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CAT5270

Dual Digitally Programmable Potentiometers (DPP) with 256 Taps & I²C Compatible Interface

Description

The CAT5270 is a volatile 256-tap by two channels, digitally programmable potentiometer (DPP) with an I²C compatible interface. Each DPP consists of a linear taper series of resistive elements connected between two externally accessible end points. The tap points between each resistive element are connected to the wiper outputs with CMOS switches. On power up the wiper position goes to mid scale.

The CAT5270 can be used as a potentiometer or as a two terminal, variable resistor. It is available in a 14-lead TSSOP package operating over the industrial temperature range (-40°C to 85°C).

Features

- Two Linear Taper Digitally Programmable Potentiometers
- 256 Resistor Taps per Potentiometer
- End to End Resistance 50 k Ω , 100 k Ω
- I²C Compatible Interface
- Low Wiper Resistance 75 Ω (typ.)
- 2.5 V to 5.5 V Operation
- Standby Current Less than 1 μ A
- Power On to Mid Scale
- 14-lead TSSOP Package
- Industrial Temperature Range

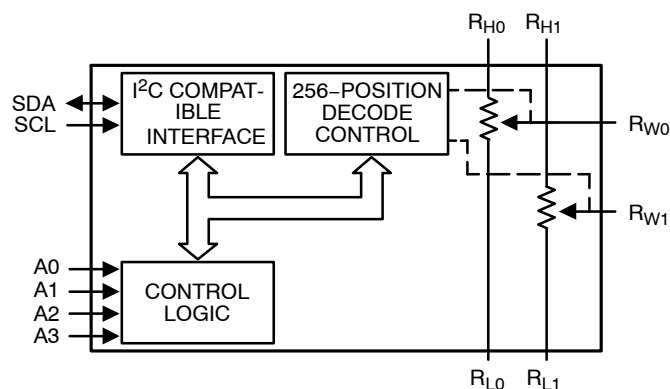
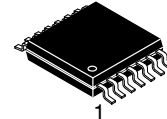


Figure 1. Functional Diagram



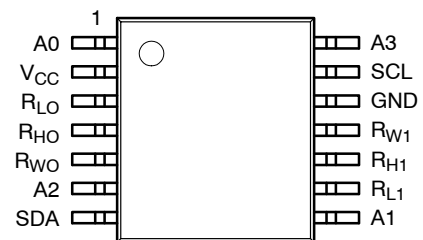
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TSSOP-14
Y SUFFIX
CASE 948AM

PIN CONNECTION



TSSOP-14 (Y)
(Top View)

ORDERING INFORMATION

See detailed ordering and shipping information in the package dimensions section on page 9 of this data sheet.

CAT5270

Pin Description

SCL: Serial Clock

The CAT5270 serial clock input pin is used to clock all data transfers into or out of the device.

SDA: Serial Data

The CAT5270 bidirectional serial data pin is used to transfer data into and out of the device. The SDA pin is an open drain output and can be wire-OR'd with the other open drain or open collector I/Os.

A0, A1, A2, A3: Device Address Inputs

These inputs set the device address when addressing multiple devices. A total of sixteen devices can be addressed on a single bus. A match in the slave address must be made with the address input in order to initiate communication with the CAT5270.

R_H, R_L: Resistor End Points

The two sets of R_H and R_L pins are equivalent to the terminal connections on a mechanical potentiometer.

R_W: Wiper

The R_W pins are equivalent to the wiper terminal of a mechanical potentiometer.

Device Operation

The CAT5270 is two resistor arrays integrated with an I²C compatible interface and two 8-bit wiper control registers. Each resistor array contains 255 separate resistive elements connected in series. The physical ends of each array are equivalent to the fixed terminals of a mechanical potentiometer (R_H and R_L). The tap positions between and at the ends of the series resistors are connected to the output

Table 1. PIN DESCRIPTION

| Pin # TSSOP-14 | Name | Function |
|-------------------|-----------------|---|
| 1 | A0 | Device Address, LSB |
| 2 | V _{CC} | Supply Voltage |
| 3 | R _{L0} | Low Reference Terminal for Potentiometer 0 |
| 4 | R _{H0} | High Reference Terminal for Potentiometer 0 |
| 5 | R _{W0} | Wiper Terminal for Potentiometer 0 |
| 6 | A2 | Device Address |
| 7 | SDA | Serial Data Input/Output |
| 8 | A1 | Device Address |
| 9 | R _{L1} | Low Reference Terminal for Potentiometer 1 |
| 10 | R _{H1} | High Reference Terminal for Potentiometer 1 |
| 11 | R _{W1} | Wiper Terminal for Potentiometer 1 |
| 12 | GND | Ground |
| 13 | SCL | Bus Serial Clock |
| 14 | A3 | Device Address |

wiper terminals (R_W) by a CMOS transistor switch. Only one tap point for each potentiometer is connected to its wiper terminal at a time and is determined by the value of the wiper control register. Data can be read or written to the wiper control register via the I²C compatible interface. Also, the device can be instructed to operate in an “increment/decrement” mode.

Table 2. ABSOLUTE MAXIMUM RATINGS

| Parameters | Ratings | Units |
|--|--------------------------------|-------|
| Temperature Under Bias | -55 to +125 | °C |
| Storage Temperature | -65 to +150 | °C |
| Voltage on Any Pin with Respect to V _{SS} (Note 1) | -2.0 to +V _{CC} + 2.0 | V |
| V _{CC} with Respect to Ground | -2.0 to +6.0 | V |
| Package Power Dissipation Capability (T _A = 25°C) | 1.0 | W |
| Lead Soldering Temperature (10 sec) | 300 | °C |
| Wiper Current | ±6 | mA |

Stresses exceeding Maximum Ratings may damage the device. Maximum Ratings are stress ratings only. Functional operation above the Recommended Operating Conditions is not implied. Extended exposure to stresses above the Recommended Operating Conditions may affect device reliability.

- The minimum DC input voltage is -0.5 V. During transitions, inputs may undershoot to -2.0 V for periods of less than 20 ns. Maximum DC voltage on output pins is V_{CC} + 0.5 V, which may overshoot to V_{CC} + 2.0 V for periods of less than 20 ns.

Table 3. RECOMMENDED OPERATING CONDITIONS

| Parameters | Ratings | Units |
|------------------------|--------------|-------|
| V _{CC} | +2.5 to +5.5 | V |
| Industrial Temperature | -40 to +85 | °C |

Table 4. POTENTIOMETER CHARACTERISTICS (V_{CC} = +2.5 V to +5.5 V, unless otherwise specified.)

| Symbol | Parameter | Test Conditions | Limits | | | Units |
|--|---|--|-----------------|----------|-----------------|--------------|
| | | | Min | Typ | Max | |
| R _{POT} | Potentiometer Resistance (100 kΩ) | | | 100 | | kΩ |
| R _{POT} | Potentiometer Resistance (50 kΩ) | | | 50 | | kΩ |
| | Potentiometer Resistance Tolerance | | | | ±20 | % |
| | R _{POT} Matching | | | | 1 | % |
| | Power Rating | 25°C, each pot | | | 50 | mW |
| I _W | Wiper Current | | | | ±3 | mA |
| R _W | Wiper Resistance | I _W = ±3 mA @ V _{CC} = 3 V | | 200 | 300 | Ω |
| R _W | Wiper Resistance | I _W = ±3 mA @ V _{CC} = 5 V | | 75 | 150 | Ω |
| V _{TERM} | Voltage on any R _H or R _L Pin | V _{SS} = 0 V | V _{SS} | | V _{CC} | V |
| | Resolution | | | 0.4 | | % |
| | Absolute Linearity (Note 4) | R _{W(n)(actual)} - R _{W(n)(expected)} (Note 7) | | | ±1 | LSB (Note 6) |
| | Relative Linearity (Note 5) | R _{W(n+1)} - R _[W(n)+LSB] (Note 7) | | | ±0.2 | LSB (Note 6) |
| TC _{RPO} | Temperature Coefficient of R _{POT} | (Note 3) | | ±100 | | ppm/°C |
| TC _{RATIO} | Ratiometric Temp. Coefficient | (Note 3) | | | 20 | ppm/°C |
| C _H /C _L /C _W | Potentiometer Capacitances | (Note 3) | | 10/10/25 | | pF |
| f _c | Frequency Response | R _{POT} = 50 kΩ (Note 3) | | 0.4 | | MHz |

- Latch-up protection is provided for stresses up to 100 mA on address and data pins from -1 V to V_{CC} + 1 V.
- This parameter is tested initially and after a design or process change that affects the parameter.
- Absolute linearity is utilized to determine actual wiper voltage versus expected voltage as determined by wiper position when used as a potentiometer.
- Relative linearity is utilized to determine the actual change in voltage between two successive tap positions when used as a potentiometer. It is a measure of the error in step size.
- LSB = R_{TOT} / 255 or (R_H - R_L) / 255, single pot
- n = 0, 1, 2, ..., 255

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Table 5. DC OPERATING CHARACTERISTICS ($V_{CC} = +2.5\text{ V}$ to $+5.5\text{ V}$, unless otherwise specified.)

| Symbol | Parameter | Test Conditions | Min | Max | Units |
|-----------|--|---|---------------------|---------------------|---------------|
| I_{CC} | Power Supply Current | $f_{SCL} = 400\text{ kHz}$, SDA = Open $V_{CC} = 5.5\text{ V}$, Inputs = GND | | 1 | mA |
| I_{SB} | Standby Current ($V_{CC} = 5.0\text{ V}$) | $V_{IN} = \text{GND}$ or V_{CC} , SDA = Open | | 5 | μA |
| I_{LI} | Input Leakage Current | $V_{IN} = \text{GND}$ to V_{CC} | | 10 | μA |
| I_{LO} | Output Leakage Current | $V_{OUT} = \text{GND}$ to V_{CC} | | 10 | μA |
| V_{IL} | Input Low Voltage | | -1 | $V_{CC} \times 0.3$ | V |
| V_{IH} | Input High Voltage | | $V_{CC} \times 0.7$ | $V_{CC} + 1.0$ | V |
| V_{OL1} | Output Low Voltage ($V_{CC} = 2.5\text{ V}$) | $I_{OL} = 3\text{ mA}$ | | 0.4 | V |

Table 6. CAPACITANCE ($T_A = 25^\circ\text{C}$, $f = 1.0\text{ MHz}$, $V_{CC} = 5\text{ V}$)

| Symbol | Test | Conditions | Max | Units |
|--------------------|---|------------------------|-----|-------|
| $C_{I/O}$ (Note 8) | Input/Output Capacitance (SDA) | $V_{I/O} = 0\text{ V}$ | 8 | pF |
| C_{IN} (Note 8) | Input Capacitance (A0, A1, A2, A3, SCL, \overline{WP}) | $V_{IN} = 0\text{ V}$ | 6 | pF |

Table 7. AC CHARACTERISTICS

| Symbol | Parameter | 2.5 V – 5.5 V | | Units |
|--------------------|---|---------------|-----|---------------|
| | | Min | Max | |
| f_{SCL} | Clock Frequency | | 400 | kHz |
| T_I (Note 8) | Noise Suppression Time Constant at SCL, SDA Inputs | | 200 | ns |
| t_{AA} | SLC Low to SDA Data Out and ACK Out | | 1 | μs |
| t_{BUF} (Note 8) | Time the bus must be free before a new transmission can start | 1.2 | | μs |
| $t_{HD:STA}$ | Start Condition Hold Time | 0.6 | | μs |
| t_{LOW} | Clock Low Period | 1.2 | | μs |
| t_{HIGH} | Clock High Period | 0.6 | | μs |
| $t_{SU:STA}$ | Start Condition Setup Time (for a Repeated Start Condition) | 0.6 | | μs |
| $t_{HD:DAT}$ | Data in Hold Time | 0 | | ns |
| $t_{SU:DAT}$ | Data in Setup Time | 50 | | ns |
| t_R (Note 8) | SDA and SCL Rise Time | | 0.3 | μs |
| t_F (Note 8) | SDA and SCL Fall Time | | 300 | ns |
| $t_{SU:STO}$ | Stop Condition Setup Time | 0.6 | | μs |
| t_{DH} | Data Out Hold Time | 100 | | ns |

Table 8. POWER UP TIMING (Notes 8 and 9)

| Symbol | Parameter | Max | Units |
|-----------|-----------------------------|-----|-------|
| t_{PUR} | Power-up to Read Operation | 1 | ms |
| t_{PUW} | Power-up to Write Operation | 1 | ms |

Table 9. WIPER TIMING

| Symbol | Parameter | Max | Units |
|------------|---|-----|---------------|
| t_{WRPO} | Wiper Response Time After Power Supply Stable | 10 | μs |
| t_{WRL} | Wiper Response Time After Instruction Issued | 10 | μs |

8. This parameter is tested initially and after a design or process change that affects the parameter.

9. t_{PUR} and t_{PUW} are delays required from the time V_{CC} is stable until the specified operation can be initiated.

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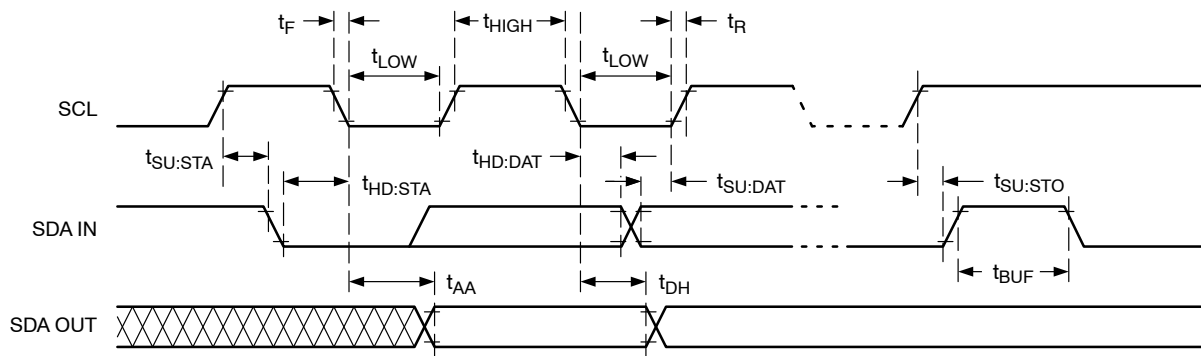


Figure 2. Bus Timing

Serial Bus Protocol

The following defines the features of the I²C compatible interface protocol:

1. Data transfer may be initiated only when the bus is not busy.
2. During a data transfer, the data line must remain stable whenever the clock line is high. Any changes in the data line while the clock is high will be interpreted as a START or STOP condition.

The device controlling the transfer is a master, typically a processor or controller, and the device being controlled is the slave. The master will always initiate data transfers and provide the clock for both transmit and receive operations. Therefore, the CAT5270 will be considered a slave device in all applications.

START Condition

The START Condition precedes all commands to the device, and is defined as a HIGH to LOW transition of SDA when SCL is HIGH (see Figure 3). The CAT5270 monitors the SDA and SCL lines and will not respond until this condition is met.

STOP Condition

A LOW to HIGH transition of SDA when SCL is HIGH determines the STOP condition (see Figure 3). All operations must end with a STOP condition.

Device Addressing

The bus Master begins a transmission by sending a START condition. The Master then sends the Slave Address Byte which contains the address of the particular slave device it is requesting. The four most significant bits of the 8-bit slave address are fixed as 0101 for the CAT5270. The next four significant bits (A3, A2, A1, A0) are the device address bits and define which device the Master is accessing (see Figure 5). Up to sixteen devices may be individually addressed by the system. Typically, +5 V (V_{CC}) and ground are hard-wired to these pins to establish the device's address.

After the Master sends a START condition and the slave address byte, the CAT5270 monitors the bus and responds with an acknowledge (on the SDA line) when its address matches the transmitted slave address.

Slave Address Byte

The most significant four bits of the slave address are a device type identifier. These bits for the CAT5270 are fixed at 0101[B] (refer to Figure 5).

The next four bits, A3 – A0, are the internal slave address and must match the physical device address which is defined by the state of the A3 – A0 input pins for the CAT5270 to successfully continue the command sequence. Only the device which slave address matches the incoming device address sent by the master executes the instruction. The A3 – A0 inputs can be actively driven by CMOS input signals or tied to V_{CC} or V_{SS}.

Acknowledge

After a successful data transfer, each receiving device is required to generate an acknowledge. The Acknowledging device pulls down the SDA line during the ninth clock cycle, signaling that it received the 8 bits of data (see Figure 4).

The CAT5270 responds with an acknowledge after receiving a START condition and its slave address. If the device has been selected along with a write operation, it responds with an acknowledge after receiving each 8-bit byte.

When the CAT5270 is in a READ mode it transmits 8 bits of data, releases the SDA line, and monitors the line for an acknowledge. Once it receives this acknowledge, the CAT5270 will continue to transmit data. If no acknowledge is sent by the Master, the device terminates data transmission and waits for a STOP condition.

If the device has been selected with an IN/DEC operation it will no longer respond with acknowledge as the received data it is not in a byte format.

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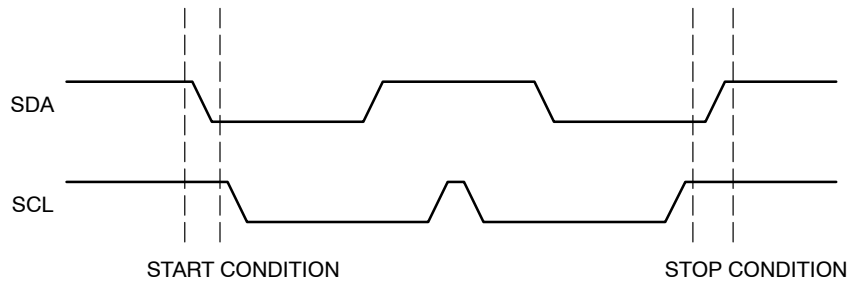


Figure 3. Start/Stop Condition

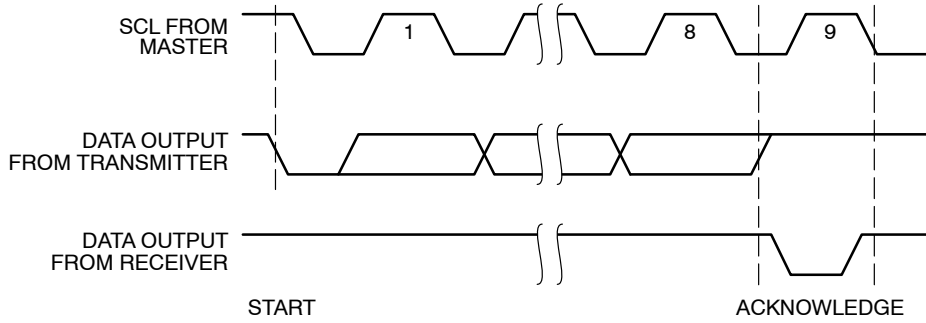


Figure 4. Acknowledge Condition

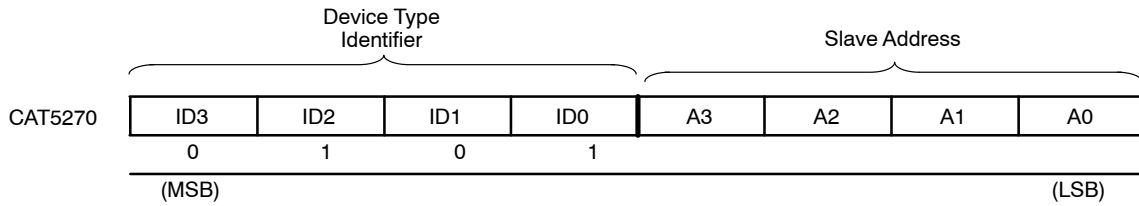


Figure 5. Identification Format for Slave Address Byte

Instruction and Register Description

Instruction Byte

The next byte sent to the CAT5270 contains the instruction and register pointer information. The four most significant bits used provide the instruction opcode I3 – I0.

Instructions

Instructions are three bytes in length. These instructions are:

- **Read Wiper Control Register** – read the current wiper position of the selected potentiometer in the WCR
- **Write Wiper Control Register** – change current wiper position in the WCR of the selected potentiometer
- **Increment/Decrement Wiper Control Register** – change step by step the current wiper position in the WCR of the selected potentiometer

The basic sequence of the three byte instructions is illustrated in Figure 8.

Write Operation

In the Write mode, the Master device sends the START condition and the slave address information to the Slave device. After the Slave generates an acknowledge, the Master sends the instruction byte that defines the requested operation of CAT5270. The instruction byte consists of a seven-bit opcode followed by pot/register selection bit. After receiving another acknowledge from the Slave, the Master device transmits the data to be written into the selected register. The CAT5270 acknowledges once more and the Master generates the STOP condition.

Increment/Decrement Command

The last command is Increment/Decrement (Figures 9 and 10). The Increment/Decrement command is different from the other commands. Once the instruction is issued and the CAT5270 has responded with an acknowledge, the master can clock the selected wiper up and/or down in one segment steps; thereby providing a fine tuning capability to the host. For each SCL clock pulse (t_{HIGH}) while SDA is HIGH, the selected wiper will move one resistor segment towards the R_H terminal. Similarly, for each SCL clock pulse while SDA is LOW, the selected wiper will move one resistor segment towards the R_L terminal.

See Instructions format for more details.

Wiper Control Register (WCR)

The CAT5270 contains two 8-bit Wiper Control Registers, one for each potentiometer. The Wiper Control Register output is decoded to select one of 256 switches along its resistor array. The contents of the WCR can be altered in two ways: it may be written by the host via Write Wiper Control Register instruction; or it can be modified one step at a time by the Increment/decrement instruction (see Instruction section for more details).

| P | WCR |
|---|-----------------------|
| 0 | Set R0 wiper position |
| 1 | Set R1 wiper position |

The Wiper Control Register is a volatile register that loses its contents when the CAT5270 is powered-down. Upon power-up, the wiper is set to midspan and may be repositioned anytime after the power has become stable.

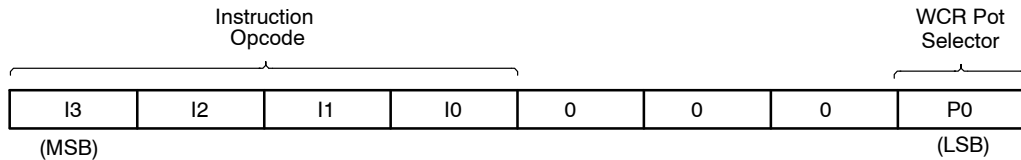


Figure 6. Instruction Byte Format

Table 10. INSTRUCTION SET

| Instruction | Instruction Set (Note 10) | | | | | | | | Operation |
|--|---------------------------|----|----|----|----|----|----|-------|---|
| | I3 | I2 | I1 | I0 | F2 | F1 | F0 | WCR/P | |
| Read Wiper Control Register | 1 | 0 | 0 | 1 | 0 | 0 | 0 | 1/0 | Read the contents of the Wiper Control Register pointed to by P |
| Write Wiper Control Register | 1 | 0 | 1 | 0 | 0 | 0 | 0 | 1/0 | Write new value to the Wiper Control Register pointed to by P |
| Increment/Decrement Wiper Control Register | 0 | 0 | 1 | 0 | 0 | 0 | 0 | 1/0 | Enable Increment/decrement of the Control Latch pointed to by P |

10. 1/0 = data is one or zero

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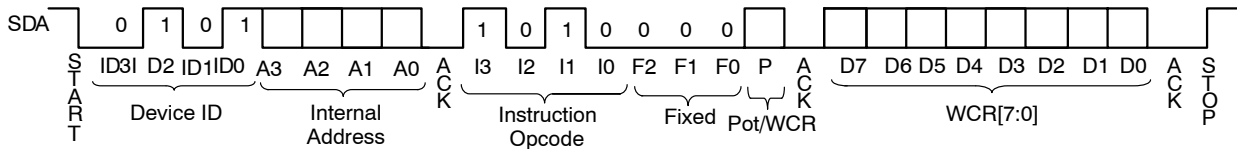


Figure 7. Write Instruction Sequence

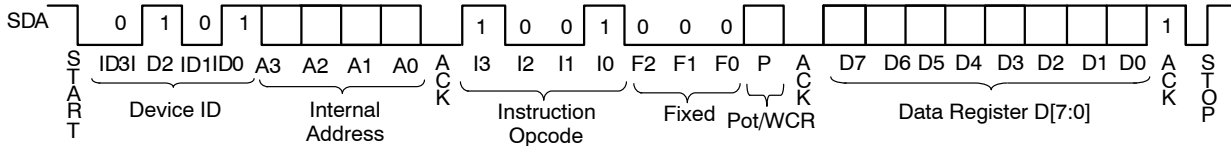


Figure 8. Read Instruction Sequence

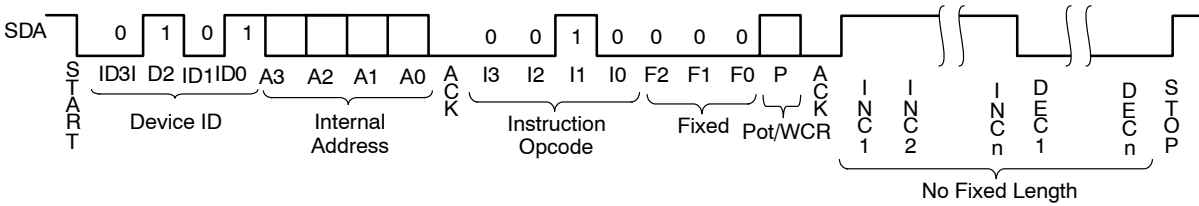


Figure 9. Increment/Decrement Instruction Sequence

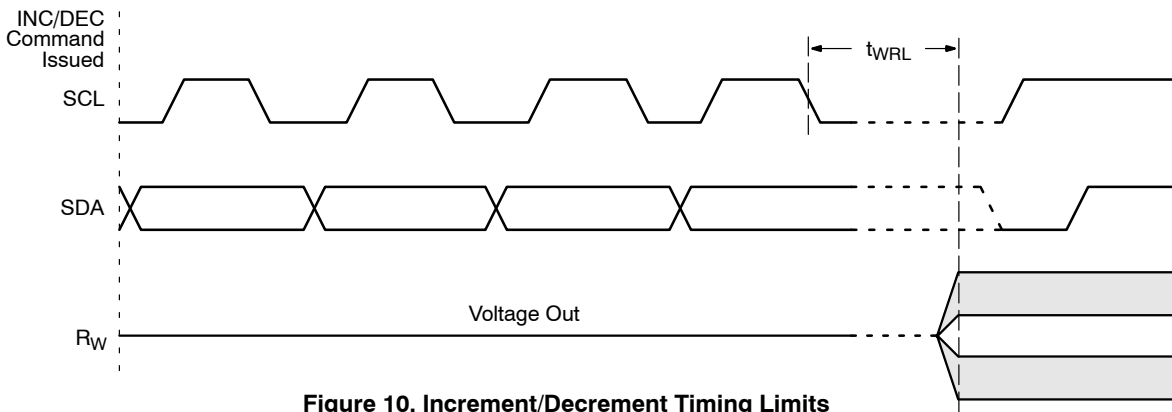


Figure 10. Increment/Decrement Timing Limits

Instruction Format

Read Wiper Control Register (WCR)

| | | | | | | | | | | | | | | | | | | | | | | | | | |
|-----------------------|------------------|---|---|---|----|----|----|-------------|-------------|---|---|---|---|---|---|-------------|------|---|---|---|---|---|---|-------------|------------------|
| S T A R T | DEVICE ADDRESSES | | | | | | | A C K | INSTRUCTION | | | | | | | A C K | DATA | | | | | | | A C K | S T O P |
| | 0 | 1 | 0 | 1 | A3 | A2 | A1 | | A0 | 1 | 0 | 0 | 1 | 0 | 0 | | 0 | P | 7 | 6 | 5 | 4 | 3 | | |

Write Wiper Control Register (WCR)

| | | | | | | | | | | | | | | | | | | | | | | | | | |
|-----------------------|------------------|---|---|---|----|----|----|-------------|-------------|---|---|---|---|---|---|-------------|------|---|---|---|---|---|---|-------------|------------------|
| S T A R T | DEVICE ADDRESSES | | | | | | | A C K | INSTRUCTION | | | | | | | A C K | DATA | | | | | | | A C K | S T O P |
| | 0 | 1 | 0 | 1 | A3 | A2 | A1 | | A0 | 1 | 0 | 1 | 0 | 0 | 0 | | 0 | P | 7 | 6 | 5 | 4 | 3 | | |

Increment (I)/Decrement (D) Wiper Control Register (WCR)

| | | | | | | | | | | | | | | | | | | | | | | |
|-----------------------|------------------|---|---|---|----|----|----|-------------|-------------|---|---|---|---|---|---|-------------|------|---|-------|-------|----|------------------|
| S T A R T | DEVICE ADDRESSES | | | | | | | A C K | INSTRUCTION | | | | | | | A C K | DATA | | | | | S T O P |
| | 0 | 1 | 0 | 1 | A3 | A2 | A1 | | A0 | 0 | 0 | 1 | 0 | 0 | 0 | | 0 | P | I / D | I / D | .. | |

CAT5270

ORDERING INFORMATION

| Part Number | Resistance | Lead Finish | Package | Shipping† |
|------------------|------------|-------------|-----------------------|--------------------|
| CAT5270YI-50-GT2 | 50 kΩ | NiPdAu | TSSOP-14 (Pb-Free) | 2000 / Tape & Reel |
| CAT5270YI-00-GT2 | 100 kΩ | | | |

†For information on tape and reel specifications, including part orientation and tape sizes, please refer to our Tape and Reel Packaging Specifications Brochure, BRD8011/D.

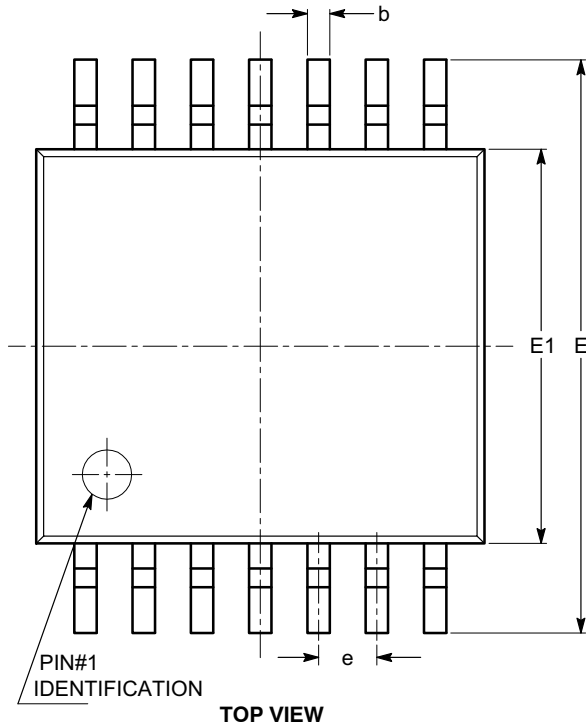
11. For detailed information and a breakdown of device nomenclature and numbering systems, please see the ON Semiconductor Device Nomenclature document, TND310/D, available at www.onsemi.com.

12. All packages are RoHS-compliant (Pb-Free, Halogen-Free).

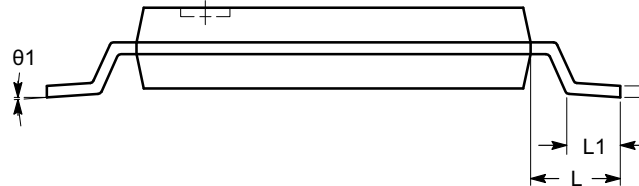
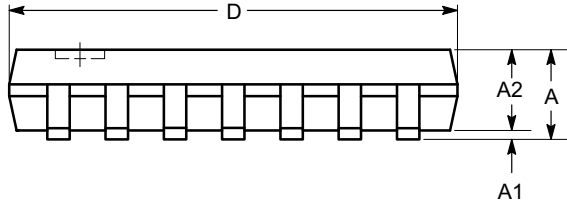
CAT5270

PACKAGE DIMENSIONS

TSSOP14, 4.4x5
CASE 948AM-01
ISSUE O




| SYMBOL | MIN | NOM | MAX |
|----------|----------|-----|------|
| A | | | 1.10 |
| A1 | 0.05 | | 0.15 |
| A2 | 0.85 | | 0.95 |
| b | 0.19 | | 0.30 |
| c | 0.13 | | 0.20 |
| D | 4.90 | | 5.10 |
| E | 6.30 | | 6.50 |
| E1 | 4.30 | | 4.50 |
| e | 0.65 BSC | | |
| L | 1.00 REF | | |
| L1 | 0.45 | | 0.75 |
| θ | 0° | | 8° |



Notes:

- (1) All dimensions are in millimeters. Angles in degrees.
- (2) Complies with JEDEC MO-153.

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