

78M6613 Split-Phase Firmware Description Document

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1 Introduction

This document describes a firmware build specifically designed for the 78M6613 with a split-phase measurement interface (Split-Phase M-API Library) and UART host interface (Application Layer). This firmware build is used as the base for all development and testing of the Split-Phase M-API Library.

The firmware provides simple methods for calibration, alarm monitoring, and access to the following measurement data over a low baud rate serial UART interface.

- Voltage rms (Line1, Line2)
- Current (Line1, Line2)
- Active Power (Line1, Line2, aggregate)
- Apparent Power (Line1, Line2, aggregate)
- Reactive Power (Line1, Line2, aggregate)
- Power Factor (Line1, Line2)
- Energy (Line 1, Line 2)
- Line Frequency

1.1 Terminology

The following terminology is used throughout this document:

- CLI – Command Line Interface (Application with ASCII based UART protocol).
- SLIP – Serial Line Interface Protocol (Application with binary UART protocol).
- CREEP – Threshold value where measurement outputs are squelched to zero.
- IMAX – External RMS current corresponding to 250 mVpk at the current input of the 78M6613. It should be set $IMAX = (V_{pk}/\sqrt{2})/R_{SENSE}$.
- VARs – Reactive Power (Q).
- VAs – Apparent Power (S).
- Watts – Active Power (P).
- VMAX – External RMS voltage corresponding to 250 mVpk at the voltage input of the 78M6613. It must be set high enough to account for overvoltages.

1.2 Hardware Assignments

The firmware supports two different hardware configurations for measuring a split-phase load. The settings in the CESTATE register must correlate to the selected hardware configuration represented in [Section 1.2.1](#) and [Section 1.2.2](#).

All measurement results, command routines, and configuration registers are accessible through the TX and RX pins of serial 0 interface (UART0/RS232). Additional 78M6613 pins utilized by this firmware are listed in [Table 1](#).

Table 1: DIO Assignments

DIO#	Direction	Purpose
DIO6	Output	WPulse (SLIP and CLI)
DIO17	Output	Ready/Active (SLIP and CLI)
DIO7, DIO19	Output	Relay Control (SLIP and CLI)
DIO16	Output	SAG (SLIP and CLI)
DIO8/DIO4/DIO5	Input	RS485 Address (SLIP only)
DIO15	Output	RS485 Tx_Enable(SLIP only)
DIO14	Input	Invoke Boot Loader(SLIP and CLI)
DIO17	Output	Boot Loader Pulse(SLIP and CLI)

RTC (Real Time Clock), LCD Driver, and Battery Modes are not supported by this firmware.

1.2.1 Fixed Reference Sensor Configuration

In conventional configurations, the AC neutral is connected to V3P3A which is the supply input of the analog circuitry and the reference potential for the A/D Converter.

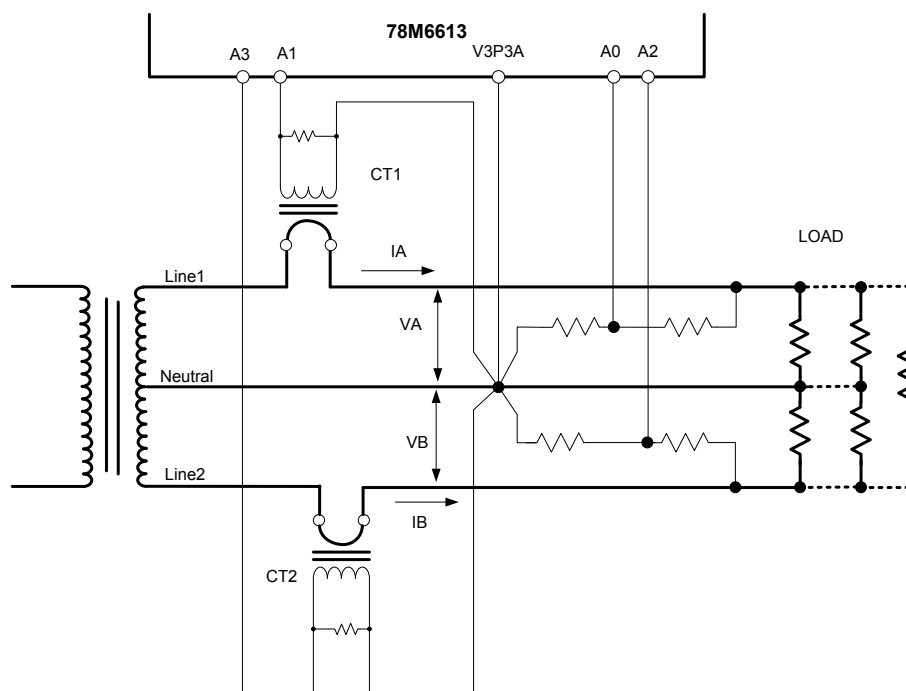


Figure 1: Simplified Connection Diagram with Fixed Reference

1.2.2 Floating Reference Sensor Configuration

In order to maintain a high impedance between the supply (Line1, Line2, Neutral) and the measurement subsystem, a “floating reference” configuration is also available.

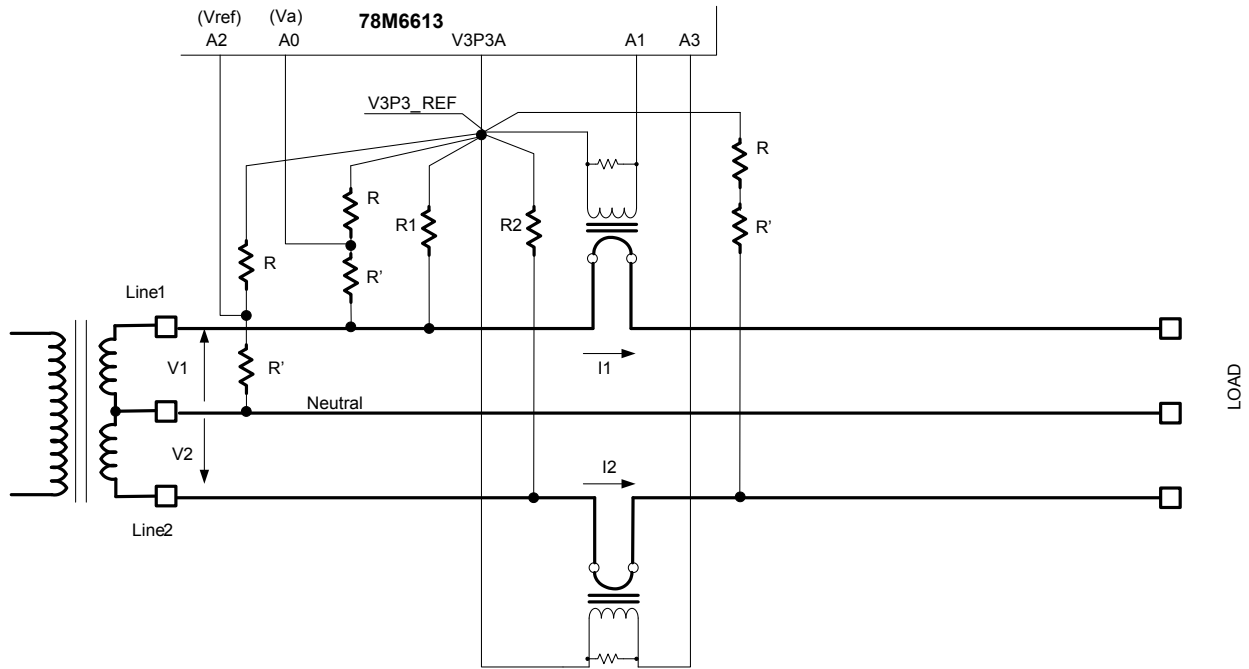


Figure 2: Simplified Connection Diagram with Floating Reference

A virtual center or reference (V3P3_REF) has been created using a voltage divider (R1 and R2). The V3P3A (AD/C reference potential) is connected to the virtual center. Two voltages are then acquired: Line 1 and Neutral, these measurements are referred to the virtual ground (V3P3_REF). For clarity, Line 1 measurement is identified as V_a and Neutral measurement is identified as V_{ref} .

The equations to reconstruct the values of V_1 and V_2 are the following:

$$V_1 = V_a - V_{ref} \quad [1]$$

$$V_2 = V_a + V_{ref} \left(1 + \frac{R'}{R' + R_1}\right)$$

Table 2 shows the results obtained from simulations using the above equations:

V1= Line 1 Voltage, V2= Line2 Voltage Vref (ADC input Neutral-V3P3_REF), Va (ADC input Line1-V3P3REF). V1 and V2 are reconstructed as the resulting values from [1].

Table 2: Simulation Results

V1	V2	Vref	Va	V1 (reconstructed)	V2 (reconstructed)
120	120	0	120	120	120
100	120	9.768	109.768	100	120.0011429
80	120	19.535	99.535	80	120.0002381
60	120	29.303	89.303	60	120.001381
40	120	39.07	79.07	40	120.0004762
20	120	48.838	68.838	20	120.001619
0	120	58.605	58.605	0	120.0007143

V1	V2	Vref	Va	V1 (reconstructed)	V2 (reconstructed)
120	120	0	120	120	120
120	100	-9.768	110.232	120	99.99885714
120	80	-19.535	100.465	120	79.9997619
120	60	-29.303	90.697	120	59.99861905
120	40	-39.07	80.93	120	39.99952381
120	20	-48.838	71.162	120	19.99838095
120	0.5	-58.361	61.639	120	0.498904762

1.3 Measurement Equations

The Split-Phase Library provides the user with continuously updated “Wideband” measurement data. Wideband measurements are generally of interest when measuring in systems that tend to have non-sinusoidal waveforms. [Table 3](#) lists the basic measurement equations for the Wideband methods.

Table 3: Measurement Equations Definitions

Symbol	Parameter	Wideband Equation
V	RMS Voltage	$V = \sqrt{\sum v(t)^2}$
I	RMS Current	$I = \sqrt{\sum i(t)^2}$
P	Active Power	$P = \sum (i(t) * v(t))$
Q	Reactive Power	$Q = \sqrt{S^2 - P^2}$
S	Apparent Power	$S = V * I$
PF	Power Factor	P/S
PA	Phase Angle	$\text{ACOS}(P/S)$

The value of voltage and current are calculated as “true RMS”. The calculation requires an accumulation of samples over time (accumulation interval), as follows:

$$I_{rms} = \sqrt{\frac{I1^2 + I2^2 + \dots + In^2}{n}} \quad V_{rms} = \sqrt{\frac{V1^2 + V2^2 + \dots + Vn^2}{n}} \quad [2]$$

Similarly for power:

$$PWR = (I1 * V1 + I2 * V2 + \dots + Vn * In) * \frac{f_s}{n}$$

Where n is the number of ADC samples in an accumulation interval for a given sample rate.

1.4 Sampling and Update Rates

This firmware utilizes an effective sampling rate of 3,641 samples per second for each sampled input. While the CE continuously accumulates sampled data at the sampled rate, status and measurement data updates to the MPU are less frequent. These updates include:

- Sag status is updated at every Mux Chcle for low-latency alarm detection.
- Measurement outputs and all other alarm conditions are updated every accumulation interval which is set to 500msec for this firmware build.

2 Functional Description

This section summarizes the functional operation of the 78M6613. Refer to the *78M6613 Data Sheet* and application notes for more information on IC operation and terminology.

2.1 Initialization and Start-up

Upon power-up, both MPU and Compute Engine (CE) cores start executing the application code from designated blocks of Flash memory. Status indicators for 'Ready' and 'Active' are available to the host via DIO pins.

2.2 Sensor (Hardware) Configuration

A few parameters specific to the hardware implementation may require one-time configuration. The firmware allows for parameters to be modified by the user at run-time and saved to Flash. These hardware-specific parameters include:

VMAX and IMAX registers define the upper and lower values of the ADC range. These parameters allow the scaling of raw data to real-world values. VMAX and IMAX should be set to a value that reflects a peak of near 250mV at the selected voltage ADC input. Values too far from this setting will cause undesired effects. When changing a current sensor its associated IMAX value will need to be re-evaluated.

The CESTATE register selects either the 'Fixed' or 'Floating' reference sensor configuration. Refer to Section 1.2 for more information on sensor interface configurations.

2.3 AC Measurement and Monitoring

The integrated AFE and CE function as a data acquisition system, controlled by the MPU. The low-voltage analog input signals are sampled and stored in CE DRAM where they are processed by the CE. The CE, a dedicated 32-bit signal processor, performs the computations necessary to all the measurements. The CE calculations and processes include:

- Multiplication of each current sample with its associated voltage sample to obtain the energy per sample (when multiplied with the constant sample time).
- Frequency-insensitive delay cancellation on all channels (to compensate for the delay between samples caused by the multiplexing scheme).
- Monitoring of the input signal frequency (for frequency and phase information).
- Monitoring of the input signal amplitude (for sag detection).
- Scaling of the processed samples based on calibration coefficients.

At the end of each accumulation interval, these atomic measurement parameters are provided to the MPU for post-processing. Alternate multiplexer cycles also gather measurements of the IC's junction temperature for additional compensation in the MPU. Post-processing functions handled by the MPU at the end of every accumulation interval include:

- Compensation for environmental variables.
- Calculation of apparent power, power factor, phase angle, and line frequency.
- Accumulation of energy data.
- Comparing of measurement outputs to configurable alarm thresholds.
- Scaling and formatting of output measurement data.
- Updating of all output registers (data and alarm status).

Figure 3 shows the data processing flow.

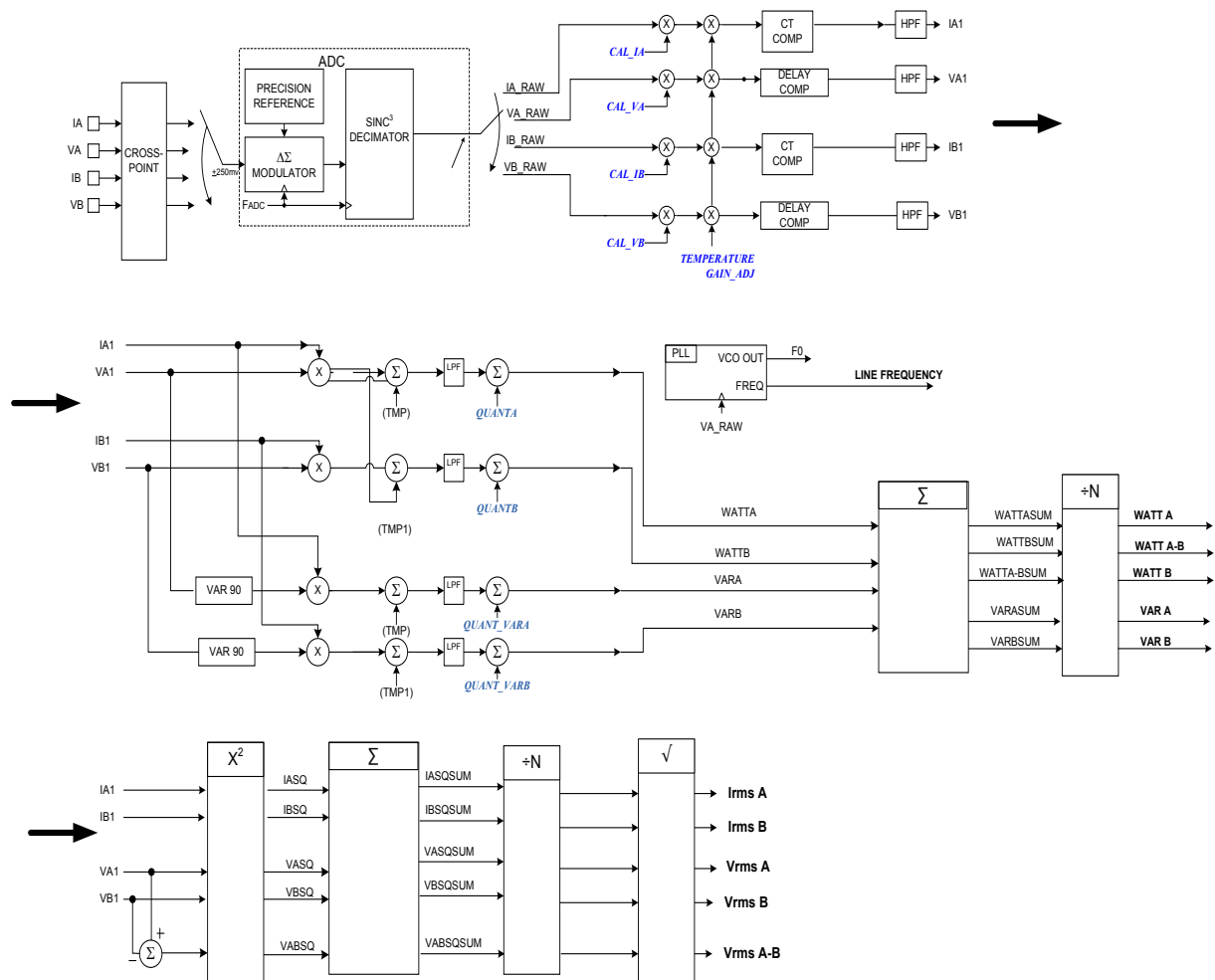


Figure 3: Simplified Signal Processing Flow

2.4 Configuration and Control

2.4.1 Input Registers

The following parameters are configurable by the user via input registers:

- Sensor range and configuration
- Calibration targets and coefficients
- Squelch or CREEP Thresholds
- Alarm Thresholds and Mask Settings

Updating Input Registers into Flash

The default values of all input registers can be updated by the user at run-time. A Flash update routine is provided that saves the current value of any input register as the default.

2.4.2 Calibration

As with any measurement system, there are also multiple sets of compensation coefficients or parameters that are used to compensate for system inaccuracies. Input registers for all coefficients can be manually modified and saved to Flash. Alternatively, high level calibration routines can be invoked. These routines automatically determine the coefficients for common parameters and save them to Flash memory. The different types of compensation parameters include:

- Voltage Sensing – Gain adjustment.
- Current Sensing – Gain and offset (QUANT) adjustment.
- Phase – Voltage-to-current phase offset compensation introduced by transformer or filters in sense circuits.
- Temperature – Offset for junction temperature at room temp.
- Temperature – Coefficients for temperature curve.
- WATT and VAR offset (QUANT) adjustment.

The calibration routines compensate for sensors and system inaccuracy. The new coefficients computed during calibration are stored in the on-chip flash.

In order to perform a calibration, an external voltage source and external current source (or load) is required. The calibration routines have a target voltage and current for both phases to match. The target calibration voltage and current values are specified in the registers 0xC1 (Voltage Line1 and Line2) and 0xC2 (Current Line1 and Line2). Important factor for accurate calibration is to define the tolerance, for example the coefficients are modified until the measured current or voltage is within the plus/minus range of the specified tolerance from the target value. The voltage calibration tolerance register is at address 0xC4 while the current tolerance is specified in register 0xC5.

Other settings for calibration are average counts and maximum number of iterations.

The average counts represent the number of voltage measurement (register 0xC6) or current measurements (register 0xC7) averaged and used to be compared against the target value.

The number of iterations sets the number of time the routine runs in order to bring the value of either voltage or current reading within the specified tolerance from the target.

NOTE: All calibration should be done in the 'Fixed Reference Sensor Configuration'.

Figure 4 shows a split-phase calibration test setup.

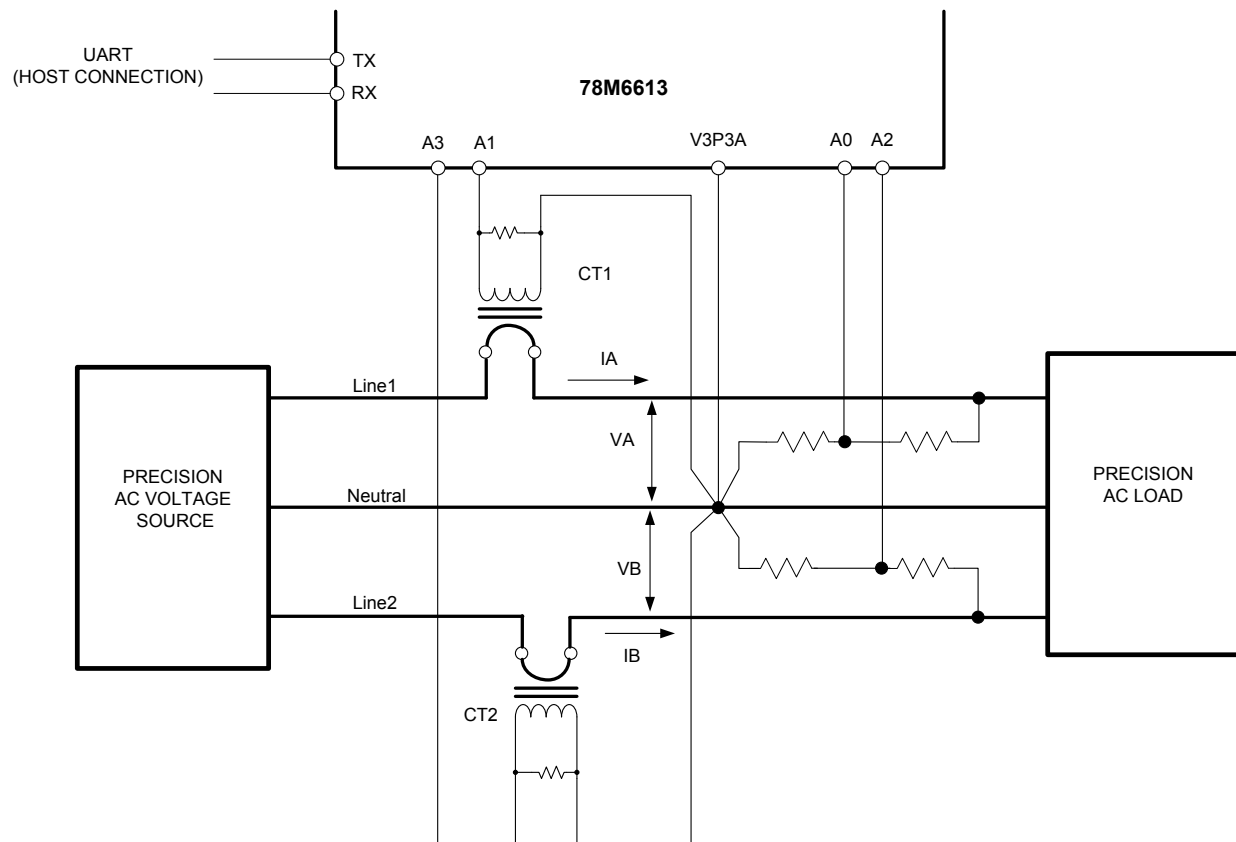


Figure 4: Split-Phase Calibration Test Setup

The source and AC load should provide a stable reference during calibration. Since the calibration procedures are dependent on production test setup, they will be described in a separate document.

2.4.3 Relay Control

Relay control is supported by the TC command. The TC command can be used to open (0) or close (1) circuit of all 2 channels. All necessary Sequence (time between each channel), Energized (for closing circuit), and De-Energized (for opening circuit) delay times are set up and used by the library using the following default values:

Energized delay time = 0ms
De-Energized delay time = 0ms

MPU Parameter	Location (hex)	LSB	Default	Comment	Example
Relay Configuration	AC	–	0	Bit 1 (Relay Polarity) 0 = Normal Polarity 1 = Inverted Polarity Bit 0 (Relay Type) 0 = non-latched 1 = latched	
Energize Delay	AE	ms	+0.000	Parameter given in relay manufacturer's data sheet is entered here. The amount of delay will be 1 ms plus the value entered in)AE.	If the user desires 8 ms of delay then enter the following: >)AE=+0.007<CR>
De-Energize Delay	AF	ms	+0.000	Parameter given in relay manufacturer's data sheet is entered here. The amount of delay will be 1 ms plus the value entered in)AF.	If the user desires 8 ms of delay then enter the following: >)AF=+0.007<CR>
Control Relay	F0	–	0	Bit 1 (Relay for Outlet 2) 0 = DIO19 = 0 1 = DIO19 = 1 Bit 0 (Relay for Outlet 1) 0 = DIO7 = 0 1 = DIO7 = 1 Note: AC[1] = 1 inverts the bits above.	Control Relay

2.4.3.1 TC Command

This section applies to the CLI version of the split-phase firmware. The SPI firmware controls the relays directly using the F0 register described in [Section 2.4.3](#).

Refer to the *78M6613 Split-Phase Evaluation Board User Manual* for the specific hardware design. The format of the TC command is as follows (where it is not a case sensitive):

>tc is the same as >TC or >Tc or >tC.

>TCxx where xx is a hex value with each bit represents the setting of each channel. The value of each bit is determined as 1 = closing and 0 = opening 0. Both channels will be processed sequentially starting from the highest channel number first with a sequence delay time in between. It is important to note that if the polarity for each Channel is inverted, bit 1 of the Relay Config register (0xF0) will be set accordingly in order for the Relay Control to work properly.

The TC commands are summarized in the following table:

TCx	Relay Control Commands	
Description	Allows the user to control the relay of all channels in one command.	
Usage	TC1 or TC01 TC2 or TC02 TC3 or TC03 TC0 or TC00	The TC command can be used to turn on/off relay of both channels. Each bit represents the control (1=on, 0=off) for each channel where the LSB represents the lowest channel number. Examples: Relay ON for Outlet 1, OFF all others. Relay ON for Outlet 2, OFF all others. Relay ON for both channels. Relay OFF for both channels.

2.4.4 Sag Detection Settings

The 78M6613 Split-Phase Firmware includes the sag detection function. SAG is defined as a momentary or permanent decrease of line voltage amplitude. The sag detection is often used to monitor the quality of the power line or utilize the sag alarm to notify external devices (for example a host microprocessor) of a pending power-down. The external device can then enter a power-down mode (for example saving data or recording the event) before a power outage. Figure 5 shows a typical sag event.

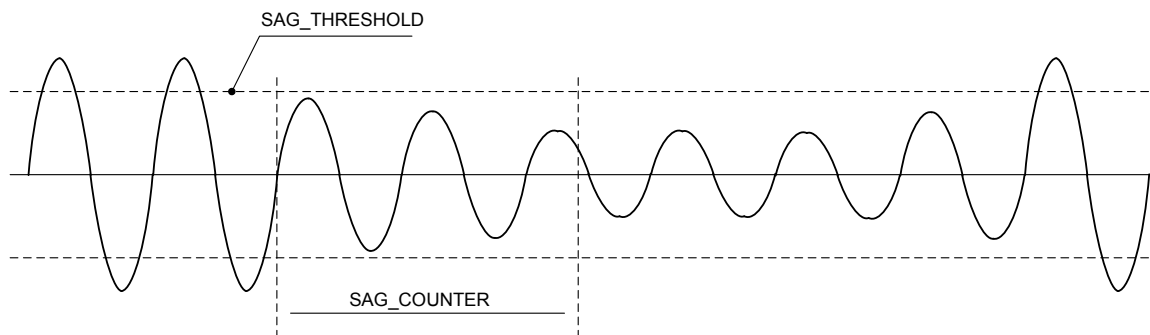


Figure 5: Sag Event

The sag detection is based on a voltage threshold (SAG_THR), and a counter value (time). The counter is updated at the ADC sample rate and starts whenever the voltage is below the SAG_THR value. The alarm bit and alarm pin are set if the counter exceeds the predefined SAG_THR count (SAG_CNT) value. SAG detection is enabled for VA or VB or both by setting bit 5 (VA) and/or bit 6 (VB) to logic high (1) in the CE's CESTATUS register (0x100E).

2.4.5 Creep Thresholds

The 78M6613 includes a “no-load” detection feature that eliminates what is commonly referred to as “meter creep.” Meter creep is defined as power (or energy) that is read by the system when there is no load attached. The FW sets line frequency, voltage and current to zero readings when the voltage falls below a programmable threshold.

2.4.6 Limit Registers (Alarms)

The Limit registers set limits on result values and causes Status Register bits to be set when a limit is exceeded. Limit registers use the same scaling applied to results, and as such, are user definable.

The user selectable alarms are the following:

- Min/Max Temperature Alarm.
- Min/Max Frequency Alarm.
- SAG Voltage Alarm.
- Under-voltage (V1 input).
- Over-voltage (V1 input).
- Over-Current (Line 1 and Line 2).
- Power Factor (Line 1 and Line 2).
- Creep Alert low current alarm (Line 1 and Line 2).

3 Split-Phase M-API Register Map

This section contains the register map for the Split-Phase M-API Library. All the registers are in a 4-byte format and are divided in three sections:

- Output Registers for reading metrology results, system status, etc.
- Input Registers for entering commands, coefficients, etc.
- CE (I/O) Registers for Compute Engine settings and status.

3.1 Output Registers

Output	Address (hex)	Resolution	Data Type	Description
Delta Temperature	20	0.1 °C	Unsigned	Temperature difference from 22 °C.
Line Frequency	21	0.01 Hz	Unsigned	Line Frequency.
Alarm Status	22		Unsigned	Bit 0 – Minimum Temperature Alarm. Bit 1 – Maximum Temperature Alarm. Bit 2 – Minimum Frequency Alarm. Bit 3 – Maximum Frequency Alarm. Bit 4 – SAG Voltage Alarm (Based on setting of CESTATUS register) Bit 5 – LOPENB – Line open on Phase B. Bit 6 – MAXV(A) – over maximum voltage on Phase A. Bit 7 – LOPENA – Line open on Phase A. Bit 8 – MAXIA – maximum current exceeded on Phase A. Bit 9 – Reserved (0) Bit 10 – Reserved (0) Bit 11 – PFA min – Power Factor Min limit exceeded on Phase A. Bit 12 – PFA Max – Power Factor Max limit exceeded on Phase A. Bit 13 – Reserved (0) Bit 14 – MAXIB – maximum current exceeded on Phase B. Bit 15 – Reserved (0) Bit 16 – Reserved (0) Bit 17 – PFB min – Power Factor Min limit exceeded on Phase B. Bit 18 – PFB Max – Factor Max limit exceeded on Phase B. Bit 19 – Multi-Fault (When Vrms(total) < Vmin * 2 (Vmin = register 0xD5)) Bit 20 – MAXIT – Total current(Phase A and B) Max limit exceeded Bit 21 – CREEP A Alert – current Creep Alert on Phase A Bit 22 – CREEP B Alert – current Creep Alert on Phase B. Bit 23 – FAULT – Line/Neutral reversed. Bit 24-25 – Reserved (0) Bit 26 – CE_READY – CE is now ready after power up. Bit 27 – 31 – Reserved (0)
Not Used	23-25	–	–	Not Used
Vrms A	26	1/000 Vrms	Unsigned	RMS Voltage Phase A
Watts A	27	1/1000 Watt	Signed	Power Phase A
Wh A (Export)	28	1/1000 WattHr	Unsigned	Energy Phase A (Export)
Wh A (Import)	29	1/1000 WattHr	Unsigned	Energy Phase A (Import)
Irms A	2A	1/1000 Arms	Unsigned	RMS Current measurement Phase A
VAR A	2B	1/1000 Watt	Signed	Reactive Power measurement Phase A.
VA A	2C	1/1000 Watt	Signed	Apparent power measurement Phase A

Output	Address (hex)	Resolution	Data Type	Description
Power Factor A	2D	0.001	Signed	*Phase A Power Factor. The output will be between -0.950 and 1.000.
Phase Angle A	2E	0.001° (degrees)	Signed	Phase A phase angle. The output will be between 180.000 and -180.000.
Wh A (Net)	2F	1/1000 WattHr	Unsigned	Energy Phase A (Net) Balance
Vrms B	66	1/1000 Vrms	Unsigned	RMS voltage Phase B
Watts B	67	1/1000 Watt	Signed	Power Phase B
Wh B (Export)	68	1/1000 WattHr	Unsigned	Energy Phase B (Export)
Wh B (Import)	69	1/1000 WattHr	Unsigned	Energy Phase B (Import)
Irms B	6A	1/1000 Arms	Unsigned	RMS Current measurement Phase B
VAR B	6B	1/1000W	Signed	Reactive power measurement Phase B
VA B	6C	1/1000 W	Signed	Apparent power measurement Phase B
Power Factor B	6D	0.001	Signed	*Phase B Power Factor. The output will be between -0.950 and 1.000.
Phase Angle B	6E	0.001° (degrees)	Signed	Phase B phase angle. The output will be between 180.000 and -180.000.
Wh B (Net)	6F	1/1000 WattHr	Unsigned	Energy Phase B (Net)
Watts Total	90	1/1000 Watt	Signed	Power Total (Phase A and B)
Wh Total (Export)	91	1/1000 WattHr	Unsigned	Energy Total (Export)
Wh Total (Import)	92	1/1000 WattHr	Unsigned	Energy Total (Import)
Irms Total	93	1/1000 Arms	Unsigned	RMS Current measurement Total (Phase A and B)
VAR Total	94	1/1000W	Signed	Reactive power measurement Total (Phase A and B)
VA Total	95	1/1000 W	Signed	Apparent power measurement Total (Phase A and B)
Wh Total (Net)	96	1/1000 WattHr	Unsigned	Energy Total (Net)
Vrms(A-B)	97	1/1000 Vrms	Unsigned	RMS Voltage (A -B)

* Positive power factor is defined as current lagging voltage (inductive). Negative power factor is defined as voltage lagging current (capacitive).

3.2 Input Registers

MPU Parameter	Location (hex)	LSB	Default	Comment
VMAX	A0	1/000 Vrms	471500	External RMS voltage corresponding to 250 mVpk (Max ADC range). VMAX Calculation: $V_{MAX} = (250mV/\sqrt{2})/(R_{shunt}/(R_{series} - R_{shunt}))$
ICREEP A	A1	1/1000 Arms	7	Minimum RMS current to be reported for Phase A. Currents measured below this value will be ignored.
IMAX A	A2	1/1000 Arms	52000	External RMS voltage corresponding to +/-250 mVpk (Max ADC range). IMAX Calculation: $IMAX = (250mV/\sqrt{2})/R_{shunt}$
ICREEP B	A3	1/1000 Arms	7	Minimum RMS current to be reported for Phase B. Currents measured below this value will be ignored.
IMAX B	A4	1/1000 Arms	52000	External RMS voltage corresponding to +/-250 mVpk (Max ADC range). IMAX Calculation: $IMAX = (250mV/\sqrt{2})/R_{shunt}$
Unused	A5	–	–	Unused
NOM_TEMP	A6	–	0	Temp_raw_x reading at 22 °C. Needed to enable temperature compensation.
Reserved	A7-BC	–	–	Reserved
Config	BD	–	1	This register is 1-byte size and is used for controlling the Min/Max and accumulation data as follows when the bit is set: BIT0 – WPulse goes into DIO6 BIT1 – Reserved BIT2 – Reserved BIT3 – Start Min/Max BIT4 – Restart Min/Maz BIT5 – Allow Negative Power Factor BIT6 – Clear Counts BIT7 – Clear Accumulation data (Wh).

MPU Parameter	Location (hex)	LSB	Default	Comment
Calibration Status	BE	–	0	This register is used for calibration Status Calibration Status: Bit =0 (clear) Calibration OK , Bit =1 (set) Calibration Failed BIT0 – Temperature Cal/Status BIT1 – Voltage CAL A Status BIT2 – Voltage CAL B Status BIT3 – Phase CAL A Status BIT4 – Phase CAL B Status BIT5 – Current CAL A Status BIT6 – Current CAL B Status BIT7 – Watt CAL A Status BIT8 – Watt Cal B Status BIT9-29 – Reserved BIT30 – UPDATE_FLASH_MPU Status BIT31 – UPDATE_FLASH_CE Status
Tolerance on Phase	BF	0.001°	100	Measured value to fall within this set tolerance plus/minus the target value (Calibration Phase entry) for the calibration to be complete.
Reserved	C0	–	0	Reserved
Calibration Voltage	C1	1/000 Vrms	120000	Target line voltage (rms) used for calibration on both Phase A and Phase B.
Calibration Current	C2	1/1000 Arms	1000	Target load current (rms) used for calibration on both Phase A and Phase B.
Calibration Phase	C3	0.1°	0	Target Phase (voltage to current). Normally set to zero. For both Phase A and Phase B.
Tolerance on Voltage	C4	1/000 Vrms	10	Measured value to fall within this set tolerance of the target value (Calibration Voltage entry) for the calibration to be complete.
Tolerance on Current	C5	1/1000 Arms	10	Measured value to fall within this set tolerance plus/minus the target value (Calibration Current entry) for the calibration to be complete.
Average Count for Voltage	C6	1	3	Number of voltage measurements taken and averaged to be compared to the target value (Calibration Voltage entry).
Average Count for Current	C7	1	3	Number of current measurements taken and averaged to be compared to the target value (Calibration Current entry).
Max Iteration for Voltage	C8	1	10	Number of attempts to reach the target value (Calibration Voltage entry) within the programmed tolerance.
Max Iteration for Current	C9	1	10	Number of attempts to reach the target value (Calibration Current entry) within the programmed tolerance.
Tolerance on Watts	CA	1/1000 Watt	10	Measured value to fall within this set plus/minus tolerance of the target Watt value for the calibration to be complete.

MPU Parameter	Location (hex)	LSB	Default	Comment
Average Count for Watts	CB	1	3	Measured value to fall within this set tolerance plus/minus the target Watt value for the calibration to be complete.
Max Iteration for Watts	CC	1	10	Number of attempts to reach the target value within the programmed tolerance.
Reserved	CD			
Calibration Temperature	CE	0.1°C	220	Target nominal temperature for calibration.
Calibration Watts	CF	1/1000 Watt	120000	Target Watts used for calibration for both Phase A and Phase B.
Temp Alarm Min Threshold	D0	0.1°C	0	Minimum Temperature Alarm Threshold. A temperature below this threshold will set the alarm (bit 0 of the Alarm Status Register).
Temp Alarm Max Threshold	D1	0.1°C	7000	Maximum Temperature Alarm Threshold. A temperature above this threshold will set the alarm (bit 1 of the Alarm Status Register).
Frequency Minimum Threshold	D2	0.01Hz	5900	Minimum Frequency Alarm Threshold. A frequency below this threshold will set the alarm (bit 2 of the Alarm Status Register).
Frequency Maximum Threshold	D3	0.01Hz	6100	Maximum Frequency Alarm Threshold. A frequency above this threshold will set the alarm (bit 3 of the Alarm Status Register).
SAG Voltage Alarm Threshold	D4	1/000 Vpk	80000	Sets an alarm (bit 4 of the Alarm Status Register) if voltage drops below the SAG threshold (and CESTATUS register bit5 or/and bit6 are set)
Min Voltage Alarm Threshold	D5	1/000 Vrms	100000	Minimum voltage level selected to flag user (bit 19 of the Alarm Status Register).
Peak Voltage Alarm Threshold	D6	1/000 Vrms	140000	Peak voltage setting that user wishes to flag (bit 6 of the Alarm Status Register).
Unused	D7-D8	–		
PFA_ Neg Threshold	DC	–	-700	Wideband Power Factor Negative Threshold. A less negative wideband power factor than this threshold will set an alarm (bit 11 of the Alarm Status Register). Only available if register 0xF2 bit 2 is set to 1.
PFA_ Pos Threshold	DD	–	700	Wideband Power Factor Positive Threshold. A positive wideband power factor less than this threshold will set an alarm (bit 12 of the Alarm Status Register).
Unused	DE - DF	–	–	Unused
Unused	E0 - E5	–	–	Unused
Alarm Mask_Status	E6	–	0x04FFFFFF	Alarm mask for bits in the Alarm Status register. A "0" masks the alarm from the register bit.
Alarm Mask_Alarm	E7	–	0x04FFFFFF	Alarm mask for an alarm pin (if DIO is configured). A "0" masks the alarm (no report).

3.3 CE Parameters

The following table lists the CE parameters for the firmware. With the exception of CESTATE and QUANT registers, the user does not typically need to alter any of these input registers as they are automatically set by Calibration Commands.

CE Parameter	Location (hex)	LSB	Default	Comment
CAL IA	1008	16384 is the default and is a gain of 1. 32767 is max giving a gain of 2.	16384	Gain constant for Phase A input.
CAL IB	1009	16384 is the default and is a gain of 1. 32767 is max giving a gain of 2.	16384	Gain constant for Phase B input.
CAL VA	100A	16384 is the default and is a gain of 1. 32767 is max giving a gain of 2.	16384	Gain constant for Phase A input.
CAL VB	100B	16384 is the default and is a gain of 1. 32767 is max giving a gain of 2.	16384	Gain constant for Phase B input.
PHASE_ADJ_IA	100C	$-16384 \leq \text{PHASE_ADJ_IA} \leq +16384$	0	Line Out A Phase adjustment = $15 * \text{PHASE_ADJ_IA} * 2^{-14}$ (degrees)
PHASE_ADJ_IB	100D	$-16384 \leq \text{PHASE_ADJ_IB} \leq +16384$	0	Line Out B Phase adjustment = $15 * \text{PHASE_ADJ_IB} * 2^{-14}$ (degrees)
CESTATE	100E	n/a	5061	Bit 15-8 SAG_CNT. Number of consecutive voltage samples below SAG Threshold to assert SAG alarm Bit 7 Reserved (1) Bit 6 1 = detect SAG on V1/B Bit 5 1 = detect SAG on V0/A Bit 2 1 = Floating Reference 0 = Fixed Reference Bit 1-0 Reserved (0)
WRATE	100F	$\text{Kh} = \text{VMAX A} * \text{IMAX A} / (\text{WRATE} * \text{X})$ 1.6826E+01 WattSec	+ 20732	Controls the number of pulses that are generated per measured Wh and VARh measurements.
Reserved	1010			Reserved
SAG Threshold	1011	$\text{VMAX} * 4.2551\text{E-}07$ (Vpk)	+168225	The voltage threshold for SAG warnings. (80vRMS when VMAX=471.5v) V0 must be above this to prevent SAG alarm.
QUANTA	1012	$\text{VMAX A} * \text{IMAX A} * 1.8541\text{E-}10$ (Watt)	0	Compensation added to the Watt calculation for Phase A. Used for compensation at low current levels. Keep below 10000d.
QUANTB	1013	$\text{VMAX A} * \text{IMAX B} * 1.8541\text{E-}10$ (Watt)	0	Compensation added to the Watt calculation for Phase B. Used for compensation at low current levels. Keep below 10000d.
QUANT VAR A	1014	$\text{VMAX A} * \text{IMAX A} * 1.8541\text{E-}10$ (Watt)	0	Compensation added to the VAR calculation for Phase A. Used for compensation at low current levels. Keep below 10000d.

CE Parameter	Location (hex)	LSB	Default	Comment
QUANT VAR B	1015	$V_{MAX A} * I_{MAX B} * 1.8541E-10$ (Watt)	0	Compensation added to the VAR calculation for Phase B. Used for compensation at low current levels. Keep below 10000d.
QUANT IA	1016	$(I_{MAX A})^2 * 4.6351E-11$ (A ²)	0	Phase A input compensation added for input noise and truncation in the squaring calculation for I ² . Used for compensation at low current levels. Keep below 10000d.
QUANT IB	1017	$(I_{MAX B})^2 * 4.6351E-11$ (A ²)	0	Phase B input compensation added for input noise and truncation in the squaring calculation for I ² . Used for compensation at low current levels. Keep below 10000d.
Reserved	1018	—	—	Reserved
Temperature Gain Adjust	1019	16384 is the default and is a gain of 1.	+16384	32767 is the max giving a gain of 2.
VREF_CORR	101A	—	0	Vref correction.
Rimbalace_CORR	101C	—	0	Resistor Imbalance correction

4 Serial Communication

The serial communication with the 78M6613 takes place over a UART (UART0) interface. The default settings for the UART of the 78M6613, as implemented in this firmware, are given below:

Baud Rate:	38400bps
Data Bits:	8
Parity:	None
Stop Bits:	1
Flow Control:	None

The host's serial interface port is required to implement these settings on its UART. In addition, the 78M6613 Split-Phase Firmware is available with one of two protocols. The two available protocols are briefly summarized below and fully documented in the Appendices.

4.1 CLI Firmware Application

The Command Line Interface (CLI) provides a simple ASCII interface to access input and output registers and to invoke commands. The CLI interface connects to a HyperTerminal or any other terminal emulation SW. The CLI interface can also be used to interface to a host processor. [Appendix A](#) describes the CLI commands and syntax.

4.2 SLIP Firmware Application

The Serial Line Interface Protocol is a simple binary UART protocol defined to support single (e. g. RS232) or multi-point device (e. g. RS485) interfaces. Appendix B describes the SLIP protocol and command/response format of the data packet.

5 Contact Information

For more information about Maxim products or to check the availability of the 78M6613, contact technical support at www.maxim-ic.com/support.

Appendix A – Command Line Interface

This appendix describes a serial interface protocol called Command Line Interface (CLI). This interface facilitates communication via UART between the energy measurement device and the host system by use of ASCII-based commands and responses.

The characters following the command prompt symbol “>” are the CLI command characters. A following carriage return “<CR>” is used to initiate the commands.

A.1 Identification Command

The I command is used to identify the revisions of Demo Code and the contained CE code. The host sends the I command to the 78M6613 as follows:

```
>I<CR>
```

The 78M6613 will reply to the host the following:

```
V1.00 2s F0 W 78M6613 Split Phase 3+S2,Aug 16 2011  
>
```

A.2 Reset Commands

A soft reset of the device can be performed by using the Z command. The soft reset restarts code execution at addr 0000 but does not alter XRAM contents. The soft reset also sets all the registers to their default values. To issue a soft reset to the device, the host sends the following:

```
>Z<CR>
```

The W command acts like a hardware reset. The energy accumulators in XRAM will reset back to zero.

Z	Reset	
Description:	Allows the user to cause soft resets.	
Usage:	Z	Soft reset.
	W	Simulates watchdog reset.

A.3 Data Access Commands

All the measurement calculations are stored in the data range of the device. The host requests measurement information using the data access command which is a right parenthesis

>) addr <CR>

To request information, the host sends the data access command, the address (in hex) which is requested, the format in which the data is desired (Hex or Decimal) and a carriage return. The contents of the addresses that would be requested by the host are contained in Register Map.

A.3.1 Individual Address Read

The host can request the information in hex or decimal format. In an address read command, the character \$ requests the information to be returned in hex format. While the character ?, requests information to be returned in decimal. When requesting information in decimal, the data is preceded by a + or a -.

An example of a command requesting the measured output located at address 0x28 in decimal is as follows:

>)28?<CR>

An example of a command requesting the measured output located at address 0x28 in hex is as follows:

>)28\$<CR>

A.3.2 Consecutive Read

The host can request information from consecutive addresses by adding additional ? for decimal or additional \$ for hex.

An example of requests for the contents in decimal of ten consecutive addresses starting with 0x32 is:

>)32??????????<CR>

An example of requests for the contents in hex of ten consecutive addresses starting with 0x32 would be:

>)32\$\$\$\$\$\$\$\$\$\$<CR>

Note: The number of characters per line is limited to no more than 60.

A.3.3 Block Reads

The block read command can also be used to read consecutive registers.

For decimal format:

>)startaddress:endaddress?

For hexadecimal format:

>)startaddress:endaddress\$

The following block read command requests a block of measurement information in decimal format:

>)20:3D?<CR>

A.3.4 Concatenated Reads

Multiple commands can also be added on a single line. Requesting information in decimal from two locations and the block command from above are given below:

```
>)32?)35?)20:2E?<CR>
```

Note: The number of characters per line is limited to no more than 60.

A.3.5 Repeat Command

The repeat command can be useful for monitoring measurements and is efficient in demands from the host.

If the host requests the contents of eight consecutive addresses with the following command string:

```
>)21????????<CR>
```

If the host then desires this same request without issuing another command, the repeat command can be used:

```
>, (no carriage return needed for the repeat command)
```

The host only needs to send one character rather than an entire string.

	Auxiliary	
Description:	Various	
Commands:	,	Typing a comma (",") repeats the command issued from the previous command line. This is very helpful when examining the value at a certain address over time, such as the CE DRAM address for the temperature.
	/	The slash ("/") is useful to separate comments from commands when sending macro text files via the serial interface. All characters in a line after the slash are ignored.

A.3.6 CE Data Access

The CE is the main signal processing unit in the device. The commands are similar to the MPU access except that the host requests access to information from the CE data space using the CE data access command which is a right bracket:

>]

Single Register CE Access

An example of a command requesting the contents located at CE address 0x28 in decimal is as follows:

>]28?<CR>

An example of a command requesting the contents located at address 0x28 in hex is as follows:

>]28\$<CR>

Consecutive CE Reads

The host can request information from consecutive addresses by adding additional ? for decimal or additional \$ for hex.

An example of requests for the contents in decimal of ten consecutive addresses starting with 0x28 would be:

>]28??????????<CR>

An example of requests for the contents in hex of ten consecutive addresses starting with 0x28 would be:

>]28\$\$\$\$\$\$\$\$\$\$<CR>

Note: The number of characters per line is limited to no more than 60.

A.4 Write Commands

A.4.1 MPU Register Write Commands

To modify the contents of an individual MPU Input Register, append the = character and the value to a read command.

```
>)addr=n<CR>
```

The)U command is used for updating default values of the MPU input registers permanently in the flash. Before issuing the)U command, CE must first be turned off by the disable CE command.

```
>CE0<CR>
```

```
>)U<CR>
```

```
>CE1<CR>
```

A.4.2 CE Register Write Commands

To modify the contents of an individual MPU Input Register, append the = character and the value to a read command.

```
>]addr=n<CR>
```

The]U command is used for updating default values of the CE input registers permanently in the flash. Before issuing the]U command, CE must first be turned off by the disable CE command.

```
>CE0<CR>
```

```
>]U<CR>
```

```
>CE1<CR>
```

A.5 Calibration Commands

There are often two types of built-in calibration routines. The first type provides complete calibration. The second group, called atomic calibration commands, provides calibration for individual portions of the IC. There is often one calibration coefficient for each voltage input and one for each current input.

A.5.1 Complete Calibration Command

The CAL command provides single-command calibration. To use this command, a precision voltage source and a precision current source are required

Enter the following:

```
>CAL<CR>
```

The response is:

```
TCal OK
```

```
VCal OK
```

```
ICal 0 OK
```

```
>
```

The device calibrates the temperature (and saves to flash), calibrates the voltage (and saves them to flash), and finally calibrates the current (and saves to flash).

A.5.2 Atomic Calibration Commands

The atomic calibration commands provide individual calibration of voltage, current, power, and temperature. A sequence of these commands results in a fully calibrated unit. The following table provides a summary of the atomic calibration commands.

CLxx	Atomic Calibration Commands	
Description:	Allows the user to Calibrate individual sections of the IC.	
Usage:	CLV	Calibrates voltage only.
	CLI1	Calibrate current only.
	CLT	Calibrate temperature only.

CLV Command

An example of an atomic calibration command would be to calibrate voltage with the CLV command. The CLV command calibrates voltage to the target value and tolerance and saves the coefficients to flash. The CLV command example is given below:

```
>CLV<CR>
```

The response is:

```
VCal OK
>
```

CLI Command

The user can then calibrate the current using the CLI command. The CLI1 command calibrates the current channel 1 to the target value and tolerance and saves the coefficients to flash. The CLI1 command example is given below:

```
>CLI1<CR>
```

The response is:

```
ICal 0 OK
>
```

CLT Command

The CLT command is used for the temperature calibration. With this command, the CE register holding current temperature are read and entered into MPU register C0 and the contents are then saved to flash. The CLT command example is given below:

```
>CLT<CR>
```

The response is:

```
TCal OK
>
```

Appendix B – SLIP Interface

This appendix describes a multi-point serial interface protocol built on top of a Serial Line Interface Protocol (SLIP) layer. It defines a payload format suitable for communicating with one or more 78M66xx energy measurement devices on a single serial bus.

B.1 Packet Format and Definition

The SLIP packet is transmitted in a block format. The useful data is encapsulated by two control bytes. These control bytes are necessary to determine when the block starts and ends. It is recommended that the host allows the firmware sufficient time to process each byte of the packet by setting a 5ms inter-character delay.

B.1.1 Packet Format

Start	Device Address	Data	CRC-8	End
"C0"	XX	XX... XXn	XX	"C0"
1Byte	1Byte	Variable, nBytes	1Byte	1Byte
Offset = 0	Offset = 1	Offset = 2	Offset = n+2	Offset = n+3

B.1.2 Start and End

A SLIP packet always starts and ends with an END character. SLIP has 4 special character codes:

```
#define END 0xC0          /* Decimal 192 - indicates start or end of a packet */
#define ESC 0xDB          /* Decimal 219 - indicates byte stuffing */
#define ESC_END 0xDC      /* Decimal 220 - ESC ESC_END means END data byte */
#define ESC_ESC 0xDD      /* Decimal 221 - ESC ESC_ESC means ESC data byte */
```

Within a SLIP packet, a data byte having a value of END (0xC0) will be stuffed with ESC (0xDB) and immediately followed by an ESC_END (0xDC) character, for example: 0xC0 data byte will appear as 0xDBDC.

Similarly, a data byte having a value of ESC (0xDB) will be immediately followed by an ESC_ESC (0xDD) character, for example: 0xDB data byte will appear as 0xDBDD.

B.1.3 Device Address

The SLIP-based interface supports a single master and multi-slave devices configuration. Messages are broadcasted on the bus by the master. The device address is contained in the message packet, so that only the specific device responds to the broadcast request. Since the device cannot detect presence of other devices on the network, it is the task of the host to manage the device addresses from the initial response to make sure no two devices with the same address are present as collision will occur.

One byte device address, ranging from 0x00 - 0x7F, shall be assigned to each 78M66xx device. Device address for each 78M66xx device shall be hardcoded using the DIO lines, for example: device addresses in the range of 0x00 to 0x07 can be assigned by using three input DIO lines.

The response packet shall be embedded with the responding device's address to identify the source of the packet and other devices shall ignore the response packet.

The packet transaction is always a command/response pair such that the master will initiate the communication by sending a request packet to a device with an assigned address. Only the addressed device will respond to the master by a NACK in the case of a bad packet, or an ACK followed by a response packet in the case of a good packet, to complete the transaction.

B.1.4 Data

The data packet consists of either the request data sent from the master to the device or the response data packet sent from the device to the master. If a data byte is 0xC0, it is replaced by 0xDBDC. If it is 0xDB, it is replaced with 0xDBDD. The conversion is done before transmission. See sample code below.

B.1.5 CRC-8

An 8-bit cyclic redundancy check (CRC-8) calculated over the Data packet is embedded in the packet. The CRC-8 represented by the polynomial, $C(x) = x^8 + x^2 + x + 1$.

After the computation of CRC, Data packet and CRC-8 is encoded with the special SLIP character codes described in Section 2.2.

Start	Device Address	Data	CRC-8	End
"C0"	XX	XX... XXn	XX	"C0"
1Byte	1Byte	Variable, nBytes	1Byte	1Byte
Offset = 0	Offset = 1	Offset = 2	Offset = n+2	Offset = n+3

Code snippet for CRC-8 calculation:

```
uint8_t crc8( uint8_t inCrc, uint8_t inData )
{
    uint8_t i, crc;
    crc = inCrc ^ inData;
    for ( i = 0; i < 8; i++ )
    {
        if ( ( crc & 0x80 ) != 0 )
        {
            crc <<= 1;
            crc ^= 0x07;
        }
        else
            crc <<= 1;
    }
    return crc;
}
```

B.2 Packet Types

The master shall broadcast a command packet addressed to a specific device. And the device shall reply by transmitting an ACK/NACK packet followed by a response packet.

The different packet types can be classified as.

- **ACK/NACK Packet** – Handshake mechanism.
- **Command Packet** – Operational phase.
- **Response Packet** – Reply to the command.

After sending the command packet, the master must wait for a response from the device before sending out the next command packet. In the case of a non-responsive device, a time-out shall be activated by the master before re-sending the command packet to the device.

ACK/NACK Packet

Every time a request packet is sent from the master to the device, the master should expect an ACK/NACK packet back from the device. ACK is to acknowledge the valid address and data integrity of the request packet.

NACK acknowledges the data integrity error like CRC error. Only device with valid address should respond with a NACK packet to avoid message collision on the bus. After sending out the NACK packet, the device considers the transaction to be complete. The device will be in receive mode, ready to receive a new command packet from the master.

If NACK is received, from the device, the master shall be in transmit mode and resend the command. The number of retries shall be at the discretion of the master. The device shall consider each retry attempt as a new command request from the master.

Start	Device Address	Data	CRC8	End
"C0"	XX (responding device address)	ACK/NACK	XX	"C0"
1Byte	1Byte	1 Byte	1 Byte	1 Byte
Offset = 0	Offset = 1	Offset = 2	Offset = 3	Offset = 4

The table below describes in detail each field of the ACK/NACK packet and its available values.

ACK/NACK packet sent from the device				
Packet Offset	Packet Names	Field Value	Field Size	Field Description
2	ACK/NACK	XX	1 byte	ACK : 0x00. NACK* : 0x80 *NACK for the checksum error.

Command Packet

The command packet is sent from the master to the device. Upon reception of the command packet, the device sends an ACK packet to the master to inform the master that it has successfully received the command and is working on it. After processing of the command, the device responds to the master with the response packet.

The operational phase comprises of the register read/write and device information command.

The 661x device register address is two bytes wide and register data is four bytes wide. Refer to 661x Firmware Description Document(FDD) for the register details. The following table shows the offset of the MPU, CE and IO RAM registers.

Register	Offset
MPU	0x0000
CE	0x1000
IO RAM	0x2000

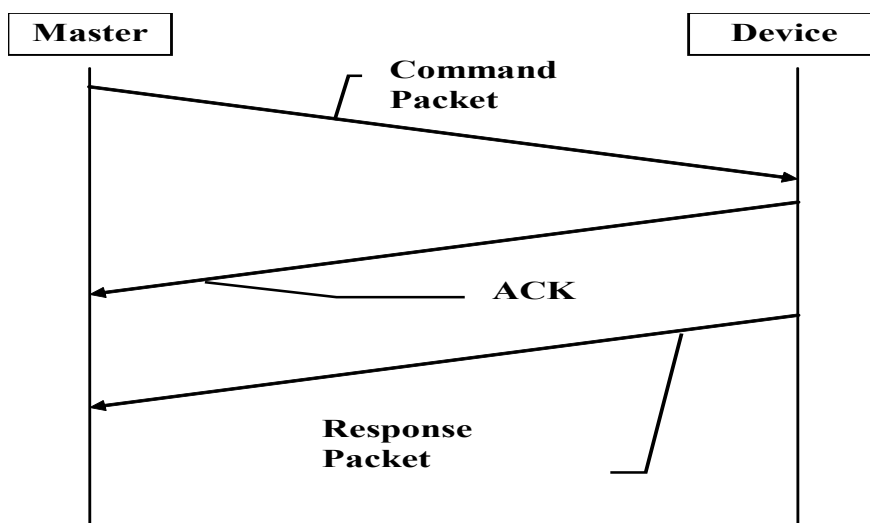
For example, an offset of 0x1000 is added to the CE register addresses defined in the Firmware Description Document.

The read/write command is limited to sixteen registers read/write operation due to the receive and transmit buffer size limitation of the device.

The device may take up to a few seconds to complete the calibration command (a MPU register – see FDD for details). Therefore the master shall allow the device enough time to process a command and wait for the device response packet before timing out or sending a new command to the device.

During Operational phase, after receiving the valid start character and device address, the device shall start a timer of 250ms. If this timer expires before receiving the end character, the receive buffer of the device is flushed and the device is ready to receive the new command packet. If the end character is received prior to expiration of this timer, the timer will be stopped and reset.

The communication flow is depicted as follows:



Start	Device Address	Data	CRC-8	End
"C0"	XX	XX... XXn	XX	"C0"
1Byte	1Byte	Variable, n Bytes	1 Byte	1Byte
Offset = 0	Offset = 1	Offset = 2	Offset = n+3	Offset = n+4

Command Type	Command Request Data
XX	XX
1Byte	n Bytes
Offset = 2	Offset = 3

The following table describes in detail each field name and its available values:

Command Packet Sent from the master to the device.				
Packet Offset	Packet Names	Command Field Value	Field Size	Packet Description
2	CmdType	Variable	1 byte	Read(single or multiple) : 0x10 Write(single or multiple) : 0x11 Contiguous Block Read : 0x20 Contiguous Block Write : 0x21 Device Information : 0x30 CLI Toggle Cmd : 0x00
3	CmdRequest Data	Variable	n bytes	Single/Multiple Read: <Register address> , <Register address2> Single/Multiple Write: <Register address1> <data1> , <Register address2> <data2> , Contiguous Block Read: <Beginning block read register address, <number of registers to read> Contiguous Block Write: <Beginning block write register address> <data1> , <data2> , <data3> Device Information: <none> CLI Toggle Command: <none>

The following table describes the field size of each data packet:

Data Packet	Field Size
<Register address>	2 bytes
<Data>	4 bytes
<Beginning block read/write register address>	2 bytes
<number of registers to read>	1 byte

Response Packet

The Response packet is sent from the device to the master in reply to the Command packet.

Start	Device Address	Data	CRC-8	End
"C0"	XX (responding device address)	XX... XXn	XX	"C0"
1Byte	1Byte	Variable, nBytes	1 Byte	1 Byte
Offset = 0	Offset = 1	Offset = 2	Offset = n+5	Offset = n+6

Cmd Read/Write Status	Cmd Return Code	Command Response Data*
XX	XX	XX
2 Bytes	1Byte	n Bytes
Offset = 2	Offset = 4	Offset = 5

* only for read operation.

The table below describes in detail each field name and its available values.

Response Packet Sent from the Device				
Packet Offset	Packet Names	Command Field Value	Field Size	Packet Description
2	CmdRWStatus	Variable	2 bytes	Each bit represents status of the register read/write operation. Bit = 0 – Success. Bit = 1 – Failure. LSB represents first read/write register operation in the command. The maximum number of register addresses for both read/write operations in a command is limited to 8. CmdRWStatus is not applicable to Device Information command.
4	CmdReturnCode	variable	1 byte	Successful operation : 0x00 Invalid Command Type : 0x80 Incorrect Data Length : 0x81 Read-only register : 0x82 Reserved register : 0x83 Invalid register address : 0x84
5	CmdResponseData	variable	n bytes	Single/Multiple Read: <data1> <data2><data n> Single/Multiple Write: <none> Contiguous Block Read: <data1> <data2><data n> Contiguous Block Write: <none> Device Information: ASCII string depicting the firmware version and the product number. CLI Toggle Command: <none>

Example 1 – Read Command Packet

In this example, the master sends a command request to read MPU register address 0x0200 of the 661x device (with device address 0x07). The device accepts the read command by sending out an ACK followed by the register data, i.e., 0x000731CC. The next example is when the command packet attempts to read an invalid register address.

For a successful transaction:

```
→ C0 07 10 02 00 88 C0           // Master sends read command Request Packet to read MPU
register 0x0200
← C0 07 00 00 C0                 // Device sends ACK
← C0 07 00 00 00 00 07 31 CC 90 C0 // Device sends out register data – 0x000731CC
```

For a failed transaction:

```
→ C0 07 10 03 10 ED C0           // Master sends read command Request Packet to read MPU
register 0x0310
← C0 07 00 00 C0                 // Device sends ACK. Packet receipt successfully.
← C0 07 00 01 84 00 00 00 00 31 C0 // Device sends out an error code of 0x84
```

Example 2 – Write Command Packet

In this example, the master sends a command request to write data 0x000927C0 to the MPU register address 0x0200 of the device (with device address 0x07). The device accepts the write command by sending out an ACK followed by a command response packet after successfully completing the write command.

```
→ C0 07 11 02 00 00 09 27 DB DC EF C0 // Master sends command request packet to write to the
register addr 0x0200
← C0 07 00 00 C0                     // Device sends ACK
← C0 07 00 00 00 00 C0               // Device sends out command response packet after
successful write.
```

Example 3 – Contiguous Block Read Command Packet

In this example, the master sends a command request to read three contiguous MPU registers from starting address 0x0200 of the 661x device (with device address 0x07). The device accepts the block read command by sending out an ACK followed by the register data. The next example is when the command packet attempts to read an invalid MPU register address.

```
→ C0 07 20 02 00 03 xx C0           // Master sends block read command
request
← C0 07 00 00 C0                     // Device sends ACK
← C0 07 00 00 00 00 09 27 DB DC 00 07 31 CC 00 00 75 30 D0 C0 // Device sends out register data –
0x000927C0, // 0x000731CC ,
0x00007530
```

Master sends block read command to read twenty six (0x1A) contiguous registers starting from address 0x0200, exceeding the maximum limit of sixteen registers read.

```
→ C0 07 20 02 00 1A 5E C0           // Master sends block read command
request
← C0 07 00 00 C0                     // Device sends ACK
← C0 07 00 00 81 8E C0               // Device sends out an error
code of 0x81
```

Example 4 – Contiguous Block Write Command Packet

In this example, the master sends a command request to write to three contiguous MPU registers from starting address 0x0200 of the 661x device (with device address 0x07). The device accepts the block write command by sending out an ACK followed by the register data.

```
→ C0 07 21 02 00 00 09 27 DB DC 00 07 31 CC 00 00 75 30 6A C0    // Master sends block write
command request
← C0 07 00 00 C0                                                  // Device sends an ACK
← C0 07 00 00 00 00 C0                                           // Device sends out command
                                                                response packet // after
                                                                successful write.
```

Example 5 – Device Information Command Packet

In this example, the master sends the device information command. The device accepts the command by sending out an ACK followed by the response packet consisting of the device information string.

```
→ C0 07 30 90 C0                                                  // Master sends the device information
command
← C0 07 00 00 C0                                                  // Device sends an ACK
← C0 07 00 00 00 56 33 2E 58 30 20 32 35 30 6D 73 20 46 30    // Device sends response packet
                                                                consisting of the string
                                                                // "V3.X0 250ms F0 MAXIM 78M6618
                                                                Feb 09 2011"
                                                                20 4D 41 58 49 4D 20 37 38 4D 36 36 31 38 20 46
                                                                65 62 20 30 39 20 32 30 31 31 49 C0
```

Example 6 – CLI Toggle Command Packet

In this example, the master sends the CLI toggle command and the device exits the multi-point serial interface mode to CLI mode. The device can toggle back to multi-point serial interface mode via the 'Q' command at the CLI prompt.

```
→ C0 07 00 00 C0                                                  // Master sends the device information
command
← C0 07 00 00 C0                                                  // Device sends an ACK
← C0 07 00 00 00 00 C0                                           // Successful operation
```

B.3 Command Registers

The following command registers are unique to the Multi-point Serial Interface.

MPU Parameter	Location (hex)	LSB	Default	Comment
Calibration Status	BE	–	0	This register is used for calibration command (Firmware's receipt byte) as well as for Calibration status (Firmware's transmission byte). Calibration Command : Bit =1 (set) performs calibration Calibration Status: Bit =0 (clear) Calibration OK , Bit =1 (set) Calibration Failed BIT0 – Temperature Cal/Status BIT1 – Voltage CAL A Command/Status BIT2 – Voltage CAL B Command/Status BIT3 – Phase CAL A Command/Status BIT4 – Phase CAL B Command/Status BIT5 – Current CAL A Command/Status BIT6 – Current CAL B Command/Status BIT7 – Watt CAL A Command/Status BIT8 – Watt Cal B Command/Status BIT9-29 - Reserved BIT30 - UPDATE_FLASH_MPU Command/Status BIT31 - UPDATE_FLASH_CE Command/Status
CMD_UART_CONF	F1	–	0	Set the value of this 'register' to 1 to use RS232 mode as the UART interface (point to point) A value of 0 sets the UART interface as RS485 mode where DIOs are needed to control the host's Rx (device's Tx_Enable bit), and to use as the device's address to support multi-drop RS485 devices.

Revision History

Revision	Date	Description
1.0	5/2011	First publication.
2	12/2011	Added Section 1.1, Terminology. Added Section 2.4.3, Relay Control. Added Section 3, Split-Phase M-API Register Map. Added Section 4.2, SLIP Firmware Application. Added Appendix B, SLIP Interface.