

## Description

The ZMID5201, ZMID5202, and ZMID5203 family of inductive position sensor ICs are used for absolute rotary or linear motion sensing in automotive, industrial, medical, and consumer applications. The ZMID520x uses the physical principles of induction in a wire loop and eddy currents to detect the position of an electrically conducting target that is sliding or rotating above a set of coils, consisting of one transmitter coil and two receiver coils.

The three coils are typically printed as copper traces on a printed circuit board (PCB). They are arranged such that the transmitter coil induces a secondary voltage in the receiver coils that depends on the position of the metallic target above the coils.

A signal representative of the target's position over the coils is obtained by demodulating and processing the secondary voltages from the receiver coils. The target can be any kind of metal, such as aluminum, steel or a PCB with a printed copper layer.

The ZMID5201/02/03 ICs are fully qualified according to the automotive standard AEC-Q100 grade 0 (-40°C to 150°C ambient temperature).

Three versions with different output interfaces are available:

- ZMID5201: Analog output
- ZMID5202: PWM digital output
- ZMID5203: SENT digital output

## Available Support

IDT provides Application Modules that demonstrate ZMID520x position sensing, including rotary, arc, and linear applications.

## Physical Characteristics

- Wide operation temperature: -40 C to +150°C
- Supply voltage: 4.5V to 5.5V
- Small 14-TSSOP package

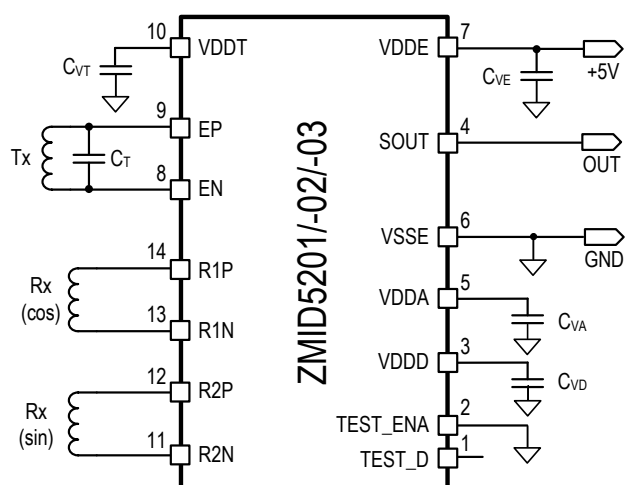
## Typical Applications

- Rotary position sensors up to 360°; e.g. steering angle sensors, potentiometer replacement
- Small-angle sensors or arc-motion sensors; e.g. pedal, vehicle level, or valve sensors
- Linear motion sensors; e.g. linear-actuator position sensors, fluid-level sensors

## Features

- Position sensing based on inductive principle
- Cost effective; no magnet required
- Immune to magnetic stray fields; no shielding required
- Suitable for harsh environments and extreme temperatures
- Only three wires (ground, supply, output)
- Nonvolatile user memory; programming through output pin
- Single IC supports on-axis and off-axis rotation, linear motion, and arc motion sensing
- High resolution, even for small angle ranges
- High accuracy:  $\leq 0.2\%$  full scale
- 9-point user linearization
- Rotation sensing up to a full turn of 360°
- Overvoltage and reverse-polarity protection: -14V to +18V maximum, depending on product
- ESD and short-circuit protection
- Power or ground loss detection
- Facilitates redundant design requirements
- Programmable non-linearity correction
- Adaptive gain control supporting a wide range of coil designs and target displacement
- The ZMID5201/02/03 products are safety-related, intermediate hardware parts supporting ISO26262-compliant systems in regard to random failures

## Application Circuit



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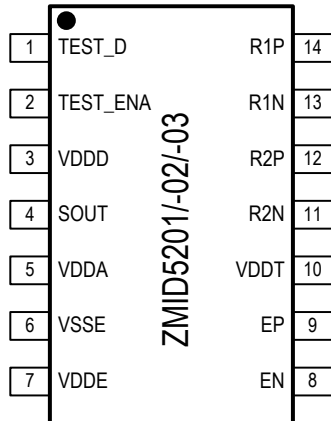
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## 1. Pin Assignments

The ZMID5201/02/03 ICs are available in a 14-TSSOP RoHS package.

**Figure 1. Pin Assignments for 14-TSSOP Package – Top View**

Note: The SOUT pin is referred to as the AOUT pin for the ZMID5201; PWM OUT for the ZMID5202; and SENT OUT for the ZMID5203.



## 2. Pin Descriptions

**Table 1. Pin Descriptions**

| Number | Name     | Type                                      | Description  |
|--------|----------|---|--|
| 1      | TEST_D   | Input/output                              | Factory test pin; must be left unconnected.  |
| 2      | TEST_ENA | Input/output                              | Factory test pin. Connect to the VSSE pin.   |
| 3      | VDDD     | Supply                                    | Internal regulated digital supply voltage. Connect capacitor $C_{VD} = 100\text{nF}$ from the VDDD pin to the VSSE pin, no other load.                                   |
| 4      | SOUT     | Analog output:<br>ZMID5201 only           | Analog output (also referred to as AOUT for the ZMID5201). Refer to section 9, Figure 6, and Figure 7 for external connections.  |
|        |          | PWM digital output:<br>ZMID5202 only      | PWM digital output (also referred to as PWM OUT for the ZMID5202). Refer to section 10 and Figure 12 for external connections.   |
|        |          | SENT digital output:<br>ZMID5203 only     | SENT output (also referred to as SENT OUT for the ZMID5203). Refer to section 11, Figure 13, Figure 14, and Figure 15 for external connections.                          |
|        |          | Digital input/output:<br>programming only | Digital One-Wire Interface (OWI) used during programming.  |
| 5      | VDDA     | Supply                                    | Internal regulated analog supply voltage. Connect $C_{VA} = 100\text{nF}$ from the VDDA pin to the VSSE pin; no other load.  |
| 6      | VSSE     | Ground                                    | Common ground connection.  |
| 7      | VDDE     | Supply                                    | External supply voltage. Connect the VDDE pin to $C_{VE} = 100\text{nF}$ capacitor in parallel with a $1\text{pF}$ to $10\text{pF}$ capacitor connected to the VSSE pin. |

| Number | Name | Type          | Description   |
|--------|------|---------------|---|
| 8      | EN   | Analog output | Connect the transmitter coil between EP and EN. The resonant frequency is adjusted with a parallel capacitor $C_T$ between EP and EN (see application diagram on page 1 and block diagram in Figure 4). |
| 9      | EP   |               |   |
| 10     | VDDT | Supply        | Internal supply voltage for transmitter amplifier. Connect to $C_{VT} = 100\text{nF}$ to VSSE.  |
| 11     | R2N  | Analog input  | Connect receiver coil 2 between the R2N and R2P pins.   |
| 12     | R2P  |               |   |
| 13     | R1N  | Analog input  | Connect receiver coil 1 between the R1N and R1P pins.   |
| 14     | R1P  |               |   |

### 3. Absolute Maximum Ratings

The absolute maximum ratings are stress ratings only. Stresses greater than those listed below can cause permanent damage to the device. Functional operation of the ZMID5201/02/03 at the absolute maximum ratings is not implied. Exposure to absolute maximum rating conditions could affect device reliability.

**Table 2. Absolute Maximum Ratings**

Note: See important notes at the end of the table.

| Symbol          | Parameter   | Conditions   | Minimum | Maximum | Units |
|-----------------|---|--|---------|---------|-------|
| $V_{VDDE}$      | External supply voltage   |  | -18     | 18      | V     |
| $V_{OUT\_ANA}$  | ZMID5201 analog output voltage on the AOUT pin <sup>[a]</sup>   | For negative voltage, external current must be limited to 10mA | -14     | 14      | V     |
|                 |   | Without external current limitation                            | -0.3    | 14      | V     |
| $V_{OUT\_PWM}$  | ZMID5202 PWM output voltage on the PWM OUT pin <sup>[a]</sup>   | For negative voltage, external current must be limited to 10mA | -14     | 18      | V     |
|                 |   | Without external current limitation                            | -0.3    | 18      | V     |
| $V_{OUT\_SENT}$ | ZMID5203 SENT output voltage on the SENT OUT pin <sup>[a]</sup> | For negative voltage, external current must be limited to 10mA | -14     | 18      | V     |
|                 |   | Without external current limitation                            | -0.3    | 18      | V     |
| $V_{OSC\_COIL}$ | Oscillator coil pins: EP, EN                                    |  | -0.3    | 5.5     | V     |
| $V_{R1P}$       | Receiver coil pin: R1P  |  | -0.3    | 3.6     | V     |
| $V_{R1N}$       | Receiver coil pin: R1N  |  |         |         |       |
| $V_{R2P}$       | Receiver coil pin: R2P  |  |         |         |       |
| $V_{R2N}$       | Receiver coil pin: R2N  |  |         |         |       |

| Symbol                | Parameter                          | Conditions | Minimum | Maximum | Units |
|-----------------------|------------------------------------|------------|---------|---------|-------|
| V <sub>TEST_ENA</sub> | Test pin: TEST_ENA                 |            | -0.3    | 5.5     | V     |
| V <sub>TEST_D</sub>   | Test pin: TEST_D                   |            | -0.3    | 3.6     | V     |
| V <sub>VDDA</sub>     | Regulated supply voltage pin: VDDA |            | -0.3    | 3.6     | V     |
| V <sub>VDDD</sub>     | Regulated supply voltage pin: VDDD |            | -0.3    | 3.6     | V     |
| V <sub>VDDT</sub>     | Regulated supply voltage pin: VDDT |            | -0.3    | 4.2     | V     |

[a] The SOUT pin is referred to as the AOUT pin for the ZMID5201; PWM OUT for the ZMID5202; and SENT OUT for the ZMID5203.

## 4. Operating Conditions

Conditions: VDDE = 5V ±10%, T<sub>AMB</sub> = -40°C to +150°C.

**Table 3. Operating Conditions**

| Symbol            | Parameter                                   | Conditions              | Minimum | Typical | Maximum | Units |
|-------------------|---|-------------------------|---------|---------|---------|-------|
| T <sub>AMB</sub>  | Ambient temperature                         |                         | -40     |         | 150     | °C    |
| T <sub>J</sub>    | Junction temperature                        |                         | -40     |         | 175     | °C    |
| T <sub>STOR</sub> | Storage temperature                         |                         | -50     |         | 150     | °C    |
| R <sub>THJA</sub> | Thermal resistance junction to ambient      |                         |         |         | 140     | °C/W  |
| V <sub>VDDE</sub> | Supply voltage                              |                         | 4.5     | 5       | 5.5     | V     |
| ESD               | Electrostatic discharge,<br>HBM 100pF/1.5kΩ | Pins VSSE, VDDE         | ±4      |         |         | kV    |
|                   |   | Pin SOUT <sup>[a]</sup> | ±3      |         |         | kV    |
|                   |   | All other pins          | ±2      |         |         | kV    |

[a] The SOUT pin is referred to as the AOUT pin for the ZMID5201, PWM OUT for the ZMID5202, and SENT OUT for the ZMID5203.

## 5. Electrical Characteristics

The following electrical specifications are valid for the operating conditions as specified in Table 3: ( $T_{AMB} = -40^{\circ}\text{C}$  to  $150^{\circ}\text{C}$ ).

**Table 4. ZMID5201/02/03 Electrical Characteristics**

| Symbol                   | Parameter                                   | Conditions   | Minimum | Typical | Maximum | Units         |
|--------------------------|---|--|---------|---------|---------|---------------|
| $V_{VDDE\_TH\_H}$        | VDDE switch ON threshold                    | The device is activated when VDDE increases above this threshold             |         |         | 4.4     | V             |
| $t_{START}$              | Startup Time                                | Time between $VDDE > V_{VDDE\_TH\_H}$ and valid output at SOUT               |         | 5       | 9       | ms            |
| $V_{VDDE\_TH\_L}$        | VDDE switch OFF threshold                   | The device is deactivated when VDDE decreases below this threshold           | 4       |         |         | V             |
| $V_{VDDE\_HYST}$         | VDDE hysteresis                             |  | 0.1     |         |         | V             |
| $V_{VDDE\_OVH}$          | Over-voltage detection high                 | The device is deactivated after VDDE increases above this voltage            |         |         | 7       | V             |
| $V_{VDDE\_OVL}$          | Over-voltage detection low                  | The device is activated after VDDE decreases below this voltage              | 5.6     |         |         | V             |
| $V_{VDDA}$               | Regulated analog supply output voltage      | Internally regulated, fixed  | 3.0     | 3.3     | 3.6     | V             |
| $V_{VDD}$                | Regulated digital supply output voltage     | Internally regulated, fixed  | 1.8     | 2.0     | 2.5     | V             |
| $V_{VDDT}$               | Regulated coil driver supply output voltage | Internally regulated, user programmable. Nominal voltage at room temperature | 2.7     | 3.3     | 4.1     | V             |
| $TC_{VDDT}$              | Temperature coefficient of VDDT regulator   |  |         | 4000    |         | ppm/K         |
| $I_{CC}$                 | Current consumption                         | Without coils, no load   | 5       |         | 9       | mA            |
|                          |   | With coils, no load; depending on programmable Tx coil current               |         | 12      | 20      | mA            |
| <b>Angle Calculation</b> |   |  |         |         |         |               |
| $t_{SAMPLE}$             | Data acquisition time                       |  | 45      | 50      | 55      | $\mu\text{s}$ |
| $t_{REFRESH}$            | Output update rate                          | Analog output  |         |         | 10      | kHz           |
| RES <sub>CORDIC</sub>    | CORDIC resolution                           | Internal; over 360° electrical   |         | 16      |         | bits          |
| <b>Performance</b>       |   |  |         |         |         |               |
| INL                      | Accuracy <sup>[a]</sup>                     | See note [a].  |         | 0.2     |         | % FS          |

[a] The achievable accuracy depends on proper coil and target design. Nonlinearity errors in the calculated position might be further improved by 9-point linearization.

**Table 5. Coil Specifications**

| Symbol            | Parameter                     | Conditions  | Minimum | Typical | Maximum | Units            |
|-------------------|-------------------------------|---|---------|---------|---------|------------------|
| L                 | Excitation coil inductance    | For Tx coil as shown in block diagram in Figure 4 | 1.5     |         | 30      | μH               |
| Q                 | Quality factor <sup>[a]</sup> | For Tx coil as shown in block diagram in Figure 4 | 10      |         |         |                  |
| f <sub>OSC</sub>  | Excitation frequency          | LC oscillator                                     | 2.2     | 3.5     | 5.6     | MHz              |
| V <sub>TX_P</sub> | Excitation coil amplitude     | Peak voltage, pins EP vs. EN                      |         |         | 7200    | mV <sub>pp</sub> |
| V <sub>RX</sub>   | Receive coil amplitude        | Input signal full range                           | 50      |         | 360     | mV <sub>pp</sub> |

[a] Recommendation: To ensure a good quality factor and low temperature drift for the LC tank circuit, use capacitors with NP0 (negative-positive-zero) or C0G (C-zero-G) ceramics. Use Equation 1 to calculate the Q factor for the circuit.

$$Q_p = \frac{R'}{\omega_r L} = R' \sqrt{\frac{C}{L}}$$

**Equation 1**

Where

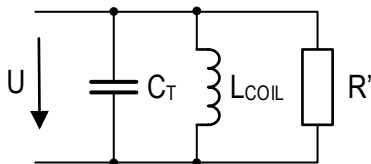
$Q_p$  Quality factor of a parallel resonator circuit as illustrated in Figure 2

$R'$  Equivalent parallel resistor

$\omega_r L$  Coil reactance at resonance frequency

$C_T$  Capacitance of parallel capacitor  $C_T$

$L_{COIL}$  Inductance of the printed circuit Tx coil

**Figure 2. Parallel Resonator Circuit**


## 6. Circuit Description

### 6.1 Overview

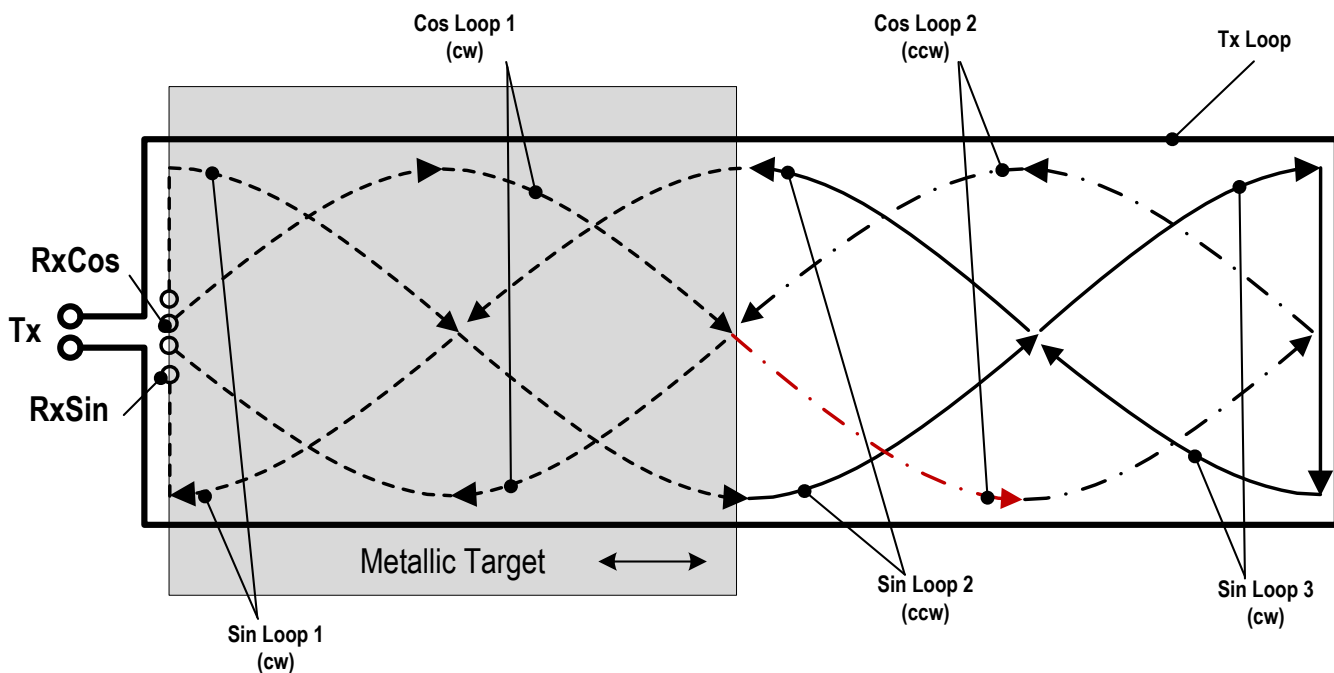
The ZMID5201/02/03 ICs are inductive position sensors for use in automotive, industrial, medical and consumer applications. They operate on the principles of induction in a wire loop and eddy currents. The sensing element is a set of coils that are directly connected to the IC. The coils consist of one transmit coil and two receive coils. The transmit coil and a capacitor form an LC oscillator that is directly driven by the IC. It generates a magnetic field within the transmit coil area that is picked up by the receiver coils.

The voltage generated by the receiver coils depends on the position of the target in the sense that areas shielded by the target generate a weaker secondary voltage compared to areas that are not shaded by the target.

The two receive coils are arranged so that the secondary voltages are relatively phase shifted by electrical  $90^\circ$ , thereby generating a response curve (receive coil output voltages versus position) that resembles a sine and cosine waveform over the range of target travel. By having a sine and cosine shaped response, a ratiometric measurement is possible, which greatly improves the robustness of the system because the output signal will remain stable, even if the gap between coils and target is varied.

Figure 3 shows an example of a linear motion sensor with one transmit coil (Tx loop) and two receive coils (Sin loop and Cos loop). The arrows in the receive coils indicate the direction of the induced current relative to each other. The direction of the current either clockwise (cw) or counterclockwise (ccw) determines the polarity of the voltage generated in each loop (RxCos, RxSin).

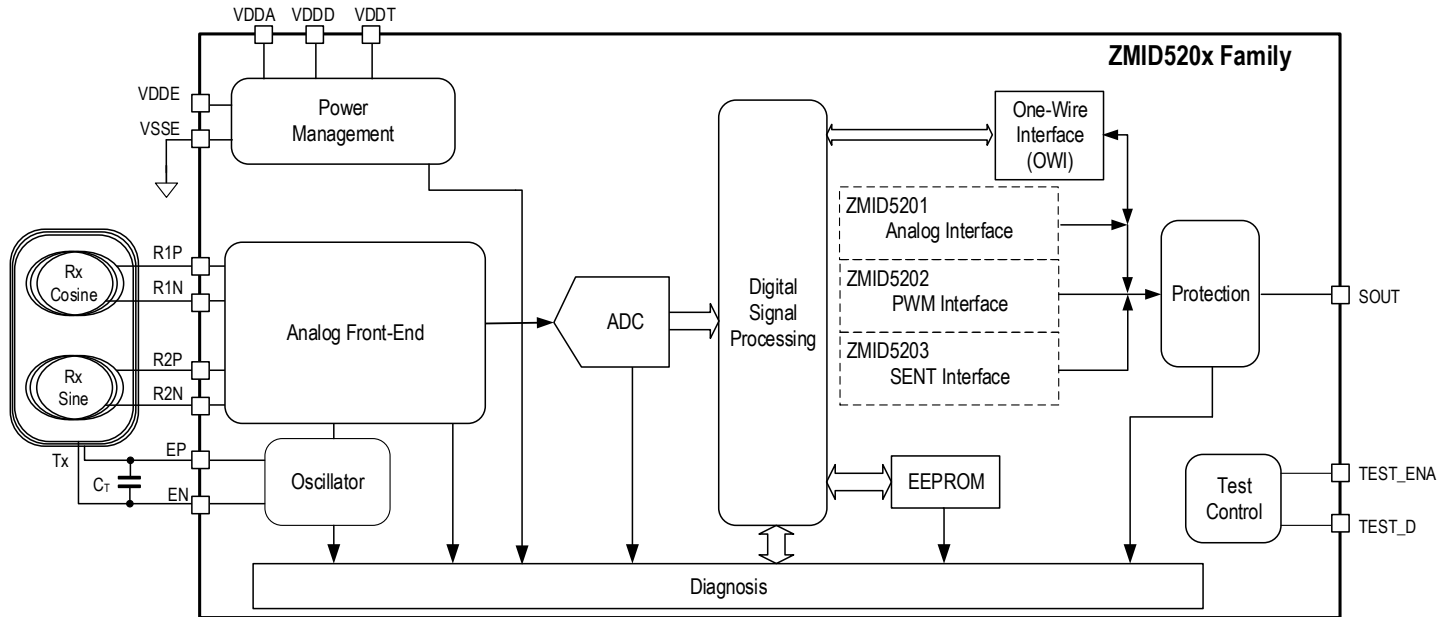
**Figure 3. Coil Design for a Linear Motion Sensor**



## 6.2 Block Diagram

Figure 4 shows the block diagram of the ZMID5201/02/03

**Figure 4. Block Diagram**



The main building blocks include the following:

- Power management: power-on-reset (POR) circuit, low drop-out (LDO) regulators for internal supplies.
- Oscillator: generation of the transmit coil signal.
- Analog front-end: demodulator and gain control for the receive signals.
- Analog-to-digital converter (ADC): conversion into digital domain.
- Digital signal processing: offset correction; conversion of sine and cosine signals into angle and magnitude; angle range adjustment; and linearization.
- EEPROM: nonvolatile storage of factory and user-programmable settings.
- One-wire interface (OWI): programming of the chip through the output pin.
- Interface options:
  - Analog output for ZMID5201
  - PWM output for ZMID5202
  - SENT output for ZMID5203
- Protection: overvoltage, reverse polarity, short circuit protection.
- Test control: factory testing; connect TEST\_D and TEST\_ENA pins as indicated in Table 1.

Note: For the LC tank circuit, the capacitor  $C_T$  should be placed as close as possible to the ZMID520x pins EP and EN to minimize the loop area between pins and capacitor(s).

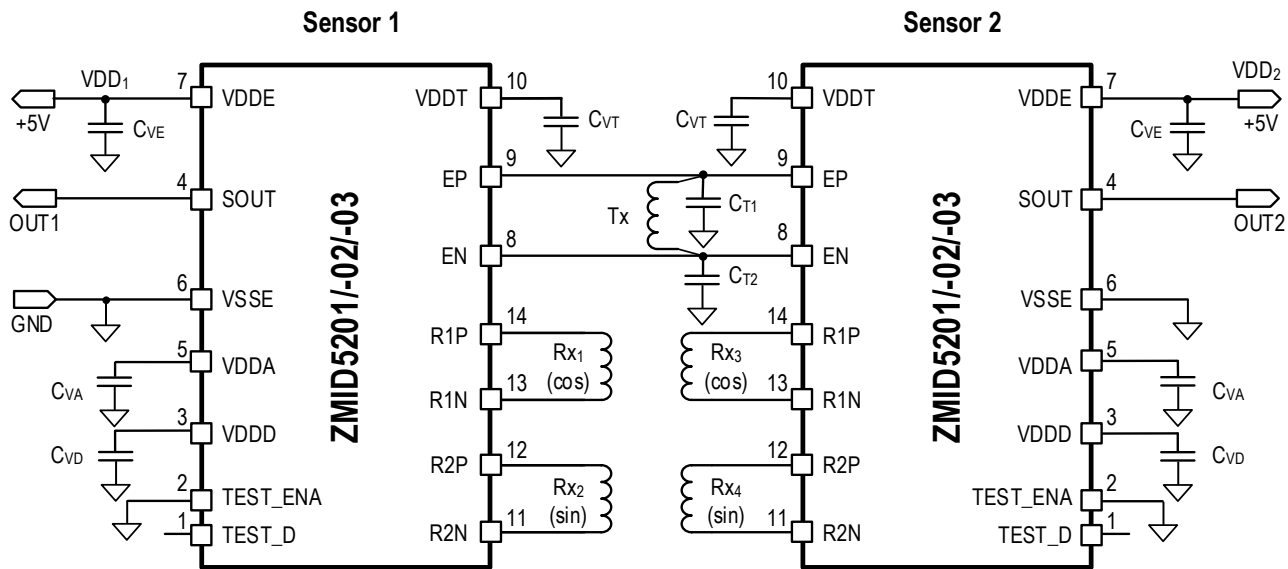
## 7. Redundant Connection

In applications requiring extended reliability, a redundant set-up is required. The ZMID5201/02/03 ICs also support this requirement by either having two identical but physically separated sensors or by interleaving the  $2 \times 2$  receiving coils and using one shared transmitter coil.

In Figure 5, two sensors share one common transmitter coil (Tx). Both sensors must share the same ground connection (GND) but could have separate positive supply connections ( $VDD_1$ ,  $VDD_2$ ). This setup is particularly useful for designs having limited coil space.

In normal operation, both chips drive the transmitter coil (Tx) and calculate the target's position through the receiving coil signals. If one chip fails to drive the transmitter coil, for example due to loss of supply, the host system can detect the failed part (loss of signal) while the second chip continues to drive the coil and maintains correct operation.

**Figure 5. Application Diagram, Dual Redundant Sensor with Shared Transmit Coil**



## 8. Protection and Diagnostics

### 8.1 I/O Protection

In order to meet the automotive requirements for overvoltage and reverse-polarity protection on both the output and power supply pins, the ZMID5201/02/03 ICs include several protection and diagnosis features:

1. Detection of broken power line, interrupted output signal, and broken ground connection on the receiving side
2. Protection against short circuit of output pin to VSSE, output pin to VDDE, and supply VDDE to VSSE
3. Overvoltage protection on supply pin VDDE
4. Overvoltage protection on output pin
5. Reverse-polarity protection on supply pin VDDE to VSSE
6. Reverse-polarity protection on output pin to VSSE
7. Reverse-polarity protection on output pin to VDDE

### 8.2 Diagnostics

The ZMID5201/02/03 monitors a number of features to accommodate ISO26262 diagnostic requirements. The monitored diagnostic features include the following:

1. Supply voltage too low or too high
2. Rx sine coil: open, short, short to ground, or short to Rx cosine coil
3. Rx sine coil: amplitude error or offset error
4. Rx cosine coil: open, short, short to ground, or short to Rx sine coil
5. Rx cosine coil: amplitude error or offset error
6. Tx coil: amplitude too low or open
7. Tx coil: frequency out of range
8. LC oscillator failure
9. CORDIC magnitude too high or too low
10. Missing target
11. Internal EEPROM failure
12. ADC signal processing overflow

### 8.3 Functional Safety

The ZMID5201/02/03 products are safety-related, intermediate hardware parts supporting ISO26262-compliant systems in regard to random failures, and, as such, they have been qualified according to ISO 26262:2012 Part 8, Clause 13 (Table 6).

Integration of ZMID5201/02/03 products into safety-related applications requires a safety analysis performed by the user.

Note: The *ZMID520x Functional Safety Manual* (FSM) is available on request (requires a non-disclosure agreement).

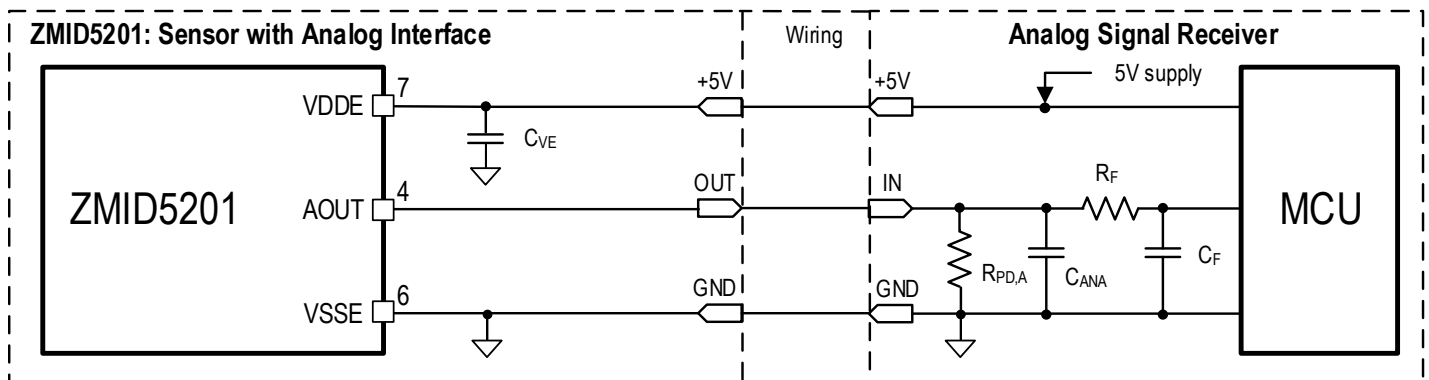
## 9. ZMID5201 Inductive Sensor with Analog Output

Typical interface circuits for the ZMID5201 are shown in Figure 6 and Figure 7.

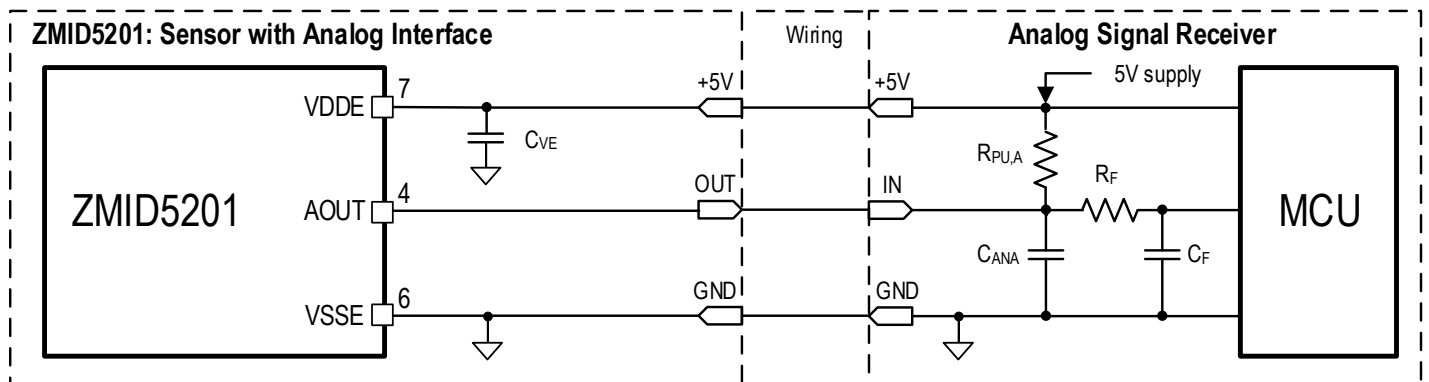
Note: The pull-up or pull-down resistors are not mandatory for normal operation. However, they are recommended for proper detection of broken ground or broken supply wires at the receiving side.

Note:  $R_F$ ,  $C_F$  = optional low pass filter. Values depend on user's application.

**Figure 6. External Components for ZMID5201 Analog Interface with Pull-Down Resistor**



**Figure 7. External Components for ZMID5201 Analog Interface with Pull-up Resistor**



**Table 6. ZMID5201 Analog Output Buffer Characteristics**

 Note: Refer to the VDDE pin description in Table 1 for the value of  $C_{VE}$ .

| Symbol        | Parameter                                | Conditions   | Minimum | Typical | Maximum | Units            |
|---------------|--|--|---------|---------|---------|------------------|
| Out_err       | Analog output error                      | Offset and nonlinearity error  | -6      |         | 6       | mV               |
| Step_large    | Output response, large step              | Step = 4.5V, $C_{ANA} = 10\text{nF}$ , $R_{PD,A} = 5\text{k}\Omega$ , 10% to 90% |         |         | 160     | $\mu\text{s}$    |
| $T_{UPD,ANA}$ | Analog output update rate (programmable) | Minimum oversampling rate  | 50.1    | 55.7    | 61.2    | $\mu\text{s}$    |
|               |  | Maximum oversampling rate  | 401     | 445.4   | 490     |                  |
| $C_{ANA}$     | Output capacitor for analog              |  | 0.47    |         | 27      | nF               |
| $RES_{ANA}$   | Analog output resolution                 |  |         |         | 10      | bits             |
| $R_{PU,A}$    | Output pull-up resistor                  |  | 3       | 4.7     | 10      | $\text{k}\Omega$ |
| $R_{PD,A}$    | Output pull down resistor                |  | 3       | 4.7     | 10      | $\text{k}\Omega$ |
|               | Normal operating range                   | Limits are programmable  | 5       |         | 95      | %VDDE            |
| Diag_high_ana | Diagnostic high for analog               |  | 96      |         |         | %VDDE            |
| Diag_low_ana  | Diagnostic low for analog                |  |         |         | 4       | %VDDE            |
| $V_{CL,L}$    | Clamping level, low <sup>[a]</sup>       | Programmable in 1% steps   | 5       |         | 68      | %VDDE            |
| $V_{CL,H}$    | Clamping level, high <sup>[a]</sup>      | Programmable in 1% steps   | 32      |         | 95      | %VDDE            |
| Current_limit | Output node short current                | Short to VDDE or VSSE  |         |         | 50      | mA               |

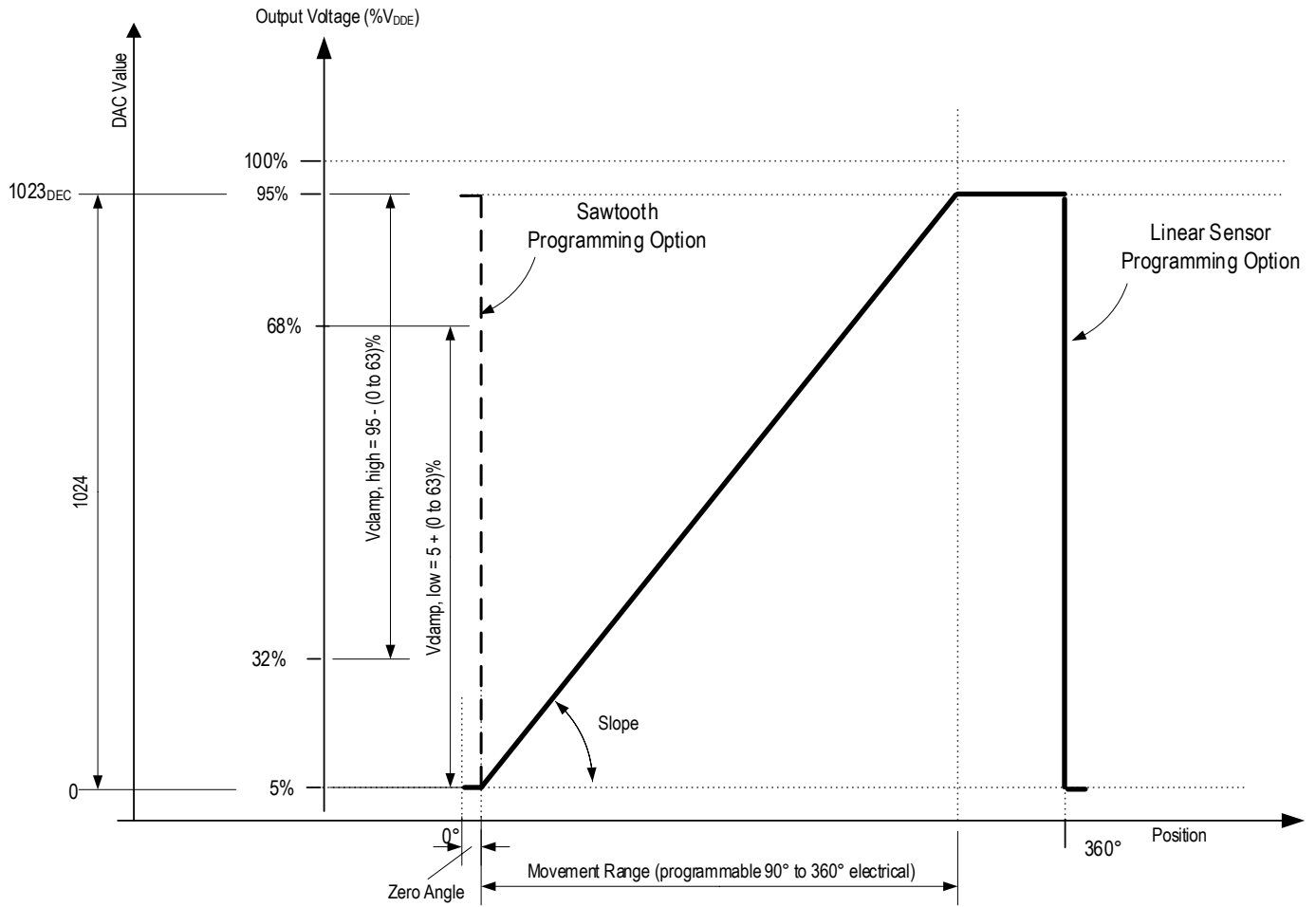
[a] Low clamping level must be programmed lower than the  $V_{CL,H}$  high clamping level.

For the ZMID5201, the 100% position range is mapped to a voltage range from 250mV to 4750mV. The stepping rate of the clamping parameters is 1% so that the analog voltage stepping rate is 47.5 mV/%. The diagnostic low level is  $\leq 200\text{mV}$  and the diagnostic high level is  $\geq 4800\text{mV}$ .

Note that the minimum and maximum output positions can be mapped to the mechanical range of the application by programming the zero angle offset, slope programming (linear vs. sawtooth), and clamping level register settings (refer to section 12 and Figure 8). For example, for a pedal sensor with ratiometric analog output (ZMID5201), having 20° mechanical degrees of movement range and clamping levels of 5% and 95%, the output value 0.25V (5% of VDDE) represents 0° mechanical degrees and the output value 4.75V (95% of VDDE) represents 20° mechanical degrees. Note that the slope can be programmed to either rising (as shown in Figure 8) or falling with increasing electrical angle.

**Figure 8. Example of ZMID5201 Analog Output Transfer Function and Programming Options**

Note: The following figure illustrates an example of 5% and 95% clamping levels and a rising slope setting.

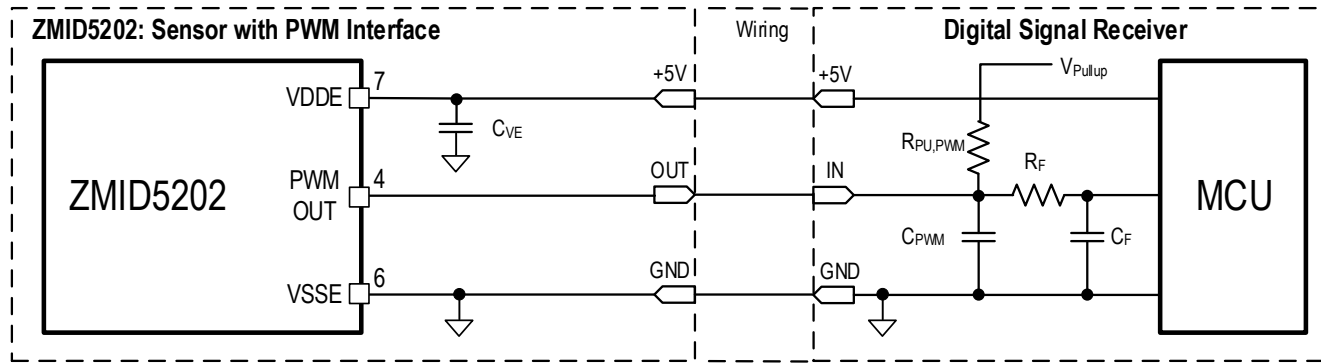


## 10. ZMID5202 Inductive Sensor with PWM Output

The typical interface circuit for the ZMID5202 is shown in Figure 9.

Note:  $R_F$ ,  $C_F$  = optional low pass filter. Values depend on user's application.

**Figure 9. External Components for ZMID5202 PWM Interface with Pull-Up Resistor**



**Table 7. ZMID5202 PWM Output Buffer Characteristics**

Note: Refer to VDDE pin in Table 1 for the value of  $C_{VE}$ .

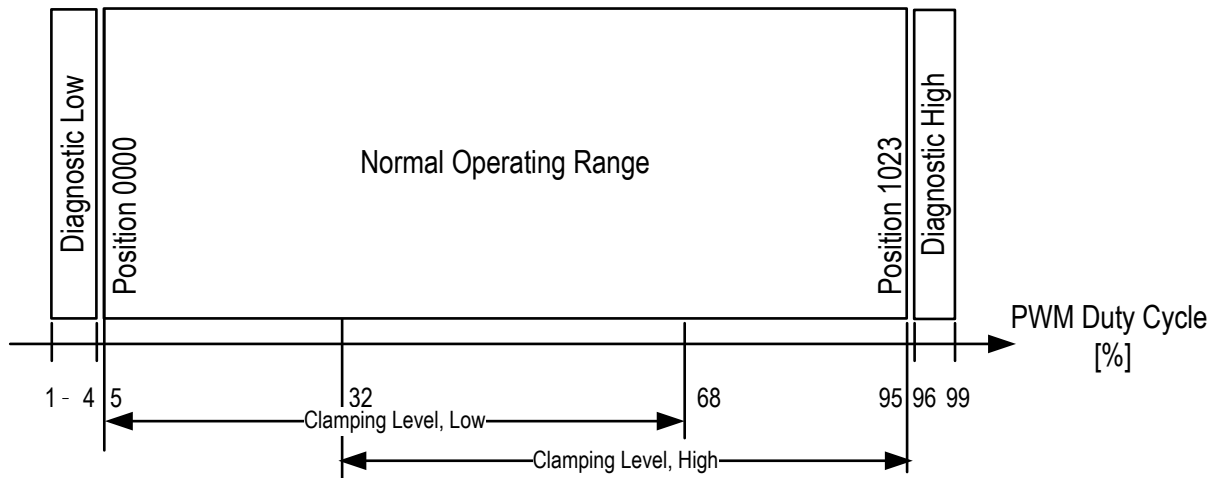
| Symbol          | Parameter                    | Conditions   | Minimum      | Typical   | Maximum      | Units           |
|-----------------|------------------------------|--|--------------|---|--------------|-----------------|
| $f_{PWM}$       | PWM output frequency         | User programmable  | Typical - 7% | 0.125<br>0.25<br>0.50<br>0.75<br>1.00<br>1.25<br>1.50<br>2.00 | Typical + 7% | kHz             |
| $t_{PWM\_FALL}$ | PWM fall time                | $C_{PWM}=4.7nF$ , $R_{PU,PWM}=1k\Omega$ ,<br>$V_{Pullup}=5V$ , 2 correction bits | 2.45         |   | 4.55         | $\mu s$         |
| $RES_{PWM}$     | PWM resolution               |  |              |   | 10           | bits            |
| $V_{Pullup}$    | PWM output voltage (pull-up) |  |              |   | 16           | V               |
| $V_{OL\_PWM}$   | PWM output LOW level         | $V_{Pullup}=5V$ to $V_{Pullup}=16V$  |              |   | 10           | $\%V_{Pullup}$  |
| $V_{OH\_PWM}$   | PWM output HIGH level        | $V_{Pullup}=5V$ to $V_{Pullup}=16V$  | 90           |   |              | $\%V_{Pullup}$  |
| $R_{PU,PWM}$    | Pullup resistor for PWM      | $V_{Pullup}=5V$  | 1            |   | 10           | k $\Omega$      |
|                 |                              | $V_{Pullup}=16V$   | 3            |   | 10           |                 |
| $C_{PWM}$       | Output capacitor for PWM     |  | 1            | 4.7   | 20           | nF              |
|                 | Normal operating range       | Limits are programmable  | 5            |   | 95           | $\%$ duty cycle |

| Symbol            | Parameter                           | Conditions               | Minimum | Typical | Maximum | Units        |
|-------------------|-------------------------------------|--------------------------|---------|---------|---------|--------------|
| Diag_high_PWM     | Diagnostic high for PWM             |                          | 96      | 97.5    |         | % duty cycle |
| Diag_low_PWM      | Diagnostic low for PWM              |                          |         | 2.5     | 4       | % duty cycle |
| D <sub>CL_L</sub> | Clamping level, low <sup>[a]</sup>  | Programmable in 1% steps | 5       |         | 68      | % duty cycle |
| D <sub>CL_H</sub> | Clamping level, high <sup>[a]</sup> | Programmable in 1% steps | 32      |         | 95      | % duty cycle |

[a] Low clamping level must be programmed lower than the D<sub>CL\_H</sub> high clamping level.

The 100% position range is mapped to a duty cycle of 5% to 95%. A clamping step of 1% is mapped to a duty cycle change of 0.9%. The diagnostic low level is mapped to a 2.5% (typical) duty cycle; the diagnostic high level is mapped to a 97.5% (typical) duty cycle.

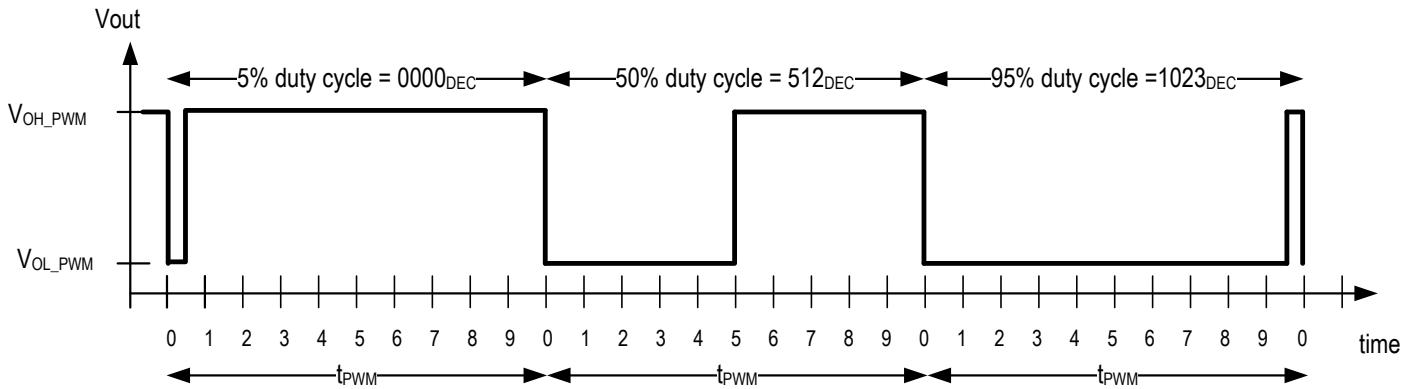
**Figure 10. PWM Signal Range**



The graph in Figure 11 shows examples of different PWM signals with 5%, 50%, and 95% duty cycle, representing the minimum, 50%, and maximum output values.

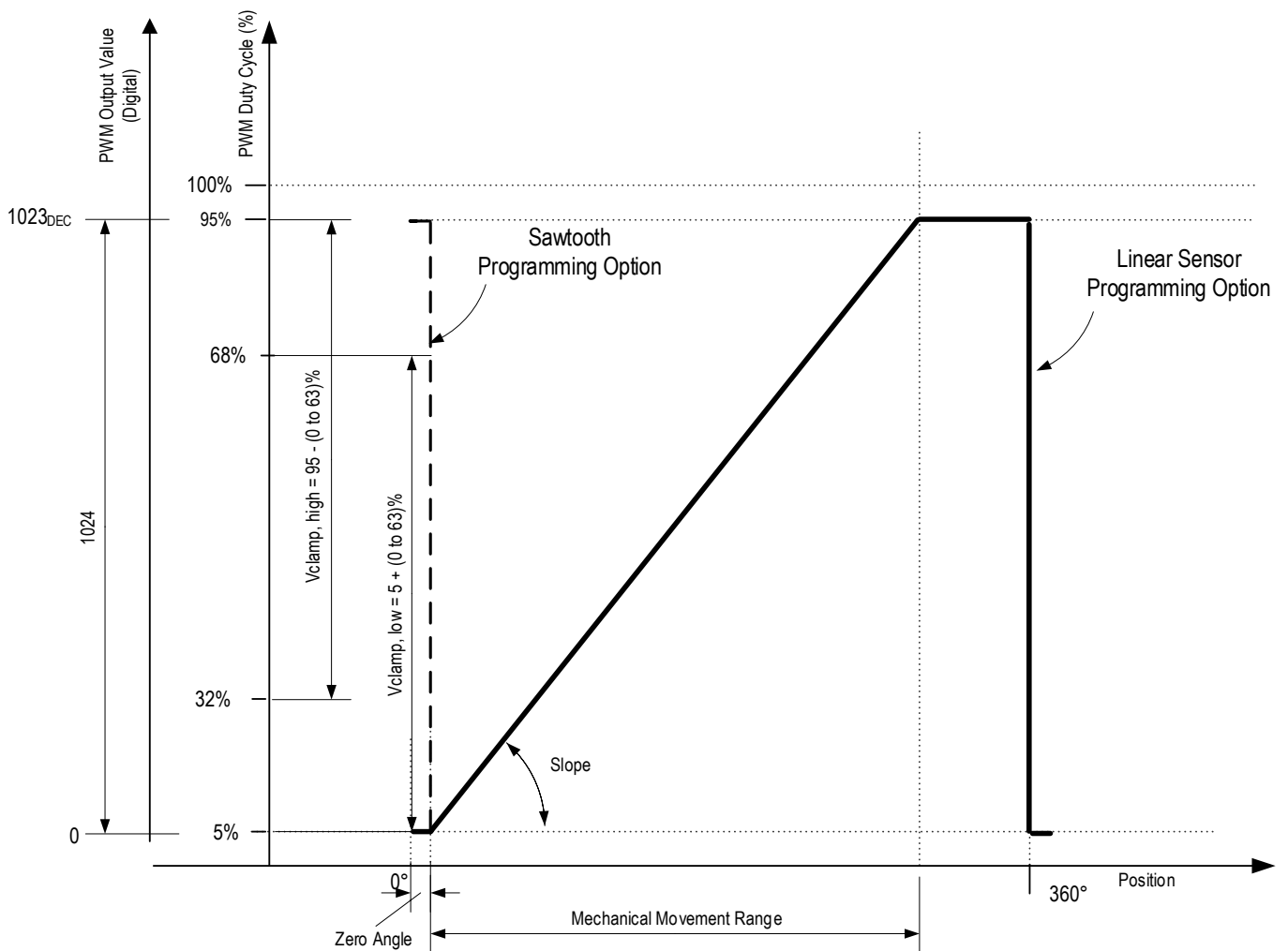
Note that the minimum and maximum output positions can be mapped to the mechanical range of the application by programming the zero angle offset, slope programming (linear or sawtooth), and clamping level (minimum/maximum duty cycle) register settings (see section 12 and Figure 12). For example, for a pedal sensor with PWM output (ZMID5202), having 20° mechanical degrees of movement range and clamping levels of 5% and 95%, the output value 0 represents 0° mechanical degrees and the output value 1023<sub>DEC</sub> represents 20° mechanical degrees. Note that the slope can be programmed to either rising (as shown in Figure 12) or falling with increasing electrical angle.

**Figure 11. Example of PWM Output Signal**



**Figure 12. Example of ZMID5202 PWM Output Transfer Function and Programming Options**

Note: The following figure illustrates an example of 5% and 95% clamping levels and a rising slope setting.

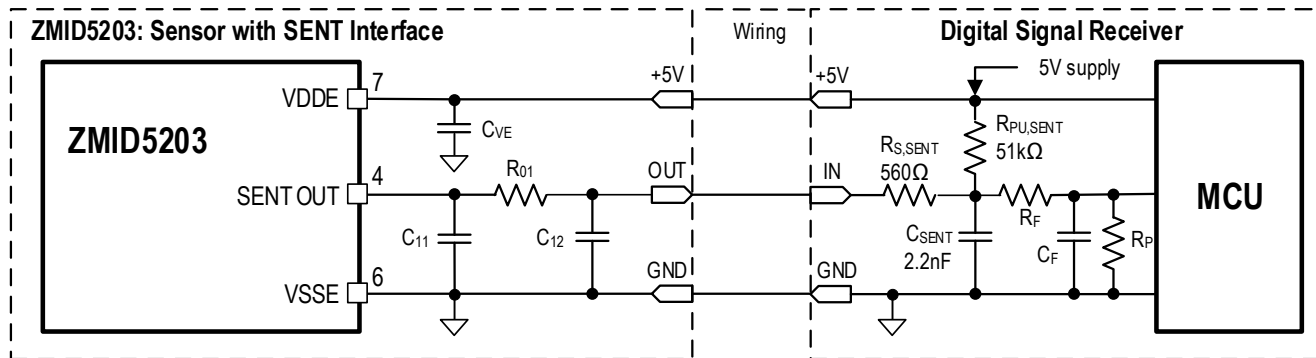


## 11. ZMID5203 Inductive Sensor with SENT Output

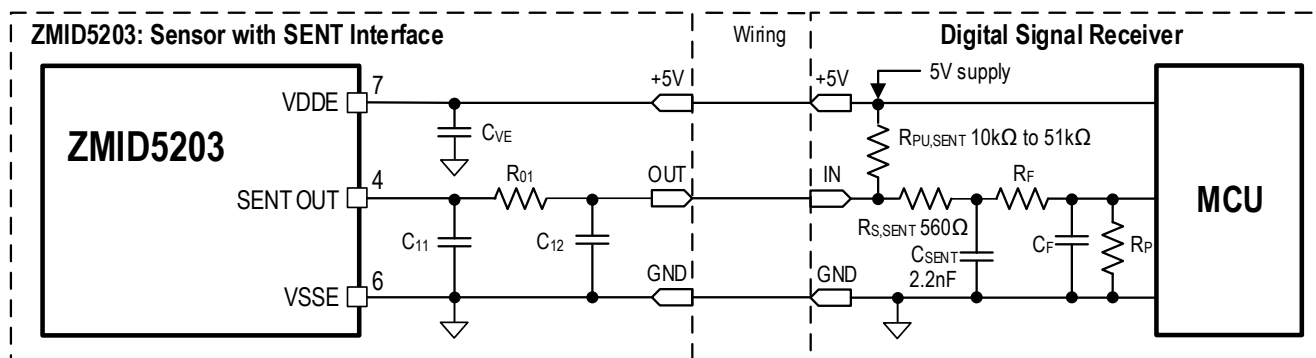
Three options for the typical interface circuit for the ZMID5203 are shown in Figure 13, Figure 14, and Figure 15.

Note:  $R_F$ ,  $C_F$  and  $R_P$  = optional low pass filter for the SENT interface. Values depend on user's application.

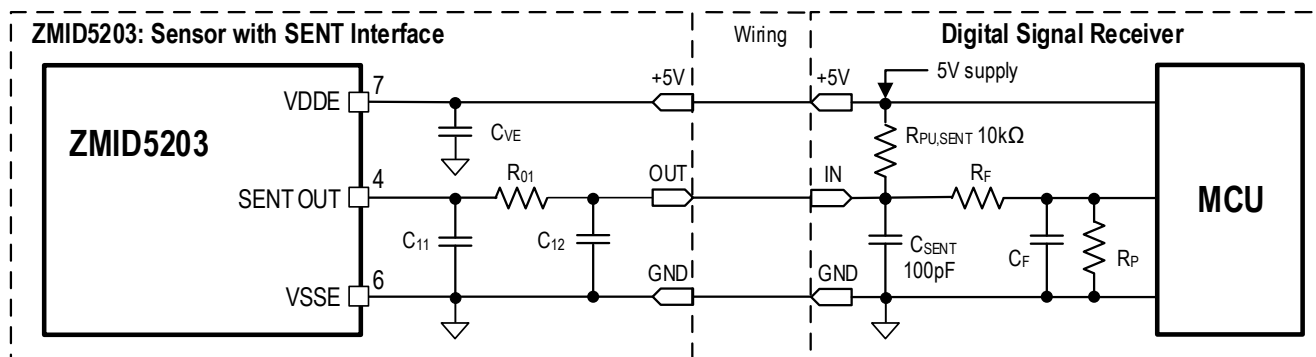
**Figure 13. External Components for ZMID5203 SENT Interface, Option A**



**Figure 14. External Components for ZMID5203 SENT Interface, Option B**



**Figure 15. External Components for ZMID5203 SENT Interface, Option C**



**Table 8. ZMID5203 SENT Output Buffer Characteristics**

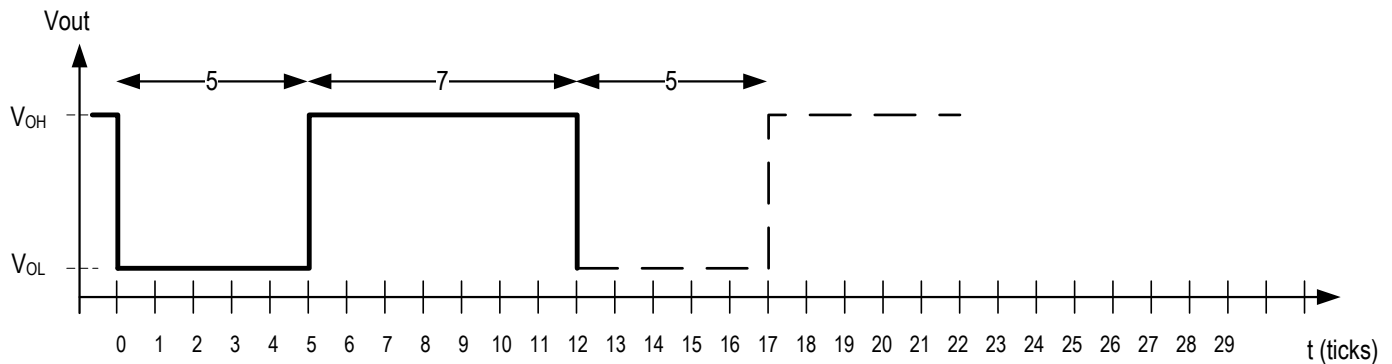
 Note: Refer to VDDE pin in Table 1 for the value of  $C_{VE}$ .

| Symbol                   | Parameter                                   | Conditions                                   | Minimum | Typical | Maximum | Units |
|--------------------------|---|--|---------|---------|---------|-------|
| RES <sub>SENT</sub>      | SENT output resolution                      |  |         |         | 12      | bits  |
| t <sub>STABLE_HIGH</sub> | SENT HIGH stabilization time                | HIGH level at 3.8V                           | 6       |         |         | μs    |
| V <sub>OL</sub>          | Output LOW level                            |  |         |         | 0.5     | V     |
| V <sub>OH</sub>          | Output HIGH level                           |  | 4.1     |         |         | V     |
| R <sub>O1</sub>          | SENT output pi (π) filter resistor          | For application circuits options A,B, and C  |         | 120     |         | Ω     |
| C <sub>11</sub>          | SENT output pi (π) filter first capacitor   | For application circuits options A, B, and C |         | 2.2     |         | nF    |
| t <sub>TICK</sub>        | Clock tick time                             |  | 3.0     | 3.36    | 3.67    | μs    |
| C <sub>12</sub>          | SENT output pi (π) filter, second capacitor | For application circuit option C             |         | 3.9     |         | nF    |
|                          |   | For application circuits options A and B     |         | 2.2     |         | nF    |

## 11.1 SENT Protocol

The SENT (Single Edge Nibble Transmission) protocol conforms to SAE J2716, Revision 2. In addition, SENT Pause and CRC can be programmed according to SAE J2716, Revision 3.

For transmitting a nibble with the 0 value, 12 clock ticks are required: a fixed LOW period of 5 ticks followed by a HIGH period of 7 ticks. One tick equals t<sub>TICK</sub> = 3.0μs to 3.67μs (see Table 8).

**Table 9. SENT Nibble Output for Value = 0<sub>DEC</sub>**


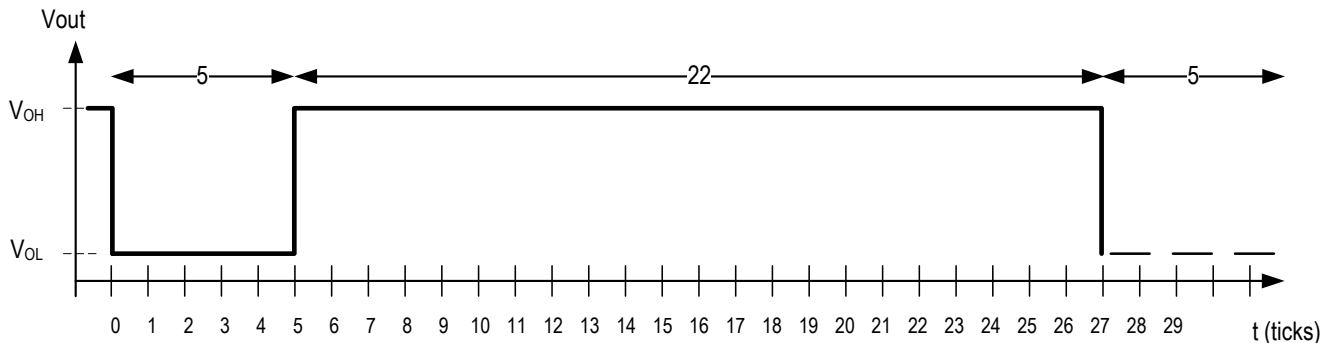
For transmitting a nibble with the value 15<sub>DEC</sub> (1111<sub>BIN</sub>, F<sub>HEX</sub>), 27 clock ticks are required: a fixed LOW period of 5 ticks followed by a HIGH period of 22 ticks. The total time for one nibble can be calculated as with the following equation:

$$t_{NIBBLE} = t_{TICK} * (12 + x)$$

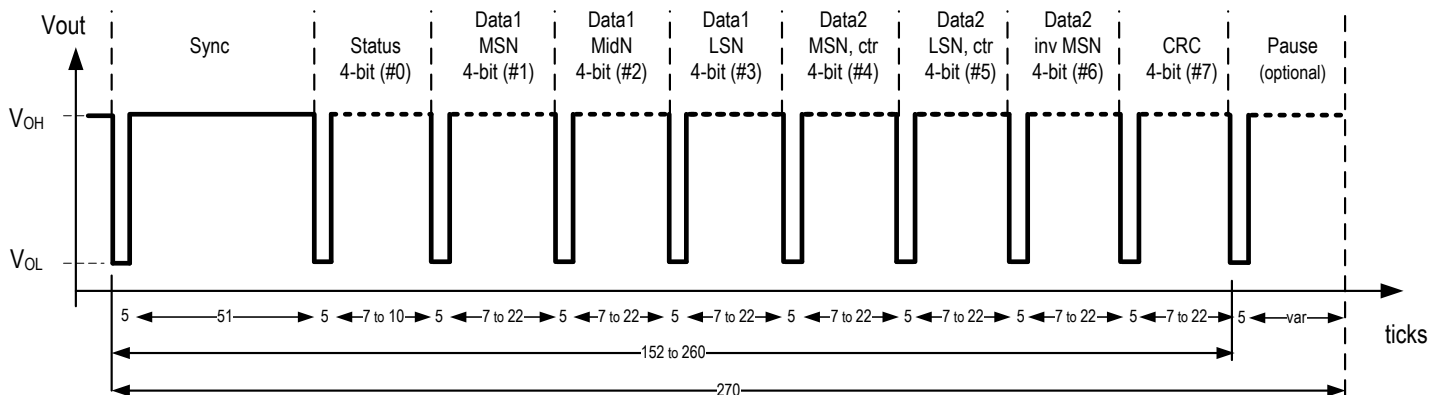
Where x = the nibble decimal value = 0 to 15.

**Table 10. SENT Tick Length**

| Decimal         | 0  | 1  | 2  | 3  | 4  | 5  | 6  | 7  | 8  | 9  | 10 | 11 | 12 | 13 | 14 | 15 |
|-----------------|----|----|----|----|----|----|----|----|----|----|----|----|----|----|----|----|
| Hexadecimal     | 0  | 1  | 2  | 3  | 4  | 5  | 6  | 7  | 8  | 9  | A  | B  | C  | D  | E  | F  |
| Number of Ticks | 12 | 13 | 14 | 15 | 16 | 17 | 18 | 19 | 20 | 21 | 22 | 23 | 24 | 25 | 26 | 27 |

**Figure 16. SENT Nibble Output for Value = 15<sub>DEC</sub>**

**Figure 17. SENT Frame**

The SENT protocol frame consists of a fixed-length synch pulse (LOW period of 5 ticks followed by a HIGH period of 51 ticks), followed by a status nibble, 6 data nibbles, and a CRC nibble. An optional pause pulse can be programmed to adjust the SENT frame to a fixed length of 270 ticks.



Note that the status nibble has a maximum length of only  $5 + 10 = 15$  ticks since bits 2 and 3 are always zero:

Status nibble:  $0000_{\text{BIN}}$  = Normal operation  
 $0011_{\text{BIN}}$  = Diagnostic state

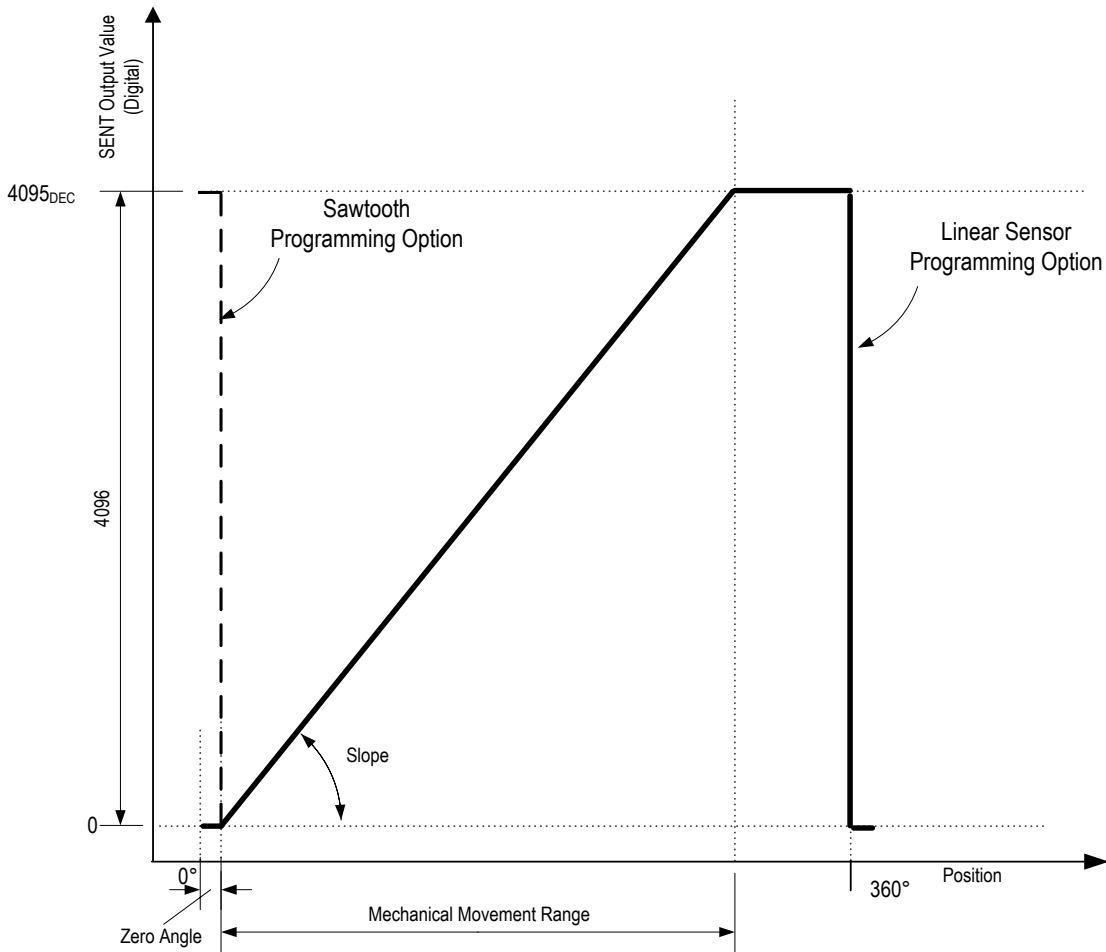
The SENT output frame format can be programmed in one of two options:

- 12-bit position data + 8-bit rolling counter ("ctr" in Figure 17) + inverted copy of Data1 MSN (nibble #1 in Figure 17) + cyclic redundancy check (CRC). In this option, the SENT frame length is between 152 and 260 ticks with a variable frame length and 270 ticks with a fixed frame length.
- 12-bit position data + "000" data + CRC. In this option, if the pause pulse is disabled, the SENT frame has the shortest possible length: less than 220 ticks.

Note that the minimum and maximum output positions can be mapped to the mechanical range of the application by programming the zero angle offset and slope register settings (see section 12 and Figure 18). For example for a pedal sensor with SENT output (ZMID5203) with 20° mechanical degrees of movement range, the output value 0 represents 0° mechanical degrees and the output value 4095<sub>DEC</sub> represents 20° mechanical degrees. Note that the slope can be programmed to either rising (as shown in Figure 18) or falling with increasing electrical angle.

**Figure 18. Example of ZMID5203 Output Transfer Function and Programming Options**

Note: The following figure illustrates an example using the rising slope setting.



## 12. Programming Options

The ZMID520x family offers a variety of programming options. The IC is programmed through the output pin via a proprietary bi-directional one-wire interface (OWI). For programming, no additional wires or programming voltage is required, so the IC can be fully programmed in the field. Note: A full description of the IDT one-wire interface protocol and a detailed memory map are available on request. The main programming functions are described in Table 11.

**Table 11. Programming Options Overview**

| Function                   | Products | Programming Option  | Notes  |
|----------------------------|----------|---|--|
| Coil input                 | All      | Reverse coil polarity (increasing or decreasing output relative to target movement) | Invert coils to change the direction of the output values  |
| Input amplifier            | All      | Offset of sine and cosine channels  | Offset correction before CORDIC angle calculation  |
| Slope of transfer function | All      | Steepness of slope, rising/falling  | Adjustment of angle range  |
| Zero position              | All      | Zero angle  | To match mechanical zero position with electrical zero position  |
| Linearization              | All      | 9-point linearization   | To increase accuracy and compensate for imperfections in coil design   |
| Transmit coil              | All      | Coil driver current and amplitude   | To optimize Tx oscillator  |
| Output mode                | All      | Linear or sawtooth  | Single or multiple ramps   |
| Clamp low, clamp high      | ZMID5201 | Minimum, maximum output voltage   | Define normal operating range  |
|                            | ZMID5202 | Minimum, maximum PWM duty cycle   | Define normal operating range  |
| Diagnostic levels          | ZMID5201 | Output voltage in diagnostic mode   | To indicate diagnostic alarm   |
|                            | ZMID5202 | PWM duty cycle in diagnostic mode   | To indicate diagnostic alarm   |
| PWM fall time              | ZMID5202 | PWM output signal slew rate   | To optimize EMC performance  |
| PWM base frequency         | ZMID5202 | PWM frequency   | Base frequency of PWM signal   |
| SENT CRC                   | ZMID5203 | CRC according to SAE J2716, Rev.2 or Rev.3  | Implementation of CRC calculation  |
| SENT Pause                 | ZMID5203 | Optional pause setting according to SAE J2716, Revision 2 or Revision 3             | Revision 2: No pause pulse<br>Revision 3: Fixed frame length + pause   |
| SENT Frame                 | ZMID5203 | Type of data transmitted in SENT frame  | 12-bit position data + 8-bit rolling counter + inverted copy of first data nibble + CRC (see Figure 17)<br>12-bit position data + "000" data + CRC |
| Diagnostics                | All      | CORDIC magnitude upper and lower levels   | To trigger alarm if CORDIC magnitude is out of range   |
|                            |          | Transmit coil frequency alarm   | Detects out of range Tx frequency  |
|                            |          | Automatic gain control (AGC)  | Detects AGC out of range   |
|                            |          | EEPROM double error; shadow register parity error                                   | Internal memory errors   |
|                            |          | R1 or R2 coil open or short   | Detect defective receiver coils  |
|                            |          | Signal processing overflow  | Internal processing errors   |

### 13. Operation at High Rotation Speeds

The ZMID520x ICs are primarily designed for low-speed or static operation due to their inherent interface types (analog ramp, PWM, SENT). There is no upper speed limit for using the ZMID520x in high speed applications; however, due to the maximum data rate at the various outputs, the resolution (on a rotary application: number of measurements per revolution) will be reduced with increasing speed.

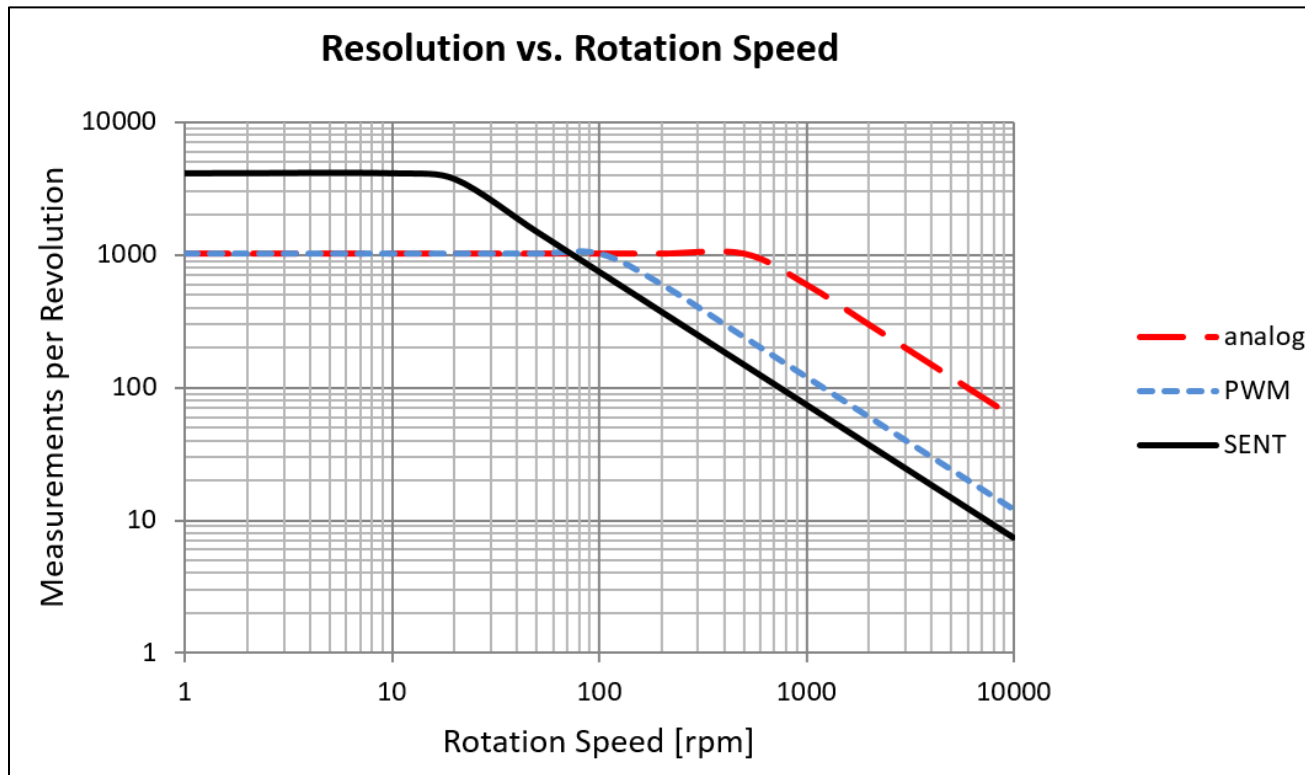
The maximum output data rates for the various versions are given in Table 12.

**Table 12. Maximum Output Data Rate**

| Product  | Type of Output | Maximum Output Rate, Updates per Second | Notes                             |
|----------|----------------|---|-----------------------------------|
| ZMID5201 | Analog ramp    | 10000                                   | Linear analog ramp                |
| ZMID5202 | PWM            | 2000                                    | Programmable from 125Hz to 2000Hz |
| ZMID5203 | SENT           | 1235                                    | 270 ticks at 3μS                  |

With these maximum output data rates, the resolution versus rotation speed relationship is shown in the graph in Figure 19.

**Figure 19. Relationship between Resolution and Rotational Speed**



For example, the number of readings per revolution at 10rpm and 1000rpm are given in Table 13.

**Table 13. Resolution at Different Rotation Speeds**

| Product  | Type of Output | Readings per Revolution at 10rpm | Readings per Revolution at 1000rpm |
|----------|----------------|----------------------------------|------------------------------------|
| ZMID5201 | Analog ramp    | 1024 (10-bit)                    | 600 (9.2-bit)                      |
| ZMID5202 | PWM            | 1024 (10-bit)                    | 120 (6.9-bit)                      |
| ZMID5203 | SENT           | 4096 (12-bit)                    | 74 (6.2-bit)                       |

## 14. Interpolation, Linearity Error Correction

A post-CORDIC linearity correction is available to correct nonlinearities and to further increase the overall accuracy of the system.

The correction factors are applied by linear interpolation between 9 equidistant points over one phase (0 to 360°) with one of two options:

- Option 1: Starting at 0° with intervals of 45°
- Option 2: Same as option1 shifted by 22.5°, starting at 22.5° with intervals of 45°

**Table 14. Linearity Correction Points**

| Point    | 1     | 2     | 3      | 4      | 5      | 6      | 7      | 8      | 9              |
|----------|-------|-------|--------|--------|--------|--------|--------|--------|----------------|
| Option 1 | 0°    | 45°   | 90°    | 135°   | 180°   | 225°   | 270°   | 315°   | 360°           |
| Option 2 | 22.5° | 67.5° | 112.5° | 157.5° | 202.5° | 247.5° | 292.5° | 337.5° | 382.5° (22.5°) |

Note that in a rotating application, correction point 1 (0°) and point 9 (360°) coincide at the same angle. Therefore in such cases, it is useful to use the same correction values for both point 1 and point 9.

In general, the correction points are applicable as follows:

Correction point 1 is used for angles  $0^\circ \leq \alpha < 45^\circ$  and optionally for  $22.5^\circ \leq \alpha < 67.5^\circ$ .

(...)

Correction point 9 is used for angles  $315^\circ \leq \alpha < (360^\circ = 0^\circ)$  and optionally for  $337.5^\circ \leq \alpha < 22.5^\circ$ .

For each point, an offset can be applied. Angle values between two points are corrected by linear interpolation between the two linearization points.

## 15. Application Examples

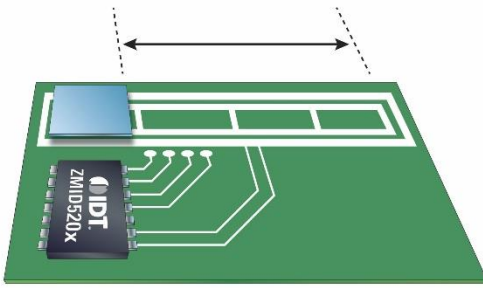
Typical coil and target arrangements are shown in Figure 20 to Figure 25: linear motion; arc motion; and on-axis (end of shaft) and off-axis (side shaft) rotary. Many other arrangements are also possible. In the figures, blue indicates the target and the dashed lines indicate range of travel. See Table 15 for resolution values.

Note: The coils are shown in a simplified form. Detailed guidelines on coil design and programming options are available on request from IDT application support. Note that within each base configuration, the movement range can be further fine-trimmed by user programming.

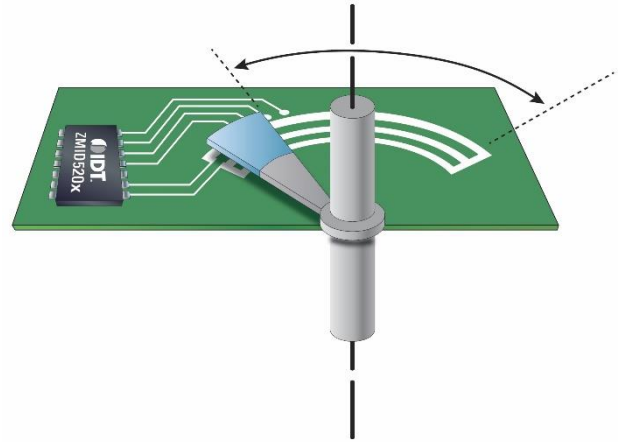
Examples:

- An angle sensor for 0 to 270° angle range would use a 360° base configuration ( $360^\circ/1$ ) and could then be trimmed to a maximum angle of 270° by user programming.
- An angle sensor for 0 to 110° angle range would use a 120° configuration ( $360^\circ/3$ ) and could then be trimmed to a maximum angle of 110° by user programming.

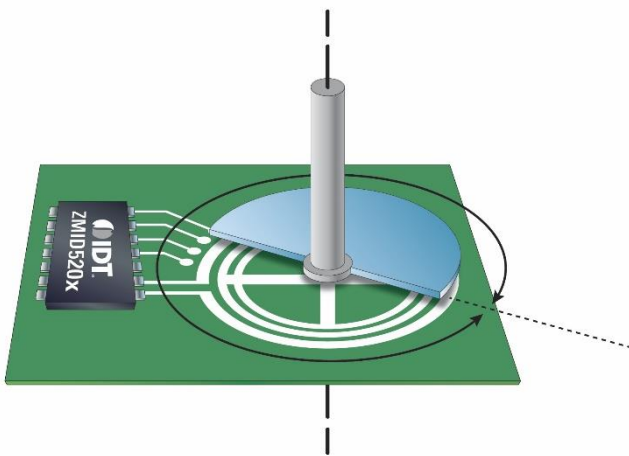
**Figure 20. Example Setup: Linear Motion**



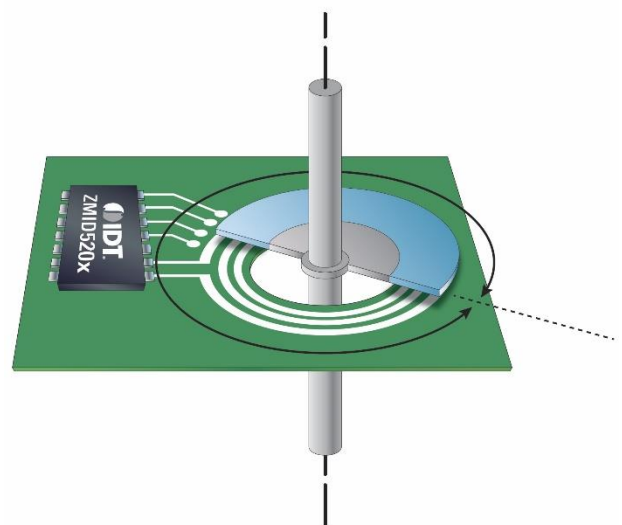
**Figure 21. Example Setup: Arc Motion**

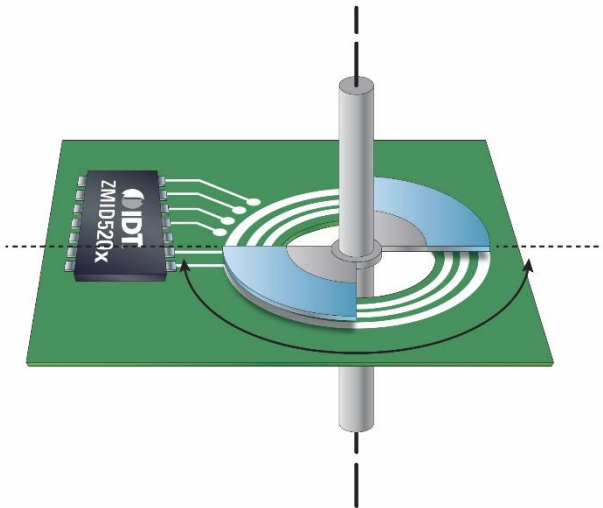
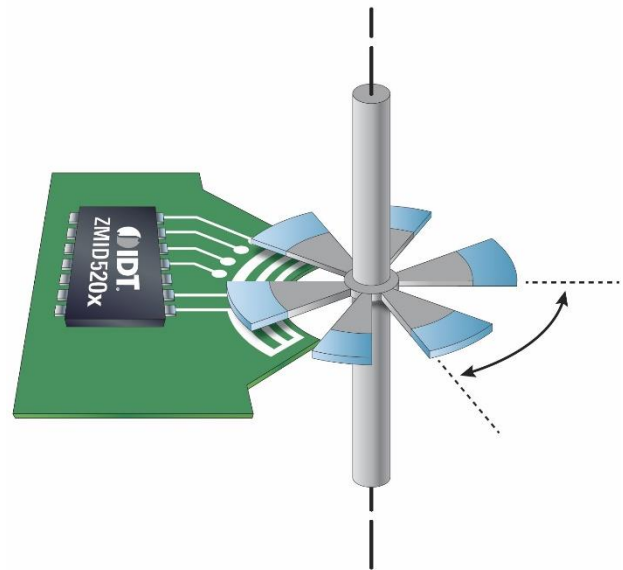


**Figure 22. Example Setup: End-of-Shaft Rotation, On-Axis, 1 × 360°**



**Figure 23. Example Setup: Side-Shaft Rotation, Off-Axis, 1 × 360°**



**Figure 24. Example Setup: Side-Shaft Rotation, Off-Axis, 2 × 180°**

**Figure 25. Example Setup: Side-Shaft Rotation, Off-Axis, 6 × 60°**


The different coil and target arrangements provide different ranges for the degrees measurement, which affects the measurement resolution (degrees per step). This varies depending on the ZMID520x product. Table 15 gives examples of resolution for various ranges of motion for each product.

**Table 15. Examples of Resolution Differences Depending on Product**

| Range of Travel for Example Application   | Resolution of Measurement                   |                                    |
|---|---|------------------------------------|
|   | ZMID5201/ZMID5202<br>(1024 steps per phase) | ZMID5203<br>(4096 steps per phase) |
| Linear Position Sensing Range of Travel =<br>Coil Length Minus Target Length<br>(See the example in Figure 20)                  | (Range of Travel)/1024                      | (Range of Travel)/4096             |
| Arc Position Sensing Range of Travel =<br>Coil Arc Angle Minus Target Angle (Width of Target)<br>(See the example in Figure 21) | (Range of Travel)/1024                      | (Range of Travel)/4096             |
| Arc Position Sensing Range of Travel = 1 × 130°<br>(The ZMID520xMARC13001 kits provide examples; see section 18)                | 130°/1024 = 0.127°                          | 130°/4096 = 0.0317°                |
| 1 × 360° (See the examples in Figure 22 and Figure 23)  | 0.35°/Step                                  | 0.088°/Step                        |
| 2 × 180° (See the example in Figure 24)   | 0.18°/Step                                  | 0.044°/Step                        |
| 6 × 60° (See the example in Figure 25)  | 0.059°/Step                                 | 0.015°/Step                        |

## 16. Package Outline Drawings

The package outline drawings are appended at the end of this document and are accessible from the link below. The package information is the most current data available and is subject to change without notice or revision of this document.

[www.idt.com/document/psc/14-tssop-package-outline-drawing-44mm-body-065mm-pitch-pgg14t1](http://www.idt.com/document/psc/14-tssop-package-outline-drawing-44mm-body-065mm-pitch-pgg14t1)

## 17. Marking Diagram



- Line 1: First four characters of part code (ZMID)
- Line 2: Next four characters of the part code (5201, 5202, or 5203) followed by
  - A = Design revision
  - E = Operation temperature range, extended automotive
- Line 3: "XXXXXX" = Lot number
- Line 4: "YYWW" = Manufacturing date:
  - YY = last two digits of manufacturing year
  - WW = manufacturing week

## 18. Ordering Information

| Orderable Part Number  | Description and Package  | MSL Rating | Shipping Packaging | Temperature    |
|--|--|------------|--------------------|----------------|
| ZMID5201AE1R   | ZMID5201; Analog Output; 14-TSSOP  | 1          | Reel               | -40° to +150°C |
| ZMID5202AE1R   | ZMID5202; PWM Output; 14-TSSOP   | 1          | Reel               | -40° to +150°C |
| ZMID5203AE1R   | ZMID5203; SENT Output; 14-TSSOP  | 1          | Reel               | -40° to +150°C |
| Note: For communication and programming, the ZMID520x Application Modules listed below require a ZMID-COMBOARD, which is available separately. The ZMID-COMBOARD can connect to two Application Modules simultaneously if the modules are the same type. |  |            |                    |                |
| ZMID-COMBOARD  | USB Communication and Programming Interface for ZMID Inductive Application Modules, Micro-USB Cable. Further information, user manual, and software download, visit <a href="http://www.IDT.com/ZMID-COMBOARD">www.IDT.com/ZMID-COMBOARD</a> .   |            |                    |                |
| ZMID5201MARC13001  | Inductive Arc Application Module with 130° Measurement Range and Analog Output including Arc Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5201MARC">www.IDT.com/ZMID5201MARC</a> .       |            |                    |                |
| ZMID5202MARC13001  | Inductive Arc Application Module with 130° Measurement Range and PWM Output including Arc Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5202MARC">www.IDT.com/ZMID5202MARC</a> .          |            |                    |                |
| ZMID5203MARC13001  | Inductive Arc Application Module with 130° Measurement Range and SENT Output including Arc Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5203MARC">www.IDT.com/ZMID5203MARC</a> .         |            |                    |                |
| ZMID5201MLIN01201  | Linear Inductive Application Module with 12mm Measurement Range and Analog Output including the Linear Application Module Sensor PCB, Sensor Target, Target Holder, Knob, and Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5201MLIN">www.IDT.com/ZMID5201MLIN</a> .        |            |                    |                |
| ZMID5202MLIN01201  | Linear Inductive Application Module with 12mm Measurement Range and PWM Output including the Linear Application Module Sensor PCB, Sensor Target, Target Holder, Knob, and Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5202MLIN">www.IDT.com/ZMID5202MLIN</a> .           |            |                    |                |
| ZMID5203MLIN01201  | Linear Inductive Application Module with 12mm Measurement Range and SENT Output including the Linear Application Module Sensor PCB, Sensor Target, Target Holder, Knob, and Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5203MLIN">www.IDT.com/ZMID5203MLIN</a> .          |            |                    |                |
| ZMID5201MROT36001  | Inductive Rotary Application Module with 360° Measurement Range and Analog Output including Rotary Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5201MROT">www.IDT.com/ZMID5201MROT</a> . |            |                    |                |
| ZMID5202MROT36001  | Inductive Rotary Application Module with 360° Measurement Range and PWM Output including Rotary Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5202MROT">www.IDT.com/ZMID5202MROT</a> .    |            |                    |                |
| ZMID5203MROT36001  | Inductive Rotary Application Module with 360° Measurement Range and SENT Output including Rotary Application Module Sensor PCB, Sensor Target, Target Holder, Rotation Axis, Knob, Module Connection Cable. For further information, kit manual, and software download, visit <a href="http://www.IDT.com/ZMID5203MROT">www.IDT.com/ZMID5203MROT</a> .   |            |                    |                |

## 19. Revision History

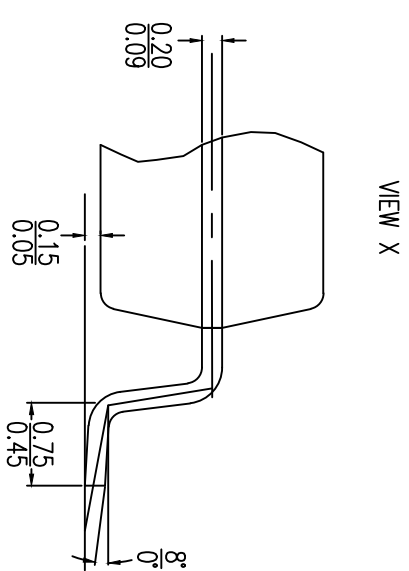
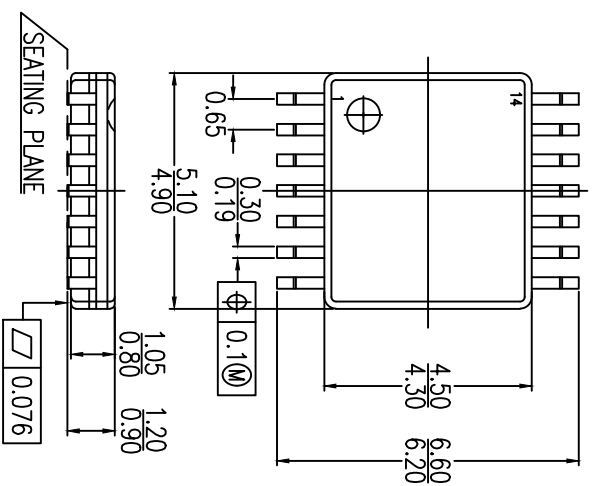
| Revision Date     | Description of Change   |
|-------------------|---|
| October 5, 2018   | <ul style="list-style-type: none"> <li>▪ Update for part order table to remove part codes ending in AE1T. Product is no longer offered in tubes.</li> <li>▪ Correction of specifications for resolution. Values have been changed from “Minimum” to “Maximum” designation.</li> <li>▪ Minor edits.</li> </ul>   |
| June 22, 2018     | <ul style="list-style-type: none"> <li>▪ Revision of the absolute maximum <math>V_{VDDT}</math> specification in Table 2.</li> <li>▪ Revision of the electrical characteristic <math>V_{VDDT}</math> specification in Table 4.</li> <li>▪ Addition of the VDDT temperature coefficient specification in Table 4.</li> </ul>   |
| May 28, 2018      | <ul style="list-style-type: none"> <li>▪ Revision of ASIL text on page 1 and in section 8.3.</li> <li>▪ Addition of <math>V_{VDD}</math> and <math>V_{VDDA}</math> specifications in Table 4.</li> <li>▪ Revision of <math>V_{VDDT}</math> specification in Table 4.</li> <li>▪ Minor edits.</li> </ul>   |
| March 5, 2018     | <ul style="list-style-type: none"> <li>▪ Revision for section 16. The package outline drawings have been updated and are now appended at the end of the document.</li> <li>▪ Addition of example for arc position sensing with a 130° travel range to Table 15.</li> <li>▪ Revision of Figure 4 and Table 1 for the name for the external capacitance.</li> <li>▪ Addition of recommendations for LC oscillator components.</li> <li>▪ Addition of update rate for analog output.</li> <li>▪ Minor edits</li> </ul> |
| December 20, 2017 | <ul style="list-style-type: none"> <li>▪ Revision of order table for new ZMID520x Application Sensor Module Kits, which replace the previous ZMID520x Evaluation Kit.</li> <li>▪ Update for template removing “short-form datasheet” section on page 2.</li> <li>▪ Revision of “Available Support” section on page 1.</li> <li>▪ Minor edits</li> </ul>   |
| May 24, 2017      | Addition of $t_{START}$ specification to Table 4.   |
| April 28, 2017    | <ul style="list-style-type: none"> <li>▪ Correction for sine and cosine labels in the following figures: application circuit on page 1, the block diagram on page 2, Figure 4, and Figure 5.</li> <li>▪ Minor edits.</li> </ul>   |
| March 28, 2017    | <ul style="list-style-type: none"> <li>▪ Correction for Table 15 for step values.</li> <li>▪ Addition of new images for Figure 20 to Figure 25.</li> <li>▪ Correction of name of ZMID520x Reference Board to ZMID520x Demo Board in kit contents given in part order table.</li> </ul>  |
| March 23, 2017    | Initial release.  |

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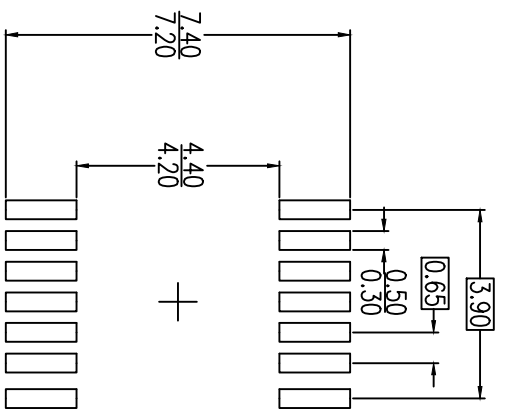
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NOTE:  
 1. ALL DIMENSIONS ARE IN MILLIMETERS



LAND PATTERN DIMENSIONS

NOTE:

1. ALL DIMENSIONS ARE IN MILLIMETERS

| Package Revision History |         |                    |
|--------------------------|---------|--------------------|
| Date Created             | Rev No. | Description        |
| Mar, 10 2017             | Rev 01  | Added Land Pattern |
| Dec, 19 2017             | Rev 02  | New Format         |

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