Seagate

Medalist 630xe

ATA Interface Drive

Product Manual

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1.0 Specification summary

Note. Throughout this manual the Medalist 630xe is referred to by its model number, ST3630A.

1.1 Format configuration

The drive is low-level formatted at the factory. You do not need to low-level format the drive.

You can operate the drive using many different address configurations, provided the number of sectors per track does not exceed 63. The following tables show Enhanced Cylinder Head Sector (ECHS) and Logical Block Address (LBA) translation geometries for the standard configurations. You can verify the parameters using the Identify Drive (EC_H) command.

Cylinders	1,223
Heads	16
Sectors per track	63
Formatted capacity (Mbytes[1])	631.1
Total sectors	1,232,784

1.2 Physical organization

Heads	4
Discs	2

1. One Mbyte equals one million bytes.

1.3 Functional specifications

Interface	ATA
Internal data-transfer rate (Mbits/sec)	22.9 to 39.6
External data-transfer rate (Mbytes/sec)	
PIO Mode 3	11.1
DMA Mode 1	13.3
Spindle speed ± 0.5% (RPM)	3,811
Segmented cache (Kbytes)	120
Zone Bit Recording method	RLL (1,7)
Bytes per sector	512
Recording density, max (BPI)	68K
Flux density, max (FCI)	45.4K
Track density, max (TPI)	3,384

1.4 Drive dimensions

Height (max)	1.00 inch (25.4 mm)
Width (max)	4.02 inches (102.1 mm)
Depth (max)	5.77 inches (146.6 mm)
Weight (max)	1.3 lb (0.59 Kg)

1.5 Seek time

All performance measurements are taken using a 25-MHz 486 AT computer (or faster) with an 8.3-MHz I/O bus. The measurements are taken using nominal power at sea level and at 25°C ambient temperature. The specifications in the table on page 3 are defined as follows:

- Track-to-track seek time is an average of all possible single-track seeks in both directions.
- Average seek time is a true statistical random average of at least 10,000 measurements of seeks between random tracks, less overhead.

- Full-stroke seek time is one-half the time needed to seek from the first data cylinder to the maximum data cylinder and back to the first data cylinder. The full-stroke average is determined by measuring 100 full-stroke seeks in both directions.

Track-to-track typ (msec)	Average typ (msec)	Full-stroke typ (msec)	Latency (msec)
5	14	34	7.87

1.6 Start and stop time

Within 10 seconds, the drive is ready. Typical and maximum start and stop times are shown in the following table. Figure 1 shows a typical startup current profile.

	Typical	Maximum
Start time	7 sec	10 sec
Stop time	6 sec	9 sec

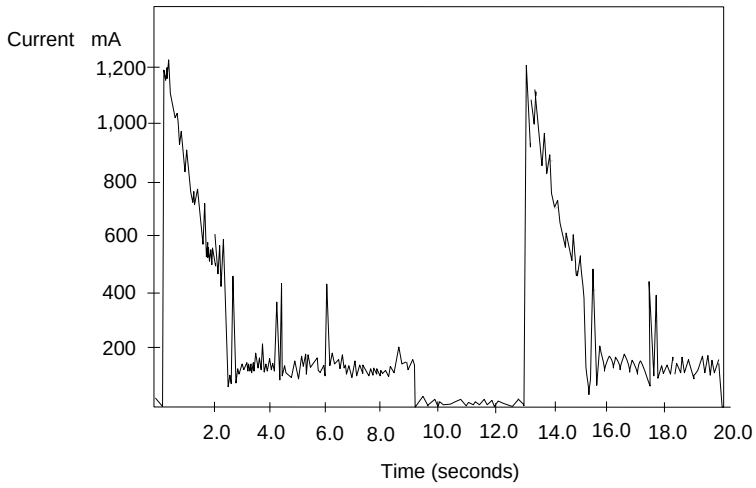

Figure 1. Typical startup current profile

1.7 Power specifications

Except during a write operation, you can apply power to the drive or remove power from the drive in any sequence without losing data or damaging the drive.

1.7.1 Power-management modes

The drive supports the following power-management modes:

- **Active mode.** The drive is seeking, reading or writing.
- **Idle mode.** When the drive receives an Idle Immediate command, or the idle timer counts down to zero, the drive enters the Idle mode. In Idle mode, the spindle remains up to speed. The segmented cache remains enabled, and the drive accepts all commands and returns to the Active mode whenever a seek, read or write operation is needed.
- **Standby mode.** When the drive receives a Standby Immediate command, or the standby timer has counted down to zero, the drive enters the Standby mode. In the Standby mode, the segmented cache remains enabled, the heads are parked in the shipping zone and the spindle is stopped. The drive accepts all commands and returns to the Active mode whenever a seek, read or write operation is needed.
- **Sleep mode.** When the drive receives a Sleep Immediate command, it enters the Sleep mode. The heads are parked in the shipping zone and the spindle is at rest. A hard reset or a soft reset returns the drive to Active mode. A soft reset preserves the current emulation and translation parameters.

1.7.1.1 Idle and Standby timers

The drive can enter the Idle mode or the Standby mode by either of two methods:

- The computer sends an Idle Immediate command or a Standby Immediate command.
- The idle timer or the standby timer counts down to zero.

The Idle and Standby timers are disabled at the factory. Use the computer's setup utility to enable and set the timer delays. When the Idle timer is enabled, it is initialized each time the drive completes a read, write or seek.

If the Idle timer reaches zero before any drive activity is required, the drive goes into the Idle mode, and the Standby timer, if it is enabled, is initialized. If the Standby timer reaches zero before any drive activity is

required, the drive goes into the Standby mode. See the *Seagate ATA Interface Reference Manual*, publication number 36111-*xxx* for details.

In both the Idle and Standby modes, the drive accepts all commands and returns to the Active mode any time disc access is necessary. There may be a slight delay between the time the drive receives the command and drive activity begins.

1.7.1.2 Power consumption

The following guidelines are used to measure power consumption:

- All measurements are taken at sea level with an ambient temperature of 25°C.
- All typical measurements are taken using nominal voltages; the peak startup power is measured using the nominal voltages.
- Seek current measurements are taken using an RMS meter while the drive is randomly seeking with two spindle rotations between each seek.

Mode	Current (amps)		Power (watts)
	+12V	+5V	
Spinup (peak)	1.2	0.35	8.5[3]
Active			
Seeking (typ)	0.34	0.23	5.23
Read/write (typ)	0.145	0.32	3.34
Idle[2] (typ)	0.12	0.085	1.865
Standby[2] (typ)	0.025	0.085	0.725
Sleep[2] (typ)	0.025	0.070	0.650

1.7.2 Voltage tolerances

	+5V	+12V
Voltage tolerance including noise	± 5%	± 5% ± 10% during spinup

2. These values apply only when power management is enabled. To enable power management, use the computer setup utility.

3. Spinup power is averaged over 7 seconds.

1.7.3 Conducted noise

The drive is expected to operate with a maximum of:

- 150 mV peak-to-peak triangular-wave injected noise at the power connector. The frequency is 10 Hz to 100 KHz with equivalent resistive loads.[4]
- 100 mV peak-to-peak triangular-wave injected noise at the power connector. The frequency is 100 KHz to 10 MHz with equivalent resistive loads.[4]

1.7.4 Environment

The acceptable environmental conditions for the drive are specified below. The specifications in this section are defined as follows:

- Operating specifications assume that the drive is powered up.
- Nonoperating specifications assume that the drive is packaged as it was shipped from the factory.

1.7.5 Ambient temperature

Operating	5° to 55°C (41° to 131°F)
Nonoperating	–40° to 70°C (–104° to 158°F)

1.7.6 Temperature gradient

Operating (max)	20°C per hour (36°F per hour)
Nonoperating (max)	30°C per hour (54°F per hour)

4. Equivalent resistance is calculated by dividing the respective voltage by the typical RMS read/write current.

1.7.7 Relative humidity

Operating	8% to 80% noncondensing Maximum wet bulb 29.4°C (85.0°F)
Nonoperating	5% to 95% noncondensing Maximum wet bulb 40.0°C (104.0°F)

1.7.8 Altitude

Operating	–1,000 ft to 10,000 ft (–305 m to 3,050 m)
Nonoperating	–1,000 ft to 40,000 ft (–305 m to 12,200 m)

1.7.9 Shock and vibration

Shock measurements are based on an 11 msec, half sine wave shock pulse, not to be repeated more than twice per second. The specifications in the table below are defined as follows:

- During normal operating shock and vibration, the drive sustains no physical damage and reads and writes data without errors.
- During abnormal operating shock and vibration, the drive sustains no physical damage, but performance is adversely affected.
- During nonoperating shock and vibration, the read/write heads are in the shipping zone and the drive sustains no physical damage.

	Normal operating	**Abnormal operating**	**Nonoperating**
Shock	2.0 Gs	10.0 Gs	75.0 Gs
5–22 Hz vibration	0.020-inch displacement peak-to-peak	0.030-inch displacement peak-to-peak	0.160-inch displacement peak-to-peak
22–300 Hz vibration	1.0 G peak-to-peak	1.5 Gs peak-to-peak	8.0 Gs peak-to-peak

1.8 Acoustics

Sound pressure is measured at idle from 1 meter above the drive top cover.

Sound pressure, typ	29 dBA
Sound pressure, max	33 dBA

1.9 Reliability

The MTBF and contact start-stop specifications assume nominal power at sea level with an ambient temperature of 25°C.

Nonrecoverable errors	1 per 10^{13} bits read
MTBF	300,000 power-on hours
Contact start-stop (CSS)	40,000 cycles
MTTR	30 minutes
Service life	5 years

1.10 Auto-park

Upon power-down, the read/write heads automatically move to the shipping zone. The heads park inside the maximum data cylinder. When power is applied, the heads recalibrate to track 0.

1.11 Agency listings

This drive is listed with agencies as follows:

- UL 1950
- CSA C22.2 No. 0-M91 and CSA C22.2 No. 950-M89
- EN 60950/10.92 as tested by TUV-Rheinland, North America

1.12 FCC verification

The ST3630A drive is intended to be contained solely within a personal computer or similar enclosure (not attached to an external device). As such, a drive is considered to be a subassembly even when individually marketed to the customer. As a subassembly, no Federal Communications Commission authorization, verification or certification of the device is required.

Seagate Technology, Inc. has tested the drive in an enclosure as described above to ensure that the total assembly (enclosure, disc drive, motherboard, power supply, etc.) does comply with the limits for a Class B computing device, pursuant to Subpart J of Part 15 of the FCC rules. Operation with noncertified assemblies is likely to result in interference to radio and television reception.

Radio and television interference. This equipment generates and uses radio frequency energy and, if not installed and used in strict accordance with the manufacturer's instructions, may cause interference to radio and television reception.

This equipment is designed to provide reasonable protection against such interference in a residential installation. However, there is no guarantee that interference will not occur in a particular installation. If this equipment does cause interference to radio or television, which can be determined by turning the equipment on and off, you are encouraged to try one or more of the following corrective measures:

- Reorient the receiving antenna.
- Move the device to one side or the other of the radio or TV.
- Move the device farther away from the radio or TV.
- Plug the equipment into a different outlet so that the receiver and computer are on different branch outlets.

If necessary, you should consult your dealer or an experienced radio/television technician for additional suggestions. You may find helpful the following booklet prepared by the Federal Communications Commission: *How to Identify and Resolve Radio-Television Interference Problems.* This booklet is available from the Superintendent of Documents, US Government Printing Office, Washington, DC 20402. Refer to publication number 004-000-00345-4.

2.0 Configuration and mounting

This section discusses the ATA interface connector and other physical features of the drive, including mounting. Figure 3 on page 13 shows the location of the following features:

- The ATA interface connector
- The power connector
- The master/slave jumper block
- The optional drive activity LED

A brief discussion of each starts on page 12.

2.1 Handling and static-discharge precautions

After you unpack the drive, and before you install it in a computer, be careful not to damage it through mishandling. Wool and synthetic clothing, carpet, plastics and Styrofoam are contributors to the static build-up that can damage sensitive components when discharged through touch. Observe the following standard handling and static-discharge precautions:

Caution:

- Keep the drive in its static-shielded bag until you are ready to complete the installation. Do not attach any cables to the drive while it is in its static-shielded bag.
- Wear a grounded wrist strap that is properly connected to earth ground, or ground yourself frequently by touching the metal chassis of a power supply that is plugged into a grounded outlet when handling the drive and throughout the entire installation procedure.
- Handle the drive by its edges or frame only.
- The drive is extremely fragile—handle it with care. Do not press down on the drive top cover.
- Always rest the drive on a padded, antistatic surface until you mount it in the computer.
- Do not touch the connector pins or the printed circuit board. Do not touch the printed circuit cable between the circuit board and the head/disc assembly.
- Do not remove the factory-installed labels from the drive or cover them with additional labels. If you do, you void the warranty. Some factory-installed labels contain information needed to service the drive. Others are used to seal out dirt and contamination.

2.2 The ATA interface connector

The drive uses a standard 40-pin interface connector with 2 rows of 20 male pins. Pin 20 is removed. The connector is shown in Figure 2.

For the mating connector, use a 40-pin, nonshielded connector with 2 rows of 20 female contacts. We recommend the following part numbers:

AMP	499496
Berg Electronics	66900-040

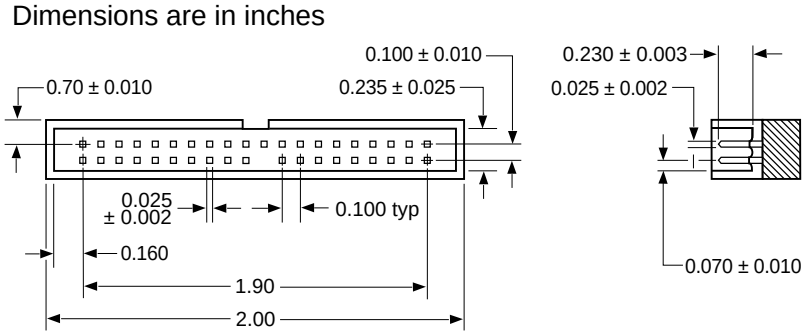

Figure 2. The drive interface connector

2.3 Power connector

The drive comes with a standard 4-pin power connector. It is also available with a standard 3-pin power connector.

2.4 Master/slave jumper block

Figure 3 shows the location of the master/slave jumper block and shows how to install the jumpers for various configurations. The jumper block accepts 2-mm (0.079-inch) jumpers. A spare jumper is attached to the jumper block. If you need additional jumpers, use Seagate part number 10562-001 or an equivalent.

Caution. If you use a jumper that is not the correct size, you may damage the jumper block and the jumper. Use the jumpers supplied with the drive.

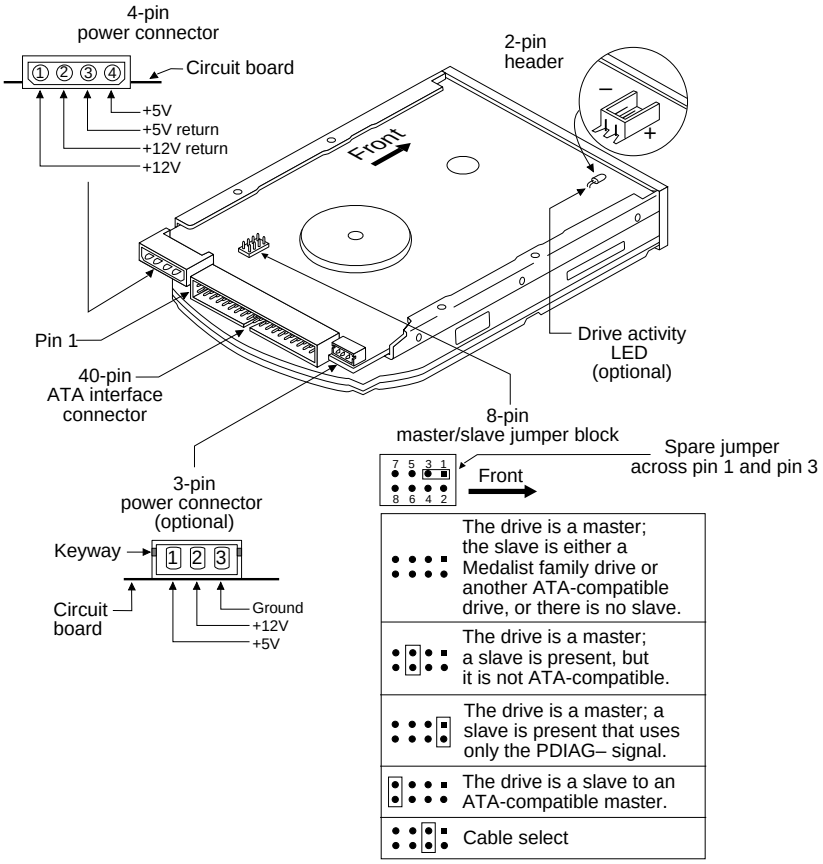

Figure 3. Connectors and jumpers

2.4.1 Single-drive configuration

Use the factory-default jumper setting when the ST3630A drive is installed as the single drive in the computer.

2.4.2 Two-drive configuration

When two drives are installed in the computer, you must configure one drive as the master and the other as the slave.

2.4.2.1 The ST3630A drive as master

The ST3630A provides three ways the slave can identify itself. You can configure the ST3630A for a slave that is:

- An ATA-compatible drive
- A non-ATA-compatible drive that does not conform to the DASP– timing parameter of the ATA spec
- A non-ATA-compatible drive that does not conform to the DASP– timing parameter of the ATA spec but negates PDIAG– when the drive is ready

2.4.2.2 The ST3630A as slave

The ST3630A drive conforms to the ATA standard for slave identification. If the master drive is a non-ATA-compatible drive, it may not recognize the ST3630A drive in the slave position. We recommend that you configure your ST3630A drive as the master when used with a non-ATA-compatible drive.

2.4.3 Cable-select configuration

If your computer and both of your drives support cable select (CSEL), you can use the cable select option to determine the master and slave. To configure your drive to use cable select, you need to install jumpers and to use a special cable-select cable as follows:

- Install a jumper on pins 3 and 4 of the master/slave jumper block as shown in Figure 3 on page 13. When a jumper is installed in this position, the drive ignores the jumper installed on pins 7 and 8.
- You must use an interface cable built for cable-select. To make a drive the master, attach it to the connector that has the CSEL signal line connected to pin 28. To make a drive the slave, attach it to the connector that has pin 28 unconnected (CSEL is not carried to pin 28 of that cable connector.) Note that CSEL is grounded at the host.

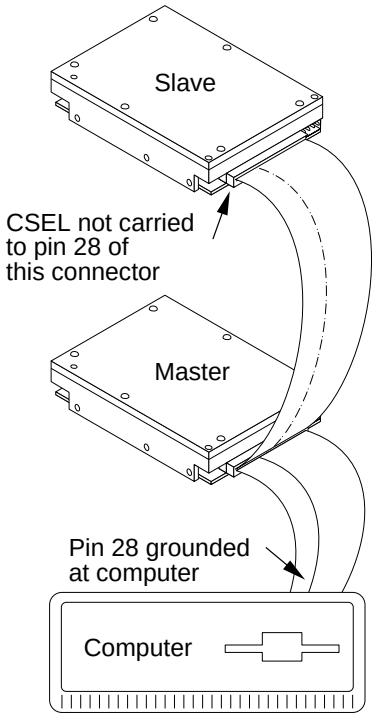

Figure 4. Connecting cable-selected drives

2.4.4 Factory-test configuration

Do not install jumpers on pins 5 and 6 and pins 7 and 8 at the same time. This configuration is used to test the drive at the factory. When jumpers are installed in both of these positions, the heads continuously seek back and forth across the media and the drive ignores all control signals sent by the interface.

2.5 Optional drive activity LED

The drive is available with or without the external activity LED shown in Figure 3 on page 13. This option is available for users for whom the activity display through the bus is inaccessible or inconvenient. There are two LED options:

- The LED is mounted directly on the printed circuit board, or
- A two-pin header is mounted on the printed circuit board for a remote LED. The anode pin of the header is nearest the edge of the PCB.

2.6 Mounting the drive

You can mount the drive in any orientation using either the bottom or the side mounting holes, as described below. Figure 5 shows the SAE dimensions for the drive. Figure 6 on page 18 shows the metric dimensions for the drive.

Note. The location of the mounting holes are different for the SAE and metric drives. Overall, the drive dimensions are the same.

- SAE drives have an "S" stamped on the frame runner and accept 6-32 UNC screws.
- Metric drives have an "M" stamped on the frame runner and accept M3 screws.

Bottom mounting holes. Insert four mounting screws not more than 0.20 inches (6 full turns) into the drive frame.

Side mounting holes. Insert four mounting screws not more than 0.13 inches (4 full turns) into the drive frame.

Caution. To prevent damage to the drive:

- Use only mounting screws of the correct size and length.
- Lightly tighten the mounting screws—do not apply more than 6 inch-pounds of torque.

Figure 5 shows the dimensions in inches. The mounting holes are located in different positions for the SAE drive than the mounting holes on the metric drive shown in Figure 6 on page 18.

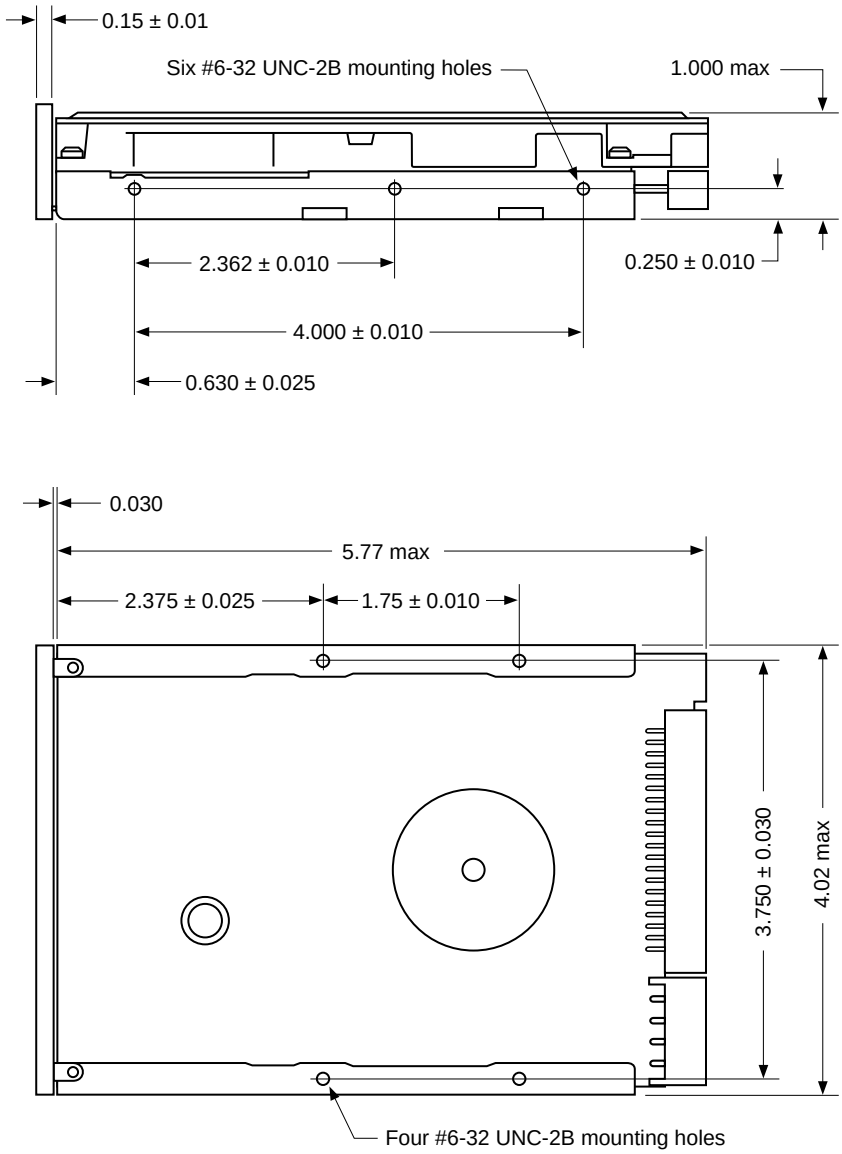

Figure 5. Standard mounting dimensions

Figure 6 shows the dimensions in millimeters. This figure shows that the mounting holes for the metric drive are in different positions than the mounting holes for the SAE drive shown in Figure 5 on page 17.

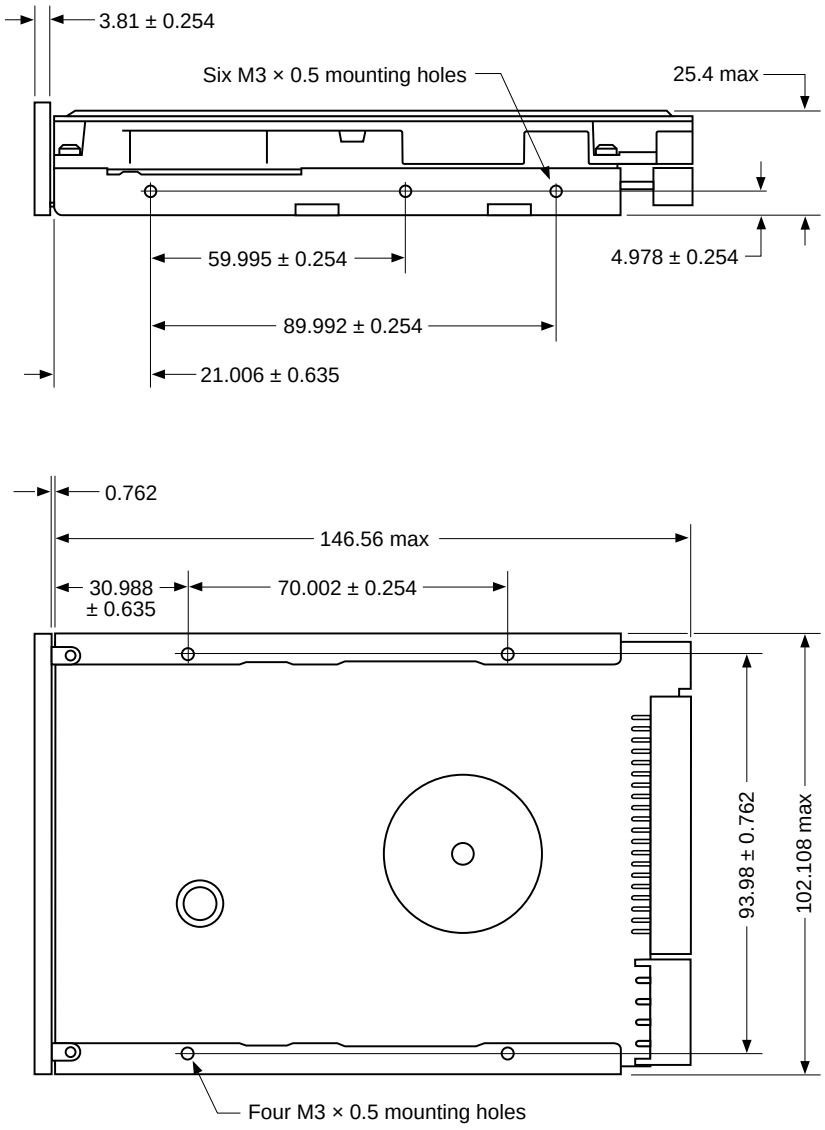

Figure 6. Metric mounting dimensions

3.0 ATA interface

The drive uses an ATA interface. The interface is in compliance with ANSI *ATA (AT Attachment) Interface X3.221, Rev. 4; SFF 8011: ATA Timing Extension for Local Bus Attachments, Rev. 2.0*; *SFF 8019: Identify Drive Data for Drives Under 8 GB* and *Draft Proposal American National Standards AT Attachment Interface X3.310-948D, Rev. 2E*. The ATA commands the drive supports are listed in the table on page 22. Commands and features with specific application for the drive are discussed in this section. For a general discussion of the Seagate ATA interface, refer to the *Seagate ATA Interface Reference Manual*, publication number 36111-*xxx*.

The ATA interface consists of single-ended, TTL-compatible receivers and drivers that use an asynchronous interface protocol. The drivers can sink up to 24 mA and drive a load up to 300 pF. The integrity of the ATA interface is affected by the interface cable. It is designed to support a 40-conductor, nonshielded interface cable with a maximum length of 18 inches (0.46 meters).

3.1 ATA interface connector pin assignments

The signal name and direction for each I/O connector pin is shown in Figure 7 on page 20. For a description of each pin, see the *Seagate ATA Interface Reference Manual*, publication number 36111-*xxx.*

Signal names are shown in upper-case letters. Signal name followed by a minus sign (–) indicate the signal is active low. Otherwise, the signal is active high.

Note. The drive does not use the SPSYNC– signal.

3.2 Bus signal levels

Signals that the drive sends have the following output characteristics measured at the drive connector.

Logic low	0 to 0.4V
Logic high	2.5 to 5.25V

Signals that the drive receives must have the following input characteristics measured at the drive connector.

Logic low	0 to 0.8V
Logic high	2.0 to 5.25V

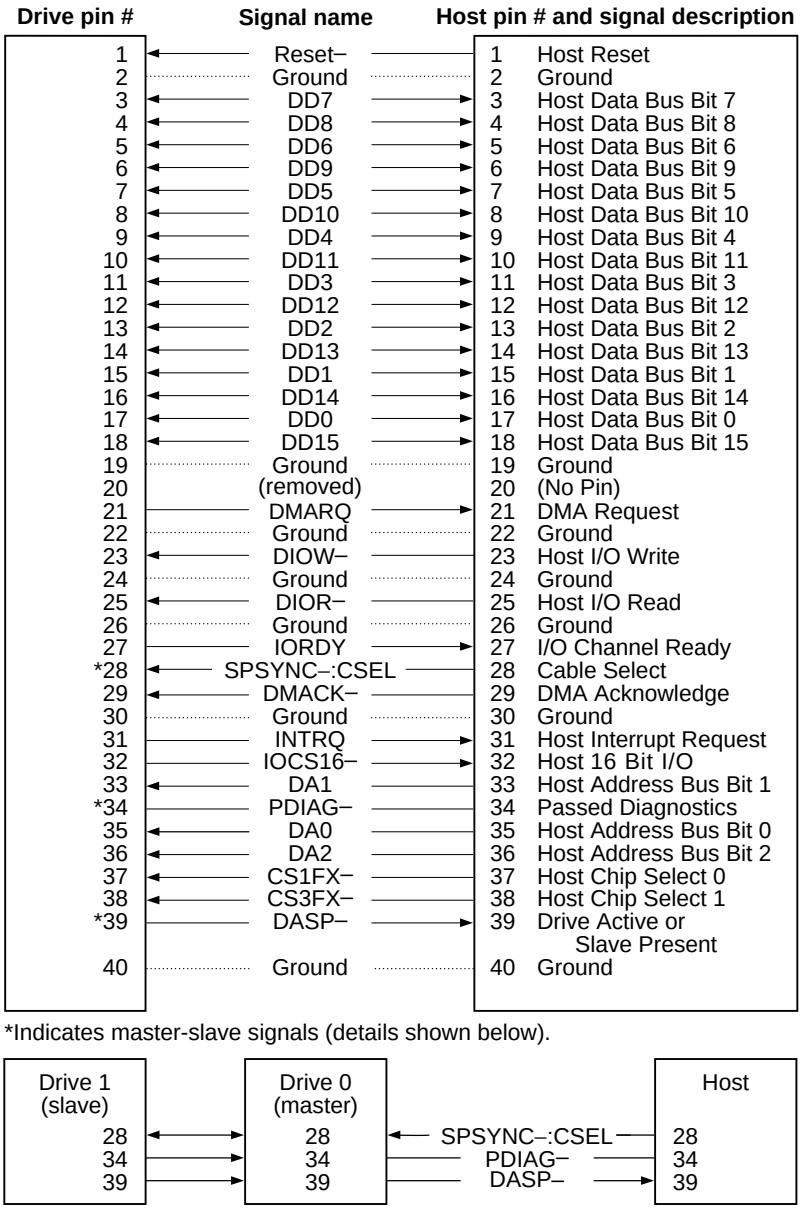

Figure 7. ATA connector pin assignments

3.3 Supported ATA commands

The table on page 22 lists all ATA commands the drive uses. Commands that have a particular application for the drive or that may be of special interest are discussed in this manual. For a complete description of all ATA interface commands the drive uses, refer to the *Seagate ATA Interface Reference Manual*, part number 36111-*xxx*. Additional information is provided by the Small Form Factor specification, SFF-8011 Rev 1.1, September 18, 1993.

The following table lists all commands implemented in the drive. The table uses the following abbreviations:

FR	Features register
SC	Sector count register
SN	Sector number register
CY	Cylinder register
DH	Drive/head register
n	This register does not contain a valid parameter for this command.
y	This register contains a valid parameter for this command. In the drive/head register, both the drive and head parameters are valid for this command.
D	The drive/head register contains a valid drive parameter for this command. The head parameter is not valid for this command.

Command name	Command code (in hex)	Parameters used				
		FR	SC	SN	CY	DH
Active and Set Idle Timer	FB	n	y	n	n	D
Active Immediate	F9	n	n	n	n	D
Check Idle Mode	FD	n	y	n	n	D
Check Power Mode	98, E5	n	y	n	n	D
Execute Drive Diagnostics	90	n	n	n	n	D
Format Track	50	n	y	n	y	y
Identify Drive	EC	n	n	n	n	D
Idle	97, E3	n	y	n	n	D
Idle and Set Idle Timer	FA	n	y	n	n	D
Idle Immediate	95, F8, E1	n	n	n	n	D
Initialize Drive Parameters	91	n	y	n	n	y
Read DMA	C8, C9	—	y	y	y	y
Read Long	22, 23	n	y	y	y	y
Read Multiple	C4	n	y	y	y	y
Read Sector	20, 21	n	y	y	y	y
Read Sector Buffer	E4	n	n	n	n	D
Read Verify Sector	40, 41	n	y	y	y	y
Recalibrate	1X	n	n	n	n	D
Seek	7X	n	n	y	y	y
Set Features	EF	y	n	n	n	D
Set Multiple Mode	C6	n	y	n	n	D
Set Sleep Mode	99, E6	n	n	n	n	D
Standby	96, E2	n	n	n	n	D
Standby Immediate	94, E0	n	n	n	n	D
Write DMA	CA, CB	—	y	y	y	y
Write Long	32, 33	n	y	y	y	y
Write Multiple	C5	n	y	y	y	y
Write Sector	30, 31	n	y	y	y	y
Write Sector Buffer	E8	n	n	n	n	D

3.3.1 Identify Drive command (EC_H)

The Identify Drive command transfers information about the drive to the host after power up. The data is organized as a single 512-byte block of data. The block's contents are shown in the table below. All reserved bits or words must be set to zero. Parameters listed with an "x" are drive-specific or vary with the state of the drive.

The parameters for the drive are listed in the table below. For a complete description of the Identify Drive command, see the *Seagate ATA Interface Reference Manual*, publication number 36111-*xxx*.

Word	Description	Value
0	Configuration	$045A_H$ Bit 10: 1 = disc transfer rate > 10 Mbits/sec Bit 6: 1 = fixed drive Bit 4: 1 = head switch time > 15 μsec Bit 3: 1 = not MFM encoded Bit 1: 1 = hard-sectored disc
1	Default cylinders	1,223
2	Reserved	0000_H
3	Default heads (default)	16
4	Bytes per track	$8D90_H$
5	Bytes per sector	0248_H
6	Default sectors per track	63
7–9	Vendor-unique	0000_H
10–19	Serial number	Drive-unique: 20 ASCII characters
20	Buffer type	0003_H Multisector with caching
21	Buffer size (number of 512-byte sectors)	$00F0_H$ (240_D)
22	ECC bytes (R/W Long)	0010_H (16_D)
23–26	Firmware revision	Drive-dependent: 8 ASCII characters
27–46	Model number	ST3630A

continued

continued from previous page

Word	Description	Value
47	Maximum sectors per interrupt on read/write multiple	0010_H
48	Double word I/O	0000_H Not supported
49	Capabilities	$0B00_H$ DMA, IORDY and LBA supported
50	Reserved	0000_H
51	PIO timing mode	0200_H
52	DMA timing mode	0200_H Single-word DMA supported
53	Current valid	0003_H Bit 0 = 1 indicates the fields reported in words 54–58 are valid; Bit 1 = 1 indicates the fields reported in words 64–8 are valid
54	Current cylinders	1,223
55	Current heads	16
56	Current sectors per track	63
57–58	Current sectors	1,232,784
59	Current multiple sector setting	01*xx*$_H$
60–61	LBA total sectors	1,232,784
62	Single-word DMA	07_H No modes are active; Modes 0, 1 and 2 are supported
63	Multiword DMA	0103_H Mode 0 is active; Modes 0 and 1 are supported
64	Advanced PIO	0001_H Mode 3 is supported
65	Minimum multiword DMA transfer per word	150 nsec
66	Recommended multiword DMA transfer per word	150 nsec

Word	Description	Value
67	Minimum PIO without IORDY	400 nsec
68	Minimum PIO with IORDY[5]	180 nsec
69–127	Reserved	0000_H
128–159	Reserved	$xxxx_H$
160–255	Reserved	0000_H

3.3.2 Format track command (50_H)

The drive accepts a Format track command (50_H) and the 512 bytes of the format data transferred by the host. However, the command does not mark bad sectors, reassign sectors or unreassign sectors. The first sector data the host transfers is ignored. A 00 data pattern is written to the track specified in the command.

5. Cycle times less than 400 nsec require IORDY.

3.3.3 Set Features command (EF_H)

The host uses the Set Features command (command code EF_H) to establish parameters that affect the execution of certain drive features. To use the command:

1. Write the Feature value to the Features register.

2. Write the Set Features command to the command register.

Note. If the value in the Features register is not supported or is invalid, the drive posts an Aborted Command error.

At power-on, or after a hard reset, the feature selections are restored to the factory-default values. If 66_H has been set, a software reset does not change the feature selections (this can be canceled by setting CC_H). If 66_H has not been set, a soft reset returns the settings to the factory defaults.

The following table shows the alterable features the drive supports. Where a factory default value exists, that value is listed.

Byte	Feature description
02_H	Enable write cache (factory default).
03_H	Set value for Set Transfer mode based on value in Sector Count register.
44_H	Use maximum length of ECC (16 bytes) on read long/write long commands (factory default).
55_H	Disable read look-ahead feature.
66_H	Use current settings as default (until hard reset or power off).
82_H	Disable write cache.
AA_H	Enable read look-ahead feature (factory default).
BB_H	4 bytes of ECC apply on read long/write long commands.
CC_H	Enable reverting to power-on defaults (factory default).

3.3.3.1 PIO and DMA Data Transfer Modes

You can set the multiword DMA mode and identify the PIO data-transfer mechanism and transfer mode with the Set Features command. To set the multiword DMA mode:

1. Write Set Features command value 03_H (Set Data Transfer mode) to the Features register.
2. Write a transfer types value to the Sector Count register. The upper 5 bits of this value define the type of data transfer, and the lower 3 bits encode the mode value.

   This changes word 63 of the Identify Drive command to the mode you enter in the Sector Count register.

The following table identifies allowable transfer types values:

Data-Transfer Mechanism		Transfer Types value	
Mechanism name	**Mode value**	**Data Upper 5 bits**	**Lower 3 bits**
PIO Transfer Mode (default: Set PIO Mode = 2)	2	00000	000
PIO Transfer Mode: Set PIO Mode = 2	2	00000	001
PIO Flow Control Transfer Mode: Set PIO Mode = 0	0	00001	000
PIO Flow Control Transfer Mode: Set PIO Mode = 1	1	00001	001
PIO Flow Control Transfer Mode: Set PIO Mode = 2	2	00001	010
PIO Flow Control Transfer Mode: Set PIO Mode = 3	3	00001	011
Multiword DMA Mode	0	00100	000
Multiword DMA Mode	1	00100	001
Reserved	—	01000	*nnn*

If the drive does not support a commanded mode, the drive returns an Aborted Command error.

If the drive receives a Set Features command with a Mechanism and mode value of 00000 001 and the drive supports disabling of IORDY, then the drive sets its default PIO transfer mode and disables IORDY.

3.3.4 Set Multiple Mode command ($C6_H$)

Command code $C6_H$ enables the drive to perform Read and Write Multiple operations and establishes the block count for these commands. You do not have to issue this command before every Read Multiple or Write Multiple command.

The Sector Count register is loaded with the number of sectors per block. Drives normally support block sizes of 2, 4, 8 and 16 sectors. However, other block-size values may also be supported, depending on the size of the drive's buffer. After receiving the Set Multiple Mode command, the drive sets BSY=1 and checks the Sector Count register.

If the Sector Count register contains a valid value and the block count is supported, the value is loaded for all subsequent Read Multiple and Write Multiple commands and execution of those commands is enabled. If a block count is not supported, an Aborted Command error is posted, and Read Multiple and Write Multiple commands are disabled.

If the Sector Count register contains 0 when the command is issued, Read and Write Multiple commands are disabled.

At power on, or after a hardware reset, the default mode is Read and Write Multiple disabled. If Disable Default has been set in the Features register, then the mode remains the same as that last established before a software reset. Otherwise it reverts to the default of disabled.

3.3.5 Read Multiple command ($C4_H$)

This command (code $C4_H$) is similar to the Read Sectors command. Interrupts are not generated on every sector, but on the transfer of a block that contains the number of sectors defined by a Set Multiple Mode command.

The number of sectors per block to be transferred without intervening interrupts is programmed by the Set Multiple Mode command, which must be executed before the Read Multiple command. Interrupts are generated when DRQ is set to 1 at the beginning of each block or partial block.

When the Read Multiple command is issued, the Sector Count register contains the number of sectors (not the number of blocks or the block count) requested.

If the number of requested sectors is not evenly divisible by the block count, as many full blocks as possible are transferred, followed by a final, partial block transfer. The partial block transfer is for *n* sectors, where

n = remainder (sector count / block count)

If the Read Multiple command is attempted before the Set Multiple Mode command has been executed or when Read Multiple commands are disabled, the Read Multiple operation is rejected with an Aborted Command error.

Disc errors encountered during Read Multiple commands are posted at the beginning of the block or partial block transfer, but DRQ is still set and the data transfer takes place as it normally would, including transfer of corrupted data, if any.

The contents of the Command Block registers, following the transfer of a data block that had a sector in error, are undefined. The host should retry the transfer as individual requests to obtain valid error information.

Subsequent blocks or partial blocks are transferred only if the error was a correctable data error. All other errors cause the command to stop after the block containing the error is transferred.

3.3.6 Write Multiple command ($C5_H$)

This command (command code $C5_H$) is similar to the Write Sectors command. Interrupts are not presented on each sector but on the transfer of a block that contains the number of sectors defined by Set Multiple Mode command.

The number of sectors per block to be transferred without intervening interrupts is programmed by the Set Multiple Mode command, which must be executed before the Write Multiple command.

When the Write Multiple command is issued, the Sector Count register contains the number of sectors (not the number of blocks or the block count) requested.

If the number of requested sectors is not evenly divisible by the block count, as many full blocks as possible are transferred, followed by a final, partial-block transfer. The partial-block transfer is for *n* sectors, where

n = remainder (sector count / block count)

If the Write Multiple command is attempted before the Set Multiple Mode command has been executed or when Write Multiple commands are disabled, the Write Multiple operation is rejected with an aborted command error.

Disc errors encountered during Write Multiple commands are posted after the attempted disc write of the block or partial block transferred. The Write command ends with the sector in error, even if it was in the middle of a block. Subsequent blocks are not transferred in the event of an error. Interrupts are generated when DRQ is set to 1 at the beginning of each block or partial block.

The contents of the Command Block registers are undefined when they follow the transfer of a data block that had a sector in error. The host should retry the transfer as individual requests to obtain valid error information.

3.4 Onboard drive diagnostics

During startup, the drive executes a series of diagnostic tests. If the diagnostic tests detect an error, the drive LED indicates the nature of the error by emitting a flash code. A subset of the error flash codes is contained in the following table:

Number of flashes	Error code description
Irregular flashes	Microprocessor error
2	ROM checksum error
3	External RAM error
4	I/O chip error
5	Buffer RAM error

3.5 ECC performance tests

The drive does not report ECC errors when it performs on-the-fly error correction. This allows the drive to correct the data without sacrificing performance.

Some older drive diagnostic utilities test the drive's ability to apply ECC by creating small data errors and then checking to see if these errors are reported. If you run one of these tests on a drive that is functioning properly, the test may report that the drive is failing to detect ECC errors. However, this does not mean that the drive is malfunctioning.

3.6 Supported BIOS

The drive uses 16 bytes of ECC with Read Long and Write Long commands. If the computer BIOS expects less than 16 bytes, some drive diagnostics may return false failures (typically time-out errors). If so, you must reconfigure the computer to receive 4 bytes of ECC.

The BIOS revisions listed in the following table are fully compatible with the ATA interface the drive uses. Earlier BIOS revisions than those listed may not fully support the ATA interface as implemented on the drive.

BIOS manufacturer	**Version supported**
American Megatrends	Dated 4/9/90 or later
Award	3.04 or higher
Quadtel	Single drive, any version Dual drive, 3.04 or higher
Phoenix	ROM BIOS Plus 286, 3.10 or higher ROM BIOS Plus 386, 1.10 or higher
PhoenixBIOS	1.00 or higher

Seagate

Seagate Technology, Inc.
920 Disc Drive, Scotts Valley, California 95066, USA

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