first byte was transferred. If that baud rate is not possible, the boot program aborts, disabling any subsequent communications.
    - To communicate in I/O Interface mode  
Send, from the controller to the target board, 0x30 in I/O Interface data format at 1/16 of the desired baud rate. Also send the 2nd byte at the same baud rate. Then send all subsequent bytes at a rate equal to the desired baud rate.

In I/O Interface mode, the CPU sees the serial receive pin as if it were a general input port in monitoring its logic transitions. If the baud rate of the incoming data is high or the chip's operating frequency is high, the CPU may not be able to keep up with the speed of logic transitions. To prevent such situations, the 1st and 2nd bytes must be transferred at 1/16 of the desired baud rate; then the boot program calculates 16 times that as the desired baud rate. When the serial operation mode is determined as I/O Interface mode, the SIO0 is configured for SCLK Input mode. Beginning with the third byte, the controller must ensure that its AC timing restrictions are satisfied at the selected baud rate. In the case of I/O Interface mode, the boot program does not check the receive error flag; thus there is no such thing as error acknowledge (bit 3, 0xN8).
  2. The 2nd byte, transmitted from the target board to the controller, is an acknowledge response to the 1st byte. The boot program echoes back the first byte: 0x86 for UART mode and 0x30 for I/O Interface mode.

#### UART mode

If the SIO0 can be programmed to the baud rate at which the 1st byte was transferred, the boot program programs the SC0BRCCR and sends back 0x86 to the controller as an acknowledge. If the SIO0 is not programmable at that baud rate, the boot program simply aborts with no error indication. Following the 1st byte, the controller should allow for a time-out period of five seconds. If it does not receive 0x86 within the allowed time-out period, the controller should give up the communication. The boot program sets the RXE bit in the SC0MOD0 register to enable reception (1) before loading the SIO transmit buffer with 0x86.

- I/O Interface mode  
The boot program programs the SC0MOD0 and SC0CR registers to configure the SIO0 in I/O Interface mode (clocked by the rising edge of SCLK0), writes 0x30 to

the SC0BUF. Then, the SIO0 waits for the SCLK0 signal to come from the controller. Following the transmission of the 1st byte, the controller should send the SCLK clock to the target board after a certain idle time (several microseconds). This must be done at 1/16 the desired baud rate. If the 2nd byte, which is from the target board to the controller, is 0x30, then the controller should take it as a go-ahead. The controller must then deliver the 3rd byte to the target board at a rate equal to the desired baud rate. The boot program sets the RXE bit in the SC0MOD register to enable reception before loading the SIO transmit buffer with 0x30.

3. The 3rd byte transmitted from the controller to the target board is a command. The code for the RAM Transfer command is 0x10.
4. The 4th byte, transmitted from the target board to the controller, is an acknowledge response to the 3rd byte. Before sending back the acknowledge response, the boot program checks for a receive error. If there was a receive error, the boot program transmits x8H (bit 3) and returns to the state in which it waits for a command (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command. When the SIO0 is configured for I/O Interface mode, the boot program does not check for a receive error.

If the 3rd byte is equal to any of the command codes listed in Table 19-4, the boot program echoes it back to the controller. When the RAM Transfer command was received, the boot program echoes back a value of 0x10 and then branches to the RAM Transfer routine. Once this branch is taken, password verification is done. Password verification is detailed in a later section "Password". If the 3rd byte is not a valid command, the boot program sends back 0xN1 (bit 0) to the controller and returns to the state in which it waits for a command (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

5. The 5th to 16th bytes transmitted from the controller to the target board, are a 12-byte password. Each byte is compared to the contents of following addresses in the flash memory. The verification is started with the 5<sup>th</sup> byte and the smallest address in the designated area. If the password verification fails, the RAM Transfer routine sets the password error flag.

Product name	Area
TMPM370FY	0x3F83_FFF4 - 0x3F83_FFFF

6. The 17th byte is a checksum value for the password sequence (5th to 16th bytes). To calculate the checksum value for the 12-byte password, add the 12 bytes together, drop the carries and take the two's complement of the total sum. Transmit this checksum value from the controller to the target board. The checksum calculation is described in details in a later section "Checksum Calculation".
7. The 18th byte, transmitted from the target board to the controller, is an acknowledge response to the 5th to 17th bytes. First, the RAM Transfer routine checks for a receive error in the 5th to 17th bytes. If there was a receive error, the boot program sends back 18H (bit 3) and returns to the state in which it waits for a command (i.e., the 3rd byte)

again. In this case, the upper four bits of the acknowledge response are the same as those of the previously issued command (i.e., all 1s). When the SIO0 is configured for I/O Interface mode, the RAM Transfer routine does not check for a receive error.

Next, the RAM Transfer routine performs the checksum operation to ensure data integrity. Adding the series of the 5th to 16th bytes must result in 0x00 (with the carry dropped). If it is not 0x00, one or more bytes of data has been corrupted. In case of a checksum error, the RAM Transfer routine sends back 0x11 to the controller and returns to the state in which it waits for a command (i.e., the 3rd byte) again.

Finally, the RAM Transfer routine examines the result of the password verification. The following two cases are treated as a password error. In these cases, the RAM Transfer routine sends back 0x11 (bit 0) to the controller and returns to the state in which it waits for a command (i.e., the 3rd byte) again.

- Irrespective of the result of the password comparison, all the 12 bytes of a password in the flash memory are the same value other than 0xFF. Not the entire password bytes transmitted from the controller matched those contained in the flash memory.

When all the above verification has been successful, the RAM Transfer routine returns a normal acknowledge response (0x10) to the controller.

8. The 19th to 22nd bytes, transmitted from the controller the target board, indicate the start address of the RAM region where subsequent data (e.g., a flash programming routine) should be stored. The 19th byte corresponds to bits 31–24 of the address and the 22nd byte corresponds to bits 7–0 of the address.
9. The 23rd and 24th bytes, transmitted from the controller to the target board, indicate the number of bytes that will be transferred from the controller to be stored in the RAM. The 23rd byte corresponds to bits 15–8 of the number of bytes to be transferred, and the 24th byte corresponds to bits 7–0 of the number of bytes.
10. The 25th byte is a checksum value for the 19th to 24th bytes. To calculate the checksum value, add all these bytes together, drop the carries and take the two's complement of the total sum. Transmit this checksum value from the controller to the target board. The checksum calculation is described in details in a later section "Checksum Calculation".
11. The 26th byte, transmitted from the target board to the controller, is an acknowledge response to the 19th to 25th bytes of data. First, the RAM Transfer routine checks for a receive error in the 19th to 25th bytes. If there was a receive error, the RAM Transfer routine sends back 0x18 and returns to the command wait state (i.e., the 3rd byte) again. In this case, the upper four bits of the acknowledge response are the same as those of the previously issued command (i.e., all 1s). When the SIO0 is configured for I/O Interface mode, the RAM Transfer routine does not check for a receive error.

Next, the RAM Transfer routine performs the checksum operation to ensure data integrity. Adding the series of the 19th to 25th bytes must result in 00H (with the carry dropped). If it is not 00H, one or more bytes of data has been corrupted. In case of a

checksum error, the RAM Transfer routine sends back 0x11 to the controller and returns to the state in which it waits for a command (i.e., the 3rd byte) again.

- The RAM storage start address must be within the range of 0x2000\_0400 to the end address of RAM.

When the above checks have been successful, the RAM Transfer routine returns a normal acknowledge response (0x10) to the controller.

12. The 27th to mth bytes from the controller are stored in the on-chip RAM of the TMPM370FY. Storage begins at the address specified by the 19th–22nd bytes and continues for the number of bytes specified by the 23rd–24th bytes.

13. The (m+1) th byte is a checksum value. To calculate the checksum value, add the 27th to mth bytes together, drop the carries and take the two's complement of the total sum. Transmit this checksum value from the controller to the target board. The checksum calculation is described in details in a later section "Checksum Calculation".

14. The (m+2) th byte is a acknowledge response to the 27th to (m+1) th bytes.

First, the RAM Transfer routine checks for a receive error in the 27th to (m+1) th bytes. If there was a receive error, the RAM Transfer routine sends back 18H (bit 3) and returns to the state in which it waits for a command (i.e., the 3rd byte) again. In this case, the upper four bits of the acknowledge response are the same as those of the previously issued command (i.e., all 1s). When the SIO0 is configured for I/O Interface mode, the RAM Transfer routine does not check for a receive error.

Next, the RAM Transfer routine performs the checksum operation to ensure data integrity. Adding the series of the 27th to (m+1) th bytes must result in 0x00 (with the carry dropped). If it is not 0x00, one or more bytes of data has been corrupted. In case of a checksum error, the RAM Transfer routine sends back 0x11 (bit 0) to the controller and returns to the command wait state (i.e., the 3rd byte) again. When the above checks have been successful, the RAM Transfer routine returns a normal acknowledge response (0x10) to the controller.

15. If the (m+2) th byte was a normal acknowledge response, a branch is made to the address specified by the 19th to 22nd bytes.

- 2) Show Flash Memory Sum Command (See Table 19-7)
  1. The processing of the 1st and 2nd bytes are the same as for the RAM Transfer command.
  2. The 3rd byte, which the target board receives from the controller, is a command. The code for the Show Flash Memory Sum command is 20H.
  3. The 4th byte, transmitted from the target board to the controller, is an acknowledge response to the 3rd byte. Before sending back the acknowledge response, the boot program checks for a receive error. If there was a receive error, the boot program transmits x8H (bit 3) and returns to the command wait state again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command. When the SIO0 is configured for I/O Interface mode, the boot program does not check for a receive error.

If the 3rd byte is equal to any of the command codes listed in Table 19-4, the boot program echoes it back to the controller. When the Show Flash Memory Sum command was received, the boot program echoes back a value of 0x20 and then branches to the Show Flash Memory Sum routine. If the 3rd byte is not a valid command, the boot program sends back 0xN1 (bit 0) to the controller and returns to the command wait state (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

4. The Show Flash Memory Sum routine adds all the bytes of the flash memory together. The 5th and 6th bytes, transmitted from the target board to the controller, indicate the upper and lower bytes of this total sum, respectively. For details on sum calculation, see a later section "Calculation of the Show Flash Memory Sum Command".
5. The 7th byte is a checksum value for the 5th and 6th bytes. To calculate the checksum value, add the 5th and 6th bytes together, drop the carry and take the two's complement of the sum. Transmit this checksum value from the controller to the target board.
6. The 8th byte is the next command code.

## 3) Show Product Information Command (See Table 19-8)

1. The processing of the 1st and 2nd bytes are the same as for the RAM Transfer command.
2. The 3rd byte, which the target board receives from the controller, is a command. The code for the Show Product Information command is 30H.
3. The 4th byte, transmitted from the target board to the controller, is an acknowledge response to the 3rd byte. Before sending back the acknowledge response, the boot program checks for a receive error. If there was a receive error, the boot program transmits 0xN8 (bit 3) and returns to the command wait state again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command. When the SIO0 is configured for I/O Interface mode, the boot program does not check for a receive error.

If the 3rd byte is equal to any of the command codes listed in Table 19-4, the boot program echoes it back to the controller. When the Show Flash Memory Sum command was received, the boot program echoes back a value of 0x30 and then branches to the Show Flash Memory Sum routine. If the 3rd byte is not a valid command, the boot program sends back 0xN1 (bit 0) to the controller and returns to the state in which it waits for a command (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

4. The 5th to 8th bytes, transmitted from the target board to the controller, are the data read from addresses shown below in the flash memory. Software version management is possible by storing a software ID in these locations.

Product name	Area
TMPM370FY	0x3F87_FFF0 - 0x3F87_FFF3

5. The 9th to 20th bytes, transmitted from the target board to the controller, indicate the product name as shown below (where [ ] is a space) in ASCII code.

Product name	Code
TMPM370FY	T, M, P, M, 3, 7, 0, F, Y, _, [ ], _

6. The 21st to 24th bytes, transmitted from the target board to the controller, indicate the start address of the flash memory area containing the password. Each product has own start address shown below.

Product name	Address
TMPM370FY	0xF4, 0xFF, 0x87, 0x3F

7. The 25th to 28th bytes, transmitted from the target board to the controller, indicate the start address of the on-chip RAM, are 0x00, 0x00, 0x00 and 0x20.
8. The 29th to 32nd bytes, transmitted from the target board to the controller, are dummy data (0x00, 0x00, 0x00 and 0x00).
9. The 33rd to 36th bytes, transmitted from the target board to the controller, indicate the end address of the on-chip RAM, are 0xFF, 0x27, 0x00 and 0x20.
10. The 37th to 40th bytes, transmitted from the target board to the controller, are 0x00, 0x00, 0x00 and 0x00. The 41st to 44th bytes, transmitted from the target board to the controller, are 0x00, 0x00, 0x00 and 0x00.
11. The 45th and 46th bytes transmitted are 0x00, 0x00.
12. The 47th to 50th bytes, transmitted from the target board to the controller, indicate the start address of the on-chip flash memory, are 0x00, 0x00, 0x80, and 0x3F.
13. The 51st to 54th bytes, transmitted from the target board to the controller, indicate the end address of the on-chip flash memory, are 0xFF, 0xFF, 0x83 and 0x3F.
14. The 55th to 56th bytes, transmitted from the target board to the controller, indicate the number of flash blocks available, are 0x06 and 0x00.
15. The 57th to 83rd bytes, transmitted from the target board to the controller, contain information about the flash blocks. Flash blocks of the same size are treated as a group. Information about the flash blocks indicate the start address of a group, the size of the blocks in that group (in halfwords) and the number of the blocks in that group.  
  
The 57th to 65th bytes are the information about the 16-kbyte blocks. The 66th to 74th bytes are the information about the 32-kbyte blocks. The 75th to 83rd bytes are the information about the 64-kbyte blocks. The 84th to 92nd bytes are the information about the 128-kbyte blocks. See Table 19-8 for the values of bytes transmitted.
16. The 93rd byte, transmitted from the target board to the controller, is a checksum value for the 5th to 92nd bytes. The checksum value is calculated by adding all these bytes together, dropping the carry and taking the two's complement of the total sum.
17. The 94th byte is the next command code.



- 4) Chip and Protection Bit Erase command (See Table 19-9)
  1. The processing of the 1st and 2nd bytes are the same as for the RAM Transfer command.
  2. The 3rd byte, which the target board receives from the controller, is a command. The code for the Show Product Information command is 0x40.
  3. The 4th byte, transmitted from the target board to the controller, is an acknowledge response to the 3rd byte. Before sending back the acknowledge response, the boot program checks for a receive error. If there was a receive error, the boot program transmits x8H (bit 3) and returns to the command wait state again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

If the 3rd byte is equal to any of the command codes listed in Table 19-4, the boot program echoes it back to the controller. When the Show Flash Memory Sum command was received, the boot program echoes back a value of 0x40. If the 3rd byte is not a valid command, the boot program sends back 0xN1 (bit 0) to the controller and returns to the state in which it waits for a command (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.
  4. The 5th byte, transmitted from the target board to the controller, is the Chip Erase Enable command code (0x54).
  5. The 6th byte, transmitted from the target board to the controller, is an acknowledge response to the 5th byte.

Before sending back the acknowledge response, the boot program checks for a receive error. If there was a receive error, the boot program transmits 0xN8 (bit 3) and returns to the command wait state again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

If the 5th byte is equal to any of the command codes to enable erasing, the boot program echoes it back to the controller. When the Show Flash Memory Sum command was received, the boot program echoes back a value of 0x54 and then branches to the Chip Erase routine. If the 5th byte is not a valid command, the boot program sends back 0xN1 (bit 0) to the controller and returns to the state in which it waits for a command (the third byte) again. In this case, the upper four bits of the acknowledge response are undefined - they hold the same values as the upper four bits of the previously issued command.

6. The 7<sup>th</sup> byte indicates whether the Chip Erase command is normally completed or not.  
At normal completion, completion code (0x4F) is sent.  
When an error was detected, error code (0x4C) is sent.
  
7. The 9th byte is the next command code.

## 5) Acknowledge Responses

The boot program represents processing states with specific codes. Table 19-10 to Table 19-13 show the values of possible acknowledge responses to the received data. The upper four bits of the acknowledge response are equal to those of the command being executed. Bit 3 of the code indicates a receive error. Bit 0 indicates an invalid command error, a checksum error or a password error. Bit 1 and bit 2 are always 0. Receive error checking is not done in I/O Interface mode.

**Table 19-10 ACK Response to the Serial Operation Mode Byte**

Return Value	Meaning
0x86	The SIO can be configured to operate in UART mode. (See Note)
0x30	The SIO can be configured to operate in I/O Interface mode.

**(Note)** If the serial operation mode is determined as UART, the boot program checks if the SIO can be programmed to the baud rate at which the operation mode byte was transferred. If that baud rate is not possible, the boot program aborts, without sending back any response.

**Table 19-11 ACK Response to the Command Byte**

Return Value	Meaning
0xN8 (See Note)	A receive error occurred while getting a command code.
0xN1 (See Note)	An undefined command code was received. (Reception was completed normally.)
0x10	The RAM Transfer command was received.
0x20	The Show Flash Memory Sum command was received.
0x30	The Show Product Information command was received.
0x40	The Chip Erase command was received.

**(Note)** The upper four bits of the ACK response are the same as those of the previous command code.

**Table 19-12 ACK Response to the Checksum Byte**

Return Value	Meaning
0xN8 (See Note)	A receive error occurred.
0xN1 (See Note)	A checksum or password error occurred.
0xN0 (See Note)	The checksum was correct.

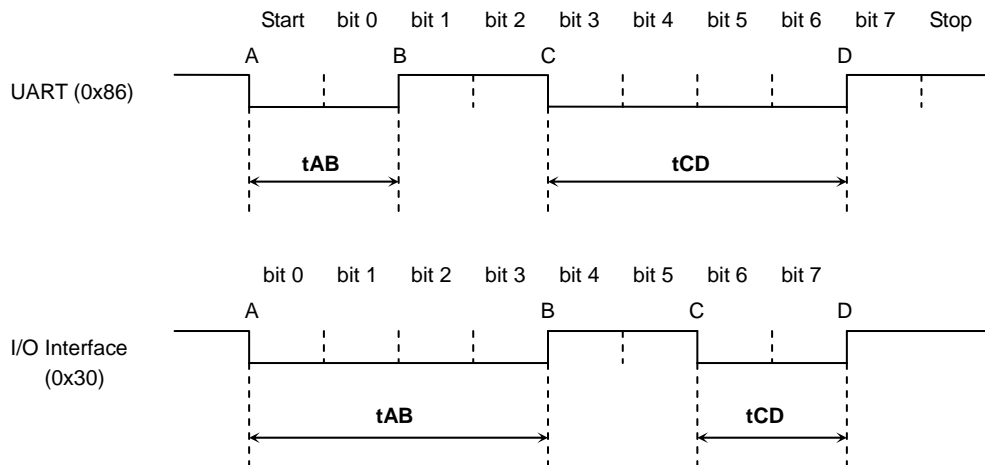
**(Note)** The upper four bits of the ACK response are the same as those of the operation command code. It is 1 ( N=RAM transfer command data [7:4] ) when password error occurs.

**Table 19-13 ACK Response to Chip and Protection Bit Erase Byte**

Return Value	Meaning
0x54	The Chip Erase enabling command was received.
0x4F	The Chip Erase command was completed.
0x4C	The Chip Erase command was abnormally completed.

## 6) Determination of a Serial Operation Mode

The first byte from the controller determines the serial operation mode. To use UART mode for communications between the controller and the target board, the controller must first send a value of 0x86 at a desired baud rate to the target board. To use I/O Interface mode, the controller must send a value of 0x30 at 1/16 the desired baud rate. Fig. 19-4 shows the waveforms for the first byte.



**Fig. 19-4 Serial Operation Mode Byte**

After  $\overline{\text{RESET}}$  is released, the boot program monitors the first serial byte from the controller, with the SIO reception disabled, and calculates the intervals of  $t_{AB}$ ,  $t_{AC}$  and  $t_{AD}$ . Fig. 19-5 shows a flowchart describing the steps to determine the intervals of  $t_{AB}$ ,  $t_{AC}$  and  $t_{AD}$ . As shown in the flowchart, the boot program captures timer counts each time a logic transition occurs in the first serial byte. Consequently, the calculated  $t_{AB}$ ,  $t_{AC}$  and  $t_{AD}$  intervals are bound to have slight errors. If the transfer goes at a high baud rate, the CPU might not be able to keep up with the speed of logic transitions at the serial receive pin. In particular, I/O Interface mode is more prone to this problem since its baud rate is generally much higher than that for UART mode. To avoid such a situation, the controller should send the first serial byte at 1/16 the desired baud rate.

The flowchart in Fig. 19-5 shows how the boot program distinguishes between UART and I/O Interface modes. If the length of  $t_{AB}$  is equal to or less than the length of  $t_{CD}$ , the serial operation mode is determined as UART mode. If the length of  $t_{AB}$  is greater than the length of  $t_{CD}$ , the serial operation mode is determined as I/O Interface mode. Bear in mind that if the baud rate is too high or the timer operating frequency is too low, the timer resolution will be coarse, relative to the intervals between logic transitions. This becomes a problem due to inherent errors caused by the way in which timer counts are captured by software; consequently the boot program might not be able to determine the serial operation mode correctly. To prevent this problem, reset UART mode within the programming routine.

For example, the serial operation mode may be determined to be I/O Interface mode when the intended mode is UART mode. To avoid such a situation, when UART mode is utilized, the controller should allow for a time-out period within which it expects to receive an echo-back (0x86) from the target board. The controller should give up the communication if it fails to get that echo-back within the allowed time. When I/O Interface mode is utilized, once the first serial byte has been transmitted, the controller should send the SCLK clock after a certain idle time to get an acknowledge response. If the received acknowledge response is not 0x30, the controller should give up further communications.

When the intended mode is I/O interface mode, the first byte does not have to be 0x30 as long as  $t_{AB}$  is

greater than  $t_{CD}$  as shown above. 0x91, 0xA1 or 0xB1 can be sent as the first byte code to determine the falling edges of Point A and Point C and the rising edges of Point B and Point D. If  $t_{AB}$  is greater than  $t_{CD}$  and SIO is selected by the resolution of the operation mode determination, the second byte code is 0x30 even though the transmitted code on the first byte is not 0x30 (The first byte code to determine I/O interface mode is described as 0x30).

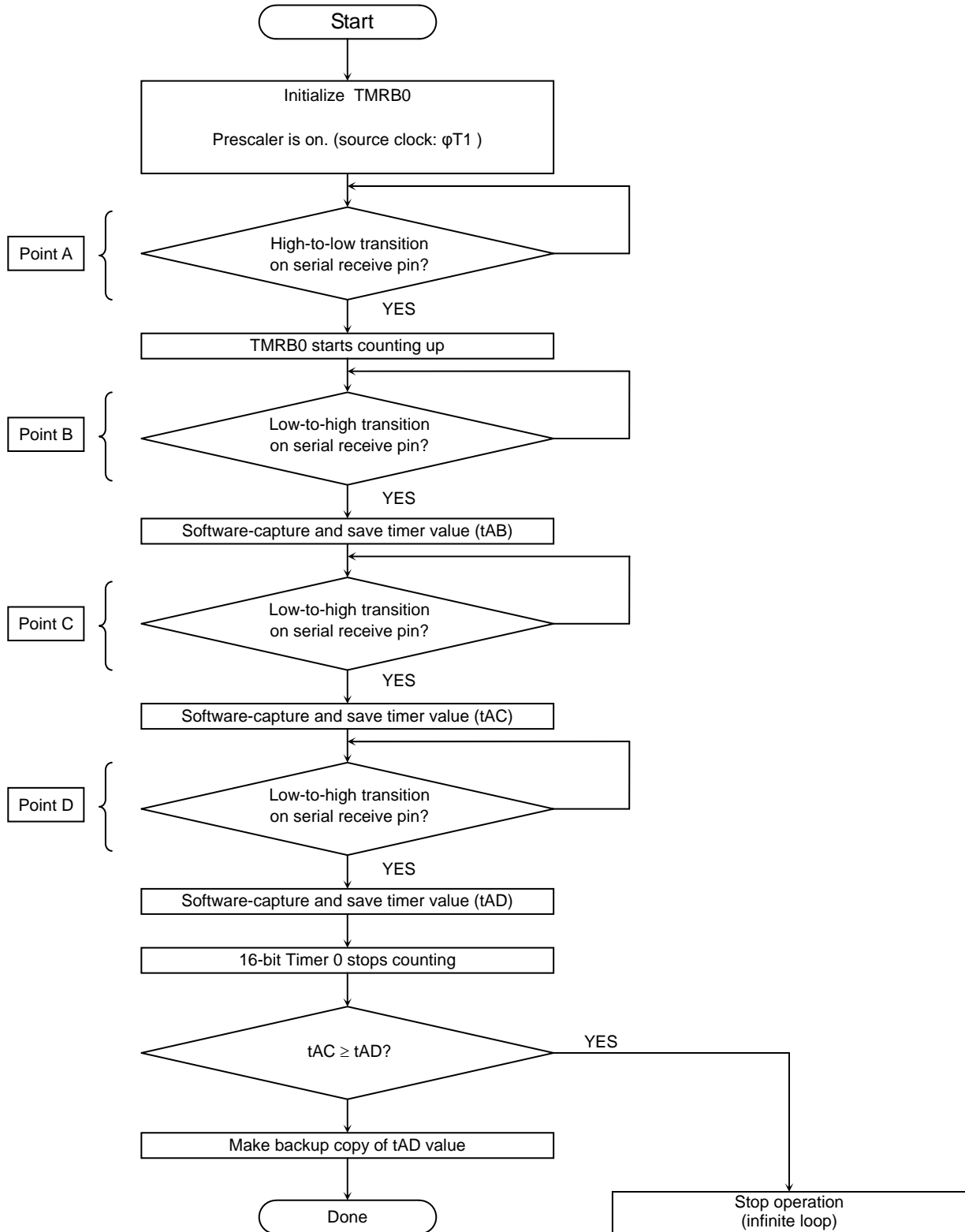
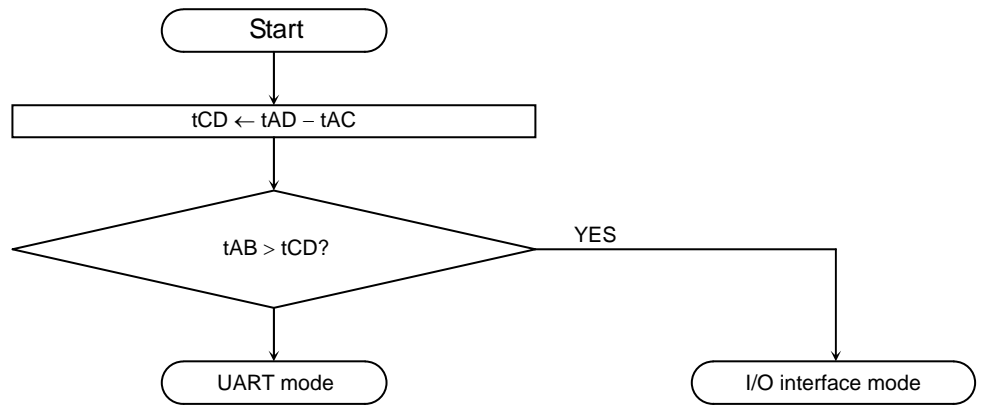


Fig. 19-5 Serial Operation Mode Byte Reception Flow



**Fig. 19-6 Serial Operation Mode Determination Flow**

7) Password

The RAM Transfer command (0x10) causes the boot program to perform password verification. Following an echo-back of the command code, the boot program verifies the contents of the 12-byte password area within the flash memory. The following table shows the password area.

Product name	Area
TMPM370FY	0x3F83_FFF4 - 0x3F83_FFFF

If all these address locations contain the same bytes of data other than 0xFF, a password area error occurs as shown in

**Fig. 19-7.** In this case, the boot program returns an error acknowledge (0x11) in response to the checksum byte (the 17th byte), regardless of whether the password sequence sent from the controller is all 0xFFs.

The password sequence received from the controller (5th to 16th bytes) is compared to the password stored in the flash memory. All of the 12 bytes must match to pass the password verification. Otherwise, a password error occurs, which causes the boot program to reply an error acknowledge in response to the checksum byte (the 17th byte).

The password verification is performed even if the security function is enabled.

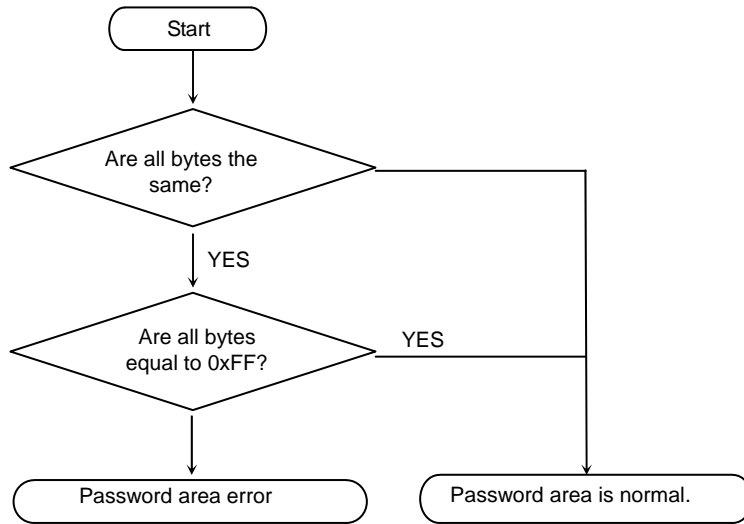


Fig. 19-7 Password Area Verification Flow



## 8) Calculation of the Show Flash Memory Sum Command

The result of the sum calculation “byte + byte + byte + ...” is responded by a word quantity. The Show Flash Memory Sum command adds all 256 Kbytes of the flash memory together and provides the total sum as a word quantity. The sum is sent to the controller, with the upper eight bits first, followed by the lower eight bits.

Example)

0xA1
0xB2
0xC3
0xD4

For the interest of simplicity, assume the depth of the flash memory is four locations. Then the sum of the four bytes is calculated as:

$$0xA1 + 0xB2 + 0xC3 + 0xD4 = 0x02EA$$

Hence, 0x02 is first sent to the controller, followed by 0xEA.

## 9) Checksum Calculation

The checksum byte for a series of bytes of data is calculated by adding the bytes together, dropping the carries, and taking the two's complement of the total sum. The Show Flash Memory Sum command and the Show Product Information command perform the checksum calculation. The controller must perform the same checksum operation in transmitting checksum bytes.

Example) Assume the Show Flash Memory Sum command provides the upper and lower bytes of the sum as 0xE5 and 0xF6. To calculate the checksum for a series of 0xE5 and 0xF6:

Add the bytes together

$$0xE5 + 0xF6 = 0x1DB$$

Take the two's complement of the sum, and that is the checksum byte.

$$0 - 0xDB = 0x25$$

(7) General Boot Program Flowchart

Fig. 19-8 shows an overall flowchart of the boot program.

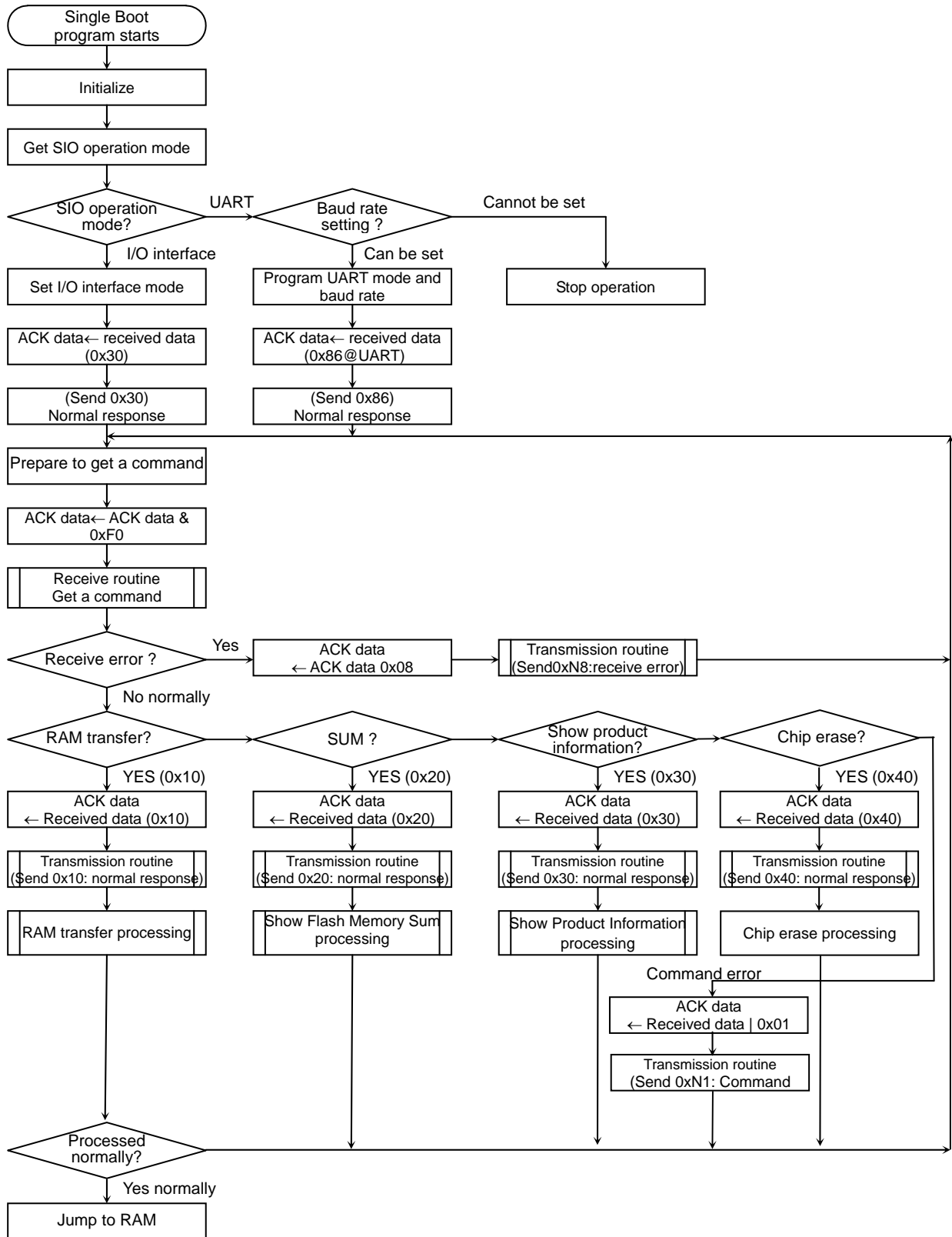


Fig. 19-8 Overall Boot Program Flow

### 19.3 On-board Programming of Flash Memory (Rewrite/Erase)

In on-board programming, the CPU is to execute software commands for rewriting or erasing the flash memory. The rewrite/erase control program should be prepared by the user beforehand. Because the flash memory content cannot be read while it is being written or erased, it is necessary to run the rewrite/erase program from the internal RAM or from an external memory device after shifting to the user boot mode.

#### 19.3.1 Flash Memory

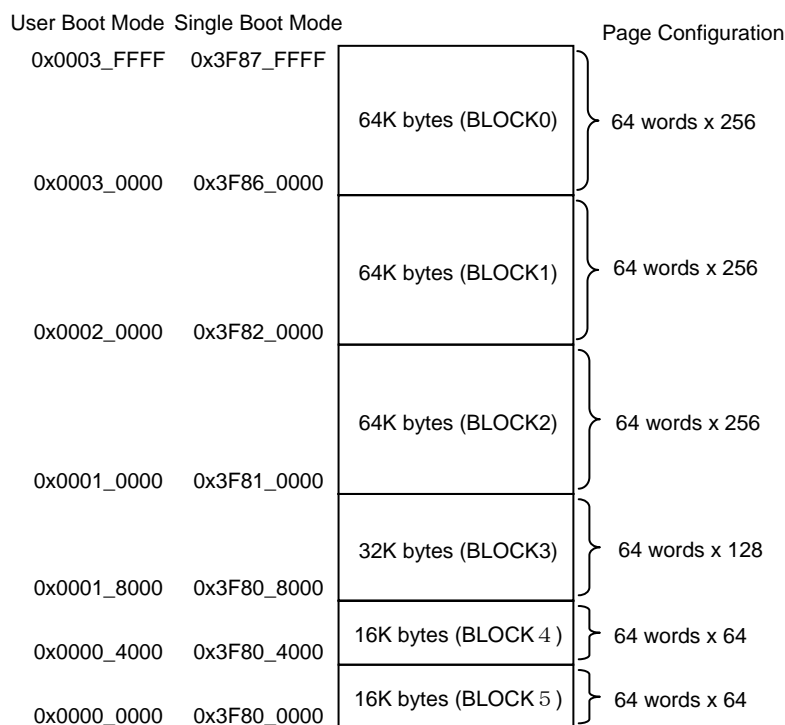
Except for some functions, writing and erasing flash memory data are in accordance with the standard JEDEC commands. In writing or erasing, use 32-bit data transfer command of the CPU to enter commands to the flash memory. Once the command is entered, the actual write or erase operation is automatically performed internally.

**Table 19-14 Flash Memory Functions**

Major functions	Description
Automatic page program	Writes data automatically per page.
Automatic chip erase	Erases the entire area of the flash memory automatically.
Automatic block erase	Erases a selected block automatically.
Protect function	By writing a 4-bit protection code, the write or erase function can be individually inhibited for each block.

Note that addressing of operation commands is different from the case of standard commands due to the specific interface arrangements with the CPU. Also note that the flash memory is written in 32-bit blocks. So, 32-bit (word) data transfer commands must be used in writing the flash memory.

(1) Block configuration



**Fig. 19-9 Block Configuration of Flash Memory (TMPM370FY)**

## (2) Basic operation

Generally speaking, this flash memory device has the following two operation modes:

- The mode to read memory data (Read mode)
- The mode to automatically erase or rewrite memory data (Automatic operation)

Transition to the automatic mode is made by executing a command sequence while it is in the memory read mode. In the automatic operation mode, flash memory data cannot be read and any commands stored in the flash memory cannot be executed. In the automatic operation mode, any interrupt or exception generation cannot set the device to the read mode except when a hardware reset is generated. During automatic operation, be sure not to cause any exceptions other than debug exceptions and reset while a debug port is connected. Any exception generation cannot set the device to the read mode except when a hardware reset is generated.

### 1) Read

When data is to be read, the flash memory must be set to the read mode. The flash memory will be set to the read mode immediately after power is applied, when CPU reset is removed, or when an automatic operation is normally terminated. In order to return to the read mode from other modes or after an automatic operation has been abnormally terminated, either the Read/reset command (a software command to be described later) or a hardware reset is used. The device must also be in the read mode when any command written on the flash memory is to be executed.

- **Read/reset command and Read command (software reset)**

When ID-Read command is used, the reading operation is terminated instead of automatically returning to the read mode. In this case, the Read/reset command can be used to return the flash memory to the read mode. Also, when a command that has not been completely written has to be canceled, the Read/reset command must be used. The Read command is used to return to the read mode after executing 32-bit data transfer command to write the data "0x0000\_00F0" to an arbitrary address of the flash memory.

- **With the Read/reset command, the device is returned to the read mode after completing the third bus write cycle.**

### 2) Command write

This flash memory uses the command control method. Commands are executed by executing a command sequence to the flash memory. The flash memory executes automatic operation commands according to the address and data combinations applied (refer to Command Sequence).

If it is desired to cancel a command write operation already in progress or when any incorrect command sequence has been entered, the Read/reset command is to be executed. Then, the flash memory will terminate the command execution and return to the read

While commands are generally comprised of several bus cycles, the operation to apply 32-bit data transmit command to the flash memory is called "bus write cycle." The bus write cycles are to be in a specific sequential order and the flash memory will perform an automatic operation when the sequence of the bus write cycle data and address of a command write operation is in accordance with a predefined specific sequence. If any bus write cycle does not follow a

predefined command write sequence, the flash memory will terminate the command execution and return to the read mode.

**(Note 1) Command sequences are executed from outside the flash memory area.**

**(Note 2) Each bus write cycle must be sequentially executed by 32-bit data transmit command. While a command sequence is being executed, access to the flash memory is prohibited. Also, don't generate any interrupt (except debug exceptions when a DSU probe is connected). If such an operation is made, it can result in an unexpected read access to the flash memory and the command sequencer may not be able to correctly recognize the command. While it could cause an abnormal termination of the command sequence, it is also possible that the written command is incorrectly recognized.**

**(Note 3) For the command sequencer to recognize a command, the device must be in the read mode prior to executing the command. Be sure to check before the first bus write cycle that the FLCS RDY/BSY bit is set to "1." It is recommended to subsequently execute a Read command.**

**(Note 4) Upon issuing a command, if any address or data is incorrectly written, be sure to perform a software reset to return to the read mode again.**

### (3) Reset

#### Hardware reset

A hardware reset is used to cancel the operational mode set by the command write operation when forcibly termination during auto programming/ erasing or abnormal termination during auto operations occurs. The flash memory has a reset input as the memory block and it is connected to the CPU reset signal. Therefore, when the RESET input pin of this device is set to  $V_{IL}$  or when the CPU is reset due to any overflow of the watch dog timer, the flash memory will return to the read mode terminating any automatic operation that may be in progress. It should also be noted that applying a hardware reset during an automatic operation can result in incorrect rewriting of data. In such a case, be sure to perform the rewriting again.

Refer to Section 19.2.1 "Reset Operation" for CPU reset operations. After a given reset input, the CPU will read the reset vector data from the flash memory and starts operation after the reset is removed.

## (4) Commands

## 1) Automatic Page Programming

Writing to a flash memory device is to make "1" data cells to "0" data cells. Any "0" data cell cannot be changed to a "1" data cell. For making "0" data cells to "1" data cells, it is necessary to perform an erase operation.

The automatic page programming function of this device writes data of each page. The TMPM370FY contains 64 words in a page. A 64 word block is defined by a same [31:8] address and it starts from the address [7:0] = 0 and ends at the address [7:0] = 0xFF. This programming unit is hereafter referred to as a "page."

Writing to data cells is automatically performed by an internal sequencer and no external control by the CPU is required. The state of automatic page programming (whether it is in writing operation or not) can be checked by the FLCS [0] <RDY/BSY> register.

Also, any new command sequence is not accepted while it is in the automatic page programming mode. If it is desired to interrupt the automatic page programming, use the hardware reset function. If the operation is stopped by a hardware reset operation, it is necessary to once erase the page and then perform the automatic page programming again because writing to the page has not been normally terminated.

The automatic page programming operation is allowed only once for a page already erased. No programming can be performed twice or more times irrespective of the data cell value whether it is "1" or "0." Note that rewriting to a page that has been once written requires execution of the automatic block erase or automatic chip erase command before executing the automatic page programming command again. Note that an attempt to rewrite a page two or more times without erasing the content can cause damages to the device.

No automatic verify operation is performed internally to the device. So, be sure to read the data programmed to confirm that it has been correctly written.

The automatic page programming operation starts when the third bus write cycle of the command cycle is completed. On and after the fifth bus write cycle, data will be written sequentially starting from the next address of the address specified in the fourth bus write cycle (in the fourth bus write cycle, the page top address will be command written) (32 bits of data is input at a time). Be sure to use the 32-bit data transfer command in writing commands on and after the fourth bus cycle. In this, any 32-bit data transfer commands shall not be placed across word boundary. On and after the fifth bus write cycle, data is command written to the same page area. Even if it is desired to write the page only partially, it is required to perform the automatic page programming for the entire page. In this case, the address input for the fourth bus write cycle shall be set to the top address of the page. Be sure to perform command write operation with the input data set to "1" for the data cells not to be set to "0." For example, if the top address of a page is not to be written, set the input data of the fourth bus write cycle to 0xFFFFFFFF to command write the data.

Once the fourth bus cycle is executed, it is in the automatic programming operation. This condition can be checked by monitoring the register bit FLCS [0] <RDY/BSY> (See Table 19-15). Any new command sequence is not accepted while it is in automatic page programming mode. If it is desired to stop operation, use the hardware reset function. Be careful in doing so because data cannot be written normally if the operation is interrupted.

When a single page has been command written normally terminating the automatic page writing process, the FLCS [0] <RDY/BSY> bit is set to "1" and it returns to the read mode. When multiple pages are to be written, it is necessary to execute the page programming command for each page because the number of pages to be written by a single execution of the automatic page program command is limited to only one page. It is not allowed for automatic page programming to process input data across pages.

Data cannot be written to a protected block. When automatic programming is finished, it automatically returns to the read mode. This condition can be checked by monitoring FLCS [0] <RDY/BSY> (Table 19-15). If automatic programming has failed, the flash memory is locked in the mode and will not return to the read mode. For returning to the read mode, it is necessary to execute hardware reset to reset the flash memory or the device. In this case, while writing to the address has failed, it is recommended not to use the device or not to use the block that includes the failed address.

**(Note) Software reset becomes ineffective in bus write cycles on and after the fourth bus write cycle of the automatic page programming command.**

2) Automatic chip erase

The automatic chip erase operation starts when the sixth bus write cycle of the command cycle is completed.

This condition can be checked by monitoring FLCS [0] <RDY/BSY> (See Table 19-15). While no automatic verify operation is performed internally to the device, be sure to read the data to confirm that data has been correctly erased. Any new command sequence is not accepted while it is in an automatic chip erase operation. If it is desired to stop operation, use the hardware reset function. If the operation is forced to stop, it is necessary to perform the automatic chip erase operation again because the data erasing operation has not been normally terminated.

Also, any protected blocks cannot be erased. If all the blocks are protected, the automatic chip erase operation will not be performed and it returns to the read mode after completing the sixth bus read cycle of the command sequence. When an automatic chip erase operation is normally terminated, it automatically returns to the read mode. If an automatic chip erase operation has failed, the flash memory is locked in the mode and will not return to the read mode.

For returning to the read mode, it is necessary to execute hardware reset to reset the device. In this case, the failed block cannot be detected. It is recommended not to use the device anymore or to identify the failed block by using the block erase function for not to use the identified block anymore.

3) Automatic block erase (fro aech block)

The automatic block erase operation starts when the sixth bus write cycle of the command cycle is completed.

This status of the automatic block erase operation can be checked by monitoring FLCS <RDY/BSY> (See Table 19-15). While no automatic verify operation is performed internally to the device, be sure to read the data to confirm that data has been correctly erased. Any new command sequence is not accepted while it is in an automatic block erase operation. If it is desired to stop operation, use the hardware reset function. In this case, it is necessary

to perform the automatic block erase operation again because the data erasing operation has not been normally terminated.

Also, any protected blocks cannot be erased. If an automatic block erase operation has failed, the flash memory is locked in the mode and will not return to the read mode. In this case, execute hardware reset to reset the device.

4) Automatic programming of protection bits (for each block)

This device is implemented with protection bits. This protection can be set for each block. See Table 19-20 for table of protection bit addresses. This device assigns 1 bit to 1 block as a protection bit. The applicable protection bit is specified by PBA in the seventh bus write cycle. By automatically programming the protection bits, write and/or erase functions can be inhibited (for protection) individually for each block. The protection status of each block can be checked by the FLCS <BLPRO> register to be described later. This status of the automatic programming operation to set protection bits can be checked by monitoring FLCS <RDY/BSY> (See Table 19-15). Any new command sequence is not accepted while automatic programming is in progress to program the protection bits. If it is desired to stop the programming operation, use the hardware reset function. In this case, it is necessary to perform the programming operation again because the protection bits may not have been correctly programmed. If all the protection bits have been programmed, all the FLCS <BLPRO> bits are set to "1" indicating that it is in the protected state (See Table 19-15). This disables subsequent writing and erasing of all blocks.

**(Note) Software reset is ineffective in the seventh bus write cycle of the automatic protection bit programming command. The FLCS <RDY/BSY> bit turns to "0" after entering the seventh bus write cycle.**



## 5) Automatic erasing of protection bits

Different results will be obtained when the automatic protection bit erase command is executed depending on the status of the protection bits and the security bits. It depends on the status of FLCS <BLPRO> whether all the <BLPRO> bits are set to "1" or not if SECBIT<SECBIT> is 0x1. Be sure to check the value of FLCS <BLPRO> before executing the automatic protection bit erase command. See chapter 17 for details.

· **When all the FLCS <BLPRO> bits are set to "1" (all the protection bits are programmed):**

When the automatic protection bit erase command is command written, the flash memory is automatically initialized within the device. When the seventh bus write cycle is completed, the entire area of the flash memory data cells is erased and then the protection bits are erased. This operation can be checked by monitoring FLCS <RDY/BSY>. If the automatic operation to erase protection bits is normally terminated, FLCS will be set to "0x00000001." While no automatic verify operation is performed internally to the device, be sure to read the data to confirm that it has been correctly erased. For returning to the read mode while the automatic operation after the seventh bus cycle is in progress, it is necessary to use the hardware reset to reset the device. If this is done, it is necessary to check the status of protection bits by FLCS <BLPRO> after returning to the read mode and perform either the automatic protection bit erase, automatic chip erase, or automatic block erase operation, as appropriate.

· **When the FLCS <BLPRO> bits include "0" (not all the protection bits are programmed):**

The protection condition can be canceled by the automatic protection bit erase operation. With this device, protection bits set by an individual block can be erased handling all the blocks at a time as shown in Table 19-21. The target bits are specified in the seventh bus write cycle and when the command is completed, the device is in a condition all the blocks are erased. The protection status of each block can be checked by FLCS <BLPRO> to be described later. This status of the programming operation for automatic protection bits can be checked by monitoring FLCS <RDY/BSY>. When the automatic operation to erase protection bits is normally terminated, the protection bits of FLCS <BLPRO> selected for erasure are set to "0."

In any case, any new command sequence is not accepted while it is in an automatic operation to erase protection bits. If it is desired to stop the operation, use the hardware reset function. When the automatic operation to erase protection bits is normally terminated, it returns to the read mode.

**(Note) The FLCS <RDY/BSY> bit is "0" while in automatic operation and it turns to "1" when the automatic operation is terminated.**

## 6) ID-Read

Using the ID-Read command, you can obtain the type and other information on the flash memory contained in the device. The data to be loaded will be different depending on the address [15:14] of the fourth and subsequent bus write cycles (recommended input data is 0x00). On and after the fourth bus write cycle, when an arbitrary flash memory area is read, the ID value will be loaded. Once the fourth bus write cycle of an ID-Read command has passed, the device will not automatically return to the read mode. In this condition, the set of the fourth bus write cycle and ID-Read commands can be repetitively executed. For returning to the read mode, use the Read/reset command or hardware reset command.

## (5) Flash control/ status register

This register is used to monitor the status of the flash memory and to indicate the protection status of each block.

Table 19-15 Flash Control Register

FLCS  
0x41FF\_F020

	31	30	29	28	27	26	25	24
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
Function	"0" is read.							
	23	22	21	20	19	18	17	16
bit Symbol	-	-	BLPRO5	BLPRO4	BLPRO3	BLPRO2	BLPRO1	BLPRO0
Read/Write	R		R	R	R	R	R	R
After reset	0		(Note 2)	(Note 2)	(Note 2)	(Note 2)	(Note 2)	(Note 2)
Function	"0" is read.		Protection for Block 5 0: disabled 1: enabled	Protection for Block 4 0: disabled 1: enabled	Protection for Block 3 0: disabled 1: enabled	Protection for Block 2 0: disabled 1: enabled	Protection for Block 1 0: disabled 1: enabled	Protection for Block 0 0: disabled 1: enabled
	15	14	13	12	11	10	9	8
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
Function	"0" is read.							
	7	6	5	4	3	2	1	0
bit Symbol	-	-	-	-	-	-	-	RDY/BSY
Read/Write	R							R
After reset	0							1
Function	"0" is read.							Ready/Busy (Note 1) 0: Auto operating 1: Auto operation terminated

## Bit 0: Ready/Busy flag bit

The RDY/BSY output is provided as a means to monitor the status of automatic operation. This bit is a function bit for the CPU to monitor the function. When the flash memory is in automatic operation, it outputs "0" to indicate that it is busy. When the automatic operation is terminated, it returns to the ready state and outputs "1" to accept the next command. If the automatic operation has failed, this bit maintains the "0" output. By applying a hardware reset, it returns to "1."

## Bit [21:16]: Protection status bits

Each of the protection bits represents the protection status of the corresponding block. When a bit is set to "1," it indicates that the block corresponding to the bit is protected. When the block is protected, data cannot be written to it.

**(Note 1)** This command must be issued in the ready state. Issuing the command in the busy state may disable both correct command transmission and further command input. To exit from the condition, execute system reset. System reset requires at least 0.5 microseconds regardless of the system clock frequency. In this condition, it takes approx. 2 ms to enable reading after reset.

**(Note 2)** The value varies depending on protection applied.

**Table 19-16 Security bit register**

SECBIT  
0x41FF\_F010

	31	30	29	28	27	26	25	24
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
Function	'0' is read							
	23	22	21	20	19	18	17	16
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
Function	'0' is read							
	15	14	13	12	11	10	9	8
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
Function	'0' is read							
	7	6	5	4	3	2	1	0
bit Symbol	-	-	-	-	-	-	-	SECBIT
Read/Write	R							R/W
After reset	0							1
Function	'0' is read							Security bits 0:disabled 1:enabled

**(Note)** This register is initialized only by power-on reset.

## (6) List of Command Sequences

Table 19-17 Flash Memory Access from the Internal CPU

Command sequence	First bus cycle	Second bus cycle	Third bus cycle	Fourth bus cycle	Fifth bus cycle	Sixth bus cycle	Seventh bus cycle
	Addr.	Addr.	Addr.	Addr.	Addr.	Addr.	Addr.
	Data	Data	Data	Data	Data	Data	Data
Read	0xXX	—	—	—	—	—	—
	0xF0	—	—	—	—	—	—
Read/Reset	0x54XX	0xAAXX	0x54XX	RA	—	—	—
	0xAA	0x55	0xF0	RD	—	—	—
ID-Read	0x54XX	0xAAXX	0x54XX	IA	0xXX	—	—
	0xAA	0x55	0x90	0x00	ID	—	—
Automatic page programming	0x54XX	0xAAXX	0x54XX	PA	PA	PA	PA
	0xAA	0x55	0xA0	PD0	PD1	PD2	PD3
Automatic chip erase	0x54XX	0xAAXX	0x54XX	0x54XX	0xAAXX	0x54XX	—
	0xAA	0x55	0x80	0xAA	0x55	0x10	—
Auto Block erase	0x54XX	0xAAXX	0x54XX	0x54XX	0xAAXX	BA	—
	0xAA	0x55	0x80	0xAA	0x55	0x30	—
Protection bit programming	0x54XX	0xAAXX	0x54XX	0x54XX	0xAAXX	0x54XX	PBA
	0xAA	0x55	0x9A	0xAA	0x55	0x9A	0x9A
Protection bit erase	0x54XX	0xAAXX	0x54XX	0x54XX	0xAAXX	0x54XX	PBA
	0xAA	0x55	0x6A	0xAA	0x55	0x6A	0x6A

## Supplementary explanation

- RA: Read address
- RD: Read data
- IA: ID address
- ID: ID data
- PA: Program page address  
PD: Program data (32 bit data)  
After the fourth bus cycle, enter data in the order of the address for a page.
- BA: Block address
- PBA: Protection bit address

**(Note 1)** Always set "0" to the address bits [1:0] in the entire bus cycle. (Recommendable setting values to bits [7:2] are "0".)

**(Note 2)** Bus cycles are "bus write cycles" except for the second bus cycle of the Read command, the fourth bus cycle of the Read/reset command, and the fifth bus cycle of the ID-Read command. Bus write cycles are executed by 32-bit data transfer commands. The address [31:16] in each bus write cycle should be the target flash memory address [31:16] of the command sequence. Use "Addr." in the table for the address [15:0].

(7) Address bit configuration for bus write cycles

**Table 19-18 Address Bit Configuration for Bus Write Cycles**

Address	Addr [31:19]	Addr [18]	Addr [17]	Addr [16]	Addr [15]	Addr [14]	Addr [13:11]	Addr [10]	Addr [9]	Addr [8]	Addr [7:0]
---------	-----------------	--------------	--------------	--------------	--------------	--------------	-----------------	--------------	-------------	-------------	---------------

Normal commands	<b>Normal bus write cycle address configuration</b>										
	Flash area	"0" is recommended.				Command				Addr[1:0]="0" (fixed) Others:0 (recommended)	
ID -READ	<b>IA: ID address (Set the fourth bus write cycle address for ID-Read operation)</b>										
	Flash area	"0" is recommended.		ID address		Addr[1:0]="0" (fixed) , Others:0 (recommended)					

Block erase	<b>BA: Block address (Set the sixth bus write cycle address for block erase operation)</b>										
	Block selection (Table 19-19)					Addr[1:0]="0" (fixed) , Others:0 (recommended)					
Auto page programming	<b>PA: Program page address (Set the fourth bus write cycle address for page programming operation)</b>										
	Page selection								Addr[1:0]="0" (fixed) Others:0 (recommended)		
Protection bit programming	<b>PBA: Protection bit address (Set the seventh bus erase cycle address for protection bit erasure)</b>										
	Flash area	Protection bit selection (Table 19-20)			Fixed to "0".			Protection bit selection (Table 19-20)		Addr[1:0]="0" (fixed) Others:0 (recommended)	
Protection bit erase	<b>PBA: Protection bit address (Set the seventh bus erase cycle address for protection bit erasure)</b>										
	Flash area	Protection bit selection (Table 19-21)		"0" is recommended.				Protection bit selection (Table 19-21)		Addr[1:0]="0" (fixed) Others:0 (recommended)	
Block erase	<b>BA: Block address (Set the sixth bus write cycle address for block erase operation)</b>										
	Block selection (Table 19-19)					Addr[1:0]="0" (fixed) , Others:0 (recommended)					

- (Note 1)** Table 19-17 "Flash Memory Access from the Internal CPU" can also be used.
- (Note 2)** Address setting can be performed according to the "Normal bus write cycle address configuration" from the first bus cycle.
- (Note 3)** "0" is recommended" can be changed as necessary.

Table 19-19 Block Address Table

Block	Address (User boot mode)	Address (Single boot mode)	Size (Kbyte)
4	0x0000_0000-0x0000_3FFF	0x3F80_0000-0x3F80_3FFF	16
5	0x0000_4000-0x0000_7FFF	0x3F80_4000-0x3F80_7FFF	16
3	0x0000_8000-0x0000_FFFF	0x3F80_8000-0x3F80_FFFF	32
2	0x0001_0000-0x0001_FFFF	0x3F81_0000-0x3F81_FFFF	64
1	0x0002_0000-0x0002_FFFF	0x3F82_0000-0x3F82_FFFF	64
0	0x0003_0000-0x0003_FFFF	0x3F83_8000-0x3F83_FFFF	64

As block address, specify any address in the block to be erased.

**(Note)** As for the addresses from the first to the fifth bus cycles, specify the upper 4 bit with the corresponding flash memory addresses of the blocks to be erased.

Table 19-20 Protection Bit Programming Address Table

Block	Protection bit	The seventh bus write cycle address						
		Address [18]	Address [17]	Address [16]	Address [15:11]	Address [10]	Address [9]	Address [8]
<b>[TMPM370FY]</b>								
Block0	BLPRO0	0	0	Fixed to "0".			0	0
Block1	BLPRO1	0	0				0	1
Block2	BLPRO2	0	0				1	0
Block3	BLPRO3	0	0				1	1
Block4	BLPRO4	0	1				0	0
Block5	BLPRO5	0	1				0	1

Table 19-21 Protection Bit Erase Address Table

Block	Protection bit	The seventh bus write cycle address [18:17]	
		Address [18]	Address [17]
Block0~3	BLPRO0~3	0	0
Block4~5	BLPRO4~5	0	1

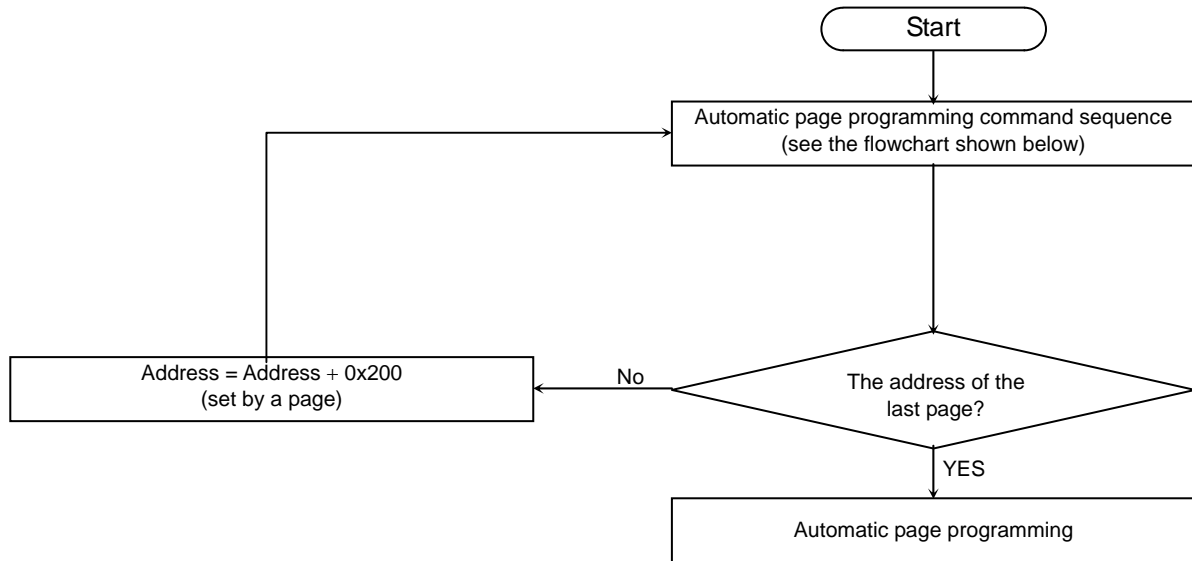
**(Note) The protection bit erase command cannot erase by individual block.**

Table 19-22 The ID-Read command's fourth bus write cycle ID address (IA) and the data to be read by the following 32-bit data transfer command (ID)

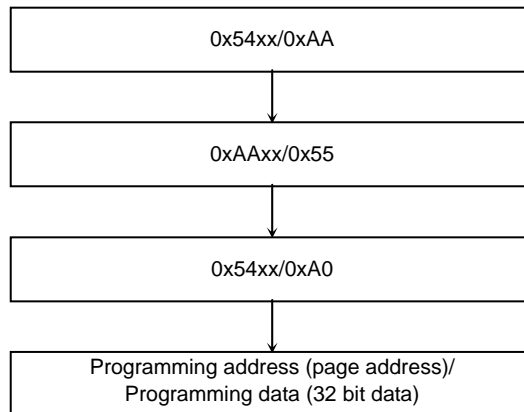
IA [15:14]	ID [7: 0]	Code
00b	0x98	Manufacturer code
01b	0x5A	Device code
10b	Reserved	---
11b	0x13	Macro code



(8) Flowchart



Automatic Page Programming Command Sequence (Address/ Command)



(Note) Command sequence is executed by 0x54xx or 0x55xx.

Fig. 19-10 Automatic Programming

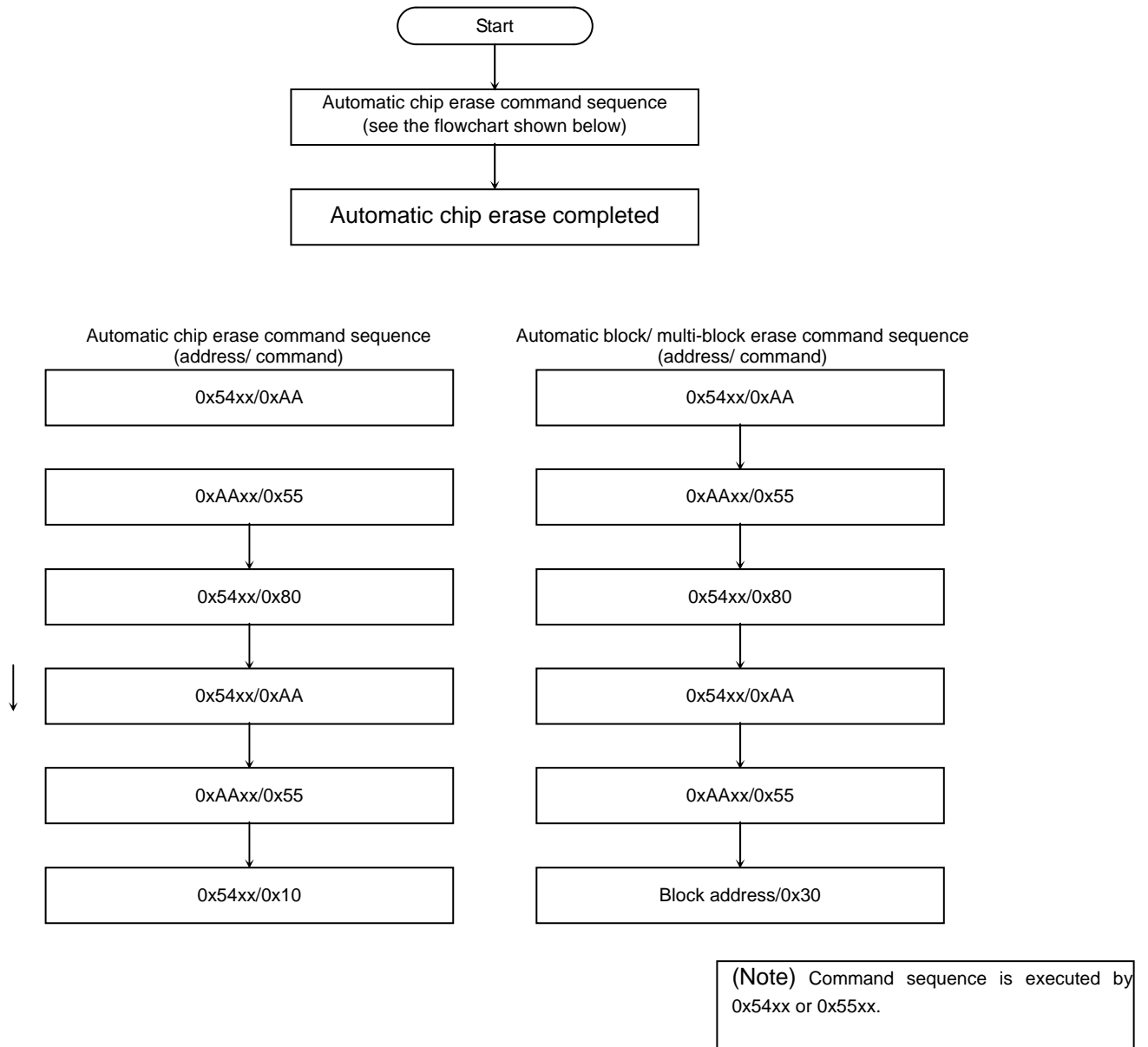


Fig. 19-11 Automatic Erase

## 20 Protect/security function

### 20.1 OutLine

The TPM370FY offers two kinds of ROM protect/ security functions. One is a write/ erase-protect function for the internal flash ROM data. The other is a security function that restricts internal flash ROM data readout and debugging.

### 20.2 Feature

#### 20.2.1 Internal Flash ROM write/erase protect

The write/ erase-protect function enables the internal flash to prohibit the writing and erasing operation for each block.

This function is available with a single chip mode, single boot mode and writer mode. To activate the function, write "1" to the corresponding bits to a block to protect. Writing "0" to the bits cancels the protection. The protection status of the bits can be monitored by the FLCS <BLPRO> bit.

### 20.2.2 Security function

The security function restricts flash ROM data readout and debugging.  
This function is available under the conditions shown below.

- 1) The SECBIT <SECBIT> bit is set to "1".
- 2) All the protection bits (the FLCS<BLPRO> bits) used to the write/erase-protect function are set to "1".

Note) The SECBIT <SECBIT> bit is set to "1" at a power-on reset right after power-on.

Table 20-1 shows details of the restrictions by the security function.

Table 20-1 Restrictions by the security function

Item	Details
1) ROM data readout	Data in the ROM area cannot be read out when writer mode is set. By executing readout, the company code 0x0098 is read. The ROM reading operation is available with a single chip mode and single boot mode.
2) Debug port	Communication of JTAG/SW and trace are prohibited.
3) Command for flash memory	Writing a command to the flash memory is prohibited. An attempt to erase the contents in the bits used for the write/erase-protection will erase all the contents of flash memory include protection bits.

## 20.3 Resistors

The flash control register shows the status of the flash memory operation and the protection of each block.

Table 20-2 Flash control register

FLCS  
0x41FF\_F020

	31	30	29	28	27	26	25	24
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
After reset	0							
function	"0" is read							
	23	22	21	20	19	18	17	16
bit Symbol	-	-	BLPRO5	BLPRO4	BLPRO3	BLPRO2	BLPRO1	BLPRO0
Read/Write	R		R	R	R	R	R	R
after Reset	0		(note2)	(note2)	(note2)	(note2)	(note2)	(note2)
function	Reading data is "0"		Block5 protect status 0: no protect status. 1: protect status.	Block4 protect status 0: no protect status. 1: protect status.	Block3 protect status 0: no protect status. 1: protect status.	Block2 protect status 0: no protect status. 1: protect status.	Block1 protect status 0: no protect status. 1: protect status.	Block0 protect status 0: no protect status. 1: protect status.
	15	14	13	12	11	10	9	8
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
after reset	0							
function	reading data is "0"							
	7	6	5	4	3	2	1	0
bit Symbol	-	-	-	-	-	-	-	RDY/BSY
Read/Write	R							R
after reset	0							1
Function	reading data is "0"							Ready/Busy (note1) 0: under auto operation 1: auto operation is finished

### Bit 0: Ready/Busy flag bit

The RDY/BSY output is provided as a means to monitor the status of automatic operation. . When the flash memory is in automatic operation, it outputs "0" to indicate that it is busy. When the automatic operation is terminated, it returns to the ready state and outputs "1" to accept the next command. If the automatic operation has failed, this bit maintains the "0" output. By applying a hardware reset, it returns to "1."

### Bit [21:16]: Protection status bits

Each of the protection bits (6 bits) represents the protection status of the corresponding block. When a bit is set to "1," it indicates that the block corresponding to the bit is protected. When the block is protected, data cannot be written to it.

**(Note 1)** This command must be issued in the ready state. Issuing the command in the busy state may disable both correct command transmission and further command input. To exit from the condition, execute system reset. System reset requires at least 0.5 microseconds regardless of the system clock frequency. In this condition, it takes approx. 2 ms to enable reading after reset.

**(Note 2)** The value varies depending on protection status.

Table 20-3 security bit register

SECBIT  
0x41FF\_F010

	31	30	29	28	27	26	25	24
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
after reset	0							
function	reading data is '0'							
	23	22	21	20	19	18	17	16
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
after reset	0							
function	reading data is '0'							
	15	14	13	12	11	10	9	8
bit Symbol	-	-	-	-	-	-	-	-
Read/Write	R							
after reset	0							
function	reading data is '0'							
	7	6	5	4	3	2	1	0
bit Symbol	-	-	-	-	-	-	-	SECBIT
Read/Write	R							R/W
after reset	0							1
function	reading data is '0'							security bit 0: disable 1: enable

**(Note)** This register is initialized only by power-on reset.

## 20.4 Writing and erasing

### 20.4.1 Protection bits

Writing and erasing protection bits are available with a single chip mode, single boot mode and writer mode.

Writing to the protection bits is done on block-by-block basis.

Erasing of the protection bits is done by two groups of the blocks: block 0 through 3 and block 4 through 5. When the settings for all the blocks are "1", erasing must be done after clearing the SECBIT <SECBIT> bit to "0". An attempt to erase protection bits when <SECBIT> bit is "1", it will erase all the contents of flash memory include protection bits. To write and erase the protection bits, command sequence is used.

See chapter 18 for details.

### 20.4.2 Security bit

The SECBIT <SECBIT> bit that activates security function is set to "1" at a power-on reset right after power-on. It can be Rewritten at single chip mode and single boot mode.by the following procedure.

- 1) Write the code 0xa74a9d23 to SECBIT register.
- 2) Write data within 16 clocks from the writing above.

Note) The above procedure is enabled only when using 32-bit data transfer command.

## 21 Special Function Registers

- [1] Port registers
- [2] 16-bit timer (TMRB)
- [3] Encoder input (ENC)
- [4] Serial interface (UART/SIO)
- [5] 12-bit A/D converter (A/DC)
- [6] OP-amp (AMP), Comparator (CMP)
- [7] Watchdog timer (WDT)
- [8] Clock generator (CG)
- [9] Oscillation frequency detector (OFD)
- [10] Power on reset (POR), Voltage detecting circuit (VLTD)
- [11] Vector engine (VE)
- [12] Programmable motor driver (PMD)
- [13] Flash
- [14] Reserved area

**(Note 1)** As for the internal I/O areas (0x4000\_0000~0x4007\_FFFF), reading the areas not described in this chapter yields undefined value. Writing these areas is ignored.

**(Note 2)** <R0> means 0(zero) is read. Writing data is disregarded.

**(Note3)** Access to the <Reserved> areas is prohibited.



## 21.1 Addresses

[1] Port [1/5]

&lt;PORT A&gt;

ADR	Register name
0x4000_0000	PA
0x4000_0001	<R0>
0x4000_0002	<R0>
0x4000_0003	<R0>
0x4000_0004	PACR
0x4000_0005	<R0>
0x4000_0006	<R0>
0x4000_0007	<R0>
0x4000_0008	PAFR1
0x4000_0009	<R0>
0x4000_000A	<R0>
0x4000_000B	<R0>
0x4000_000C	PAFR2
0x4000_000D	<R0>
0x4000_000E	<R0>
0x4000_000F	<R0>

ADR	Register name
0x4000_0010	
0x4000_0011	
0x4000_0012	
0x4000_0013	
0x4000_0014	
0x4000_0015	
0x4000_0016	
0x4000_0017	
0x4000_0018	
0x4000_0019	
0x4000_001A	
0x4000_001B	
0x4000_001C	
0x4000_001D	
0x4000_001E	
0x4000_001F	

ADR	Register name
0x4000_0020	
0x4000_0021	
0x4000_0022	
0x4000_0023	
0x4000_0024	
0x4000_0025	
0x4000_0026	
0x4000_0027	
0x4000_0028	PAOD
0x4000_0029	<R0>
0x4000_002A	<R0>
0x4000_002B	<R0>
0x4000_002C	PAPUP
0x4000_002D	<R0>
0x4000_002E	<R0>
0x4000_002F	<R0>

ADR	Register name
0x4000_0030	PAPDN
0x4000_0031	<R0>
0x4000_0032	<R0>
0x4000_0033	<R0>
0x4000_0034	
0x4000_0035	
0x4000_0036	
0x4000_0037	
0x4000_0038	PAIE
0x4000_0039	<R0>
0x4000_003A	<R0>
0x4000_003B	<R0>
0x4000_003C	
0x4000_003D	
0x4000_003E	
0x4000_003F	

&lt;PORT B&gt;

ADR	Register name
0x4000_0040	PB
0x4000_0041	<R0>
0x4000_0042	<R0>
0x4000_0043	<R0>
0x4000_0044	PBCR
0x4000_0045	<R0>
0x4000_0046	<R0>
0x4000_0047	<R0>
0x4000_0048	PBFR1
0x4000_0049	<R0>
0x4000_004A	<R0>
0x4000_004B	<R0>
0x4000_004C	
0x4000_004D	
0x4000_004E	
0x4000_004F	

ADR	Register name
0x4000_0050	
0x4000_0051	
0x4000_0052	
0x4000_0053	
0x4000_0054	
0x4000_0055	
0x4000_0056	
0x4000_0057	
0x4000_0058	
0x4000_0059	
0x4000_005A	
0x4000_005B	
0x4000_005C	
0x4000_005D	
0x4000_005E	
0x4000_005F	

ADR	Register name
0x4000_0060	
0x4000_0061	
0x4000_0062	
0x4000_0063	
0x4000_0064	
0x4000_0065	
0x4000_0066	
0x4000_0067	
0x4000_0068	
0x4000_0069	
0x4000_006A	
0x4000_006B	
0x4000_006C	PBPUP
0x4000_006D	<R0>
0x4000_006E	<R0>
0x4000_006F	<R0>

ADR	Register name
0x4000_0070	PBPDN
0x4000_0071	<R0>
0x4000_0072	<R0>
0x4000_0073	<R0>
0x4000_0074	
0x4000_0075	
0x4000_0076	
0x4000_0077	
0x4000_0078	PBIE
0x4000_0079	<R0>
0x4000_007A	<R0>
0x4000_007B	<R0>
0x4000_007C	
0x4000_007D	
0x4000_007E	
0x4000_007F	

&lt;PORT C&gt;

ADR	Register name
0x4000_0080	PC
0x4000_0081	<R0>
0x4000_0082	<R0>
0x4000_0083	<R0>
0x4000_0084	PCCR
0x4000_0085	<R0>
0x4000_0086	<R0>
0x4000_0087	<R0>
0x4000_0088	PCFR1
0x4000_0089	<R0>
0x4000_008A	<R0>
0x4000_008B	<R0>
0x4000_008C	
0x4000_008D	
0x4000_008E	
0x4000_008F	

ADR	Register name
0x4000_0090	
0x4000_0091	
0x4000_0092	
0x4000_0093	
0x4000_0094	
0x4000_0095	
0x4000_0096	
0x4000_0097	
0x4000_0098	
0x4000_0099	
0x4000_009A	
0x4000_009B	
0x4000_009C	
0x4000_009D	
0x4000_009E	
0x4000_009F	

ADR	Register name
0x4000_00A0	
0x4000_00A1	
0x4000_00A2	
0x4000_00A3	
0x4000_00A4	
0x4000_00A5	
0x4000_00A6	
0x4000_00A7	
0x4000_00A8	PCOD
0x4000_00A9	<R0>
0x4000_00AA	<R0>
0x4000_00AB	<R0>
0x4000_00AC	PCPUP
0x4000_00AD	<R0>
0x4000_00AE	<R0>
0x4000_00AF	<R0>

ADR	Register name
0x4000_00B0	PCPDN
0x4000_00B1	<R0>
0x4000_00B2	<R0>
0x4000_00B3	<R0>
0x4000_00B4	
0x4000_00B5	
0x4000_00B6	
0x4000_00B7	
0x4000_00B8	PCIE
0x4000_00B9	<R0>
0x4000_00BA	<R0>
0x4000_00BB	<R0>
0x4000_00BC	
0x4000_00BD	
0x4000_00BE	
0x4000_00BF	

## [1] Port [2/5]

## &lt;PORT D&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_00C0	PD	0x4000_00D0		0x4000_00E0		0x4000_00F0	PDPDN
0x4000_00C1	<R0>	0x4000_00D1		0x4000_00E1		0x4000_00F1	<R0>
0x4000_00C2	<R0>	0x4000_00D2		0x4000_00E2		0x4000_00F2	<R0>
0x4000_00C3	<R0>	0x4000_00D3		0x4000_00E3		0x4000_00F3	<R0>
0x4000_00C4	PDCR	0x4000_00D4		0x4000_00E4		0x4000_00F4	
0x4000_00C5	<R0>	0x4000_00D5		0x4000_00E5		0x4000_00F5	
0x4000_00C6	<R0>	0x4000_00D6		0x4000_00E6		0x4000_00F6	
0x4000_00C7	<R0>	0x4000_00D7		0x4000_00E7		0x4000_00F7	
0x4000_00C8	PDFR1	0x4000_00D8		0x4000_00E8	PDOD	0x4000_00F8	PDIE
0x4000_00C9	<R0>	0x4000_00D9		0x4000_00E9	<R0>	0x4000_00F9	<R0>
0x4000_00CA	<R0>	0x4000_00DA		0x4000_00EA	<R0>	0x4000_00FA	<R0>
0x4000_00CB	<R0>	0x4000_00DB		0x4000_00EB	<R0>	0x4000_00FB	<R0>
0x4000_00CC	PDFR2	0x4000_00DC		0x4000_00EC	PDPUP	0x4000_00FC	
0x4000_00CD	<R0>	0x4000_00DD		0x4000_00ED	<R0>	0x4000_00FD	
0x4000_00CE	<R0>	0x4000_00DE		0x4000_00EE	<R0>	0x4000_00FE	
0x4000_00CF	<R0>	0x4000_00DF		0x4000_00EF	<R0>	0x4000_00FF	

## &lt;PORT E&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0100	PE	0x4000_0110		0x4000_0120		0x4000_0130	PEPDN
0x4000_0101	<R0>	0x4000_0111		0x4000_0121		0x4000_0131	<R0>
0x4000_0102	<R0>	0x4000_0112		0x4000_0122		0x4000_0132	<R0>
0x4000_0103	<R0>	0x4000_0113		0x4000_0123		0x4000_0133	<R0>
0x4000_0104	PECR	0x4000_0114		0x4000_0124		0x4000_0134	
0x4000_0105	<R0>	0x4000_0115		0x4000_0125		0x4000_0135	
0x4000_0106	<R0>	0x4000_0116		0x4000_0126		0x4000_0136	
0x4000_0107	<R0>	0x4000_0117		0x4000_0127		0x4000_0137	
0x4000_0108	PEFR1	0x4000_0118		0x4000_0128	PEOD	0x4000_0138	PEIE
0x4000_0109	<R0>	0x4000_0119		0x4000_0129	<R0>	0x4000_0139	<R0>
0x4000_010A	<R0>	0x4000_011A		0x4000_012A	<R0>	0x4000_013A	<R0>
0x4000_010B	<R0>	0x4000_011B		0x4000_012B	<R0>	0x4000_013B	<R0>
0x4000_010C	PEFR2	0x4000_011C		0x4000_012C	PEPUP	0x4000_013C	
0x4000_010D	<R0>	0x4000_011D		0x4000_012D	<R0>	0x4000_013D	
0x4000_010E	<R0>	0x4000_011E		0x4000_012E	<R0>	0x4000_013E	
0x4000_010F	<R0>	0x4000_011F		0x4000_012F	<R0>	0x4000_013F	

## &lt;PORT F&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0140	PF	0x4000_0150	PFFR3	0x4000_0160		0x4000_0170	PFPDN
0x4000_0141	<R0>	0x4000_0151	<R0>	0x4000_0161		0x4000_0171	<R0>
0x4000_0142	<R0>	0x4000_0152	<R0>	0x4000_0162		0x4000_0172	<R0>
0x4000_0143	<R0>	0x4000_0153	<R0>	0x4000_0163		0x4000_0173	<R0>
0x4000_0144	PFCR	0x4000_0154		0x4000_0164		0x4000_0174	
0x4000_0145	<R0>	0x4000_0155		0x4000_0165		0x4000_0175	
0x4000_0146	<R0>	0x4000_0156		0x4000_0166		0x4000_0176	
0x4000_0147	<R0>	0x4000_0157		0x4000_0167		0x4000_0177	
0x4000_0148	PFFR1	0x4000_0158		0x4000_0168	PFOD	0x4000_0178	PFIE
0x4000_0149	<R0>	0x4000_0159		0x4000_0169	<R0>	0x4000_0179	<R0>
0x4000_014A	<R0>	0x4000_015A		0x4000_016A	<R0>	0x4000_017A	<R0>
0x4000_014B	<R0>	0x4000_015B		0x4000_016B	<R0>	0x4000_017B	<R0>
0x4000_014C	PFFR2	0x4000_015C		0x4000_016C	PFPUP	0x4000_017C	
0x4000_014D	<R0>	0x4000_015D		0x4000_016D	<R0>	0x4000_017D	
0x4000_014E	<R0>	0x4000_015E		0x4000_016E	<R0>	0x4000_017E	
0x4000_014F	<R0>	0x4000_015F		0x4000_016F	<R0>	0x4000_017F	

## [1] Port [3/5]

## &lt;PORT G&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0180	PG	0x4000_0190		0x4000_01A0		0x4000_01B0	PGPDN
0x4000_0181	<R0>	0x4000_0191		0x4000_01A1		0x4000_01B1	<R0>
0x4000_0182	<R0>	0x4000_0192		0x4000_01A2		0x4000_01B2	<R0>
0x4000_0183	<R0>	0x4000_0193		0x4000_01A3		0x4000_01B3	<R0>
0x4000_0184	PGCR	0x4000_0194		0x4000_01A4		0x4000_01B4	
0x4000_0185	<R0>	0x4000_0195		0x4000_01A5		0x4000_01B5	
0x4000_0186	<R0>	0x4000_0196		0x4000_01A6		0x4000_01B6	
0x4000_0187	<R0>	0x4000_0197		0x4000_01A7		0x4000_01B7	
0x4000_0188	PGFR1	0x4000_0198		0x4000_01A8	PGOD	0x4000_01B8	PGIE
0x4000_0189	<R0>	0x4000_0199		0x4000_01A9	<R0>	0x4000_01B9	<R0>
0x4000_018A	<R0>	0x4000_019A		0x4000_01AA	<R0>	0x4000_01BA	<R0>
0x4000_018B	<R0>	0x4000_019B		0x4000_01AB	<R0>	0x4000_01BB	<R0>
0x4000_018C		0x4000_019C		0x4000_01AC	PGPUP	0x4000_01BC	
0x4000_018D		0x4000_019D		0x4000_01AD	<R0>	0x4000_01BD	
0x4000_018E		0x4000_019E		0x4000_01AE	<R0>	0x4000_01BE	
0x4000_018F		0x4000_019F		0x4000_01AF	<R0>	0x4000_01BF	

## &lt;PORT H&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_01C0	PH	0x4000_01D0		0x4000_01E0		0x4000_01F0	PHPDN
0x4000_01C1	<R0>	0x4000_01D1		0x4000_01E1		0x4000_01F1	<R0>
0x4000_01C2	<R0>	0x4000_01D2		0x4000_01E2		0x4000_01F2	<R0>
0x4000_01C3	<R0>	0x4000_01D3		0x4000_01E3		0x4000_01F3	<R0>
0x4000_01C4	PHCR	0x4000_01D4		0x4000_01E4		0x4000_01F4	
0x4000_01C5	<R0>	0x4000_01D5		0x4000_01E5		0x4000_01F5	
0x4000_01C6	<R0>	0x4000_01D6		0x4000_01E6		0x4000_01F6	
0x4000_01C7	<R0>	0x4000_01D7		0x4000_01E7		0x4000_01F7	
0x4000_01C8	PHFR1	0x4000_01D8		0x4000_01E8	PHOD	0x4000_01F8	PHIE
0x4000_01C9	<R0>	0x4000_01D9		0x4000_01E9	<R0>	0x4000_01F9	<R0>
0x4000_01CA	<R0>	0x4000_01DA		0x4000_01EA	<R0>	0x4000_01FA	<R0>
0x4000_01CB	<R0>	0x4000_01DB		0x4000_01EB	<R0>	0x4000_01FB	<R0>
0x4000_01CC		0x4000_01DC		0x4000_01EC	PHPUP	0x4000_01FC	
0x4000_01CD		0x4000_01DD		0x4000_01ED	<R0>	0x4000_01FD	
0x4000_01CE		0x4000_01DE		0x4000_01EE	<R0>	0x4000_01FE	
0x4000_01CF		0x4000_01DF		0x4000_01EF	<R0>	0x4000_01FF	

## &lt;PORT I&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0200	PI	0x4000_0210		0x4000_0220		0x4000_0230	PIPDN
0x4000_0201	<R0>	0x4000_0211		0x4000_0221		0x4000_0231	<R0>
0x4000_0202	<R0>	0x4000_0212		0x4000_0222		0x4000_0232	<R0>
0x4000_0203	<R0>	0x4000_0213		0x4000_0223		0x4000_0233	<R0>
0x4000_0204	PICR	0x4000_0214		0x4000_0224		0x4000_0234	
0x4000_0205	<R0>	0x4000_0215		0x4000_0225		0x4000_0235	
0x4000_0206	<R0>	0x4000_0216		0x4000_0226		0x4000_0236	
0x4000_0207	<R0>	0x4000_0217		0x4000_0227		0x4000_0237	
0x4000_0208		0x4000_0218		0x4000_0228	PIOD	0x4000_0238	PIIE
0x4000_0209		0x4000_0219		0x4000_0229	<R0>	0x4000_0239	<R0>
0x4000_020A		0x4000_021A		0x4000_022A	<R0>	0x4000_023A	<R0>
0x4000_020B		0x4000_021B		0x4000_022B	<R0>	0x4000_023B	<R0>
0x4000_020C		0x4000_021C		0x4000_022C	PIPUP	0x4000_023C	
0x4000_020D		0x4000_021D		0x4000_022D	<R0>	0x4000_023D	
0x4000_020E		0x4000_021E		0x4000_022E	<R0>	0x4000_023E	
0x4000_020F		0x4000_021F		0x4000_022F	<R0>	0x4000_023F	

## [1] Port [4/5]

## &lt;PORT J&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0240	PJ	0x4000_0250		0x4000_0260		0x4000_0270	PJPDN
0x4000_0241	<R0>	0x4000_0251		0x4000_0261		0x4000_0271	<R0>
0x4000_0242	<R0>	0x4000_0252		0x4000_0262		0x4000_0272	<R0>
0x4000_0243	<R0>	0x4000_0253		0x4000_0263		0x4000_0273	<R0>
0x4000_0244	PJCR	0x4000_0254		0x4000_0264		0x4000_0274	
0x4000_0245	<R0>	0x4000_0255		0x4000_0265		0x4000_0275	
0x4000_0246	<R0>	0x4000_0256		0x4000_0266		0x4000_0276	
0x4000_0247	<R0>	0x4000_0257		0x4000_0267		0x4000_0277	
0x4000_0248	PJFR1	0x4000_0258		0x4000_0268	PJOD	0x4000_0278	PJIE
0x4000_0249	<R0>	0x4000_0259		0x4000_0269	<R0>	0x4000_0279	<R0>
0x4000_024A	<R0>	0x4000_025A		0x4000_026A	<R0>	0x4000_027A	<R0>
0x4000_024B	<R0>	0x4000_025B		0x4000_026B	<R0>	0x4000_027B	<R0>
0x4000_024C		0x4000_025C		0x4000_026C	PJPUP	0x4000_027C	
0x4000_024D		0x4000_025D		0x4000_026D	<R0>	0x4000_027D	
0x4000_024E		0x4000_025E		0x4000_026E	<R0>	0x4000_027E	
0x4000_024F		0x4000_025F		0x4000_026F	<R0>	0x4000_027F	

## &lt;PORT K&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_0280	PK	0x4000_0290		0x4000_02A0		0x4000_02B0	PKPDN
0x4000_0281	<R0>	0x4000_0291		0x4000_02A1		0x4000_02B1	<R0>
0x4000_0282	<R0>	0x4000_0292		0x4000_02A2		0x4000_02B2	<R0>
0x4000_0283	<R0>	0x4000_0293		0x4000_02A3		0x4000_02B3	<R0>
0x4000_0284	PKCR	0x4000_0294		0x4000_02A4		0x4000_02B4	
0x4000_0285	<R0>	0x4000_0295		0x4000_02A5		0x4000_02B5	
0x4000_0286	<R0>	0x4000_0296		0x4000_02A6		0x4000_02B6	
0x4000_0287	<R0>	0x4000_0297		0x4000_02A7		0x4000_02B7	
0x4000_0288	PKFR1	0x4000_0298		0x4000_02A8	PKOD	0x4000_02B8	PKIE
0x4000_0289	<R0>	0x4000_0299		0x4000_02A9	<R0>	0x4000_02B9	<R0>
0x4000_028A	<R0>	0x4000_029A		0x4000_02AA	<R0>	0x4000_02BA	<R0>
0x4000_028B	<R0>	0x4000_029B		0x4000_02AB	<R0>	0x4000_02BB	<R0>
0x4000_028C		0x4000_029C		0x4000_02AC	PKPUP	0x4000_02BC	
0x4000_028D		0x4000_029D		0x4000_02AD	<R0>	0x4000_02BD	
0x4000_028E		0x4000_029E		0x4000_02AE	<R0>	0x4000_02BE	
0x4000_028F		0x4000_029F		0x4000_02AF	<R0>	0x4000_02BF	

## &lt;PORT L&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4000_02C0	PL	0x4000_02D0		0x4000_02E0		0x4000_02F0	
0x4000_02C1	<R0>	0x4000_02D1		0x4000_02E1		0x4000_02F1	
0x4000_02C2	<R0>	0x4000_02D2		0x4000_02E2		0x4000_02F2	
0x4000_02C3	<R0>	0x4000_02D3		0x4000_02E3		0x4000_02F3	
0x4000_02C4		0x4000_02D4		0x4000_02E4		0x4000_02F4	
0x4000_02C5		0x4000_02D5		0x4000_02E5		0x4000_02F5	
0x4000_02C6		0x4000_02D6		0x4000_02E6		0x4000_02F6	
0x4000_02C7		0x4000_02D7		0x4000_02E7		0x4000_02F7	
0x4000_02C8	PLFR1	0x4000_02D8		0x4000_02E8		0x4000_02F8	PLIE
0x4000_02C9	<R0>	0x4000_02D9		0x4000_02E9		0x4000_02F9	<R0>
0x4000_02CA	<R0>	0x4000_02DA		0x4000_02EA		0x4000_02FA	<R0>
0x4000_02CB	<R0>	0x4000_02DB		0x4000_02EB		0x4000_02FB	<R0>
0x4000_02CC		0x4000_02DC		0x4000_02EC		0x4000_02FC	
0x4000_02CD		0x4000_02DD		0x4000_02ED		0x4000_02FD	
0x4000_02CE		0x4000_02DE		0x4000_02EE		0x4000_02FE	
0x4000_02CF		0x4000_02DF		0x4000_02EF		0x4000_02FF	

## [2] 16-bit timer [1/3]

## &lt;TMRB0&gt;

ADR	Register name
0x4001_0000	TB0EN
0x4001_0001	<R0>
0x4001_0002	<R0>
0x4001_0003	<R0>
0x4001_0004	TB0RUN
0x4001_0005	<R0>
0x4001_0006	<R0>
0x4001_0007	<R0>
0x4001_0008	TB0CR
0x4001_0009	<R0>
0x4001_000A	<R0>
0x4001_000B	<R0>
0x4001_000C	TB0MOD
0x4001_000D	<R0>
0x4001_000E	<R0>
0x4001_000F	<R0>

ADR	Register name
0x4001_0010	TB0FFCR
0x4001_0011	<R0>
0x4001_0012	<R0>
0x4001_0013	<R0>
0x4001_0014	TB0ST
0x4001_0015	<R0>
0x4001_0016	<R0>
0x4001_0017	<R0>
0x4001_0018	TB0IM
0x4001_0019	<R0>
0x4001_001A	<R0>
0x4001_001B	<R0>
0x4001_001C	TB0UCL
0x4001_001D	TB0UCH
0x4001_001E	<R0>
0x4001_001F	<R0>

ADR	Register name
0x4001_0020	TB0RG0L
0x4001_0021	TB0RG0H
0x4001_0022	<R0>
0x4001_0023	<R0>
0x4001_0024	TB0RG1L
0x4001_0025	TB0RG1H
0x4001_0026	<R0>
0x4001_0027	<R0>
0x4001_0028	TB0CP0L
0x4001_0029	TB0CP0H
0x4001_002A	<R0>
0x4001_002B	<R0>
0x4001_002C	TB0CP1L
0x4001_002D	TB0CP1H
0x4001_002E	<R0>
0x4001_002F	<R0>

ADR	Register name
0x4001_0030	
0x4001_0031	
0x4001_0032	
0x4001_0033	
0x4001_0034	
0x4001_0035	
0x4001_0036	
0x4001_0037	
0x4001_0038	
0x4001_0039	
0x4001_003A	
0x4001_003B	
0x4001_003C	
0x4001_003D	"
0x4001_003E	
0x4001_003F	

## &lt;TMRB1&gt;

ADR	Register name
0x4001_0040	TB1EN
0x4001_0041	<R0>
0x4001_0042	<R0>
0x4001_0043	<R0>
0x4001_0044	TB1RUN
0x4001_0045	<R0>
0x4001_0046	<R0>
0x4001_0047	<R0>
0x4001_0048	TB1CR
0x4001_0049	<R0>
0x4001_004A	<R0>
0x4001_004B	<R0>
0x4001_004C	TB1MOD
0x4001_004D	<R0>
0x4001_004E	<R0>
0x4001_004F	<R0>

ADR	Register name
0x4001_0050	TB1FFCR
0x4001_0051	<R0>
0x4001_0052	<R0>
0x4001_0053	<R0>
0x4001_0054	TB1ST
0x4001_0055	<R0>
0x4001_0056	<R0>
0x4001_0057	<R0>
0x4001_0058	TB1IM
0x4001_0059	<R0>
0x4001_005A	<R0>
0x4001_005B	<R0>
0x4001_005C	TB1UCL
0x4001_005D	TB1UCH
0x4001_005E	<R0>
0x4001_005F	<R0>

ADR	Register name
0x4001_0060	TB1RG0L
0x4001_0061	TB1RG0H
0x4001_0062	<R0>
0x4001_0063	<R0>
0x4001_0064	TB1RG1L
0x4001_0065	TB1RG1H
0x4001_0066	<R0>
0x4001_0067	<R0>
0x4001_0068	TB1CP0L
0x4001_0069	TB1CP0H
0x4001_006A	<R0>
0x4001_006B	<R0>
0x4001_006C	TB1CP1L
0x4001_006D	TB1CP1H
0x4001_006E	<R0>
0x4001_006F	<R0>

ADR	Register name
0x4001_0070	
0x4001_0071	
0x4001_0072	
0x4001_0073	
0x4001_0074	
0x4001_0075	
0x4001_0076	
0x4001_0077	
0x4001_0078	
0x4001_0079	
0x4001_007A	
0x4001_007B	
0x4001_007C	
0x4001_007D	
0x4001_007E	
0x4001_007F	

## &lt;TMRB2&gt;

ADR	Register name
0x4001_0080	TB2EN
0x4001_0081	<R0>
0x4001_0082	<R0>
0x4001_0083	<R0>
0x4001_0084	TB2RUN
0x4001_0085	<R0>
0x4001_0086	<R0>
0x4001_0087	<R0>
0x4001_0088	TB2CR
0x4001_0089	<R0>
0x4001_008A	<R0>
0x4001_008B	<R0>
0x4001_008C	TB2MOD
0x4001_008D	<R0>
0x4001_008E	<R0>
0x4001_008F	<R0>

ADR	Register name
0x4001_0090	TB2FFCR
0x4001_0091	<R0>
0x4001_0092	<R0>
0x4001_0093	<R0>
0x4001_0094	TB2ST
0x4001_0095	<R0>
0x4001_0096	<R0>
0x4001_0097	<R0>
0x4001_0098	TB2IM
0x4001_0099	<R0>
0x4001_009A	<R0>
0x4001_009B	<R0>
0x4001_009C	TB2UCL
0x4001_009D	TB2UCH
0x4001_009E	<R0>
0x4001_009F	<R0>

ADR	Register name
0x4001_00A0	TB2RG0L
0x4001_00A1	TB2RG0H
0x4001_00A2	<R0>
0x4001_00A3	<R0>
0x4001_00A4	TB2RG1L
0x4001_00A5	TB2RG1H
0x4001_00A6	<R0>
0x4001_00A7	<R0>
0x4001_00A8	TB2CP0L
0x4001_00A9	TB2CP0H
0x4001_00AA	<R0>
0x4001_00AB	<R0>
0x4001_00AC	TB2CP1L
0x4001_00AD	TB2CP1H
0x4001_00AE	<R0>
0x4001_00AF	<R0>

ADR	Register name
0x4001_00B0	
0x4001_00B1	
0x4001_00B2	
0x4001_00B3	
0x4001_00B4	
0x4001_00B5	
0x4001_00B6	
0x4001_00B7	
0x4001_00B8	
0x4001_00B9	
0x4001_00BA	
0x4001_00BB	
0x4001_00BC	
0x4001_00BD	
0x4001_00BE	
0x4001_00BF	

## [2] 16-bit timer [2/3]

## &lt;TMRB3&gt;

ADR	Register name
0x4001_00C0	TB3EN
0x4001_00C1	<R0>
0x4001_00C2	<R0>
0x4001_00C3	<R0>
0x4001_00C4	TB3RUN
0x4001_00C5	<R0>
0x4001_00C6	<R0>
0x4001_00C7	<R0>
0x4001_00C8	TB3CR
0x4001_00C9	<R0>
0x4001_00CA	<R0>
0x4001_00CB	<R0>
0x4001_00CC	TB3MOD
0x4001_00CD	<R0>
0x4001_00CE	<R0>
0x4001_00CF	<R0>

ADR	Register name
0x4001_00D0	TB3FFCR
0x4001_00D1	<R0>
0x4001_00D2	<R0>
0x4001_00D3	<R0>
0x4001_00D4	TB3ST
0x4001_00D5	<R0>
0x4001_00D6	<R0>
0x4001_00D7	<R0>
0x4001_00D8	TB3IM
0x4001_00D9	<R0>
0x4001_00DA	<R0>
0x4001_00DB	<R0>
0x4001_00DC	TB3UCL
0x4001_00DD	TB3UCH
0x4001_00DE	<R0>
0x4001_00DF	<R0>

ADR	Register name
0x4001_00E0	TB3RG0L
0x4001_00E1	TB3RG0H
0x4001_00E2	<R0>
0x4001_00E3	<R0>
0x4001_00E4	TB3RG1L
0x4001_00E5	TB3RG1H
0x4001_00E6	<R0>
0x4001_00E7	<R0>
0x4001_00E8	TB3CP0L
0x4001_00E9	TB3CP0H
0x4001_00EA	<R0>
0x4001_00EB	<R0>
0x4001_00EC	TB3CP1L
0x4001_00ED	TB3CP1H
0x4001_00EE	<R0>
0x4001_00EF	<R0>

ADR	Register name
0x4001_00F0	
0x4001_00F1	
0x4001_00F2	
0x4001_00F3	
0x4001_00F4	
0x4001_00F5	
0x4001_00F6	
0x4001_00F7	
0x4001_00F8	
0x4001_00F9	
0x4001_00FA	
0x4001_00FB	
0x4001_00FC	
0x4001_00FD	"
0x4001_00FE	
0x4001_00FF	

## &lt;TMRB4&gt;

ADR	Register name
0x4001_0100	TB4EN
0x4001_0101	<R0>
0x4001_0102	<R0>
0x4001_0103	<R0>
0x4001_0104	TB4RUN
0x4001_0105	<R0>
0x4001_0106	<R0>
0x4001_0107	<R0>
0x4001_0108	TB4CR
0x4001_0109	<R0>
0x4001_010A	<R0>
0x4001_010B	<R0>
0x4001_010C	TB4MOD
0x4001_010D	<R0>
0x4001_010E	<R0>
0x4001_010F	<R0>

ADR	Register name
0x4001_0110	TB4FFCR
0x4001_0111	<R0>
0x4001_0112	<R0>
0x4001_0113	<R0>
0x4001_0114	TB4ST
0x4001_0115	<R0>
0x4001_0116	<R0>
0x4001_0117	<R0>
0x4001_0118	TB4IM
0x4001_0119	<R0>
0x4001_011A	<R0>
0x4001_011B	<R0>
0x4001_011C	TB4UCL
0x4001_011D	TB4UCH
0x4001_011E	<R0>
0x4001_011F	<R0>

ADR	Register name
0x4001_0120	TB4RG0L
0x4001_0121	TB4RG0H
0x4001_0122	<R0>
0x4001_0123	<R0>
0x4001_0124	TB4RG1L
0x4001_0125	TB4RG1H
0x4001_0126	<R0>
0x4001_0127	<R0>
0x4001_0128	TB4CP0L
0x4001_0129	TB4CP0H
0x4001_012A	<R0>
0x4001_012B	<R0>
0x4001_012C	TB4CP1L
0x4001_012D	TB4CP1H
0x4001_012E	<R0>
0x4001_012F	<R0>

ADR	Register name
0x4001_0130	
0x4001_0131	
0x4001_0132	
0x4001_0133	
0x4001_0134	
0x4001_0135	
0x4001_0136	
0x4001_0137	
0x4001_0138	
0x4001_0139	
0x4001_013A	
0x4001_013B	
0x4001_013C	
0x4001_013D	"
0x4001_013E	
0x4001_013F	

## &lt;TMRB5&gt;

ADR	Register name
0x4001_0140	TB5EN
0x4001_0141	<R0>
0x4001_0142	<R0>
0x4001_0143	<R0>
0x4001_0144	TB5RUN
0x4001_0145	<R0>
0x4001_0146	<R0>
0x4001_0147	<R0>
0x4001_0148	TB5CR
0x4001_0149	<R0>
0x4001_014A	<R0>
0x4001_014B	<R0>
0x4001_014C	TB5MOD
0x4001_014D	<R0>
0x4001_014E	<R0>
0x4001_014F	<R0>

ADR	Register name
0x4001_0150	TB5FFCR
0x4001_0151	<R0>
0x4001_0152	<R0>
0x4001_0153	<R0>
0x4001_0154	TB5ST
0x4001_0155	<R0>
0x4001_0156	<R0>
0x4001_0157	<R0>
0x4001_0158	TB5IM
0x4001_0159	<R0>
0x4001_015A	<R0>
0x4001_015B	<R0>
0x4001_015C	TB5UCL
0x4001_015D	TB5UCL
0x4001_015E	<R0>
0x4001_015F	<R0>

ADR	Register name
0x4001_0160	TB5RG0L
0x4001_0161	TB5RG0H
0x4001_0162	<R0>
0x4001_0163	<R0>
0x4001_0164	TB5RG1L
0x4001_0165	TB5RG1H
0x4001_0166	<R0>
0x4001_0167	<R0>
0x4001_0168	TB5CP0L
0x4001_0169	TB5CP0H
0x4001_016A	<R0>
0x4001_016B	<R0>
0x4001_016C	TB5CP1L
0x4001_016D	TB5CP1H
0x4001_016E	<R0>
0x4001_016F	<R0>

ADR	Register name
0x4001_0170	
0x4001_0171	
0x4001_0172	
0x4001_0173	
0x4001_0174	
0x4001_0175	
0x4001_0176	
0x4001_0177	
0x4001_0178	
0x4001_0179	
0x4001_017A	
0x4001_017B	
0x4001_017C	
0x4001_017D	
0x4001_017E	
0x4001_017F	

## [2] 16-bit timer [3/3]

## &lt;TMRB6&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4001_0180	TB6EN	0x4001_0190	TB6FFCR	0x4001_01A0	TB6RG0L	0x4001_01B0	
0x4001_0181	<R0>	0x4001_0191	<R0>	0x4001_01A1	TB6RG0H	0x4001_01B1	
0x4001_0182	<R0>	0x4001_0192	<R0>	0x4001_01A2	<R0>	0x4001_01B2	
0x4001_0183	<R0>	0x4001_0193	<R0>	0x4001_01A3	<R0>	0x4001_01B3	
0x4001_0184	TB6RUN	0x4001_0194	TB6ST	0x4001_01A4	TB6RG1L	0x4001_01B4	
0x4001_0185	<R0>	0x4001_0195	<R0>	0x4001_01A5	TB6RG1H	0x4001_01B5	
0x4001_0186	<R0>	0x4001_0196	<R0>	0x4001_01A6	<R0>	0x4001_01B6	
0x4001_0187	<R0>	0x4001_0197	<R0>	0x4001_01A7	<R0>	0x4001_01B7	
0x4001_0188	TB6CR	0x4001_0198	TB6IM	0x4001_01A8	TB6CP0L	0x4001_01B8	
0x4001_0189	<R0>	0x4001_0199	<R0>	0x4001_01A9	TB6CP0H	0x4001_01B9	
0x4001_018A	<R0>	0x4001_019A	<R0>	0x4001_01AA	<R0>	0x4001_01BA	
0x4001_018B	<R0>	0x4001_019B	<R0>	0x4001_01AB	<R0>	0x4001_01BB	
0x4001_018C	TB6MOD	0x4001_019C	TB6UCL	0x4001_01AC	TB6CP1L	0x4001_01BC	
0x4001_018D	<R0>	0x4001_019D	TB6UCH	0x4001_01AD	TB6CP1H	0x4001_01BD	
0x4001_018E	<R0>	0x4001_019E	<R0>	0x4001_01AE	<R0>	0x4001_01BE	
0x4001_018F	<R0>	0x4001_019F	<R0>	0x4001_01AF	<R0>	0x4001_01BF	

## &lt;TMRB7&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4001_01C0	TB7EN	0x4001_01D0	TB7FFCR	0x4001_01E0	TB7RG0L	0x4001_01F0	
0x4001_01C1	<R0>	0x4001_01D1	<R0>	0x4001_01E1	TB7RG0H	0x4001_01F1	
0x4001_01C2	<R0>	0x4001_01D2	<R0>	0x4001_01E2	<R0>	0x4001_01F2	
0x4001_01C3	<R0>	0x4001_01D3	<R0>	0x4001_01E3	<R0>	0x4001_01F3	
0x4001_01C4	TB7RUN	0x4001_01D4	TB7ST	0x4001_01E4	TB7RG1L	0x4001_01F4	
0x4001_01C5	<R0>	0x4001_01D5	<R0>	0x4001_01E5	TB7RG1H	0x4001_01F5	
0x4001_01C6	<R0>	0x4001_01D6	<R0>	0x4001_01E6	<R0>	0x4001_01F6	
0x4001_01C7	<R0>	0x4001_01D7	<R0>	0x4001_01E7	<R0>	0x4001_01F7	
0x4001_01C8	TB7CR	0x4001_01D8	TB7IM	0x4001_01E8	TB7CP0L	0x4001_01F8	
0x4001_01C9	<R0>	0x4001_01D9	<R0>	0x4001_01E9	TB7CP0H	0x4001_01F9	
0x4001_01CA	<R0>	0x4001_01DA	<R0>	0x4001_01EA	<R0>	0x4001_01FA	
0x4001_01CB	<R0>	0x4001_01DB	<R0>	0x4001_01EB	<R0>	0x4001_01FB	
0x4001_01CC	TB7MOD	0x4001_01DC	TB7UCL	0x4001_01EC	TB7CP1L	0x4001_01FC	
0x4001_01CD	<R0>	0x4001_01DD	TB7UCH	0x4001_01ED	TB7CP1H	0x4001_01FD	"
0x4001_01CE	<R0>	0x4001_01DE	<R0>	0x4001_01EE	<R0>	0x4001_01FE	
0x4001_01CF	<R0>	0x4001_01DF	<R0>	0x4001_01EF	<R0>	0x4001_01FF	

## [3] Encoder input (ENC)

## &lt;ENC0&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4001_0400	EN0TNCRLL	0x4001_0410		0x4001_0420		0x4001_0430	
0x4001_0401	EN0TNCRLH	0x4001_0411		0x4001_0421		0x4001_0431	
0x4001_0402	EN0TNCRHL	0x4001_0412		0x4001_0422		0x4001_0432	
0x4001_0403	<R0>	0x4001_0413		0x4001_0423		0x4001_0433	
0x4001_0404	EN0RELOADL	0x4001_0414		0x4001_0424		0x4001_0434	
0x4001_0405	EN0RELOADH	0x4001_0415		0x4001_0425		0x4001_0435	
0x4001_0406	<R0>	0x4001_0416		0x4001_0426		0x4001_0436	
0x4001_0407	<R0>	0x4001_0417		0x4001_0427		0x4001_0437	
0x4001_0408	EN0INTLL	0x4001_0418		0x4001_0428		0x4001_0438	
0x4001_0409	EN0INTLH	0x4001_0419		0x4001_0429		0x4001_0439	
0x4001_040A	EN0INTHL	0x4001_041A		0x4001_042A		0x4001_043A	
0x4001_040B	<R0>	0x4001_041B		0x4001_042B		0x4001_043B	
0x4001_040C	EN0CNTLL	0x4001_041C		0x4001_042C		0x4001_043C	
0x4001_040D	EN0CNTLH	0x4001_041D		0x4001_042D		0x4001_043D	
0x4001_040E	EN0CNTHL	0x4001_041E		0x4001_042E		0x4001_043E	
0x4001_040F	<R0>	0x4001_041F		0x4001_042F		0x4001_043F	

## &lt;ENC1&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4001_0500	EN1TNCRLL	0x4001_0510		0x4001_0520		0x4001_0530	
0x4001_0501	EN1TNCRLH	0x4001_0511		0x4001_0521		0x4001_0531	
0x4001_0502	EN1TNCRHL	0x4001_0512		0x4001_0522		0x4001_0532	
0x4001_0503	<R0>	0x4001_0513		0x4001_0523		0x4001_0533	
0x4001_0504	EN1RELOADL	0x4001_0514		0x4001_0524		0x4001_0534	
0x4001_0505	EN1RELOADH	0x4001_0515		0x4001_0525		0x4001_0535	
0x4001_0506	<R0>	0x4001_0516		0x4001_0526		0x4001_0536	
0x4001_0507	<R0>	0x4001_0517		0x4001_0527		0x4001_0537	
0x4001_0508	EN1INTLL	0x4001_0518		0x4001_0528		0x4001_0538	
0x4001_0509	EN1INTLH	0x4001_0519		0x4001_0529		0x4001_0539	
0x4001_050A	EN1INTHL	0x4001_051A		0x4001_052A		0x4001_053A	
0x4001_050B	<R0>	0x4001_051B		0x4001_052B		0x4001_053B	
0x4001_050C	EN1CNTLL	0x4001_051C		0x4001_052C		0x4001_053C	
0x4001_050D	EN1CNTLH	0x4001_051D		0x4001_052D		0x4001_053D	
0x4001_050E	EN1CNTHL	0x4001_051E		0x4001_052E		0x4001_053E	
0x4001_050F	<R0>	0x4001_051F		0x4001_052F		0x4001_053F	



## [4] Serial interface (UART/SIO) [1/2]

## &lt;SIO0&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4002_0080	SC0EN	0x4002_0090	SC0BRCCR	0x4002_00A0	SC0RFC	0x4002_00B0	SC0FCNF
0x4002_0081	<R0>	0x4002_0091	<R0>	0x4002_00A1	<R0>	0x4002_00B1	<R0>
0x4002_0082	<R0>	0x4002_0092	<R0>	0x4002_00A2	<R0>	0x4002_00B2	<R0>
0x4002_0083	<R0>	0x4002_0093	<R0>	0x4002_00A3	<R0>	0x4002_00B3	<R0>
0x4002_0084	SC0BUF	0x4002_0094	SC0BRADD	0x4002_00A4	SC0TFC	0x4002_00B4	
0x4002_0085	<R0>	0x4002_0095	<R0>	0x4002_00A5	<R0>	0x4002_00B5	
0x4002_0086	<R0>	0x4002_0096	<R0>	0x4002_00A6	<R0>	0x4002_00B6	
0x4002_0087	<R0>	0x4002_0097	<R0>	0x4002_00A7	<R0>	0x4002_00B7	
0x4002_0088	SC0CR	0x4002_0098	SC0MOD1	0x4002_00A8	SC0RST	0x4002_00B8	
0x4002_0089	<R0>	0x4002_0099	<R0>	0x4002_00A9	<R0>	0x4002_00B9	
0x4002_008A	<R0>	0x4002_009A	<R0>	0x4002_00AA	<R0>	0x4002_00BA	
0x4002_008B	<R0>	0x4002_009B	<R0>	0x4002_00AB	<R0>	0x4002_00BB	
0x4002_008C	SC0MOD0	0x4002_009C	SC0MOD2	0x4002_00AC	SC0TST	0x4002_00BC	
0x4002_008D	<R0>	0x4002_009D	<R0>	0x4002_00AD	<R0>	0x4002_00BD	
0x4002_008E	<R0>	0x4002_009E	<R0>	0x4002_00AE	<R0>	0x4002_00BE	
0x4002_008F	<R0>	0x4002_009F	<R0>	0x4002_00AF	<R0>	0x4002_00BF	

## &lt;SIO1&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4002_00C0	SC1EN	0x4002_00D0	SC1BRCCR	0x4002_00E0	SC1RFC	0x4002_00F0	SC1FCNF
0x4002_00C1	<R0>	0x4002_00D1	<R0>	0x4002_00E1	<R0>	0x4002_00F1	<R0>
0x4002_00C2	<R0>	0x4002_00D2	<R0>	0x4002_00E2	<R0>	0x4002_00F2	<R0>
0x4002_00C3	<R0>	0x4002_00D3	<R0>	0x4002_00E3	<R0>	0x4002_00F3	<R0>
0x4002_00C4	SC1BUF	0x4002_00D4	SC1BRADD	0x4002_00E4	SC1TFC	0x4002_00F4	
0x4002_00C5	<R0>	0x4002_00D5	<R0>	0x4002_00E5	<R0>	0x4002_00F5	
0x4002_00C6	<R0>	0x4002_00D6	<R0>	0x4002_00E6	<R0>	0x4002_00F6	
0x4002_00C7	<R0>	0x4002_00D7	<R0>	0x4002_00E7	<R0>	0x4002_00F7	
0x4002_00C8	SC1CR	0x4002_00D8	SC1MOD1	0x4002_00E8	SC1RST	0x4002_00F8	
0x4002_00C9	<R0>	0x4002_00D9	<R0>	0x4002_00E9	<R0>	0x4002_00F9	
0x4002_00CA	<R0>	0x4002_00DA	<R0>	0x4002_00EA	<R0>	0x4002_00FA	
0x4002_00CB	<R0>	0x4002_00DB	<R0>	0x4002_00EB	<R0>	0x4002_00FB	
0x4002_00CC	SC1MOD0	0x4002_00DC	SC1MOD2	0x4002_00EC	SC1TST	0x4002_00FC	
0x4002_00CD	<R0>	0x4002_00DD	<R0>	0x4002_00ED	<R0>	0x4002_00FD	
0x4002_00CE	<R0>	0x4002_00DE	<R0>	0x4002_00EE	<R0>	0x4002_00FE	
0x4002_00CF	<R0>	0x4002_00DF	<R0>	0x4002_00EF	<R0>	0x4002_00FF	

## &lt;SIO2&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4002_0100	SC2EN	0x4002_0110	SC2BRCCR	0x4002_0120	SC2RFC	0x4002_0130	SC2FCNF
0x4002_0101	<R0>	0x4002_0111	<R0>	0x4002_0121	<R0>	0x4002_0131	<R0>
0x4002_0102	<R0>	0x4002_0112	<R0>	0x4002_0122	<R0>	0x4002_0132	<R0>
0x4002_0103	<R0>	0x4002_0113	<R0>	0x4002_0123	<R0>	0x4002_0133	<R0>
0x4002_0104	SC2BUF	0x4002_0114	SC2BRADD	0x4002_0124	SC2TFC	0x4002_0134	
0x4002_0105	<R0>	0x4002_0115	<R0>	0x4002_0125	<R0>	0x4002_0135	
0x4002_0106	<R0>	0x4002_0116	<R0>	0x4002_0126	<R0>	0x4002_0136	
0x4002_0107	<R0>	0x4002_0117	<R0>	0x4002_0127	<R0>	0x4002_0137	
0x4002_0108	SC2CR	0x4002_0118	SC2MOD1	0x4002_0128	SC2RST	0x4002_0138	
0x4002_0109	<R0>	0x4002_0119	<R0>	0x4002_0129	<R0>	0x4002_0139	
0x4002_010A	<R0>	0x4002_011A	<R0>	0x4002_012A	<R0>	0x4002_013A	
0x4002_010B	<R0>	0x4002_011B	<R0>	0x4002_012B	<R0>	0x4002_013B	
0x4002_010C	SC2MOD0	0x4002_011C	SC2MOD2	0x4002_012C	SC2TST	0x4002_013C	
0x4002_010D	<R0>	0x4002_011D	<R0>	0x4002_012D	<R0>	0x4002_013D	
0x4002_010E	<R0>	0x4002_011E	<R0>	0x4002_012E	<R0>	0x4002_013E	
0x4002_010F	<R0>	0x4002_011F	<R0>	0x4002_012F	<R0>	0x4002_013F	

## [4] Serial interface (UART/SIO) [2/2]

&lt;SIO3&gt;

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4002_0140	SC3EN	0x4002_0150	SC3BRCR	0x4002_0160	SC3RFC	0x4002_0170	SC3FCNF
0x4002_0141	<R0>	0x4002_0151	<R0>	0x4002_0161	<R0>	0x4002_0171	<R0>
0x4002_0142	<R0>	0x4002_0152	<R0>	0x4002_0162	<R0>	0x4002_0172	<R0>
0x4002_0143	<R0>	0x4002_0153	<R0>	0x4002_0163	<R0>	0x4002_0173	<R0>
0x4002_0144	SC3BUF	0x4002_0154	SC3BRADD	0x4002_0164	SC3TFC	0x4002_0174	
0x4002_0145	<R0>	0x4002_0155	<R0>	0x4002_0165	<R0>	0x4002_0175	
0x4002_0146	<R0>	0x4002_0156	<R0>	0x4002_0166	<R0>	0x4002_0176	
0x4002_0147	<R0>	0x4002_0157	<R0>	0x4002_0167	<R0>	0x4002_0177	
0x4002_0148	SC3CR	0x4002_0158	SC3MOD1	0x4002_0168	SC3RST	0x4002_0178	
0x4002_0149	<R0>	0x4002_0159	<R0>	0x4002_0169	<R0>	0x4002_0179	
0x4002_014A	<R0>	0x4002_015A	<R0>	0x4002_016A	<R0>	0x4002_017A	
0x4002_014B	<R0>	0x4002_015B	<R0>	0x4002_016B	<R0>	0x4002_017B	
0x4002_014C	SC3MOD0	0x4002_015C	SC3MOD2	0x4002_016C	SC3TST	0x4002_017C	
0x4002_014D	<R0>	0x4002_015D	<R0>	0x4002_016D	<R0>	0x4002_017D	
0x4002_014E	<R0>	0x4002_015E	<R0>	0x4002_016E	<R0>	0x4002_017E	
0x4002_014F	<R0>	0x4002_015F	<R0>	0x4002_016F	<R0>	0x4002_017F	

## [5] 12-bit A/D converter (A/DC) [1/4]

&lt;ADC A&gt;

ADR	Register name
0x4003_0000	ADACLK
0x4003_0001	"
0x4003_0002	"
0x4003_0003	"
0x4003_0004	ADAMOD0
0x4003_0005	"
0x4003_0006	"
0x4003_0007	"
0x4003_0008	ADAMOD1
0x4003_0009	"
0x4003_000A	"
0x4003_000B	"
0x4003_000C	ADAMOD2
0x4003_000D	"
0x4003_000E	"
0x4003_000F	"

ADR	Register name
0x4003_0010	ADACMPCR0L
0x4003_0011	ADACMPCR0H
0x4003_0012	"
0x4003_0013	"
0x4003_0014	ADACMPCR1L
0x4003_0015	ADACMPCR1H
0x4003_0016	"
0x4003_0017	"
0x4003_0018	ADACMP0L
0x4003_0019	ADACMP0H
0x4003_001A	"
0x4003_001B	"
0x4003_001C	ADACMP1L
0x4003_001D	ADACMP1H
0x4003_001E	"
0x4003_001F	"

ADR	Register name
0x4003_0020	ADAREG0L
0x4003_0021	ADAREG0H
0x4003_0022	"
0x4003_0023	"
0x4003_0024	ADAREG1L
0x4003_0025	ADAREG1H
0x4003_0026	"
0x4003_0027	"
0x4003_0028	ADAREG2L
0x4003_0029	ADAREG2H
0x4003_002A	"
0x4003_002B	"
0x4003_002C	ADAREG3L
0x4003_002D	ADAREG3H
0x4003_002E	"
0x4003_002F	"

ADR	Register name
0x4003_0030	ADAREG4L
0x4003_0031	ADAREG4H
0x4003_0032	"
0x4003_0033	"
0x4003_0034	ADAREG5L
0x4003_0035	ADAREG5H
0x4003_0036	"
0x4003_0037	"
0x4003_0038	ADAREG6L
0x4003_0039	ADAREG6H
0x4003_003A	"
0x4003_003B	"
0x4003_003C	ADAREG7L
0x4003_003D	ADAREG7H
0x4003_003E	"
0x4003_003F	"

ADR	Register name
0x4003_0040	ADAREG8L
0x4003_0041	ADAREG8H
0x4003_0042	"
0x4003_0043	"
0x4003_0044	ADAREG9L
0x4003_0045	ADAREG9H
0x4003_0046	"
0x4003_0047	"
0x4003_0048	ADAREG10L
0x4003_0049	ADAREG10H
0x4003_004A	"
0x4003_004B	"
0x4003_004C	ADAREG11L
0x4003_004D	ADAREG11H
0x4003_004E	"
0x4003_004F	"

ADR	Register name
0x4003_0050	ADAPSEL0
0x4003_0051	"
0x4003_0052	"
0x4003_0053	"
0x4003_0054	ADAPSEL1
0x4003_0055	"
0x4003_0056	"
0x4003_0057	"
0x4003_0058	ADAPSEL2
0x4003_0059	"
0x4003_005A	"
0x4003_005B	"
0x4003_005C	ADAPSEL3
0x4003_005D	"
0x4003_005E	"
0x4003_005F	"

ADR	Register name
0x4003_0060	ADAPSEL4
0x4003_0061	"
0x4003_0062	"
0x4003_0063	"
0x4003_0064	ADAPSEL5
0x4003_0065	"
0x4003_0066	"
0x4003_0067	"
0x4003_0068	ADAPSEL6
0x4003_0069	"
0x4003_006A	"
0x4003_006B	"
0x4003_006C	ADAPSEL7
0x4003_006D	"
0x4003_006E	"
0x4003_006F	"

ADR	Register name
0x4003_0070	ADAPSEL8
0x4003_0071	"
0x4003_0072	"
0x4003_0073	"
0x4003_0074	ADAPSEL9
0x4003_0075	"
0x4003_0076	"
0x4003_0077	"
0x4003_0078	ADAPSEL10
0x4003_0079	"
0x4003_007A	"
0x4003_007B	"
0x4003_007C	ADAPSEL11
0x4003_007D	"
0x4003_007E	"
0x4003_007F	"

ADR	Register name
0x4003_0080	ADAPINTS0
0x4003_0081	"
0x4003_0082	"
0x4003_0083	"
0x4003_0084	ADAPINTS1
0x4003_0085	"
0x4003_0086	"
0x4003_0087	"
0x4003_0088	ADAPINTS2
0x4003_0089	"
0x4003_008A	"
0x4003_008B	"
0x4003_008C	ADAPINTS3
0x4003_008D	"
0x4003_008E	"
0x4003_008F	"

ADR	Register name
0x4003_0090	ADAPINTS4
0x4003_0091	"
0x4003_0092	"
0x4003_0093	"
0x4003_0094	ADAPINTS5
0x4003_0095	"
0x4003_0096	"
0x4003_0097	"
0x4003_0098	ADAPSET00
0x4003_0099	ADAPSET01
0x4003_009A	ADAPSET02
0x4003_009B	ADAPSET03
0x4003_009C	ADAPSET10
0x4003_009D	ADAPSET11
0x4003_009E	ADAPSET12
0x4003_009F	ADAPSET13

ADR	Register name
0x4003_00A0	ADAPSET20
0x4003_00A1	ADAPSET21
0x4003_00A2	ADAPSET22
0x4003_00A3	ADAPSET23
0x4003_00A4	ADAPSET30
0x4003_00A5	ADAPSET31
0x4003_00A6	ADAPSET32
0x4003_00A7	ADAPSET33
0x4003_00A8	ADAPSET40
0x4003_00A9	ADAPSET41
0x4003_00AA	ADAPSET42
0x4003_00AB	ADAPSET43
0x4003_00AC	ADAPSET50
0x4003_00AD	ADAPSET51
0x4003_00AE	ADAPSET52
0x4003_00AF	ADAPSET53

ADR	Register name
0x4003_00B0	ADATSET0
0x4003_00B1	ADATSET1
0x4003_00B2	ADATSET2
0x4003_00B3	ADATSET3
0x4003_00B4	ADATSET4
0x4003_00B5	ADATSET5
0x4003_00B6	ADATSET6
0x4003_00B7	ADATSET7
0x4003_00B8	ADATSET8
0x4003_00B9	ADATSET9
0x4003_00BA	ADATSET10
0x4003_00BB	ADATSET11
0x4003_00BC	ADASSET0
0x4003_00BD	ADASSET1
0x4003_00BE	ADASSET2
0x4003_00BF	ADASSET3

## [5] 12-bit A/D converter (A/DC) [2/4]

ADR	Register name
0x4003_00C0	ADASSET4
0x4003_00C1	ADASSET5
0x4003_00C2	ADASSET6
0x4003_00C3	ADASSET7
0x4003_00C4	ADASSET8
0x4003_00C5	ADASSET9
0x4003_00C6	ADASSET10
0x4003_00C7	ADASSET11
0x4003_00C8	ADAASET0
0x4003_00C9	ADAASET1
0x4003_00CA	ADAASET2
0x4003_00CB	ADAASET3
0x4003_00CC	ADAASET4
0x4003_00CD	ADAASET5
0x4003_00CE	ADAASET6
0x4003_00CF	ADAASET7

ADR	Register name
0x4003_00D0	ADAASET8
0x4003_00D1	ADAASET9
0x4003_00D2	ADAASET10
0x4003_00D3	ADAASET11
0x4003_00D4	Reserved
0x4003_00D5	Reserved
0x4003_00D6	Reserved
0x4003_00D7	Reserved
0x4003_00D8	
0x4003_00D9	
0x4003_00DA	
0x4003_00DB	
0x4003_00DC	
0x4003_00DD	
0x4003_00DE	
0x4003_00DF	

ADR	Register name
0x4003_00E0	
0x4003_00E1	
0x4003_00E2	
0x4003_00E3	
0x4003_00E4	
0x4003_00E5	
0x4003_00E6	
0x4003_00E7	
0x4003_00E8	
0x4003_00E9	
0x4003_00EA	
0x4003_00EB	
0x4003_00EC	
0x4003_00ED	
0x4003_00EE	
0x4003_00EF	

ADR	Register name
0x4003_00F0	
0x4003_00F1	
0x4003_00F2	
0x4003_00F3	
0x4003_00F4	
0x4003_00F5	
0x4003_00F6	
0x4003_00F7	
0x4003_00F8	
0x4003_00F9	
0x4003_00FA	
0x4003_00FB	
0x4003_00FC	
0x4003_00FD	
0x4003_00FE	
0x4003_00FF	

## [5]12-bit A/D converter (A/D) [3/4]

## &lt;ADC B&gt;

ADR	Register name
0x4003_0200	ADBCLK
0x4003_0201	"
0x4003_0202	"
0x4003_0203	"
0x4003_0204	ADBMOD0
0x4003_0205	"
0x4003_0206	"
0x4003_0207	"
0x4003_0208	ADBMOD1
0x4003_0209	"
0x4003_020A	"
0x4003_020B	"
0x4003_020C	ADBMOD2
0x4003_020D	"
0x4003_020E	"
0x4003_020F	"

ADR	Register name
0x4003_0210	ADBCMPCR0L
0x4003_0211	ADBCMPCR0H
0x4003_0212	"
0x4003_0213	"
0x4003_0214	ADBCMPCR1L
0x4003_0215	ADBCMPCR1H
0x4003_0216	"
0x4003_0217	"
0x4003_0218	ADBCMP0L
0x4003_0219	ADBCMP0H
0x4003_021A	"
0x4003_021B	"
0x4003_021C	ADBCMP1L
0x4003_021D	ADBCMP1H
0x4003_021E	"
0x4003_021F	"

ADR	Register name
0x4003_0220	ADBREG0L
0x4003_0221	ADBREG0H
0x4003_0222	"
0x4003_0223	"
0x4003_0224	ADBREG1L
0x4003_0225	ADBREG1H
0x4003_0226	"
0x4003_0227	"
0x4003_0228	ADBREG2L
0x4003_0229	ADBREG2H
0x4003_022A	"
0x4003_022B	"
0x4003_022C	ADBREG3L
0x4003_022D	ADBREG3H
0x4003_022E	"
0x4003_022F	"

ADR	Register name
0x4003_0230	ADBREG4L
0x4003_0231	ADBREG4H
0x4003_0232	"
0x4003_0233	"
0x4003_0234	ADBREG5L
0x4003_0235	ADBREG5H
0x4003_0236	"
0x4003_0237	"
0x4003_0238	ADBREG6L
0x4003_0239	ADBREG6H
0x4003_023A	"
0x4003_023B	"
0x4003_023C	ADBREG7L
0x4003_023D	ADBREG7H
0x4003_023E	"
0x4003_023F	"

ADR	Register name
0x4003_0240	ADBREG8L
0x4003_0241	ADBREG8H
0x4003_0242	"
0x4003_0243	"
0x4003_0244	ADBREG9L
0x4003_0245	ADBREG9H
0x4003_0246	"
0x4003_0247	"
0x4003_0248	ADBREG10L
0x4003_0249	ADBREG10H
0x4003_024A	"
0x4003_024B	"
0x4003_024C	ADBREG11L
0x4003_024D	ADBREG11H
0x4003_024E	"
0x4003_024F	"

ADR	Register name
0x4003_0250	ADBPSEL0
0x4003_0251	"
0x4003_0252	"
0x4003_0253	"
0x4003_0254	ADBPSEL1
0x4003_0255	"
0x4003_0256	"
0x4003_0257	"
0x4003_0258	ADBPSEL2
0x4003_0259	"
0x4003_025A	"
0x4003_025B	"
0x4003_025C	ADBPSEL3
0x4003_025D	"
0x4003_025E	"
0x4003_025F	"

ADR	Register name
0x4003_0260	ADBPSEL4
0x4003_0261	"
0x4003_0262	"
0x4003_0263	"
0x4003_0264	ADBPSEL5
0x4003_0265	"
0x4003_0266	"
0x4003_0267	"
0x4003_0268	ADBPSEL6
0x4003_0269	"
0x4003_026A	"
0x4003_026B	"
0x4003_026C	ADBPSEL7
0x4003_026D	"
0x4003_026E	"
0x4003_026F	"

ADR	Register name
0x4003_0270	ADBPSEL8
0x4003_0271	"
0x4003_0272	"
0x4003_0273	"
0x4003_0274	ADBPSEL9
0x4003_0275	"
0x4003_0276	"
0x4003_0277	"
0x4003_0278	ADBPSEL10
0x4003_0279	"
0x4003_027A	"
0x4003_027B	"
0x4003_027C	ADBPSEL11
0x4003_027D	"
0x4003_027E	"
0x4003_027F	"

ADR	Register name
0x4003_0280	ADBPINTS0
0x4003_0281	"
0x4003_0282	"
0x4003_0283	"
0x4003_0284	ADBPINTS1
0x4003_0285	"
0x4003_0286	"
0x4003_0287	"
0x4003_0288	ADBPINTS2
0x4003_0289	"
0x4003_028A	"
0x4003_028B	"
0x4003_028C	ADBPINTS3
0x4003_028D	"
0x4003_028E	"
0x4003_028F	"

ADR	Register name
0x4003_0290	ADBPSET4
0x4003_0291	"
0x4003_0292	"
0x4003_0293	"
0x4003_0294	ADBPINTS5
0x4003_0295	"
0x4003_0296	"
0x4003_0297	"
0x4003_0298	ADBPSET00
0x4003_0299	ADBPSET01
0x4003_029A	ADBPSET02
0x4003_029B	ADBPSET03
0x4003_029C	ADBPSET10
0x4003_029D	ADBPSET11
0x4003_029E	ADBPSET12
0x4003_029F	ADBPSET13

ADR	Register name
0x4003_02A0	ADBPSET20
0x4003_02A1	ADBPSET21
0x4003_02A2	ADBPSET22
0x4003_02A3	ADBPSET23
0x4003_02A4	ADBPSET30
0x4003_02A5	ADBPSET31
0x4003_02A6	ADBPSET32
0x4003_02A7	ADBPSET33
0x4003_02A8	ADBPSET40
0x4003_02A9	ADBPSET41
0x4003_02AA	ADBPSET42
0x4003_02AB	ADBPSET43
0x4003_02AC	ADBPSET50
0x4003_02AD	ADBPSET51
0x4003_02AE	ADBPSET52
0x4003_02AF	ADBPSET53

ADR	Register name
0x4003_02B0	ADBTSET0
0x4003_02B1	ADBTSET1
0x4003_02B2	ADBTSET2
0x4003_02B3	ADBTSET3
0x4003_02B4	ADBTSET4
0x4003_02B5	ADBTSET5
0x4003_02B6	ADBTSET6
0x4003_02B7	ADBTSET7
0x4003_02B8	ADBTSET8
0x4003_02B9	ADBTSET9
0x4003_02BA	ADBTSET10
0x4003_02BB	ADBTSET11
0x4003_02BC	ADBSSET0
0x4003_02BD	ADBSSET1
0x4003_02BE	ADBSSET2
0x4003_02BF	ADBSSET3

## [5] 12-bit A/D converter (A/DC) [4/4]

ADR	Register name
0x4003_02C0	ADBSSET4
0x4003_02C1	ADBSSET5
0x4003_02C2	ADBSSET6
0x4003_02C3	ADBSSET7
0x4003_02C4	ADBSSET8
0x4003_02C5	ADBSSET9
0x4003_02C6	ADBSSET10
0x4003_02C7	ADBSSET11
0x4003_02C8	ADBASET0
0x4003_02C9	ADBASET1
0x4003_02CA	ADBASET2
0x4003_02CB	ADBASET3
0x4003_02CC	ADBASET4
0x4003_02CD	ADBASET5
0x4003_02CE	ADBASET6
0x4003_02CF	ADBASET7

ADR	Register name
0x4003_02D0	ADBASET8
0x4003_02D1	ADBASET9
0x4003_02D2	ADBASET10
0x4003_02D3	ADBASET11
0x4003_02D4	Reserved
0x4003_02D5	Reserved
0x4003_02D6	Reserved
0x4003_02D7	Reserved
0x4003_02D8	
0x4003_02D9	
0x4003_02DA	
0x4003_02DB	
0x4003_02DC	
0x4003_02DD	
0x4003_02DE	
0x4003_02DF	

ADR	Register name
0x4003_02E0	
0x4003_02E1	
0x4003_02E2	
0x4003_02E3	
0x4003_02E4	
0x4003_02E5	
0x4003_02E6	
0x4003_02E7	
0x4003_02E8	
0x4003_02E9	
0x4003_02EA	
0x4003_02EB	
0x4003_02EC	
0x4003_02ED	
0x4003_02EE	
0x4003_02EF	

ADR	Register name
0x4003_02F0	
0x4003_02F1	
0x4003_02F2	
0x4003_02F3	
0x4003_02F4	
0x4003_02F5	
0x4003_02F6	
0x4003_02F7	
0x4003_02F8	
0x4003_02F9	
0x4003_02FA	
0x4003_02FB	
0x4003_02FC	
0x4003_02FD	
0x4003_02FE	
0x4003_02FF	

## [6] OP-amp / Comparator (AMP/CMP)

ADR	Register name
0x4003_0400	AMPCTLA
0x4003_0401	
0x4003_0402	
0x4003_0403	
0x4003_0404	Reserved
0x4003_0405	
0x4003_0406	
0x4003_0407	
0x4003_0408	AMPCTLB
0x4003_0409	
0x4003_040A	
0x4003_040B	
0x4003_040C	Reserved
0x4003_040D	
0x4003_040E	
0x4003_040F	

ADR	Register name
0x4003_0410	AMPCTLC
0x4003_0411	
0x4003_0412	
0x4003_0413	
0x4003_0414	Reserved
0x4003_0415	
0x4003_0416	
0x4003_0417	
0x4003_0418	AMPCTLD
0x4003_0419	
0x4003_041A	
0x4003_041B	
0x4003_041C	Reserved
0x4003_041D	
0x4003_041E	
0x4003_041F	

ADR	Register name
0x4003_0420	CMPCTLA
0x4003_0421	
0x4003_0422	
0x4003_0423	
0x4003_0424	Reserved
0x4003_0425	
0x4003_0426	
0x4003_0427	
0x4003_0428	CMPCTLB
0x4003_0429	
0x4003_042A	
0x4003_042B	
0x4003_042C	Reserved
0x4003_042D	
0x4003_042E	
0x4003_042F	

ADR	Register name
0x4003_0430	CMPCTLC
0x4003_0431	
0x4003_0432	
0x4003_0433	
0x4003_0434	Reserved
0x4003_0435	
0x4003_0436	
0x4003_0437	
0x4003_0438	CMPCTLD
0x4003_0439	
0x4003_043A	
0x4003_043B	
0x4003_043C	Reserved
0x4003_043D	
0x4003_043E	
0x4003_043F	

## [7] Watchdog timer (WDT)

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4004_0000	WDMOD	0x4004_0010		0x4004_0020		0x4004_0030	
0x4004_0001	<R0>	0x4004_0011		0x4004_0021		0x4004_0031	
0x4004_0002	<R0>	0x4004_0012		0x4004_0022		0x4004_0032	
0x4004_0003	<R0>	0x4004_0013		0x4004_0023		0x4004_0033	
0x4004_0004	WDCR	0x4004_0014		0x4004_0024		0x4004_0034	
0x4004_0005	<R0>	0x4004_0015		0x4004_0025		0x4004_0035	
0x4004_0006	<R0>	0x4004_0016		0x4004_0026		0x4004_0036	
0x4004_0007	<R0>	0x4004_0017		0x4004_0027		0x4004_0037	
0x4004_0008		0x4004_0018		0x4004_0028		0x4004_0038	
0x4004_0009		0x4004_0019		0x4004_0029		0x4004_0039	
0x4004_000A		0x4004_001A		0x4004_002A		0x4004_003A	
0x4004_000B		0x4004_001B		0x4004_002B		0x4004_003B	
0x4004_000C		0x4004_001C		0x4004_002C		0x4004_003C	
0x4004_000D		0x4004_001D		0x4004_002D		0x4004_003D	
0x4004_000E		0x4004_001E		0x4004_002E		0x4004_003E	
0x4004_000F		0x4004_001F		0x4004_002F		0x4004_003F	

## [8] Clock generator (CG)

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4004_0200	SYSCR0	0x4004_0210	CKSEL	0x4004_0220	IMCGA0	0x4004_0230	
0x4004_0201	SYSCR1	0x4004_0211	<R0>	0x4004_0221	IMCGA1	0x4004_0231	
0x4004_0202	SYSCR2	0x4004_0212	<R0>	0x4004_0222	IMCGA2	0x4004_0232	
0x4004_0203	<R0>	0x4004_0213	<R0>	0x4004_0223	IMCGA3	0x4004_0233	
0x4004_0204	OSCCR0	0x4004_0214	ICRCG	0x4004_0224	IMCGB0	0x4004_0234	
0x4004_0205	OSCCR1	0x4004_0215	<R0>	0x4004_0225	IMCGB1	0x4004_0235	
0x4004_0206	OSCCR2	0x4004_0216	<R0>	0x4004_0226	IMCGB2	0x4004_0236	
0x4004_0207	OSCCR3	0x4004_0217	<R0>	0x4004_0227	IMCGB3	0x4004_0237	
0x4004_0208	STBYCR0	0x4004_0218	NMIFLG	0x4004_0228	IMCGC0	0x4004_0238	
0x4004_0209	STBYCR1	0x4004_0219	<R0>	0x4004_0229	IMCGC1	0x4004_0239	
0x4004_020A	STBYCR2	0x4004_021A	<R0>	0x4004_022A	IMCGC2	0x4004_023A	
0x4004_020B	<R0>	0x4004_021B	<R0>	0x4004_022B	IMCGC3	0x4004_023B	
0x4004_020C	PLLSELO	0x4004_021C	RSTFLG	0x4004_022C	IMCGD0	0x4004_023C	
0x4004_020D	PLLSEL1	0x4004_021D	<R0>	0x4004_022D	IMCGD1	0x4004_023D	
0x4004_020E	<R0>	0x4004_021E	<R0>	0x4004_022E	IMCGD2	0x4004_023E	
0x4004_020F	<R0>	0x4004_021F	<R0>	0x4004_022F	IMCGD3	0x4004_023F	

## [9] Oscillation frequency detector (OFD)

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4004_0800	CLKSCR1	0x4004_0810	CLKSMX_PLOFF	0x4004_0820		0x4004_0830	
0x4004_0801	<R0>	0x4004_0811	"	0x4004_0821		0x4004_0831	
0x4004_0802	<R0>	0x4004_0812	<R0>	0x4004_0822		0x4004_0832	
0x4004_0803	<R0>	0x4004_0813	<R0>	0x4004_0823		0x4004_0833	
0x4004_0804	CLKSCR2	0x4004_0814	CLKSMX_PLLON	0x4004_0824		0x4004_0834	
0x4004_0805	<R0>	0x4004_0815	"	0x4004_0825		0x4004_0835	
0x4004_0806	<R0>	0x4004_0816	<R0>	0x4004_0826		0x4004_0836	
0x4004_0807	<R0>	0x4004_0817	<R0>	0x4004_0827		0x4004_0837	
0x4004_0808	CLKSMIN_PLOFFL	0x4004_0818		0x4004_0828		0x4004_0838	
0x4004_0809	CLKSMIN_PLOFFH	0x4004_0819		0x4004_0829		0x4004_0839	
0x4004_080A	<R0>	0x4004_081A		0x4004_082A		0x4004_083A	
0x4004_080B	<R0>	0x4004_081B		0x4004_082B		0x4004_083B	
0x4004_080C	CLKSMIN_PLLONL	0x4004_081C		0x4004_082C		0x4004_083C	
0x4004_080D	CLKSMIN_PLLONH	0x4004_081D		0x4004_082D		0x4004_083D	
0x4004_080E	<R0>	0x4004_081E		0x4004_082E		0x4004_083E	
0x4004_080F	<R0>	0x4004_081F		0x4004_082F		0x4004_083F	

## [10] Power on reset (POR), Voltage detecting circuit (VLTD)

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4004_0900	VDCR	0x4004_0910		0x4004_0920		0x4004_0930	
0x4004_0901		0x4004_0911		0x4004_0921		0x4004_0931	
0x4004_0902		0x4004_0912		0x4004_0922		0x4004_0932	
0x4004_0903		0x4004_0913		0x4004_0923		0x4004_0933	
0x4004_0904	VDSR	0x4004_0914		0x4004_0924		0x4004_0934	
0x4004_0905		0x4004_0915		0x4004_0925		0x4004_0935	
0x4004_0906		0x4004_0916		0x4004_0926		0x4004_0936	
0x4004_0907		0x4004_0917		0x4004_0927		0x4004_0937	
0x4004_0908		0x4004_0918		0x4004_0928		0x4004_0938	
0x4004_0909		0x4004_0919		0x4004_0929		0x4004_0939	
0x4004_090A		0x4004_091A		0x4004_092A		0x4004_093A	
0x4004_090B		0x4004_091B		0x4004_092B		0x4004_093B	
0x4004_090C		0x4004_091C		0x4004_092C		0x4004_093C	
0x4004_090D		0x4004_091D		0x4004_092D		0x4004_093D	
0x4004_090E		0x4004_091E		0x4004_092E		0x4004_093E	
0x4004_090F		0x4004_091F		0x4004_092F		0x4004_093F	



## [11] Vector engine (VE) [1/3]

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0000	VEEN	0x4005_0010	REPTIME	0x4005_0020	ERRDET	0x4005_0030	TMPREG1
0x4005_0001	<R0>	0x4005_0011	<R0>	0x4005_0021	<R0>	0x4005_0031	"
0x4005_0002	<R0>	0x4005_0012	<R0>	0x4005_0022	<R0>	0x4005_0032	"
0x4005_0003	<R0>	0x4005_0013	<R0>	0x4005_0023	<R0>	0x4005_0033	"
0x4005_0004	CPURUNTRG	0x4005_0014	TRGMODE	0x4005_0024	SCHTASKRUN	0x4005_0034	TMPREG2
0x4005_0005	<R0>	0x4005_0015	<R0>	0x4005_0025	"	0x4005_0035	"
0x4005_0006	<R0>	0x4005_0016	<R0>	0x4005_0026	<R0>	0x4005_0036	"
0x4005_0007	<R0>	0x4005_0017	<R0>	0x4005_0027	<R0>	0x4005_0037	"
0x4005_0008	TASKAPP	0x4005_0018	ERRINTEN	0x4005_0028	Reserved	0x4005_0038	TMPREG3
0x4005_0009	<R0>	0x4005_0019	<R0>	0x4005_0029	Reserved	0x4005_0039	"
0x4005_000A	<R0>	0x4005_001A	<R0>	0x4005_002A	Reserved	0x4005_003A	"
0x4005_000B	<R0>	0x4005_001B	<R0>	0x4005_002B	Reserved	0x4005_003B	"
0x4005_000C	ACTSCH	0x4005_001C	COMPEND	0x4005_002C	TMPREG0	0x4005_003C	TMPREG4
0x4005_000D	<R0>	0x4005_001D	<R0>	0x4005_002D	"	0x4005_003D	"
0x4005_000E	<R0>	0x4005_001E	<R0>	0x4005_002E	"	0x4005_003E	"
0x4005_000F	<R0>	0x4005_001F	<R0>	0x4005_002F	"	0x4005_003F	"

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0040	TMPREG5	0x4005_0050	TPWM0	0x4005_0060	IQREF0	0x4005_0070	CIDKP0
0x4005_0041	"	0x4005_0051	"	0x4005_0061	"	0x4005_0071	"
0x4005_0042	"	0x4005_0052	<R0>	0x4005_0062	<R0>	0x4005_0072	<R0>
0x4005_0043	"	0x4005_0053	<R0>	0x4005_0063	<R0>	0x4005_0073	<R0>
0x4005_0044	MCTLF0	0x4005_0054	OMEGA0	0x4005_0064	VD0	0x4005_0074	CIQKI0
0x4005_0045	"	0x4005_0055	"	0x4005_0065	<R0>	0x4005_0075	"
0x4005_0046	<R0>	0x4005_0056	<R0>	0x4005_0066	<R0>	0x4005_0076	<R0>
0x4005_0047	<R0>	0x4005_0057	<R0>	0x4005_0067	<R0>	0x4005_0077	<R0>
0x4005_0048	MODE0	0x4005_0058	THETA0	0x4005_0068	VQ0	0x4005_0078	CIQKP0
0x4005_0049	<R0>	0x4005_0059	"	0x4005_0069	"	0x4005_0079	"
0x4005_004A	<R0>	0x4005_005A	<R0>	0x4005_006A	<R0>	0x4005_007A	<R0>
0x4005_004B	<R0>	0x4005_005B	<R0>	0x4005_006B	<R0>	0x4005_007B	<R0>
0x4005_004C	FMODE0	0x4005_005C	IDREF0	0x4005_006C	CIDKI0	0x4005_007C	VDIH0
0x4005_004D	"	0x4005_005D	"	0x4005_006D	"	0x4005_007D	"
0x4005_004E	<R0>	0x4005_005E	<R0>	0x4005_006E	<R0>	0x4005_007E	<R0>
0x4005_004F	<R0>	0x4005_005F	<R0>	0x4005_006F	<R0>	0x4005_007F	<R0>

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0080	VDILH0	0x4005_0090	MDPRD0	0x4005_00A0	COS0	0x4005_00B0	SECTOR0
0x4005_0081	"	0x4005_0091	"	0x4005_00A1	"	0x4005_00B1	<R0>
0x4005_0082	<R0>	0x4005_0092	<R0>	0x4005_00A2	<R0>	0x4005_00B2	<R0>
0x4005_0083	<R0>	0x4005_0093	<R0>	0x4005_00A3	<R0>	0x4005_00B3	<R0>
0x4005_0084	VQIH0	0x4005_0094	MINPLS0	0x4005_00A4	SIN0	0x4005_00B4	SECTORM0
0x4005_0085	"	0x4005_0095	"	0x4005_00A5	"	0x4005_00B5	<R0>
0x4005_0086	<R0>	0x4005_0096	<R0>	0x4005_00A6	<R0>	0x4005_00B6	<R0>
0x4005_0087	<R0>	0x4005_0097	<R0>	0x4005_00A7	<R0>	0x4005_00B7	<R0>
0x4005_0088	VQILH0	0x4005_0098	TRGCRC0	0x4005_00A8	COSM0	0x4005_00B8	IAO0
0x4005_0089	"	0x4005_0099	"	0x4005_00A9	"	0x4005_00B9	"
0x4005_008A	<R0>	0x4005_009A	<R0>	0x4005_00AA	<R0>	0x4005_00BA	<R0>
0x4005_008B	<R0>	0x4005_009B	<R0>	0x4005_00AB	<R0>	0x4005_00BB	<R0>
0x4005_008C	FPWMCHG0	0x4005_009C	Reserved	0x4005_00AC	SINM0	0x4005_00BC	IBO0
0x4005_008D	"	0x4005_009D	Reserved	0x4005_00AD	"	0x4005_00BD	"
0x4005_008E	<R0>	0x4005_009E	Reserved	0x4005_00AE	<R0>	0x4005_00BE	<R0>
0x4005_008F	<R0>	0x4005_009F	Reserved	0x4005_00AF	<R0>	0x4005_00BF	<R0>

## [11] Vector engine (VE) [2/3]

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_00C0	ICO0	0x4005_00D0	VDC0	0x4005_00E0	MODE1	0x4005_00F0	THETA1
0x4005_00C1	"	0x4005_00D1	"	0x4005_00E1	<R0>	0x4005_00F1	"
0x4005_00C2	<R0>	0x4005_00D2	<R0>	0x4005_00E2	<R0>	0x4005_00F2	<R0>
0x4005_00C3	<R0>	0x4005_00D3	<R0>	0x4005_00E3	<R0>	0x4005_00F3	<R0>
0x4005_00C4	IAADC0	0x4005_00D4	ID0	0x4005_00E4	FMODE1	0x4005_00F4	IDREF1
0x4005_00C5	"	0x4005_00D5	"	0x4005_00E5	"	0x4005_00F5	"
0x4005_00C6	<R0>	0x4005_00D6	"	0x4005_00E6	<R0>	0x4005_00F6	<R0>
0x4005_00C7	<R0>	0x4005_00D7	"	0x4005_00E7	<R0>	0x4005_00F7	<R0>
0x4005_00C8	IBADC0	0x4005_00D8	IQ0	0x4005_00E8	TPWM1	0x4005_00F8	IQREF1
0x4005_00C9	"	0x4005_00D9	"	0x4005_00E9	"	0x4005_00F9	"
0x4005_00CA	<R0>	0x4005_00DA	"	0x4005_00EA	<R0>	0x4005_00FA	<R0>
0x4005_00CB	<R0>	0x4005_00DB	"	0x4005_00EB	<R0>	0x4005_00FB	<R0>
0x4005_00CC	ICADC0	0x4005_00DC	MCTLF1	0x4005_00EC	OMEGA1	0x4005_00FC	VD1
0x4005_00CD	"	0x4005_00DD	<R0>	0x4005_00ED	"	0x4005_00FD	<R0>
0x4005_00CE	<R0>	0x4005_00DE	<R0>	0x4005_00EE	<R0>	0x4005_00FE	<R0>
0x4005_00CF	<R0>	0x4005_00DF	<R0>	0x4005_00EF	<R0>	0x4005_00FF	<R0>

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0100	VQ1	0x4005_0110	CIQKP1	0x4005_0120	VQILH1	0x4005_0130	TRGCRC1
0x4005_0101	<R0>	0x4005_0111	"	0x4005_0121	"	0x4005_0131	"
0x4005_0102	<R0>	0x4005_0112	<R0>	0x4005_0122	<R0>	0x4005_0132	<R0>
0x4005_0103	<R0>	0x4005_0113	<R0>	0x4005_0123	<R0>	0x4005_0133	<R0>
0x4005_0104	CID_KI1	0x4005_0114	VDIH1	0x4005_0124	FPWMCHG1	0x4005_0134	Reserved
0x4005_0105	"	0x4005_0115	"	0x4005_0125	"	0x4005_0135	Reserved
0x4005_0106	<R0>	0x4005_0116	<R0>	0x4005_0126	<R0>	0x4005_0136	Reserved
0x4005_0107	<R0>	0x4005_0117	<R0>	0x4005_0127	<R0>	0x4005_0137	Reserved
0x4005_0108	CID_KP1	0x4005_0118	VDILH1	0x4005_0128	MDPRD1	0x4005_0138	COS1
0x4005_0109	"	0x4005_0119	"	0x4005_0129	"	0x4005_0139	"
0x4005_010A	<R0>	0x4005_011A	<R0>	0x4005_012A	<R0>	0x4005_013A	<R0>
0x4005_010B	<R0>	0x4005_011B	<R0>	0x4005_012B	<R0>	0x4005_013B	<R0>
0x4005_010C	CIQ_KI1	0x4005_011C	VQIH1	0x4005_012C	MINPLS1	0x4005_013C	SIN1
0x4005_010D	"	0x4005_011D	"	0x4005_012D	"	0x4005_013D	"
0x4005_010E	<R0>	0x4005_011E	<R0>	0x4005_012E	<R0>	0x4005_013E	<R0>
0x4005_010F	<R0>	0x4005_011F	<R0>	0x4005_012F	<R0>	0x4005_013F	<R0>

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0140	COSM1	0x4005_0150	IAO1	0x4005_0160	IBADC1	0x4005_0170	IQ1
0x4005_0141	"	0x4005_0151	"	0x4005_0161	"	0x4005_0171	"
0x4005_0142	<R0>	0x4005_0152	<R0>	0x4005_0162	<R0>	0x4005_0172	"
0x4005_0143	<R0>	0x4005_0153	<R0>	0x4005_0163	<R0>	0x4005_0173	"
0x4005_0144	SINM1	0x4005_0154	IBO1	0x4005_0164	ICADC1	0x4005_0174	Reserved
0x4005_0145	"	0x4005_0155	"	0x4005_0165	"	0x4005_0175	Reserved
0x4005_0146	<R0>	0x4005_0156	<R0>	0x4005_0166	<R0>	0x4005_0176	Reserved
0x4005_0147	<R0>	0x4005_0157	<R0>	0x4005_0167	<R0>	0x4005_0177	Reserved
0x4005_0148	SECTOR1	0x4005_0158	ICO1	0x4005_0168	VDC1	0x4005_0178	TADC
0x4005_0149	<R0>	0x4005_0159	"	0x4005_0169	"	0x4005_0179	"
0x4005_014A	<R0>	0x4005_015A	<R0>	0x4005_016A	<R0>	0x4005_017A	<R0>
0x4005_014B	<R0>	0x4005_015B	<R0>	0x4005_016B	<R0>	0x4005_017B	<R0>
0x4005_014C	SECTORM1	0x4005_015C	IAADC1	0x4005_016C	ID1	0x4005_017C	VCMPU0
0x4005_014D	<R0>	0x4005_015D	"	0x4005_016D	"	0x4005_017D	"
0x4005_014E	<R0>	0x4005_015E	<R0>	0x4005_016E	"	0x4005_017E	<R0>
0x4005_014F	<R0>	0x4005_015F	<R0>	0x4005_016F	"	0x4005_017F	<R0>

## [11] Vector engine (VE) [3/3]

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0180	VCMPV0	0x4005_0190	VTRGCMP10	0x4005_01A0	VCMPV1	0x4005_01B0	VTRGCMP11
0x4005_0181	"	0x4005_0191	"	0x4005_01A1	"	0x4005_01B1	"
0x4005_0182	<R0>	0x4005_0192	<R0>	0x4005_01A2	<R0>	0x4005_01B2	<R0>
0x4005_0183	<R0>	0x4005_0193	<R0>	0x4005_01A3	<R0>	0x4005_01B3	<R0>
0x4005_0184	VCMPW0	0x4005_0194	VTRGSEL0	0x4005_01A4	VCMPW1	0x4005_01B4	VTRGSEL1
0x4005_0185	"	0x4005_0195	<R0>	0x4005_01A5	"	0x4005_01B5	<R0>
0x4005_0186	<R0>	0x4005_0196	<R0>	0x4005_01A6	<R0>	0x4005_01B6	<R0>
0x4005_0187	<R0>	0x4005_0197	<R0>	0x4005_01A7	<R0>	0x4005_01B7	<R0>
0x4005_0188	OUTCR0	0x4005_0198	EMGRS0	0x4005_01A8	OUTCR1	0x4005_01B8	EMGRS1
0x4005_0189	"	0x4005_0199	<R0>	0x4005_01A9	"	0x4005_01B9	<R0>
0x4005_018A	<R0>	0x4005_019A	<R0>	0x4005_01AA	<R0>	0x4005_01BA	<R0>
0x4005_018B	<R0>	0x4005_019B	<R0>	0x4005_01AB	<R0>	0x4005_01BB	<R0>
0x4005_018C	VTRGCMP00	0x4005_019C	VCMPU1	0x4005_01AC	VTRGCMP01	0x4005_01BC	Reserved
0x4005_018D	"	0x4005_019D	"	0x4005_01AD	"	0x4005_01BD	Reserved
0x4005_018E	<R0>	0x4005_019E	<R0>	0x4005_01AE	<R0>	0x4005_01BE	Reserved
0x4005_018F	<R0>	0x4005_019F	<R0>	0x4005_01AF	<R0>	0x4005_01BF	Reserved

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_01C0	Reserved	0x4005_01D0	Reserved	0x4005_01E0	Reserved	0x4005_01F0	Reserved
0x4005_01C1	Reserved	0x4005_01D1	Reserved	0x4005_01E1	Reserved	0x4005_01F1	Reserved
0x4005_01C2	Reserved	0x4005_01D2	Reserved	0x4005_01E2	Reserved	0x4005_01F2	Reserved
0x4005_01C3	Reserved	0x4005_01D3	Reserved	0x4005_01E3	Reserved	0x4005_01F3	Reserved
0x4005_01C4	Reserved	0x4005_01D4	Reserved	0x4005_01E4	Reserved	0x4005_01F4	Reserved
0x4005_01C5	Reserved	0x4005_01D5	Reserved	0x4005_01E5	Reserved	0x4005_01F5	Reserved
0x4005_01C6	Reserved	0x4005_01D6	Reserved	0x4005_01E6	Reserved	0x4005_01F6	Reserved
0x4005_01C7	Reserved	0x4005_01D7	Reserved	0x4005_01E7	Reserved	0x4005_01F7	Reserved
0x4005_01C8	Reserved	0x4005_01D8	Reserved	0x4005_01E8	Reserved	0x4005_01F8	Reserved
0x4005_01C9	Reserved	0x4005_01D9	Reserved	0x4005_01E9	Reserved	0x4005_01F9	Reserved
0x4005_01CA	Reserved	0x4005_01DA	Reserved	0x4005_01EA	Reserved	0x4005_01FA	Reserved
0x4005_01CB	Reserved	0x4005_01DB	Reserved	0x4005_01EB	Reserved	0x4005_01FB	Reserved
0x4005_01CC	Reserved	0x4005_01DC	Reserved	0x4005_01EC	Reserved	0x4005_01FC	Reserved
0x4005_01CD	Reserved	0x4005_01DD	Reserved	0x4005_01ED	Reserved	0x4005_01FD	Reserved
0x4005_01CE	Reserved	0x4005_01DE	Reserved	0x4005_01EE	Reserved	0x4005_01FE	Reserved
0x4005_01CF	Reserved	0x4005_01DF	Reserved	0x4005_01EF	Reserved	0x4005_01FF	Reserved

## [12] Programmable motor driver (PMD) [1/2]

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0400	MDEN0	0x4005_0410	MDCNT0	0x4005_0420	CMPW0	0x4005_0430	EMGRELO
0x4005_0401	<R0>	0x4005_0411	"	0x4005_0421	"	0x4005_0431	<R0>
0x4005_0402	<R0>	0x4005_0412	<R0>	0x4005_0422	<R0>	0x4005_0432	<R0>
0x4005_0403	<R0>	0x4005_0413	<R0>	0x4005_0423	<R0>	0x4005_0433	<R0>
0x4005_0404	PORTMD0	0x4005_0414	MDPRD0	0x4005_0424	MODESEL0	0x4005_0434	EMGCR0
0x4005_0405	<R0>	0x4005_0415	"	0x4005_0425	<R0>	0x4005_0435	"
0x4005_0406	<R0>	0x4005_0416	<R0>	0x4005_0426	<R0>	0x4005_0436	<R0>
0x4005_0407	<R0>	0x4005_0417	<R0>	0x4005_0427	<R0>	0x4005_0437	<R0>
0x4005_0408	MDCR0	0x4005_0418	CMPU0	0x4005_0428	MDOUT0	0x4005_0438	EMGSTA0
0x4005_0409	<R0>	0x4005_0419	"	0x4005_0429	"	0x4005_0439	<R0>
0x4005_040A	<R0>	0x4005_041A	<R0>	0x4005_042A	<R0>	0x4005_043A	<R0>
0x4005_040B	<R0>	0x4005_041B	<R0>	0x4005_042B	<R0>	0x4005_043B	<R0>
0x4005_040C	CNTSTA0	0x4005_041C	CMPV0	0x4005_042C	MDPOT0	0x4005_043C	OVVCR0
0x4005_040D	<R0>	0x4005_041D	"	0x4005_042D	"	0x4005_043D	"
0x4005_040E	<R0>	0x4005_041E	"	0x4005_042E	<R0>	0x4005_043E	<R0>
0x4005_040F	<R0>	0x4005_041F	"	0x4005_042F	<R0>	0x4005_043F	<R0>

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0440	OVVSTA0	0x4005_0450	TRGCMP20	0x4005_0460	TRGSEL0	0x4005_0470	Reserved
0x4005_0441	<R0>	0x4005_0451	"	0x4005_0461	"	0x4005_0471	Reserved
0x4005_0442	<R0>	0x4005_0452	<R0>	0x4005_0462	"	0x4005_0472	Reserved
0x4005_0443	<R0>	0x4005_0453	<R0>	0x4005_0463	"	0x4005_0473	Reserved
0x4005_0444	DTR0	0x4005_0454	TRGCMP30	0x4005_0464	Reserved	0x4005_0474	Reserved
0x4005_0445	<R0>	0x4005_0455	"	0x4005_0465	Reserved	0x4005_0475	Reserved
0x4005_0446	<R0>	0x4005_0456	<R0>	0x4005_0466	Reserved	0x4005_0476	Reserved
0x4005_0447	<R0>	0x4005_0457	<R0>	0x4005_0467	Reserved	0x4005_0477	Reserved
0x4005_0448	TRGCMP00	0x4005_0458	TRGCR0	0x4005_0468	Reserved	0x4005_0478	Reserved
0x4005_0449	"	0x4005_0459	"	0x4005_0469	Reserved	0x4005_0479	Reserved
0x4005_044A	<R0>	0x4005_045A	<R0>	0x4005_046A	Reserved	0x4005_047A	Reserved
0x4005_044B	<R0>	0x4005_045B	<R0>	0x4005_046B	Reserved	0x4005_047B	Reserved
0x4005_044C	TRGCMP10	0x4005_045C	TRGMD0	0x4005_046C	Reserved	0x4005_047C	Reserved
0x4005_044D	"	0x4005_045D	"	0x4005_046D	Reserved	0x4005_047D	Reserved
0x4005_044E	<R0>	0x4005_045E	"	0x4005_046E	Reserved	0x4005_047E	Reserved
0x4005_044F	<R0>	0x4005_045F	"	0x4005_046F	Reserved	0x4005_047F	Reserved

## [12] Programmable motor driver (PMD) [2/2]

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_0480	MDEN1	0x4005_0490	MDCNT1	0x4005_04A0	CMPW1	0x4005_04B0	EMGREL1
0x4005_0481	<R0>	0x4005_0491	"	0x4005_04A1	"	0x4005_04B1	<R0>
0x4005_0482	<R0>	0x4005_0492	<R0>	0x4005_04A2	<R0>	0x4005_04B2	<R0>
0x4005_0483	<R0>	0x4005_0493	<R0>	0x4005_04A3	<R0>	0x4005_04B3	<R0>
0x4005_0484	PORTMD1	0x4005_0494	MDPRD1	0x4005_04A4	MODESEL1	0x4005_04B4	EMGCR1
0x4005_0485	<R0>	0x4005_0495	"	0x4005_04A5	"	0x4005_04B5	"
0x4005_0486	<R0>	0x4005_0496	<R0>	0x4005_04A6	<R0>	0x4005_04B6	<R0>
0x4005_0487	<R0>	0x4005_0497	<R0>	0x4005_04A7	<R0>	0x4005_04B7	<R0>
0x4005_0488	MDCR1	0x4005_0498	CMPU1	0x4005_04A8	MDOUT1	0x4005_04B8	EMGSTA1
0x4005_0489	<R0>	0x4005_0499	"	0x4005_04A9	"	0x4005_04B9	<R0>
0x4005_048A	<R0>	0x4005_049A	<R0>	0x4005_04AA	<R0>	0x4005_04BA	<R0>
0x4005_048B	<R0>	0x4005_049B	<R0>	0x4005_04AB	<R0>	0x4005_04BB	<R0>
0x4005_048C	CNTSTA1	0x4005_049C	CMPV1	0x4005_04AC	MDPOT1	0x4005_04BC	OVVCR1
0x4005_048D	<R0>	0x4005_049D	"	0x4005_04AD	<R0>	0x4005_04BD	"
0x4005_048E	<R0>	0x4005_049E	<R0>	0x4005_04AE	<R0>	0x4005_04BE	<R0>
0x4005_048F	<R0>	0x4005_049F	<R0>	0x4005_04AF	<R0>	0x4005_04BF	<R0>

ADR	Register name	ADR	Register name	ADR	Register name	ADR	Register name
0x4005_04C0	OVVSTA1	0x4005_04D0	TRGCMP21	0x4005_04E0	TRGSEL1	0x4005_04F0	Reserved
0x4005_04C1	<R0>	0x4005_04D1	"	0x4005_04E1	"	0x4005_04F1	Reserved
0x4005_04C2	<R0>	0x4005_04D2	<R0>	0x4005_04E2	"	0x4005_04F2	Reserved
0x4005_04C3	<R0>	0x4005_04D3	<R0>	0x4005_04E3	"	0x4005_04F3	Reserved
0x4005_04C4	DTR1	0x4005_04D4	TRGCMP31	0x4005_04E4	Reserved	0x4005_04F4	Reserved
0x4005_04C5	<R0>	0x4005_04D5	"	0x4005_04E5	Reserved	0x4005_04F5	Reserved
0x4005_04C6	<R0>	0x4005_04D6	<R0>	0x4005_04E6	Reserved	0x4005_04F6	Reserved
0x4005_04C7	<R0>	0x4005_04D7	<R0>	0x4005_04E7	Reserved	0x4005_04F7	Reserved
0x4005_04C8	TRGCMP01	0x4005_04D8	TRGCR1	0x4005_04E8	Reserved	0x4005_04F8	Reserved
0x4005_04C9	"	0x4005_04D9	"	0x4005_04E9	Reserved	0x4005_04F9	Reserved
0x4005_04CA	<R0>	0x4005_04DA	<R0>	0x4005_04EA	Reserved	0x4005_04FA	Reserved
0x4005_04CB	<R0>	0x4005_04DB	<R0>	0x4005_04EB	Reserved	0x4005_04FB	Reserved
0x4005_04CC	TRGCMP11	0x4005_04DC	TRGMD1	0x4005_04EC	Reserved	0x4005_04FC	Reserved
0x4005_04CD	"	0x4005_04DD	"	0x4005_04ED	Reserved	0x4005_04FD	Reserved
0x4005_04CE	<R0>	0x4005_04DE	"	0x4005_04EE	Reserved	0x4005_04FE	Reserved
0x4005_04CF	<R0>	0x4005_04DF	"	0x4005_04EF	Reserved	0x4005_04FF	Reserved



## 22. Electrical Characteristics

### 22.1 Absolute Maximum Ratings

Parameter		Symbol	Rating	Unit
Supply voltage		DVDD5	- 0.3 to 6	V
		DVDDE	- 0.3 to 6	
		VINREG5	- 0.3 to 6	
		AVDD	- 0.3 to 6	
		AMPVDD	- 0.3 to 6	
		VOUT15	- 0.3 to 3	
		VOUT3	- 0.3 to 3.9	
Input voltage		VIN	- 0.3 to VDD+0.3	V
Low-level output current	Per pin	I <sub>OL</sub>	5	mA
	Total	ΣI <sub>OL</sub>	50	
High-level output current	Per pin	I <sub>OH</sub>	- 5	
	Total	ΣI <sub>OH</sub>	50	
Power consumption (Ta = 85°C)		PD	600	mW
Soldering temperature (10s)		T <sub>SOLDER</sub>	260	°C
Storage temperature		T <sub>STG</sub>	- 55 to 125	°C
Operating Temperature	Except during Flash W/E	T <sub>OPR</sub>	- 40 to 85	°C
	During Flash W/E		0 to 70	
Write/erase cycles		N <sub>EW</sub>	100	cycle

**(Note)** Absolute maximum ratings are limiting values of operating and environmental conditions which should not be exceeded under the worst possible conditions. The equipment manufacturer should design so that no Absolute maximum rating value is exceeded with respect to current, voltage, power consumption, temperature, etc. Exposure to conditions beyond those listed above may cause permanent damage to the device or affect device reliability, which could increase potential risks of personal injury due to IC blowup and/or burning.

## 22.2 DC Electrical Characteristics (1/2)

Ta = -40 to 85°C

Parameter		Symbol	Rating	Min.	Typ. (Note 1)	Max.	Unit
Supply voltage	DVDD5 = DVDDE = AVDD =VINREG5 DVSS =AVSS = CVSS = 0V	DVDD AVDD VINREG5	fosc = 8 to 10MHz fsys = 1 to 80MHz	4.5	-	5.5	V
Supply voltage (during Flash W/E)	DVDD5 = DVDDE = AVDD =VINREG5 DVSS =AVSS = CVSS = 0V	DVDD AVDD VINREG5	fosc = 8 to 10MHz fsys = 1 to 80MHz (Ta (°C) = 0 to 70)	4.5	-	5.5	V
High-level input voltage	Schmitt-Input	V <sub>IL1</sub>	DVDD5 = 4.5 to 5.5V	-0.3		0.25 DVDD5	V
Low-level input voltage	Schmitt-Input	V <sub>IH1</sub>	DVDD5 = 4.5V to 5.5V	0.75 DVDD5		DVDD5	
Capacitance for VOUT15 and VOUT3 (Note 3)		C <sub>out</sub>	DVDD5 = 4.5V to 5.5V	1		0.47	μF
Low-level output voltage		V <sub>OL</sub>	I <sub>OL</sub> = 1.6mA DVDD5 ≥ 4.5V	-	-	0.4	V
High-level output voltage		V <sub>OH</sub>	I <sub>OH</sub> = -1.6mA DVDD5 ≥ 4.5V	4.1	-	-	V
Input leakage current		I <sub>LI</sub>	0.0 ≤ V <sub>IN</sub> ≤ DVDD 0.0 ≤ V <sub>IN</sub> ≤ AVDD	-	0.02	± 5	μA
Output leakage current		I <sub>LO</sub>	0.2 ≤ V <sub>IN</sub> ≤ DVDD - 0.2 0.2 ≤ V <sub>IN</sub> ≤ AVDD - 0.2	-	0.05	± 10	
Pull-up resistor at Reset		R <sub>RST</sub>	4.5V ≤ DVDD ≤ 5.5V	-	50	150	kΩ
Schmitt-Triggered port		V <sub>TH</sub>	4.5V ≤ DVDD ≤ 5.5V	0.3	0.6	-	V
Programmable pull-up/ pull-down resistor		P <sub>KH</sub>	4.5V ≤ DVDD ≤ 5.5V	-	50	150	kΩ
Pin capacitance (Except power supply pins)		C <sub>IO</sub>	f <sub>c</sub> = 1MHz	-	-	10	pF

(Note 1) Ta = 25°C, DVDD5 = DVDDE = AVDD = VINREG5 = 5V, unless otherwise noted.

(Note 2) The same voltage must be supplied to DVDD5, DVDDE, AVDD and VINREG5.

(Note 3) VOUT15 and VOUT3 pin should be connected to GND via a capacitance.



## 22.3 DC Electrical Characteristics (2/2)

$T_a = -40$  to  $85^\circ\text{C}$  DVDD5 = DVDDE = VINREG5 = AVDD = AMPVDD = 4.5V to 5.5V

Parameter	Symbol	Rating	Min.	Typ. (Note 1)	Max.	Unit
NORMAL (Note 2) Gear 1/1	$I_{CC}$	$f_{sys} = 80\text{MHz}$ ( $f_{osc} = 10\text{MHz}$ )			80	mA
STOP				7	T.B.D	mA
Write Erase Current				T.B.D	T.B.D	mA

(Note 1)  $T_a = 25^\circ\text{C}$ , DVDD5 = DVDDE = AVDD = VINREG5 = 5V, unless otherwise noted.

(Note 2) ICC NORMAL: Measured with the dhrystone ver. 2.1 operated in FLASH. All functions operates excluding A/D, Op amp and Comparator.

(Note 3) A/D reference voltage supply can not go into off state.

## 22.4 12-bit ADC Electrical Characteristics

DVDD=VINREG5=AVDD/VREFH = 4.5V to 5.5V,  
DVSS=CVSS=AVSS/VREFL=0V,  $T_a = -40$  to  $85^\circ\text{C}$

Parameter	Symbol	Rating	Min.	Typ.	Max.	Unit
Analog reference voltage (+)	VREFH	-		AVDD		V
Analog input voltage	VAIN	-	AVSS	-	AVDD	V
Analog supply current (Note.1)(Note 2)	IREF	DVSS = AVSS	-	3.5	4.5	mA
Supply current (Note 1)	A/D conversion	-	Non- IREF	-	3	mA
INL error	—	AIN resistance $\leq 600\Omega$ AIN load capacitance $\leq 0.1\mu\text{F}$ Conversion time $\geq 2\mu\text{s}$			$\pm 5$	LSB
DNL error					$\pm 4$	
Offset error					$\pm 5$	
Full-scale error					$\pm 5$	
Total error					$\pm 5$	

(Note 1) Current for ADC 1 unit.

(Note 2) A/D reference voltage supply can not go into off state.

(Note 3)  $1\text{LSB} = (\text{AVDD} - \text{AVSS}) / 4096[\text{V}]$

## 22.5 Op-Amps Electrical Characteristics

DVDD5 = DVDDE = VINREG5 = 4.5V to 5.5V,  
DVSS = CVSS = 0V, Ta = -40 to 85°C

Parameter	Symbol	Rating	Min.	Typ.	Max.	Unit
Gain (Note 1)	VGAIN	AVDD = 4.5 to 5.5V AVSS = 0V	× 1.5	-	× 10	
Input voltage range	VAMPIN		$\frac{(AVDD \times 0.1)}{VGAIN}$	-	$\frac{(AVDD \times 0.9)}{VGAIN}$	V
Offset voltage	VOFF		- 3 × VGAIN	-	+ 3 × VGAIN	mV
Gain error			-	± 1	± 3	%
Slew rate (Note 2)	Vthr	AVDD = 4.5 to 5.5V AVSS = 0V 5pF, VGAIN = × 2.5	2	-	-	V/μs

(Note 1) Gain can be selected among ×2.5, ×3, ×3.5, ×4, ×6 and ×8 by register setting.

(Note 2) Slew rate means a slant til the output of amplifier reaches AVDD-0.001×AVDD.

## 22.6 Comparator Electrical Characteristics

DVDD5 = DVDDE = VINREG5 = 4.5V to 5.5V,  
DVSS = CVSS = 0V, Ta = -40 to 85°C

Parameter	Symbol	Rating	Min.	Typ.	Max.	Unit
Offset voltage	VOFF	AVDD = 4.5 to 5.5V AVSS = 0V	-	± 4	-	%
AIN input voltage range	VIN		AVSS	-	AVDD	V
Reference voltage range	VREF		0.9	-	AVDD-0.2	V
Response time (Note 1)			-	-	1	μs

(Note 1)  $1.0V \leq VREF \leq AVDD-0.2V$

## 22.7 AC Electrical Characteristics

AC measurement condition

Output levels: High 0.8DVDD5 V/Low 0.2DVDD5, CL=30pF

Input levels: Refer to low-level input voltage and high-level input voltage in 22.2 DC Electrical Characteristics.

In the table below, the letter x represents the period of the system clock (fsys). It varies depending on the programming of the clock gear function.

### 22.7.1 Serial Channel Timing (SIO)

(1) I/O Interface mode

SCLK input mode

(DVDD5 = 4.5V to 5.5V, Ta = -40 to 85°C)

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
SCLK cycle	t <sub>SCY</sub>	T.B.D		T.B.D		ns
SCLK Clock High width (input)	T <sub>SC<sub>H</sub></sub>	T.B.D		T.B.D		ns
SCLK Clock Low width (input)	T <sub>SC<sub>L</sub></sub>	T.B.D		T.B.D		ns
TxD to SCLK rise or fall (Note 1)	t <sub>OSS</sub>	T.B.D		T.B.D (Note 2)		ns
TxD hold or fall after SCLK rising (Note 1)	t <sub>OHS</sub>	T.B.D		T.B.D		ns
RxD valid to SCLK rise or fall (Note 1)	t <sub>SRD</sub>	T.B.D		T.B.D		ns
RxD hold or fall after SCLK rising (Note 1)	t <sub>HSR</sub>	T.B.D		T.B.D		ns

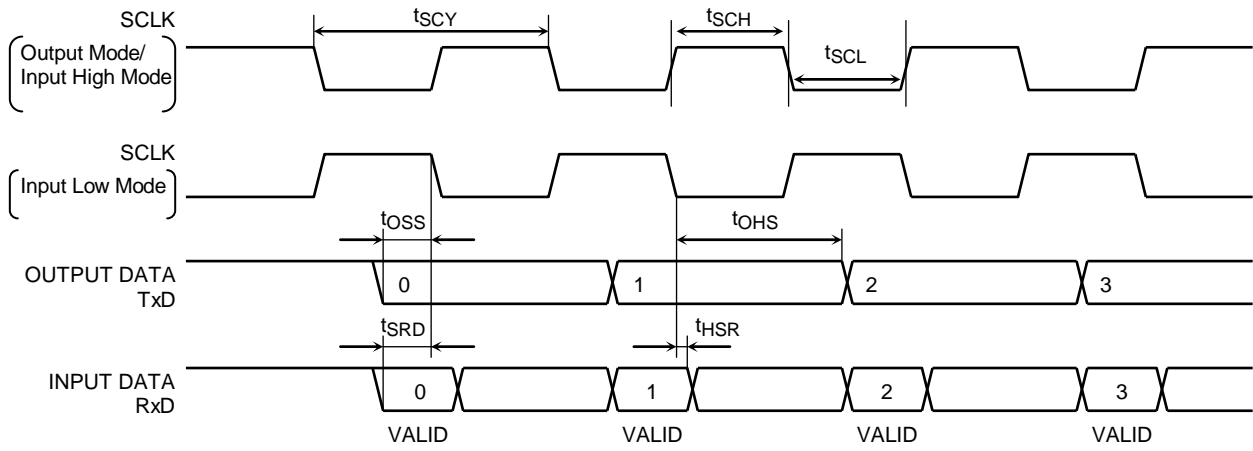
**(Note 1) SCLK rise or fall:** Measured relative to the programmed active edge of SCLK.

**(Note 2) Keep this value positive by adjusting SCLK cycle.**

SCLK output mode

(DVDD5 = 4.5V to 5.5V, Ta = -40 to 85°C)

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
SCLK cycle (programmable)	t <sub>SCY</sub>	T.B.D		T.B.D		ns
TxD to SCLK rise	t <sub>OSS</sub>	T.B.D		T.B.D		ns
TxD hold after SCLK rising	t <sub>OHS</sub>	T.B.D		T.B.D		ns
RxD valid to SCLK rise	t <sub>SRD</sub>	T.B.D		T.B.D		ns
RxD hold after SCLK rising	t <sub>HSR</sub>	T.B.D		T.B.D		ns



### 22.7.2 Event Counter

Ta = -40 to 85°C

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
Clock low pulse width	$t_{VCKL}$	$2x + 100$		125		ns
Clock high pulse width	$t_{VCKH}$	$2x + 100$		125		ns

### 22.7.3 Capture

Ta = -40 to 85°C

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
Low pulse width	$t_{CPL}$	$2x + 100$		125		ns
High pulse width	$t_{CPH}$	$2x + 100$		125		ns

### 22.7.4 General Interrupts

Ta = -40 to 85°C

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
Low pulse width for INT0 to F	$t_{INTAL}$	$x + 100$		112.5		ns
High pulse width for INT0 to F	$t_{INTAH}$	$x + 100$		112.5		ns

### 22.7.5 STOP Release Interrupts

Ta = -40 to 85°C

Parameter	Symbol	Equation		80MHz		Unit
		Min.	Max.	Min.	Max.	
Low pulse width for INT0 to F	$t_{INTBL}$	100		100		ns
High pulse width for INT0 to F	$t_{INTBH}$	100		100		ns

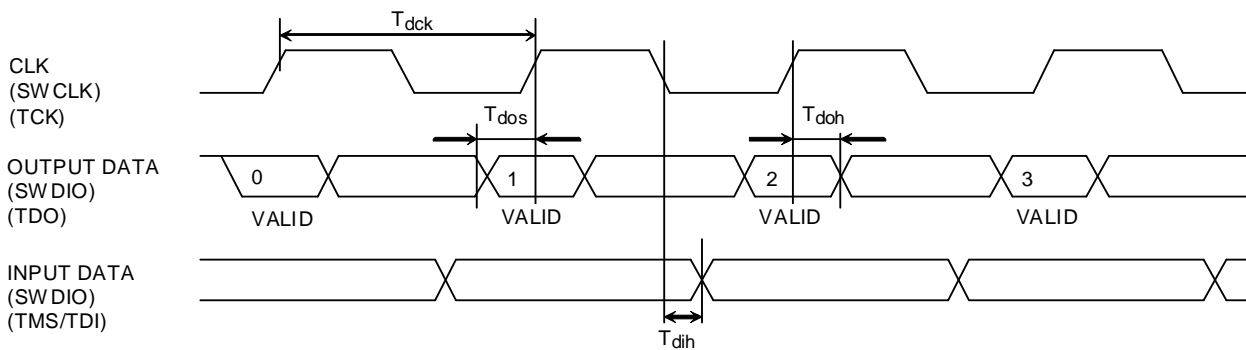
### 22.7.6 Debug Communication

#### (1) SWD Interface

Parameter	Symbol	Min.	Max.	Unit
CLK cycle	$T_{dck}$	T.B.D	-	ns
DATA to CLK rising	$T_{dos}$	T.B.D	-	ns
DATA hold after CLK rising	$T_{doh}$	T.B.D	-	ns
DATA hold after CLK falling	$T_{dih}$	-	T.B.D	ns

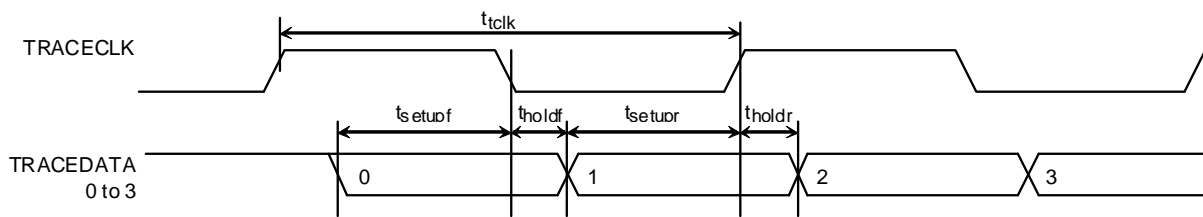
#### (2) JTAG Interface

Parameter	Symbol	Min.	Max.	Unit
CLK cycle	$T_{dck}$	T.B.D	-	ns
DATA to CLK rising	$T_{dos}$	T.B.D	-	ns
DATA hold after CLK rising	$T_{doh}$	T.B.D	-	ns



22.7.7 TRACE Output

Parameter	Symbol	Min.	Max.	Unit
TRACECLK cycle	$t_{clk}$	T.B.D	-	ns
TRACEDATA valid to DCLK rise	$t_{setupr}$	T.B.D	-	ns
TRACEDATA hold after DCLK rising	$t_{holdr}$	T.B.D	-	ns
TRACEDATA valid to DCLK fall	$t_{setupf}$	T.B.D	-	ns
TRACEDATA hold after DCLK falling	$t_{holdf}$	T.B.D	-	ns



## 22.8 Recommended Oscillation Circuit

The TMPM330 has been evaluated by the oscillator vendor below. Use this information when selecting external parts.

**(Note)**The load value of the oscillator is the sum of loads (C1 and C2) and the floating load of the actual assembled board. There is a possibility of operating error when using C1 and C2 values in the table below. When designing the board, design the minimum length pattern around the oscillator. We also recommend that oscillator evaluation be carried out using the actual board.

### (1) Connection example

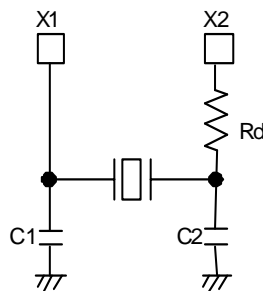


Fig. 22-1 High-frequency oscillation connection

### (2) Recommended ceramic oscillator

The TMPM370 recommends the high-frequency oscillator by Murata Manufacturing Co., Ltd.

Please refer to the following URL for details.

<http://www.murata.co.jp>

### (3) Recommended ceramic oscillator

The TMPM370 recommends the high-frequency oscillator by KYOCERA KINSEKI Corporation.

Please refer to the following URL for details.

<http://www.kinseki.co.jp>



## 22.9 Handling Precaution

### Solderability of lead free products

Test parameter	Test condition	Note
Solderability	Use of Sn-37Pb solder Bath Solder bath temperature = 230°C, Dipping time = 5 seconds The number of times = one, Use of R-type flux	Pass: solderability rate until forming $\geq$ 95%
	Use of Sn-3.0Ag-0.5Cu solder bath Solder bath temperature = 245°C, Dipping time = 5 seconds The number of times = one, Use of R-type flux (use of lead free)	

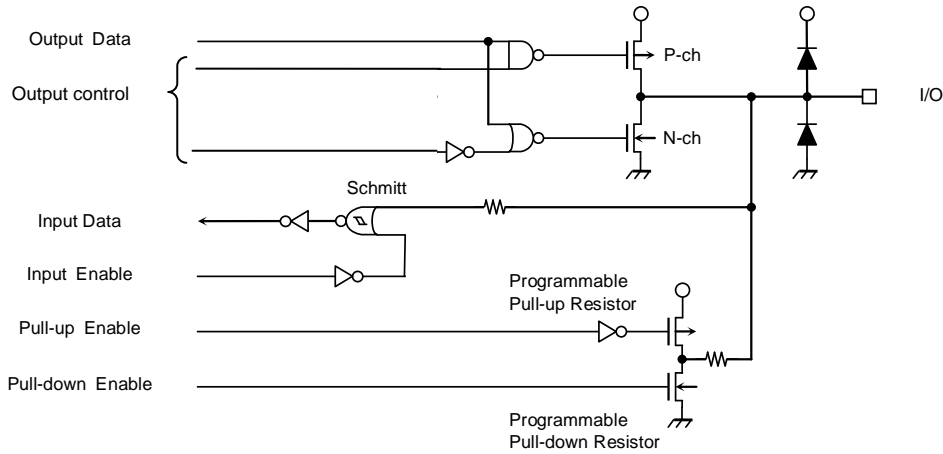
### 23. Port Section Equivalent Circuit Schematics

- How to read the schematics

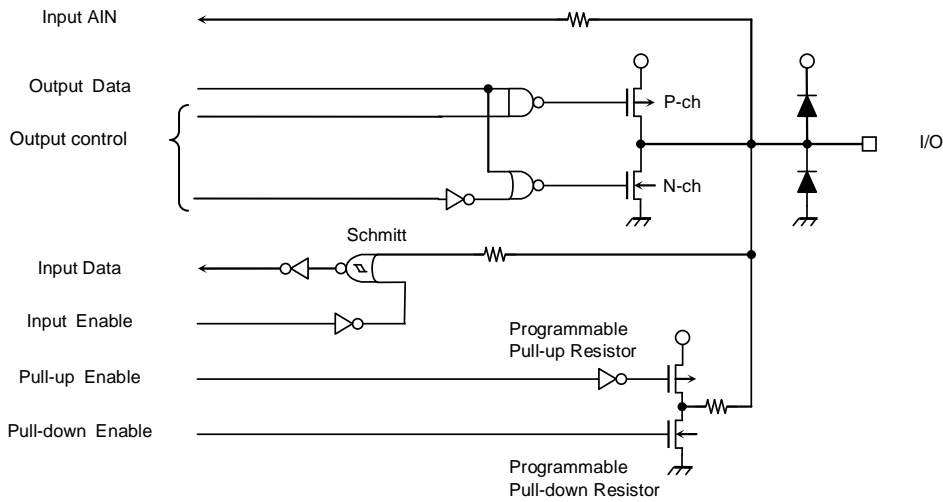
Basically, the gate symbols written are the same as those used for the standard CMOS logic IC [74HCXX] series.

The input protection resistance ranges from several tens of ohms to several hundreds of ohms. Damping resistor and Feedback resistor are shown with a typical value.

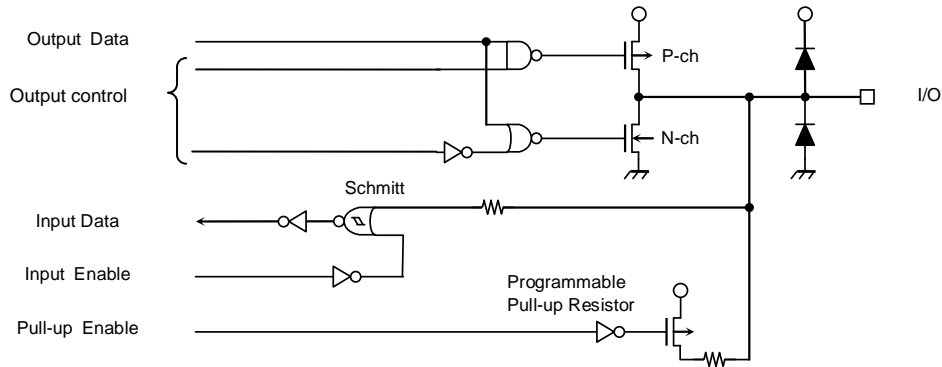
- PA0-7 PC0-7, PD0-6, PE0-7, PF0-4, PG0-7



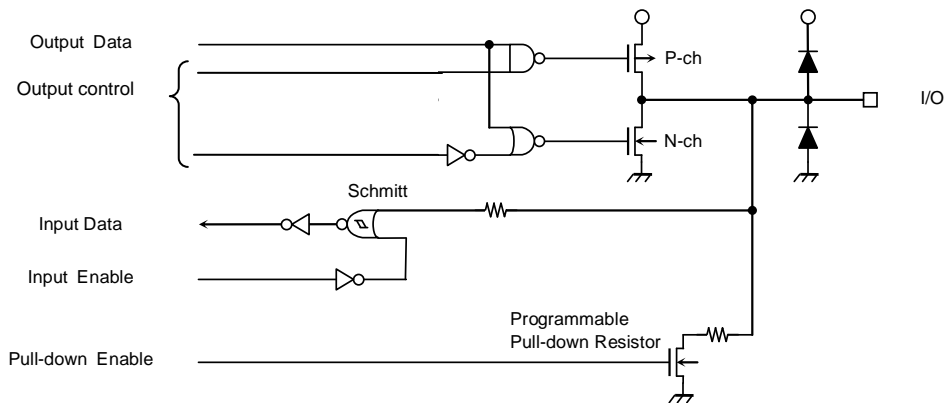
- PH0-7, PI0-3, PJ0-7, PK0-1



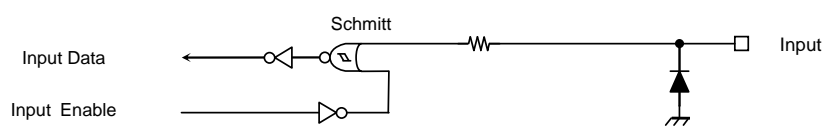
- PB0-3, PB5-7



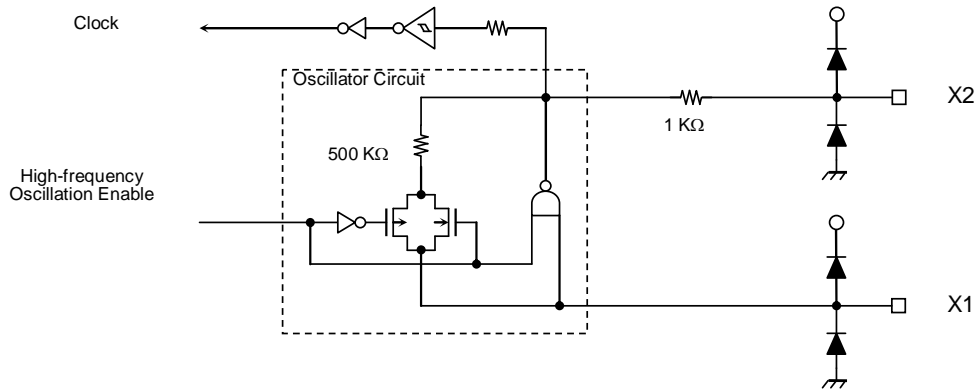
- PB4



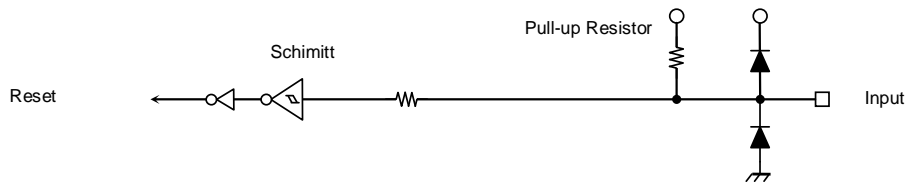
- PL0-1



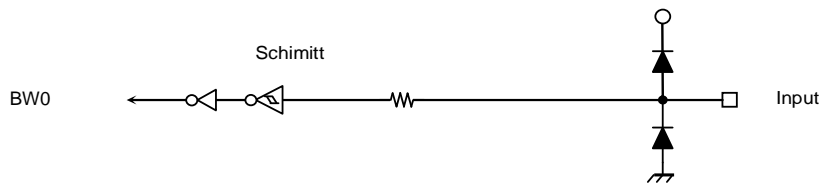
- X1, X2



- $\overline{\text{RESET}}$

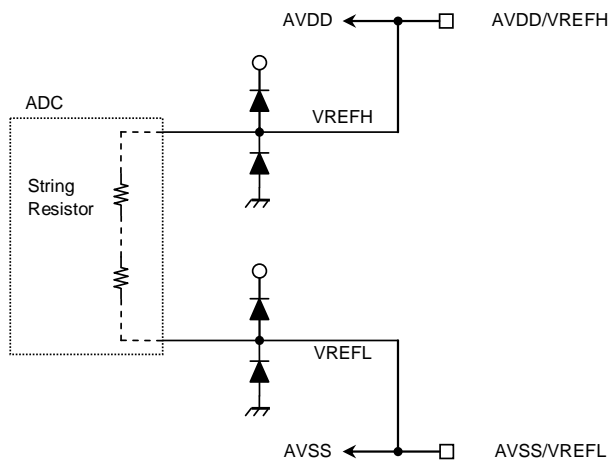


- BW0

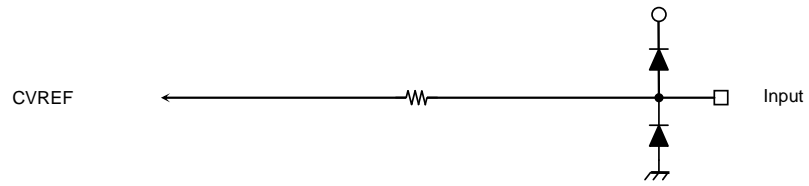


Note : BW0 must be connected with GND.

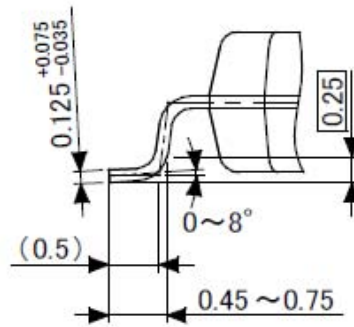
- AVDDA/VREFHA, AVSSA/VREFLA, AVddb/VREFHB, AVSSB/VREFLB



- CVREFABC, CVREFD





Pin detail

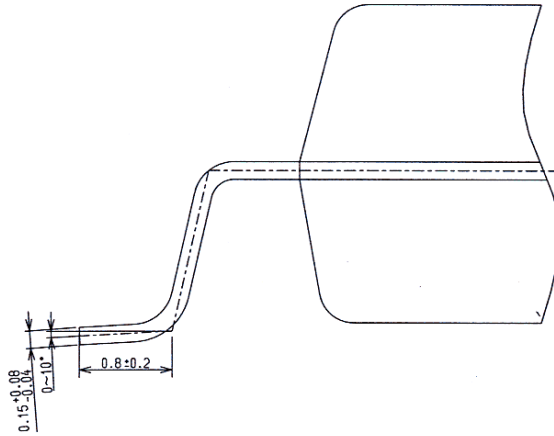
(Note 1) For more dimensional information, please contact any one of our representatives

(Note 2) The package is palladized





Pin detail



- |         |   |
|---------|---|
| (Note1) | For more dimensional information, please contact any one of our representatives |
| (Note2) | The package is palladized   |

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