

TI Designs: TIDA-01421

Automotive Brushed-Motor Ripple Counter Reference Design for Sensorless Position Measurement



Description

The demand to retain memory on the position of the seat, window, sliding door, mirror, lift-gate, and others driven by that motor has increased as small motors within the modern automotive vehicle continue to evolve. Existing solutions utilize multiple magnetic sensors attached to the body of a motor to provide a feedback loop to the motor control module.

A sensorless approach provides redundancy for existing solutions and, in some cases, removes the requirement for motors with sensors attached. The sensorless approach has become increasingly popular through the implementation of an in-line, current-sense signal-conditioning circuit. This design provides a solution that is easily modifiable for many automotive motor systems that control position measurement.

Resources

TIDA-01421	Design Folder
INA240-Q1	Product Folder
TLV2316-Q1	Product Folder
LMV7275-Q1	Product Folder

Features

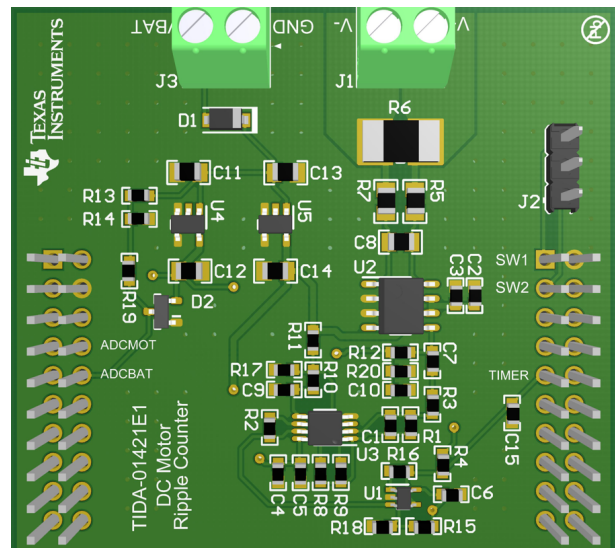
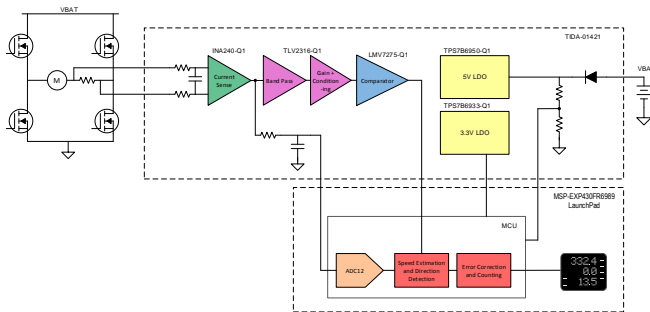
- Configurable for Many DC Motor Solutions
- Wide Common Mode Input Range for In-line Motor Current Sensing
- Operational for Typical 9-V to 18-V Battery Supply
- Simple Interfacing With MSP430™ LaunchPad™ Development Kit for Interfacing and Digital Capture
- Highly Accurate Test Solution

Applications

- [Memory Seats](#)
- [Power Windows](#)
- [Lift Gate and Power Trunk](#)
- [Side Mirrors](#)



[ASK Our E2E Experts](#)





An IMPORTANT NOTICE at the end of this TI reference design addresses authorized use, intellectual property matters and other important disclaimers and information.

1 System Description

Motor position memory is being applied in more areas of the automotive vehicle including configuration and comfort settings for different driver profiles as well as diagnostics for more efficient and smarter control of the motor. The demand for more cost-efficient and easily-configurable solutions for many different motor types has increased. For example, the seats in a vehicle can feature many axes of movement and ergonomic adjustment all controlled by individual motors. Existing memory solutions for these seats require motors with magnetic Hall-effect sensors plus the additional extra wiring for each sensor. Sensorless position measurement reduces the requirement for this many sensors and wiring by sensing the in-line motor current at the seat control module itself.

A sensorless approach is possible for brushed DC motors due to the effect that the back-electromagnetic force (BEMF) has on the motor current seen entering the motor. As the motor rotates, the impedance seen by the BEMF periodically changes due to the nature of the DC motor brushes making contact with multiple poles of the motor and effectively shorting some of the motor windings. This change in impedance changes the measured current in a very periodic pattern proportional to the actual speed of the motor.

This system provides a way to measure this varying in-line motor current, filter and condition the resultant signal, then provide a 3.3-V digital logic level series of rising and falling edges for a digital processor to count and analyze for accuracy and feedback to the main motor controller. With some simple changes in current sense resistor values, gain settings, and filter bandwidths, this solution can quickly be modified for use with many small motor systems.

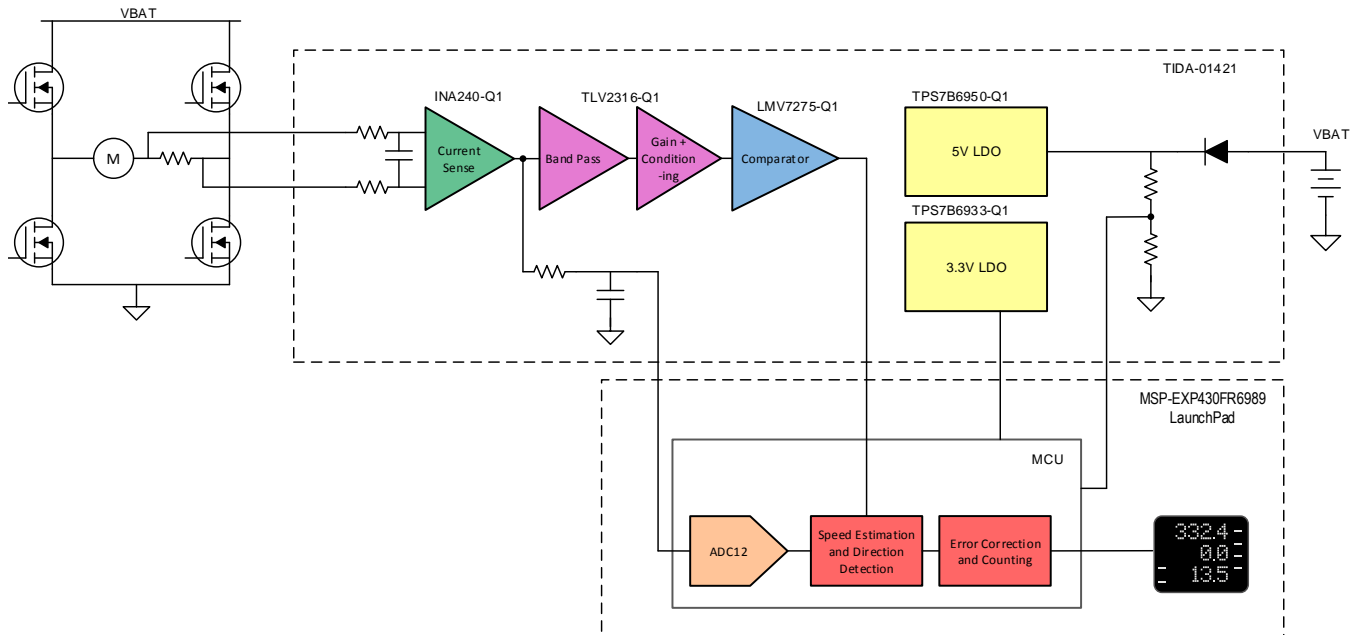
1.1 Key System Specifications

Table 1. Key System Specifications

PARAMETER	SPECIFICATIONS
Normal power supply operating range	9 V to 18 V
Common mode input range	-4 V to 80 V
Operating ripple frequency range	100 Hz to 1.3 kHz
Maximum motor current	±16 A

2 System Overview

2.1 Block Diagram



2.2 Highlighted Products

2.2.1 INA240-Q1

The INA240-Q1 is a wide common-mode range, high-accuracy, bidirectional current shunt monitor. With a -4 V to 80 V common-mode range, the device can sense within all typical operating voltage ranges for a DC motor application as well as be protected from typical automotive overvoltage and undervoltage fault conditions. The device features a very large common mode rejection ratio of 120 dB , providing an accurate, low noise measurement even in speed controlled, PWM driven motor solutions. The accuracy and drift performance of this device allow for minimal error when measuring the motor ripples. The device can operate from a single supply from 2.7 V to 5.5 V .

2.2.2 TLV2316-Q1

The TLV2316-Q1 is a dual, low-voltage, rail-to-rail general-purpose operational amplifier. The robust design provides ease-of-use to the circuit designer: a unity-gain stable, integrated radio frequency (RF) and electromagnetic interference (EMI) rejection filter, no phase reversal in overdrive condition, and high electrostatic discharge protection. This dual operational amplifier (op amp) is utilized for the two-stage signal conditioning before the output comparator.

2.2.3 LMV7275-Q1

The LMV7275-Q1 is a single rail-to-rail input low-power comparator and features an open-drain output for correct level shifting to interface with a typical 3.3 V microcontroller (MCU) GPIO. The tiny SC-70 package is ideal for low-voltage, low-power, and space-critical designs.

2.2.4 TPS7B69-Q1

The TPS7B69-Q1 is a family of high-voltage, low quiescent current low-dropout linear regulators (LDOs) available in both 3.3 V and 5 V output options. The LDOs power all of the devices on this design, but also provide the necessary 3.3 V to power an MCU.

2.3 System Design Theory

The current measured in-line with the brushed motor has both a large-amplitude, very-low frequency DC component and a small-amplitude, high-frequency AC component. Both of these components must be considered when choosing the correct configuration for this design.

The total current seen in-line with the motor can be solved in [Equation 1](#) as:

$$I_{\text{MOTOR}} = \frac{(V_{\text{ARMATURE}} - V_{\text{BEMF}})}{R_{\text{ARMATURE}}} \quad (1)$$

where,

- V_{ARMATURE} is the DC voltage applied across the motor armatures,
- V_{BEMF} is the BEMF generated by the motor during operation,
- R_{ARMATURE} is the equivalent series resistance seen between the armatures.

The DC-component current is the main source driving the inductive load of the motor. The motor load varies widely depending on the necessary torque to drive the mechanical motor assembly. In high-torque automotive applications like windows and seats, the steady-state current delivered to these loads can be in the range of 10 A to 20 A.

The AC-component current is created by the sinusoidal BEMF generated by the motor, as well as the periodic changes in motor coil impedance due to the motor brushes shorting adjacent commutator poles. The amplitude and frequency of this component also varies both on the mechanical load on the motor and the design of the motor itself. This AC component contains the ripple that the user should measure and is directly proportional to the actual motor speed. Every ripple corresponds to a commutator pole rotation across the armature brushes. The total sub-divisions of a full rotation can be captured by knowing the total number of poles in the motor.

2.3.1 PCB Size and Form Factor

The design includes daughtercard jumpers for connection to an MSP430™ LaunchPad™ to easily interface with an MCU for ripple counting. This requirement is responsible for the necessary 2 in of width on the PCB, after which all other layout considerations were made. The final board design is 2.1 in × 1.9 in after making all the necessary design considerations. The PCB is two-sided and components are only placed on the top side.

The total PCB area is much less in a production design because the large connectors for the battery, in-line motor sense, and the MSP430 LaunchPad jumpers are not necessary. The local linear regulators on the board are likely to be shared with other components on the motor driver controller assembly. The current sense, signal conditioning, comparator devices, and associated passive components on this design were kept as close together as possible to minimize the board space they use, which indicates a typical production-design use case.

2.3.2 Current Sense Amplifier Stage

The total motor current can be measured by sensing on the low side of the driver bridge, or in-line with the motor. Sensing current on the low side introduces additional impedances and layout concerns to retain accuracy of the ripple signal. Additionally, to measure ripples in both directions, low-side sensing requires a sensing amplifier on both sides of the full bridge, which increases the total component count. When measuring in-line with the motor, bidirectional measurement with a single device is possible. However, there are design concerns that must be made to ensure an accurate output for the signal conditioning stage.

The MOSFET bridge driving the motor in an automotive application is typically powered directly by the automotive battery. The typical supply range of the battery is 9 V to 14 V; however, some typical automotive conditions can lead to operating voltages of 6 V to 40 V. Note that, when choosing a current sense amplifier, it must be able to withstand common-mode voltages across this entire range to prevent functional damage to the device. The INA240-Q1 has a very-wide common mode range of –4 V to 80 V, which is very capable of withstanding all the possible common-mode conditions expected for the design.

The INA240-Q1 can also be biased to provide a bidirectional output to measure both motor rotational directions. The output stage of the INA240-Q1 utilizes two reference pins, REF1 and REF2, to bias the output. By tying REF2 to the supply voltage V+ and REF1 to ground, the output of the INA240-Q1 rests at the mid-supply rail voltage. In this application, the supply voltage is 5 V; therefore, depending on the motor direction, the output is between 0 V to 2.5 V or 2.5 V to 5 V. This output voltage can be calculated in Equation 2 as:

$$V_{OUT} = I_{MOTOR} \times R_{SENSE} \times GAIN + 2.5 V \quad (2)$$

The maximum current to be sensed can be used to choose the correct value for the sense resistor. For this design, a maximum of 16 A has been chosen. With the INA240-Q1 gain of 50 V/V and 4.9 V as the maximum output voltage, R_{SENSE} can be solved in Equation 4 by using the previous Equation 2:

$$R_{SENSE} = \frac{(4.9 V - 2.5 V)}{(16 A \times 50 V/V)} = 3 m\Omega \quad (4)$$

The sense resistor must be sized properly for handling a very large amount of power. A size 2512 resistor rated for 3 W has been chosen for this design.

A simple common-mode RC input filter can be used at the input of the INA240-Q1 device to reduce the noise generated by high-frequency motor brush and potential PWM switching noise.

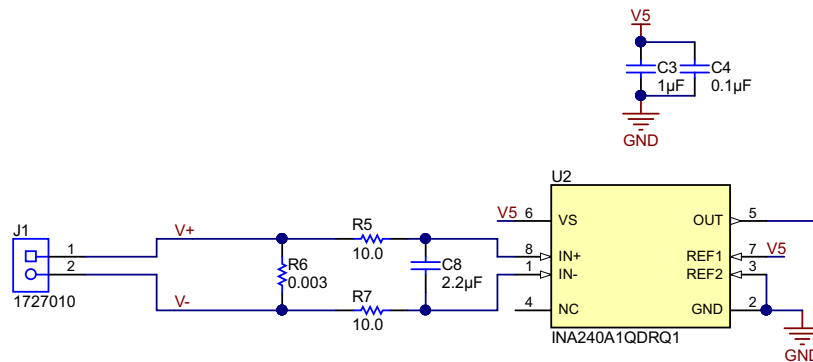


Figure 1. Schematic of Current Sense Amplifier Stage

2.3.3 Band-Pass Filter Stage

The output of the current sense amplifier is filtered with an active band-pass filter to look at the motor ripple signal and remove additional noise and the DC-component variance. The ripple frequency that must be measured largely depends on the typical rotations per minute (RPM) of the motor and the total number of commutator poles. For this design, the filter is limited to about 100 Hz to 1.3 kHz. An inverting amplifier topology has been used to allow for biasing before the next amplifier stage. The simple TLV2316-Q1 has been chosen for its low-voltage operation and rail-to-rail input. Standard op-amp design guidelines pertaining to power supply decoupling and layout considerations are followed.

Figure 2 shows a schematic of the band-pass filter stage.

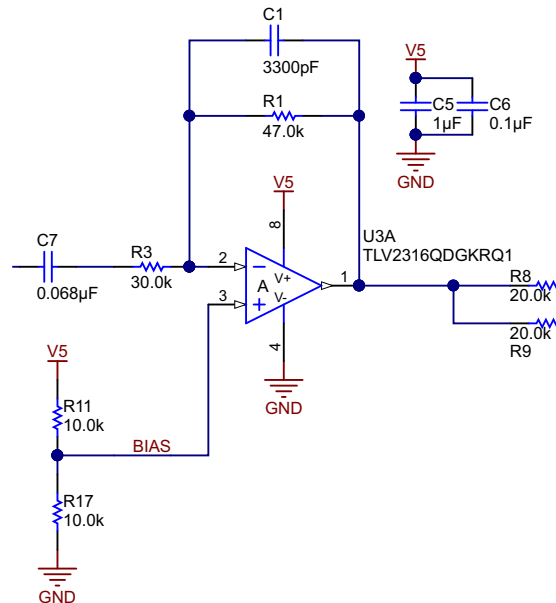


Figure 2. Schematic of Band-Pass Filter Stage

2.3.4 Differential Amplifier for DC-Bias Adjustment

The main goal for the signal conditioning amplifier stages is to generate a clean, low-noise AC signal that can be measured by the final comparator to generate a 0-V to 3.3-V square wave with a switching frequency equal to the motor ripple frequency. Biasing the sinusoidal ripple waveform around the comparator reference point is the preferred method for generating this square wave. The previous filter stage starts this process but the specific filter requirements and operating frequency range lead to some additional necessary steps in the design to ensure proper biasing for the comparator stage.

The high-pass portion of the previous filter stage is configured to approximately 100 Hz, which requires a fairly large RC filter to achieve. This filter also generates a huge time constant that shows its effects on the signal during the very large initial spike in motor current at start-up. This current spike is large enough and slow enough to not be filtered out by the high-pass circuit, and the value for the RC time-constant means that the low-frequency DC component of the signal does not settle to a resting point very quickly. The motor begins to turn during this current spike and ripples are generated. The comparator misses multiple ripples for counting if this change in the effective DC-bias point of the signal is left to remain.

Figure 3 shows the initial spike in current (yellow waveform) and the resultant signal after the differential amplifier stage (green waveform).

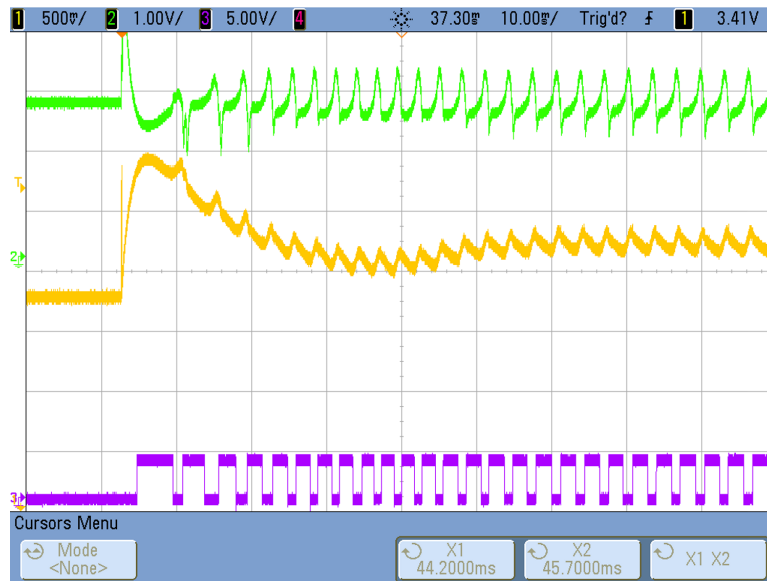


Figure 3. Oscilloscope Image of Initial Current Spike

This low-speed, high-amplitude current spike is removed from the signal with the unique use of a differential amplifier stage. The output of the band-pass filter is used for both the positive and negative inputs of the amplifier, but one side of the amplifier is very slightly filtered with a low-pass RC filter. This small RC filter causes a very slight phase shift and attenuation of the ripple signal, but has very little effect on the large DC-bias spike. The common mode essentially stays the same on both inputs and is negated by the amplifier. The phase and amplitude difference between the AC signals on both inputs leads to a differential output retaining the ripple frequency component. A very large differential gain of 55 V/V provides a large signal swing of the signal difference and a DC re-biasing around 2.5 V allows the output of this stage to have a very clean and consistent bias point for the signal being measured by the comparator.

Figure 4 shows the schematic for the differential amplifier stage of the signal chain. The BIAS signal comes from the resistor divider used to bias the previous band-pass filter stage.

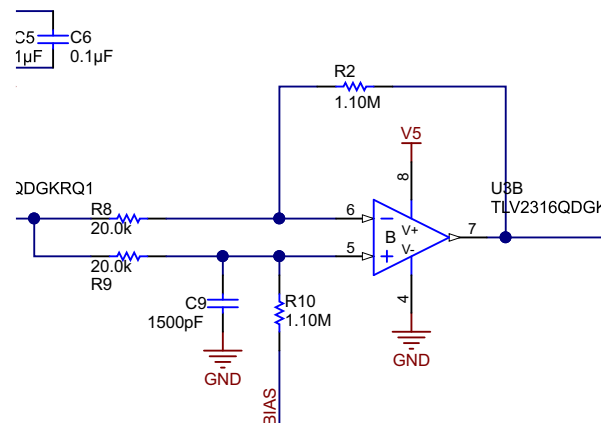
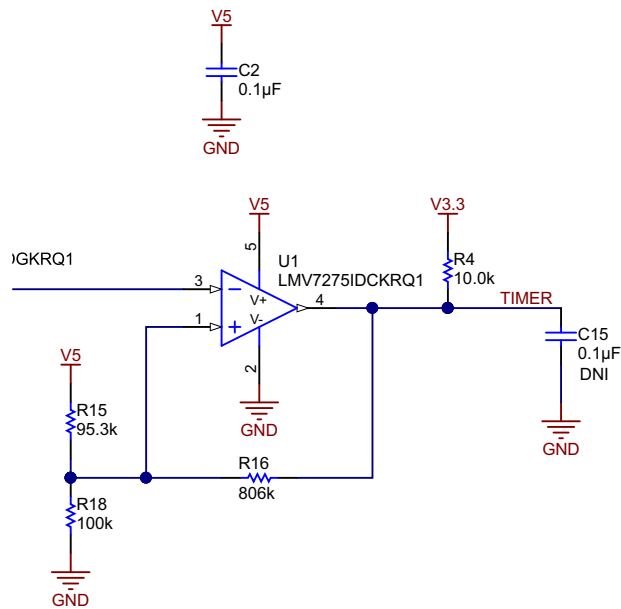


Figure 4. Schematic of Differential Amplifier Stage

2.3.5 Comparator Stage

The comparator stage of the design generates the final 0- to 3.3-V signal used by the MCU for counting. An open-drain output device has been chosen to create the proper 3.3-V levels for input into a typical MCU GPIO. An inverting hysteresis topology (see Figure 5) has been utilized to reduce the effects of noise on the input of the comparator.


Figure 5. Schematic of Comparator Stage

For an inverting open-drain topology, the DC thresholds with hysteresis can be determined in [Equation 5](#) and [Equation 6](#) as:

$$V_{TL} = \left((R_{18} \parallel R_{16}) \times \frac{V_{CC}}{((R_{18} \parallel R_{16}) + R_{15})} \right) + \left((R_{15} \parallel R_{18}) \times \frac{V_{OL}}{((R_{15} \parallel R_{18}) + R_{16})} \right) \quad (5)$$

$$V_{TH} = \left((R_{18} \parallel R_{16}) \times \frac{V_{CC}}{((R_{18} \parallel R_{16}) + R_{15})} \right) + \left((R_{15} \parallel R_{18}) \times \frac{V_{OH}}{((R_{15} \parallel R_{18}) + R_{16})} \right) \quad (6)$$

For this application, the $V_{OL} = 0$ V causes a slight offset to the centering of the main biasing point for the comparator. Because the AC signal is centered around 2.5 V, the comparator reference point in combination with the feedback resistor is adjusted to allow the V_{TL} and V_{TH} to be centered around 2.5 V as well.

2.3.6 Motor Power Supply and Current Monitoring

This design includes both the power supply and motor current as the output pin on the LaunchPad jumpers for additional monitoring and control. These pins can be used to recognize faults like overvoltage and overcurrent conditions and can also be used to help correct for errors in the ripple counter.

The battery voltage measures directly after the reverse protection diode. This voltage is then scaled down to meet the input range of a typical 3.3-V MCU. For this design, normal operation is considered 9 V to 18 V, so 18 V is scaled to equal 3 V. Overvoltage conditions can still be monitored up to 19.7 V for the configured voltage divider. Protection diodes and a current limiting resistor have been added on this line to protect the MCU from damage if the battery voltage exceeds 19.7 V. A resistor divider at the output of the current sense amplifier is used to attenuate the signal to meet the maximum 3.3-V input requirements of the MCU ADC.

Assorted mechanical effects on the motor, including brush noise and unusual loading conditions, can cause unwanted effects on the measured signal current. These effects can lead to excessive false or missed triggering of the output comparator. Error correction can be performed in the MCU relying on basic estimations of the motor speed, which are based on the power supply voltage and motor DC current. The motor speed can then be translated to a proportional ripple frequency and compared to the actual ripple frequency. Comparing the estimated ripple frequency to the actual frequency allows for smart error correction of the running ripple count.

Use [Equation 7](#) and the frequency-dependent equation for the BEMF voltage to estimate the motor speed:

$$V_{BEMF} = \omega \times K_e \tag{7}$$

where,

- ω is the motor speed,
- K_e is the motor constant (taken from the data sheet of the motor).

Replacing V_{BEMF} in the previous and solving for ω leads to Equation 8:

$$\omega = \frac{V_{ARMATURE} - (I_{MOTOR} \times R_{ARMATURE})}{K_e} \tag{8}$$

$R_{ARMATURE}$ and K_e are known parameters of the motor. $V_{ARMATURE}$ is the motor supply voltage and I_{MOTOR} is the motor DC current, which are both values that can be captured by the MCU ADC. The motor current value can also be used to infer the direction of the output for adding or subtracting counts from the total during operation.

Figure 6 shows the circuitry used to monitor these signals.

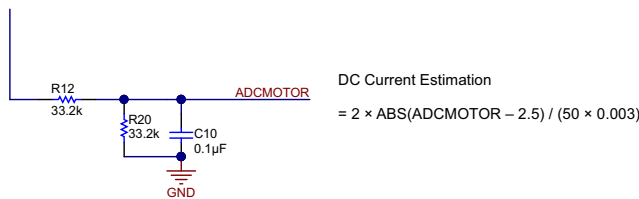


Figure 6. Schematic of Monitoring Connections (A)

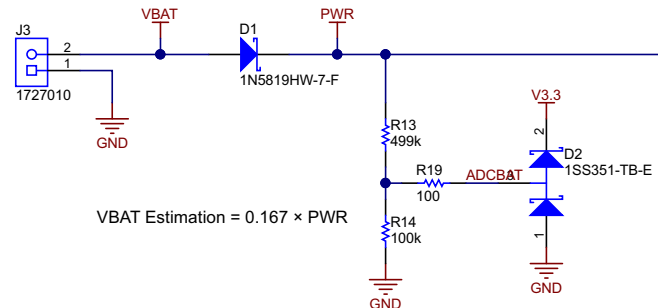


Figure 7. Schematic of Monitoring Connections (B)

2.3.7 3.3-V and 5-V Regulators

This design uses two linear dropout regulators (LDO) for the necessary 3.3- and 5-V voltage supply. These devices have a wide input voltage for operation and protection for the entire possible battery voltage range and all possible fault conditions.

The only design consideration to make for these devices is sizing the capacitors. The data sheet recommends that the input capacitor be larger than 0.1 μ F and the output capacitor should be between 2.2 μ F and 100 μ F. A 4.7- μ F value was used as the input capacitor and 2.2 μ F was used as an output capacitor on both devices.

Figure 8 shows the configuration of these LDOs.

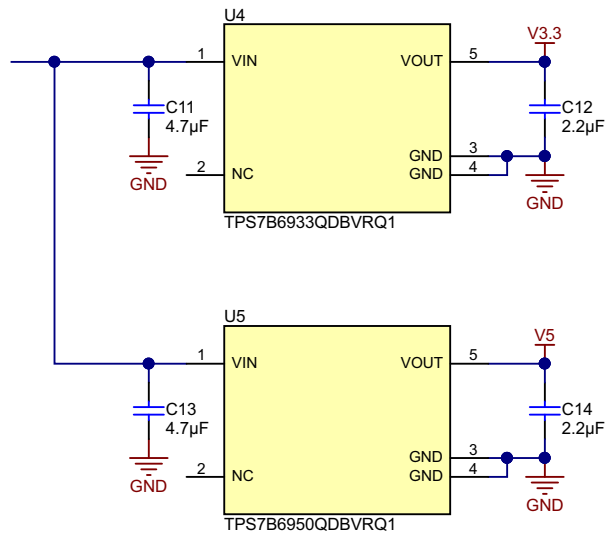


Figure 8. Schematic of LDO Configuration

2.3.8 LaunchPad™ Connectors

To interface with a typical MSP430 Launchpad, the appropriate 20-pin jumpers are used. The following signals are tied to these jumpers:

- 3.3 V for powering the MSP430
- Output of the comparator tied to one of the timer counter pins of the MSP430 for both counting of the ripples and to use the TimerB peripheral to measure the frequency of the ripples for error correction
- Battery supply (ADCBAT) and DC motor current (ADCMOTOR) for both error correction and fault detection
- Two GPIO connections tied to jumper J2 for general purpose use, such as button press signals to detect motor direction

The specific pinout is chosen based on the featured peripherals of the MSP-EXP430FR6989. This board is chosen for very basic functional tests of design from a digital standpoint.

[Figure 9](#) shows the schematic connections to the LaunchPad jumpers.

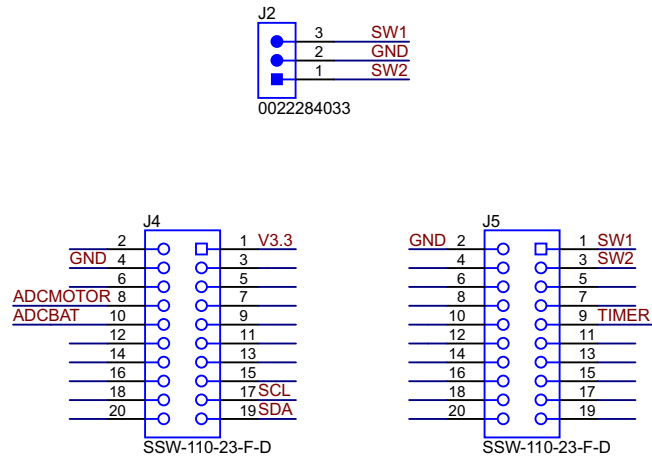


Figure 9. Schematic of MSP430™ LaunchPad™ Jumper Configuration

3 Getting Started Hardware

The larger 20-pin connectors J4 and J7 can interface with a typical MSP430 LaunchPad. The MSP-EXP430FR6989 was used for testing of the design to allow the ripple count to be output to the onboard LCD screen of the LaunchPad.

Jumper J3 provides a connection for a power supply. Jumper J1 is the connection to place the current sense amplifier in-line with the motor. The final jumper, J2, is a simple connection to the LaunchPad GPIOs for button-press detection or other triggering. [Table 2](#) lists details on all the connections.

Table 2. Table of all Jumper Connections

JUMPER	PURPOSE
J1	In-line motor current sense connection
J3	Battery power supply connection
J2	MSP430™ GPIO connection for button press, triggering, and so forth
J4, J7	MSP-EXP430FR6989 LaunchPad™ connectors

Figure 10 shows a rendering of the top side of the PCB and Figure 11 shows the PCB attached to the LaunchPad.

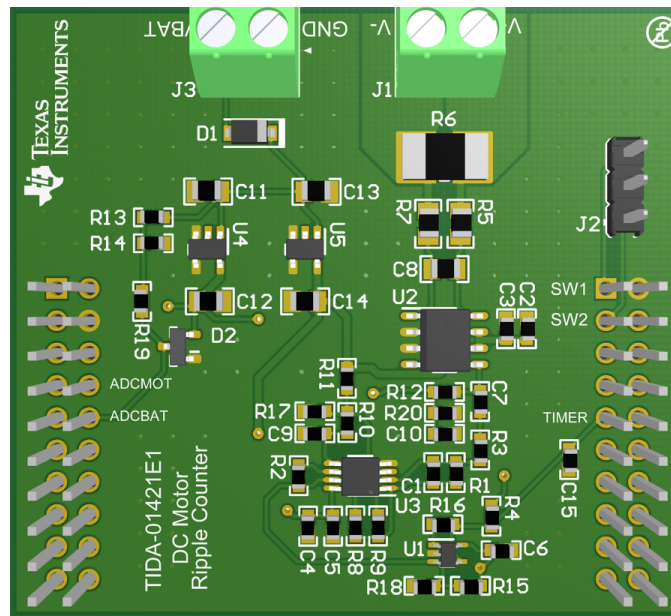


Figure 10. 3D Rendering of Top Side PCB

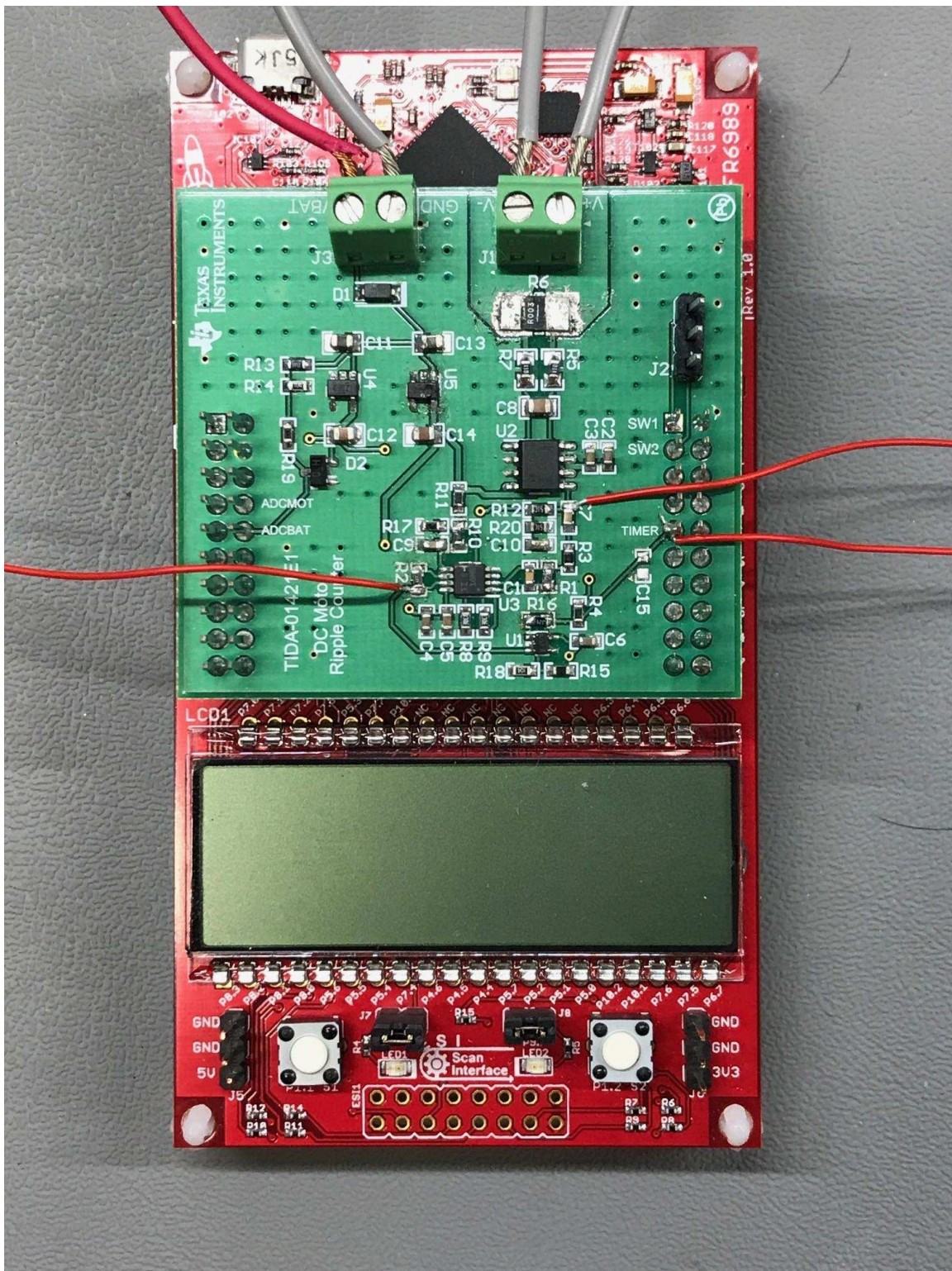


Figure 11. TIDA-01421 Attached to MSP-EXP430FR6989 LaunchPad™

4 Testing and Results

This design was tested in conjunction with the motor driver design of TIDA-01330, a two-axis seat motor driver design. For testing, this board drove the motors on a standard car seat assembly. The ripple counter design was inserted in-line with the motor driver output for both the forward-backward axis as well as the up-down axis motors.

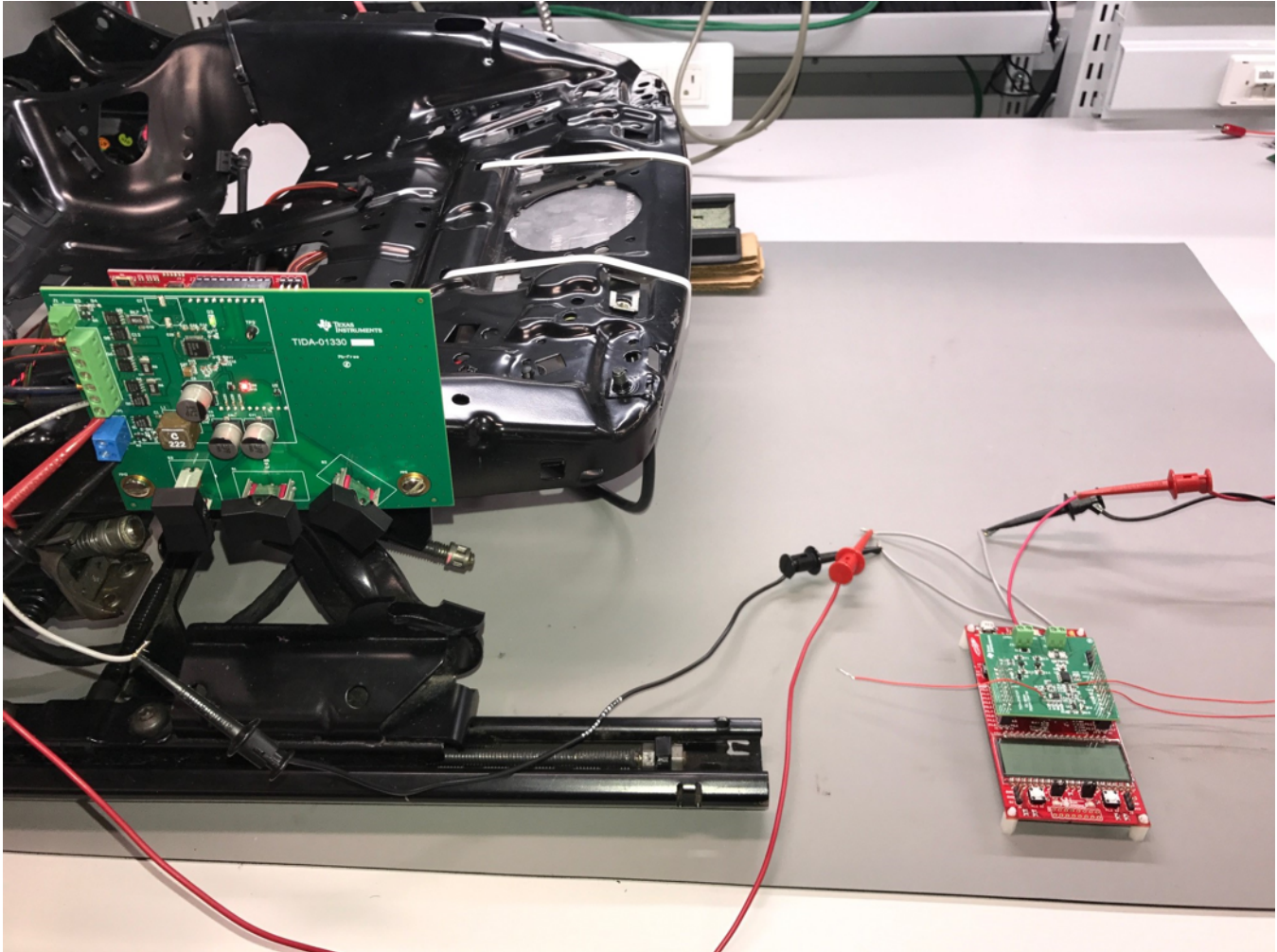


Figure 12. Test Setup of TIDA-01421 Tested in Combination of Automotive Seat Assembly and TIDA-01330

4.1 Forward-Backward Motor Operation

In all of the following results, the yellow waveform is the output of the INA240-Q1, the green waveform is the output of the differential-amplifier stage, and the purple waveform is the output of the comparator.

4.1.1 Normal Operation at 12 V

The initial tests show the results of the ripple counter when measuring the forward-backward motor at 12 V.

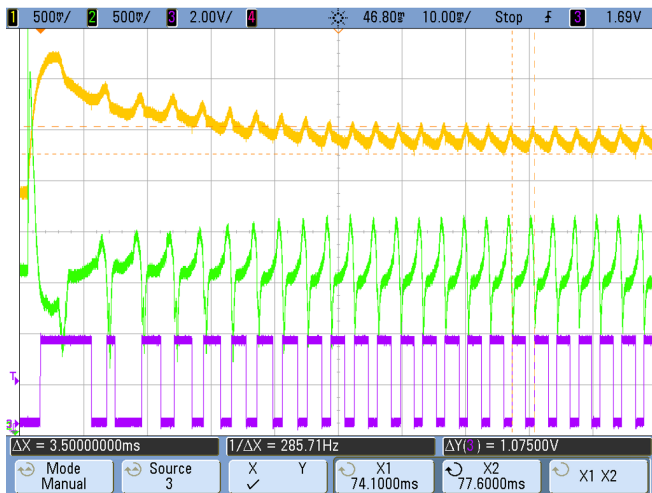


Figure 13. Forward Motor Operation at 12 V

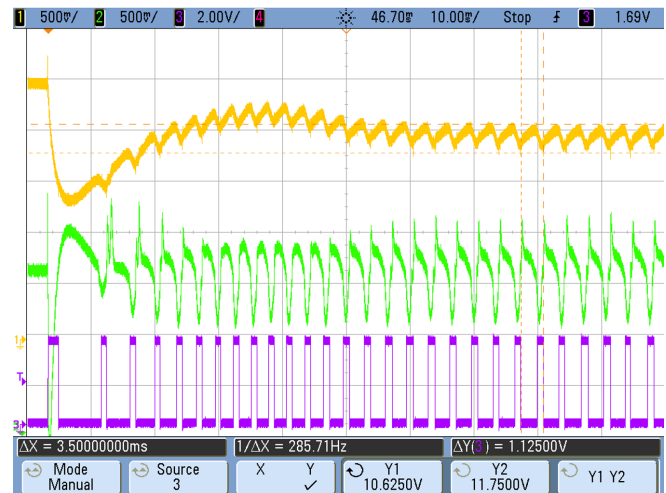


Figure 14. Backward Motor Operation at 12 V

4.1.2 Operation at 9 V and 18 V

The next set of results show the change in motor speed based on a change in the motor supply voltage at 9 V and 18 V.

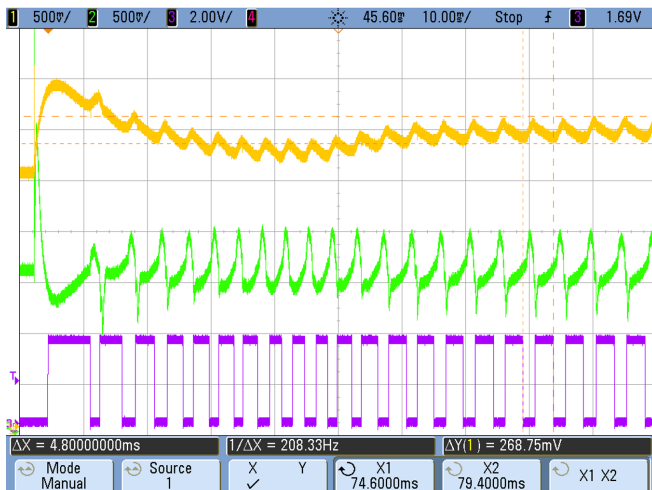


Figure 15. Forward Motor Operation at 9 V

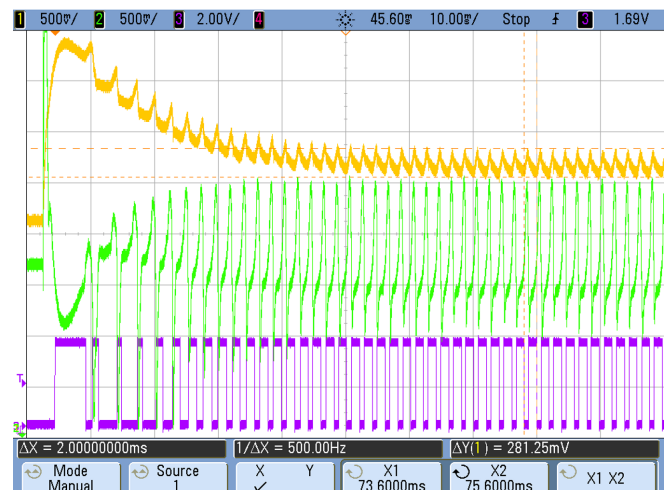


Figure 16. Forward Motor Operation at 18 V

4.1.3 Operation With Added Weight on Seat Assembly

The final set of results show the effects of adding 60 pounds of additional weight on the seat assembly to increase torque on the motor.

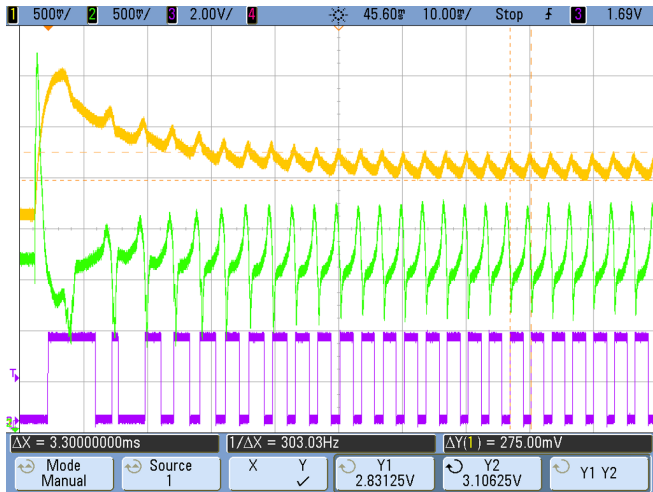


Figure 17. Forward Motor Operation at 12 V With 60 Pounds of Added Weight

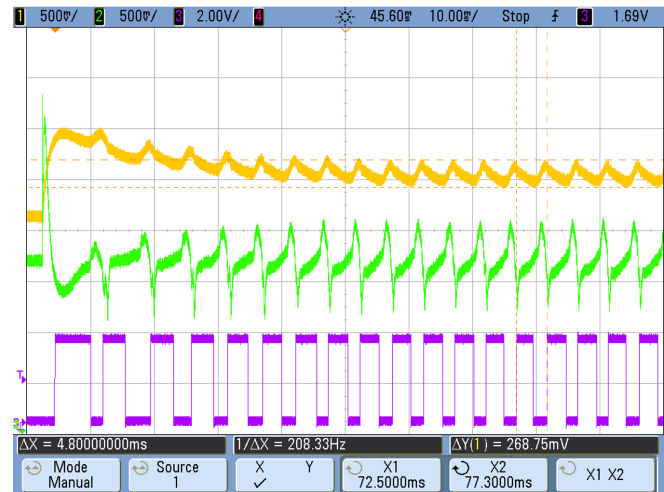


Figure 18. Forward Motor Operation at 9 V With 60 Pounds of Added Weight

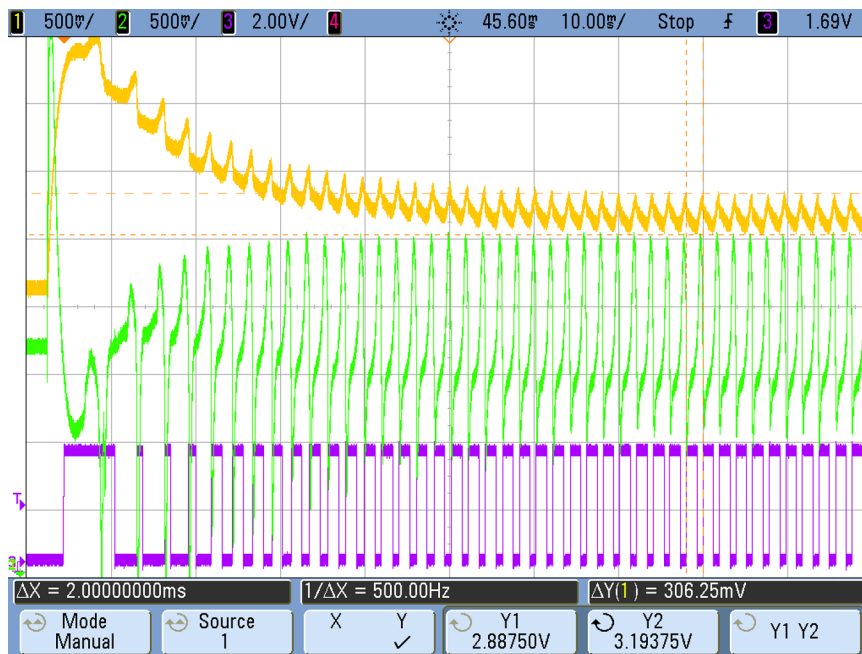


Figure 19. Forward Motor Operation at 18 V With 60 Pounds of Added Weight

4.2 Up-Down Motor Operation

4.2.1 Normal 12-V Operation

The initial tests show the performance of the ripple counter when measuring the up-down motor at 12 V.

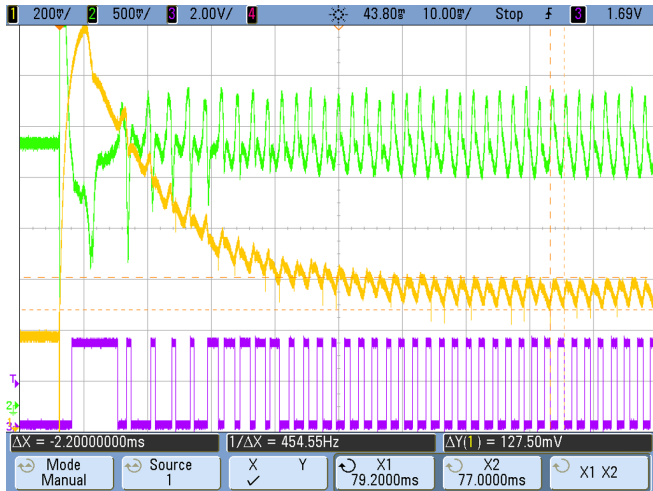


Figure 20. Upward Motor Operation at 12 V

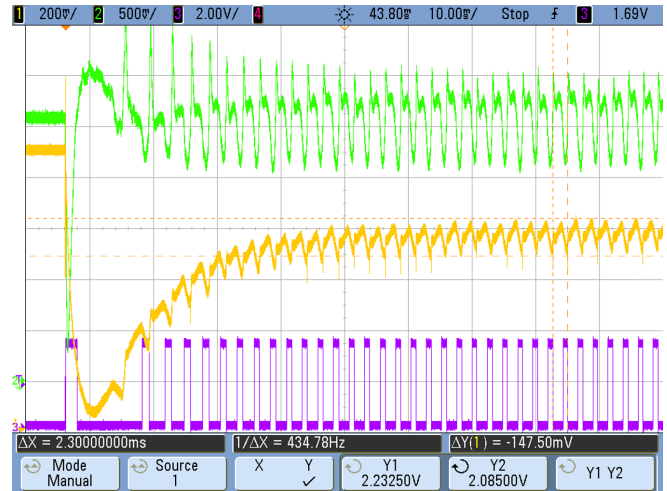


Figure 21. Downward Motor Operation at 12 V

4.2.2 Operation at 9 V and 18 V

The next set of results show the change in motor speed based on a change in motor supply at 9 V and 18 V.

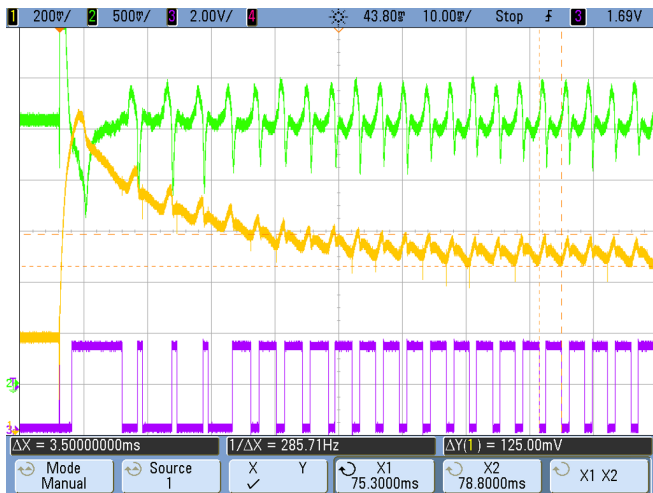


Figure 22. Upward Motor Operation at 9 V

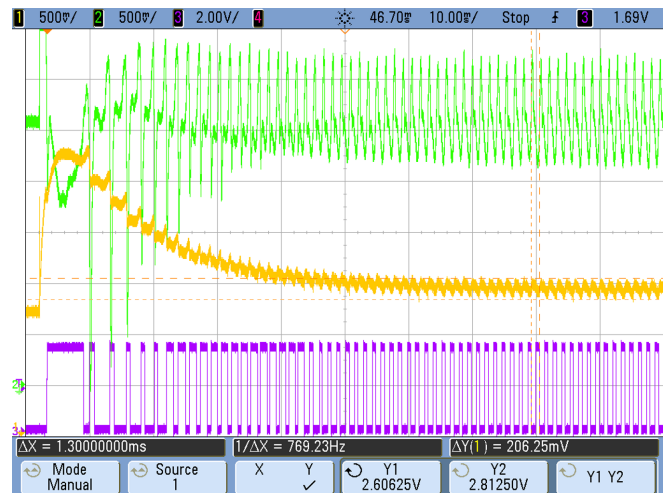


Figure 23. Upward Motor Operation at 18 V

4.2.3 Operation With Added Weight on Seat Assembly

The final set of results show the effects of adding 60 pounds of additional weight on the seat assembly to increase torque on the motor.



Figure 24. Upward Motor Operation at 12 V With 60 Pounds of Added Weight

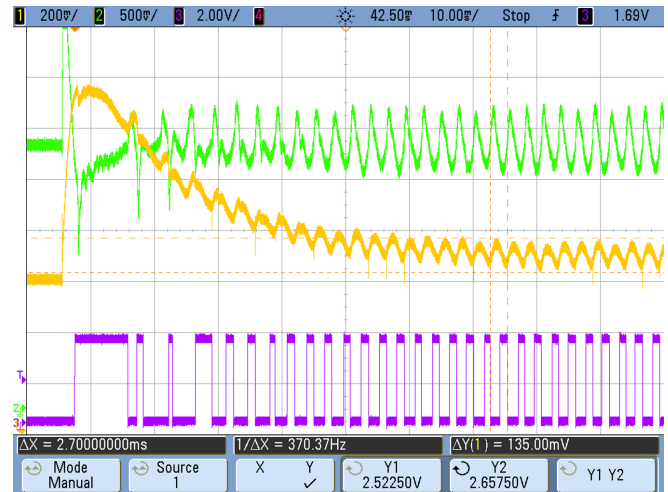


Figure 25. Upward Motor Operation at 9 V With 60 Pounds of Added Weight

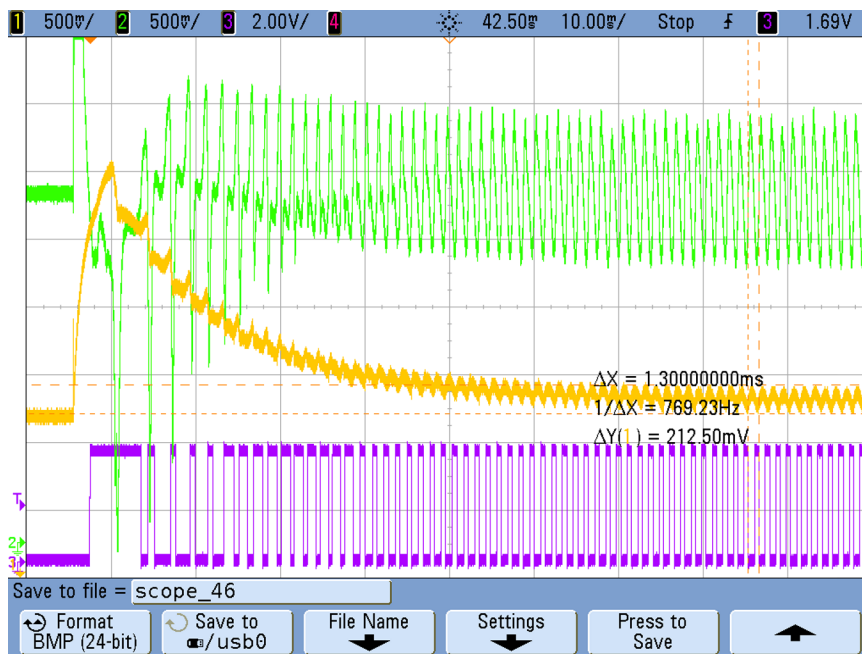


Figure 26. Upward Motor Operation at 18 V With 60 Pounds of Added Weight

5 Design Files

5.1 Schematics

To download the schematics, see the design files at [TIDA-01421](#).

5.2 Bill of Materials

To download the bill of materials (BOM), see the design files at [TIDA-01421](#).

5.3 PCB Layout Recommendations

5.3.1 Layout Prints

To download the layer plots, see the design files at [TIDA-01421](#).

5.4 Altium Project

To download the Altium project files, see the design files at [TIDA-01421](#).

5.5 Gerber Files

To download the Gerber files, see the design files at [TIDA-01421](#).

5.6 Assembly Drawings

To download the assembly drawings, see the design files at [TIDA-01421](#).

6 Software Files

To download the software files, see the design files at [TIDA-01421](#).

7 Trademarks

MSP430, LaunchPad are trademarks of Texas Instruments.
All other trademarks are the property of their respective owners.

Revision History

NOTE: Page numbers for previous revisions may differ from page numbers in the current version.

Changes from Original (July 2017) to A Revision	Page
• Changed all instances of INA282-Q1 to INA240-Q1	3

IMPORTANT NOTICE FOR TI DESIGN INFORMATION AND RESOURCES

Texas Instruments Incorporated ("TI") technical, application or other design advice, services or information, including, but not limited to, reference designs and materials relating to evaluation modules, (collectively, "TI Resources") are intended to assist designers who are developing applications that incorporate TI products; by downloading, accessing or using any particular TI Resource in any way, you (individually or, if you are acting on behalf of a company, your company) agree to use it solely for this purpose and subject to the terms of this Notice.

TI's provision of TI Resources does not expand or otherwise alter TI's applicable published warranties or warranty disclaimers for TI products, and no additional obligations or liabilities arise from TI providing such TI Resources. TI reserves the right to make corrections, enhancements, improvements and other changes to its TI Resources.

You understand and agree that you remain responsible for using your independent analysis, evaluation and judgment in designing your applications and that you have full and exclusive responsibility to assure the safety of your applications and compliance of your applications (and of all TI products used in or for your applications) with all applicable regulations, laws and other applicable requirements. You represent that, with respect to your applications, you have all the necessary expertise to create and implement safeguards that (1) anticipate dangerous consequences of failures, (2) monitor failures and their consequences, and (3) lessen the likelihood of failures that might cause harm and take appropriate actions. You agree that prior to using or distributing any applications that include TI products, you will thoroughly test such applications and the functionality of such TI products as used in such applications. TI has not conducted any testing other than that specifically described in the published documentation for a particular TI Resource.

You are authorized to use, copy and modify any individual TI Resource only in connection with the development of applications that include the TI product(s) identified in such TI Resource. NO OTHER LICENSE, EXPRESS OR IMPLIED, BY ESTOPPEL OR OTHERWISE TO ANY OTHER TI INTELLECTUAL PROPERTY RIGHT, AND NO LICENSE TO ANY TECHNOLOGY OR INTELLECTUAL PROPERTY RIGHT OF TI OR ANY THIRD PARTY IS GRANTED HEREIN, including but not limited to any patent right, copyright, mask work right, or other intellectual property right relating to any combination, machine, or process in which TI products or services are used. Information regarding or referencing third-party products or services does not constitute a license to use such products or services, or a warranty or endorsement thereof. Use of TI Resources may require a license from a third party under the patents or other intellectual property of the third party, or a license from TI under the patents or other intellectual property of TI.

TI RESOURCES ARE PROVIDED "AS IS" AND WITH ALL FAULTS. TI DISCLAIMS ALL OTHER WARRANTIES OR REPRESENTATIONS, EXPRESS OR IMPLIED, REGARDING TI RESOURCES OR USE THEREOF, INCLUDING BUT NOT LIMITED TO ACCURACY OR COMPLETENESS, TITLE, ANY EPIDEMIC FAILURE WARRANTY AND ANY IMPLIED WARRANTIES OF MERCHANTABILITY, FITNESS FOR A PARTICULAR PURPOSE, AND NON-INFRINGEMENT OF ANY THIRD PARTY INTELLECTUAL PROPERTY RIGHTS.

TI SHALL NOT BE LIABLE FOR AND SHALL NOT DEFEND OR INDEMNIFY YOU AGAINST ANY CLAIM, INCLUDING BUT NOT LIMITED TO ANY INFRINGEMENT CLAIM THAT RELATES TO OR IS BASED ON ANY COMBINATION OF PRODUCTS EVEN IF DESCRIBED IN TI RESOURCES OR OTHERWISE. IN NO EVENT SHALL TI BE LIABLE FOR ANY ACTUAL, DIRECT, SPECIAL, COLLATERAL, INDIRECT, PUNITIVE, INCIDENTAL, CONSEQUENTIAL OR EXEMPLARY DAMAGES IN CONNECTION WITH OR ARISING OUT OF TI RESOURCES OR USE THEREOF, AND REGARDLESS OF WHETHER TI HAS BEEN ADVISED OF THE POSSIBILITY OF SUCH DAMAGES.

You agree to fully indemnify TI and its representatives against any damages, costs, losses, and/or liabilities arising out of your non-compliance with the terms and provisions of this Notice.

This Notice applies to TI Resources. Additional terms apply to the use and purchase of certain types of materials, TI products and services. These include; without limitation, TI's standard terms for semiconductor products (<http://www.ti.com/sc/docs/stdterms.htm>), [evaluation modules](#), and [samples](http://www.ti.com/sc/docs/sampterm.htm) (<http://www.ti.com/sc/docs/sampterm.htm>).

Mailing Address: Texas Instruments, Post Office Box 655303, Dallas, Texas 75265
Copyright © 2018, Texas Instruments Incorporated