

## Vibration-Tolerant High-Accuracy Hall-Effect Wheel Speed and Direction Sensor IC

### FEATURES AND BENEFITS

- **Hall-effect technology** allows ease of use for ring magnet and ferromagnetic target sensing with back-biased magnet
- **Vibration detection** optimized for wheel speed applications allows for blanking of vibration on vibration with minimum delay in output recovery
- **Digital PW and AK protocol** provides speed and direction information, signal integrity, and functional status
- **Integrated capacitor** in a single overmolded miniature package provides greater EMC robustness
- **SolidSpeed Digital Architecture** supports advanced algorithms, maintaining pitch accuracy during dynamic air gap disturbances
- **EEPROM** enables traceability throughout the product life cycle



### PACKAGE:



2-Pin SIP  
(suffix UB)

*Not to scale*

### DESCRIPTION

The A19303 is an optimized Hall-effect integrated circuit (IC) with PW and AK Protocol that provides a user-friendly two-wire solution for applications where pitch accuracy is important for the determination of speed and direction of the sensed target. The small package includes an integrated capacitor and Hall-based IC in a single overmolded design, with an additional molded lead-stabilizing bar for robust shipping and ease of assembly.

The IC's SolidSpeed Digital Architecture offers intelligent algorithms capable of maintaining stable operation during dynamic air gap movements. The sophisticated digital controller provides highly accurate speed and direction information with vibration detection ideal for ABS applications.

The IC includes built-in EEPROM scratch memory available for device traceability throughout sensor module production.

The IC is offered in the UB package, which integrates the IC and a high temperature ceramic capacitor in a single overmolded SIP package for enhanced EMC performance.

The 2-pin SIP package is lead (Pb) free, with tin leadframe plating.

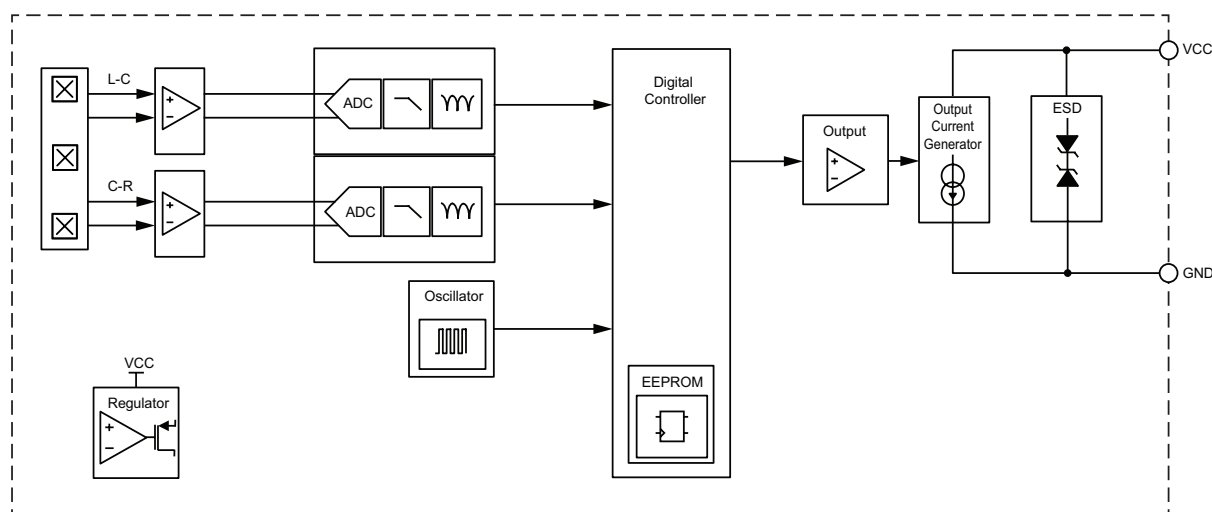


Figure 1: Functional Block Diagram

# A19303

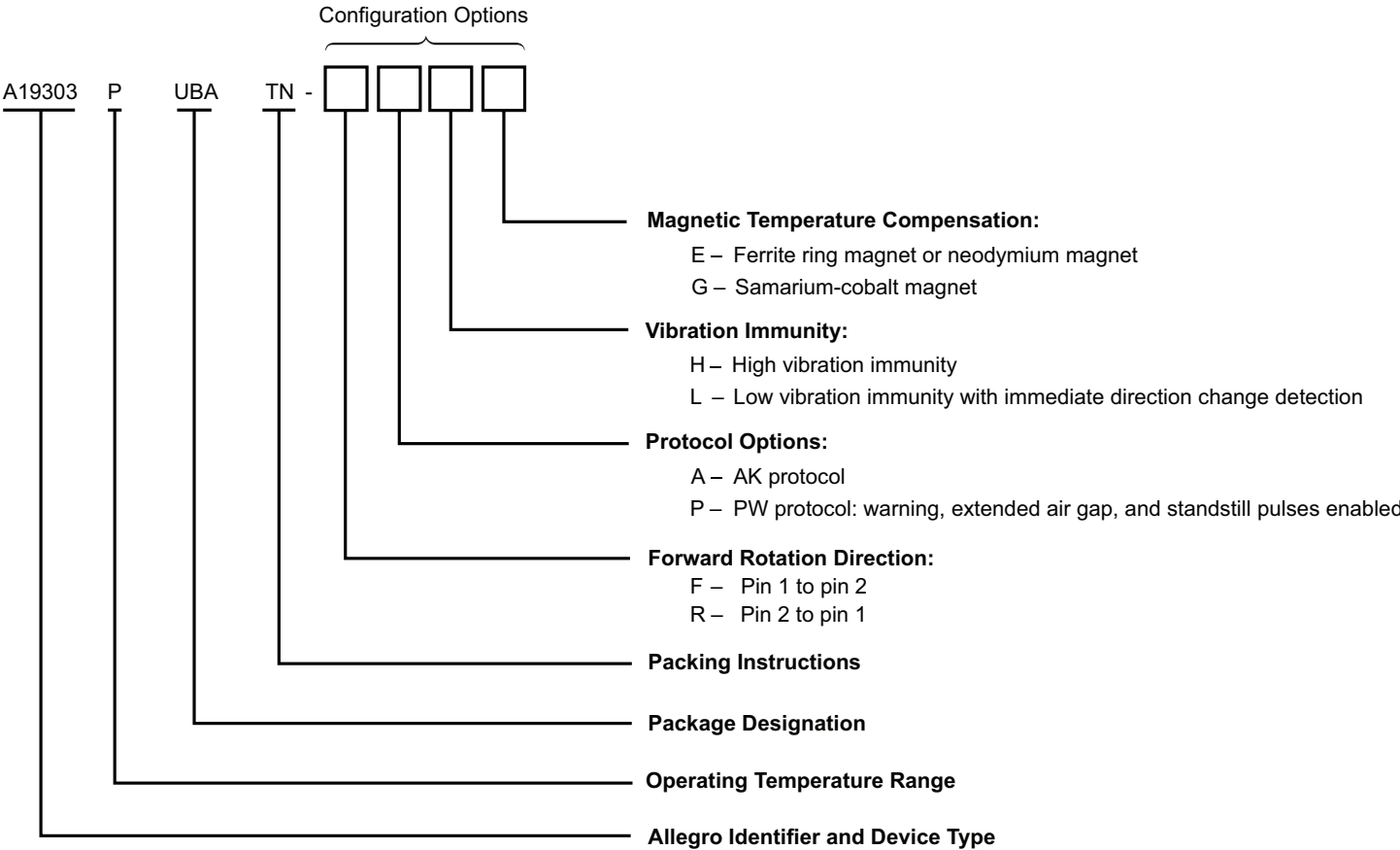
## Vibration-Tolerant High-Accuracy Hall-Effect Wheel Speed and Direction Sensor IC

### SELECTION GUIDE [1]

Part Number	Packing
A19303LUBATN-FPHE	Tape and reel, 4000 pieces per reel



[1] Not all combinations are available. Contact Allegro sales for availability and pricing of custom programming options.



SPECIFICATIONS

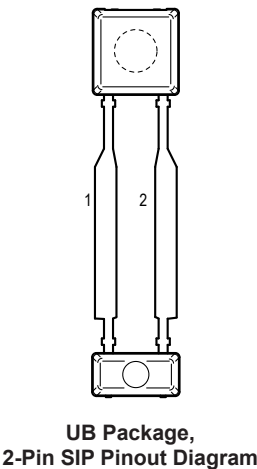
ABSOLUTE MAXIMUM RATINGS

Characteristic	Symbol	Notes	Rating	Unit
Supply Voltage	$V_{CC}$	Refer to Power Derating section; potential between pin 1 and pin 2	28	V
Reverse Supply Voltage	$V_{RCC}$		-18	V
Operating Ambient Temperature	$T_A$		-40 to 150	°C
Junction Temperature	$T_{J(max)}$		165	°C
Storage Temperature	$T_{stg}$		-65 to 170	°C

INTERNAL DISCRETE CAPACITOR RATINGS

Characteristic	Symbol	Test Conditions	Value (Typ.)	Unit
Nominal Capacitance	$C_{SUPPLY}$	Connected between pin 1 and pin 2 (refer to Figure 2)	2.2	nF

PINOUT DIAGRAM



PINOUT TABLE

Name	Number	Function
VCC	1	Supply Voltage
GND	2	Ground

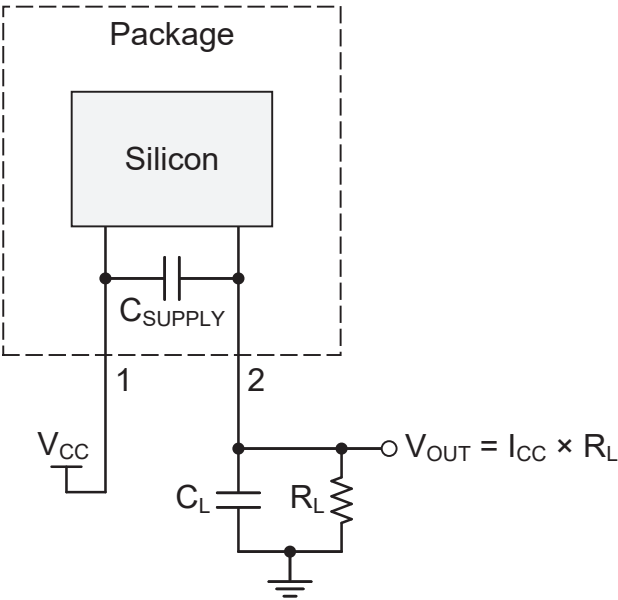


Figure 2: Typical Application Circuit

**OPERATING CHARACTERISTICS:** Valid over operating voltage and temperature, unless otherwise specified

Characteristic	Symbol	Test Conditions		Min.	Typ. <sup>[1]</sup>	Max.	Unit
ELECTRICAL SUPPLY CHARACTERISTICS							
Supply Voltage <sup>[2]</sup>	V <sub>CC</sub>	Potential between pin 1 and pin 2	-xPxx variant	4	–	24	V
			-xAxx variant	5.2	–	24	V
Undervoltage Lockout (UVLO) Hysteresis	V <sub>HYS(AK)</sub>	-xAxx variant		1.1	–	–	V
Reverse Supply Current <sup>[3]</sup>	I <sub>RCC</sub>	V <sub>CC</sub> = V <sub>RCC(max)</sub>		–10	–	–	mA
Supply Zener Clamp Voltage	V <sub>Zsupply</sub>	I <sub>CC</sub> = 36.6 mA		28	–	–	V
Supply Current	I <sub>CC(LOW)</sub>	Low-current state		5.9	7	8.4	mA
	I <sub>CC(MID)</sub>	Mid-current state		12	14	16	mA
	I <sub>CC(HIGH)</sub>	High-current state		23.52	28.0	33.6	mA
Supply Current Ratio <sup>[4]</sup>	I <sub>CC(MID)</sub> / I <sub>CC(LOW)</sub>	Measured as ratio of mid current to low current (isothermal)		1.9	–	–	–
	I <sub>CC(HIGH)</sub> / I <sub>CC(LOW)</sub>	Measured as ratio of high current to low current (isothermal)		3.6	–	–	–
Output Rise/Fall Time	t <sub>r</sub> , t <sub>f</sub>	Voltage measured at pin 2 in Figure 2; R <sub>L</sub> = 100 Ω, C <sub>L</sub> = 10 pF, measured between 10% and 90% of I <sub>CC(LOW)</sub> and I <sub>CC(MID)</sub> (-xPxx variants)		0	–	1.5	μs
Slew Rate	SR	Measured at pin 2 in Figure 2; R <sub>L</sub> = 50 Ω, C <sub>L</sub> = 10 pF, measured between 10% and 90% of I <sub>CC(LOW)</sub> and I <sub>CC(HIGH)</sub> or I <sub>CC(LOW)</sub> and I <sub>CC(MID)</sub> (-xAxx variant)		8	–	28	mA/μs
POWER-ON CHARACTERISTICS							
Power-On State	POS	V <sub>CC</sub> > V <sub>CC(min)</sub> , as connected in Figure 2		I <sub>CC(LOW)</sub>			mA
Power-On Time <sup>[5]</sup>	t <sub>PO</sub>	V <sub>CC</sub> > V <sub>CC(min)</sub> , as connected in Figure 2		–	0.25	1	ms
OPERATING CHARACTERISTICS AND PERFORMANCE							
Operating Differential Magnetic Input <sup>[6]</sup>	B <sub>DIFF(pk-pk)</sub>	Peak-to-peak of differential magnetic input (T <sub>A</sub> = 160°C)		20	–	–	G
Operating Differential Magnetic Range <sup>[6]</sup>	B <sub>DIFF</sub>	Refer to Figure 6		–700	–	700	G
Operating Magnetic Input Signal Variation	ΔB <sub>DIFF(pk-pk)</sub>	Bounded amplitude ratio within T <sub>WINDOW</sub> <sup>[7]</sup> ; no missed output transitions or flat line condition; possible incorrect direction information; see Figure 4 and Figure 5		0.6	–	–	–
Operating Magnetic Input Signal Window	T <sub>WINDOW</sub>	Rolling window where ΔB <sub>DIFF(pk-pk)</sub> cannot exceed bounded ratio; see Figure 4 and Figure 5		4	–	–	T <sub>CYCLE</sub>
Calibration Period	T <sub>CAL</sub>	Period between power-on and valid speed and correct direction output (f ≤ 200 Hz)		–	–	2	T <sub>CYCLE</sub>
Operate Point	B <sub>OP</sub>	% of peak-to-peak IC-processed signal		–	50	–	%
Release Point	B <sub>RP</sub>	% of peak-to-peak IC-processed signal		–	50	–	%
Switch Point Hysteresis	B <sub>HYS</sub>			–	15	–	%

Continued on next page...

**OPERATING CHARACTERISTICS (continued): Valid over operating voltage and temperature, unless otherwise specified**

Characteristic	Symbol	Test Conditions	Min.	Typ. <sup>[1]</sup>	Max.	Unit
Switch Point Separation	$B_{DIFF(SP-SEP)}$	Required amount of amplitude separation between channel A and channel B at each $B_{OP}$ and $B_{RP}$ occurrence. Channels must be in phase; see Figure 7	32.5	—	—	%
<b>OUTPUT PROTOCOL CHARACTERISTICS <sup>[8]</sup> (-xAxx variant)</b>						
Bit Width	$t_p$	Refer to Figure 8	40	50	60	$\mu s$
Standstill Period	$t_{STOP}$		105	150	195	ms
AK Off Time	$t_{W(PRE)}$	Pre-low time	—	75	—	$\mu s$
Air Gap Reserve Level	$B_{LR}$	Signal amplitude that engages AK LR bit	—	24	—	$G_{pk-pk}$
Operating Frequency <sup>[9]</sup>	$f_{SIG}$		0	—	2.5	kHz
<b>OUTPUT PROTOCOL CHARACTERISTICS <sup>[8]</sup> (-xPxx variant)</b>						
Pulse Width Off Time	$t_{W(PRE)}$	Refer to Figure 9	38	45	52	$\mu s$
Forward Pulse Width	$t_{W(FWD)}$		76	90	104	$\mu s$
Reverse Pulse Width	$t_{W(REV)}$		153	180	207	$\mu s$
EA Forward Pulse Width	$t_{W(EA FWD)}$		306	360	414	$\mu s$
EA Reverse Pulse Width	$t_{W(EA REV)}$		612	720	828	$\mu s$
Warning Pulse Width	$t_{W(WARN)}$		38	45	52	$\mu s$
Standstill Pulse Width	$t_{W(STILL)}$		1232	1440	1656	$\mu s$
Standstill Period	$t_{STOP}$		590	737	848	ms
Operating Frequency, Forward Pulses <sup>[9]</sup> <sup>[10]</sup>	$f_{FWD}$		0	—	3.9	kHz
Operating Frequency, Reverse Pulses <sup>[9]</sup> <sup>[10]</sup>	$f_{REV}$		0	—	2.4	kHz
Operating Frequency, Warning Pulses <sup>[9]</sup> <sup>[10]</sup>	$f_{WARN}$		0	—	5	kHz
Operating Frequency, EA Pulses <sup>[9]</sup> <sup>[10]</sup>	$f_{EA}$	EA pulses output when $f < f_{EA}$ and $B_{DIFF(pk-pk)} < B_{EA}$	—	117	—	Hz
Air Gap Warning Level	$B_{WARN}$	Warning pulses output when $B_{DIFF(pk-pk)} < B_{WARN}$	—	24	—	$G_{pk-pk}$
Extended Air Gap Level	$B_{EA}$	EA pulses output when $f < f_{EA}$ and $B_{DIFF(pk-pk)} < B_{EA}$	—	84	—	$G_{pk-pk}$

Continued on next page...

**OPERATING CHARACTERISTICS (continued): Valid over operating voltage and temperature, unless otherwise specified**

Characteristic	Symbol	Test Conditions	Min.	Typ. <sup>[1]</sup>	Max.	Unit
<b>THERMAL CHARACTERISTICS</b>						
Magnetic Temperature Coefficient <sup>[11]</sup>	TC	Based on ferrite ring magnet and neodymium magnet (-xxxE variant)	–	0.16	–	%/°C
		Based on samarium-cobalt magnet (-xxxG variant)	–	0.04	–	%/°C
Package Thermal Resistance <sup>[12]</sup>	R <sub>θJA</sub>	Single-layer PCB with copper limited to solder pads	–	213	–	°C/W
<b>PERFORMANCE CHARACTERISTICS</b>						
Vibration Immunity		Output will be blanked for vibration magnitudes less than defined T <sub>CYCLE</sub> (-xxHx variant)	–	–	1	T <sub>CYCLE</sub>
Vibration Recovery		Amount of constant rotation post vibration scenario before output pulses resume (-xxHx variant)	–	–	2	T <sub>CYCLE</sub>
Pulse After Direction Change		-xxHx variant	–	–	1.75	T <sub>CYCLE</sub>

<sup>[1]</sup> Typical values are at T<sub>A</sub> = 25°C and V<sub>CC</sub> = 12 V. Performance may vary for individual units, within the specified maximum and minimum limits.

<sup>[2]</sup> Maximum voltage must be adjusted for power dissipation and junction temperature; refer to Power Derating section.

<sup>[3]</sup> Negative current is defined as conventional current coming out of (sourced from) the specified device terminal.

<sup>[4]</sup> Supply current ratio is taken as a mean value of I<sub>CC(MID)</sub> / I<sub>CC(LOW)</sub> and I<sub>CC(HIGH)</sub> / I<sub>CC(LOW)</sub>.

<sup>[5]</sup> Output transients prior to t<sub>PO</sub> should be ignored.

<sup>[6]</sup> Differential magnetic field is measured for Channel A (E1-E2) and Channel B (E2-E3) independently. Each channel's differential magnetic field is measured between two Hall elements. Magnetic field is measured orthogonally to the front of the package. B<sub>DIFF(pk-pk)</sub> only valid at T<sub>A(max)</sub> due to magnetic temperature compensation. Refer to UB package drawing.

<sup>[7]</sup> Symmetrical signal variation is defined as the largest amplitude ratio from B<sub>n</sub> to B<sub>n</sub> + T<sub>WINDOW</sub>. Signal variation may occur continuously while B<sub>DIFF</sub> remains in the operating magnetic range.

<sup>[8]</sup> Pulse width measured at threshold of (I<sub>CC(MID)</sub> + I<sub>CC(LOW)</sub>) / 2 and (I<sub>CC(HIGH)</sub> + I<sub>CC(LOW)</sub>) / 2.

<sup>[9]</sup> Frequency is based on B<sub>DIFF</sub> frequency.

<sup>[10]</sup> These frequency ranges are based on valid pulse width generation with each pulse width preceding with a t<sub>w(PRE)(MAX)</sub>.

<sup>[11]</sup> Magnets decrease in strength with increasing temperature. The device temperature coefficient compensates to help maintain a consistent maximum air gap over temperature.

<sup>[12]</sup> Additional thermal information is available on the Allegro website.

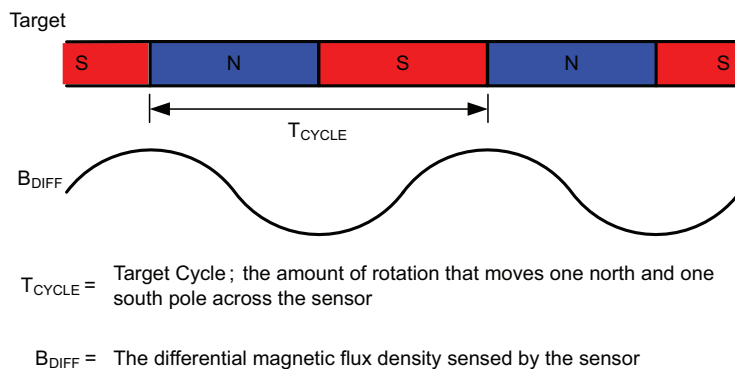
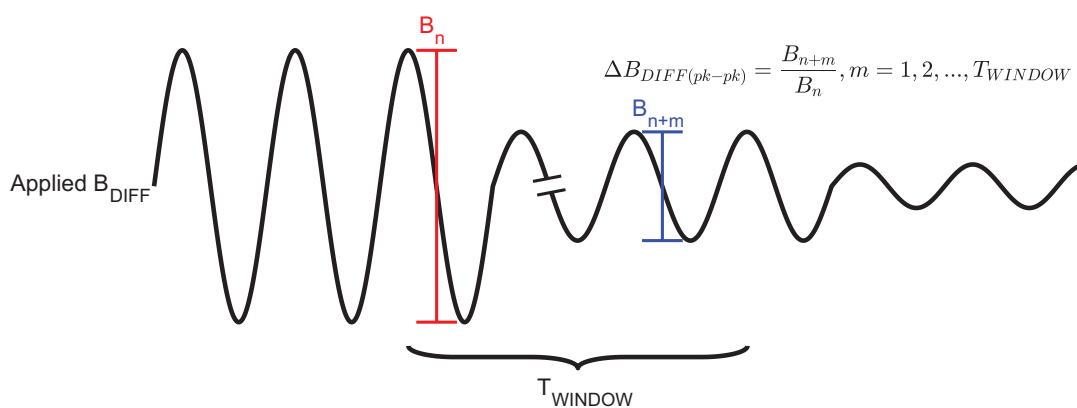
Figure 3: Definition of  $T_{\text{CYCLE}}$ 

Figure 4: Single Period-to-Period Variation

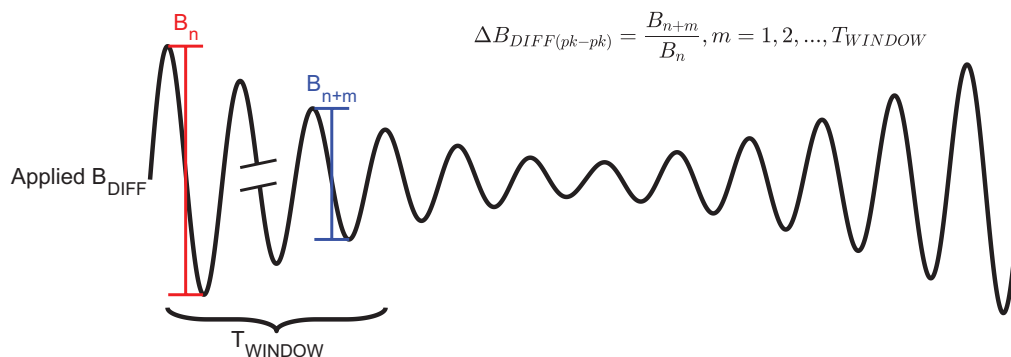


Figure 5: Repeated Period-to-Period Variation

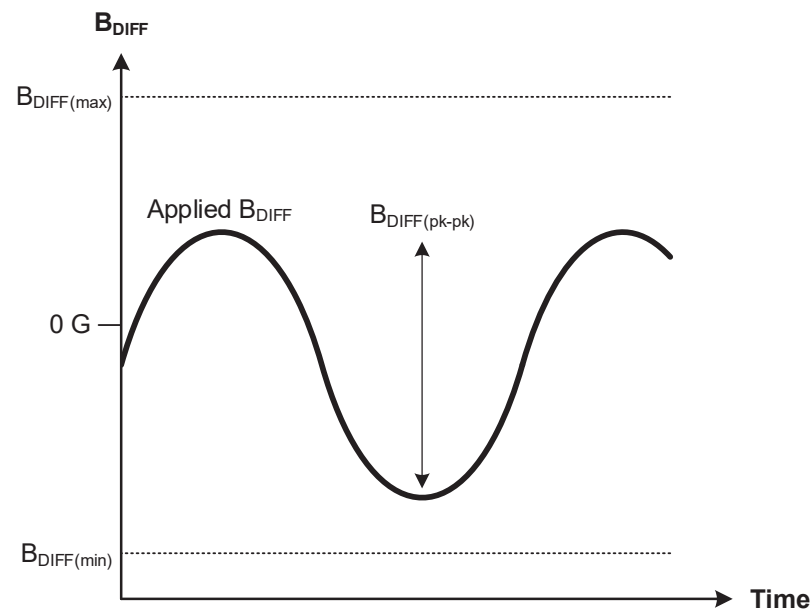


Figure 6: Definition of Differential Magnetic Input

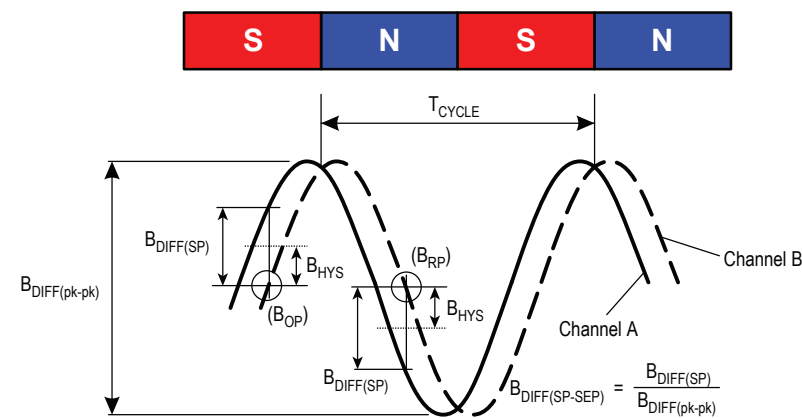


Figure 7: Definition of Switch Point Separation



## FUNCTIONAL DESCRIPTION

The A19303 sensor IC contains a single-chip Hall-effect circuit that supports three Hall elements. These elements are used in differential pairs to provide electrical signals containing information regarding edge position and direction of target rotation. The A19303 is intended for use with ring magnet targets, or, when back-biased with an appropriate magnet, with ferromagnetic targets. The IC detects the peaks of the magnetic signals and sets dynamic thresholds based on these detected signals. Output events are triggered when  $B_{DIFF}$  transitions through the switch points.

## FORWARD ROTATION

For the -Fxxx variant, when the target is rotating such that a target feature passes from pin 1 to pin 2, this is referred to as forward rotation. This direction of rotation is indicated on the output by bits GDR and DR in the generated AK word. For the -Rxxx variant, forward direction is indicated for target rotation from pin 2 to 1 (refer to Figure 8).

## REVERSE ROTATION

For the -Fxxx variant, when the target is rotating such that a target feature passes from pin 2 to pin 1, this is referred to as reverse rotation. This direction of rotation is indicated on the output by bits GDR and DR in the generated AK word. For the -Rxxx variant, reverse direction is indicated for target rotation from pin 1 to 2.

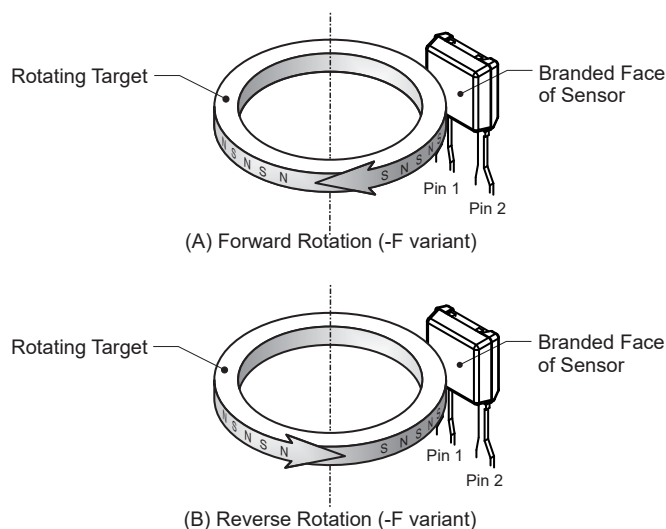


Figure 8: Target Orientation Relative to Device (ring magnet shown).

## AK PROTOCOL DESCRIPTION

When a target passes in front of the device (opposite the branded face of the package case), the A19303 generates an AK word for each magnetic pole or for each tooth and each valley of the target. Speed information is provided by the output pulse rate, while direction of target rotation is provided in the AK data bits.

## PW PROTOCOL DESCRIPTION

When a target passes in front of the device (opposite the branded face of the package case), the A19303 generates an output pulse for each magnetic pole or for each tooth and each valley of the target. Speed information is provided by the output pulse rate, while direction of target rotation is provided by the duration of the output pulses.

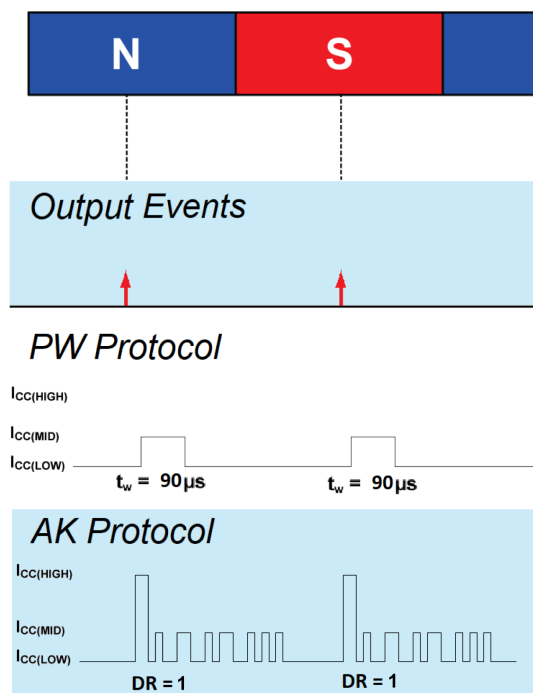


Figure 9: Output Timing Example

## AK BIT DEFINITIONS

The AK protocol (-xAxx variant) consists of 10 pulses. A single speed pulse, 8 data bits, and a single parity bit. The speed pulse and data bit definitions are described below.

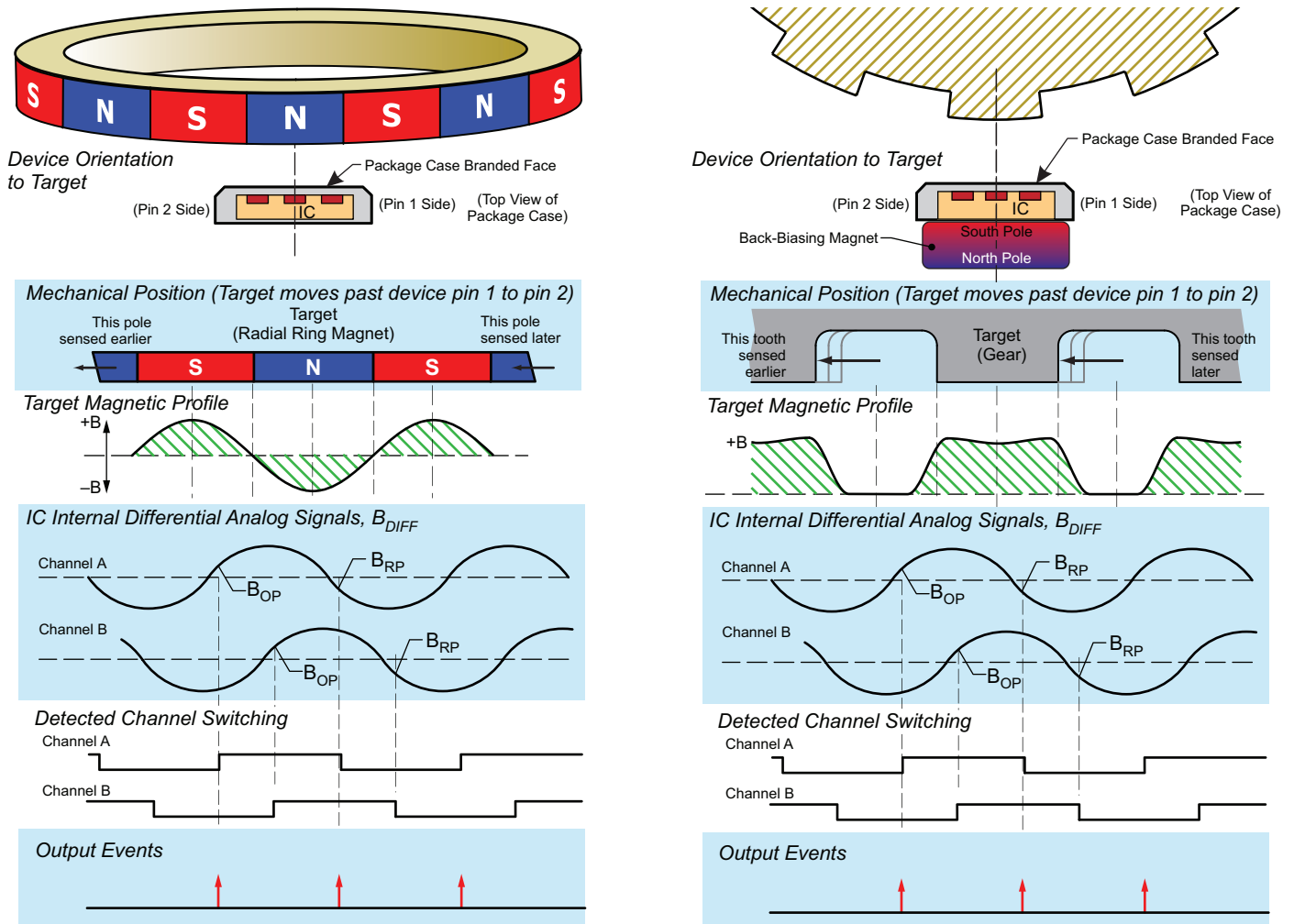
Field	Abbreviation	Coding
Speed Pulse	SP	$I_{CC(HIGH)}$ if speed pulse, $I_{CC(MID)}$ if standstill pulse

Bit Number	Field	Abbreviation	Coding	Post-Power-On Default Value
0	Air Gap Reserve	LR	1 if $G_{pkpk} < B_{LR(pk-pk)}$ , 0 otherwise	0
1	Status Mode	M	1 if not in running mode, 0 otherwise	1
2	Unused	N/A	0 always	0
3	Validity of the Direction of Rotation	GDR	1 if direction is valid, 0 otherwise	0
4	Direction	DR	0 if forward rotation, 1 if reverse rotation	0
5	Air Gap Indication	LM0	LM LSB	0
6	Air Gap Indication	LM1	LM	0
7	Air Gap Indication	LM2	LM MSB	0
8	Parity	P	1 if parity incl. parity bit is even, 0 otherwise	1

## LM AIR GAP TABLE

Data bits [5:7] report the air gap indication. These bits give 8 air gap ranges in respect to the measured peak to peak magnetic field ( $B_{DIFF(pk-pk)}$ ).

LM2	LM1	LM0	Threshold Value (Typ.)	Units
0	0	0	$\leq 12$	G
0	0	1	$> 12$	G
0	1	0	$> 18$	G
0	1	1	$> 24$	G
1	0	0	$> 36$	G
1	0	1	$> 54$	G
1	1	0	$> 78$	G
1	1	1	$> 111$	G



**Figure 10: Basic Operation**

Channel A or Channel B can be used as the output switching channel. This is determined on startup by the first channel that switches. The non-switching channel is used for direction detection.

### Calibration and Direction Validation

When power is applied to the A19303, the built-in algorithm performs an initialization routine. For a short period after power-on, the device calibrates itself and determines the direction of target rotation. Once the calibration routine is complete, the A19303 will transmit accurate speed and direction information.

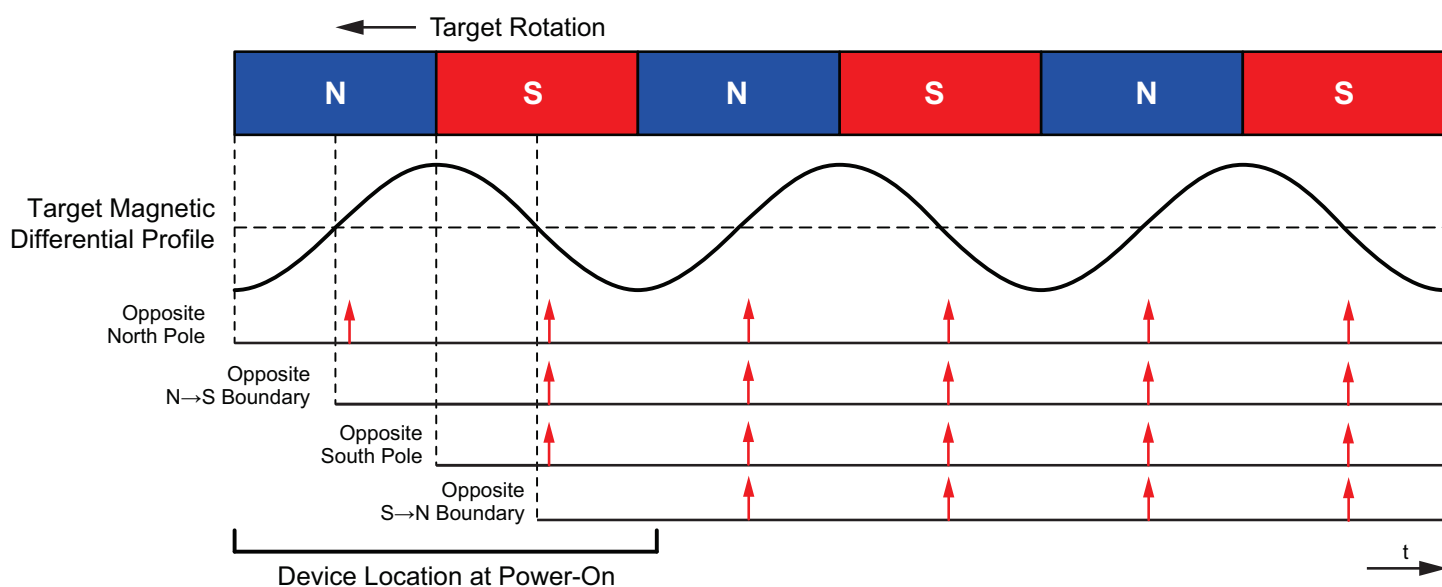


Figure 11: Calibration Behavior

### Direction Changes, Vibrations, and Anomalous Events

During normal operation, the A19303 will be exposed to changes in the direction of target rotation (Figure 12), vibrations of the target (Figure 13), and anomalous events such as sudden air gap changes.

During calibration, output pulses with direction information are immediately transmitted to the output. Depending on target design, air gap, and the phase of the target, direction may be momentarily incorrect. Following a direction change in running mode, direction changes are immediately transmitted to the output.

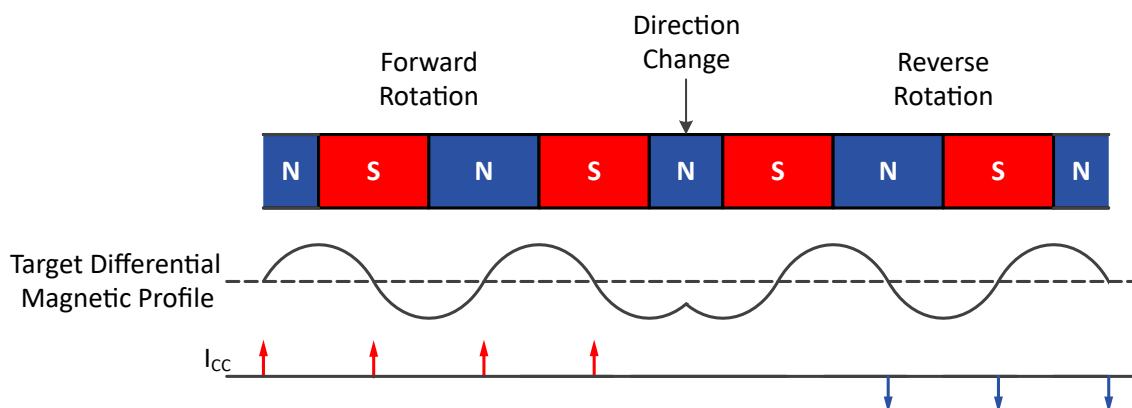


Figure 12: Direction Change Behavior (-xxHx variant)

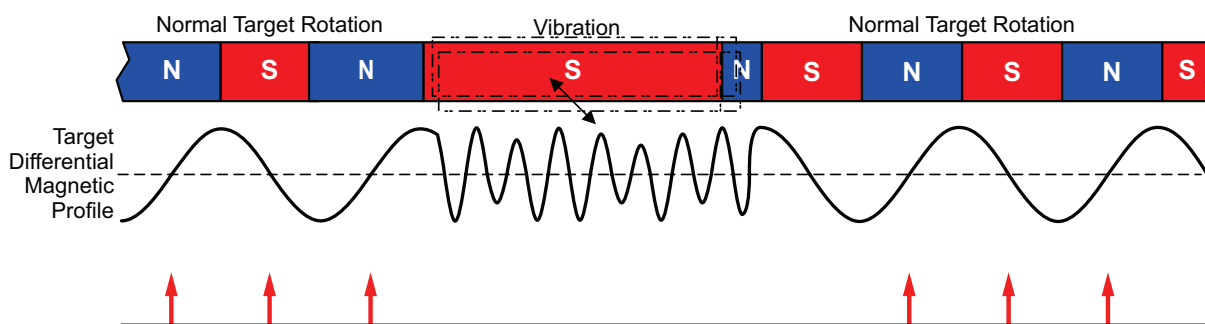


Figure 13: Vibration Behavior (-xxHx variant)

## POWER DERATING

The device must be operated below the maximum junction temperature of the device ( $T_{J(max)}$ ). Under certain combinations of peak conditions, reliable operation may require derating supplied power or improving the heat dissipation properties of the application. This section presents a procedure for correlating factors affecting operating  $T_J$ . (Thermal data is also available on the Allegro MicroSystems website.)

The Package Thermal Resistance ( $R_{\theta JA}$ ) is a figure of merit summarizing the ability of the application and the device to dissipate heat from the junction (die), through all paths to the ambient air. Its primary component is the Effective Thermal Conductivity (K) of the printed circuit board, including adjacent devices and traces. Radiation from the die through the device case ( $R_{\theta JC}$ ) is a relatively small component of  $R_{\theta JA}$ . Ambient air temperature ( $T_A$ ) and air motion are significant external factors, damped by overmolding.

The effect of varying power levels (Power Dissipation or  $P_D$ ), can be estimated. The following formulas represent the fundamental relationships used to estimate  $T_J$ , at  $P_D$ .

$$P_D = V_{IN} \times I_{IN} \quad (1)$$

$$\Delta T = P_D \times R_{\theta JA} \quad (2)$$

$$T_J = T_A + \Delta T \quad (3)$$

For example, given common conditions such as:  $T_A = 25^\circ\text{C}$ ,  $V_{CC} = 12\text{ V}$ ,  $I_{CC} = 7.15\text{ mA}$ , and  $R_{\theta JA} = 213^\circ\text{C/W}$ , then:

$$\begin{aligned} P_D &= V_{CC} \times I_{CC} = 12\text{ V} \times 7.15\text{ mA} = 85.8\text{ mW} \\ \Delta T &= P_D \times R_{\theta JA} = 85.8\text{ mW} \times 213^\circ\text{C/W} = 18.3^\circ\text{C} \\ T_J &= T_A + \Delta T = 25^\circ\text{C} + 18.3^\circ\text{C} = 43.3^\circ\text{C} \end{aligned}$$

A worst-case estimate,  $P_{D(max)}$ , represents the maximum allowable power level ( $V_{CC(max)}$ ,  $I_{CC(max)}$ ), without exceeding  $T_{J(max)}$ , at a selected  $R_{\theta JA}$  and  $T_A$ .

*Example:* Reliability for  $V_{CC}$  at  $T_A = 150^\circ\text{C}$ , package UB, using minimum-K PCB.

Observe the worst-case ratings for the device, specifically:  $R_{\theta JA} = 213^\circ\text{C/W}$ ,  $T_{J(max)} = 165^\circ\text{C}$ ,  $V_{CC(max)} = 24\text{ V}$ , and  $I_{CC(AVG)} = 16.6\text{ mA}$ .  $I_{CC(AVG)}$  is computed using  $I_{CC(HIGH)(max)}$ ,  $I_{CC(MID)(max)}$ , and  $I_{CC(LOW)(max)}$ , with an input signal frequency of  $f_{SIG(max)}$  (AK protocol).

Calculate the maximum allowable power level ( $P_{D(max)}$ ). First, invert equation 3:

$$\Delta T_{max} = T_{J(max)} - T_A = 165^\circ\text{C} - 150^\circ\text{C} = 15^\circ\text{C}$$

This provides the allowable increase to  $T_J$  resulting from internal power dissipation. Then, invert equation 2:

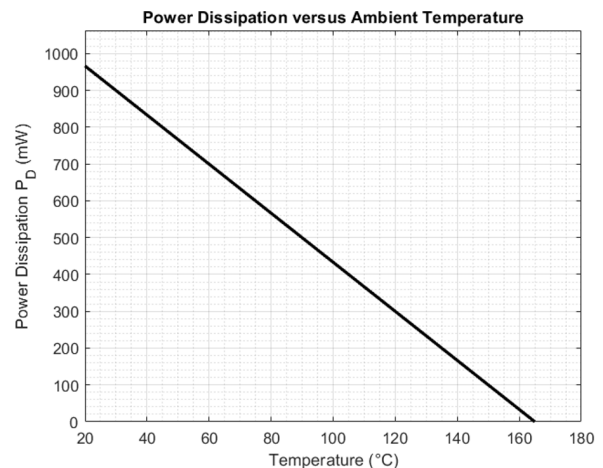
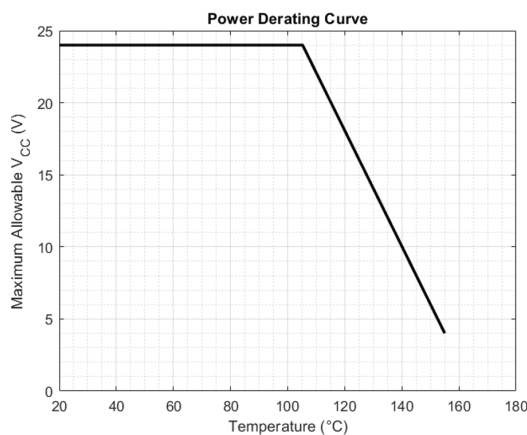
$$P_{D(max)} = \Delta T_{max} \div R_{\theta JA} = 15^\circ\text{C} \div 213^\circ\text{C/W} = 70.4\text{ mW}$$

Finally, invert equation 1 with respect to voltage:

$$V_{CC(est)} = P_{D(max)} \div I_{CC(AVG)} = 70.4\text{ mW} \div 16.6\text{ mA} = 4.2\text{ V}$$

The result indicates that, at  $T_A$ , the application and device can dissipate adequate amounts of heat at voltages  $\leq V_{CC(est)}$ .

Compare  $V_{CC(est)}$  to  $V_{CC(max)}$ . If  $V_{CC(est)} \leq V_{CC(max)}$ , then reliable operation between  $V_{CC(est)}$  and  $V_{CC(max)}$  requires enhanced  $R_{\theta JA}$ . If  $V_{CC(est)} \geq V_{CC(max)}$ , then operation between  $V_{CC(est)}$  and  $V_{CC(max)}$  is reliable under these conditions.





## Revision History

Number	Date	Description
–	March 9, 2023	Initial release
1	June 21, 2023	Updated Figure 7 (page 8)

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