



## Specification for D-PHY<sup>SM</sup>

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Further technical changes to this document are expected as work continues in the D-PHY Working Group.

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## Release History

Date	Version	Description
08-Mar-2016	v2.0	Initial Board adopted release.
05-Jul-2019	v2.5	Board adopted release.
21-Jul-2021	v3.0	Board adopted release.

## 1 Introduction

This specification provides a flexible, low-cost, High-Speed serial interface solution for communication interconnection between components inside a mobile device. Traditionally, these interfaces are CMOS parallel busses at low bit rates with slow edges for EMI reasons. The D-PHY solution enables significant extension of the interface bandwidth for more advanced applications. The D-PHY solution can be realized with very low power consumption.

### 1.1 Scope

The scope of this document is to specify the lowest layers of High-Speed source-synchronous interfaces to be applied by MIPI Alliance application or protocol level specifications. This includes the physical interface, electrical interface, low-level timing and the PHY-level protocol. These functional areas taken together are known as D-PHY.

The D-PHY specification shall always be used in combination with a higher layer MIPI specification that references this specification. Any other use of the D-PHY specification is strictly prohibited, unless approved in advance by the MIPI Board of Directors.

The following topics are outside the scope of this document:

**Explicit specification of signals of the clock generator unit.** Of course, the D-PHY specification does implicitly require some minimum performance from the clock signals. Intentionally, only the behavior on the interface pins is constrained. Therefore, the clock generation unit is excluded from this specification, and will be a separate functional unit that provides the required clock signals to the D-PHY in order to meet the specification. This allows all kinds of implementation trade-offs as long as these do not violate this specification. More information can be found in [Section 5](#).

**Test modes, patterns, and configurations.** Obviously testability is very important, but because the items to test are mostly application specific or implementation related, the specification of tests is deferred to either the higher layer specifications or the product specification. Furthermore MIPI D-PHY compliance testing is not included in this specification.

**Procedure to resolve contention situations.** The D-PHY contains several mechanisms to detect Link contention. However, certain contention situations can only be detected at higher levels and are therefore not included in this specification.

**Ensure proper operation of a connection between different Lane Module types.** There are several different Lane Module types to optimally support the different functional requirements of several applications. This means that next to some base-functionality there are optional features which can be included or excluded. This specification only ensures correct operation for a connection between matched Lane Modules types, which means: Modules that support the same features and have complementary functionality. In case the two sides of the Lane are not the same type, and these are supposed to work correctly, it shall be ensured by the manufacturer(s) of the Lane Module(s) that the provided additional functionality does not corrupt operation. This can be easiest accomplished if the additional functionality can be disabled by other means independent of the MIPI D-PHY interface, such that the Lane Modules behave as if they were the same type.

**ESD protection level of the IO.** The required level will depend on a particular application environment and product type.

**Exact Bit-Error-Rate (BER) value.** The actual value of the achieved BER depends on the total system integration and the hostility of the environment. Therefore, it is impossible to specify a BER for individual parts of the Link. This specification allows for implementations with a  $BER < 10^{-12}$ .

**Specification of the PHY-Protocol Interface.** The D-PHY specification includes a PHY-Protocol Interface (PPI) annex that provides one possible solution for this interface. This annex is limited to the essential signals for normal operation in order to clarify the kind of signals needed at this

46 interface. For power reasons this interface will be internal for most applications. Practical  
47 implementations may be different without being inconsistent with the D-PHY specification.

48 **Implementations.** This specification is intended to restrict the implementation as little as possible.  
49 Various sections of this specification use block diagrams or example circuits to illustrate the  
50 concept and are not in any way claimed to be the preferred or required implementation. Only the  
51 behavior on the D-PHY interface pins is normative.

52 D-PHY Specification evolution is primarily driven by the need to achieve higher data rates and better  
53 efficiency, while at the same time respecting backward compatibility. In this process the previous version of  
54 the specification is taken and modifications are added, without compromising backward compatibility.  
55 Each new version of the specification that is derived both preserves all the specification components of the  
56 previous version, and adds the new changes. Due to technology evolution, some parameters are changed to  
57 optimize for newer technologies.

58 It is recommended to always follow the latest version of the D-PHY Specification, irrespective of the  
59 targeted data rate. The product data sheet should mention both the targeted D-PHY Specification version  
60 and data rates. This will enable the system integrator to make proper decisions to achieve interoperability  
61 goals.

62 Regulatory compliance methods are not within the scope of this document. It is the responsibility of  
63 product manufacturers to ensure that their designs comply with all applicable regulatory requirements.

## 1.2 Purpose

64 The D-PHY specification is used by manufacturers to design products that adhere to MIPI Alliance  
65 interface specifications for mobile device such as, but not limited to, camera, display and unified protocol  
66 interfaces.

67 Implementing this specification reduces the time-to-market and design cost of mobile devices by  
68 standardizing the interface between products from different manufacturers. In addition, richer feature sets  
69 requiring high bit rates can be realized by implementing this specification. Finally, adding new features to  
70 mobile devices is simplified due to the extensible nature of the MIPI Alliance Specifications.

## 2 Terminology

### 2.1 Use of Special Terms

The MIPI Alliance has adopted Section 13.1 of the *IEEE Standards Style Manual*, which dictates use of the words “shall”, “should”, “may”, and “can” in the development of documentation, as follows:

The word *shall* is used to indicate mandatory requirements strictly to be followed in order to conform to the Specification and from which no deviation is permitted (*shall* equals *is required to*).

The use of the word *must* is deprecated and shall not be used when stating mandatory requirements; *must* is used only to describe unavoidable situations.

The use of the word *will* is deprecated and shall not be used when stating mandatory requirements; *will* is only used in statements of fact.

The word *should* is used to indicate that among several possibilities one is recommended as particularly suitable, without mentioning or excluding others; or that a certain course of action is preferred but not necessarily required; or that (in the negative form) a certain course of action is deprecated but not prohibited (*should* equals *is recommended that*).

The word *may* is used to indicate a course of action permissible within the limits of the Specification (*may* equals *is permitted to*).

The word *can* is used for statements of possibility and capability, whether material, physical, or causal (*can* equals *is able to*).

All sections are normative, unless they are explicitly indicated to be informative.

### 2.2 Definitions

**Bi-directional:** A single Data Lane that supports communication in both the Forward and Reverse directions.

**Control Burst:** A High-Speed burst of short duration used to transfer commands in Alternate Low-Power mode.

**DDR Clock:** A half-rate clock used for dual-edged data transmission.

**D-PHY:** The source synchronous PHY defined in this document. Early versions of D-PHY communicated on the order of 500 Mbps, hence the Roman numeral for 500 or “D.”

**Escape Mode:** An optional mode of operation for Data Lanes that allows low bit-rate commands and data to be transferred at very low power.

**Forward Direction:** The signal direction is defined relative to the direction of the High-Speed DDR clock. Transmission from the side sending the clock to the side receiving the clock is the Forward Direction.

**Lane:** Consists of two complementary Lane Modules communicating via two-Line, point-to-point Lane Interconnects. Sometimes Lane is also used to denote interconnect only. A Lane can be used for either Data or Clock signal transmission.

**Lane Interconnect:** Two-Line, point-to-point interconnect used for both differential High-Speed signaling and Low-Power, single-ended signaling.

**Lane Module:** Module at each side of the Lane for driving and/or receiving signals on the Lane.

**Line:** An interconnect wire used to connect a driver to a receiver. Two Lines are required to create a Lane Interconnect.

**Link:** A connection between two devices containing one Clock Lane and at least one Data Lane. A Link consists of at least two PHYs and two Lane Interconnects.

110   **Low Voltage Low Power:** An optional signal voltage range in LP mode.

111   **Master:** The Master side of a Link is defined as the side that transmits the High-Speed Clock. The Master  
112   side transmits data in the Forward Direction.

113   **PHY:** A functional block that implements the features necessary to communicate over the Lane  
114   Interconnect. A PHY consists of one Lane Module configured as a Clock Lane, one or more Lane Modules  
115   configured as Data Lanes and a PHY Adapter Layer.

116   **PHY Adapter:** A protocol layer that converts symbols from an APPI to the signals used by a specific PHY  
117   PPI.

118   **PHY Configuration:** A set of Lanes that represent a possible Link. A PHY configuration consists of a  
119   minimum of two Lanes, one Clock Lane and one or more Data Lanes.

120   **Reverse Direction:** Reverse Direction is the opposite of the Forward Direction. See the description for  
121   Forward Direction.

122   **Slave:** The Slave side of a Link is defined as the side that does not transmit the High-Speed Clock. The  
123   Slave side may transmit data in the Reverse Direction.

124   **Transmission Line Interconnect Structure:** The physical interconnect realization between Master and  
125   Slave.

126   **Turnaround:** Reversing the direction of communication on a Data Lane.

127   **Unidirectional:** A single Lane that supports communication in the Forward Direction only.

128   **Unit Interval:** Time equal to the duration of any HS state on the Clock Lane.

## 2.3 Abbreviations

129   e.g.           For example (Latin: exempli gratia)

130   i.e.           That is (Latin: id est)

## 2.4 Acronyms

131   ALP           Alternate Low-Power: identifier for operation mode

132   ALP-ED       Alternate Low-Power Exit Detector

133   ALP Stop      Alternate Low-Power Stop state

134   ALP ULPS     Alternate Low-Power Ultra -Low Power State

135   ALP Wake     Alternate Low-Power exit state

136   APPI          Abstracted PHY-Protocol Interface

137   BER           Bit Error Rate

138   BTA           Bus Turnaround

139   CIL           Control and Interface Logic

140   CTLE          Continuous-Time Linear Equalizer

141   DCD           Duty-Cycle Distortion

142   DDR           Double Data Rate

143   DUT           Device Under Test

144   EMI           Electro Magnetic Interference

145   EoB           End of Burst

146	EoT	End of Transmission
147	HS	High-Speed; identifier for operation mode
148	HS-RX	High-Speed Receiver (Low-Swing Differential)
149	HS-TX	High-Speed Transmitter (Low-Swing Differential)
150	IO	Input-Output
151	IoT	Internet of Things
152	ISTO	Industry Standards and Technology Organization
153	LP	Low-Power: identifier for operation mode
154	LP-CD	Low-Power Contention Detector
155	LPDT	Low-Power Data Transmission
156	LP-RX	Low-Power Receiver (Large-Swing Single-Ended)
157	LP-TX	Low-Power Transmitter (Large-Swing Single-Ended)
158	LPS	Low-Power State(s)
159	LSB	Least Significant Bit
160	LVLP	Low Voltage Low Power
161	Mbps	Megabits per second
162	MSB	Most Significant Bit
163	PHY	Physical Layer
164	PLL	Phase-Locked Loop
165	PPI	PHY-Protocol Interface
166	RF	Radio Frequency
167	RX	Receiver
168	SE	Single-Ended
169	SoT	Start of Transmission
170	SSC	Spread Spectrum Clocking
171	TLIS	Transmission-Line Interconnect Structure
172	TX	Transmitter
173	UI	Unit Interval
174	ULPS	Ultra-Low Power State

### 3 References

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## 4 D-PHY Overview

D-PHY describes a source synchronous, high speed, low power, low cost PHY, especially suited for mobile applications. This D-PHY specification has been written primarily for the connection of camera and display applications to a host processor. Nevertheless, it can be applied to many other applications. It is envisioned that the same type of PHY will also be used in a dual-simplex configuration for interconnections in a more generic communication network. Operation and available data-rates for a Link are asymmetrical due to a Master-Slave relationship between the two sides of the Link. The asymmetrical design significantly reduces the complexity of the Link. Some features like Bi-directional, half-duplex operation are optional. Exploiting this feature is attractive for applications that have asymmetrical data traffic requirements and when the cost of separate interconnects for a return channel is too high. While this feature is optional, it avoids mandatory overhead costs for applications that do not have return traffic requirements or want to apply physically distinct return communication channels.

### 4.1 Summary of PHY Functionality

The D-PHY provides a synchronous connection between Master and Slave. A practical PHY Configuration consists of a clock signal and one or more data signals. The clock signal is Unidirectional, originating at the Master and terminating at the Slave. The data signals can either be Unidirectional or Bi-directional depending on the selected options. For half-duplex operation, the Reverse Direction data rate is one-fourth of the Forward Direction data rate. Token passing is used to control the communication direction of the Link.

The Link includes a High-Speed signaling mode for fast-data traffic and a Low-Power signaling mode for control purposes. Optionally, a Low-Power Escape Mode can be used for low speed asynchronous data communication. High speed data communication appears in bursts with an arbitrary number of payload data bytes. The optional Alternate Low-Power signaling mode allows all of the Control mode and Escape Mode signaling to be done using the same mechanisms used for high speed data communication. A PHY implementation shall support Low-Power signaling mode, and may support Alternate Low-Power mode. The Alternate Low-Power mode is suitable for IoT applications with long channels, for which it can substitute the Low-Power mode. PHY implementations may additionally support a dynamic switching between the Alternate Low-Power mode and the Low-Power mode; such optional capability is defined in *Annex A*.

The PHY uses two wires per Data Lane plus two wires for the Clock Lane. This gives four wires for the minimum PHY Configuration. In High-Speed mode each Lane is terminated on both sides and driven by a low-swing, differential signal. In Low-Power mode all wires are operated single-ended and non-terminated. For EMI reasons, the drivers for this mode shall be slew-rate controlled and current limited. In Alternate Low-Power mode the communication is done primarily using low-swing, differential signaling with both sides terminated as in High-Speed mode. Some unique events occur with a non-terminated receiver, and even with both Lines of a Lane being driven to the same electrical level.

The actual maximum achievable bit rate in High-Speed mode is determined by the performance of transmitter, receiver and interconnect implementations. Therefore, the maximum bit rate is not specified in this document. However, this specification is primarily intended to define a solution for a data rate range of 80 to 1500 Mbps per Lane without deskew calibration, up to 2500 Mbps with deskew calibration, and up to 9,000 Mbps with equalization. Furthermore, if reverse High-Speed data communication is implemented, it can be done at much lower rates than the forward direction communication due to the asymmetric nature of D-PHY traffic. This specification does not set a maximum limit on those rates, however such information should be included in product datasheets. When ALP mode is implemented the minimum data rate is 4 Mbps in the forward direction and 1 Mbps in the reverse direction. When the implementation supports a data rate greater than 1500 Mbps, it shall also support deskew capability. When a PHY implementation supports a data rate greater than 2500 Mbps, it shall also support equalization, and Spread Spectrum Clocking shall be available. Although PHY Configurations are not limited to this range, practical constraints make it the most suitable range for the intended applications. For a fixed clock frequency, the

234 available data capacity of a PHY Configuration can be increased by using more Data Lanes. Effective data  
235 throughput can be reduced by employing burst mode communication. The maximum data rate in Low-  
236 Power mode is 10 Mbps. The upper range of data rates in Alternate Low-Power mode is consistent with the  
237 limits set for High-Speed mode.

238 The Spread Spectrum Clocking, Transmit Equalization, and Deskew features can be applied for the  
239 transmission at any HS data rate.

## 4.2 Mandatory Functionality

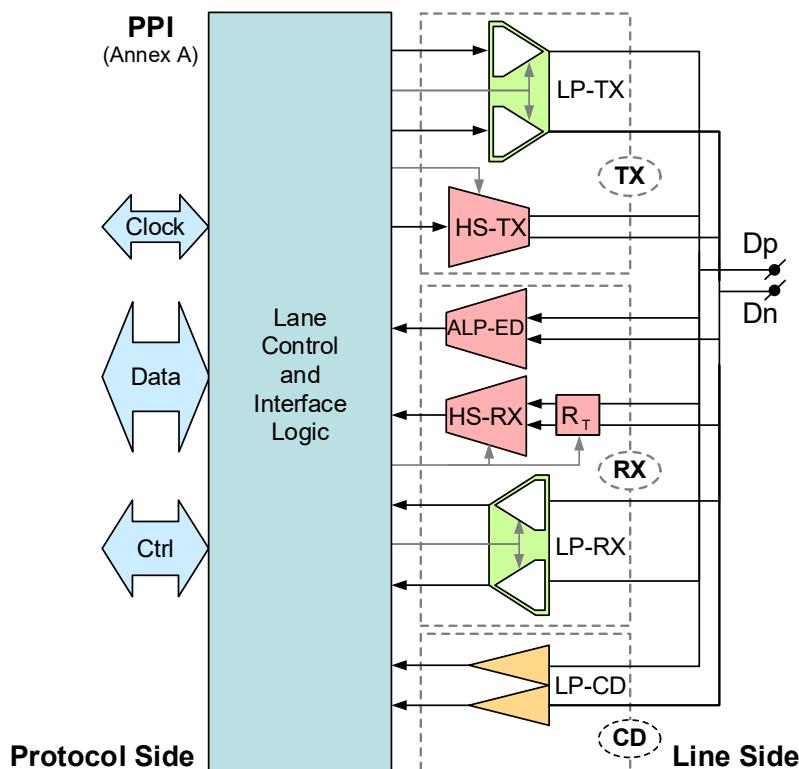
240 All functionality that is specified in this document and which is not explicitly stated in *Section 5.5* shall be  
241 implemented for all D-PHY Configurations.

## 5 Architecture

This Section describes the internal structure of the PHY including its functions at the behavioral level. Furthermore, several possible PHY Configurations are given. Each configuration can be considered as a suitable combination from a set of basic modules.

### 5.1 Lane Modules

A PHY Configuration contains a Clock Lane Module and one or more Data Lane Modules. Each of these PHY Lane Modules communicates via two Lines to a complementary part at the other side of the Lane Interconnect.



**Figure 1 Universal Lane Module Functions**

Each Lane Module consists of one or more differential High-Speed functions utilizing both interconnect wires simultaneously, one or more single-ended Low-Power functions operating on each of the interconnect wires individually, and control & interface logic. Optionally, a low power, low speed ALP Exit Detector (ALP-ED) may exist in a Lane Module. An overview of all functions is shown in **Figure 1**. High-Speed signals have a low voltage swing, e.g., 200 mV, while Low-Power signals have a large swing, e.g., 1.2 V. High-Speed functions are used for High-Speed Data transmission and ALP communication. The Low-Power functions are mainly used for Control, but have other, optional, use cases. The I/O functions are controlled by a Lane Control and Interface Logic block. This block interfaces with the Protocol and determines the global operation of the Lane Module.

High-Speed functions include a differential transmitter (HS-TX) and a differential receiver (HS-RX).

A Lane Module may contain a HS-TX, a HS-RX, or both. A HS-TX and a HS-RX within a single Lane Module are never enabled simultaneously during normal operation. An enabled High-Speed function shall terminate the Lane on its side of the Lane Interconnect as defined in **Section 9.1.1** and **Section 9.2.1**. If a

262 High-Speed function in the Lane Module is not enabled then the function shall be put into a high  
263 impedance state.

264 Low-Power functions include single-ended transmitters (LP-TX), receivers (LP-RX) and Low-Power  
265 Contention-Detectors (LP-CD). Low-Power functions are always present in pairs as these are single-ended  
266 functions operating on each of the two interconnect wires individually. An LP-TX may support an optional  
267 Low Voltage Low Power (LVLP) operation, in which the maximum voltage is limited in comparison to the  
268 normal Low-Power mode. An LP-RX that meets the VIH specification in **Section 9.2.2** supports LVLP  
269 operation.

270 Alternate Low-Power functions include:

- 271 • A Transmitter, which can also drive both Lines to the same ground level
- 272 • An ALP Exit Detector
- 273 • A Receiver

274 Alternate Low-Power and High-Speed mode share common HS-TX and HS-RX functions. An additional  
275 ALP-ED is used for ALP exit detection. If ALP mode is supported this ALP-ED shall be present in all Data  
276 and Clock Lanes to detect the ALP exit.

277 Presence of High-Speed and Low-Power functions is correlated. That is, if a Lane Module contains a HS-  
278 TX it shall also contain a LP-TX. A similar constraint holds for HS-RX and LP-RX, with the addition of  
279 ALP-ED if ALP mode is supported.

280 If a Lane Module containing a LP-RX is powered, that LP-RX shall always be active and continuously  
281 monitor Line levels unless the Lane is configured to work in ALP mode. The LP-RX shall be disabled when  
282 a Lane Module is configured for ALP mode, and the ALP-ED shall monitor Line levels for an ALP exit. A  
283 LP-TX shall only be enabled when driving Low-Power states. The LP-CD function is only required for a  
284 Lane Module supporting Bi-directional operation in Low-Power mode. If present, the LP-CD function is  
285 enabled to detect contention situations while the LP-TX is driving Low-Power states. The LP-CD checks  
286 for contention before driving a new state on the Line except in ULPS.

287 The activities of LP-TX, HS-TX, and HS-RX in a single Lane Module are mutually exclusive, except for  
288 some short crossover periods. For detailed specification of the Line side Clock and Data signals, and the  
289 HS-TX, HS-RX, LP-TX, LP-RX, LP-CD, and ALP-ED functions, see **Section 9** and **Section 10**.

290 For proper operation, the set of functions in the Lane Modules on both sides of the Lane Interconnect has to  
291 be matched. This means for each HS and LP transmit or receive function on one side of the Lane  
292 Interconnect, a complementary HS or LP receive or transmit function must be present on the other side. In  
293 addition, a Contention Detector is needed in any Lane Module that combines TX and RX functions and  
294 supports LP mode. An ALP receive function is needed for RX Lane Modules supporting ALP mode.

## 5.2 Master and Slave

295 Each Link has a Master and a Slave side. The Master provides the High-Speed Clock signal to the Clock  
296 Lane and is the main data source. The Slave receives the clock signal at the Clock Lane and is the main  
297 data sink. The main direction of data communication, from source to sink, is denoted as the Forward  
298 Direction. Data communication in the opposite direction is called Reverse transmission. Only Bi-  
299 directional Data Lanes can transmit in the Reverse direction. In all cases, the Clock Lane remains in the  
300 Forward Direction, but Bi-directional Data Lane(s) can be turned around, sourcing data from the Slave  
301 side.

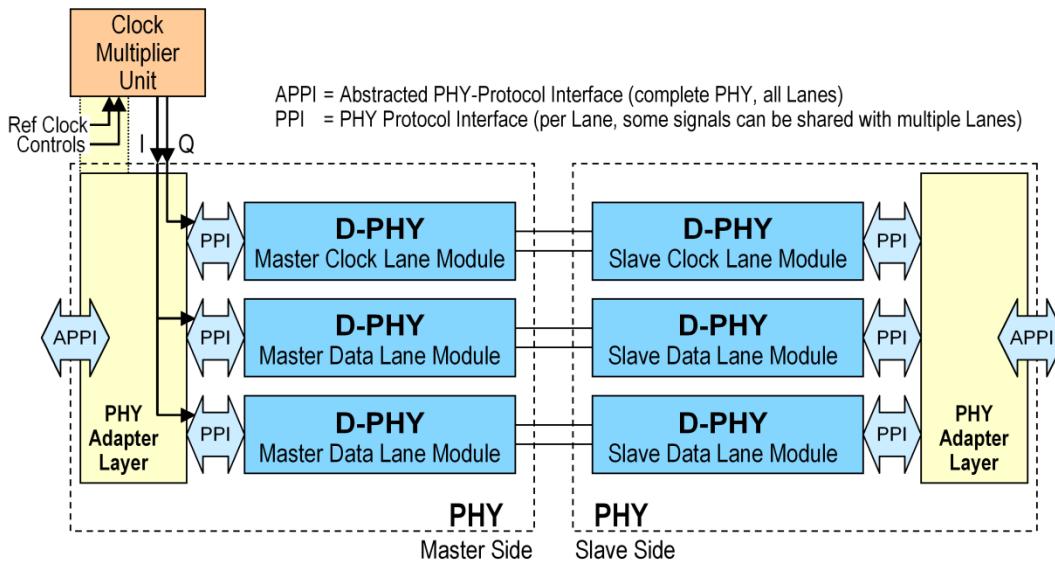
### 5.3 High Frequency Clock Generation

In many cases a PLL Clock Multiplier is needed for the high frequency clock generation at the Master Side. The D-PHY specification uses an architectural model where a separate Clock Multiplier Unit outside the PHY generates the required high frequency clock signals for the PHY. Whether this Clock Multiplier Unit in practice is integrated inside the PHY is left to the implementer.

### 5.4 Clock Lane, Data Lanes and the PHY-Protocol Interface

A complete Link contains, beside Lane Modules, a PHY Adapter Layer that ties all Lanes, the Clock Multiplier Unit, and the PHY Protocol Interface together. **Figure 2** shows a PHY Configuration example for a Link with two Data Lanes plus a separate Clock Multiplier Unit. The PHY Adapter Layer, though a component of a PHY, is not within the scope of this specification.

The logical PHY-Protocol interface (PPI) for each individual Lane includes a set of signals to cover the functionality of that Lane. As shown in **Figure 2**, Clock signals may be shared for all Lanes. The reference clock and control signals for the Clock Multiplier Unit are not within the scope of this specification.



**Figure 2** Two Data Lane PHY Configuration

## 5.5 Selectable Lane Options

A PHY Configuration consists of one Clock Lane and one or more Data Lanes. All Data Lanes shall support High-Speed transmission and Escape Mode in the Forward Direction. All Lanes may support ALP mode.

There are two main types of Data Lanes:

- Bi-directional (featuring Turnaround and some Reverse communication functionality)
- Unidirectional (without Turnaround or any kind of Reverse communication functionality)

Bi-directional Data Lanes shall include one or both of the following Reverse communication options:

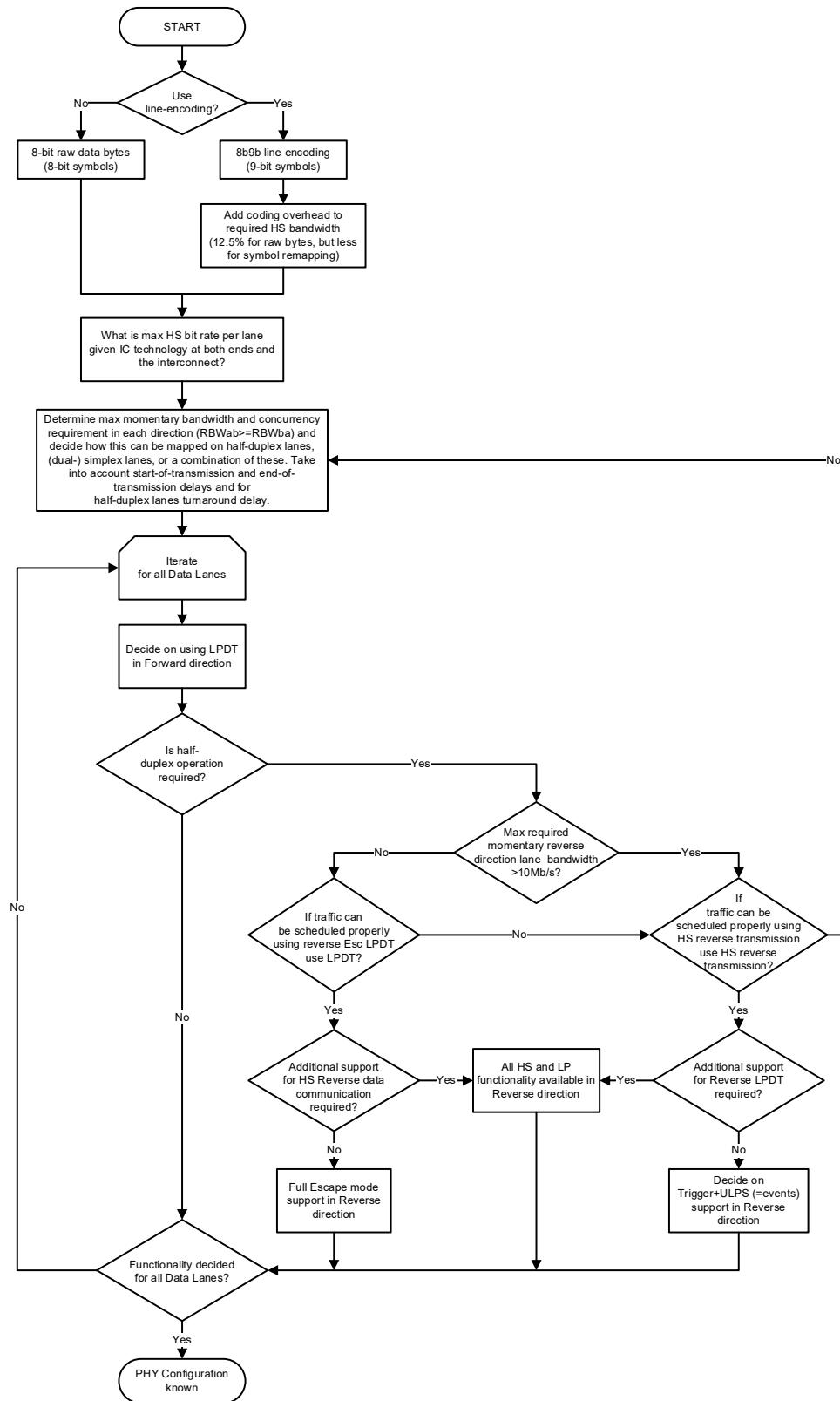
- High-Speed Reverse communication
- Low-Power Reverse Escape Mode (including or excluding LPDT)

All Lanes shall include Escape Mode support, and may include ALP mode support, for ULPs and Triggers in the Forward Direction. Other Escape Mode and ALP mode functionality is optional; all possible Escape Mode and ALP mode features are described in *Section 6*. Applications shall define what additional Escape Mode or ALP mode functionality is required and, for Bi-directional Lanes, shall select Escape Mode and/or ALP mode functionality for each direction individually.

This results in many options for complete PHY Configurations. The degrees of freedom are:

- Single or Multiple Data Lanes
- Bi-directional and/or Unidirectional Data Lane (per Lane)
- Supported types of Reverse communication (per Lane)
- Functionality supported by Escape Mode (for each direction per Lane)
- Functionality supported by ALP mode (for each direction per Lane)
- Data transmission can be with 8-bit raw data (default) or using 8b9b encoded symbol (see *Annex C*)

*Figure 3* is a flow graph of the option selection process. Practical configuration examples can be found in *Section 5.7*.

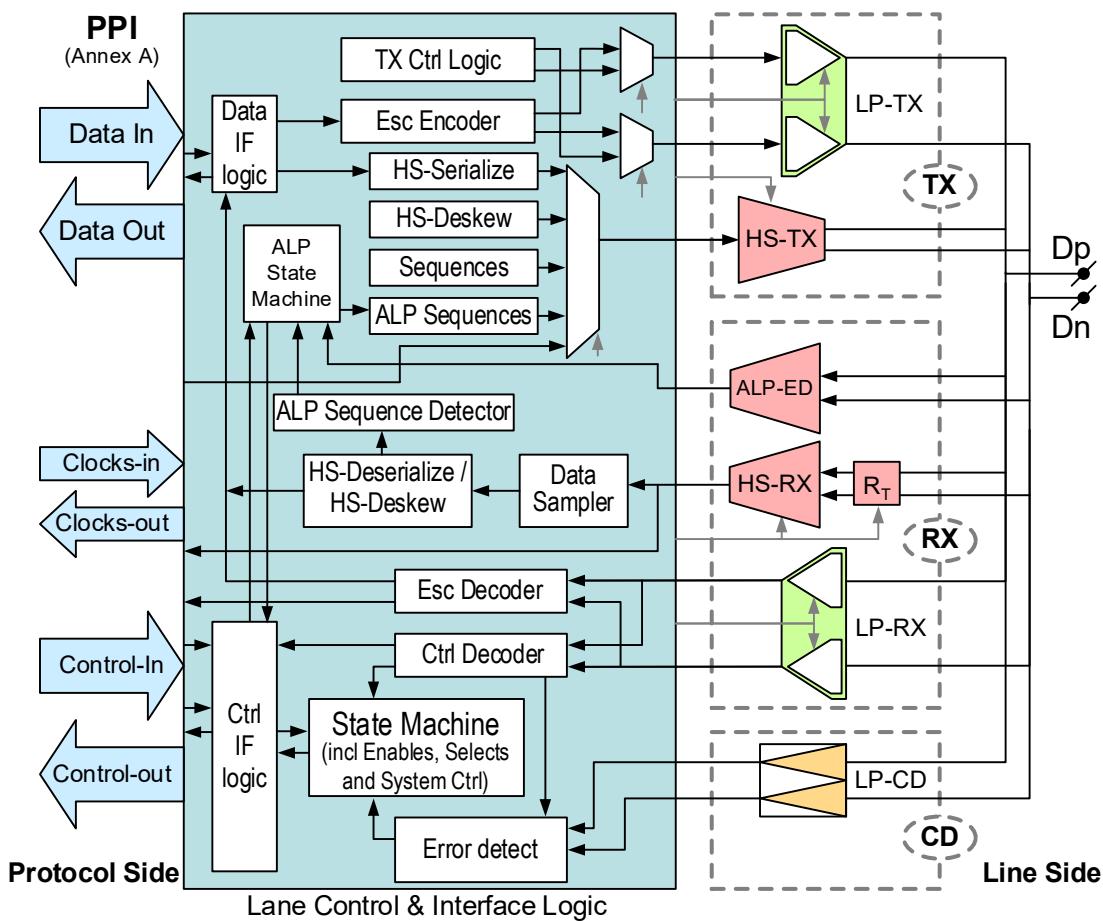


**Figure 3 Option Selection Flow Graph**

## 5.6 Lane Module Types

The required functions in a Lane Module depend on the Lane type and which side of the Lane Interconnect the Lane Module is located. There are three main Lane types: Clock Lane, Unidirectional Data Lane and Bi-directional Data Lane. Several PHY Configurations can be constructed with these Lane types. See **Figure 3** for more information on selecting Lane options.

**Figure 4** shows a Universal Lane Module Diagram with a global overview of internal functionality of the CIL function. This Universal Module can be used for all Lane Types. The requirements for the ‘Control and Interface Logic’ (CIL) function depend on the Lane type and Lane side. **Section 6** and **Annex A** implicitly specify the contents of the CIL function. The actual realization is left to the implementer.



**Figure 4 Universal Lane Module Architecture**

Of course, stripped-down versions of the Universal Lane Module that just support the required functionality for a particular Lane type are possible. These stripped-down versions are identified by the acronyms in **Table 1**. For simplification reasons, any of the four identification characters can be replaced by an X, which means that this can be any of the available options. For example, a CIL-MFEN is therefore a stripped-down CIL function for the Master Side of a Unidirectional Lane with Escape Mode functionality only in the Forward Direction. A CIL-SRXX is a CIL function for the Slave Side of a Lane with support for Bi-directional High-Speed communication and any allowed subset of Escape Mode.

Note that a CIL-XFXN implies a Unidirectional Link, while either a CIL-XRXX or CIL-XXXY block implies a Bi-directional Link. Note that Forward ‘Escape’ (ULPS) entry for Clock Lanes is different than Escape Mode entry for Data Lanes.

358

**Table 1 Lane Type Descriptors**

Prefix	Lane Interconnect Side	High-Speed Capabilities	Forward Direction Escape Mode Features Supported	Reverse Direction Escape Mode Features Supported <sup>1</sup>
CIL-	M – Master S – Slave X – Don't Care	F – Forward Only R – Reverse and Forward X – Don't Care <sup>2</sup>	A – All (including LPDT) E – Events – Triggers and ULPS Only X – Don't Care	A – All (including LPDT) E – Events – Triggers and ULPS Only N – None Y – Any (A, E, or A and E) X – Don't Care
	C – Clock	N – Not Applicable	N – Not Applicable	

**Note:**

1. "Any" is any combination of one or more functions.
2. Only valid for Data Lanes, means "F" or "R".

359 The recommend PHY Protocol Interface contains Data-in and Data-out in byte format, Input and/or output  
 360 Clock signals and Control signals. Control signals include requests, handshakes, test settings, and  
 361 initialization. A proposal for a logical internal interface is described in Annex A. Although not a  
 362 requirement it may be very useful to use the proposed PPI. For external use on IC's an implementation may  
 363 multiplex many signals on the same pins. However, for power efficiency reasons, the PPI is normally  
 364 within an IC.

### 5.6.1 Unidirectional Data Lane

For a Unidirectional Data Lane the Master Module shall contain at least a HS-TX, a LP-TX, and a CIL-MFXN function. The Slave side shall contain at least a HS-RX, a LP-RX and a CIL-SFXN. It may contain an ALP-ED.

### 5.6.2 Bi-directional Data Lanes

A Bi-directional Data Lane Module includes some form of Reverse communication; either High-Speed Reverse Communication, Reverse Escape Mode, or both. The functions required depend on what methods of Reverse communication are included in the Lane Module.

#### 5.6.2.1 Bi-directional Data Lane without High-Speed Reverse Communication

A Bi-directional Data Lane Module without High-Speed Reverse Communication shall include a Reverse Escape Mode. The Master-side Lane Module includes a HS-TX, LP-TX, LP-RX, LP-CD, and CIL-MFXY. The Slave-side consists of a HS-RX, LP-RX, LP-TX, LP-CD and a CIL-SFXY. It may contain an ALP-ED.

#### 5.6.2.2 Bi-directional Data Lane with High-Speed Reverse Communication

A Bi-directional Data Lane Module with High-Speed Reverse Communication shall include a Reverse Escape Mode. The Master-side Lane Module includes a HS-TX, HS-RX, LP-TX, LP-RX, LP-CD, and CIL-MRXX. The Slave-side consists of a HS-RX, HS-TX, LP-RX, LP-TX, LP-CD and a CIL-SRXX. It may contain an ALP-ED.

This type of Lane Module may seem suitable for both Master and Slave side but because of the asymmetry of the Link one side shall be configured as Master and the other side as Slave.

### 5.6.3 Clock Lane

For the Clock Lane, only a limited set of Line states is used. However, for Clock Transmission and Low-Power mode the same TX and RX functions are required as for Unidirectional Data Lanes. A Clock Lane Module for the Master Side therefore contains a HS-TX, LP-TX, and a CIL-MCNN function, while the Slave Side Module includes a HS-RX, a LP-RX and a CIL-SCNN function. It may contain an ALP-ED.

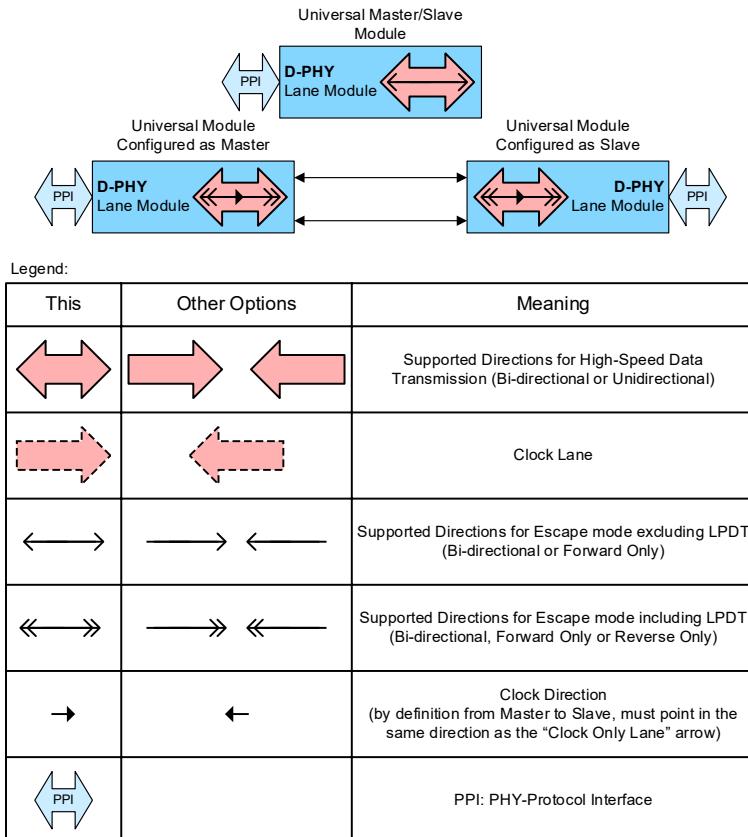
Note that the required functionality for a Clock Lane is similar, but not identical, to a Unidirectional Data Lane. The High-Speed DDR Clock is transmitted in quadrature phase with Data signals instead of in-phase. In addition, the Clock Lane Escape Mode entry is different than that used for Data Lanes. Furthermore, since a Clock Lane only supports ULPS, an Escape Mode entry code is not required.

The internal clock signals with the appropriate phases are generated outside the PHY and delivered to the individual Lanes. The realization of the Clock generation unit is outside the scope of this specification. The quality of the internal clock signals shall be sufficient to meet the timing requirement for the signals as specified in *Section 10*.

## 5.7 Configurations

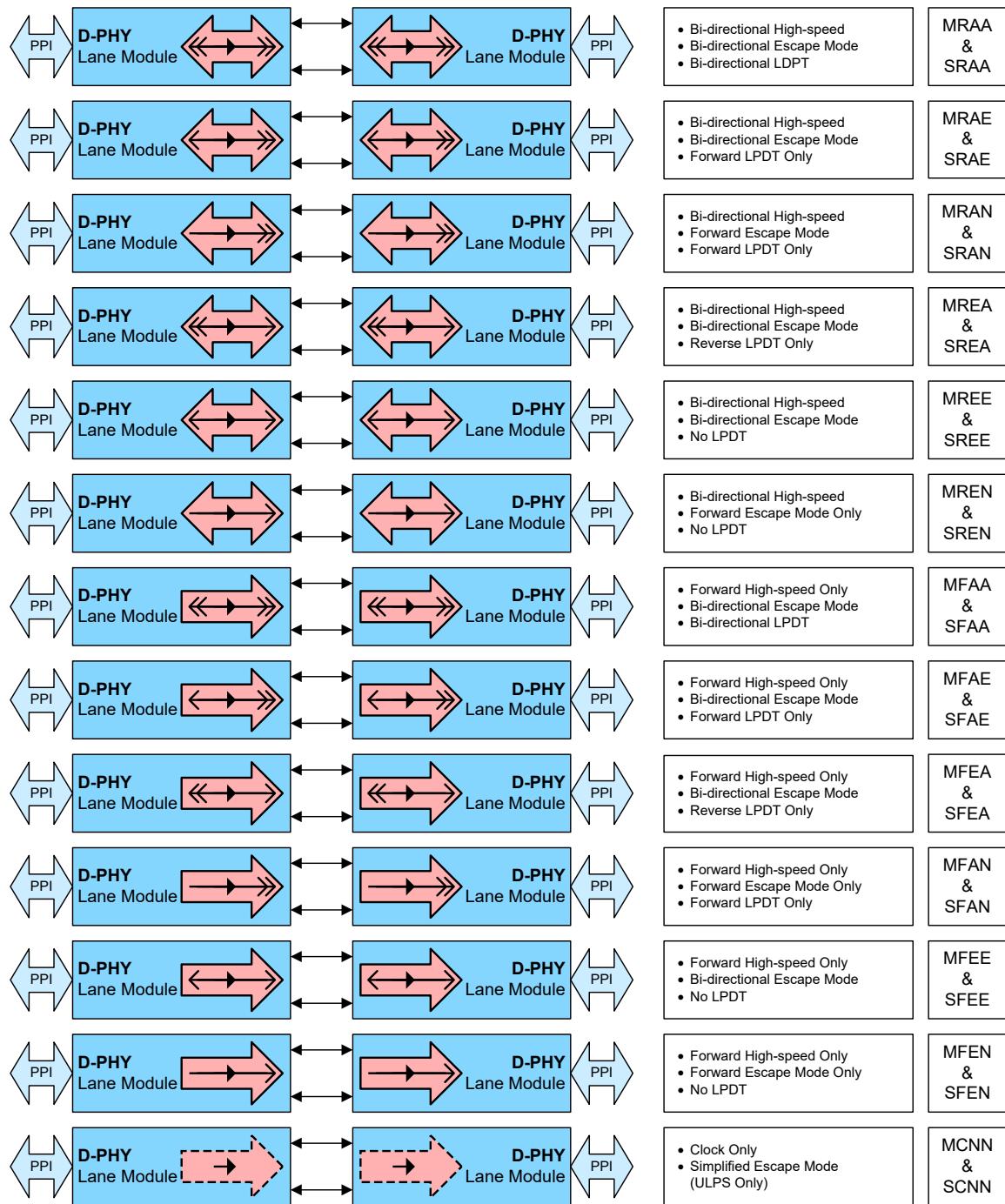
This Section outlines several common PHY Configurations but should not be considered an exhaustive list of all possible arrangements. Any other configuration that does not violate the requirements of this document is also allowed.

In order to create an abstraction level, the Lane Modules are represented in this Section by Lane Module Symbols. *Figure 5* shows the syntax and meaning of symbols.



**Figure 5 Lane Symbol Macros and Symbols Legend**

398  
399  
400  
401 For multiple Data Lanes a large variety of configurations is possible. **Figure 6** shows an overview of symbolic representations for different Lane types. The acronyms mentioned for each Lane type represent the functionality of each module in a short way. This also sets the requirements for the CIL function inside each Module.



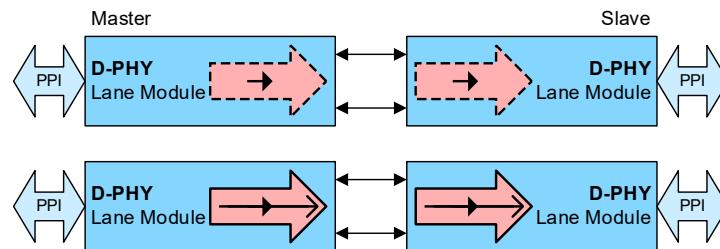
402  
**Figure 6 Possible Data Lane Types and a Basic Unidirectional Clock Lane**

### 5.7.1 Unidirectional Configurations

All Unidirectional configurations are constructed with a Clock Lane and one or more Unidirectional Data Lanes. Two basic configurations can be distinguished: Single Data Lane and Multiple Data Lanes. For completeness a Dual-Simplex configuration is also shown. At the PHY level there is no difference between a Dual-Simplex configuration and two independent Unidirectional configurations.

#### 5.7.1.1 PHY Configuration with a Single Data Lane

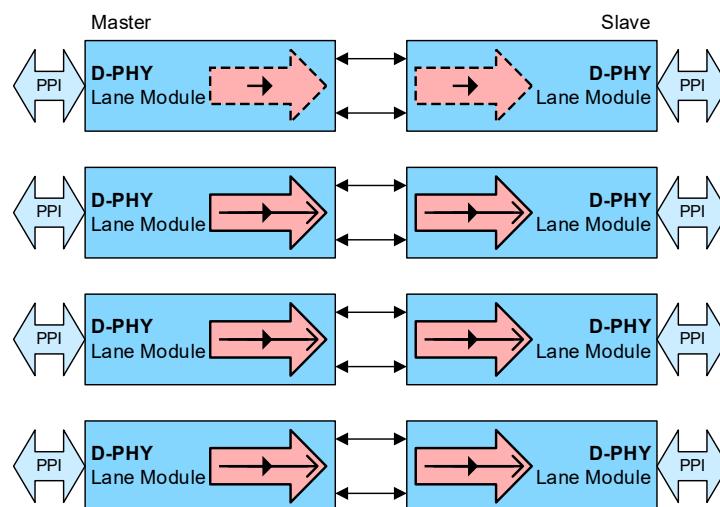
This configuration includes one Clock Lane and one Unidirectional Data Lane from Master to Slave. Communication is therefore only possible in the Forward Direction. *Figure 7* shows an example configuration without LPDT. This configuration requires four interconnect signal wires.



**Figure 7 Unidirectional Single Data Lane Configuration**

#### 5.7.1.2 PHY Configuration with Multiple Data Lanes

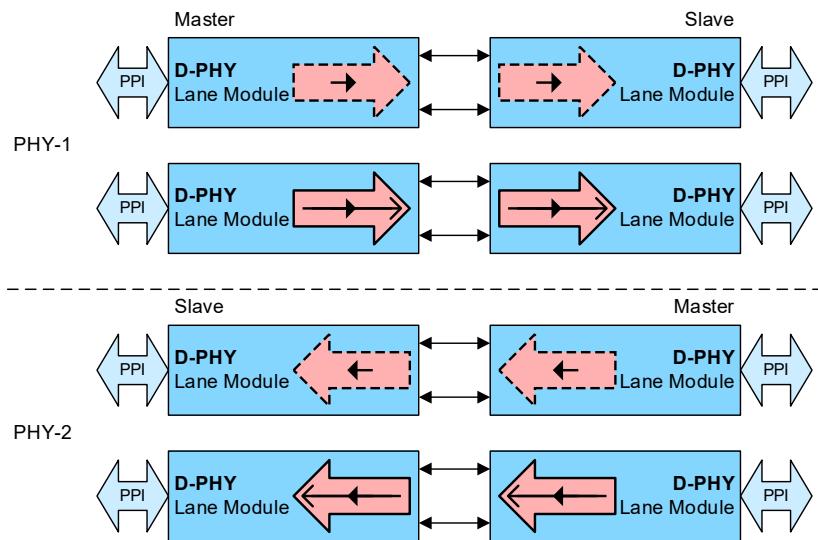
This configuration includes one Clock Lane and multiple Unidirectional Data Lanes from Master to Slave. Bandwidth is extended, but communication is only possible in the Forward Direction. The PHY specification does not require all Data Lanes to be active simultaneously. In fact, the Protocol layer controls all Data Lanes individually. *Figure 8* shows an example of this configuration for three Data Lanes. If N is the number of Data Lanes, this configuration requires  $2*(N+1)$  interconnect wires.



**Figure 8 Unidirectional Multiple Data Lane Configuration without LPDT**

### 5.7.1.3 Dual-Simplex (Two Directions with Unidirectional Lanes)

This case is the same as two independent (dual), Unidirectional (simplex) Links: one for each direction. Each direction has its own Clock Lane and may contain either a single, or multiple, Data Lanes. Please note that the Master and Slave side for the two different directions are opposite. The PHY Configuration for each direction shall comply with the D-PHY specifications. As both directions are conceptually independent, the bit rates for each direction do not have to match. However, for practical implementations, it is attractive to match rates and share some internal signals as long as both Links fulfill all specifications externally. **Figure 9** shows an example of this dual PHY Configuration.



424

**Figure 9 Two Directions Using Two Independent Unidirectional PHYs without LPDT**

### 5.7.2 Bi-Directional Half-Duplex Configurations

Bi-directional configurations consist of a Clock Lane and one or more Bi-directional Data Lanes. Half-duplex operation enables Bi-directional traffic across shared interconnect wires. This configuration saves wires compared to the Dual-Simplex configuration. However, time on the Link is shared between Forward and Reverse traffic and Link Turnaround. The High-Speed bit rate in the Reverse direction is, by definition, one-fourth of the bit rate in the Forward Direction. LPDT can have similar rates in the Forward and Reverse directions. This configuration is especially useful for cases with asymmetrical data traffic.

#### 5.7.2.1 PHY Configurations with a Single Data Lane

This configuration includes one Clock Lane and one of any kind of Bi-directional Data Lane. This allows time-multiplexed data traffic in both Forward and Reverse directions. **Figure 10** shows this configuration with a Data Lane that supports both High-Speed and Escape (without LPDT) communication in both directions. Other possibilities are that only one type of Reverse communication is supported or LPDT is also included in one or both directions. All these configurations require four interconnect wires.

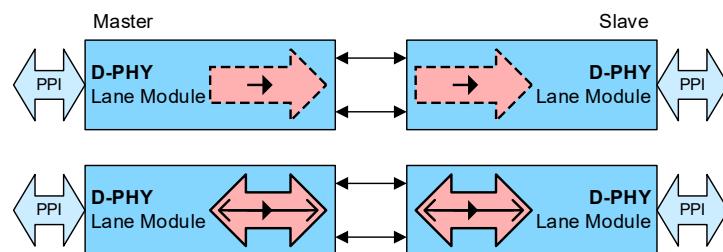


Figure 10 Bidirectional Single Data Lane Configuration

#### 5.7.2.2 PHY Configurations with Multiple Data Lanes

This configuration includes one Clock Lane and multiple Bi-directional Data Lanes. Communication is possible in both the Forward and Reverse direction for each individual Lane. The maximum available bandwidth scales with the number of Lanes for each direction. The PHY specification does not require all Data Lanes to be active simultaneously or even to be operating in the same direction. In fact, the Protocol layer controls all Data Lanes individually. **Figure 11** shows an example configuration with two Data Lanes. If N is the number of Data Lanes, this configuration requires  $2*(N+1)$  interconnect wires.

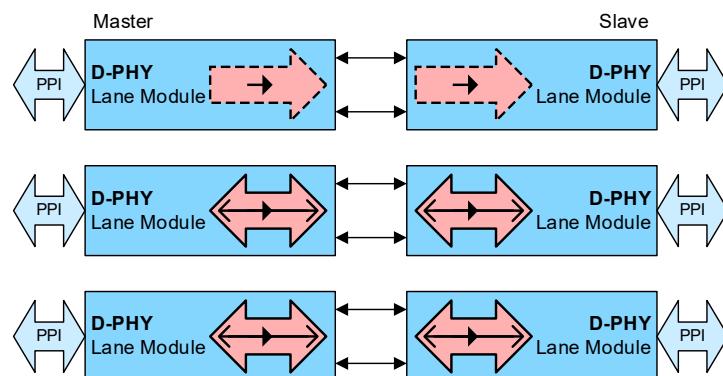
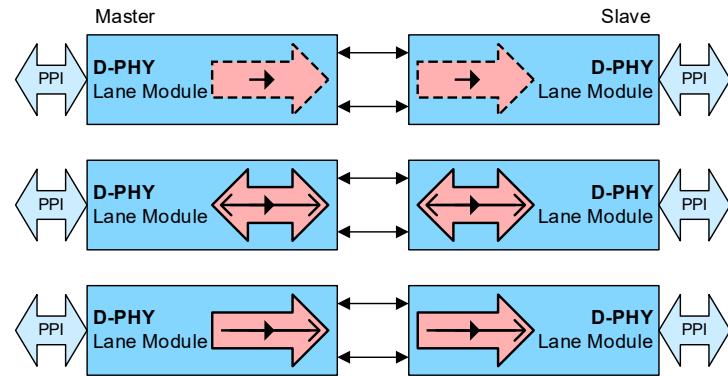


Figure 11 Bi-directional Multiple Data Lane Configuration

### 5.7.3 Mixed Data Lane Configurations

Instead of using only one Data Lane type, PHY Configurations may combine different Unidirectional and Bi-directional Data Lane types. *Figure 12* shows an example configuration with one Bi-directional and one Unidirectional Data Lane, both without LPDT.



**Figure 12 Mixed Type Multiple Data Lane Configuration**

## 6 Global Operation

This Section specifies operation of the D-PHY including signaling types, communication mechanisms, operating modes and coding schemes. Detailed specifications of the required electrical functions can be found in *Section 9*.

### 6.1 Transmission Data Structure

During High-Speed, or Low-Power, transmission, the Link transports payload data provided by the protocol layer to the other side of the Link. This Section specifies the restrictions for the transmitted and received payload data.

#### 6.1.1 Data Units

The minimum payload data unit shall be one byte. Data provided to a TX and taken from a RX on any Lane shall be an integer number of bytes. This restriction holds for both High-Speed and Low-Power data transmission in any direction.

#### 6.1.2 Bit Order, Serialization, and De-Serialization

For serial transmission, the data and control patterns shall be serialized in the transmitting PHY and de-serialized in the receiving PHY with the same LSB-MSB order. Binary sequences within this specification shall be serialized in time so that the LSB is transmitted first and the MSB is transmitted last, with the LSB being the leftmost bit of a binary sequence and the MSB being the rightmost bit unless clearly defined differently in the text.

#### 6.1.3 Encoding and Decoding

Line coding is not required by this specification. However, if Line coding is used, it shall be implemented according to Annex C.

#### 6.1.4 Data Buffering

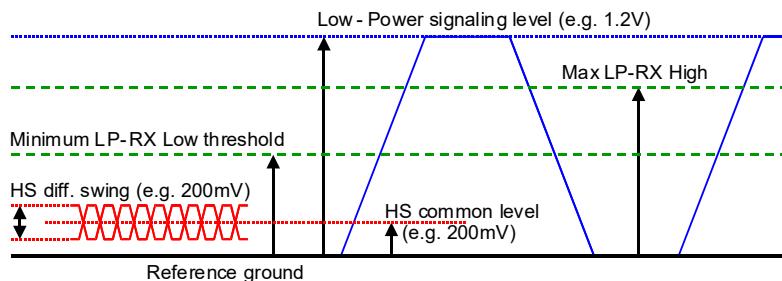
Data transmission takes place on protocol request. As soon as communication starts, the protocol layer at the transmit side shall provide valid data as long as it does not stop its transmission request. For Lanes that use Line coding, control symbols can also be inserted into the transmission. The protocol on the receive side shall take the data as soon as delivered by the receiving PHY. The signaling concept, and therefore the PHY protocol handshake, does not allow data throttling. Any data buffering for this purpose shall be inside the protocol layer.

## 6.2 Lane States and Line Levels

Transmitter functions determine the Lane state by driving certain Line levels. The Link can operate in one of two possible transmission schemes, which are defined by the Line levels used. The primary transmission scheme uses a combination of HS differential signaling and LP mode single-ended signaling. An optional, secondary transmission scheme uses a combination of HS differential signaling and Alternate Low-Power (ALP) mode which includes an additional special Lane state in which both lines are pulled to ground simultaneously.

### 6.2.1 HS and LP Mode Lane States and Line Levels

During normal operation either a HS-TX or a LP-TX is driving a Lane. A HS-TX always drives the Lane differentially. The two LP-TX's drive the two Lines of a Lane independently and single-ended. This results in two possible High-Speed Lane states and four possible Low-Power Lane states. The High-Speed Lane states are Differential-0 and Differential-1. The interpretation of Low-Power Lane states depends on the mode of operation. The LP-Receiver shall always interpret both High-Speed differential states as LP-00.



**Figure 13 Line Levels in HS and LP Modes**

The Stop state has a very exclusive and central function. If the Line levels show a Stop state for the minimum required time, the PHY state machine shall return to the Stop state regardless of the previous state. This can be in RX or TX mode depending on the most recent operating direction. **Table 2** lists all the states that can appear on a Lane during normal operation. Detailed specifications of electrical levels can be found in **Section 9**.

All LP state periods shall be at least  $T_{LPX}$  in duration. State transitions shall be smooth and exclude glitch effects. A clock signal can be reconstructed by exclusive-ORing the Dp and Dn Lines. Ideally, the reconstructed clock has a duration of at least  $2*T_{LPX}$ , but may have a duty cycle other than 50% due to signal slope and trip levels effects.

**Table 2 Lane State Descriptions**

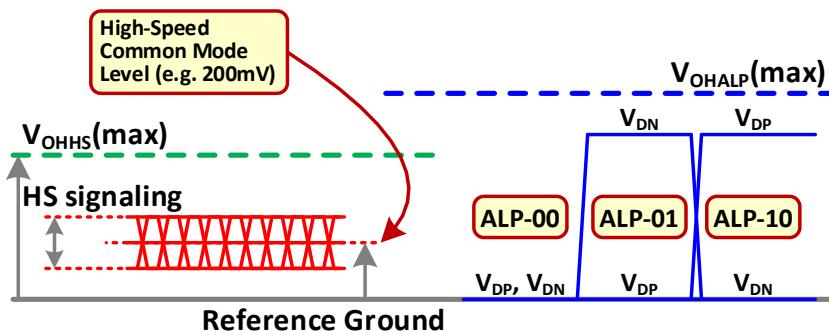
State Code	Line Voltage Levels		High-Speed	Low-Power	
	Dp-Line	Dn-Line		Burst Mode	Control Mode
HS-0	HS Low	HS High	Differential-0	N/A, Note 1	N/A, Note 1
HS-1	HS High	HS Low	Differential-1	N/A, Note 1	N/A, Note 1
LP-00	LP Low	LP Low	N/A	Bridge	Space
LP-01	LP Low	LP High	N/A	HS-Rqst	Mark-0
LP-10	LP High	LP Low	N/A	LP-Rqst	Mark-1
LP-11	LP High	LP High	N/A	Stop	N/A, Note 2

**Note:**

1. During High-Speed transmission the Low-Power Receivers observe LP-00 on the Lines.
2. If LP-11 occurs during Escape Mode the Lane returns to Stop state (Control mode LP-11).

## 6.2.2 HS and ALP Mode Lane States and Line Levels

ALP mode replaces the LP mode Line levels with low-voltage levels as used for HS mode. A standby state in ALP mode is also defined, where both lines in a Lane are grounded. This Lane state is called ALP-00, which can be further differentiated logically as either ALP Stop or ALP ULPS. ALP Stop and ALP ULPS are defined by the following relationships of the Line levels:  $V_{DP} = V_{DN} \sim 0$  V, and  $V_{OD} \sim 0$  V. The Line levels of high-speed signaling and ALP states is illustrated in **Figure 14**. The ALP-01 and ALP-10 line levels are identical to the line levels of an unterminated HS-0 and HS-1, respectively.



**Figure 14 Line Levels in HS and ALP Modes**

**Table 3** lists the different Line states and how they are used in HS and ALP modes.

**Table 3 ALP Mode Lane State Descriptions**

State Code	Line Voltage Levels		High-Speed Burst Mode	Alternate Low-Power
	Dp-Line	Dn-Line		
HS-0	HS Low	HS High	Differential-0	N/A, Note 1
HS-1	HS High	HS Low	Differential-1	N/A, Note 2
ALP-00	ALP Low	ALP Low	N/A	Stop or ULPS State
ALP-01	ALP Low	ALP High	N/A	Wake
ALP-10	ALP High	ALP Low	N/A	End of Burst

**Note:**

1. The HS-0 state produces the same ALP-ED response as an ALP-01 state.
2. The HS-1 state produces the same ALP-ED response as an ALP-00 state.

## 6.3 Operating Modes: Control, High-Speed, and Escape

### 6.3.1 LP and HS Operating Modes

501 During normal operation in HS and LP modes, a Data Lane will be either in Control or High-Speed mode.  
502 High-Speed Data transmission happens in bursts and starts from and ends at a Stop state (LP-11), which is  
503 by definition in Control mode. The Lane is only in High-Speed mode during Data bursts. The sequence to  
504 enter High-Speed mode is: LP-11, LP-01, LP-00 at which point the Data Lane remains in High-Speed mode  
505 until a LP-11 is received. The Escape Mode can only be entered via a request within Control mode. The  
506 Data Lane shall always exit Escape Mode and return to Control mode after detection of a Stop state. If not  
507 in High-Speed or Escape Mode the Data Lane shall stay in Control mode. For Data Lanes and for Clock  
508 Lanes the Stop state serves as a general standby state and may last for any period of time  $> T_{HS-EXIT}$  or  $>$   
509  $T_{LP-EXIT}$ . Examples of the duration of the Stop state are shown in **Figure 15**. Possible events starting from  
510 the Stop state are High-Speed Data Transmission request (LP-11, LP-01, LP-00), Escape Mode request  
511 (LP-11, LP-10, LP-00, LP-01, LP-00) or Turnaround request (LP-11, LP-10, LP-00, LP-10, LP-00).

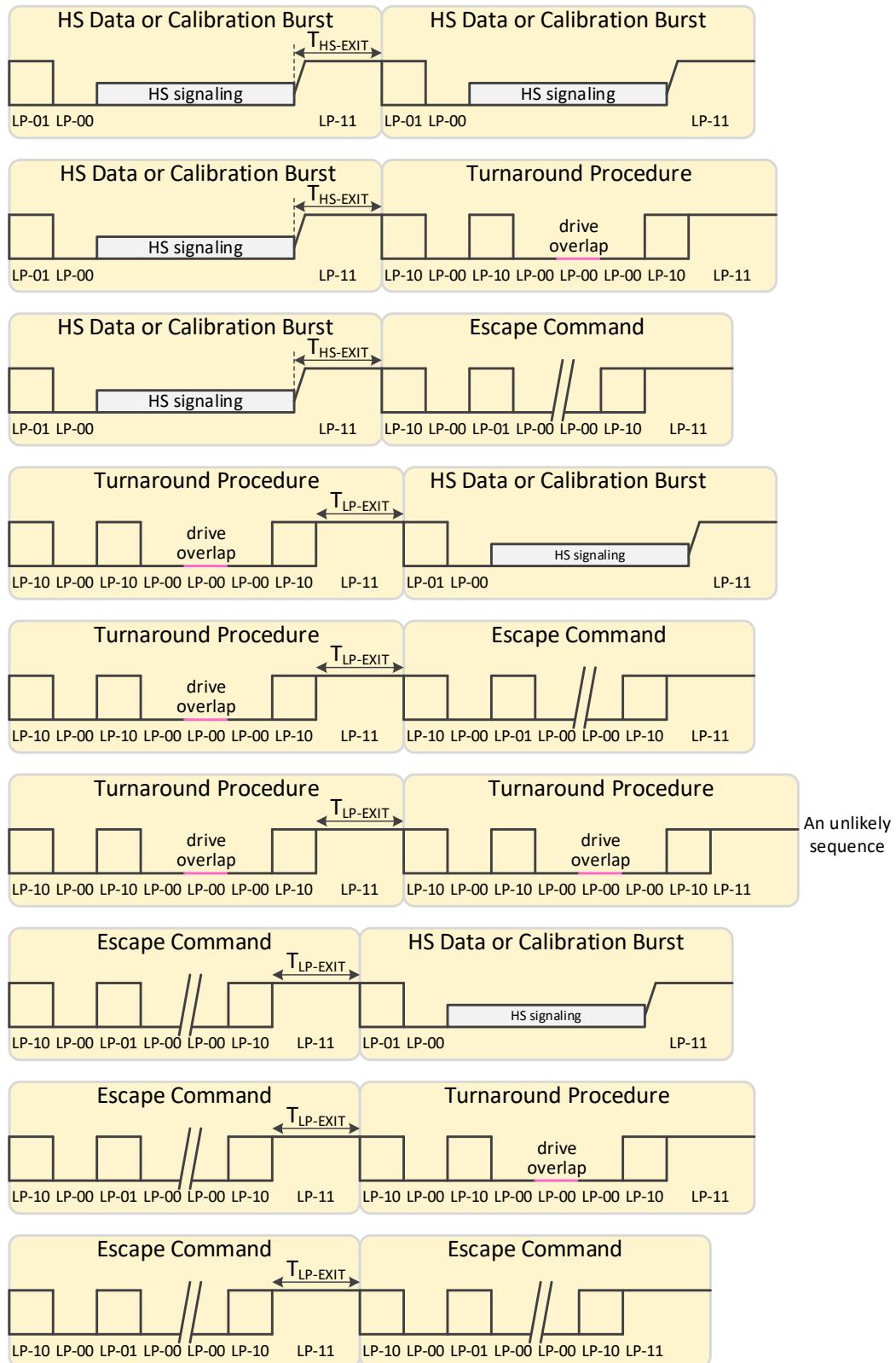


Figure 15 Examples of the Stop State Duration Between LP Sequences and HS Bursts

### 6.3.2 ALP and HS Operating Modes

During operation in HS and ALP modes, a Data Lane will be in the ALP Stop state (ALP-00), the ALP ULPS state (ALP-00), the ALP Wake state (ALP-01), or High-Speed mode. The only difference between the ALP Stop state and the ALP ULPS state at the PHY level is that the receiver is given a longer time to wake up from the ALP ULPS state by virtue of a longer TALP-WAKEUP pulse generated by the transmitter. High-Speed transmission starts from ALP Stop and ends in an ALP Stop or ALP ULPS state. The Lane is only in HS mode during data bursts and during ALP control bursts. The sequence to enter HS mode for an ALP Control Burst is: ALP-01 and HS-0 followed by a frequency dependent Preamble and Extended-Sync, and finally an 8-bit Control-Sync. This is illustrated in *Figure 18*. Control-Code words sent after the Control-Sync define the purpose of the Control Burst. The transmission of specially formatted control bursts using HS functions suit the same functions as the transmission of LP Control and Escape Modes. While operating in the ALP mode - HS mode cycle, the Lane shall exit the HS mode by returning to ALP Stop, or ALP ULPS in case of a previously sent ULPS Control Burst, after a long HS-Trail period (described later). If not in HS mode, the Lane shall stay in ALP Stop or ALP ULPS states, which serve as standby states and may last for any period of time longer than T<sub>ALPX</sub>. An ALP Wake pulse shall be detected by the ALP Exit Detector (ALP-ED) to transition out of an ALP ULPS state or an ALP Stop state. The Lane transitions via ALP Wake to ALP Stop upon an ALP ULPS state exit. Any HS data or control bursts may follow an ALP Stop state.

The Clock Lane also operates in HS and ALP modes. It transitions between ALP Stop or ALP ULPS states and HS mode, in which the clock signal is transmitted. ALP Stop and ALP ULPS states are exited by an ALP Wake pulse of adequate duration as for a Data Lane. The Clock Lane transitions to the ALP Stop state when the clock signal is stopped after which a transition to ALP ULPS state is possible using a HS-Zero/HS-Trail control sequence as shown in *Figure 31*.

Note that any ALP Wake pulse transmitted on a Data Lane while it is in the ALP Stop state with the Clock Lane inactive (i.e., in either the ALP ULPS or ALP Stop state) shall not signal the start of a high-speed burst transmission; instead, the receiver shall simply pass it to the protocol for further interpretation.

There is no equivalence for HS-Idle (*Section 6.15*) in ALP mode.

## 6.4 High-Speed Data Transmission

High-Speed Data Transmission occurs in bursts. To aid receiver synchronization, data bursts shall be extended on the transmitter side with a leader and trailer sequence and shall be eliminated on the receiver side. These leader and trailer sequences can therefore only be observed on the transmission lines.

Transmission starts from, and ends with, a Stop state. During the intermediate time between bursts a Data Lane shall remain in the Stop state, unless a Turnaround or Escape request is presented on the Lane. During a HS Data Burst the Clock Lane shall be in High-Speed mode, providing a Clock to the Slave side.

### 6.4.1 Burst Payload Data

The payload data of a burst shall always represent an integer number of payload data bytes with a minimum length of one byte. Note that for short bursts the Start and End overhead consumes much more time than the actual transfer of the payload data. There is no maximum number of bytes implied by the PHY. However, in the PHY there is no autonomous way of error recovery during a HS data burst and the practical BER will not be zero. Therefore, it is important to consider for every individual protocol what the best choice is for maximum burst length.

### 6.4.2 Start-of-Transmission

After a Transmit request, a Data Lane leaves the Stop state and prepares for High-Speed mode by means of a Start-of-Transmission (SoT) procedure. *Table 4* describes the sequence of events on TX and RX side.

Table 4 Start-of-Transmission Sequence

TX Side	RX Side
Drives Stop state (LP-11)	Observes Stop state
Drives HS-Rqst state (LP-01) for time $T_{LPX}$	Observes transition from LP-11 to LP-01 on the Lines
Drives Bridge state (LP-00) for time $T_{HS-PREPARE}$	Observes transition from LP-01 to LP-00 on the Lines, enables Line Termination after time $T_{D-TERM-EN}$
Enables High-Speed driver and disables Low-Power drivers simultaneously.	–
Drives HS-0 for a time $T_{HS-ZERO}$	Enables HS-RX and waits for timer $T_{HS-SETTLE}$ to expire in order to neglect transition effects
–	Starts looking for Leader-Sequence
Inserts the HS Sync-Sequence '00011101' beginning on a rising Clock edge	–
–	Synchronizes upon recognition of Leader Sequence '011101'
Continues to Transmit High-Speed payload data	–
–	Receives payload data

#### 6.4.3 End-of-Transmission

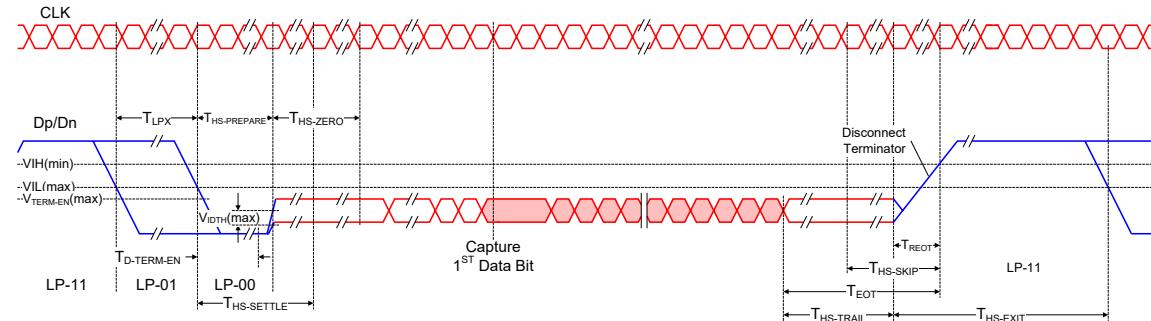
At the end of a Data Burst, a Data Lane leaves High-Speed Transmission mode and enters the Stop state by means of an End-of-Transmission (EoT) procedure. *Table 5* shows a possible sequence of events during the EoT procedure. Note, EoT processing may be handled by the protocol or by the D-PHY.

**Table 5 End-of-Transmission Sequence**

TX Side	RX Side
Completes Transmission of payload data	Receives payload data
Toggles differential state immediately after last payload data bit and keeps that state for a time $T_{HS-TRAIL}$	–
Disables the HS-TX, enables the LP-TX, and drives Stop state (LP-11) for a time $T_{HS-EXIT}$	Detects the Lines leaving LP-00 state and entering Stop state (LP-11) and disables Termination
–	Neglect bits of last period $T_{HS-SKIP}$ to hide transition effects
–	Detect last transition in valid Data, determine last valid Data byte and skip trailer sequence

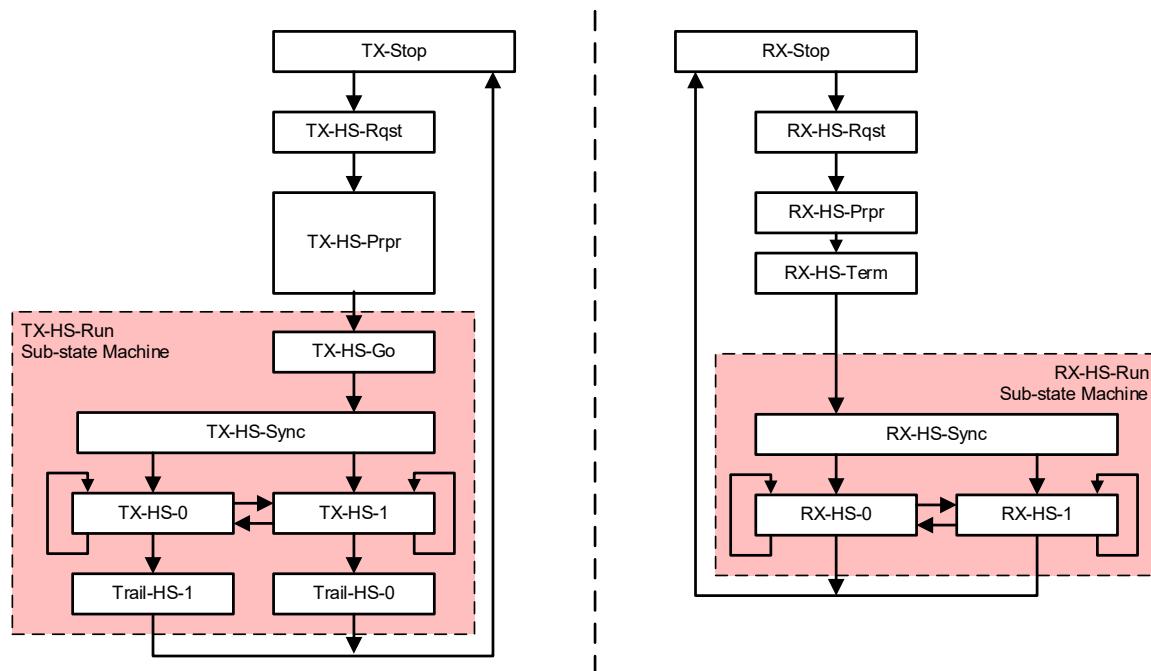
#### 6.4.4 HS Data Transmission Burst

**Figure 16** shows the sequence of events during the transmission of a Data Burst. Transmission can be started and ended independently for any Lane by the protocol. However, for most applications the Lanes will start synchronously but may end at different times due to an unequal amount of transmitted bytes per Lane. The handshake with the protocol-layer is described in *Annex A*.



**Figure 16 High-Speed Data Transmission in Bursts**

**Figure 17** shows the state machine for High-Speed data transmission that is described in *Table 6*.



**Figure 17 TX and RX State Machines for High-Speed Data Transmission**

565

**Table 6 High-Speed Data Transmission State Machine Description**

<b>State</b>	<b>Line Condition/State</b>	<b>Exit State</b>	<b>Exit Conditions</b>
TX-Stop	Transmit LP-11	TX-HS-Rqst	On request of Protocol for High-Speed Transmission
TX-HS-Rqst	Transmit LP-01	TX-HS-Prpr	End of timed interval $T_{LPX}$
TX-HS-Prpr	Transmit LP-00	TX-HS-Go	End of timed interval $T_{HS-PREPARE}$
TX-HS-Go	Transmit HS-0	TX-HS-Sync	End of timed interval $T_{HS-ZERO}$
TX-HS-Sync	Transmit sequence HS-00011101	TX-HS-0	After Sync sequence if first payload data bit is 0
—	—	TX-HS-1	After Sync sequence if first payload data bit is 1
TX-HS-0	Transmit HS-0	TX-HS-0	Send another HS-0 bit after a HS-0 bit
—	—	TX-HS-1	Send a HS-1 bit after a HS-0 bit
—	—	Trail-HS-1	Last payload bit is HS-0, trailer sequence is HS-1
TX-HS-1	Transmit HS-1	TX-HS-0	Send a HS-1 bit after a HS-0 bit
—	—	TX-HS-1	Send another HS-1 bit after a HS-1
—	—	Trail-HS-0	Last payload bit is HS-1, trailer sequence is HS-0
Trail-HS-0	Transmit HS-0	TX-Stop	End of timed interval $T_{HS-TRAIL}$
Trail-HS-1	Transmit HS-1	TX-Stop	End of timed interval $T_{HS-TRAIL}$
RX-Stop	Receive LP-11	RX-HS-Rqst	Line transition to LP-01
RX-HS-Rqst	Receive LP-01	RX-HS-Prpr	Line transition to LP-00
RX-HS-Prpr	Receive LP-00	RX-HS-Term	End of timed interval $T_{D-TERM-EN}$
RX-HS-Term	Receive LP-00	RX-HS-Sync	End of timed interval $T_{HS-SETTLE}$
RX-HS-Sync	Receive HS sequence ...00000011101	RX-HS-0	Proper match found for Sync sequence in HS stream, the following bits are payload data. (When deskew is supported, bit errors in the Leader sequence are not tolerated.)
—	—	RX-HS-1	—
RX-HS-0	Receive HS-0	RX-HS-0	Receive payload data bit or trailer bit
—	—	RX-HS-1	—
—	—	RX-Stop	Line transition to LP-11
RX-HS-1	Receive HS-1	RX-HS-0	Receive payload data bit or trailer bit
—	—	RX-HS-1	—
—	—	RX-Stop	Line transition to LP-11

**Note:**

Stop states (TX-Stop, RX-Stop) have multiple valid exit states.

#### 6.4.5 Alternate Low Power (ALP) Mode and HS Transmission Burst

566 *Figure 18* shows the general burst format of ALP mode. Both Clock and Data Lanes start in the ALP Stop  
567 state. If in ALP ULPS state, a Lane shall make an initial transition to ALP Stop state before any other  
568 communication can be attempted. The ALP Stop and ALP ULPS states are very similar to the Stop and  
569 ULPS states in LP mode, respectively. The transmitter drives the ALP Wake pulse for an extended period of  
570 time to wake up the receiver. This state is similar to HS-Zero state at the start of an HS burst, and shall last  
571 for a period of  $T_{ALP-HS-ZERO}$ . The ALP-ED detects the ALP Wake pulse and the differential termination is  
572 enabled. After waking up, and depending on the data rate, the transmitter sends the 1010... Preamble,  
573 Extended-Sync followed by an HS-Sync for a data burst or a Control-Sync and Control-Code for a Control  
574 Burst. At the end of any burst the transmitter sends a long HS-Trail sequence before transitioning to the  
575 default ALP Stop state, or ALP ULPS state in case of an ULPS Entry Control Burst. During the HS-Trail  
576 period of a Control Burst, the receiver recognizes the end-of-burst (EOB) and disables the differential  
577 termination.

578 The ALP Exit Detector is a differential receiver with an offset input threshold voltage used to detect the  
579 difference in differential levels between the ALP-00 state and any ALP Wake state. By having a longer time  
580 to wake up, the receiver can afford to have a lower power consumption in the ALP ULPS state compared to  
581 the ALP Stop state. The circuit designer may choose to optimize the implementation of the ALP Exit  
582 Detector by using a low power differential receiver architecture with a configurable bias to trade off power  
583 versus detection time.

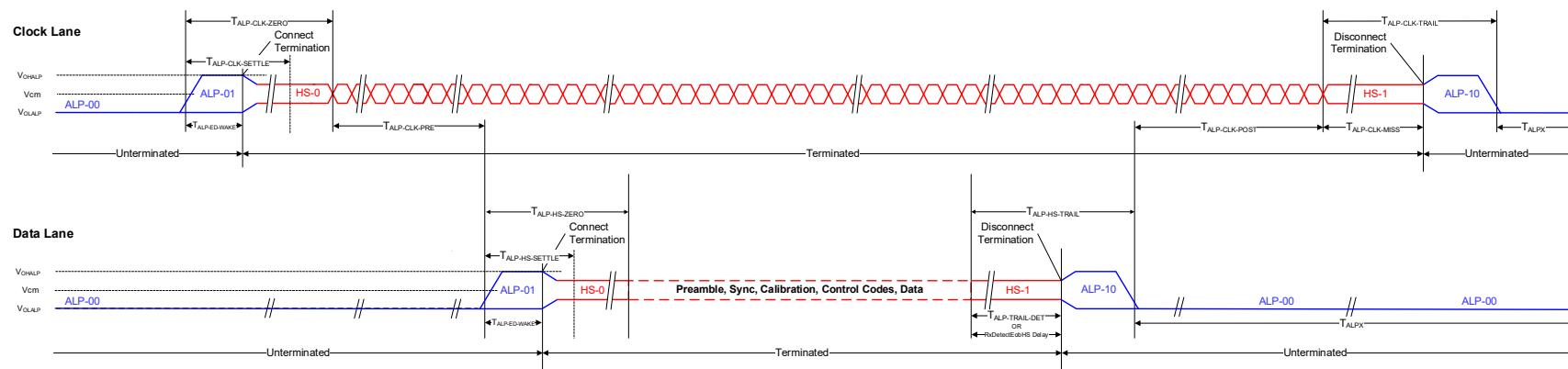
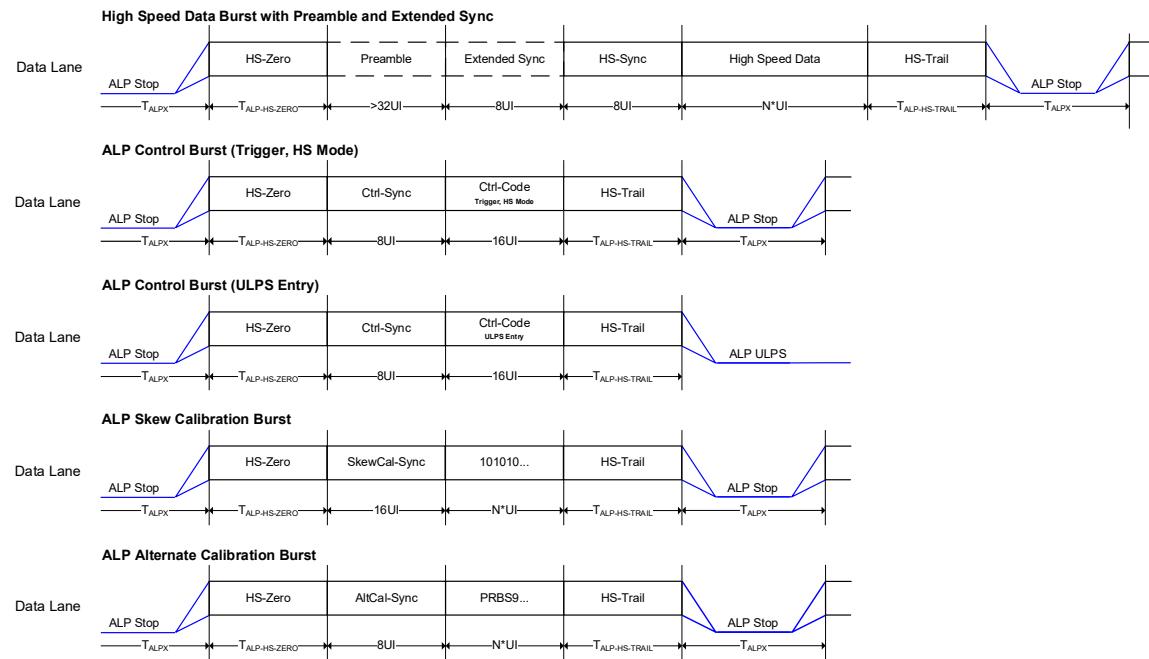


Figure 18 ALP Mode General Burst Format

585     Figure 19 shows examples of the structures of HS Data and ALP Control Bursts. The Clock Lane is  
 586     enabled and a forwarded clock present when these transactions happen on a Data Lane.



**Figure 19 Examples of High Speed Data and ALP Control Bursts**

587     The receiver shall support two distinct mechanisms to detect the end-of-burst (EoB):  
 588       • HS-Trail detection for Control and Calibration Bursts  
 589       • Controller assisted EoB detection for HS Data Bursts  
 590  
 591     For the HS-Trail based detection mechanism, a receiver shall detect an HS-1 sequence exceeding the ALP  
 592     Trail Exit duration  $T_{ALP-TRAIL-DET}$  as an HS-Trail as the end of the current burst. This event triggers the  
 593     disabling of the HS termination and HS-RX, and it enables the ALP-ED in preparation for the detection of  
 594     the next Start-of-Burst.

595     This HS-Trail-based detection mechanism shall be used in the following scenarios:  
 596       • Any ALP Control Burst including, but not limited to, Triggers, ALP ULPS entry, and Fast BTA  
 597       • Skew Calibration Sequence  
 598       • Alternate Calibration Sequence

599     Due to the chance of HS-Trail being mimicked in the payload of normal HS Data Bursts, a controller-  
 600     assisted EoB detection mechanism is defined for the detection of EoB at the end of HS Data Bursts. This  
 601     relies on the receiver controller using the PPI input signal RxDetectEobHS to indicate to the PHY, that the  
 602     end of a HS Data Burst has been detected. The controller possesses all of the necessary information to parse  
 603     the incoming packets and to detect their boundaries as well as to detect an EoB.

604     This controller assisted EoB detection mechanism shall be used in the following scenario:  
 605       • Any HS Data burst  
 606  
 607     To ensure a deterministic behavior and also guarantee similarity between the two detection mechanisms,  
 608     the controller shall assert the EoB PPI signal during the HS-Trail period. The PPI signal RxDetectEobHS  
 609     should be flagged as early as possible into an HS-Trail period for a fast transition of the receiver into ALP  
 610     Stop. However, as HS-Trail has no maximum time limit, it can be extended as needed to accommodate  
 additional latency in the controller identifying and signaling the EoB event to the PHY.

611      The receiver shall use the SYNC information at the beginning of the burst to identify the type of the  
612      incoming burst, and consequently select the adequate end-of-burst detection mechanism.

## 6.5 Bi-directional Data Lane Turnaround

The transmission direction of a Bi-directional Data Lane can be swapped by means of a Link Turnaround procedure. This procedure enables information transfer in the opposite direction of the current direction. The procedure is the same for either a change from Forward-to-Reverse direction or Reverse-to-Forward Direction. Notice that Master and Slave side shall not be changed by Turnaround.

The Turnaround procedure can be performed in two ways: one is via a Control Mode Lane Turnaround that uses LP mode signaling, and the other is via a Fast Lane Turnaround using HS mode signaling along with ALP mode.

The requirements for Control Mode Lane Turnaround support and Fast Lane Turnaround support are as follows:

- Fast Lane Turnaround should be supported if ALP mode is implemented in a Bi-directional Lane Module.
- Control Mode Lane Turnaround should be supported if LP mode is implemented in a Bi-directional Lane Module.

### 6.5.1 Control Mode Lane Turnaround

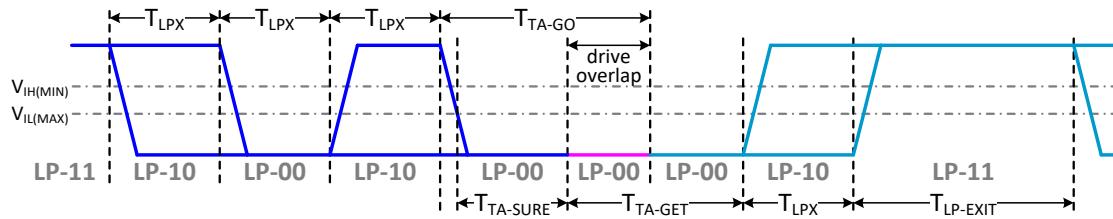
Control Mode Lane Turnaround shall be handled completely in Control mode. **Table 7** lists the sequence of events during Turnaround.

Table 7 Control Mode Lane Turnaround Sequence

Initial TX Side = Final RX Side	Initial RX Side = Final TX Side
Drives Stop state (LP-11)	Observes Stop state
Drives LP-Rqst state (LP-10) for a time $T_{LPX}$	Observes transition from LP-11 to LP-10 states
Drives Bridge state (LP-00) for a time $T_{LPX}$	Observes transition from LP-10 to LP-00 states
Drives LP-10 for a time $T_{LPX}$	Observes transition from LP-00 to LP-10 states
Drives Bridge state (LP-00) for a time $T_{TA-GO}$	Observes the transition from LP-10 to Bridge state and waits for a time $T_{TA-SURE}$ . After correct completion of this time-out this side knows it is in control.
—	Drives Bridge state (LP-00) for a period $T_{TA-GET}$
Stops driving the Lines and observes the Line states with its LP-RX in order to see an acknowledgement.	—
—	Drives LP-10 for a period $T_{LPX}$
Observes LP-10 on the Lines, interprets this as acknowledge that the other side has indeed taken control. Waits for Stop state to complete Turnaround procedure.	—
—	Drives Stop state (LP-11) for a period $T_{LP-EXIT}$
Observes transition to Stop state (LP-11) on the Lines, interprets this as Turnaround completion acknowledgement, switches to normal LP receive mode and waits for further actions from the other side	—

629 **Figure 20** shows the Control Mode Lane Turnaround procedure graphically.

630

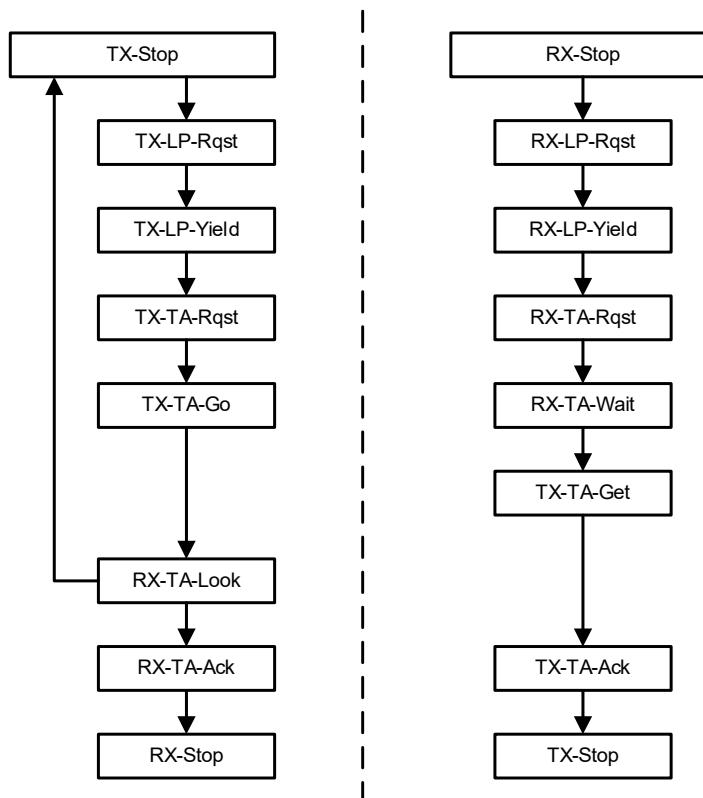


**Figure 20 Control Mode Lane Turnaround Procedure**

631 The Low-Power clock timing for both sides of the Link does not have to be the same, but may differ.  
 632 However, the ratio between the Low-Power State Periods,  $T_{LPX}$ , is constrained to ensure proper Turnaround  
 633 behavior. See **Table 18** for the ratio of  $T_{LPX}(\text{MASTER})$  to  $T_{LPX}(\text{SLAVE})$ .

634 The Control Mode Lane Turnaround procedure can be interrupted if the Lane is not yet driven into TX-LP-Yield by means of driving a Stop state. Driving the Stop state shall abort the Turnaround procedure and return the Lane to the Stop state. The PHY shall ensure against interruption of the procedure after the end of TX-TA-Rqst, RX-TA-Rqst, or TX-TA-GO. Once the PHY drives TX-LP-Yield, it shall not abort the Turnaround procedure. The Protocol may take appropriate action if it determines an error has occurred because the Turnaround procedure did not complete within a certain time. See **Section 7.3.5** for more details. **Figure 21** shows the Control Mode Lane Turnaround state machine that is described in **Table 8**.

641



**Figure 21 Control Mode Lane Turnaround State Machine**

642

**Table 8 Control Mode Lane Turnaround State Machine Description**

State	Line Condition/State	Exit State	Exit Conditions
Any RX state	Any Received	RX-Stop	Observe LP-11 at Lines
TX-Stop	Transmit LP-11	TX-LP-Rqst	On request of Protocol for Turnaround
TX-LP-Rqst	Transmit LP-10	TX-LP-Yield	End of timed interval $T_{LPX}$
TX-LP-Yield	Transmit LP-00	TX-TA-Rqst	End of timed interval $T_{LPX}$
TX-TA-Rqst	Transmit LP-10	TX-TA-Go	End of timed interval $T_{LPX}$
TX-TA-Go	Transmit LP-00	RX-TA-Look	End of timed interval $T_{TA-GO}$
RX-TA-Look	Receive LP-00	RX-TA-Ack	Line transition to LP-10
RX-TA-Ack	Receive LP-10	RX-Stop	Line transition to LP-11
RX-Stop	Receive LP-11	RX-LP-Rqst	Line transition to LP-10
RX-LP-Rqst	Receive LP-10	RX-LP-Yield	Line transition to LP-00
RX-LP-Yield	Receive LP-00	RX-TA-Rqst	Line transition to LP-10
RX-TA-Rqst	Receive LP-10	RX-TA-Wait	Line transition to LP-00
RX-TA-Wait	Receive LP-00	TX-TA-Get	End of timed interval $T_{TA-SURE}$
TX-TA-Get	Transmit LP-00	TX-TA-Ack	End of timed interval $T_{TA-GET}$
TX-TA-Ack	Transmit LP-10	TX-Stop	End of timed interval $T_{LPX}$

**Note:**

During RX-TA-Look, the protocol may cause the PHY to transition to TX-Stop.

During High-Speed data transmission, Stop states (TX-Stop, RX-Stop) have multiple valid exit states.

### 6.5.2 Fast Lane Turnaround

643 Fast Lane Turnaround can be supported by a Link, which supports ALP mode. It reduces the latency to  
 644 change the transmission direction of a Bi-directional Lane when operating at high speeds. A Fast Lane  
 645 Turnaround is initiated by an ALP Control Burst with a dedicated 16-bit Control-Code of Fast Lane  
 646 Turnaround Sequence. This code informs the receiver, that the Lane is about to change the direction of  
 647 transmission after completion of the HS-Trail of the ongoing ALP Control Burst. The lane direction is  
 648 reversed in the following ALP Stop state. While in this state both sides of the Lane drive the lines  
 649 momentarily before the initiating side stops driving the lines. The other side of the Lane is now driving the  
 650 lines. **Figure 22** shows an example of a Fast Lane Turnaround Procedure using HS and ALP modes with  
 651 the Link reversing direction twice so that the direction of traffic is the same at the start and end of the  
 652 sequence.

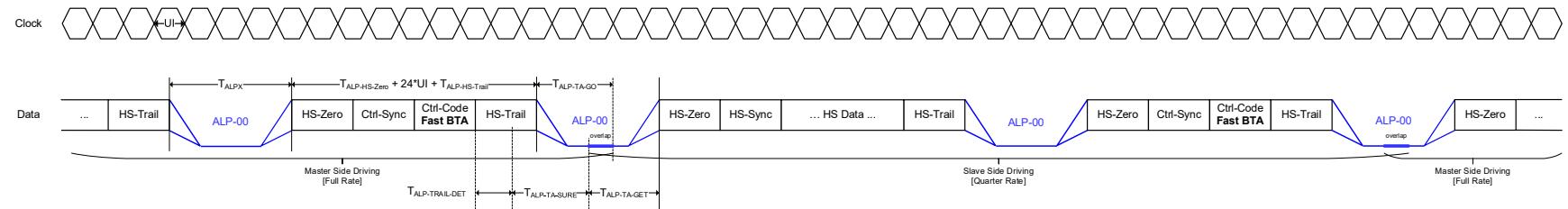


Figure 22 Fast Lane Turnaround Procedure in ALP Mode

654 **Table 9** lists the sequence of events during a single Fast Lane Turnaround.

**Table 9 Fast Lane Turnaround Sequence**

Initial TX Side = Final RX Side	Initial RX Side = Final TX Side
Drives ALP Stop state.	Observes Stop State.
Starts transmitting an ALP Control Burst with a leading HS-Zero.	Observes HS-Zero through ALP-ED. Enables Termination, HS-RX and looks for Sync word.
Transmits the Ctrl-Sync and Fast Turnaround Ctrl-Code (11011001 00100110).	Detects Fast Turnaround Ctrl-Code and waits for HS-Trail.
Transmits HS-Trail to close the burst followed by ALP-00 state for a time of $T_{ALP-TA-GO}$ .	After a time of $T_{ALP-TRAIL-DET}$ the HS-Trail is identified and a new counter is started $T_{ALP-TA-SURE}$ .
–	Starts driving ALP Stop state for a period $T_{ALP-TA-GET}$ after $T_{ALP-TA-SURE}$ expires.
Stops driving the lines after $T_{ALP-TA-GO}$ expires. Enables ALP-ED.	–
–	After a time $T_{ALP-TA-SURE}$ this side can start transmitting HS Data or Control Bursts as needed.
Observes the HS-Zero through ALP-ED. Enables Termination, HS-RX and looks for Sync word to synchronize. Receives data in the reverse direction.	Transmits a burst.

655 HS-Trail has no maximum time limit specified however, in the context of a Fast Lane Turnaround, an  
 656 indirect limit is set such that  $T_{ALP-HS-TRAIL} < T_{ALP-TRAIL-DET} + T_{ALP-TA-SURE}$ . This constraint ensures the Initial  
 657 TX Side is driving ALP-00 before the start of  $T_{ALP-TA-GET}$  to avoid a bus contention situation.

## 6.6 Escape Mode

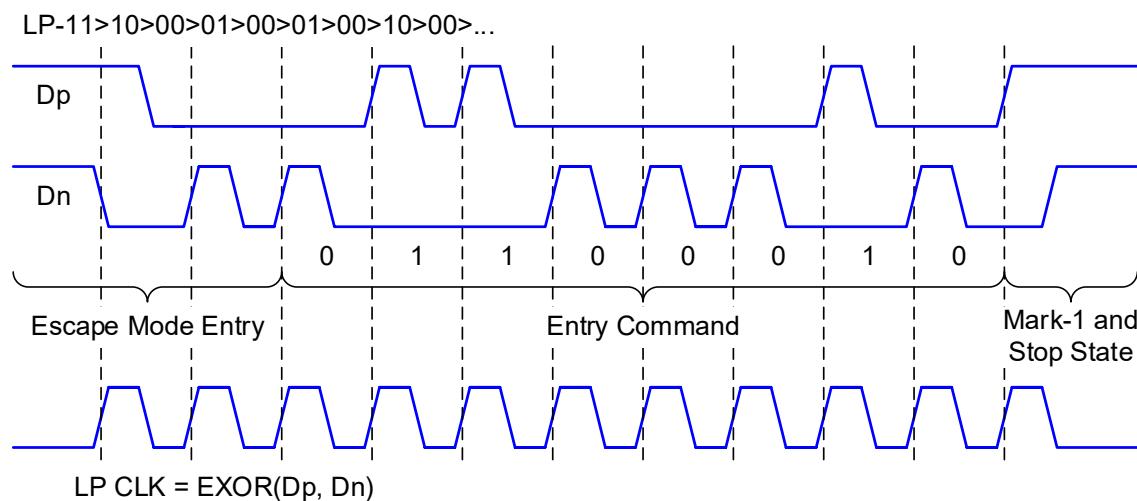
658 Escape Mode is a special mode of operation for Data Lanes using Low-Power states. With this mode some  
 659 additional functionality becomes available. Escape Mode operation shall be supported in the Forward  
 660 Direction and is optional in the Reverse direction. If supported, Escape Mode does not have to include all  
 661 available features.

662 A Data Lane shall enter Escape Mode via an Escape Mode Entry procedure (LP-11, LP-10, LP-00, LP-01,  
 663 LP-00). As soon as the final Bridge state (LP-00) is observed on the Lines the Lane shall enter Escape  
 664 Mode in the Space state (LP-00). If an LP-11 is detected at any time before the final Bridge state (LP-00),  
 665 the Escape Mode Entry procedure shall be aborted and the receive side shall wait for, or return to, the Stop  
 666 state.

667 For Data Lanes, once Escape Mode is entered, the transmitter shall send an 8-bit entry command to indicate  
 668 the requested action. *Table 10* lists all currently available Escape Mode commands and actions. All  
 669 unassigned commands are reserved for future expansion.

670 The Stop state shall be used to exit Escape Mode and cannot occur during Escape Mode operation because  
 671 of the Spaced-One-Hot encoding. Stop state immediately returns the Lane to Control mode. If the entry  
 672 command doesn't match a supported command, that particular Escape Mode action shall be ignored and the  
 673 receive side waits until the transmit side returns to the Stop state. The duration of the Stop state period shall  
 674 be at least  $T_{LP-EXIT,MIN}$ .

675 The PHY in Escape Mode shall apply Spaced-One-Hot bit encoding for asynchronous communication.  
 676 Therefore, operation of a Data Lane in this mode does not depend on the Clock Lane. The complete Escape  
 677 Mode action for a Trigger-Reset command is shown in *Figure 23*.



678 **Figure 23 Trigger-Reset Command in Escape Mode**

679 Spaced-One-Hot coding means that each Mark state is interleaved with a Space state. Each symbol consists  
 680 therefore of two parts: a One-Hot phase (Mark-0 or Mark-1) and a Space phase. The TX shall send Mark-0  
 681 followed by a Space to transmit a ‘zero-bit’ and it shall send a Mark-1 followed by a Space to transmit a  
 682 ‘one-bit’. A Mark that is not followed by a Space does not represent a bit. The last phase before exiting  
 683 Escape Mode with a Stop state shall be a Mark-1 state that is not part of the communicated bits, as it is not  
 684 followed by a Space state. The Clock can be derived from the two Line signals, Dp and Dn, by means of an  
 685 exclusive-OR function. The length of each individual LP state period shall be at least  $T_{LPX,MIN}$ .

686

**Table 10 Escape Entry Codes**

Escape Mode Action	Command Type	Entry Command Pattern (leftmost bit transmitted first)
Low-Power Data Transmission	Mode	11100001
Ultra-Low Power State	Mode	00011110
Undefined-1	Mode	10011111
Undefined-2	Mode	11011110
Reset-Trigger [Remote Application]	Trigger	01100010
Entry sequence for HS Test Mode	Trigger	01011101
Unknown-4	Trigger	00100001
Unknown-5	Trigger	10100000

### 6.6.1 Remote Triggers

687 Trigger signaling is the mechanism to send a flag to the protocol at the receiving side, on request of the  
688 protocol on the transmitting side. This can be either in the Forward or Reverse direction depending on the  
689 direction of operation and available Escape Mode functionality. Trigger signaling requires Escape Mode  
690 capability and at least one matching Trigger Escape Entry Command on both sides of the interface.

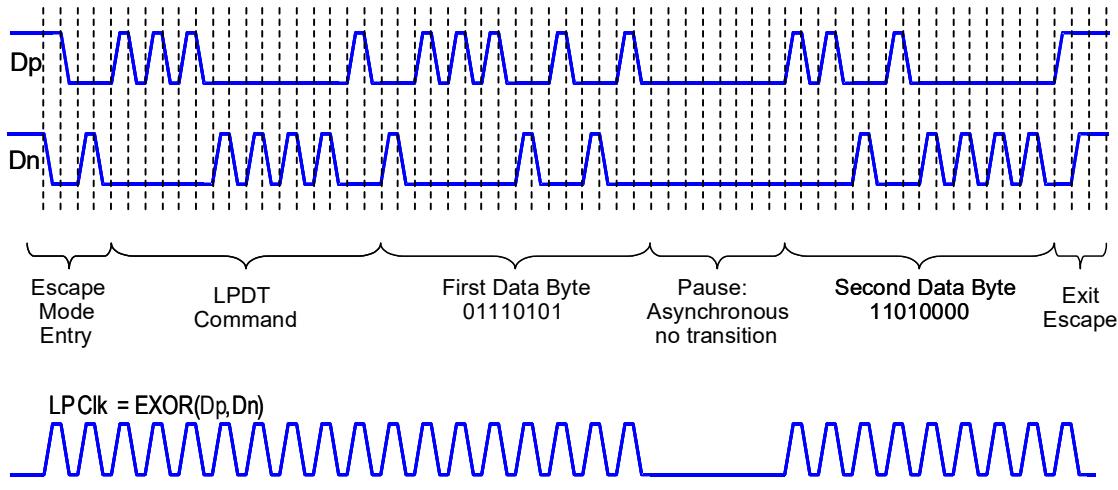
691 *Figure 23* shows an example of an Escape Mode Reset-Trigger action. The Lane enters Escape Mode via  
692 the Escape Mode Entry procedure. If the Entry Command Pattern matches the Reset-Trigger Command a  
693 Trigger is flagged to the protocol at the receive side via the logical PPI. Any bit received after a Trigger  
694 Command but before the Lines go to the Stop state shall be ignored. Therefore, dummy bytes can be  
695 concatenated in order to provide Clock information to the receive side.

696 Note that Trigger signaling including Reset-Trigger is a generic messaging system. The Trigger commands  
697 do not impact the behavior of the PHY itself. Therefore, Triggers can be used for any purpose by the  
698 Protocol layer.

### 6.6.2 Low-Power Data Transmission

If the Escape Mode Entry procedure is followed-up by the Entry Command for Low-Power Data Transmission (LPDT), then Data can be communicated by the protocol at low speed, while the Lane remains in Low-Power mode.

Data shall be encoded on the lines with the same Spaced-One-Hot code as used for the Entry Commands. The data is self-coded by the applied bit encoding and does not rely on the Clock Lane. The Lane can pause while using LPDT by maintaining a Space state on the Lines. A Stop state on the Lines stops LPDT, exits Escape Mode, and switches the Lane to Control mode. The last phase before Stop state shall be a Mark-1 state, which does not represent a data-bit. **Figure 24** shows a two-byte transmission with a pause period between the two bytes.



**Figure 24 Two Data Byte Low-Power Data Transmission Example**

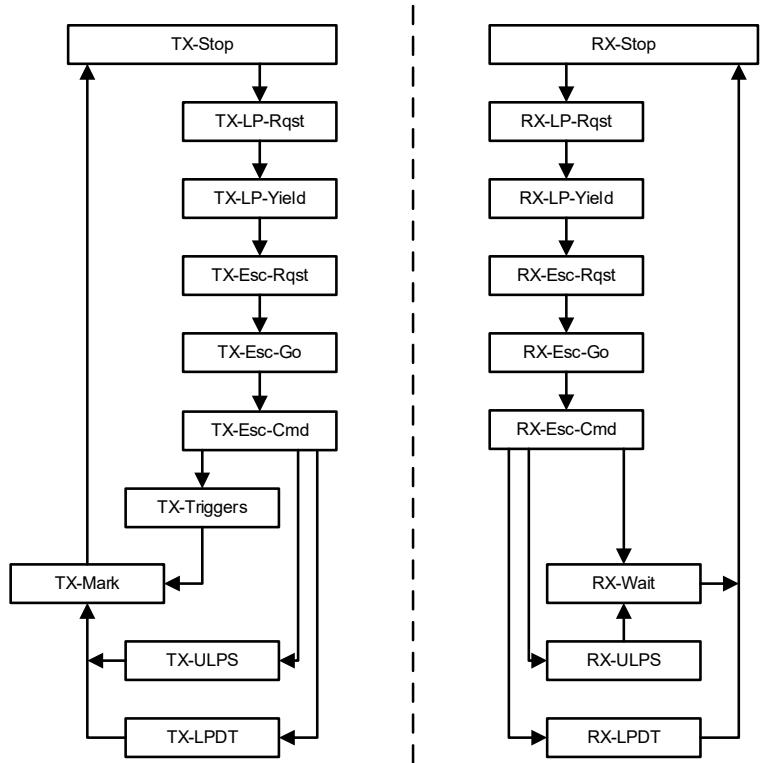
Using LPDT, a Low-Power (Bit) Clock signal ( $f_{\text{MOMENTARY}} < 20 \text{ MHz}$ ) provided to the transmit side is used to transmit data. Data reception is self-timed by the bit encoding. Therefore, a variable clock rate can be allowed. At the end of LPDT the Lane shall return to the Stop state.

### 6.6.3 Ultra-Low Power State

If the Ultra-Low Power State Entry Command is sent after an Escape Mode Entry command, the Lane shall enter the Ultra-Low Power State (ULPS). This command shall be flagged to the receive side Protocol. During this state, the Lines are in the Space state (LP-00). Ultra-Low Power State is exited by means of a Mark-1 state with a length  $T_{\text{WAKEUP}}$  followed by a Stop state. Annex A describes an example of an exit procedure and a procedure to control the length of time spent in the Mark-1 state.

#### 6.6.4 Escape Mode State Machine

718 The state machine for Escape Mode operation is shown in **Figure 25** and described in **Table 11**.



719

**Figure 25 Escape Mode State Machine**

**Table 11 Escape Mode State Machine Description**

<b>State</b>	<b>Line Condition/State</b>	<b>Exit State</b>	<b>Exit Conditions</b>
Any RX state	Any Received	RX-Stop	Observe LP-11 at Lines
TX-Stop	Transmit LP-11	TX-LP-Rqst	On request of Protocol for Esc Mode (PPI)
TX-LP-Rqst	Transmit LP-10	TX-LP-Yield	After time $T_{LPX}$
TX-LP-Yield	Transmit LP-00	TX-Esc-Rqst	After time $T_{LPX}$
TX-Esc-Rqst	Transmit LP-01	TX-Esc-Go	After time $T_{LPX}$
TX-Esc-Go	Transmit LP-00	TX-Esc-Cmd	After time $T_{LPX}$
TX-Esc-Cmd	Transmit sequence of 8-bit (16-Line-states) One-Spaced-Hot encoded Entry Command	TX-Triggers	After a Trigger Command
		TX-ULPS	After Ultra-Low Power Command
		TX-LPDT	After Low-Power Data Transmission Command
TX-Triggers	Space state or optional dummy bytes for the purpose of generating clocks	TX-Mark	Exit of the Trigger State on request of Protocol (PPI)
TX-ULPS	Transmit LP-00	TX-Mark	End of ULP State on request of Protocol (PPI)
TX-LPDT	Transmit serialized, Spaced-One-Hot encoded payload data		After last transmitted data bit
TX-Mark	Mark-1	TX-Stop	Next driven state after time $T_{LPX}$ , or $T_{WAKEUP}$ if leaving ULP State
RX-Stop	Receive LP-11	RX-LP-Rqst	Line transition to LP-10
RX-LP-Rqst	Receive LP-10	RX-LP-Yield	Line transition to LP-00
RX-LP-Yield	Receive LP-00	RX-Esc-Rqst	Line transition to LP-01
RX-Esc-Rqst	Receive LP-01	RX-Esc-Go	Line transition to LP-00
RX-Esc-Go	Receive LP-00	RX-Esc-Cmd	Line transition out of LP-00
RX-Esc-Cmd	Receive sequence of 8-bit (16-Line-states) One-Spaced-Hot encoded Entry Command	RX-Wait	After Trigger and Unrecognized Commands
		RX-ULPS	After Ultra-Low Power Command
		RX-LPDT	After Low-Power Data Transmission Command
RX-ULPS	Receive LP-00	RX-Wait	Line transition to LP-10
RX-LPDT	Receive serial, Spaced-One-Hot encoded payload data	RX-Stop	Line transition to LP-11 (Last state should be a Mark-1)
RX-Wait	Any, except LP-11	RX-Stop	Line transition to LP-11

**Note:**

During High-Speed data transmission, Stop states (TX-Stop, RX-Stop) have multiple valid exit states.

### 6.6.5 Escape Mode Equivalents in ALP Mode

ALP Control-Codes support the same functionalities as Escape Mode in LP mode. Only the LPDT function does not have an equivalent in ALP mode. **Table 12** shows the mapping between the ALP Control-Codes and the LP Escape Sequences, along with recommended codes if the optional PPI is adopted.

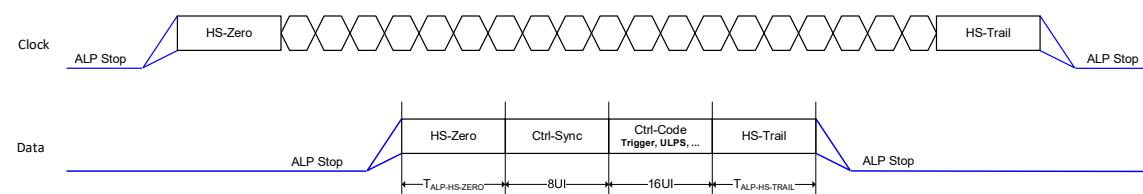
**Table 12 ALP Control-Code Definitions**

ALP Control Action	ALP Control-Code (leftmost bit transmitted first)	TxRequestTypeEsc PPI Code	Corresponding Escape Mode Sequence	Notes
Reserved	Reserved	0000	Reserved	2
ULPS	00011110 11100001	0001	Escape Mode Entry + Ultra-Low Power State	—
Undefined-1	10011111 01100000	0010	Escape Mode Entry + Undefined-1 Mode	—
Undefined-2	11011110 00100001	0011	Escape Mode Entry + Undefined-2 Mode	—
Reset-Trigger	01100010 10011101	0100	Escape Mode Entry + Reset-Trigger	—
Unknown 3 / HS-Test	01011101 10100010	0101	Escape Mode Entry + Unknown-3 / HS-Test Trigger	1
Unknown-4	00100001 11011110	0110	Escape Mode Entry + Unknown-4 Trigger	—
Unknown-5	10100000 01011111	0111	Escape Mode Entry + Unknown-5 Trigger	—
Reserved	Reserved	Other	Reserved	2

**Note:**

1. ALP Control-Code 0101110110100010 may be used as a dual-purpose trigger. HS-Test is available on the forward direction only, with Unknown-3 available on the reverse direction.
2. The optional Dynamic LP-ALP mode uses additional reserved values, as described in Section H.1.1.

These ALP Control-Codes can be used in ALP Control Bursts to signal special functions to the protocol of the receiver. An ALP Control Burst example is shown in **Figure 26**.



**Figure 26 ALP Control Burst Example**

728 All Control Bursts start and end in the ALP Stop state, with the exception of a ULPS Control Burst where  
729 the Data Lane shall enter the ALP ULPS state at the end of the burst. During this state, the Lines are in the  
730 ALP-00 state. The ALP ULPS state is exited by means of an ALP-01 Line state with a length  $T_{ALP-WAKEUP}$   
731 followed by a transition to ALP Stop state. A similar procedure is used for the Clock Lane wakeup as  
732 explained in **Section 6.8.2**.

## 6.7 High-Speed Clock Transmission

In High-Speed mode the Clock Lane provides a low-swing, differential DDR (half-rate) clock signal from Master to Slave for High-Speed Data Transmission. The Clock signal shall have quadrature-phase with respect to a toggling bit sequence on a Data Lane in the Forward Direction and a rising edge in the center of the first transmitted bit of a burst. Details of the Data-Clock relationship and timing specifications can be found in **Section 10**.

A Clock Lane is similar to a Unidirectional Data Lane. However, there are some timing differences and a Clock Lane transmits a High-Speed Clock signal instead of data bits. Furthermore, the Low-Power and Alternate Low-Power mode functionalities are defined differently for a Clock Lane than a Data Lane. A Clock Lane is Unidirectional and does not include regular Escape Mode functionality. Only ULPS is supported via a special entry sequence using the LP-Rqst state in LP mode, or HS-Zero/HS-Trail sequence in ALP mode as per **Section 6.8.2**. High-Speed Clock Transmission shall start from, and exit to, a Stop state or ALP Stop state in LP mode and ALP mode, respectively.

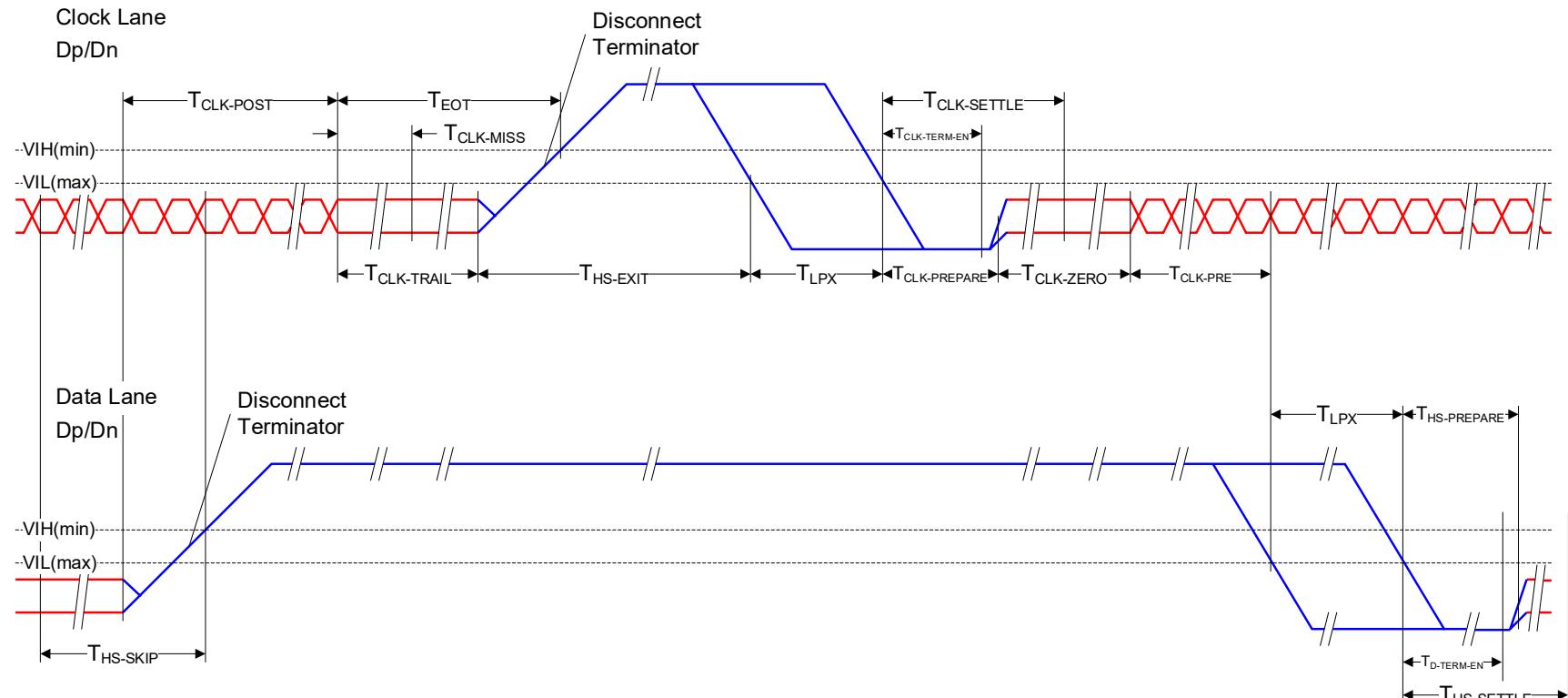
The Clock Lane Module is controlled by the Protocol via the Clock Lane PPI. The Protocol shall only stop the Clock Lane when there are no High-Speed transmissions active in any Data Lane.

The High-Speed Data Transmission start-up time of a Data Lane is extended if the Clock Lane is in a low-power mode. In that case the Clock Lane shall first return to High-Speed operation before the Transmit Request can be handled.

The next sections define the clock transmission in LP and ALP operation.

### 6.7.1 Low-Power Mode

The High-Speed Clock signal shall continue running for a period  $T_{CLK-POST}$  after the last Data Lane switches to Low-Power mode and ends with a HS-0 state. The procedure for switching the Clock Lane to Low-Power mode is given in **Table 13**. Note the Clock Burst always contains an even number of transitions as it starts and ends with a HS-0 state. This implies that the clock provides transitions to sample an even number of bits on any associated Data Lanes. Clock periods shall be reliable and according to the HS timing specifications. The procedure to return the Clock Lane to High-Speed Clock Transmission is given in **Table 14**. Both Clock Start and Stop procedures are shown in **Figure 27**.



758

**Figure 27 Switching the Clock Lane between Clock Transmission and Low-Power Mode**

759

760

**Table 13 Procedure to Switch Clock Lane to Low-Power Mode**

Master Side	Slave Side
Drives High-Speed Clock signal (Toggling HS-0/HS-1)	Receives High-Speed Clock signal (Toggling HS-0/HS-1)
Last Data Lane goes into Low-Power mode	–
Continues to drives High-Speed Clock signal for a period $T_{CLK-POST}$ and ends with HS-0 state	–
Drives HS-0 for a time $T_{CLK-TRAIL}$	Detects absence of Clock transitions within a time $T_{CLK-MISS}$ , disables HS-RX then waits for a transition to the Stop state
Disables the HS-TX, enables LP-TX, and drives Stop state (LP-11) for a time $T_{HS-EXIT}$	–
–	Detects the Lines transitions to LP-11, disables HS termination, and enters Stop state

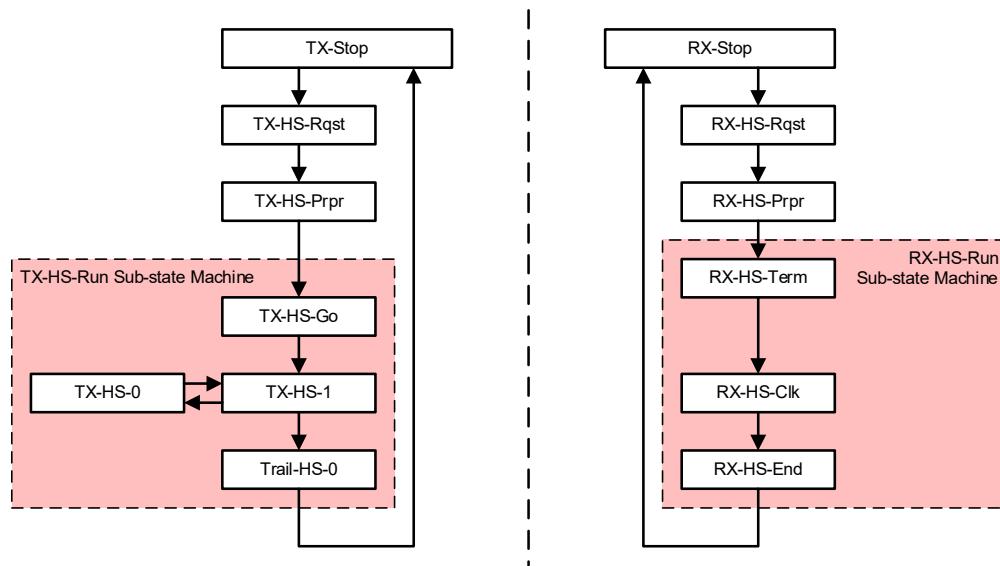
761

**Table 14 Procedure to Initiate High-Speed Clock Transmission**

TX Side	RX Side
Drives Stop state (LP-11)	Observes Stop state
Drives HS-Req state (LP-01) for time $T_{LPX}$	Observes transition from LP-11 to LP-01 on the Lines
Drives Bridge state (LP-00) for time $T_{CLK-PREPARE}$	Observes transition from LP-01 to LP-00 on the Lines. Enables Line Termination after time $T_{CLK-TERM-EN}$
Enables High-Speed driver and disables Low-Power drivers simultaneously. Drives HS-0 for a time $T_{CLK-ZERO}$ .	Enables HS-RX and waits for timer $T_{CLK-SETTLE}$ to expire in order to neglect transition effects
–	Receives HS-signal
Drives the High-Speed Clock signal for time period $T_{CLK-PRE}$ before any Data Lane starts up	Receives High-Speed Clock signal

762

The Clock Lane state machine is shown in **Figure 28** and is described in **Table 15**.



763

**Figure 28 High-Speed Clock Transmission State Machine**

764

**Table 15 Description of High-Speed Clock Transmission State Machine**

State	Line Condition/State	Exit State	Exit Conditions
TX-Stop	Transmit LP-11	TX-HS-Rqst	On request of Protocol for High-Speed Transmission
TX-HS-Rqst	Transmit LP-01	TX-HS-Prpr	End of timed interval $T_{LPX}$
TX-HS-Prpr	Transmit LP-00	TX-HS-Go	End of timed interval $T_{CLK-PREPARE}$
TX-HS-Go	Transmit HS-0	TX-HS-1	End of timed interval $T_{CLK-ZERO}$
TX-HS-0	Transmit HS-0	TX-HS-1	Send a HS-1 phase after a HS-0 phase Clock
TX-HS-1	Transmit HS-1	TX-HS-0	Send a HS-0 phase after a HS-1 phase Clock
		Trail-HS-0	On request to put Clock Lane in Low-Power
Trail-HS-0	Transmit HS-0	TX-Stop	End of timed interval $T_{CLK-TRAIL}$
RX-Stop	Receive LP-11	RX-HS-Rqst	Line transition to LP-01
RX-HS-Rqst	Receive LP-01	RX-HS-Prpr	Line transition to LP-00
RX-HS-Prpr	Receive LP-00	RX-HS-Term	End of timed interval $T_{CLK-TERM-EN}$
RX-HS-Term	Receive LP-00	RX-HS-Clk	End of timed interval $T_{CLK-SETTLE}$
RX-HS-Clk	Receive DDR-Q Clock signal	RX-Clk-End	Time-out $T_{CLK-MISS}$ on the period on the Clock Lane without Clock signal transitions
RX-HS-End	Receive HS-0	RX-HS-Stop	Line transition to LP-11

**Note:**

During High-Speed data transmission, Stop states (TX-Stop, RX-Stop) have multiple valid exit states.

### 6.7.2 Alternate Low-Power Mode

The High-Speed Clock signal in ALP mode shall continue running for a period  $T_{ALP-CLK-POST}$  after the last Data Lane in either the forward or reverse direction has switched to ALP Stop state. In ALP mode the Clock Lane shall end with a HS-1 trail period before transitioning to ALP Stop state. To resume communication, the Clock Lane shall wake up and provide a stable high speed clock for a time of  $T_{ALP-CLK-PRE}$  before the Data Lanes can start a high-speed burst transmission. Clock Lane Start and Stop procedures in ALP mode are shown in *Figure 29*.

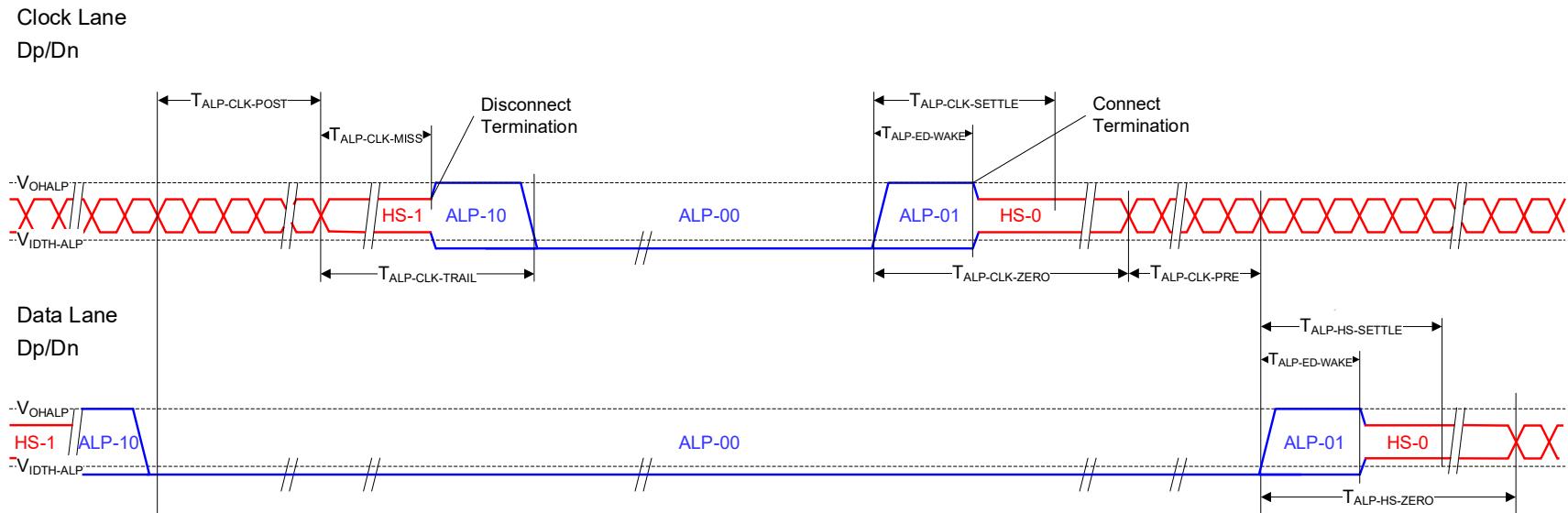


Figure 29 Switching the Clock Lane Between Clock Transmission and ALP Mode

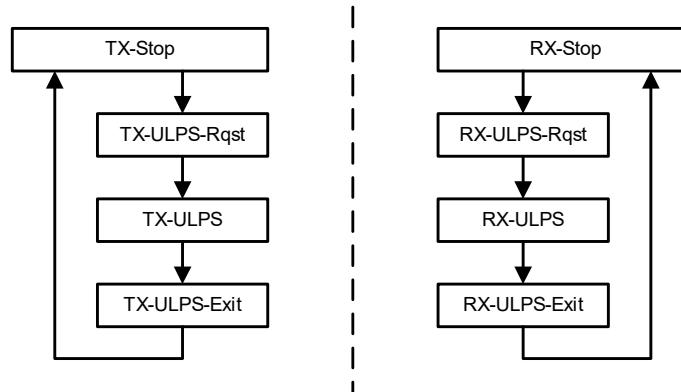
## 6.8 Clock Lane Ultra-Low Power State

### 6.8.1 Clock Lane ULPS in LP Mode

Although a Clock Lane does not include regular Escape Mode, the Clock Lane shall support the Ultra-Low Power State.

A Clock Lane shall enter Ultra-Low Power State via a Clock Lane Ultra-Low Power State Entry procedure. In this procedure, starting from Stop state, the transmit side shall drive TX-ULPS-Rqst State (LP-10) and then drive TX-ULPS State (LP-00). After this, the Clock Lane shall enter Ultra-Low Power State. If an error occurs, and an LP-01 or LP-11 is detected immediately after the TX-ULPS-Rqst state, the Ultra-Low Power State Entry procedure shall be aborted, and the receive side shall wait for, or return to, the Stop state, respectively.

The receiving PHY shall flag the appearance of ULP State to the receive side Protocol. During this state the Lines are in the ULP State (LP-00). Ultra-Low Power State is exited by means of a Mark-1 TX-ULPS-Exit State with a length  $T_{WAKEUP}$  followed by a Stop State. Annex A describes an example of an exit procedure that allows control of the length of time spent in the Mark-1 TX-ULPS-Exit State.



Note: Horizontally aligned states occur simultaneously.

**Figure 30 Clock Lane Ultra-Low Power State State Machine**

**Table 16 Clock Lane Ultra-Low Power State State Machine Description**

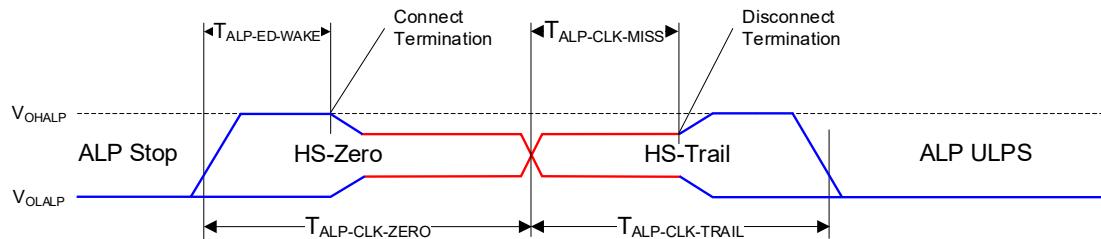
State	Line Condition/State	Exit State	Exit Conditions
TX-Stop	Transmit LP-11	TX-ULPS-Rqst	On request of Protocol for Ultra-Low Power State
TX-ULPS-Rqst	Transmit LP-10	TX-ULPS	End of timed interval $T_{LPX}$
TX-ULPS	Transmit LP-00	TX-ULPS-Exit	On request of Protocol to leave Ultra-Low Power State
TX-ULPS-Exit	Transmit LP-10	TX-Stop	End of timed interval $T_{WAKEUP}$
RX-Stop	Receive LP-11	RX-ULPS-Rqst	Line transition to LP-10
RX-ULPS-Rqst	Receive LP-10	RX-ULPS	Line transition to LP-00
RX-ULPS	Receive LP-00	RX-ULPS-Exit	Line transition to LP-10
RX-ULPS-Exit	Receive LP-10	RX-Stop	Line transition to LP-11

**Note:**

During High-Speed data transmission, Stop states (TX-Stop, RX-Stop) have multiple valid exit states.

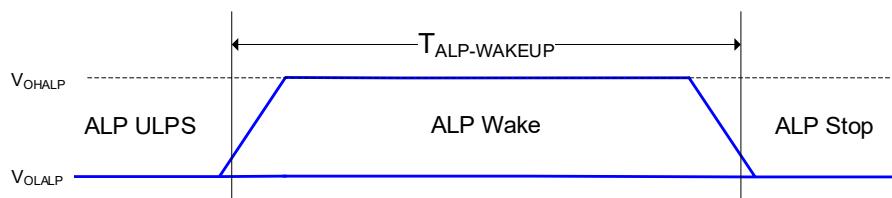
### 6.8.2 Clock Lane ULPS in ALP Mode

A Clock Lane is unidirectional and does not support the same level of ALP Command functionality as Data Lanes. However, ALP ULPS shall be supported via a special entry sequence as shown in **Figure 31**. The Clock Lane receiver shall interpret an HS-Zero period of  $T_{ALP-CLK-ZERO}$  followed by an HS-Trail (HS-1) period of  $T_{ALP-CLK-TRAIL}$  as an ULPS Entry request. Afterwards the Clock Lane shall move to an ultra-low power mode of operation in which most of the internal circuitry can be disabled.



**Figure 31 Clock Lane ALP ULPS Entry Sequence**

To wake up a Clock Lane from an ALP ULPS state, a long ALP Wake pulse of a duration  $T_{ALP-WAKEUP}$  shall be sent by the transmitter followed by an ALP Stop state. The Clock Lane ALP-ED shall detect this sequence as an ALP ULPS exit and shall transition to ALP Stop. The differential termination shall remain disabled throughout the entire sequence.



**Figure 32 Clock Lane ALP ULPS Exit Sequence**

**Table 17 Clock Lane ALP Ultra-Low Power State State Machine Description**

State	Line Condition/State	Exit State	Exit Conditions
TX-ALP-Stop	Transmit ALP-00	TX- ALP-ULPS-Rqst	On request of Protocol for ALP ULPS state
TX-ALP-ULPS-Rqst	Transmit ALP-01 / HS-0	TX-ALP-ULPS	End of timed interval $T_{ALP-CLK-ZERO}$
	Transmit HS-1 / ALP-10		End of timed interval $T_{ALP-CLK-TRAIL}$
TX-ALP-ULPS	Transmit ALP-00	TX-ALP-ULPS-Exit	On request of Protocol to leave ALP ULPS state
TX-ALP-ULPS-Exit	Transmit ALP-01	TX-ALP-Stop	End of timed interval $T_{ALP-WAKEUP}$
RX-ALP-Stop	Receive ALP-00	RX-ALP-ULPS-Rqst	Line transition to ALP-01
RX-ALP-ULPS-Rqst	Receive ALP-01 / HS-0	RX-ALP-ULPS	Line transition to HS-1
	Receive HS-1 / ALP-10		Line transition to ALP-00
RX-ALP-ULPS	Receive ALP-00	RX-ALP-ULPS-Exit	Line transition to ALP-01
RX-ALP-ULPS-Exit	Receive ALP-01	RX-ALP-Stop	Line transition to ALP-00

## 6.9 Global Operation Timing Parameters

798     Table 18 and Table 19 list the ranges for all timing parameters used in this Section for LP mode - HS mode  
799     operation cycles and ALP mode - HS mode operation cycles, respectively. The values in the table assume a  
800     UI variation in the range defined by  $\Delta UI$  (see Table 47).

801     Transmitters shall support all transmitter-specific timing parameters defined in Table 18. Transmitters  
802     supporting ALP mode shall support all transmitter-specific timing parameters defined in Table 19.

803     Receivers shall support all Receiver-specific timing parameters in defined in Table 18. Receivers  
804     supporting ALP mode shall support all receiver-specific timing parameters in Table 19.

805     Also note that while corresponding receiver tolerances are not defined for every transmitter-specific  
806     parameter, receivers shall also support reception of all allowed conformant values for all transmitter-  
807     specific timing parameters in Table 18 and Table 19 for all HS UI values up to, and including, the  
808     maximum supported HS clock rate specified in the receiver's datasheet.

809     When the PHY is supporting  $> 4.5$  Gbps and is configured to operate at a lower bit rate, then the system  
810     designer must ensure that the transmitter is compatible with the receiver's timing requirements. The  
811     receiver requirements should be specified in the receiver's datasheet or other document.

**Table 18 Operation Timing Parameters in LP Mode - HS Mode Cycles**

Parameter	Description	Min	Typ	Max	Unit	Notes
T <sub>CLK-MISS</sub>	Timeout for receiver to detect absence of Clock transitions and disable the Clock Lane HS-RX.	–	–	60	ns	1, 6, 8
T <sub>CLK-POST</sub>	Time that the transmitter continues to send HS clock after the last associated Data Lane has transitioned to LP mode. Interval is defined as the period from the end of T <sub>HS-TRAIL</sub> to the beginning of T <sub>CLK-TRAIL</sub> .	60 ns + 52*UI	–	–	–	5, 11
T <sub>CLK-PRE</sub>	Time that the HS clock shall be driven by the transmitter prior to any associated Data Lane beginning the transition from LP to HS mode.	8	–	–	UI	5
T <sub>CLK-PREPARE</sub>	Time that the transmitter drives the Clock Lane LP-00 Line state immediately before the HS-0 Line state starting the HS transmission.	38	–	95	ns	5, 9
T <sub>CLK-SETTLE</sub>	Time interval during which the HS receiver should ignore any Clock Lane HS transitions, starting from the beginning of T <sub>CLK-PREPARE</sub> .	95	–	300	ns	6, 7
T <sub>CLK-TERM-EN</sub>	Time for the Clock Lane receiver to enable the HS Line termination, starting from the time point when Dn crosses V <sub>IL,MAX</sub> .	Time for Dn to reach V <sub>TERM-EN</sub>	–	38	ns	6
T <sub>CLK-TRAIL</sub>	Time that the transmitter drives the HS-0 state after the last payload clock bit of a HS transmission burst.	60	–	–	ns	5
T <sub>CLK-PREPARE + T<sub>CLK-ZERO</sub></sub>	T <sub>CLK-PREPARE</sub> + time that the transmitter drives the HS-0 state prior to starting the Clock.	300	–	–	ns	5
T <sub>D-TERM-EN</sub>	Time for the Data Lane receiver to enable the HS Line termination, starting from the time point when Dn crosses V <sub>IL,MAX</sub> .	Time for Dn to reach V <sub>TERM-EN</sub>	–	35 ns + 4*UI	–	6
T <sub>EOT</sub>	Transmitted time interval from the start of T <sub>HS-TRAIL</sub> or T <sub>CLK-TRAIL</sub> , to the start of the LP-11 state following a HS burst.	–	–	105 ns + n*12*UI	–	3, 5
T <sub>HS-EXIT</sub>	Time that the transmitter drives LP-11 following a HS burst.	100	–	–	ns	5, 11
T <sub>LP-EXIT</sub>	Time that the transmitter drives LP-11 between any LP sequences, or between an LP sequence and a HS burst.	2*T <sub>LPX,MIN</sub>	–	–	–	–
T <sub>HS-PREPARE</sub>	Time that the transmitter drives the Data Lane LP-00 Line state immediately before the HS-0 Line state starting the HS transmission.	40 ns + 4*UI	–	85 ns + 6*UI	–	5, 10
T <sub>HS-PREPARE + T<sub>HS-ZERO</sub></sub>	T <sub>HS-PREPARE</sub> + time that the transmitter drives the HS-0 state prior to transmitting the Sync sequence.	145 ns + 10*UI	–	–	–	5
T <sub>HS-SETTLE</sub>	Time interval during which the HS receiver shall ignore any Data Lane HS transitions, starting from the beginning of T <sub>HS-PREPARE</sub> . The HS receiver shall ignore any Data Lane transitions before the minimum value, and the HS receiver shall respond to any Data Lane transitions after the maximum value.	85 ns + 6*UI	–	145 ns + 10*UI	–	6

Parameter	Description	Min	Typ	Max	Unit	Notes
$T_{HS\text{-}SKIP}$	Time interval during which the HS-RX should ignore any transitions on the Data Lane, following a HS burst. The end point of the interval is defined as the beginning of the LP-11 state following the HS burst.	40 ns	—	55 ns + 4*UI	—	6
$T_{HS\text{-}SYNC}$	Time that the transmitter drives the HS Data sync pattern.	$n^8$			UI	3
$T_{HS\text{-}TRAIL}$	Time that the transmitter drives the flipped differential state after last payload data bit of a HS transmission burst.	max( $n^8\text{UI}$ , $60\text{ ns} + n^4\text{UI}$ )	—	—	—	2, 3, 5
$T_{INIT}$	See <b>Section 6.11</b> .	100	—	—	$\mu\text{s}$	5
$T_{LPX}$	Transmitted length of any Low-Power state period.	50	—	—	ns	4, 5
Ratio $T_{LPX}$	Ratio of $T_{LPX(\text{MASTER})}/T_{LPX(\text{SLAVE})}$ between Master and Slave side.	2/3	—	3/2	—	—
$T_{TA\text{-}GET}$	Time that the new transmitter drives the Bridge state (LP-00) after accepting control during a Link Turnaround.	$5*T_{LPX}$			—	5
$T_{TA\text{-}GO}$	Time that the transmitter drives the Bridge state (LP-00) before releasing control during a Link Turnaround.	$4*T_{LPX}$			—	5
$T_{TA\text{-}SURE}$	Time that the new transmitter waits after the LP-10 state before transmitting the Bridge state (LP-00) during a Link Turnaround.	$T_{LPX}$	—	$2*T_{LPX}$	—	5
$T_{WAKEUP}$	Time that a transmitter drives a Mark-1 state prior to a Stop state in order to initiate an exit from ULPS.	1	—	—	ms	5

**Note:**

1. The minimum value depends on the bit rate. Implementations should ensure proper operation for all the supported bit rates.
2. If  $a > b$  then  $\max(a, b) = a$  otherwise  $\max(a, b) = b$ .
3. Where  $n = 1$  for Forward-direction HS mode and  $n = 4$  for Reverse-direction HS mode.
4.  $T_{LPX}$  is an internal state machine timing reference. Externally measured values may differ slightly from the specified values due to asymmetrical rise and fall times.
5. Transmitter-specific parameter.
6. Receiver-specific parameter.
7. The stated values are considered informative guidelines rather than normative requirements since this parameter is untestable in typical applications.
8. During HS Test mode the  $T_{CLK\text{-}MISS}$  parameter should be used for re-initialization of pattern checkers. The device should only exit the HS Test mode in the cases described in **Section 12**.
9. There is no direct relation between  $T_{LPX}$  and an observed  $T_{CLK\text{-}PREPARE}$ .
10. There is no direct relation between  $T_{LPX}$  and an observed  $T_{HS\text{-}PREPARE}$ .  $T_{HS\text{-}PREPARE}$  limits the LP to HS signaling transition, and minimum LP-state duration doesn't apply.
11. Transmitter should support programmability for this parameter so that a system integrator can program it as per application needs.

**Table 19 Operation Timing Parameters in ALP Mode - HS Mode Cycles**

Parameter	Description	Min	Typ	Max	Unit	Notes
T <sub>ALP-CLK-MISS</sub>	Timeout for receiver to detect absence of Clock transitions and disable the Clock Lane HS-RX.	–	–	5	μs	1, 6, 8
T <sub>ALP-CLK-POST</sub>	Time that the transmitter continues to send HS clock after the last associated Data Lane has transitioned to ALP-00 Line State. Interval is defined as the period from the end of T <sub>ALP-HS-TRAIL</sub> to the beginning of T <sub>ALP-CLK-TRAIL</sub> .	60 ns + 52*UI	–	–	–	5, 11
T <sub>ALP-CLK-PRE</sub>	Time that the HS clock shall be driven by the transmitter prior to any associated Data Lane beginning the transition from ALP-00 to ALP-01 Line state.	8	–	–	UI	5
T <sub>ALP-CLK-SETTLE</sub>	Time interval during which the HS receiver should ignore any Clock Lane HS transitions, starting from the beginning of T <sub>ALP-CLK-ZERO</sub> .	50	–	205	ns	6, 7
T <sub>ALP-CLK-TRAIL</sub>	Time that the transmitter drives the HS-1 / ALP-10 Line states after the last valid clock edge of a HS transmission burst.	60	–	–	ns	5
T <sub>ALP-CLK-ZERO</sub>	Time that the transmitter drives the ALP-01 / HS-0 Line states prior to starting the Clock.	205	–	–	ns	5
T <sub>ALP-ED-WAKE</sub>	Time for the ALP-ED to detect activity on the lines and enable the HS Line termination, starting from the time point when Dn-Dp crosses V <sub>IDTH-ALP</sub> .	–	–	50	ns	6, 12
T <sub>ALP-HS-ZERO</sub>	Time that the transmitter drives the ALP-01 / HS-0 Line state prior to transmitting the Sync sequence.	80 ns + 4*UI	–	–	–	5
T <sub>ALP-HS-SETTLE</sub>	Time interval during which the HS receiver shall ignore any Data Lane HS transitions, starting from the beginning of T <sub>ALP-HS-ZERO</sub> . The HS receiver shall ignore any Data Lane transitions before the minimum value, and the HS receiver shall respond to any Data Lane transitions after the maximum value.	50 ns	–	80 ns + 4*UI	–	6
T <sub>ALP-HS-SYNC</sub>	Time that the transmitter drives the HS Data sync pattern.	n*8			UI	3
T <sub>ALP-HS-TRAIL</sub>	Time that the transmitter drives the HS-1 / ALP-10 Line states after last payload data bit of a HS transmission burst.	max( n*16*UI, 60 ns + n*4*UI )	–	–	–	2, 3, 5, 11
T <sub>ALP-INIT</sub>	See <b>Section 6.11</b> .	100	–	–	μs	5
T <sub>ALPX</sub>	Transmitted length of any ALP-00 Line state.	100	–	–	ns	4, 5
T <sub>ALP-TRAIL-DET</sub>	Time for the receiver to identify a long HS-1 sequence as an HS-TRAIL period.	n*12*UI	–	max( n*16*UI, 60 ns + n*4*UI )	–	2, 3
T <sub>ALP-TA-GET</sub>	Time that the new transmitter drives the ALP-00 state after accepting control during a Link Turnaround.	max( 32*UI, T <sub>ALPX</sub> )			–	2, 4, 5

Parameter	Description	Min	Typ	Max	Unit	Notes
T <sub>ALP-TA-GO</sub>	Time that the transmitter drives the ALP-00 state before releasing control during a Link Turnaround.		max( 16*UI, 50 ns)		–	2, 5, 9
T <sub>ALP-TA-SURE</sub>	Time that the new transmitter waits after detecting the HS-TRAIL and before transmitting the ALP-00 state during a Link Turnaround.		max( 16*UI, 50 ns)		–	2, 5, 9, 10
T <sub>ALP-WAKEUP</sub>	Time that a transmitter drives an ALP Wake pulse in order to initiate an exit from ALP ULPS state.	1	–	–	ms	5

**Note:**

1. The minimum value depends on the bit rate. Implementations should ensure proper operation for all the supported bit rates.
2. If  $a > b$  then  $\max(a, b) = a$  otherwise  $\max(a, b) = b$ .
3. Where  $n = 1$  for Forward-direction HS mode and  $n = 4$  for Reverse-direction HS mode.
4.  $T_{ALPX}$  is an internal state machine timing reference. Externally measured values may differ slightly from the specified values due to asymmetrical rise and fall times.
5. Transmitter-specific parameter.
6. Receiver-specific parameter.
7. The stated values are considered informative guidelines rather than normative requirements since this parameter is untestable in typical applications.
8. During HS Test mode the  $T_{ALP-CLK-MISS}$  parameter should be used for re-initialization of pattern checkers. The device should only exit the HS Test mode in the cases described in **Section 12**.
9. The alignment of  $T_{ALP-TA-GO}$  and  $T_{ALP-TA-SURE}$  allows control over the ALP-00 overlap period when driven by both ends of the link.
10.  $T_{ALP-TA-SURE}$  sets an indirect maximum limit for  $T_{ALP-HS-TRAIL}$  in the context of a Link Turnaround.
11. Transmitter should support programmability for this parameter so that system integrator can program it as per application needs.
12. The termination shall be enabled before this time expires. Any transient effect in the lines may settle during  $T_{ALP-CLK-TRAIL}$  or  $T_{ALP-HS-TRAIL}$ .

## 6.10 System Power States

Each Lane within a PHY Configuration, that is powered and enabled, has potentially three different power consumption levels: High-Speed Transmission mode, Low-Power mode and Ultra-Low Power State. For details on Ultra-Low Power State see **Section 6.6.3** and **Section 6.8**. The transition between these modes shall be handled by the PHY.

If a Lane supports ALP mode, the power consumptions levels can also differ between High-Speed Transmission mode, ALP Stop state, and ALP ULPS state. For details on ALP Stop and ALP ULPS states refer to **Section 6.4.5**, **Section 6.7.2**, and **Section 6.8.2**. The transition between these modes shall be handled by the PHY.

## 6.11 Initialization

All PHYs support LP mode. If ALP mode is also supported, it is up to the system implementer to decide whether the Link is initialized using the LP initialization or the ALP initialization. The chosen initialization depends on the targeted low-power mode, which can be either LP mode or ALP mode.

### 6.11.1 LP Initialization

After power-up, the Slave side PHY shall be initialized when the Master PHY drives a Stop State (LP-11) for a period longer than  $T_{INIT}$ . The first Stop state longer than the specified  $T_{INIT}$  is called the Initialization period. The Master PHY itself shall be initialized by a system or Protocol input signal (PPI). The Master side shall ensure that a Stop State longer than  $T_{INIT}$  does not occur on the Lines before the Master is initialized. The Slave side shall ignore all Line states during an interval of unspecified length prior to the Initialization period. In multi-Lane configurations, all Lanes shall be initialized simultaneously.

Note that  $T_{INIT}$  is a protocol-dependent parameter, and thus the exact requirements for  $T_{INIT,MASTER}$  and  $T_{INIT,SLAVE}$  (transmitter and receiver initialization Stop state lengths, respectively,) are defined by the protocol layer specification and are outside the scope of this document. However, the D-PHY specification does place a minimum bound on the lengths of  $T_{INIT,MASTER}$  and  $T_{INIT,SLAVE}$ , which each shall be no less than 100  $\mu$ s. A protocol layer specification using the D-PHY specification may specify any values greater than this limit, for example,  $T_{INIT,MASTER} \geq 1$  ms and  $T_{INIT,SLAVE} = 500$  to 800  $\mu$ s.

**Table 20 Initialization States**

State	Entry Conditions	Exit State	Exit Conditions	Line Levels
Master Off	Power-down	Master Initialization	Power-up	Any LP level except Stop States for periods longer than $T_{INIT}$
Master Init	Power-up or Protocol request	TX-Stop	A First Stop state for a period longer than $T_{INIT,MASTER}$ as specified by the Protocol	Any LP signaling sequence that ends with a long Initialization Stop state
Slave Off	Power-down	Any LP state	Power-up	Any
Slave Init	Power-up or Protocol request	RX-Stop	Observe Stop state at the inputs for a period $T_{INIT,SLAVE}$ as specified by the Protocol	Any LP signaling sequence which ends with the first long Initialization Stop period

### 6.11.2 ALP Initialization

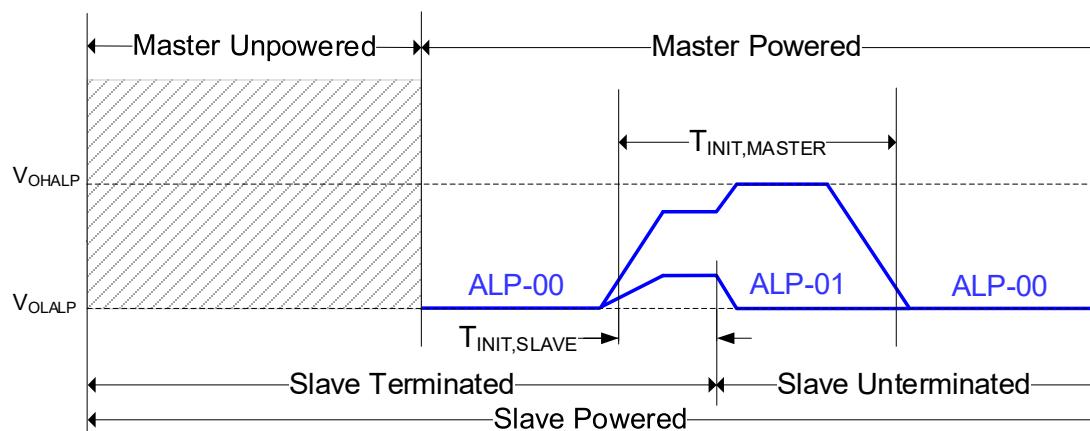
After power-up, the Slave side PHY shall be initialized when the Master PHY transmits an ALP Wake pulse with a duration longer than  $T_{INIT}$ . The sequence of transmitting this pulse followed by a transition to ALP Stop state is called the initialization period. The Link shall be configured in such a way that the Slave PHY is powered up and ready before the Master PHY transmits the initialization sequence. The Master PHY itself shall be initialized by a system or protocol layer input signal (PPI). The Master PHY shall ensure that no ALP-01 Lane state with a period longer than  $T_{INIT}$  occurs on the Lane before the Master PHY is initialized. The Slave PHY shall ignore all Lane states during an interval of unspecified length prior to the initialization period. In multi-Lane configurations, all Lanes shall be initialized simultaneously.

When the Slave PHY enters the Init State before the Master PHY, the D<sub>p</sub> and D<sub>n</sub> lines are not driven by the Master PHY. The Slave PHY shall have its differential termination  $Z_{ID}$  enabled until an ALP Wake pulse is observed, to avoid an uncontrolled voltage difference at its receiver input pins, which could cause a false ALP-ED trigger. When the power supply of the Master PHY comes up, its transmitter may temporarily generate a differential voltage glitch on the Lines. Such a voltage glitch shall be limited to below the ALP-ED threshold  $V_{IDTH-ALP}$  in order not to cause a false ALP-ED trigger. The Master PHY shall not use Half Swing mode in the Init State. Prior to collapsing the Master PHY power supply, the system integrator should ensure that the Slave PHY is in the Init State or already powered down to avoid a false ALP-ED trigger.

Note that  $T_{INIT}$  is a protocol-dependent parameter, and thus the exact requirements for  $T_{INIT,MASTER}$  and  $T_{INIT,SLAVE}$  (transmitter and receiver initialization durations, respectively) are defined by the protocol layer specification and are outside the scope of this document. However, the D-PHY specification does place a minimum bound on the lengths of  $T_{INIT,MASTER}$  and  $T_{INIT,SLAVE}$ , which each shall be no less than 100  $\mu$ s. A protocol layer specification using the D-PHY specification may specify any values greater than this limit, for example,  $T_{INIT,MASTER} \geq 1$  ms and  $T_{INIT,SLAVE} = 500$  to 800  $\mu$ s. The Slave PHY shall disable its termination within the allocated  $T_{INIT,SLAVE}$  period.

**Table 21 ALP Initialization States**

State	Entry Conditions	Exit State	Exit Conditions	Line Levels
Master Off	Power-down	Master Initialization	Power-up	Any ALP levels except ones where $V_{DN}-V_{DP} > V_{IDTH-ALP}$ for periods larger than $T_{INIT}$
Master Init	Power-up or protocol request	TX-Stop	An ALP Wake pulse with a period longer than $T_{INIT,MASTER}$ as specified by the protocol layer.	Any signaling sequence that ends with long ALP Wake pulse
Slave Off	Power-down	RX-ULPS	Power-up	Any
Slave Init	Power-up or protocol layer request	RX-Stop	An ALP Wake pulse with a period longer than $T_{INIT,SLAVE}$ as specified by the protocol layer	Any signaling sequence that ends with long ALP Wake pulse



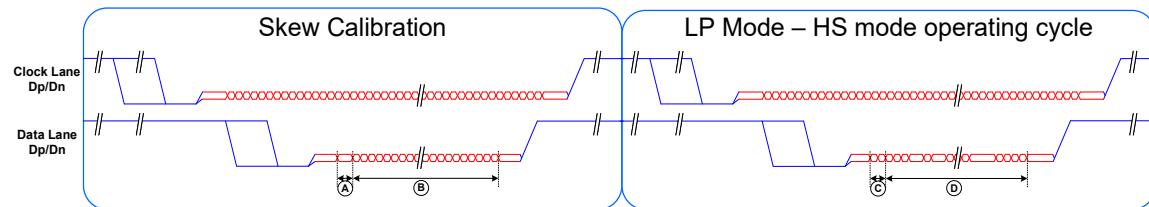
**Figure 33 Example of Initialization Period after Power-Up**

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## 6.12 Skew Calibration

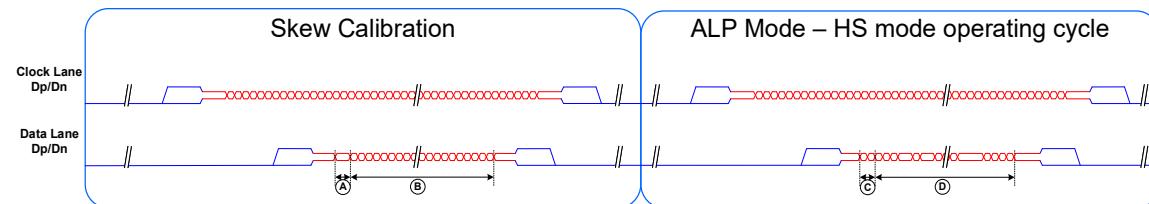
864 Receiver deskew shall be initiated by the transmitter for the DUTs supporting > 1.5 Gbps. The transmitter  
865 shall send a special deskew burst, as shown in **Figure 34** and **Figure 35**. When operating above 1.5 Gbps  
866 or changing to any rate above 1.5 Gbps, an initial deskew sequence shall be transmitted before High-Speed  
867 Data Transmission in normal operation. When operating at or below 1.5 Gbps, the transmission of initial  
868 deskew sequence is optional. Periodic deskew is optional irrespective of data rate.

869 When changing states, for example from ULPS to HS, transmission of any deskew sequence is optional,  
870 provided HS operation resumes at a rate for which an initial deskew sequence has previously been  
871 transmitted.



- A. HS Sync-Sequence for HS Skew-Calibration ('11111111\_11111111')
- B. Same as clock lane ('01010101')  
→ Performs HS Skew-Calibration in RX side
- C. HS Sync-Sequence for normal HS mode ('00011101')
- D. HS payload data

872 **Figure 34 High-Speed Data Transmission in Skew-Calibration, LP Mode**

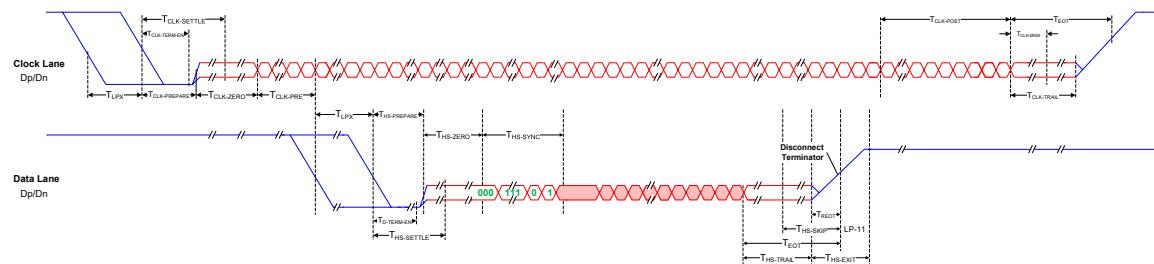


- A. HS Sync-Sequence for HS Skew-Calibration ('11111111\_11111111')
- B. Same as clock lane ('01010101')  
→ Performs HS Skew-Calibration in RX side
- C. HS Sync-Sequence for normal HS mode ('00011101')
- D. HS payload data

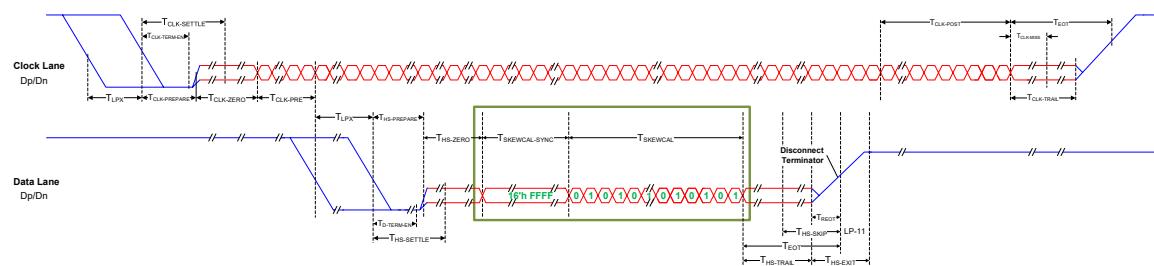
873 **Figure 35 High-Speed Data Transmission in Skew-Calibration, ALP Mode**

874 The transmitter deskew burst shall use a sync pattern consisting of all one's, lasting a duration of 16 UI.  
 875 After the sync pattern is sent, the payload shall be a clock pattern (01010101...) of minimum duration  
 876  $2^{15}$  UI for initial deskew calibration, and of minimum duration  $2^{10}$  UI for periodic calibration. See **Figure**  
 877 **36** and **Figure 37**.

### High-Speed Data Transmission in Normal Mode

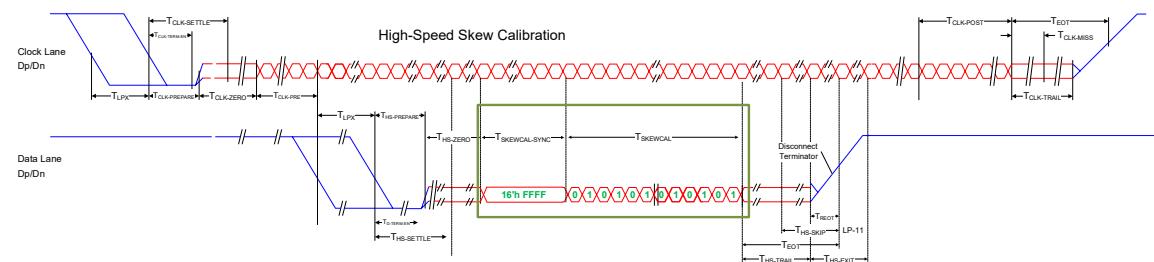
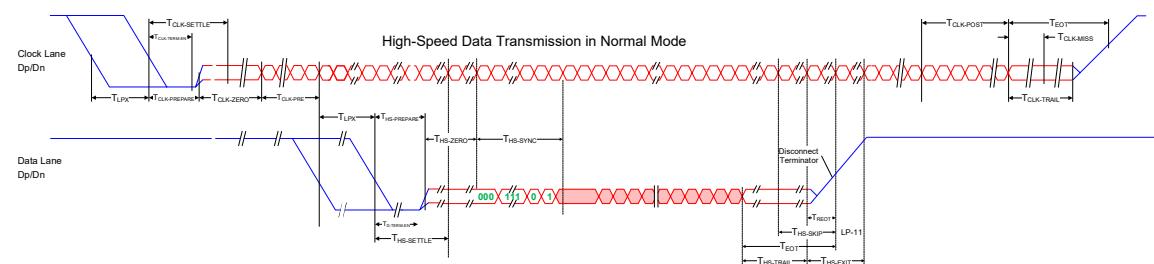


### High-Speed Skew Calibration



878

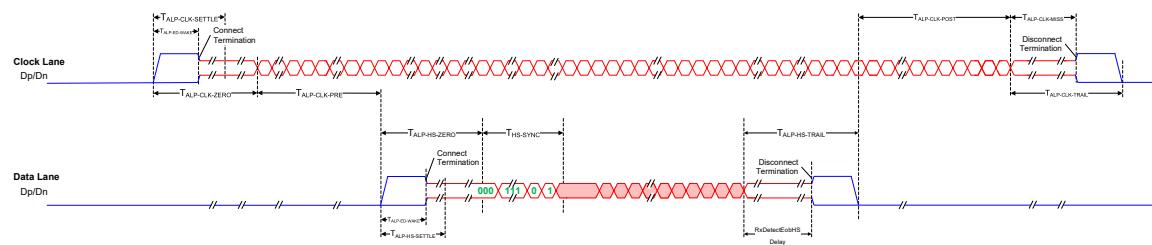
**Figure 36 Normal Mode vs Skew Calibration, LP Mode**



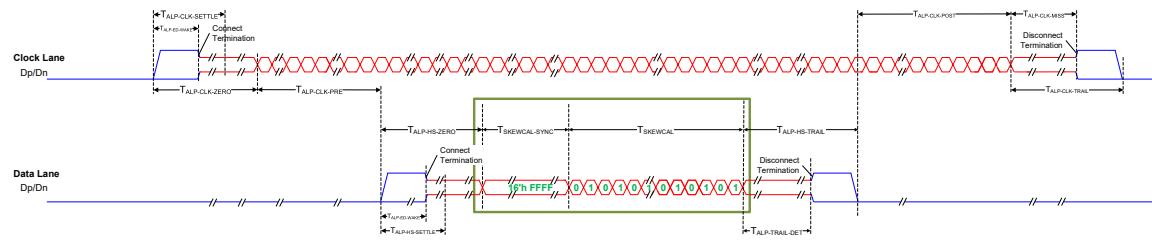
879

**Figure 37 Normal Mode vs Skew Calibration, LP Mode (Zoom-In)**

### High-Speed Data Transmission in Normal Mode



### High-Speed Skew Calibration



**Figure 38 Normal Mode vs Skew Calibration, ALP Mode**

880

881 The receiver shall detect the deskew sync pattern and initiate deskew calibration upon detection. The  
882 transmitter deskew sequence transmission shall be initiated under the transmitter configuration control on  
883 all active lanes simultaneously. The start-of-transmission sequence is described in **Table 22**, and the end-of-  
884 transmission sequence is described in **Table 23** when LP mode is used.

885

**Table 22 Start-of-Skew Calibration Sequence**

<b>TX Side</b>	<b>RX Side</b>
Drives stop state (LP-11)	Observes stop state
Drives HS-Rqst state (LP-01) for time $T_{LPX}$	Observes transition from LP-11 to LP-01 on the lines
Drives bridge state (LP-00) for time $T_{HS-PREPARE}$	Observes transition from LP-01 to LP-00 on the lines, and enables Line termination after time $T_{D\_TERMEN}$
Simultaneously enables high-speed driver and disables low-power drivers	–
Drives HS-0 for a time $T_{HS-ZERO}$	Enables HS-RX and waits for timer $T_{HS-SETTLE}$ to expire in order to neglect transition effects
–	Starts looking for leader sequence
Inserts the high-speed sync sequence for high-speed skew-calibration: '11111111_11111111' beginning on a rising clock edge	–
–	Synchronizes upon recognition of leader sequence: '1111_1111'
Continues to transmit high speed data that is the same as the Clock Lane: '01010101'	–
–	Receives '01010101' data
–	Performs high-speed skew-calibration between clock and data lanes
–	Finishes high-speed skew-calibration between clock and data lanes

886

**Table 23 End-of-Skew Calibration Sequence**

<b>TX Side</b>	<b>RX Side</b>
Completes transmission of '01010101' data	Receives '01010101' data
Toggles differential state immediately after last payload data bit and holds that state for a time $T_{HS-TRAIL}$	–
Disables the HS-TX, enables the LP-TX, and drives the stop state (LP-11) for a time $T_{HS-EXIT}$	Detects the lines leaving LP-00 state and entering the stop state (LP-11), and disables termination
–	Neglects bits of last period $T_{HS-SKIP}$ to hide transition effects
–	Detects last transition of valid data, determines last valid data byte and skip trailer sequence
–	Starts looking for leader sequence

**Note:**

*During skew calibration time, high-speed skew calibration on the RX side has to finish. The TX side is not aware of the RX side completing calibration.*

887 The  $T_{SKEWCAL}$  maximum is 100  $\mu s$  at initial calibration and 10  $\mu s$  maximum for periodic calibration. The  
888 timing parameters are shown in **Table 24**.

889 **Table 24 Skew-Calibration Timing Parameters**

Parameter	Description	Min	Typ	Max	Unit	Notes
$T_{SKEWCAL-SYNC}$	Time that the transmitter drives the skew-calibration sync pattern, $FFFF_H$	–	16	–	UI	–
$T_{SKEWCAL}$	Time that the transmitter drives the skew-calibration pattern in the initial skew-calibration mode	–	–	100	$\mu s$	–
		$2^{15}$	–	–	UI	–
$T_{SKEWCAL}$	Time that the transmitter drives the skew-calibration pattern in the periodic skew-calibration mode	–	–	10	$\mu s$	–
		$2^{10}$	–	–	UI	–

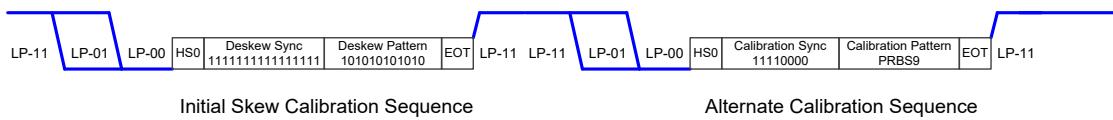
890 For periodic deskew calibration, the transmitter shall finish the current burst before sending a deskew  
891 sequence.

892 During the Receiver deskew calibration, jittered signals are present at the input of the Receiver. The  
893 Receiver deskew block should function properly with Spread Spectrum Clocking in active mode. The intent  
894 of periodic deskew is to fine tune the deskew established by the initial deskew sequence.

## 6.13 Alternate Calibration Sequence

The Alternate Calibration Sequence is intended to compensate for inter-symbol interference. It is used in combination with the Initial Skew Calibration. When operating above 2.5 Gbps, or changing to any data rate above 2.5 Gbps, an Alternate Calibration Sequence consisting of a leading HS0 pattern, a Calibration Sync and a Calibration Pattern shall be transmitted following any Initial Skew Calibration. This calibration is required at Link power up, and/or at Link re-initialization. For transmitters operating at or below 2.5 Gbps, the transmission of the Alternate Calibration Sequence is optional.

The Alternate Calibration Sequence can be disabled by system integrators if the receiver doesn't require or support this feature.



**Figure 39 Initial Calibration Sequence Including Alternate Calibration Sequence with LP Mode**

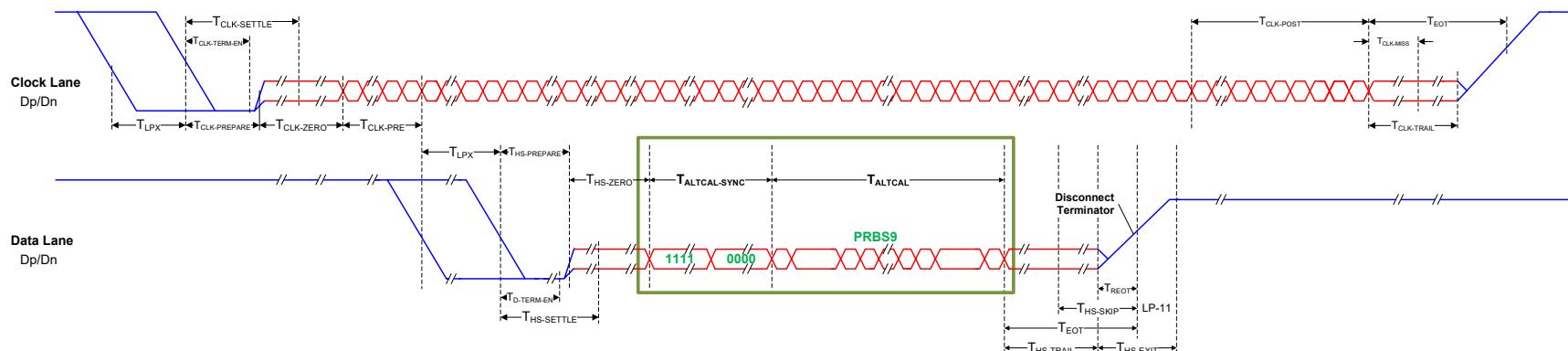
The Alternate Calibration Sequence shall use an Alternate Calibration Sync of duration  $T_{ALTCAL-SYNC}$ . After the Alternate Calibration Sync is sent, the payload shall be a PRBS9 sequence of a minimum duration of  $T_{ALTCAL}$ .

The PRBS9 sequence is defined by the polynomial  $x^0 + x^5 + x^9$ . The PRBS9 sequence generator shall be initialized prior to the Alternate Calibration using an initial 9-bit seed value of 011111111 (Q9:Q1). The first 8-bit word of the payload is the seed value contained in the PRBS9 sequence generator registers Q1 through Q8. The PRBS9 sequence generator is shifted 8 times before each successive 8-bit word is output on Data[7:0]. Data[7:0] is shown in *Annex D*.

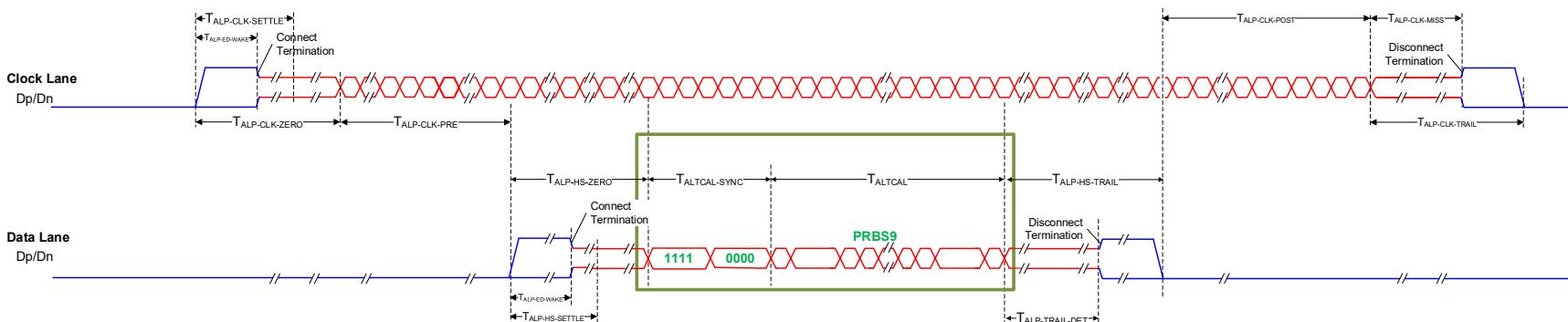
The same polynomial  $x^0 + x^5 + x^9$  also applies for a 16-bit and 32-bit data interface. The PRBS9 sequence generator is shifted 16 or 32 times before each successive 16-bit or 32-bit word is output on Data[15:0] or Data[31:0], respectively.

The PRBS9 sequence generator as shown in *Figure 131* in *Annex D* shall be supported for an 8-bit data interface example.

The order of transmission shall be LSB first. For example, the first two bytes with the initial seed is transmitted as 1111 1111 1000 0011.



**Figure 40 Alternate Calibration Sequence Timing Diagram, LP Mode**



**Figure 41 Alternate Calibration Sequence Timing Diagram, ALP Mode**

**Table 25 Alternate Calibration Timing Parameters**

Parameter	Description	Min	Typ	Max	Unit	Notes
T <sub>ALTCAL-SYNC</sub>	Time that the transmitter drives the Alternate Calibration Sync, 11110000	—	8	—	UI	—
T <sub>ALTCAL</sub>	Time that the transmitter drives the Alternate Calibration Pattern	—	—	100	μs	—
		$2^{15}$	—	—	UI	—

## 6.14 Preamble Sequence

The Preamble Sequence is short in length and inserted at the beginning of every high speed payload with the objective of fine-tuning the clock-to-data skew due to variations in temperature and voltage. The Preamble Sequence is intended for data rates above 2.5 Gbps.

The Preamble Sequence consists of a programmable length Preamble pattern of duration  $T_{PREAMBLE}$ , and a fixed length Extended Sync pattern of duration  $T_{EXTSYNC}$ . The Extended Sync pattern is provided in order to prevent the Preamble pattern from being detected as a Leader sequence in case of certain 2-bit errors.

The Preamble Sequence shall be supported by transmitters and receivers operated above 2.5 Gbps. In this case, the Preamble Sequence shall be inserted in every HS burst when enabled.

Receivers operated above 2.5 Gbps shall detect the Extended Sync pattern and the Leader sequence.

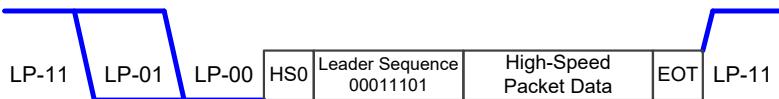
The transmitter shall allow the duration of the Preamble pattern to be programmable within the range of  $T_{PREAMBLE}$ , in steps of 32 UI.

All Preamble patterns shall always be followed by the Extended Sync pattern before transmitting the Leader sequence. The Preamble pattern shall consist of a 1010... pattern of duration  $T_{PREAMBLE}$  per **Table 26**.

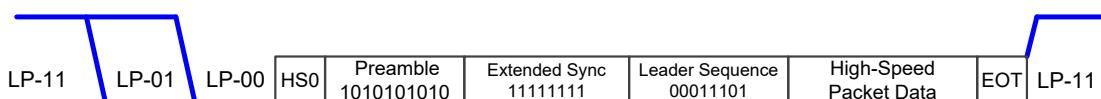
The transmitter Preamble pattern duration shall be configurable by system integrators, and should cover the entire  $T_{PREAMBLE}$  range in **Table 26**, including the option to disable the Preamble and Extended Sync and to transmit only a HS Burst.

A receiver may support only a subset of  $T_{PREAMBLE}$  range which shall be specified in the receiver's datasheet. The Extended Sync pattern shall consist of a HS-1 of duration  $T_{EXTSYNC}$ .

The transmitter shall transmit the Extended Sync pattern for all values of Preamble length.



**Figure 42 Normal High Speed Burst with LP Mode**



**Figure 43 High Speed Burst and Preamble Sequence with LP Mode**

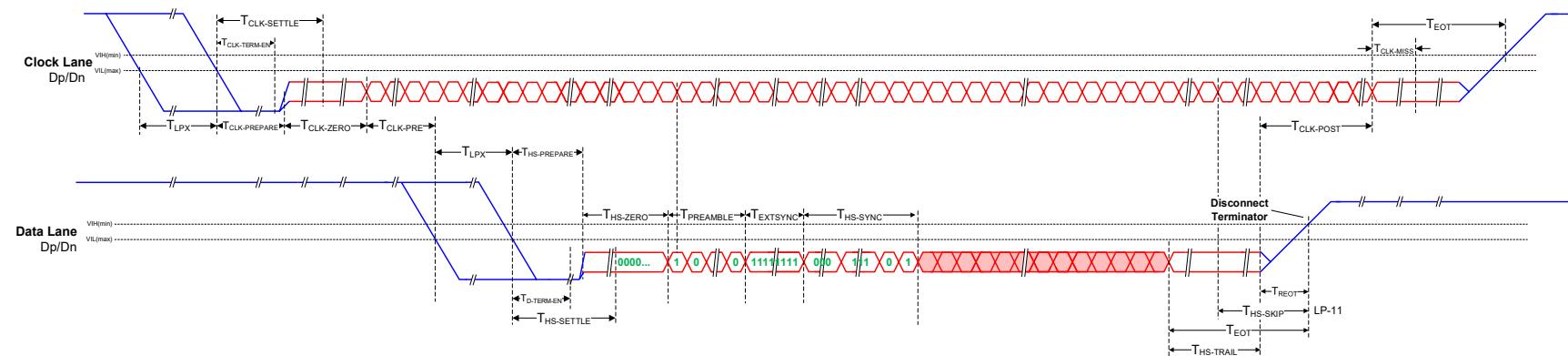


Figure 44 Preamble Timing Diagram (LP Mode)

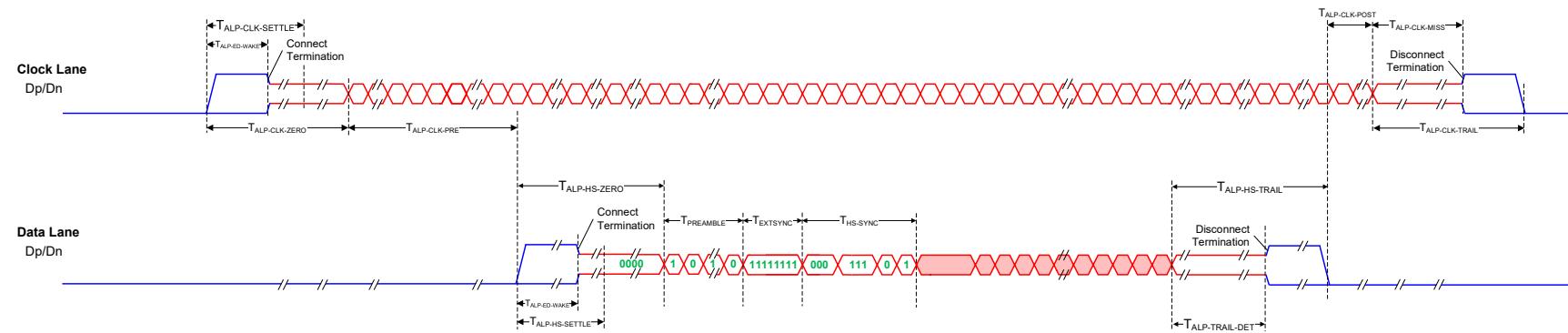


Figure 45 Preamble Timing Diagram (ALP Mode)

Table 26 Preamble Timing Parameters

Parameter	Description	Min	Typ	Max	Unit	Notes
$T_{PREAMBLE}$	Time the Preamble pattern of 1010 is transmitted	32	32	512	UI	Programmable in steps of 32 UI
$T_{EXTSYNC}$	Time the Extended Sync pattern of HS-1 is transmitted.	—	8	—	UI	—

## 6.15 HS-Idle State

Support for the HS-Idle State is optional for a PHY in LP mode - HS mode operation cycles. There is no HS-Idle State support when using ALP mode. The HS-Idle state may be used between two HS Data Bursts while remaining in HS signaling. When the HS-Idle state is used, there is no transition to LP signaling between two HS Data Bursts. The latency between two HS Data Bursts can be decreased by using the HS-Idle State, depending on the data rate and the HS-Idle timings. The HS-Idle State comprises the HS-Idle-Post, the HS-Idle-ClkHS0, and the HS-Idle-Pre sub-states, as shown in the state diagram in **Figure 47**. A PHY can either enter HS-Idle State, or enter LP Stop State, for all its Data Lanes.

In the HS-Idle State, the Clock Lane shall stop in an HS-0 state after all Data Lanes have completed their Data Bursts and have transitioned to HS-0 states. HS-0 for the Clock Lane and for the Data Lanes in HS-Idle State shall be generated by the PHY. After the payload data is transmitted all Data Lanes shall signal an HS-0, irrespective of the polarity of the last payload bit. The RX state machine shall transition to the HS-Idle state if the Clock Lane receiver detects no clock activity for a period of  $T_{CLK-MISS}$  and all Data Lanes are in HS-0. The RX state machine shall transition to the Stop state when all the Data Lanes are in LP-11.

The state transitions for the HS-Idle State are described in **Table 28**. This table starts with the last bit of an HS Data Burst before transitioning in and out of the HS-Idle State. **Table 28** concludes with the first bits of an HS Data Burst after exit of the HS-Idle State.

The Clock Lane shall continue signaling for  $T_{HS-IDLE-POST}$  after the HS Data Bursts are completed on all Lanes, in order to allow enough time to flush the receiver pipelines.

The HS-0 state on the Clock Lane shall be driven for a duration of  $T_{HS-IDLE-CLKHS0}$ .

The Clock Lane shall be active for a duration of  $T_{HS-IDLE-PRE}$  before the next HS Data Burst.

The HS-Idle state shall exit to SoT. The start and end of the  $T_{HS-IDLE-POST}$ ,  $T_{HS-IDLE-CLKHS0}$ , and  $T_{HS-IDLE-PRE}$  timing parameters is shown in **Figure 46**. The values of these timing parameters are defined in **Table 27**. A transmitter shall support the default timing values at start-up. A system integrator may configure HS-Idle State parameters to different values, based on the receiver capability.

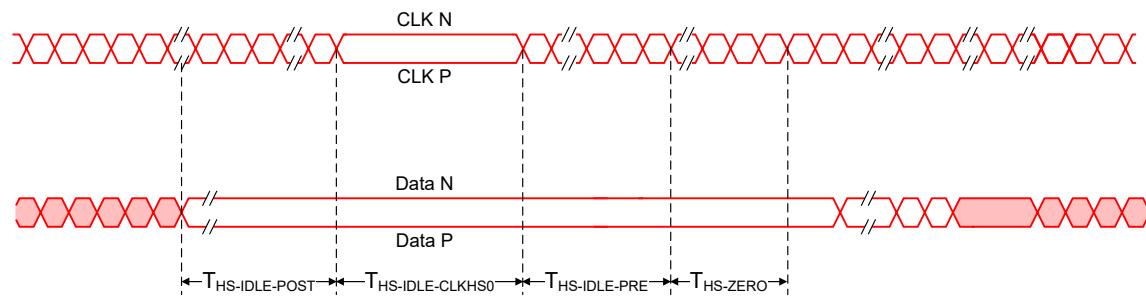
A receiver employing duty cycle correction mechanisms on a Lane may need special considerations to handle the idle periods when the optional HS-Idle state is supported.

**Table 27 HS-Idle State Timing Parameters**

Timing	Min	Default	Max	Notes
$T_{HS-IDLE-POST}$	$n^*8 \text{ UI}$	256 UI	512 UI	1
$T_{HS-IDLE-CLKHS0}$	60 ns	60 ns	500 ns	2
$T_{HS-IDLE-PRE}$	$n^*8 \text{ UI}$	32 UI	96 UI	1

**Note:**

1. Transmitter shall support programmability in  $n^*8 \text{ UI}$  steps from min to max. If PPI is used, then  $n$  is the TX PPI bus width in bytes; if PPI is not used, then  $n$  is implementation specific. The system integrator shall have access to program these parameters as per the application need.
2. For long HS-Idle state, where latency is not a limitation, legacy LP mode provides a more optimal power solution.



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**Figure 46 HS-Idle Timing Diagram Example**

**Table 28 HS-Idle State Machine Description**

Data Lane State	Data Line Condition/State	Data Lane Exit State	Data Lane Exit Conditions	Clock Lane Condition	Clock Lane Exit Condition
TX-HS-0	Transmit HS-0	TX-HS-0	Send HS-0 TxHSIdleClkHS is high level	Toggling	–
TX-HS-1	Transmit HS-1	TX-HS-0	Send HS-0 TxHSIdleClkHS is high level	Toggling	–
HS-IDLE-POST	Transmit HS-0	TX-HS-0	Send TX-HS-0 for $T_{HS-IDLE-POST}$	Toggling	Send HS-0 when TxHSIdleClkHS is high level
HS-IDLE-CLKHS0	Transmit HS-0	TX-HS-0	Send TX-HS-0 for $T_{HS-IDLE-CLKHS0}$	Transmit HS-0	Start toggling when TxHSIdleClkHS is low level and TxHSIdleClkReadyHS is high level
HS-IDLE-PRE	Transmit HS-0	SOT HS-0	Send TX-HS-0 for $T_{HS-IDLE-PRE}$	Toggling	–
SOT HS-0	Transmit HS-0	TX-HS-Sync	Send TX-HS-0 for $T_{HS-ZERO}$	Toggling	–
Tx-HS-Sync	Transmit Leader sequence HS-00011101	TX-HS-0	Send HS-0 bit as first bit of payload	Toggling	–
–	–	TX-HS-1	Send HS-1 bit as first bit of payload	–	–
TX-HS-0	Transmit HS-0	TX-HS-0	Send another HS-0 bit after a HS-0 bit	Toggling	–
–	–	TX-HS-1	Send a HS-1 bit after a HS-0 bit	Toggling	–
TX-HS-1	Transmit HS-1	TX-HS-1	Send a HS-1 bit	Toggling	–
–	–	TX-HS-0	Send another HS-0 bit after a HS-1 bit	Toggling	–
RX-HS-0	Receive HS-0	RX-HS-0	Receive HS-0 in HS-Idle-Post	–	–
RX-HS-1	Receive HS-1	RX-HS-0	Receive HS-0 in HS-Idle Post	–	–
HS-IDLE-POST	Receive HS-0	RX-HS-0	End of timed interval $T_{HS-IDLE-POST}$	Toggling	Receive HS-0 (clock miss)
HS-IDLE-CLKHS0	Receive HS-0	RX-HS-0	End of timed interval $T_{HS-IDLE-CLKHS0}$	Receive HS-0	Receive toggling clock

Data Lane State	Data Line Condition/State	Data Lane Exit State	Data Lane Exit Conditions	Clock Lane Condition	Clock Lane Exit Condition
HS-IDLE-PRE	Receive HS-0	SOT HS-0	End of timed interval $T_{HS-IDLE-PRE}$	Toggling	–
SOT HS-0	Receive HS-0	RX-HS-Sync	End of timed interval $T_{HS-ZERO}$	Toggling	–
RX-HS-Sync	Receive Leader sequence HS-00011101	RX-HS-0	Receive payload data bit	Toggling	–
–	–	RX-HS-1	Receive payload data bit	–	–
RX-HS-0	Receive HS-0	RX-HS-0	Receive payload data bit	Toggling	–
–	–	RX-HS-1	Receive payload data bit	Toggling	–
RX-HS-1	Receive HS-1	RX-HS-1	Receive payload data bit	Toggling	–
–	–	RX-HS-0	Receive payload data bit	Toggling	–

## 6.16 Sync Patterns

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*Table 29* lists all of the Sync Patterns, and the targeted usage for each one.

**Table 29 Sync Pattern Definition**

Sync Patterns	Usage	Note
00011101	High Speed Data	–
10010010	Alternate Low-Power mode Control Burst	1
1111111111111111	Skew Calibration	–
11110000	Alternate Calibration	–
1111111100011101	High Speed Data when preamble is enabled	–

**Note:**

1. *Usage might be extended in the future.*

## 6.17 Global Operation Flow Diagram

All previously described aspects of operation, either including or excluding optional parts, are contained in Lane Modules. **Figure 47** shows the operational flow diagram for a Data Lane Module. Within both TX and RX five main processes can be distinguished: High-Speed Transmission, LP mode, ALP mode, Calibration, and Initialization.

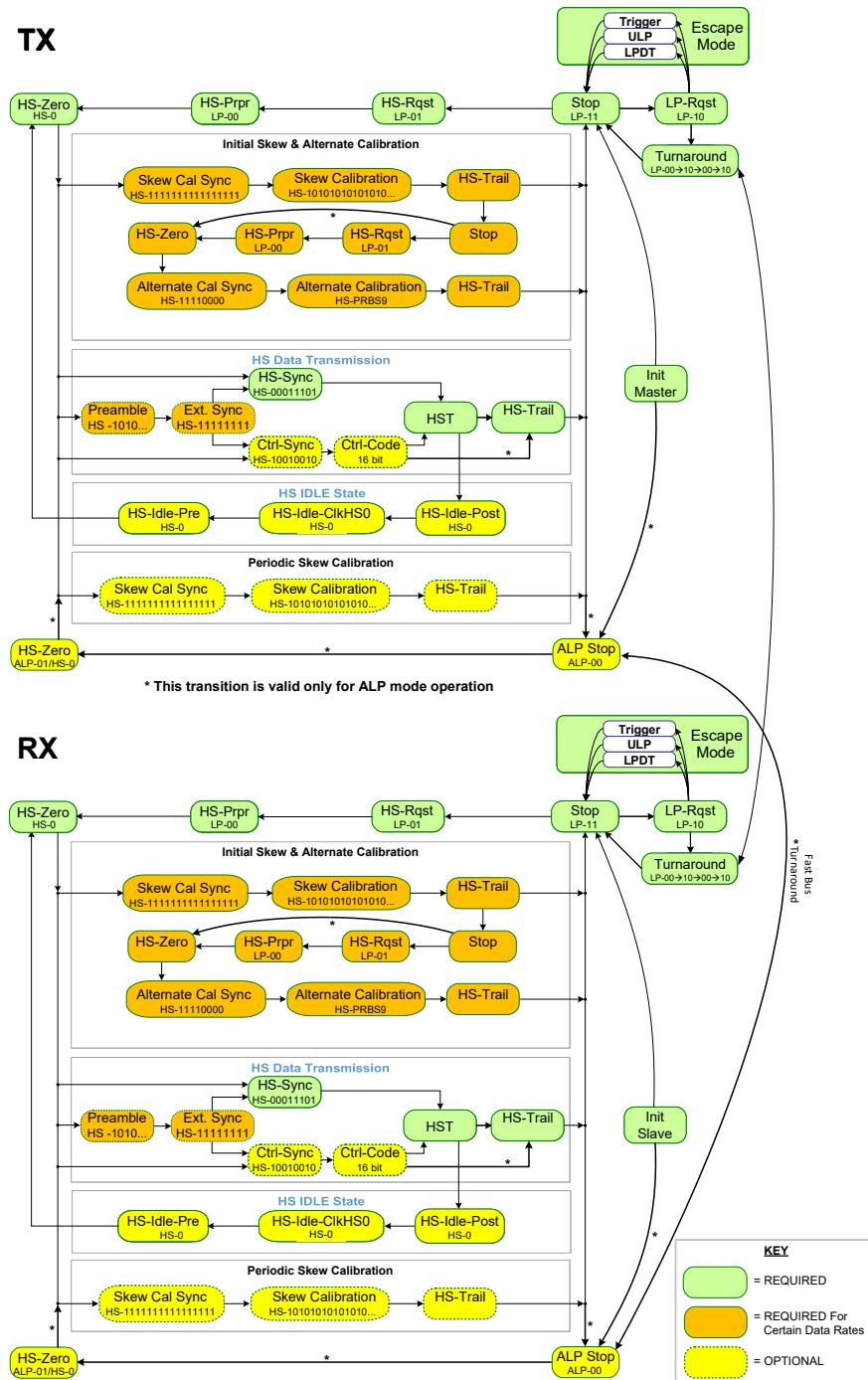
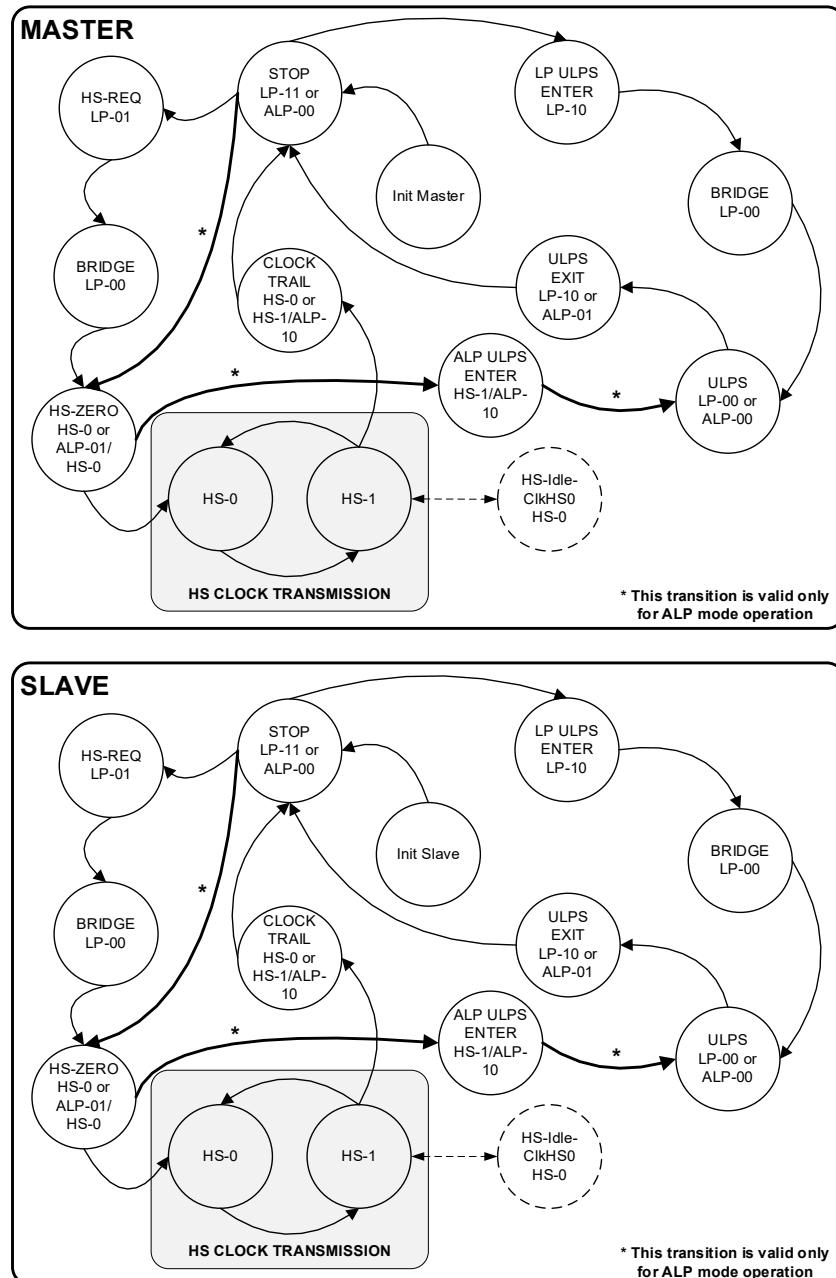


Figure 47 Data Lane Module State Diagram

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984  
985 **Figure 48** shows the state diagram for a Clock Lane Module. The Clock Lane Module has four major operational states: Init (of unspecified duration), Low-Power Stop state, Ultra-Low Power state, and High-Speed clock transmission. The Figure also shows the transition states as described previously.



**Figure 48 Clock Lane Module State Diagram**

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## 6.18 Data Rate Dependent Parameters (Informative)

The high speed data transfer rate of the D-PHY may be programmable to values determined by a particular implementation. Any individual data transfer between SoT and EoT sequences must take place at a given, fixed rate. However, reprogramming the data rate of the D-PHY high speed transfer is allowed at initialization, before starting the exit from ULP state or in Stop state whenever the HS clock is not running. The method of data rate reprogramming is out of the scope of this document.

Many time parameter values in this document are specified as the sum of a fixed time and a particular number of High-Speed UIs. The parameters may need to be recomputed if the data rate, and therefore the UI value, is changed. These parameters, with their allowed values, are listed in *Table 18* and *Table 19*. For clarity, the parameter names and purposes are repeated here.

### 6.18.1 Parameters Containing Only UI Values

$T_{CLK-PRE}$  and  $T_{ALP-CLK-PRE}$  are the minimum number of High-Speed clock cycles the Master must send over the Clock Lane after it is restarted in HS mode and before any data transmission may begin. If a particular protocol at the Slave side requires more clock cycles than  $T_{CLK-PRE}$  or  $T_{ALP-CLK-PRE}$ , the Master side protocol should ensure that these are transmitted.

### 6.18.2 Parameters Containing Time and UI values

Several parameters are specified as the sum of an explicit time and a number of UI. The explicit time values, in general, are derived from the time needed to charge and discharge the interconnect to its specified values given the specified drive voltages and Line termination values. As such, the explicit time values are not data rate dependent. It is conceivable to use the sum of an analog timer and a HS clock counter to ensure the implementation satisfies these parameters. If these explicit time values are implemented by counting HS clock cycles only, the count value is a function of the data rate and, therefore, must be changed when the data rate is changed.

$T_{D-TERM-EN}$  is the time to enable Data Lane receiver Line termination measured from when  $D_n$  crosses  $V_{IL,MAX}$ .

$T_{HS-PREPARE}$ , is the time to drive LP-00 before starting the HS transmission on a Data Lane.

$T_{HS-PREPARE} + T_{HS-ZERO,MIN}$  is the sum of the time to drive LP-00 in preparation for the start of HS transmission plus the time to send HS-0, i.e. turn on the Line termination and drive the interconnect with the HS driver, prior to sending the SoT Sync sequence.

$T_{HS-TRAIL}$  is the time the transmitter must drive the flipped last data bit after sending the last payload data bit of a HS transmission burst. This time is required by the receiver to determine EoT.

$T_{HS-SKIP}$  is the time the receiver must “back up” and skip data to ignore the transition period of the EoT sequence.

$T_{CLK-POST,MIN}$  is the minimum time that the transmitter continues sending HS clocks after the last Data Lane has transitioned to LP mode following a HS transmission burst. If a particular receiver implementation requires more clock cycles than  $T_{CLK-POST,MIN}$  to finish reception, the transmitter must supply sufficient clocks to accomplish the reception.

For ALP operation similar parameters exist:  $T_{ALP-HS-ZERO}$ ,  $T_{ALP-HS-TRAIL}$ , and  $T_{ALP-CLK-POST}$ . Additionally, new parameters are introduced whose timing has both absolute and relative components:  $T_{ALP-HS-SETTLE,MIN}$ ,  $T_{ALP-TRAIL-DET}$ ,  $T_{ALP-TA-GO}$ ,  $T_{ALP-TA-SURE}$ , and  $T_{ALP-TA-GET}$ .

### 6.18.3 Parameters Containing Only Time Values

Several parameters are specified only as explicit time values. As in *Section 6.18.2*, these explicit time values are typically derived from the time needed to charge and discharge the interconnect and are, therefore, not data rate dependent. It is conceivable to use an analog timer or a HS clock counter to ensure the implementation satisfies these parameters. However, if these time values are implemented by counting HS clock cycles only, the count value is a function of the data rate and, therefore, must be changed when the data rate is changed.

The following parameters are based on time values alone:

- $T_{HS\text{-}SKIP,MIN}$
- $T_{CLK\text{-}MISS,MAX}$
- $T_{CLK\text{-}TRAIL,MIN}$
- $T_{CLK\text{-}TERM-EN}$
- $T_{CLK\text{-}PREPARE}$
- $T_{ALP\text{-}CLK\text{-}MISS,MAX}$
- $T_{ALP\text{-}CLK\text{-}SETTLE}$
- $T_{ALP\text{-}CLK\text{-}TRAIL,MIN}$
- $T_{ALP\text{-}CLK\text{-}ZERO,MIN}$
- $T_{ALP\text{-}ED\text{-}WAKE,MAX}$
- $T_{ALP\text{-}HS\text{-}SETTLE,MIN}$

### 6.18.4 Parameters Containing Only Time Values That Are Not Data Rate Dependent

The remaining parameters in *Table 18* shall be complied with even when the High-Speed clock is off. These parameters include Low-Power and initialization state durations and LP signaling intervals. Though these parameters are not HS data rate dependent, some implementations of D-PHY may need to adjust these values when the data rate is changed.

## 6.19 Interoperability

**Table 30** summarizes integration and downward compatibility for all possible combinations of the Tx's D-PHY Specification version and the Rx's D-PHY Specification version. The table shows the maximum operating speed for each possible combination, and indicates the combinations that require deskew initialization. For example, a D-PHY v2.0 Tx and a D-PHY v1.2 Rx are compatible for speeds up to 1.5 Gbps without deskew initialization, and speeds above 1.5 Gbps if deskew initialization is used.

**Table 30 D-PHY Version Integration and Downward Compatibility**

		Rx D-PHY Specification Version													
		D-PHY v3.0		D-PHY v2.5		D-PHY v2.1		D-PHY v2.0		D-PHY v1.2		D-PHY v1.1		D-PHY v1.0	
Tx D-PHY Specification Version	D-PHY v1.0	Max Speed (Gbps)	Deskew Initialization	D-PHY v1.1	Max Speed (Gbps)	Deskew Initialization	D-PHY v1.2	Max Speed (Gbps)	Deskew Initialization	D-PHY v2.0	Max Speed (Gbps)	Deskew Initialization	D-PHY v2.1	Max Speed (Gbps)	Deskew Initialization
	D-PHY v1.1	1.0	–	1.0	–	1.0	–	1.0	–	1.0	–	1.0	–	1.0	–
	D-PHY v1.2	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.0	–
	D-PHY v2.0	2.5	Yes	2.5	Yes	2.5	Yes	2.5	Yes	2.5	Yes	2.5	Yes	1.5	–
	D-PHY v2.1	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.0	–
	D-PHY v2.5	4.5	Yes	4.5	Yes	4.5	Yes	4.5	Yes	2.5	Yes	2.5	Yes	1.5	–
	D-PHY v3.0	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.0	–
	D-PHY v2.0	4.5	Yes	4.5	Yes	4.5	Yes	4.5	Yes	2.5	Yes	2.5	Yes	1.5	–
	D-PHY v2.1	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.5	–	1.0	–
	D-PHY v2.5	4.5	Yes	4.5	Yes	4.5	Yes	4.5	Yes	2.5	Yes	2.5	Yes	1.5	–

**Note:**

Cells containing dashes (‘–’) indicate that Deskew Initialization is not required

A D-PHY v2.0 physical layer transmitter is compatible with a D-PHY v2.1 physical layer receiver, and vice versa. A D-PHY v2.0 transmitter may operate in conjunction with a D-PHY v2.1 receiver, but such a transmitter is incapable of sending a D-PHY 2.1 Alternate Calibration Sequence or Preamble Sequence plus Extended Sync pattern to the receiver. Similarly, a D-PHY v2.1 transmitter may operate in conjunction with a D-PHY v2.0 receiver by ensuring that the D-PHY v2.1 Alternate Calibration Sequence and Preamble Sequence plus Extended Sync pattern are disabled in the transmitter.

The D-PHY v2.1 Alternate Calibration Sequence and Preamble Sequence plus Extended Sync pattern are supported by D-PHY v2.1 transmitters and receivers operated above 2.5 Gbps. When enabled, the Alternate Calibration Sequence is transmitted following any Initial Skew Calibration, and the Preamble Sequence followed by the Extended Sync pattern is inserted in every HS burst. These features allow the system to more robustly compensate for variations such as temperature and voltage when operating at bit rates above 2.5 Gbps. Whether these features are enabled is therefore use-case dependent and, in any event, they cannot be enabled when a D-PHY v2.0 transmitter or receiver is present.

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## 7 Fault Detection

There are three different mechanisms to detect malfunctioning of the Link. Bus contention and error detection functions are contained within the D-PHY. These functions should detect many typical faults. However, some faults cannot be detected within the D-PHY and require a protocol-level solution. Therefore, the third detection mechanism is a set of application specific watchdog timers.

### 7.1 Contention Detection

If a Bi-directional Lane Module and a Unidirectional Module are combined in one Lane, only Unidirectional functionality is available. Because in this case the additional functionality of one Bi-directional PHY Module cannot be reliably controlled from the limited functionality PHY side, the Bi-directional features of the Bi-directional Module shall be safely disabled. Otherwise in some cases deadlock may occur which can only be resolved with a system power-down and re-initialization procedure.

During normal operation one and only one side of a Link shall drive a Lane at any given time except for certain transition periods. Due to errors or system malfunction a Lane may end up in an undesirable state, where the Lane is driven from two sides or not driven at all. This condition eventually results in a state conflict and is called Contention.

All Lane Modules with LP Bi-directionality shall include contention detection functions to detect the following contention conditions:

- Modules on both sides of the same Line drive opposite LP levels against each other. In this case, the Line voltage will settle to some value between  $V_{OL,MIN}$  and  $V_{OH,MAX}$ . Because  $V_{IL}$  is greater than  $V_{IHCD}$ , the settled value will always be either higher than  $V_{IHCD}$ , lower than  $V_{IL}$ , or both. Refer to **Section 8**. This ensures that at least one side of the Link, possibly both, will detect the fault condition.
- The Module at one side drives LP-high while the other side drives HS-low on the same Line. In this case, the Line voltage will settle to a value lower than  $V_{IL}$ . The contention shall be detected at the side that is transmitting the LP-high.

The first condition can be detected by the combination of LP-CD and LP-RX functions. The LP-RX function should be able to detect the second contention condition. Details on the LP-CD and LP-RX electrical specifications can be found in **Section 9**. Except when the previous state was TX-ULPS, contention shall be checked before the transition to a new state. Contention detection in ULPS is not required because the bit period is not defined and a clock might not be available.

After contention has been detected, the Protocol shall take proper measures to resolve the situation. No contention detection mechanism exists in ALP mode.

## 7.2 Sequence Error Detection

If for any reason the Lane signal is corrupted the receiving PHY may detect signal sequence errors. Errors detected inside the PHY may be communicated to the Protocol via the PPI. This kind of error detection is optional, but strongly recommended as it enhances reliability. The following sequence errors can be distinguished:

- SoT Error
- SoT Sync Error
- EoT Sync Error
- Escape Entry Command Error
- LP Transmission Sync Error
- False Control Error

### 7.2.1 SoT Error

When deskew is not supported, the Leader sequence for Start of High-Speed Transmission is fault tolerant for any single-bit error and some multi-bit errors. Therefore the synchronization may be usable, but confidence in the payload data is lower. If this situation occurs, then an SoT Error is indicated.

When deskew is supported, bit errors are not tolerated in the Leader sequence. If there is an error in the Leader sequence, then the payload data is not reliable.

The exact sequences that cause the SoT Error are beyond the scope of this document.

### 7.2.2 SoT Sync Error

If the SoT Leader sequence is corrupted in a way that proper synchronization cannot be expected, a SoT Sync Error is indicated. The exact sequences that cause the SoT Sync Error are beyond the scope of this document.

### 7.2.3 EoT Sync Error

The EoT Sync Error is indicated when the last bit of a transmission does not match a byte boundary. This error can only be indicated in case of EoT processing on detection of LP-11.

### 7.2.4 Escape Mode Entry Command Error

If the receiving Lane Module does not recognize the received Entry Command for Escape Mode an Escape Mode Entry Command Error is indicated.

### 7.2.5 LP Transmission Sync Error

At the end of a Low-Power Data transmission procedure, if data is not synchronized to a Byte boundary an Escape Sync Error signal is indicated.

### 7.2.6 False Control Error

If a LP-Rqst (LP-10) is not followed by the remainder of a valid Escape or Turnaround sequence, a False Control Error is indicated. This error is also indicated if a HS-Rqst (LP-01) is not correctly followed by a Bridge State (LP-00).

For a Fast Lane Turnaround procedure, a False Control Error is generated if the Fast-BTA Control Code is not followed by an HS-Trail sequence.

## 7.3 Protocol Watchdog Timers (Informative)

It is not possible for the PHY to detect all fault cases. Therefore, additional protocol-level time-out mechanisms are necessary in order to limit the maximum duration of certain modes and states.

### 7.3.1 HS RX Timeout

In HS RX mode if no EoT is received within a certain period the protocol should time-out. The timeout period can be protocol specific.

### 7.3.2 HS TX Timeout

The maximum transmission length in HS TX is bounded. The timeout period is protocol specific.

### 7.3.3 Escape Mode Timeout

A device may timeout during Escape Mode. The timeout should be greater than the Escape Mode Silence Limit of the other device. The timeout period is protocol specific.

### 7.3.4 Escape Mode Silence Timeout

A device may have a bounded length for LP TX-00 during Escape Mode, after which the other device may timeout. The timeout period is protocol specific. For example, a display module should have an Escape Mode Silence Limit, after which the host processor can timeout.

### 7.3.5 Turnaround Errors

#### 7.3.5.1 Control Mode Lane Turnaround Errors

A Turnaround procedure always starts from a Stop State. The procedure begins with a sequence of Low-Power States ending with a Bridge State (LP-00) during which drive sides are swapped. The procedure is finalized by the response including a Turn State followed by a Stop State driven from the other side. If the actual sequence of events violates the normal Control Lane Mode Turnaround procedure a “False Control Error” may be flagged to the Protocol. See [Section 7.2.6](#). The Turn State response serves as an acknowledgement for the correctly completed Control Lane Mode Turnaround procedure. If no acknowledgement is observed within a certain time period the Protocol should time-out and take appropriate action. This period should be larger than the maximum possible Turnaround time for a particular system. There is no time-out for this condition in the PHY.

#### 7.3.5.2 Fast Lane Turnaround Errors

A Fast Lane Turnaround procedure always starts from an ALP Stop state. The procedure begins with the transmission of a Control Burst carrying the Fast-BTA Control Code followed by a transition to ALP-00 after the HS-Trail period is completed during which drive sides are swapped. The procedure is finalized by a response driven from the other side which usually will consist of an acknowledgement packet sent by the remote controller. If the actual sequence of events violates the normal Fast Lane Turnaround procedure then a “False Control Error” may be flagged to the protocol layer. See [Section 7.2.6](#). The Turn State response serves as an acknowledgement for the correctly completed Fast Lane Turnaround procedure. If no acknowledgement is observed within a certain time period then the protocol layer should time-out and take appropriate action. This period should be larger than the maximum possible Turnaround time for a particular system. There is no time-out for this condition in the PHY.

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## 8 Interconnect and Lane Configuration

The interconnect between transmitter and receiver carries all signals used in D-PHY communication. This includes both high speed, low voltage signaling I/O technology and low speed, low power signaling for control functions. For this reason, the physical connection shall be implemented by means of balanced, differential, point-to-point transmission lines referenced to ground. The total interconnect may consist of several cascaded transmission Line segments, such as, printed circuit boards, flex-foils, and cable connections.

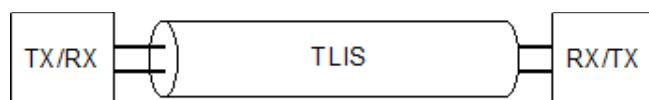


Figure 49 Point-to-point Interconnect

### 8.1 Lane Configuration

The complete physical connection of a Lane consists of a transmitter (TX), and/or receiver (RX) at each side, with some Transmission-Line-Interconnect-Structure (TLIS) in between. The overall Lane performance is therefore determined by the combination of these three elements. The split between these elements is defined to be on the module (IC) pins. This Section defines both the required performance of the Transmission-Line-Interconnect-Structure for the signal routing as well as the I/O-cell Reflection properties of TX and RX. This way the correct overall operation of the Lane can be ensured.

With respect to physical dimensions, the Transmission-Line-Interconnect-Structure will typically be the largest part. Besides printed circuit board and flex-foil traces, this may also include elements such as vias and connectors.

### 8.2 Boundary Conditions

The reference characteristic impedance level is  $100\ \Omega$  differential,  $50\ \Omega$  single-ended per Line, and  $25\ \Omega$  common-mode for both Lines together. The  $50\ \Omega$  impedance level for single-ended operation is also convenient for test and characterization purposes.

This typical impedance level is required for all three parts of the Lane: TX, TLIS, and RX. The tolerances for characteristic impedances of the interconnect and the tolerance on Line termination impedances for TX and RX are specified by means of S-parameter templates over the whole operating frequency range.

The differential channel is also used for LP single-ended signaling. Therefore, it is strongly recommended to apply only very loosely coupled differential transmission lines.

The flight time for signals across the interconnect shall not exceed two nanoseconds.

### 8.3 Definitions

The frequency 'fh' is the fundamental frequency of the operating data rate, e.g. for an operating data rate of 1 Gb/s 'fh' is 500 MHz.

The frequency 'fh<sub>MAX</sub>' is a device specification and indicates the maximum supported fh for a particular device.

The frequency 'f<sub>LP,MAX</sub>' is the maximum toggle frequency for Low-Power mode.

RF interference frequencies are denoted by 'f<sub>INT</sub>', where f<sub>INT,MIN</sub> defines the lower bound for the band of relevant RF interferers.

The frequency f<sub>MAX</sub> for devices supporting data rates up to 1.5 Gbps is defined by the maximum of (1/5t<sub>F,MIN</sub>, 1/5t<sub>R,MIN</sub>), where t<sub>R</sub> and t<sub>F</sub> are the rise and fall times of the High-Speed signaling.

For devices supporting data rates of more than 1.5 Gbps, f<sub>MAX</sub> is  $\frac{3}{4} * \text{data rate}$ .

The frequency 'fh<sub>MIN</sub>' is defined as fh<sub>MIN</sub> = fh/10.

## 8.4 S-parameter Specifications

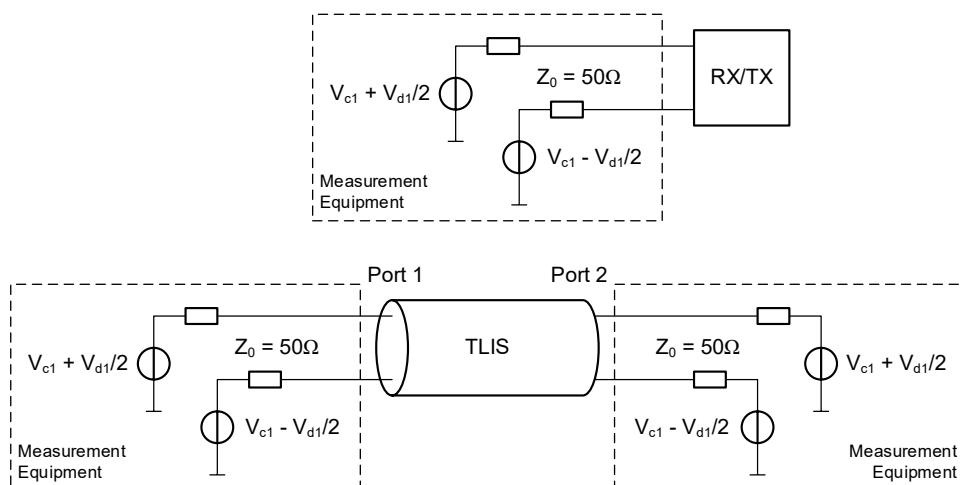
The required performance of the physical connection is specified by means of S-parameter requirements for TX, TLIS, and RX, for TLIS by mixed-mode, 4-port parameters, and for RX and TX by mixed-mode, reflection (return loss) parameters. The S-parameter limits are defined over the whole operating frequency range by means of templates.

The differential transmission properties are most relevant and therefore this specification uses mixed-mode parameters. As the performance needs depend on the targeted bit rates, most S-parameter requirements are specified on a normalized frequency axis with respect to bit rate. Only the parameters that are important for the suppression of external (RF) interference are specified on an absolute frequency scale. This scale extends up to  $f_{MAX}$ . Beyond this frequency the circuitry itself shall suppress the high-frequency interference signals sufficiently.

Only the overall performance of the TLIS and the maximum reflection of RX and TX are specified. This fully specifies the signal behavior at the RX/TX-module pins. The subdivision of losses, reflections and mode-conversion budget to individual physical fractions of the TLIS is left to the system designer. Annex B includes some rules of thumb for system design and signal routing guidelines.

## 8.5 Characterization Conditions

All S-parameter definitions are based on a  $50 \Omega$  impedance reference level. The characterization can be done with a measurement system, as shown in **Figure 50**.



**Figure 50 Set-up for S-parameter Characterization of RX, TX and TLIS**

The syntax of S-parameters is  $S[\text{measured-mode}][\text{driven-mode}][\text{measured-port}][\text{driven-port}]$ . Examples:  $Sdd21$  of TLIS is the differential signal at port 2 due to a differential signal driven at port 1;  $Sdc22$  is the measured differential reflected signal at port 2 due to a common signal driven at port 2.

## 8.6 Interconnect Specifications

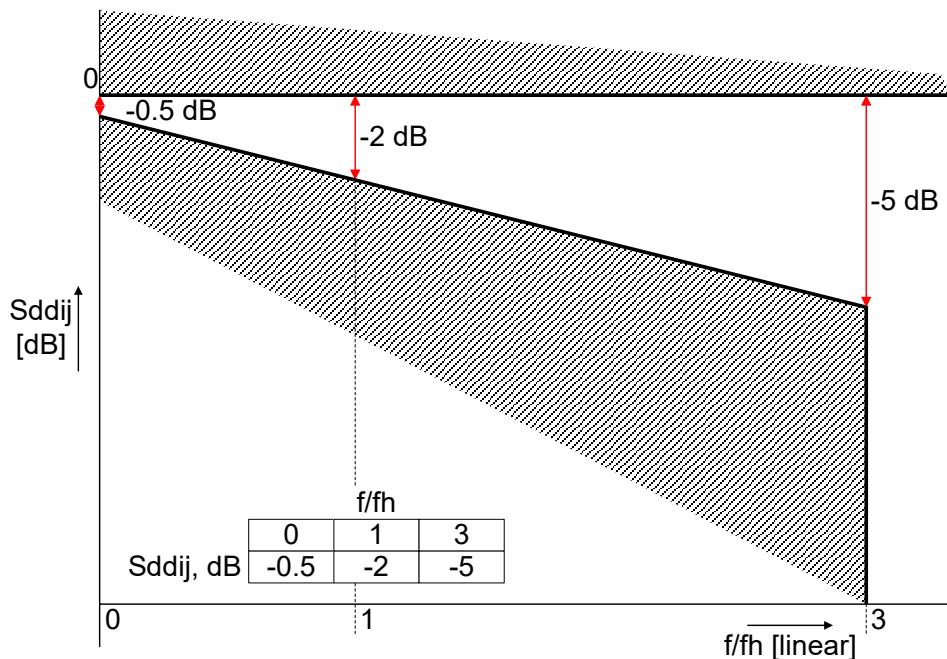
The Transmission-Line Signal-Routing (TLSR) is specified by means of mixed-mode 4-port S-parameter behavior templates over the frequency range. This includes the differential and common-mode, insertion and return losses, and mode-conversion limitations.

The interconnect specifications are applicable for both mobile applications and IoT applications. It is common for IoT applications to have longer interconnect lengths between the Master and Slave devices. For longer interconnect lengths, the use of low-loss dielectric materials should be considered to meet the parametric limits of the interconnect characteristics defined in this section.

### 8.6.1 Differential Characteristics

#### 8.6.1.1 Differential Insertion Loss for Data Rate $\geq 80$ Mbps and $\leq 1.5$ Gbps

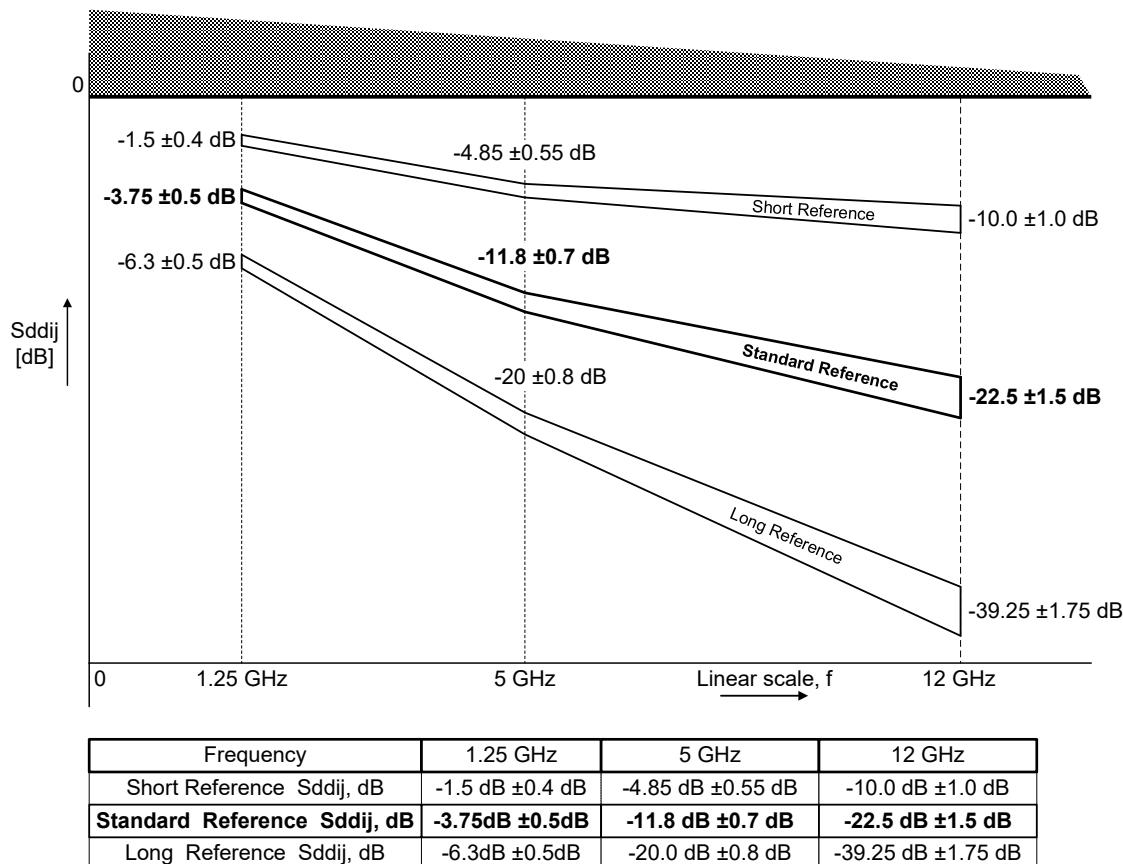
The differential transfer behavior (insertion loss) of the TLIS when supporting data rates  $\geq 80$  Mbps and  $\leq 1.5$  Gbps shall meet the Sdd21 template shown in *Figure 51*, where  $i \neq j$ .



**Figure 51** Template for Differential Insertion Losses, Data Rates  $\geq 80$  Mbps and  $\leq 1.5$  Gbps

### 8.6.1.2 Differential Insertion Loss for Data Rate > 1.5 Gbps

The differential transfer behavior (insertion loss) of the TLIS when supporting data rates > 1.5 Gbps shall meet the Sdd21 template shown in **Figure 52**, where  $i \neq j$ .



**Figure 52 Template for Differential Insertion Losses, Data Rates > 1.5 Gbps**

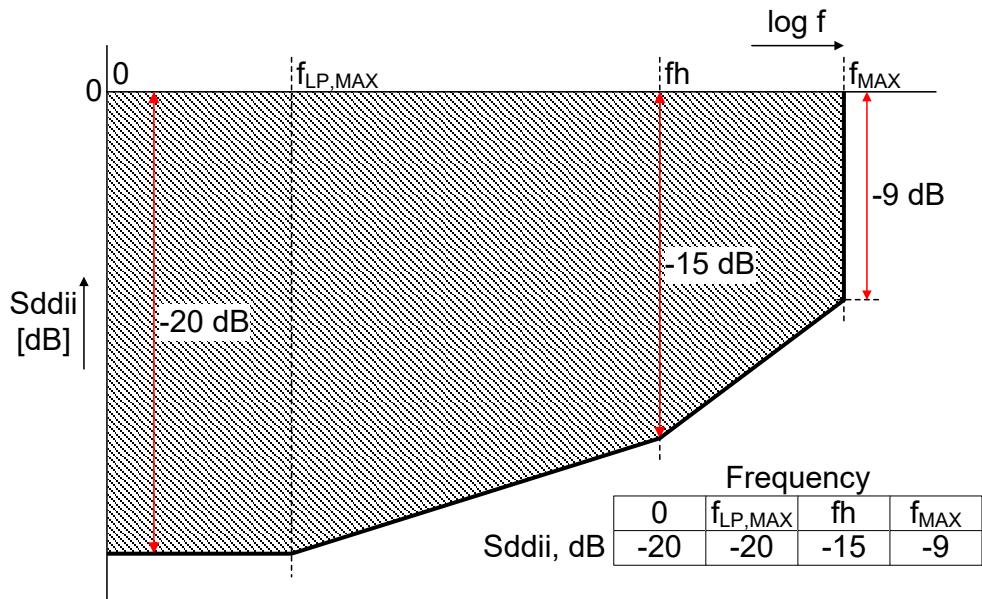
Three Reference channels (Short, Standard, and Long) are defined to support a wide range of display and camera applications:

- Transmitters and receivers shall support the Standard Reference channel; it is the default requirement.
- Short Reference channel support is optional. In applications targeting lower interconnect loss, and when the Transmitter or the Receiver support the optional power saving modes, this channel can be referenced for better system power optimization.
- Long Reference Channel support is optional. This is aimed at supporting higher loss interconnect like Chip-On-Glass (COG). In order to support such an interconnect, the data rate may need to be limited. COG interconnect is used for display panels and has reduced cost compared to other solutions. However, it increases the total loss of interconnect due to additional routing on the glass, bonding between the glass and PCB, and bonding between the glass and silicon.

Specific guidance on usage of these reference channels is provided in **Section 10.4**.

### 8.6.1.3 Differential Reflection Loss for Data Rate $\geq 80$ Mbps and $\leq 1.5$ Gbps

When supported data rates are  $\geq 80$  Mbps and  $\leq 1.5$  Gbps, the differential reflection for both ports of the TLIS is specified by Sdd11 and Sdd22, and should match the template shown in **Figure 53**. Not meeting the differential reflection coefficient might impact interoperability and operation.



**Figure 53 Template for Differential Reflection at Both Ports**

### 8.6.1.4 Differential Reflection Loss for Data Rate $> 1.5$ Gbps and $\leq 4.5$ Gbps

When supported data rates are  $> 1.5$  Gbps and  $\leq 4.5$  Gbps, the differential reflection for both ports of the TLIS is specified by Sdd11 and Sdd22, and should be better than -12 dB in the range from 0 to fmax. Not meeting the differential reflection coefficient might impact interoperability and operation.

### 8.6.2 Common-mode Characteristics

The common-mode insertion loss is implicitly specified by means of the differential insertion loss and the Intra-Lane cross coupling. The requirements for common-mode insertion loss are therefore equal to the differential requirements.

### 8.6.3 Intra-Lane Cross-Coupling

The two lines applied as a differential pair during HS transmission are also used individually for single-ended signaling during Low-Power mode. Therefore, the coupling between the two wires shall be restricted in order to limit single-ended cross coupling. The coupling between the two wires is defined as the difference of the S-parameters  $S_{CC21}$  and  $S_{DD21}$  or  $S_{CC12}$  and  $S_{DD12}$ . In either case, the difference shall not exceed  $-20$  dB for frequencies up to  $10*f_{LP,MAX}$ .

### 8.6.4 Mode-Conversion Limits

All mixed-mode, 4-port S-parameters for differential to common-mode conversion, and vice-versa, shall not exceed  $-26$  dB for frequencies below  $f_{MAX}$ . This includes  $S_{DC12}$ ,  $S_{CD21}$ ,  $S_{CD12}$ ,  $S_{DC21}$ ,  $S_{CD11}$ ,  $S_{DC11}$ ,  $S_{CD22}$ , and  $S_{DC22}$ .

### 8.6.5 Inter-Lane Cross-Coupling

The common-mode and differential inter-Lane cross coupling between Lanes (clock and data) shall meet the requirements as shown in *Figure 54* and *Figure 55*, respectively.

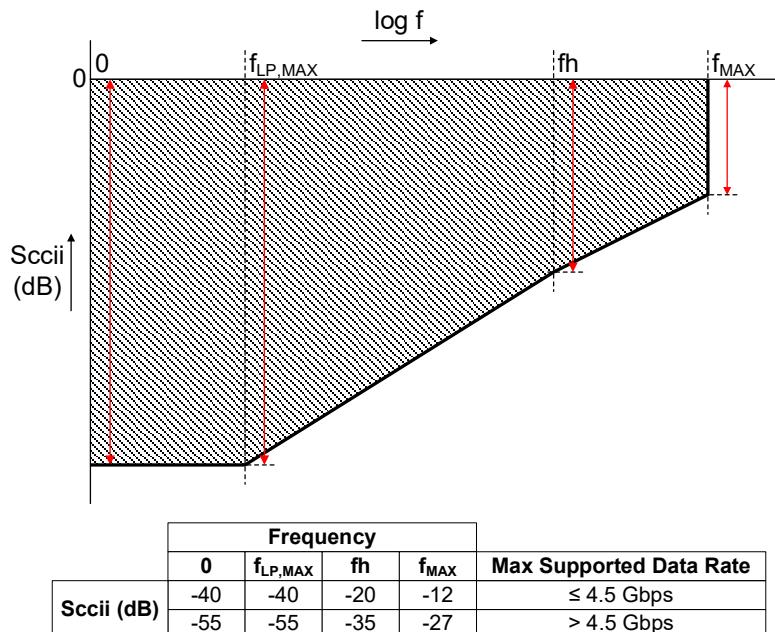
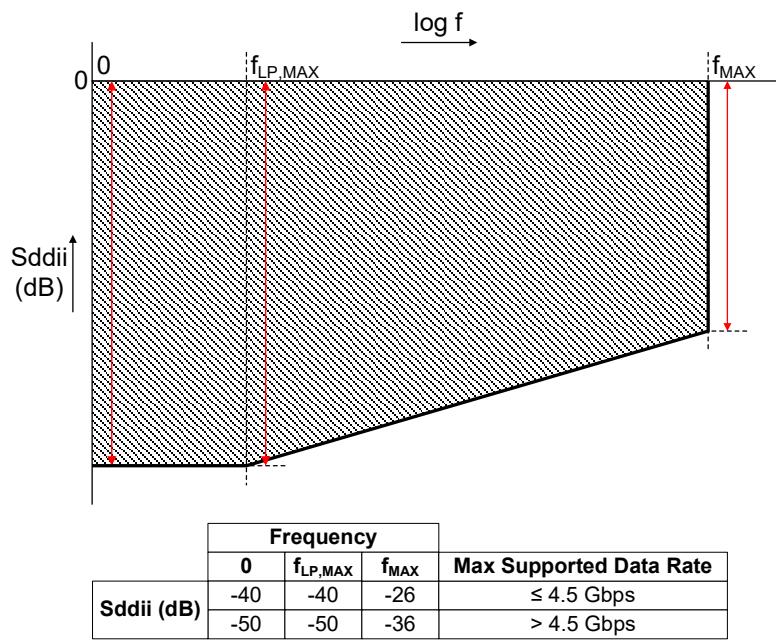


Figure 54 Inter-Lane Common-mode Cross-Coupling Template



1258

**Figure 55 Inter-Lane Differential Cross-Coupling Template**

### 8.6.6 Inter-Lane Static Skew

1259 The difference in phase delay between any Data Lane and the Clock Lane shall be less than UI/50 for all  
1260 frequencies up to and including  $f_h$ , when the supported data rate is less than or equal to 1.5 Gbps.

1261

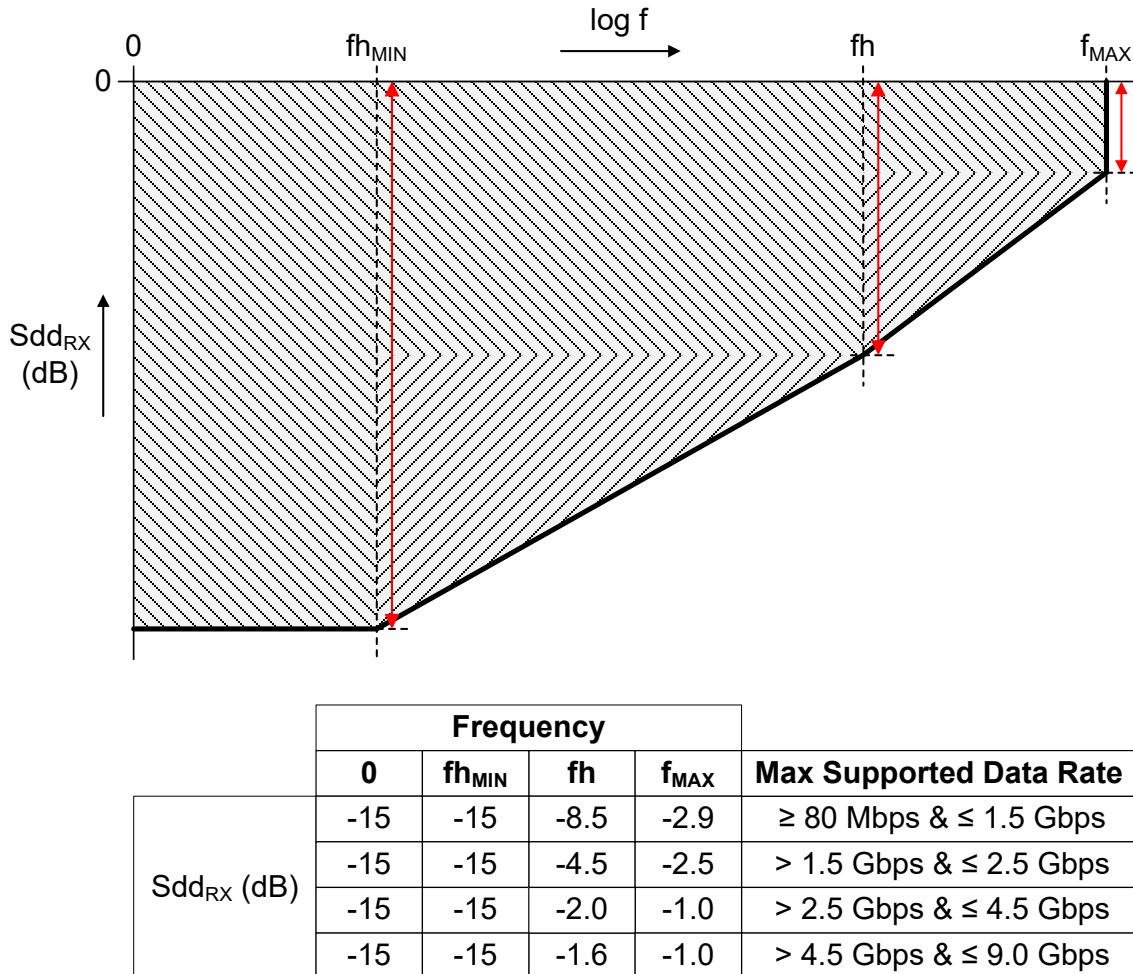
$$\frac{|Sdd12_{DATA}(\varphi) - Sdd12_{CLOCK}(\varphi)|}{\omega} < \frac{UI}{50}$$

## 8.7 Driver and Receiver Characteristics

Besides the TLIS the Lane consists of two RX-TX modules, one at each side. This section specifies the reflection behavior (return loss) of these RX-TX modules in HS mode. The signaling characteristics of all possible functional blocks inside the RX-TX modules can be found in [Section 9](#).

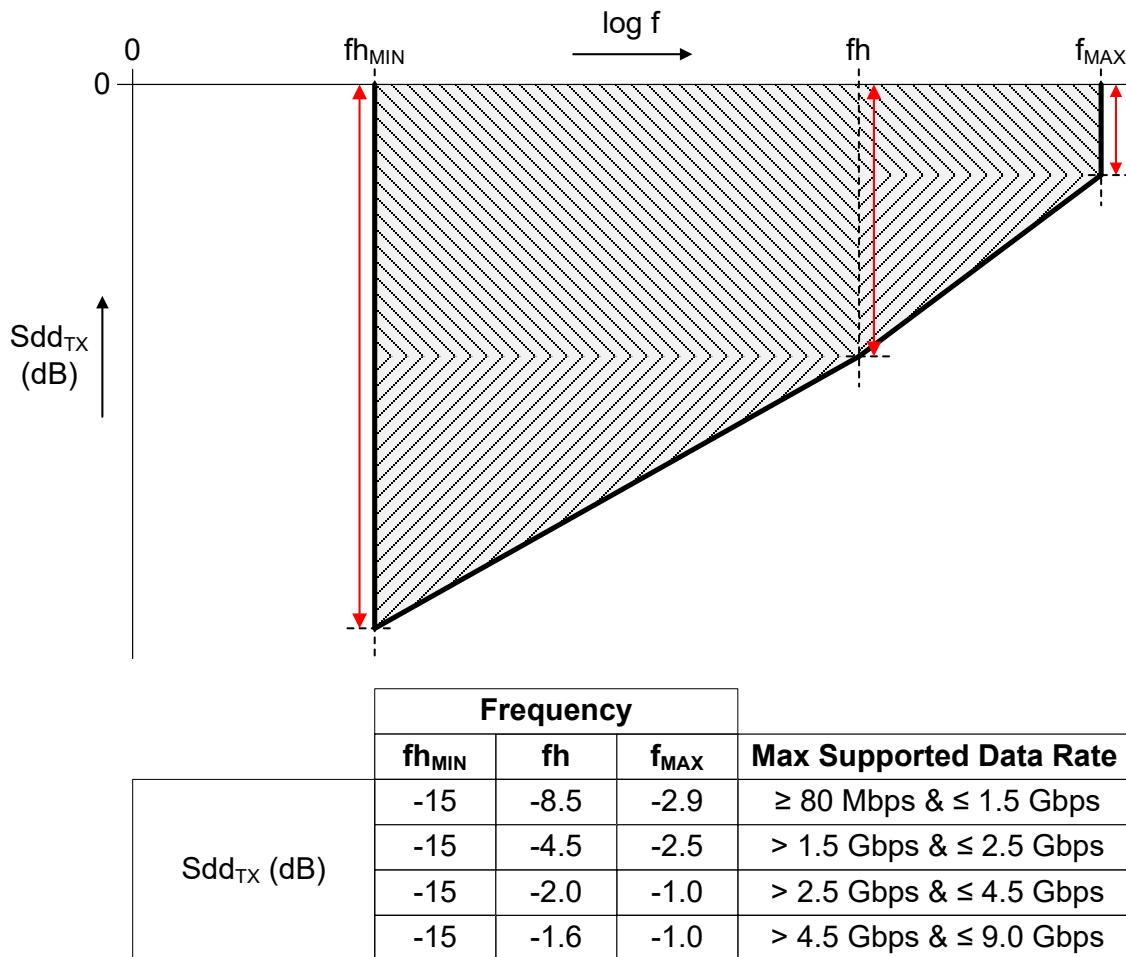
### 8.7.1 Differential Characteristics

The differential reflection of a Lane Module in High-Speed RX mode should conform to the limits specified by the template shown in [Figure 56](#).



**Figure 56 Differential Reflection Template for Lane Module Receivers**

1268 The differential reflection of a Lane Module in High-Speed TX mode should conform to the limits  
1269 specified by the template shown in **Figure 57**.

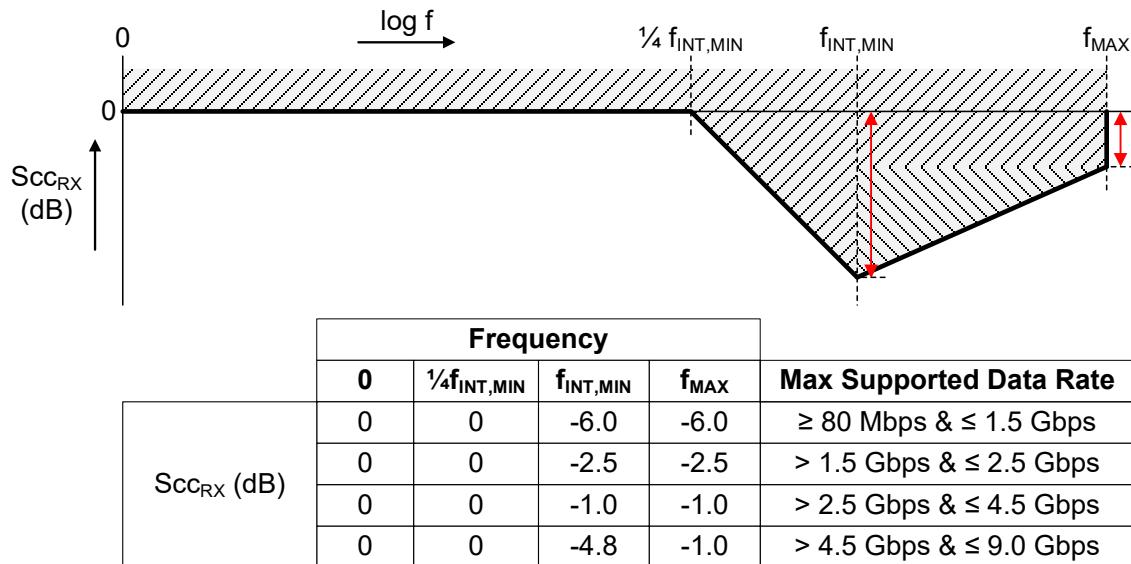


1270 **Figure 57 Differential Reflection Template for Lane Module Transmitters**

### 8.7.2 Common-Mode Characteristics

The common-mode return loss specification is different for a High-Speed TX and RX mode, because the RX is not DC terminated to ground. The common-mode reflection of a Lane Module in High-Speed TX mode,  $S_{CC,RX}$ , should be less than -6.0 dB from  $f_{LP,MAX}$  up to  $f_{MAX}$  for devices supporting data rates up to 1.5 Gbps, less than -2.5 dB for devices supporting data rates up to 2.5 Gbps, and less than -1.0 dB for devices supporting data rates up to 9 Gbps.

The common-mode reflection of a Lane Module in High-Speed RX mode should conform to the limits specified by the template shown in **Figure 58**. Assuming a high DC common-mode impedance, this implies a sufficiently large capacitor at the termination center tap. The minimum value allows integration. While the common-mode termination is especially important for reduced influence of RF interferers, the RX requirement limits reflection for the most relevant frequency band.



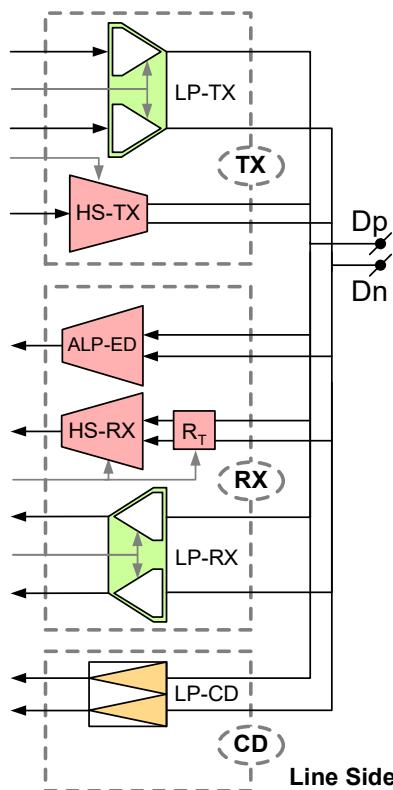
**Figure 58 Template for RX Common-Mode Return Loss**

### 8.7.3 Mode-Conversion Limits

The differential to common-mode conversion limits of RX should be -26 dB up to  $f_{MAX}$ .

## 9 Electrical Characteristics

A PHY may contain the following electrical functions: a High-Speed Transmitter (HS-TX), a High-Speed Receiver (HS-RX), a Low-Power Transmitter (LP-TX), a Low-Power Receiver (LP-RX), a Low-Power Contention Detector (LP-CD), and an Alternate Low-Power Exit Detector (ALP-ED) if ALP mode is supported. A PHY does not need to contain all electrical functions, only the functions that are required for a particular PHY Configuration. The required functions for each configuration are specified in **Section 5**. All electrical functions included in any PHY shall meet the specifications in this Section. **Figure 59** shows the complete set of electrical functions required for a fully featured PHY transceiver.



**Figure 59 Electrical Functions of a Fully Featured D-PHY Transceiver**

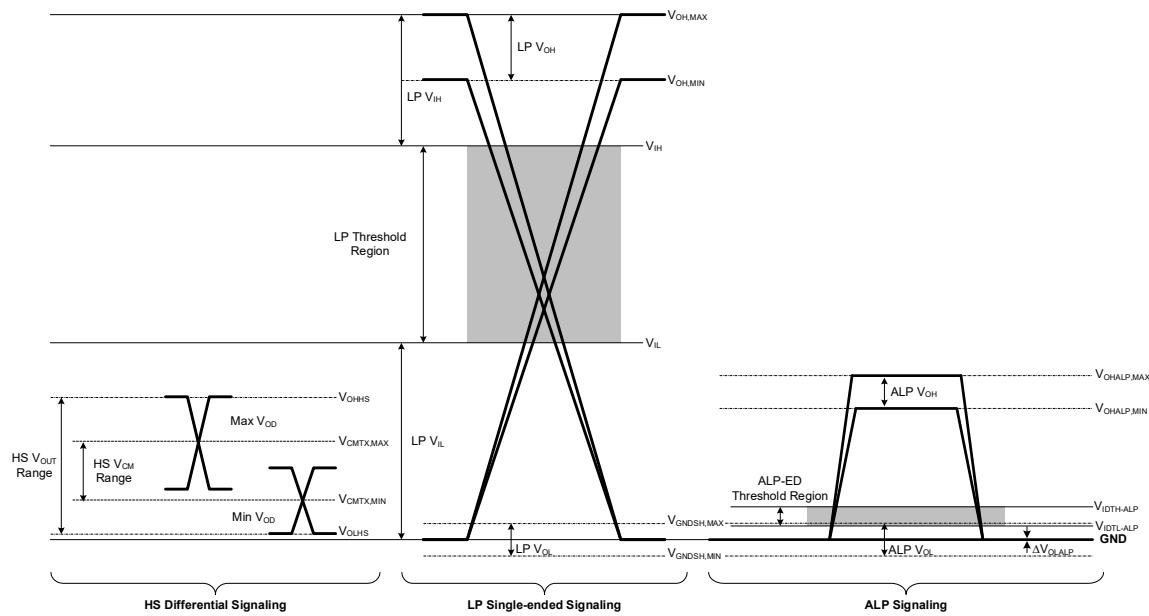
The HS transmitter and HS receiver are used for the transmission of the HS data and clock signals. The HS transmitter and receiver use low-voltage differential signaling for signal transmission. The HS receiver contains a switchable parallel termination.

The LP transmitter and LP receiver serve as a low power signaling mechanism. The LP transmitter is a push-pull driver and the LP receiver is an un-terminated, single-ended receiver.

The ALP Exit Detector is used to wake up the PHY from one of the low power standby states when operating in ALP mode. It is a differential comparator with a built-in offset.

The signal levels are different for differential HS mode, single-ended LP mode, and ALP mode. **Figure 60** shows the HS, LP, and ALP signal levels on the left, center, and right sides, respectively. The HS signaling levels are below the LP low-level input threshold such that LP receiver always detects low on HS signals.

All absolute voltage levels are relative to the ground voltage at the transmit side.

**Figure 60 D-PHY Signaling Levels**

1302 A Lane switches between Low-Power and High-Speed mode or Alternate Low-Power and High-Speed mode during normal operation. Bidirectional Lanes can also switch communication direction. The change of operating mode or direction requires enabling and disabling certain electrical functions. These enable and disable events shall not cause glitches on the Lines that would result in a detection of an incorrect signal level. Therefore, all mode and direction changes shall be smooth to always ensure a proper detection of the Line signals.

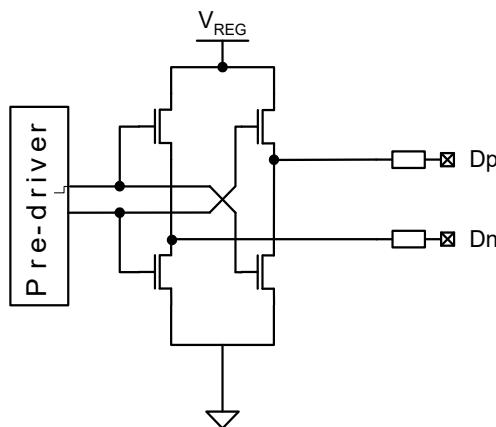
## 9.1 Driver Characteristics

### 9.1.1 High-Speed Transmitter

#### 9.1.1.1 Differential & Common-Mode Swing

A HS differential signal driven on the Dp and Dn pins is generated by a differential output driver. For reference, Dp is considered as the positive side and Dn as the negative side. The Lane state is called Differential-1 (HS-1) when the potential on Dp is higher than the potential of Dn. The Lane state is called Differential-0 (HS-0), when the potential on Dp is lower than the potential of Dn. *Figure 61* shows an example implementation of a HS transmitter.

Note, this Section uses Dp and Dn to reference the pins of a Lane Module regardless of whether the pins belong to a Clock Lane Module or a Data Lane Module.



**Figure 61 Example HS Transmitter**

The differential output voltage  $V_{OD}$  is defined as the difference of the voltages  $V_{DP}$  and  $V_{DN}$  at the Dp and Dn pins, respectively.

$$V_{OD} = V_{DP} - V_{DN}$$

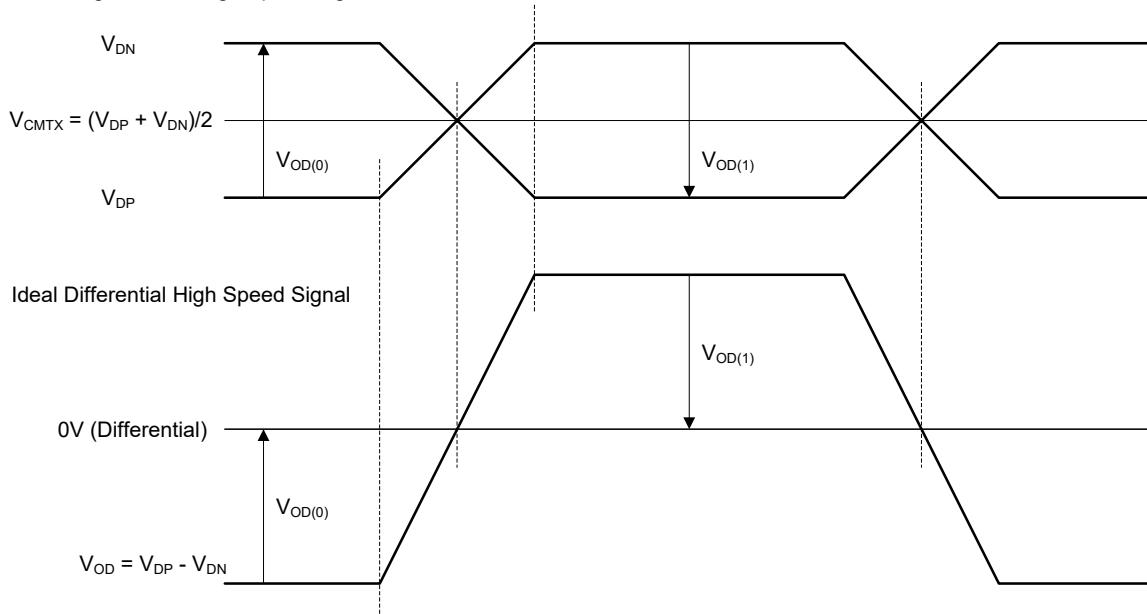
The output voltages  $V_{DP}$  and  $V_{DN}$  at the Dp and Dn pins shall not exceed the High-Speed output high voltage  $V_{OHHS}$  when driving into a ZID load impedance.  $V_{OLHS}$  is the High-Speed output, low voltage on Dp and Dn and is determined by  $V_{OD}$  and  $V_{CMTX}$ . The High-Speed  $V_{OUT}$  is bounded by the minimum value of  $V_{OLHS}$  and the maximum value of  $V_{OHHS}$ .

The common-mode voltage  $V_{CMTX}$  is defined as the arithmetic mean value of the voltages at the Dp and Dn pins:

$$V_{CMTX} = \frac{V_{DP} + V_{DN}}{2}$$

1327 V<sub>OD</sub> and V<sub>CMTX</sub> are graphically shown in **Figure 62** for ideal HS signals. **Figure 63** shows single-ended HS  
 1328 signals with the possible kinds of distortion of the differential output and common-mode voltages. V<sub>OD</sub> and  
 1329 V<sub>CMTX</sub> may be slightly different for driving a Differential-1 or a Differential-0 on the pins.

Ideal Single-Ended High Speed Signals



1330

**Figure 62 Ideal Single-Ended and Resulting Differential HS Signals**

### 9.1.1.2 Differential Voltage Mismatch

1331 The output differential voltage mismatch  $\Delta V_{OD}$  is defined as the difference of the absolute values of the  
 1332 differential output voltage in the Differential-1 state  $V_{OD(1)}$  and the differential output voltage in the  
 1333 Differential-0 state  $V_{OD(0)}$ . This is expressed by:

$$\Delta V_{OD} = |V_{OD(1)}| - |V_{OD(0)}|$$

1334

### 9.1.1.3 Static Common-Mode Mismatch & Transient Common-Mode Voltage

If  $V_{CMTX(1)}$  and  $V_{CMTX(0)}$  are the common-mode voltages for static Differential-1 and Differential-0 states respectively, then the common-mode reference voltage is defined by:

$$V_{CMTX,REF} = \frac{V_{CMTX(1)} + V_{CMTX(0)}}{2}$$

1337

The transient common-mode voltage variation is defined by:

$$\Delta V_{CMTX}(t) = V_{CMTX}(t) - V_{CMTX,REF}$$

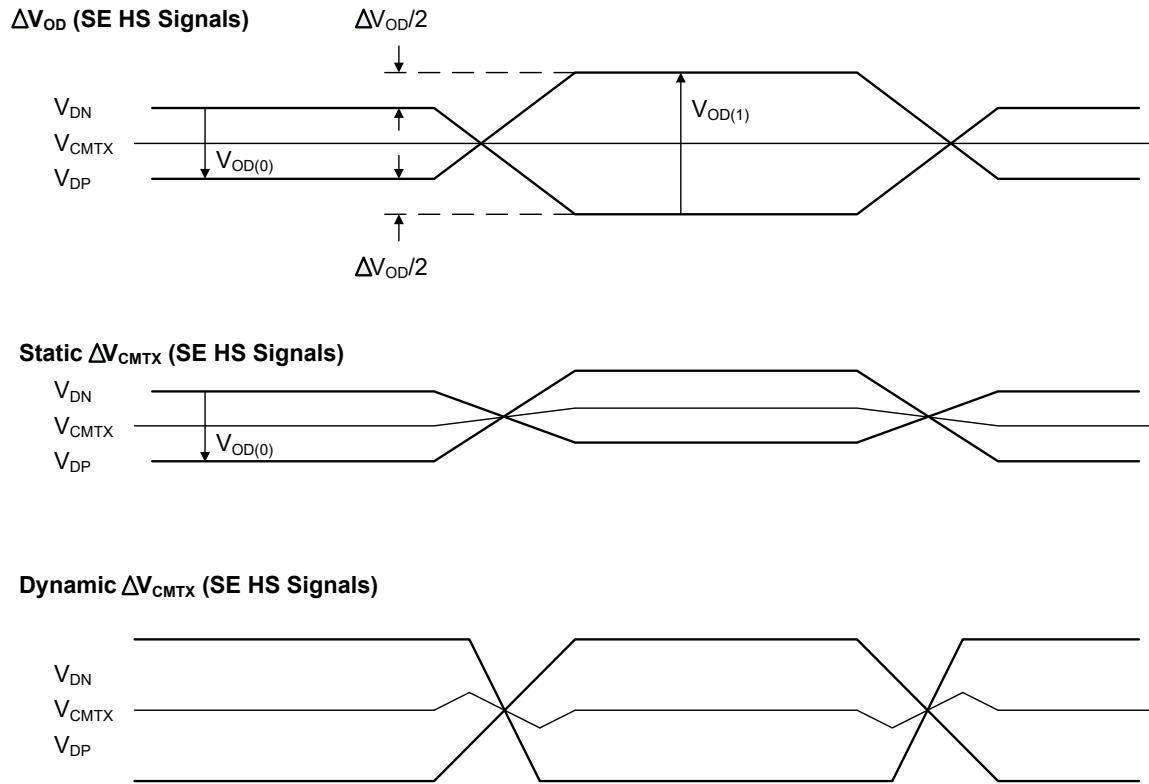
1339

The static common-mode voltage mismatch between the Differential-1 and Differential-0 state is given by:

$$\Delta V_{CMTX(1,0)} = \frac{V_{CMTX(1)} - V_{CMTX(0)}}{2}$$

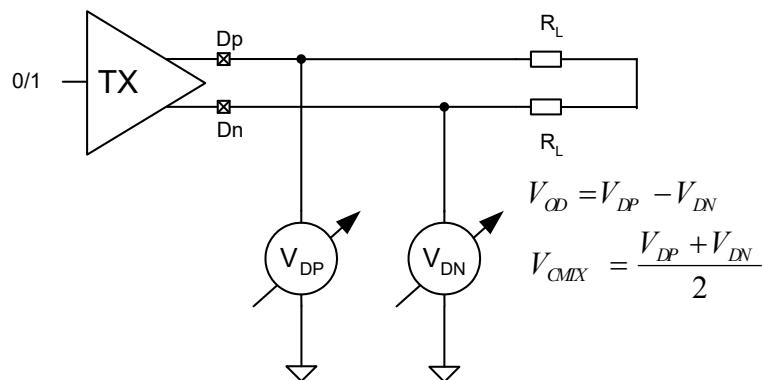
1341

The transmitter shall send data such that the high frequency and low frequency common-mode voltage variations do not exceed  $\Delta V_{CMTX(HF)}$  and  $\Delta V_{CMTX(LF)}$ , respectively. An example test circuit for the measurement of  $V_{OD}$  and  $V_{CMTX}$  is shown in **Figure 64**.



**Figure 63 Possible  $\Delta V_{CMTX}$  and  $\Delta V_{OD}$  Distortions of the Single-ended HS Signals**

1345



1346

**Figure 64 Example Circuit for VCMTX and VOD Measurements**

#### 9.1.1.4 Output Resistance

The single-ended output impedance of the transmitter at both the Dp and Dn pins is denoted by  $Z_{\text{OS}}$ .  $\Delta Z_{\text{OS}}$  is the mismatch of the single-ended output impedances at the Dp and Dn pins, denoted by  $Z_{\text{OSDP}}$  and  $Z_{\text{OSDN}}$ , respectively. This mismatch is defined as the ratio of the absolute value of the difference of  $Z_{\text{OSDP}}$  and  $Z_{\text{OSDN}}$  and the average of those impedances:

$$\Delta Z_{\text{OS}} = 2 \frac{|Z_{\text{OSDP}} - Z_{\text{OSDN}}|}{Z_{\text{OSDP}} + Z_{\text{OSDN}}}$$

When using ALP mode, the output impedance  $Z_{\text{OS}}$  is relaxed, when the transmitter drives an ALP-00 Lane state. The single-ended output impedance of the transmitter at both the Dp and Dn pins in ALP-00 Lane state is denoted by  $Z_{\text{OS-ALP00}}$ . The single-ended output impedance  $Z_{\text{OS-ALP00}}$  can be determined by injecting an AC current into the Dp and Dn pins and measuring the peak-to-peak voltage amplitude.

The output impedance  $Z_{\text{OS}}$  ( $Z_{\text{OS-ALP00}}$  when ALP mode is used) and the output impedance mismatch  $\Delta Z_{\text{OS}}$  shall be compliant with **Table 31** for Lane states HS-1, HS-0, ALP-01, ALP-10, and ALP-00 for all allowed loading conditions. It is recommended that implementations keep the output impedance during state transitions as close as possible to the steady state value. The output impedance  $Z_{\text{OS}}$  can be determined by injecting an AC current into the Dp and Dn pins and measuring the peak-to-peak voltage amplitude.

#### 9.1.1.5 Rise/Fall Times

The rise and fall times,  $t_r$  and  $t_f$ , are defined as the transition time between 20% and 80% of the full HS signal swing. Full HS Swing can be calculated by driving a steady state pattern. The driver shall meet the  $t_r$  and  $t_f$  specifications for all allowable  $Z_{\text{ID}}$ . The specifications for TX common-mode return loss and the TX differential mode return loss can be found in **Section 8**.

Rise/Fall Times are defined for a maximum data rate of 1.5 Gbps. For Data rates above 1.5 Gbps, the Eye diagram specification defined in **Section 10.2.5** governs the slew rate requirements of the transmitter.

It is recommended that a High-Speed transmitter that is directly terminated at its pins should not generate any overshoot in order to minimize EMI.

### 9.1.1.6 Half Swing Mode

In the Half Swing mode, differential swing of the transmitter is reduced to half that of the default swing specification. This is an optional mode that a transmitter can choose to support for power savings. Transmitter Half Swing mode can be used with the Receiver either in terminated or unterminated mode. Half Swing mode is defined for a termination ZID. There is no transmitter parameter defined for the operation with an unterminated receiver, due to the difficulty of measuring excess reflections on the Line. Refer to the Receiver termination condition in **Section 9.2.1**. A Transmitter with full swing operation shall not operate with a Receiver in unterminated mode due to the violation of V<sub>OHHS</sub>.

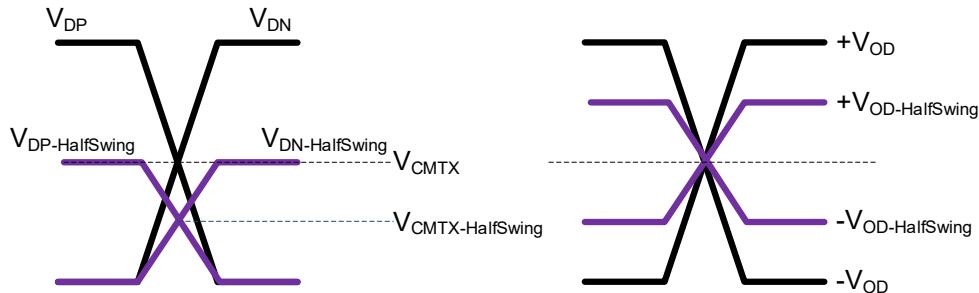


Figure 65 Common-Mode and Differential Swing in Half Swing Mode versus Default

### 9.1.1.7 De-emphasis

To mitigate additional channel-induced ISI above 2.5 Gbps, an HS-TX needs to use channel equalization in the form of de-emphasis. The transmitter de-emphasis has two taps, where the first tap is the cursor and the second tap is the first post-cursor. The taps are separated by UI and the transmitter de-emphasis ratio EQ<sub>TX</sub> determines the de-emphasis level. Two de-emphasis ratios are defined.

*Figure 66* shows an example transmit waveform with de-emphasis. After a logical bit transition, the amplitude of the differential output voltage signal V<sub>DIF-TX</sub>(t) conforms to the differential AC output voltage amplitude V<sub>OD</sub>. The next bit that retains the same logical state is reduced in amplitude. The differential AC output voltage amplitude with de-emphasis V<sub>OD-EQ</sub> is defined as the reduced amplitude. EQ<sub>TX</sub> is defined as the minus 20 log of the ratio of V<sub>OD-EQ</sub> and V<sub>OD</sub> as shown in the following equation:

$$EQ_{TX} = -20 \log \left( \frac{V_{OD-EQ}}{V_{OD}} \right)$$



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**Figure 66 De-emphasis Example**

### 9.1.1.8 Alternate Low Power Levels

When using ALP mode, ALP Control Bursts are transmitted in High-Speed mode as a replacement for LP signaling. The HS transmitter electrical specifications, when operating in High-Speed mode, are the same whether associated with LP or ALP modes. There are, however, some additional requirements when supporting ALP mode in order to enable the ALP Lane states:

- ALP-01
- ALP-10
- ALP-00

$V_{OLALP}$  is the output low-level voltage in ALP mode, when the pad pin is not loaded.  $V_{OHALP}$  is the output high-level voltage in ALP mode, when the pad pin is not loaded. The HS transmitter shall drive the Dp and Dn pin potentials to the targeted low- or high-levels. The HS transmitter shall not drive the pad pin potential statically beyond the maximum value of  $V_{OHALP}$ .

The transmitter output voltage mismatch in ALP-00 Lane state  $|\Delta V_{OLALP}|$  is defined as the absolute value of the difference of the voltages  $V_{OLALP,DP}$  and  $V_{OLALP,DN}$  at the Dp and Dn pins, respectively. This is expressed by:

$$|\Delta V_{OLALP}| = |V_{OLALP,DP} - V_{OLALP,DN}|$$

The Lane state is called ALP-01 when the transmitter drives the  $V_{OLALP}$  and  $V_{OHALP}$  potentials on the Dp and Dn pins, respectively. This state is used for ALP Wake pulses and at the start of an HS Data Burst following an ALP-00 Lane state as part of the HS-Zero or CLK-Zero periods.

The Lane state is called ALP-10 when the transmitter drives the  $V_{OHALP}$  and  $V_{OLALP}$  potentials on the Dp and Dn pins, respectively. This state is used at the end of an HS Data Burst as part of the HS-Trail or CLK-Trail periods before transitioning to an ALP-00 Lane state.

The Lane state is called ALP-00 when the transmitter drives the  $V_{OLALP}$  potential on both the Dp and Dn pins and the difference Dp and Dn Line levels is within the limits defined by  $|\Delta V_{OLALP}|$ . It is used during ALP Stop or ALP ULPS states to reduce power consumption.

### 9.1.1.9 HS TX Parameters

The HS Transmitter DC Specifications are presented in **Table 31**, and the HS Transmitter AC Specifications are presented in **Table 32**.

**Table 31 HS Transmitter DC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
EQ <sub>TX1</sub>	De-emphasis Option 1	2.5	3.5	4.5	dB	1
EQ <sub>TX2</sub>	De-emphasis Option 2	6	7	8	dB	1
V <sub>CMTX</sub>	HS transmit static common-mode voltage	150	200	250	mV	2
V <sub>CMTX-HalfSwing</sub>	HS transmit static common-mode voltage in Half Swing mode	75	100	250	mV	2, 4
ΔV <sub>CMTX(1,0)</sub>	V <sub>CMTX</sub> mismatch when output is Differential-1 or Differential-0	–	–	5	mV	3
V <sub>OD</sub>	HS transmit differential voltage	140	200	270	mV	2
V <sub>OD-HalfSwing</sub>	HS transmit differential voltage In Half Swing mode	70	100	135	mV	2, 4
ΔV <sub>OD</sub>	V <sub>OD</sub> mismatch when output is Differential-1 or Differential-0	–	–	14	mV	3
V <sub>OHHs</sub>	HS output high voltage	–	–	360	mV	2
Z <sub>os</sub>	Single ended output impedance	40	50	62.5	Ω	–
ΔZ <sub>os</sub>	Single ended output impedance mismatch	–	–	20	%	–
V <sub>OHALP</sub>	Output high level voltage in ALP mode	150	–	435	mV	5
V <sub>OLALP</sub>	Output low level voltage in ALP mode	-50	–	50	mV	5
ΔV <sub>OLALP</sub>	Transmitter output voltage mismatch in ALP-00 Lane state	–	–	10	mV	5
Z <sub>OS_ALP00</sub>	Single-ended output impedance in ALP-00 Lane state	40	–	300	Ω	5

**Note:**

- When the maximum supported data rate is > 2.5 Gbps. Conformance requirements for the transmitter are defined through the eye diagram. The values for equalization in this table are informative.
- Value when driving into load impedance anywhere in the Z<sub>ID</sub> range.
- A transmitter should minimize ΔV<sub>OD</sub> and ΔV<sub>CMTX(1,0)</sub> in order to minimize radiation and optimize signal integrity.
- Half Swing mode is optional. It is an additional capability a transmitter can support for better system power optimization.
- Value while driving into load impedance in the Z<sub>ID-OPEN</sub> range.

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**Table 32 HS Transmitter AC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$\Delta V_{CMTX(HF)}$	Common-level variations above 450MHz	—	—	15	mV <sub>RMS</sub>	—
$\Delta V_{CMTX(LF)}$	Common-level variation between 50-450MHz	—	—	25	mV <sub>PEAK</sub>	—
$t_R$ and $t_F$	20%-80% rise time and fall time	—	—	0.3	UI	1, 2
		—	—	0.35	UI	1, 3
		100	—	—	ps	4, 5

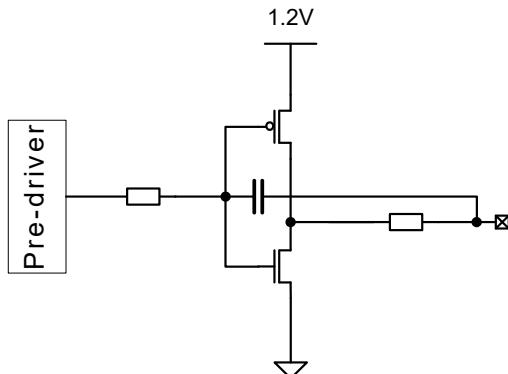
**Note:**

1. *UI* is equal to  $1/(2*fh)$ . See **Section 8.3** for the definition of  $fh$ .
2. Applicable when supporting maximum HS bit rates  $\leq 1$  Gbps ( $UI \geq 1$  ns).
3. Applicable when supporting maximum HS bit rates  $> 1$  Gbps ( $UI \leq 1$  ns) but  $\leq 1.5$  Gbps ( $UI \geq 0.667$  ns).
4. Applicable when supporting maximum HS bit rates  $\leq 1.5$  Gbps. However, to avoid excessive radiation, bit rates  $< 1$  Gbps ( $UI \geq 1$  ns), should not use values below 150 ps.
5. For maximum supported HS bit rates  $> 1.5$  Gbps, the transmitter transition times are governed by the eye diagram.

### 9.1.2 Low-Power Transmitter

The Low-Power transmitter shall be a slew-rate controlled push-pull driver. It is used for driving the Lines in all Low-Power operating modes. It is therefore important that the static power consumption of an LP transmitter is as low as possible. The slew-rate of signal transitions is bounded in order to keep EMI low. A Low-Power transmitter may additionally support the optional Low Voltage Low Power operation, in which the maximum output voltage is limited in comparison to the normal Low Power mode.

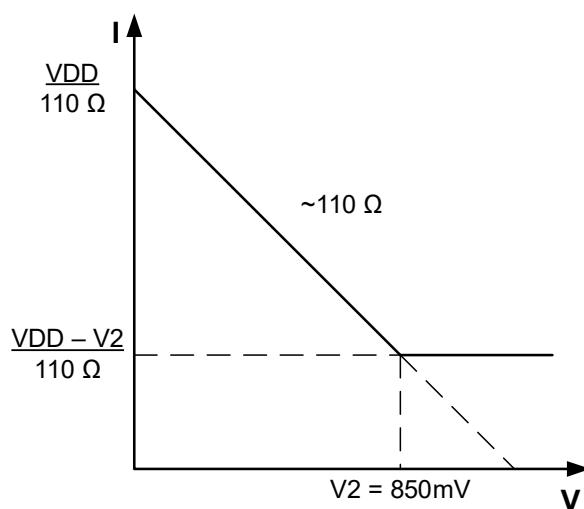
An example of an LP transmitter is shown in **Figure 67**.



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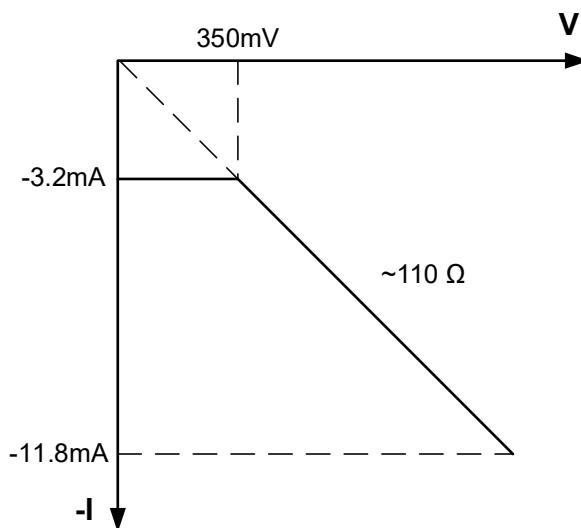
**Figure 67 Example LP Transmitter**

**V<sub>OL</sub>** is the Thevenin output, low-level voltage in the LP transmit mode. This is the voltage at an unloaded pad pin in the low-level state. **V<sub>OH</sub>** is the Thevenin output, high-level voltage in the high-level state, when the pad pin is not loaded. The LP transmitter shall not drive the pad pin potential statically beyond the maximum value of **V<sub>OH</sub>**. The pull-up and pull-down output impedances of LP transmitters shall be as described in **Figure 68** and **Figure 69**, respectively. The circuit for measuring **V<sub>OL</sub>** and **V<sub>OH</sub>** is shown in **Figure 70**.

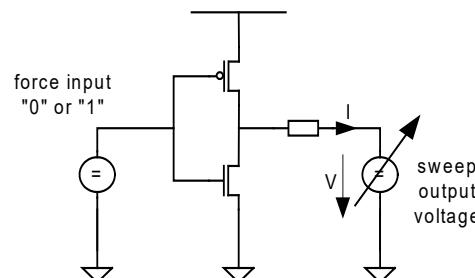


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**Figure 68 V-I Characteristic for LP Transmitter Driving Logic High**



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**Figure 69 V-I Characteristic for LP Transmitter Driving Logic Low**

1431

**Figure 70 LP Transmitter V-I Characteristic Measurement Setup**

1432

The impedance  $Z_{OLP}$  is defined by:

$$Z_{OLP} = \left| \frac{V_{THEVENIN} - V_{PIN}}{I_{OUT}} \right|$$

1433

The times  $T_{RLP}$  and  $T_{FLP}$  are the 15%-85% rise and fall times, respectively, of the output signal voltage, when the LP transmitter is driving a capacitive load  $C_{LOAD}$ . The 15%-85% levels are relative to the fully settled  $V_{OH}$  and  $V_{OL}$  voltages. The slew rate  $\delta V/\delta t_{SR}$  is the derivative of the LP transmitter output signal voltage over time. The LP transmitter output signal transitions shall meet the maximum and minimum slew rate specifications as shown in **Table 34**. The intention of specifying a maximum slew rate value is to limit EMI.

**Table 33 LP Transmitter DC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$V_{OH}$	Thevenin output high level	1.1	1.2	1.3	V	1
		0.95	—	1.3	V	2, 6
		0.95	—	1.1	V	3, 6
$V_{OL}$	Thevenin output low level	-50	—	50	mV	—
$Z_{OLP}$	Output impedance of LP transmitter	110	—	—	$\Omega$	4, 5

**Note:**

1. Applicable in normal Low Power mode when the supported data rate  $\leq 1.5$  Gbps.
2. Applicable in normal Low Power mode when the supported data rate  $> 1.5$  Gbps.
3. Applicable for all data rates when Lane Module is in optional LVLP operation.
4. See **Figure 68** and **Figure 69**.
5. Though no maximum value for  $Z_{OLP}$  is specified, the LP transmitter output impedance shall ensure the  $T_{RLP}/T_{FLP}$  specification is met.
6. The margin between  $V_{OH,MIN}$  and  $V_{IH,MIN}$  depends on the targeted channel connecting the LP-TX and the LP-RX and the system noise. The margin can be verified through link simulations, especially for LP-RX implementations as per D-PHY v1.0 or v1.1.

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**Table 34 LP Transmitter AC Specifications**

Parameter	Description		Min	Nom	Max	Units	Notes
T <sub>RLP</sub> /T <sub>FLP</sub>	15%-85% rise time and fall time		—	—	25	ns	1
T <sub>REOT</sub>	30%-85% rise time and fall time		—	—	35	ns	5, 6
T <sub>LP-PULSE-TX</sub>	Pulse width of the LP exclusive-OR clock	First LP exclusive-OR clock pulse after Stop state or last pulse before Stop state	40	—	—	ns	4
		All other pulses	20	—	—	ns	4
T <sub>LP-PER-TX</sub>	Period of the LP exclusive-OR clock		90	—	—	ns	—
δV/δt <sub>SR</sub>	Slew rate @ C <sub>LOAD</sub> = 0pF		—	—	500	mV/ns	1, 3, 7, 8
—	Slew rate @ C <sub>LOAD</sub> = 5pF		—	—	300	mV/ns	1, 3, 7, 8
—	Slew rate @ C <sub>LOAD</sub> = 20pF		—	—	250	mV/ns	1, 3, 7, 8
—	Slew rate @ C <sub>LOAD</sub> = 70pF		—	—	150	mV/ns	1, 3, 7, 8
—	Slew rate @ C <sub>LOAD</sub> = 0 to 70pF (Falling Edge Only)		30	—	—	mV/ns	1, 2, 3, 12
			25	—	—	mV/ns	1, 3, 13, 16
—	Slew rate @ C <sub>LOAD</sub> = 0 to 70pF (Rising Edge Only)		30	—	—	mV/ns	1, 3, 9, 12
			25	—	—	mV/ns	1, 3, 13, 15
—	Slew rate @ C <sub>LOAD</sub> = 0 to 70pF (Rising Edge Only)		30 – 0.075 * (V <sub>O,INST</sub> – 700)	—	—	mV/ns	1, 3, 10, 11, 12
			25 – 0.0625 * (V <sub>O,INST</sub> – 550)	—	—	mV/ns	1, 3, 10, 14, 13
C <sub>LOAD</sub>	Load capacitance		0	—	70	pF	1

**Note:**

1. C<sub>LOAD</sub> includes the low-frequency equivalent transmission Line capacitance. The capacitance of TX and RX are assumed to always be <10 pF. The distributed Line capacitance can be up to 50 pF for a transmission Line with 2 ns delay.
2. When the output voltage is between 400 mV and 930 mV.
3. Measured as average across any 50 mV segment of the output signal transition.
4. This parameter value can be lower than T<sub>LPX</sub> due to differences in rise vs. fall signal slopes and trip levels and mismatches between D<sub>P</sub> and D<sub>N</sub> LP transmitters. Any LP exclusive-OR pulse observed during HS EoT (transition from HS level to LP-11) is glitch behavior as described in **Section 9.2.2**.
5. The rise-time of T<sub>REOT</sub> starts from the HS common-level at the moment the differential amplitude drops below 70mV, due to stopping the differential drive.
6. With an additional load capacitance C<sub>CM</sub> between 0 and 60 pF on the termination center tap at RX side of the Lane
7. This value represents a corner point in a piece-wise linear curve.
8. When the output voltage is in the range specified by V<sub>PIN(ABSMAX)</sub>.
9. When the output voltage is between 400 mV and 700 mV.
10. Where V<sub>O,INST</sub> is the instantaneous output voltage, V<sub>D<sub>P</sub></sub> or V<sub>D<sub>N</sub></sub>, in millivolts.
11. When the output voltage is between 700 mV and 930 mV.
12. Applicable when the maximum supported data rate ≤ 1.5 Gbps.
13. Applicable when the maximum supported data rate > 1.5 Gbps or in LVLP operation.
14. When the output voltage is between 550 mV and 790 mV
15. When the output voltage is between 400 mV and 550 mV
16. When the output voltage is between 400 mV and 790 mV

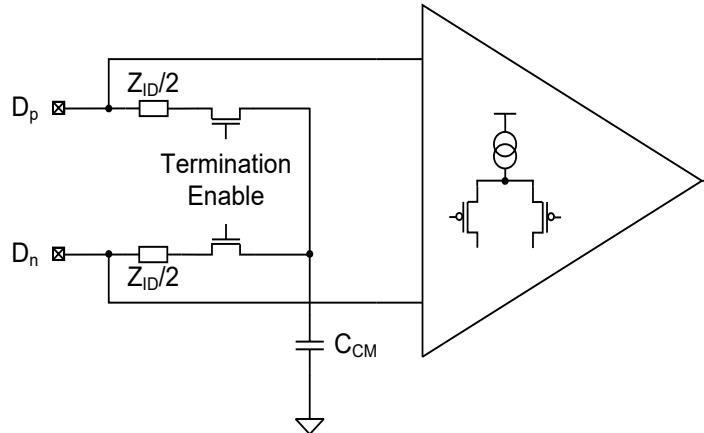
1442 There are minimum requirements on the duration of each LP state. To determine the duration of the LP  
1443 state, the D<sub>p</sub> and D<sub>n</sub> signal lines are each compared to a common trip-level. The result of these  
1444 comparisons is then exclusive-ORed to produce a single pulse train. The output of this “exclusive-OR  
1445 clock” can then be used to find the minimum pulse width output of an LP transmitter.

1446 Using a common trip-level in the range [V<sub>IL,MAX</sub> + V<sub>OL,MIN</sub>, V<sub>IH,MIN</sub> + V<sub>OL,MAX</sub>], the exclusive-OR clock  
1447 shall not contain pulses shorter than T<sub>LP-PULSE-TX</sub>.

## 9.2 Receiver Characteristics

### 9.2.1 High-Speed Receiver

The HS receiver is a differential Line receiver. It contains a switchable parallel input termination,  $Z_{ID}$ , between the positive input pin  $D_p$  and the negative input pin  $D_n$ . A simplified diagram of an example implementation using a PMOS input stage is shown in *Figure 71*.



**Figure 71 HS Receiver Implementation Example**

The differential input high and low threshold voltages of the HS receiver are denoted by  $V_{IDTH}$  and  $V_{IDTL}$ , respectively.  $V_{ILHS}$  and  $V_{IHHS}$  are the single-ended, input low and input high voltages, respectively.  $V_{CMRX(DC)}$  is the differential input common-mode voltage. The HS receiver shall be able to detect differential signals at its  $D_p$  and  $D_n$  input signal pins when both signal voltages,  $V_{DP}$  and  $V_{DN}$ , are within the common-mode voltage range and if the voltage difference of  $V_{DP}$  and  $V_{DN}$  exceeds either  $V_{IDTH}$  or  $V_{IDTL}$ . The High-Speed receiver shall receive High-Speed data correctly while rejecting common-mode interference  $\Delta V_{CMRX(HF)}$  and  $\Delta V_{CMRX(LF)}$ .

During operation of the HS receiver, termination impedance  $Z_{ID}$  is required between the  $D_p$  and  $D_n$  pins of the HS receiver.  $Z_{ID}$  shall be disabled when the module is not in the HS receive mode. When transitioning from Low-Power Mode to HS receive mode the termination impedance shall not be enabled until the single-ended input voltages on both  $D_p$  and  $D_n$  fall below  $V_{TERM-EN}$ . To meet this requirement, a receiver does not need to sense the  $D_p$  and  $D_n$  lines to determine when to enable the Line termination, rather the LP to HS transition timing can allow the Line voltages to fall to the appropriate level before the Line termination is enabled.

The RX common-mode return loss and the RX differential mode return loss are specified in *Section 8*.  $C_{CM}$  is the common-mode AC termination, which ensures a proper termination of the receiver at higher frequencies. For higher data rates,  $C_{CM}$  is needed at the termination center tap in order to meet the common-mode reflection requirements.

When a Transmitter is in Half Swing mode, the receiver may choose to turn off the termination in High Speed mode for lower data rate operation. This is an optional mode that can be supported in addition to the default mode. A receiver in unterminated mode shall not operate with TX full swing.

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**Table 35 HS Receiver DC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$V_{CMRX(DC)}$	Common-mode voltage HS receive mode	70	—	330	mV	1, 2
$Z_{ID}$	Differential input impedance	80	100	125	$\Omega$	3
$Z_{ID-OPEN}$	Differential input impedance in unterminated mode	10K	—	—	$\Omega$	4

**Note:**

1. Excluding possible additional RF interference of 100 mV peak sine wave beyond 450 MHz.
2. This table value includes a ground difference of 50 mV between the transmitter and the receiver, the static common-mode level tolerance and variations below 450 MHz
3.  $Z_{ID}$  can be higher than 125  $\Omega$  in unterminated mode.
4. Unterminated mode for HS-RX is optional. This mode can only be used when a transmitter is in Half Swing mode.  $Z_{ID-OPEN}$  is defined for a differential voltage with maximum amplitude of  $|V_{OD-HalfSwing}|$  and within the common voltage range of  $V_{CMTX-HalfSwing}$ .

1474

**Table 36 HS Receiver AC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$\Delta V_{CMRX(HF)}$	Common-mode interference beyond 450 MHz	—	—	100	mV	2, 5
		—	—	50	mV	2, 6
$\Delta V_{CMRX(LF)}$	Common-mode interference 50MHz – 450MHz	-50	—	50	mV	1, 4, 5
		-25	—	25	mV	1, 4, 6
$V_{IDTH}$	Differential input high threshold	—	—	70	mV	5
		—	—	40	mV	6
$V_{IDTL}$	Differential input low threshold	-70	—	—	mV	5
		-40	—	—	mV	6
$V_{IHHS}$	Single-ended input high voltage	—	—	460	mV	7
$V_{ILHS}$	Single-ended input low voltage	-40	—	—	mV	7
$V_{TERM-EN}$	Single-ended threshold for HS termination enable	—	—	450	mV	—
$C_{CM}$	Common-mode termination	—	—	60	pF	3

**Note:**

1. Excluding ‘static’ ground shift of 50 mV.
2.  $\Delta V_{CMRX(HF)}$  is the peak amplitude of a sine wave superimposed on the receiver inputs.
3. For higher bit rates a 14 pF capacitor will be needed to meet the common-mode return loss specification.
4. Voltage difference compared to the DC average common-mode potential.
5. For devices supporting data rates  $\leq 1.5$  Gbps.
6. For devices supporting data rates  $> 1.5$  Gbps and  $\leq 4.5$  Gbps. At data rates  $> 4.5$  Gbps, the Receiver sensitivity is defined by parameter  $VDIF\_RX$  as specified in **Section 10.2.5**.
7. Excluding possible additional RF interference of 100 mV peak sine wave beyond 450 MHz.

### 9.2.1.1 Reference Receiver Equalization

To mitigate additional channel induced ISI at operational data rates larger than the rates specified in **Table 37**, an HS-RX can utilize equalization in the form of a continuous-time linear equalizer (CTLE). The reference receiver equalization is defined for TX conformance testing and includes a first-order CTLE. It is not intended to define the implementation of a receiver, which may need a more complex circuit to pass all receiver requirements.

**Table 37 Maximum Data Rates Without Reference Receiver Equalization**

Description	Reference Channel			Units	Notes
	Short	Standard	Long		
Maximum data rate for operation without Reference Receiver Equalization	6.5	4.5	2.5	Gbps	-

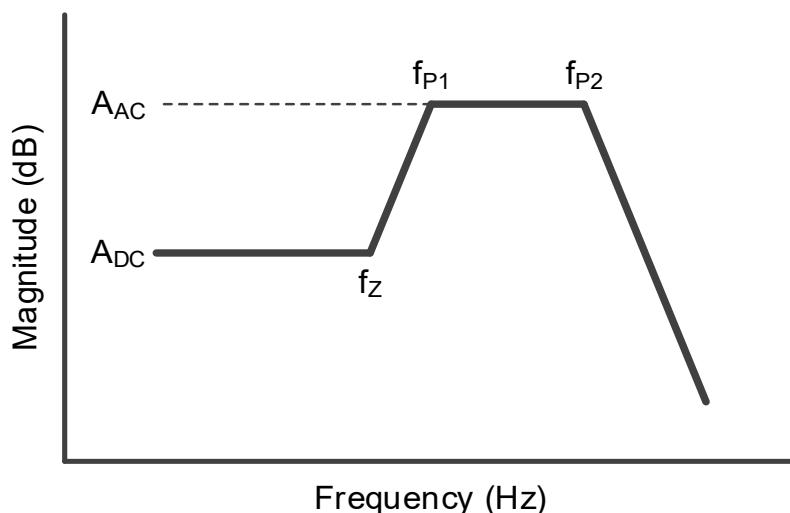
A Clock Lane can exhibit excessive duty cycle distortion at the receiver, and unacceptable reduction of timing margins as a consequence. Asymmetries in the Clock and Data Lanes further degrade the timing margins of the Link. To mitigate such impairments, the reference receiver equalizer employs a mechanism to correct duty cycle distortion for the Clock Lane, and employs similar CTLE stages for both Clock and Data Lanes.

The CTLE characteristics are defined by the following transfer function:

$$H(s) = \frac{A_{DC} \omega_{P1} \omega_{P2}}{\omega_z} \cdot \frac{s + \omega_z}{(s + \omega_{P1})(s + \omega_{P2})}$$

Where  $A_{DC}$  is the DC gain,  
 $\omega_{P1} = 2\pi f_{P1}$  with  $f_{P1}$  being the first pole frequency  
 $\omega_{P2} = 2\pi f_{P2}$  with  $f_{P2}$  being the second pole frequency  
 $\omega_z = 2\pi f_z$  with  $f_z$  being the zero frequency

**Figure 72** shows an example of the CTLE frequency response with the associated CTLE parameters. The parameters such as  $A_{DC}$ ,  $f_z$ ,  $f_{P1}$ , and  $f_{P2}$  are to be chosen based on the targeted channel. The CTLE parameters shall be chosen within the limits defined in **Table 41**.



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**Figure 72 Example of CTLE Frequency Response**

1496 Parameter  $f_{P1}$  is determined by other parameters as follows:  $f_{P1} = f_Z \cdot 10^{((A_{AC}-A_{DC})/20)}$

1497 Some set points for the CTLE are listed in *Table 38* through *Table 40*, targeted for operation at certain data  
1498 rates over the MIPI reference channels and reference package with  $C_{PAD}$ .

1499 **Table 38 CTLE Set Points for Standard Channel, 9 Gbps (Informative)**

$A_{AC}$ (dB)	$A_{DC}$ (dB)	$f_Z$ (GHz)	$f_{P2}$ (GHz)
6	2	1.2	10
6	5	1.2	10
7	6	1.2	10
8	6	1.2	10

**Table 39 CTLE Set Points for Short Channel, 11 Gbps (Informative)**

$A_{AC}$ (dB)	$A_{DC}$ (dB)	$f_Z$ (GHz)	$f_{P2}$ (GHz)
2	0	0.85	10
5	3	0.85	10
6	5	0.85	10
9	5	0.85	10

**Table 40 CTLE Set Points for Long Channel, 6 Gbps (Informative)**

$A_{AC}$ (dB)	$A_{DC}$ (dB)	$f_Z$ (GHz)	$f_{P2}$ (GHz)
2	2	1	10
4	4	1	10
8	4	1	10
10	6	1	10

1500 The HS-RX may use the Alternate Calibration Sequence described in *Section 6.13* to perform CTLE  
 1501 adaptation. The system designer should ensure that the length of  $T_{ALTCAL}$  in the transmitter is compatible  
 1502 with the receiver's requirements. The receiver shall complete its calibration within the maximum limit of  
 1503  $T_{ALTCAL}$ . The minimum supported value of  $T_{ALTCAL}$  should be specified in the receiver's datasheet.

1504 The system designer might prefer to set the CTLE parameters at system initialization based on the known  
 1505 characteristics of the channel, transmitter and receiver to avoid CTLE calibration.

**Table 41 HS-RX Reference Receiver Equalization Parameters**

Parameter	Description	Minimum	Nominal	Maximum	Units	Notes
$A_{AC}$	CTLE AC gain	–	–	10	dB	–
$A_{DC}$	CTLE DC gain	–2	–	6	dB	–
$f_z$	CTLE zero frequency	0.4	–	1.2	GHz	–
$f_{p2}$	CTLE second pole frequency	–	–	10	GHz	–

### 9.2.2 Low-Power Receiver

The Low-Power receiver is an un-terminated, single-ended receiver circuit. The LP receiver is used to detect the Low-Power state on each pin. For high robustness, the LP receiver shall filter out noise pulses and RF interference. It is recommended the implementer optimize the LP receiver design for low power.

The input low-level voltage,  $V_{IL}$ , is the voltage at which the receiver is required to detect a low state in the input signal. A lower input voltage,  $V_{IL-ULPS}$ , may be used when the receiver is in the Ultra-Low Power State.  $V_{IL}$  is larger than the maximum single-ended Line voltage during HS transmission. Therefore, an LP receiver shall detect low during HS signaling.

The input high-level voltage,  $V_{IH}$ , is the voltage at which the receiver is required to detect a high state in the input signal. In order to reduce noise sensitivity on the received signal, an LP receiver shall incorporate a hysteresis. The hysteresis voltage is defined as  $V_{HYST}$ .

The LP receiver shall reject any input signal smaller than  $e_{SPIKE}$ . Signal pulses wider than  $T_{MIN-RX}$  shall propagate through the LP receiver.

Furthermore, the LP receivers shall be tolerant of super-positioned RF interference on top of the wanted Line signals. This implies an input signal filter. The LP receiver shall meet all specifications for interference with peak amplitude  $V_{INT}$  and frequency  $f_{INT}$ . The interference shall not cause glitches or incorrect operation during signal transitions.

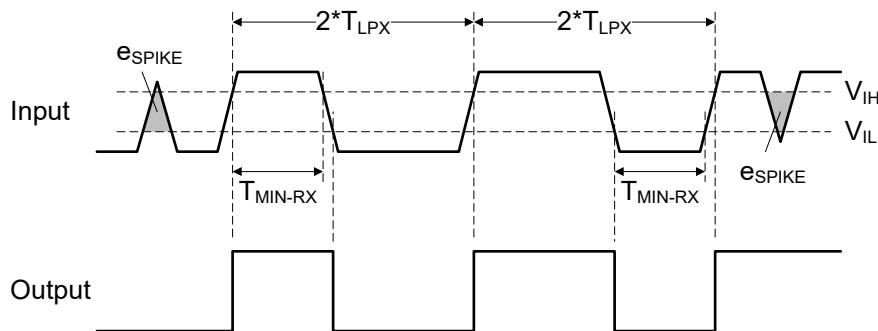


Figure 73 Input Glitch Rejection of Low-Power Receivers

1523

**Table 42 LP Receiver DC specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$V_{IH}$	Logic 1 input voltage	740	—	—	mV	1
$V_{IL}$	Logic 0 input voltage, not in ULP State	—	—	550	mV	—
$V_{IL-ULPS}$	Logic 0 input voltage, ULP State	—	—	300	mV	—
$V_{HYST}$	Input hysteresis	25	—	—	mV	—

**Note:**

1.  $V_{IH}$  applies to all data rates from D-PHY v2.1 onwards. A D-PHY v2.0 or earlier LP receiver is compatible with a D-PHY v2.1 transmitter in LP mode.

1524

**Table 43 LP Receiver AC Specifications**

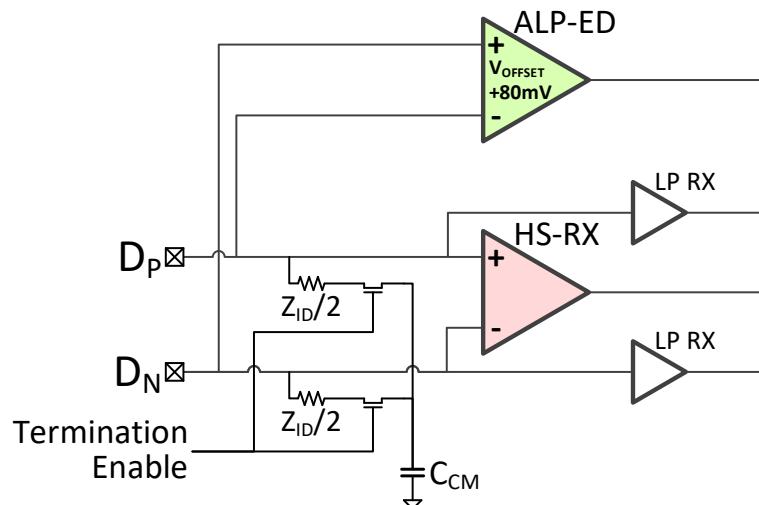
Parameter	Description	Min	Nom	Max	Units	Notes
eSPIKE	Input pulse rejection	—	—	300	V·ps	1, 2, 3
$T_{MIN-RX}$	Minimum pulse width response	20	—	—	ns	4
$V_{INT}$	Peak interference amplitude	—	—	200	mV	—
$f_{INT}$	Interference frequency	450	—	—	MHz	—

**Note:**

1. Time-voltage integration of a spike above  $V_{IL}$  when being in LP-0 state or below  $V_{IH}$  when being in LP-1 state. eSpike generation will ensure the spike is crossing both  $V_{IL,MAX}$  and  $V_{IH,MIN}$  levels.
2. An impulse less than this will not change the receiver state.
3. In addition to the required glitch rejection, implementers shall ensure rejection of known RF-interferers.
4. An input pulse greater than this shall toggle the output.

### 9.2.3 Alternate Low-Power Exit Detector

The ALP Exit Detector (ALP-ED) is a differential receiver circuit. The ALP-ED is used to sense the differential level of the Dn and Dp signals solely for the detection of an ALP Stop or ALP ULPS state transition to an ALP Wake state. No time is defined for the ALP-ED to detect the ALP Wake pulse. The times to exit the Init state, ALP Stop state, or ALP ULPS state are different, allowing for different response times of the ALP-ED to detect the ALP Wake event. The ALP-ED shall detect the Wake event within the defined time it is signaled by the transmitter. A conceptual diagram of a receiver front end including ALP-ED is shown in **Figure 74**.



**Figure 74 Receiver Front End Including ALP-ED**

The ALP-ED shall operate in a signal voltage range defined by  $V_{ILALP}$  and  $V_{IHALP}$  and a common-mode voltage range  $V_{CMRX-ALP}$ .

When enabled the ALP-ED shall indicate an ALP-00 Lane state when the voltage difference of  $V_{DN}$  and  $V_{DP}$  is smaller than the minimum ALP-ED exit threshold voltage  $V_{IDTL-ALP}$ . The ALP-00 Lane state is indicated when the following relation holds:

$$V_{DN}(t) - V_{DP}(t) < V_{IDTL-ALP}$$

When enabled the ALP-ED shall indicate an ALP-01 Lane state when the voltage difference of  $V_{DN}$  and  $V_{DP}$  is larger than the maximum ALP-ED exit threshold voltage  $V_{IDTH-ALP}$ . ALP Wake is indicated when the following relation holds:

$$V_{DN}(t) - V_{DP}(t) > V_{IDTH-ALP}$$

**Table 44 ALP-ED Receiver DC Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$V_{CMRX-ALP}$	Common-mode voltage during ALP Stop and ALP Wake	-50	—	330	mV	1, 2, 3
$V_{IDTH-ALP}$	Differential input high threshold for ALP Wake	—	—	135	mV	—
$V_{IDTL-ALP}$	Differential input low threshold for ALP Stop or ALP ULPS	25	—	—	mV	—
$V_{IHALP}$	Single-ended input high voltage for ALP mode	—	—	485	mV	1, 2
$V_{ILALP}$	Single-ended input low voltage for ALP mode	-50	—	—	mV	1, 2

**Note:**

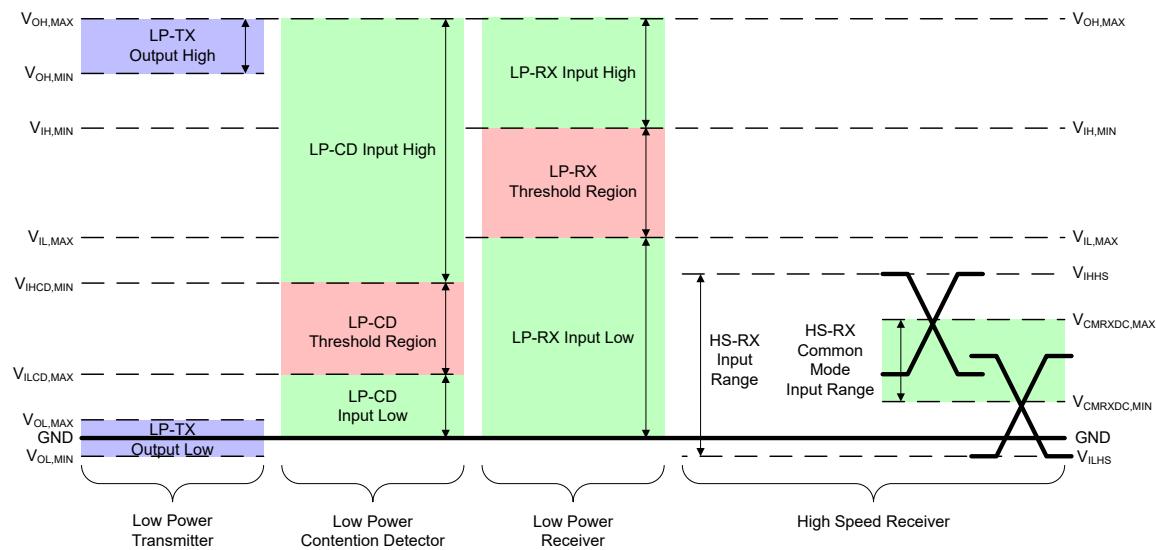
1. Excluding possible additional RF interference of 100 mV peak sine wave beyond 450 MHz.
2. This table value includes a ground shift of 50 mV between the transmitter and the receiver, the static common-mode level tolerance and variations below 450 MHz.
3. Upper limit is defined in line with upper limit of  $V_{CMRX}$ .

### 9.3 Line Contention Detection

The Low-Power receiver and a separate Contention Detector (LP-CD) shall be used in a Bi-directional Data Lane to monitor the Line voltage on each Low-Power signal. This is required to detect Line contention as described in [Section 7.1](#). The Low-Power receiver shall be used to detect an LP high fault when the LP transmitter is driving high and the pin voltage is less than  $V_{IL}$ . Refer to [Table 42](#). The LP-CD shall be used to detect an LP low fault when the LP transmitter is driving low and the pin voltage is greater than  $V_{IHCD}$ . Refer to [Table 45](#). An LP low fault shall not be detected when the pin voltage is less than  $V_{ILCD}$ .

The general operation of a contention detector shall be similar to that of an LP receiver with lower threshold voltages. Although the DC specifications differ, the AC specifications of the LP-CD are defined to match those of the LP receiver and the LP-CD shall meet the specifications listed in [Table 43](#) except for  $T_{MIN-RX}$ . The LP-CD shall sufficiently filter the input signal to avoid false triggering on short events.

The LP-CD threshold voltages ( $V_{ILCD}$ ,  $V_{IHCD}$ ) are shown along with the normal signaling voltages in [Figure 75](#).



**Figure 75 Signaling and Contention Voltage Levels**

**Table 45 Contention Detector (LP-CD) DC Specifications**

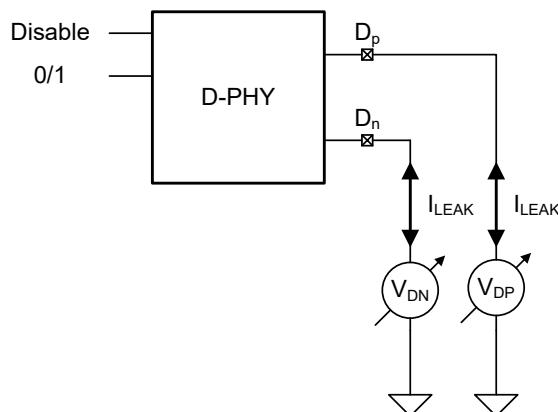
Parameter	Description	Min	Nom	Max	Units	Notes
$V_{IHCD}$	Logic 1 contention threshold	450	—	—	mV	—
$V_{ILCD}$	Logic 0 contention threshold	—	—	200	mV	—

## 9.4 Input Characteristics

No structure within the PHY may be damaged when a DC signal within the signal voltage range  $V_{PIN}$  is applied to a pad pin for an indefinite period of time.  $V_{PIN(ABSMAX)}$  is the maximum transient output voltage at the transmitter pin. The transmitter output voltage shall not exceed  $V_{PIN,MAX}$  for a period greater than  $T_{VPIN(ABSMAX)}$ . When the PHY is in the Low-Power receive mode the pad pin leakage current shall be  $I_{LEAK}$  when the pad signal voltage is within the signal voltage range of  $V_{PIN}$ . When a PHY is operated in the optional LVLP operating range, the pad pin leakage current shall be within the range defined by  $I_{LEAK}$  for pad signal voltages in the range of  $V_{PIN-LVLP}$ . The specification of  $I_{LEAK}$  assures interoperability of any PHY in the LP mode by restricting the maximum load current of an LP transmitter. An example test circuit for leakage current measurement is shown in **Figure 76**.

When operating in ALP mode the pin leakage current mismatch is bounded by  $\Delta I_{LEAK}$ . It is defined as the difference of the pin leakage currents at the D<sub>p</sub> and D<sub>n</sub> pins of a receiver when signal voltages range from  $V_{OLALP,MIN}$  to  $V_{OHALP,MAX}$ .

The ground supply voltages shifts between a Master and a Slave shall be less than  $V_{GNDsh}$ .



**Figure 76 Pin Leakage Measurement Example Circuit**

1571

**Table 46 Pin Characteristic Specifications**

Parameter	Description	Min	Nom	Max	Units	Notes
$V_{PIN}$	Pin signal voltage range	-50	—	1350	mV	—
$V_{PIN-LVLP}$	Pin signal voltage range in LVLP operation	-50	—	1150	mV	—
$I_{LEAK}$	Pin leakage current	-100	—	100	$\mu A$	1
$\Delta I_{LEAK}$	Pin leakage current mismatch	-10	—	10	$\mu A$	5
$V_{GND SH}$	Ground shift	-50	—	50	mV	—
		-5	—	5	mV	2
$V_{PIN(ABSMAX)}$	Transient pin voltage level	-0.15	—	1.45	V	3, 4
$T_{V_{PIN}(ABSMAX)}$	Maximum transient time above $V_{PIN(MIN)}$ or below $V_{PIN(MIN)}$	—	—	20	ns	—

**Note:**

1. When the Lane Module is in LP receive mode and the pad voltage is in the signal voltage range  $V_{PIN}$  for LP mode, or in the signal range  $V_{PIN-LVLP}$  for LVLP operation,  $I_{LEAK}$  should be well within the limits in LVLP operation.
2. Ground shift when operating in Half Swing mode.
3. The voltage overshoot and undershoot beyond the  $V_{PIN}$  range is only allowed for a duration of  $T_{V_{PIN}(ABSMAX)}$  after any LP-0 to LP-1 transition or vice versa. For all other situations it must stay within the  $V_{PIN}$  range.
4. This value includes ground shift.
5. This parameter only applies when ALP mode is used.

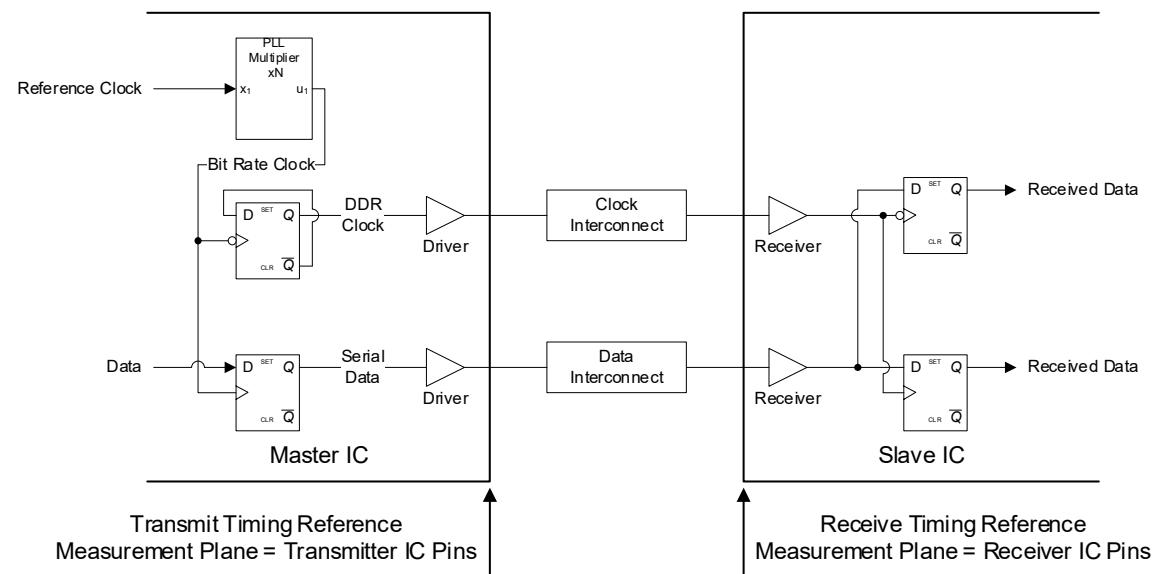
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## 10 High-Speed Data-Clock Timing

This Section specifies the required timings on the High-Speed signaling interface independent of the electrical characteristics of the signal. The PHY is a source synchronous interface in the Forward Direction. In either the Forward or Reverse signaling modes there shall be only one clock source. In the Reverse direction, Clock is sent in the Forward Direction and one of four possible edges is used to launch the data.

Data transmission may occur at any rate greater than the minimum specified data bit rate.

**Figure 77** shows an example PHY Configuration using a DDR Clock and including the reference measurement planes for the specified timings. Note that the effect of signal degradation inside each package due to parasitic effects is included in the timing budget for the transmitter and receiver and is not included in the interconnect degradation budget. See **Section 8** for details.



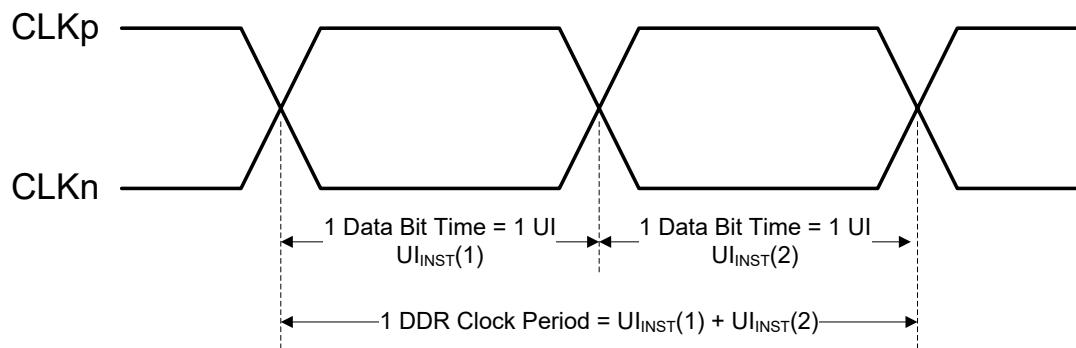
1581  
**Figure 77 Conceptual D-PHY Data and Clock Timing Reference Measurement Planes**

## 10.1 High-Speed Clock Timing

The Master side of the Link shall send a differential clock signal to the Slave side to be used for data sampling. This signal shall be a DDR (half-rate) clock and shall have one transition per data bit time. All timing relationships required for correct data sampling are defined relative to the clock transitions. Therefore, implementations may use frequency spreading modulation on the clock to reduce EMI.

The DDR Clock signal shall maintain a quadrature phase relationship to the data signal. Data shall be sampled on both the rising and falling edges of the Clock signal. The term “rising edge” means “rising edge of the differential signal, i.e. CLKp – CLKn, and similarly for “falling edge”. Therefore, the period of the Clock signal shall be the sum of two successive instantaneous data bit times. This relationship is shown in **Figure 78**.

Note that the UI indicated in **Figure 78** is the instantaneous UI. Implementers shall specify a maximum data rate and corresponding maximum clock frequency,  $f_{hMAX}$ , for a given implementation. For a description of  $f_{hMAX}$ , see **Section 8.3**.



**Figure 78 DDR Clock Definition**

As can be seen in **Figure 77**, the same clock source is used to generate the DDR Clock and launch the serial data. Since the Clock and Data signals propagate together over a channel of specified skew, the Clock may be used directly to sample the Data lines in the receiver. Such a source-synchronous system accommodates certain instantaneous variations in UI within clock and data signals as the low frequency jitter is expected to be tracked up to a data rate/20. Example values are:

- 450 MHz at 9 Gbps, or
- 225 MHz at 4.5 Gbps, or
- 125 MHz at 2.5 Gbps, or
- 75 MHz at 1.5 Gbps.

The high frequency jitter beyond a data rate/2 can be neglected. UI variation is deterministic and random in nature.  $\Delta UI$  bounds the instantaneous variation of UI resulting from deterministic modulating sources. It limits clock impairments such as duty-cycle distortion and periodic jitter.  $\Delta UI$  also accounts for SSC modulation if applicable.  $\Delta UI$  is defined as the ratio of the peak deterministic jitter of  $UI_{INST}$  over the average of  $UI_{INST}$  for an arbitrarily long number of bits.

The allowed instantaneous UI variation can cause large, instantaneous data rate variations. Therefore, devices shall accommodate these instantaneous variations with appropriate logic. It is recommended that devices accommodate these instantaneous variations using some method, such as with appropriate FIFO logic outside of the PHY, or provide an accurate clock source to the Lane Module to eliminate these instantaneous variations, or the data sink outside the PHY can be designed to be tolerant of UI variations.

The Period Jitter of a Clock Lane shall stay within the limits of PJ.

- When SSC is disabled, the Period Jitter is defined as the peak-to-peak deviation of a clock period over the average of 32,000 periods of continuous clock cycles.
- When SSC is enabled, the Period Jitter is defined as the peak-to-peak deviation of a clock period over the average clock cycle of one or more complete SSC modulation cycles.

The UI<sub>INST</sub> specifications for the Clock signal are summarized in *Table 47*.

**Table 47 Clock Signal Specification**

Clock Parameter	Symbol	Min	Typ	Max	Units	Notes
UI instantaneous	UI <sub>INST</sub>	–	–	12.5	ns	1, 2
		–	–	250	ns	6, 7
UI variation	$\Delta$ UI	-0.10	–	0.10	UI	5
		-0.15	–	0.15		4
Period Jitter	PJ	-5.0	–	5.0	% of Clock Period	3
		-7.5	–	7.5		4

**Note:**

1. This value corresponds to a minimum operating data rate of 80 Mbps. This instantaneous value does not take into account UI variations due to jitter or SSC modulation.
2. The minimum UI shall not be violated for any single bit period, i.e., any DDR half cycle within a data burst. The allowed instantaneous UI variation can cause instantaneous data rate variations. Therefore, devices should either accommodate these instantaneous variations with appropriate FIFO logic outside of the PHY or provide an accurate clock source to the Lane Module to eliminate these instantaneous variations.
3. Applies when the nominal DDR Clock period within a single burst (i.e. clock rising edge to next rising edge) is  $\geq 0.444$  ns and  $< 0.8$  ns.
4. Applies when the nominal DDR Clock period within a single burst (i.e. clock rising edge to next rising edge) is  $< 0.444$  ns
5. Applies when the nominal DDR Clock period within a single burst (i.e. clock rising edge to next rising edge) is  $\geq 0.444$  ns and  $< 500$  ns.
6. This value is only applicable in the context of ALP and corresponds to a minimum operating data rate of 4 Mbps in forward direction and 1 Mbps in reverse direction. This instantaneous value does not take into account UI variations due to jitter or SSC modulation.
7.  $\Delta$ UI bounds the deterministic variation of UI.

## 10.2 Forward High-Speed Data Transmission Timing

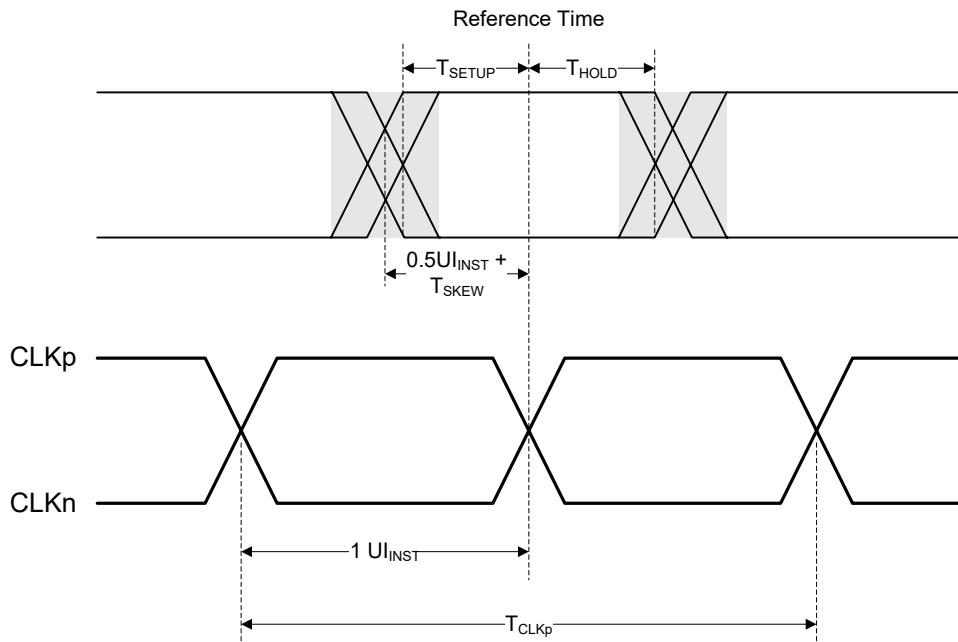
### 10.2.1 Forward High-Speed Data Transmission Timing with a DDR Clock

The timing relationship of the DDR Clock differential signal to the Data differential signal is shown in **Figure 79**. Data is launched in a quadrature relationship to the clock such that the Clock signal edge may be used directly by the receiver to sample the received data.

The transmitter shall ensure that a rising edge of the DDR Clock is sent during the first payload bit of a transmission burst such that the first payload bit can be sampled by the receiver on the rising clock edge, the second bit can be sampled on the falling edge, and all following bits can be sampled on alternating rising and falling edges.

All timing values are measured with respect to the actual observed crossing of the Clock differential signal. The effects due to variations in this level are included in the clock to data timing budget.

Receiver input offset and threshold effects shall be accounted as part of the receiver setup and hold parameters.



**Figure 79 Data to Clock Timing Definitions**

### 10.2.2 Data-Clock Timing Specifications

#### 10.2.2.1 Data Rate $\geq 0.08$ Gbps and $\leq 1$ Gbps

The Data-Clock timing parameters shown in *Figure 79* are specified in *Table 48*. The skew specification,  $T_{SKEW[TX]}$ , is the allowed deviation of the data launch time to the ideal  $\frac{1}{2}$  UI<sub>INST</sub> displaced quadrature clock edge. The setup and hold times,  $T_{SETUP[RX]}$  and  $T_{HOLD[RX]}$ , respectively, describe the timing relationships between the data and clock signals.  $T_{SETUP[RX]}$  is the minimum time that data shall be present before a rising or falling clock edge and  $T_{HOLD[RX]}$  is the minimum time that data shall remain in its current state after a rising or falling clock edge. The timing budget specifications for a receiver shall represent the minimum variations observable at the receiver for which the receiver will operate at the maximum specified acceptable bit error rate.

**Table 48 Data-Clock Timing for  $\geq 0.08$  Gbps and  $\leq 1$  Gbps**

Parameter	Symbol	Min	Max	Unit	Note
<b>HS-TX Timing</b>					
TX Data to Clock Skew	$T_{SKEW[TX]}$	-0.15	0.15	UI <sub>HS</sub>	1
<b>HS-RX Timing</b>					
RX Data to Clock Setup Time Tolerance	$T_{SETUP[RX]}$	0.15	–	UI <sub>HS</sub>	1
RX Data to Clock Hold Time Tolerance	$T_{HOLD[RX]}$	0.15	–	UI <sub>HS</sub>	1
<b>Channel Timing</b>					
Channel Data to Clock Skew	$T_{SKEW[TLIS]}$	-0.2	0.2	UI <sub>HS</sub>	–

**Note:**

1. All jitter specifications are specified with a  $100\ \Omega$  differential termination.

#### 10.2.2.2 Data Rate $> 1$ Gbps and $\leq 1.5$ Gbps

The timing budget has been adjusted between the Transmitter, Receiver, and Channel to support a maximum data rate of 1.5 Gbps.

**Table 49 Data-Clock Timing for  $> 1$  Gbps and  $\leq 1.5$  Gbps**

Parameter	Symbol	Min	Max	Unit	Note
<b>HS-TX Timing</b>					
TX Data to Clock Skew	$T_{SKEW[TX]}$	-0.2	0.2	UI <sub>HS</sub>	1
<b>HS-RX Timing</b>					
RX Data to Clock Setup Time Tolerance	$T_{SETUP[RX]}$	0.2	–	UI <sub>HS</sub>	1
RX Data to Clock Hold Time Tolerance	$T_{HOLD[RX]}$	0.2	–	UI <sub>HS</sub>	1
<b>Channel Timing</b>					
Channel Data to Clock Skew	$T_{SKEW[TLIS]}$	-0.1	0.1	UI <sub>HS</sub>	–

**Note:**

1. All jitter specifications are specified with a  $100\ \Omega$  differential termination.

### 10.2.2.3 Data Rate > 1.5 Gbps and ≤ 4.5 Gbps

For data rates prescribed in this section, jitter specifications have been decomposed into Deterministic jitter and Random jitter based on a target BER of  $10^{-12}$ . Meeting the jitter specifications is a recommendation, whereas meeting the Eye diagram specification is a requirement.

**Table 50 Data-Clock Timing for > 1.5 Gbps and ≤ 4.5 Gbps**

Parameter	Symbol	Min	Max	Unit	Note
<b>HS-TX Timing</b>					
TX Data to Clock Total Jitter	T <sub>JTX</sub>	—	0.3	UI <sub>HS</sub>	1
TX Data to Clock Deterministic Jitter	D <sub>JTX</sub>	—	0.2	UI <sub>HS</sub>	1
TX Data to Clock Random Jitter	R <sub>JTX</sub>	—	0.1	UI <sub>HS</sub>	1
TX Static Data to Clock Skew	T <sub>SKEW[TX]</sub> static	-0.2	0.2	UI <sub>HS</sub>	1
<b>HS-RX Timing</b>					
RX Data to Clock Total Jitter Tolerance	T <sub>JRX</sub>	0.50	—	UI <sub>HS</sub>	1
RX Data to Clock Deterministic Jitter Tolerance	D <sub>JRX</sub>	0.40	—	UI <sub>HS</sub>	1
RX Data to Clock Random Jitter Tolerance	R <sub>JRX</sub>	0.10	—	UI <sub>HS</sub>	1
RX Static Data to Clock Skew Tolerance	T <sub>SKEW[RX]</sub> static	-0.3	0.3	UI <sub>HS</sub>	1
<b>Channel Timing</b>					
Channel Static Data to Clock Skew	T <sub>SKEW[TLIS]</sub> static	-0.1	0.1	UI <sub>HS</sub>	—
<b>Limit for BER</b>					
Target Bit Error Rate	BER	—	$10^{-12}$	—	—
Q Factor for BER	QBER	—	7.0345	—	—

**Note:**

1. All jitter specifications are specified with a  $100\ \Omega$  differential termination

#### 10.2.2.4 Data Rate > 4.5 Gbps and ≤ 9.0 Gbps

For data rates prescribed in this section, jitter specifications have been decomposed into Deterministic jitter and Random jitter based on a target BER of  $10^{-12}$ . Meeting the jitter specifications is a recommendation, whereas meeting the Eye diagram specification is a requirement.

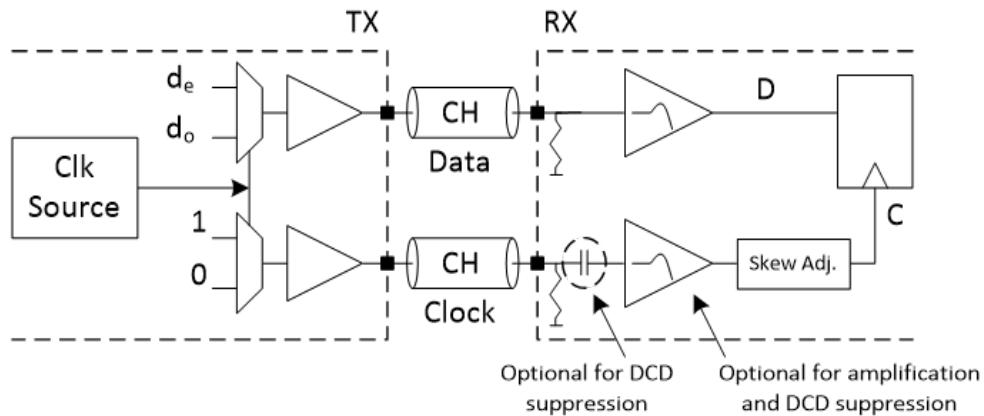
**Table 51 Data-Clock Timing for > 4.5 Gbps and ≤ 9.0 Gbps**

Parameter	Symbol	Min	Max	Unit	Note
<b>HS-TX Timing</b>					
TX Data to Clock Total Jitter	TJ <sub>TX</sub>	–	0.3	UI <sub>HS</sub>	1
TX Data to Clock Deterministic Jitter	DJ <sub>TX</sub>	–	0.2	UI <sub>HS</sub>	1
TX Data to Clock Random Jitter	RJ <sub>TX</sub>	–	0.1	UI <sub>HS</sub>	1
TX Static Data to Clock Skew	T <sub>SKEW[TX]</sub> static	-0.25	0.25	UI <sub>HS</sub>	1
<b>HS-RX Timing</b>					
RX Data to Clock Total Jitter Tolerance	TJ <sub>RX</sub>	0.50	–	UI <sub>HS</sub>	1
RX Data to Clock Deterministic Jitter Tolerance	DJ <sub>RX</sub>	0.40	–	UI <sub>HS</sub>	1
RX Data to Clock Random Jitter Tolerance	RJ <sub>RX</sub>	0.10	–	UI <sub>HS</sub>	1
RX Static Data to Clock Skew Tolerance	T <sub>SKEW[RX]</sub> static	-0.4	0.4	UI <sub>HS</sub>	1
<b>Channel Timing</b>					
Channel Static Data to Clock Skew	T <sub>SKEW[TLIS]</sub> static	-0.15	0.15	UI <sub>HS</sub>	–
<b>Limit for BER</b>					
Target Bit Error Rate	BER	–	$10^{-12}$	–	–
Q Factor for BER	QBER	–	7.0345	–	–

**Note:**

1. All jitter specifications are specified with a  $100\ \Omega$  differential termination

1653 A lossy channel amplifies the duty-cycle distortion (DCD) of the high-speed forwarded clock. To reduce  
1654 this DCD amplification effect, the HS receiver can use duty cycle correction techniques (such as an AC-  
1655 coupling capacitor) after the RX Clock Lane receiver termination, shown in **Figure 80**. Additionally, CTLE  
1656 or other frequency peaking circuits with gains at the clock frequency may be utilized to restore the received  
1657 forwarded clock to proper levels.



1658

**Figure 80 Duty Cycle Distortion Suppression Technique**

### 10.2.3 Normative Spread Spectrum Clocking (SSC)

Spread Spectrum Clocking (sometimes referred to as “Spectrum Spread Clocking”) is a common technique where a low frequency modulation is added to the Transmitter’s clock to reduce the peak emissions.

All Transmitters conformant to D-PHY v2.0 and above shall support SSC as per **Table 52** for data rates operating above 2.5 Gbps.

All Receivers conformant to D-PHY v2.0 and above shall support SSC as per **Table 52** for data rates operating above 2.5 Gbps.

All Transmitters conformant to D-PHY v2.0 and above shall provide the system integrator with a mechanism to enable/disable SSC transmissions.

SSC can be used in HS Data Transmission mode. If used during HS Data Transmission mode, SSC transmission shall be consistent during the entire mode.

SSC should not be used in Escape Mode.

SSC shall be implemented within the Transmitter such that a single modulated profile, single modulation rate and a single SSC deviation is common between the clock and all High-speed data lanes.

All SSC parameters are defined for the HS Clock.

Modulation using a triangular profile for the frequency spread should be the baseline. Implementers can provide further emissions reduction using more-complex modulation profiles.

1675 **Table 52 Spread Spectrum Clocking Requirements**

Parameter	Symbol	Min	Max	Units	Notes
Modulation Rate	T <sub>SSC-MOD-RATE</sub>	30	33	kHz	–
SSC Deviation	T <sub>SSC-FREQ-DEV</sub>	-5000	0	PPM	1, 2
SSC df/dt	SSC <sub>df/dt</sub>	N/A	1250	PPM/μs	3, 4, 5

**Note:**

1. The required SSC deviation is also called “Down-Spread”.
2. Any implementation with an SSC deviation significantly smaller than 5000 PPM may fail in EMI testing below 1 GHz clock rate (Data Rate < 2 Gbps).
3. df/dt limit shall be for clock and all data lanes.
4. Measured over a 0.5 μs interval using an alternating 010101010... input pattern at highest data rate. The measurements shall be low pass filtered using a filter with 3 dB cutoff frequency that is 60 times the modulation rate. The filter stopband rejection shall be a second order low-pass of 40 dB per decade. Evaluation of the maximum df/dt is achieved by inspection of the low-pass filtered waveform.
5. Maximum change rate of 1250 PPM/μs is limiting the absolute value of the df/dt.

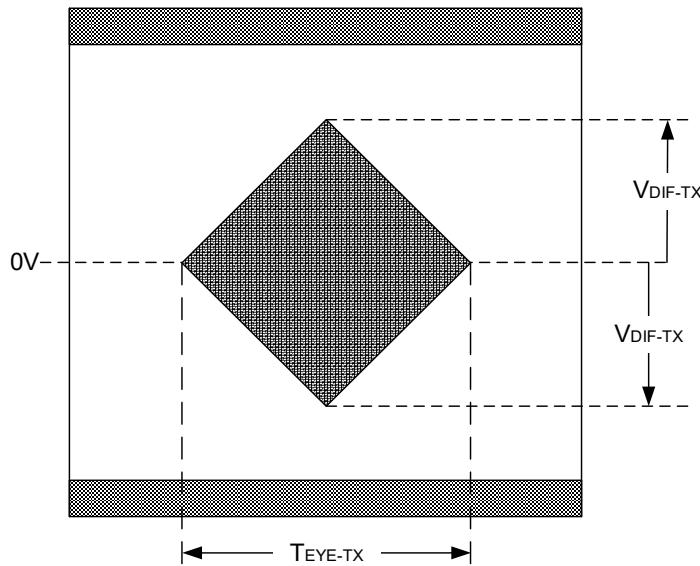
#### 10.2.4 Transmitter Eye Diagram Specification

The Eye Diagram Specification shown below shall be used to evaluate the performance of Transmitters operating at data rates greater than 1.5 Gbps, and is specified for differential data signals with regard to the differential zero of the forwarded clock. The Transmitter Eye Diagram requirements are specified in **Table 53**, which use **Figure 81** as a reference.

The Transmitter Eye Diagram Specification applies to both Data Lanes and Clock Lanes.

The method to measure the Transmitter Eye Diagram of the Clock Lane is defined in the CTS document.

The Clock Lane signal is also constrained, as per the HS Clock Timing defined in **Section 10.1**.

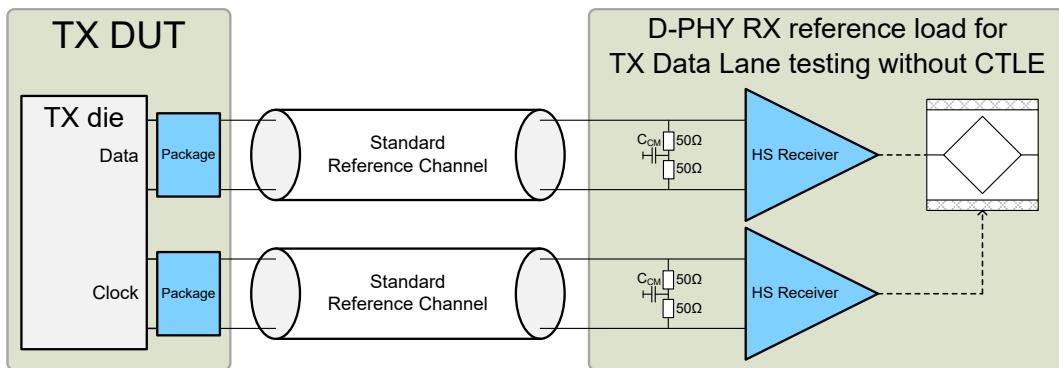


**Figure 81 TX Eye Diagram Specification**

**Table 53 Transmitter Eye Diagram Specification**

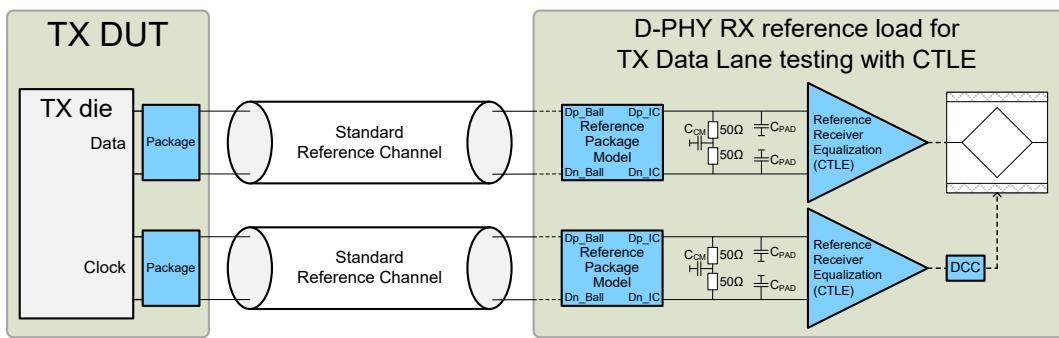
Bit Error Rate	$T_{EYE-TX}$	$V_{DIF-TX}$
$10^{-12}$	0.5 UI	40 mV

At data rates less than or equal to the rates specified in *Table 37, “Maximum Data Rates Without Reference Receiver Equalization”*, the Eye Diagram for the transmitter is specified after the Transmitter output passes through the reference channels described in *Section 8*, with the termination at the output of the reference channel ( $Z_{ID}$ ) equal to  $100\ \Omega$ . This configuration is shown in *Figure 82*. The reference channel includes only insertion loss as defined in the TLIS specification in *Section 8.6.1.2*.



**Figure 82 Transmitter Eye Measurement Without Receiver Equalization**

At symbol rates greater than the rates specified in *Table 37*, the eye will become closed, so it is necessary to use Receiver Equalization to open the eye. For such data rates there shall be no incursions into the Eye Interior when the Transmitter transmits a pseudorandom test pattern into the reference channels described in *Section 8*, followed by the Reference Package Model described in *Annex F*, with a termination at the output of the Reference Package Model ( $Z_{ID}$ ) equal to  $100\ \Omega$  in parallel with the  $C_{PAD}$  capacitance budget of  $1.0\ pF$ . The Reference Package Model effectively increases the RX capacitance. The resulting signal is processed by the Reference Receiver Equalization (CTLE). This concept is illustrated in *Figure 83*. The reference channels are described in *Section 8.6.1.2*. Guidelines for setting the CTLE parameters for the reference channels described in *Section 8.6.1.2* are provided in *Table 38*, *Table 39*, and *Table 40*.

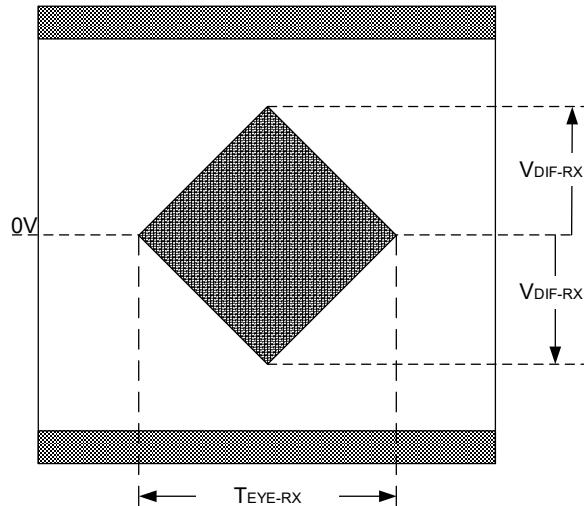


**Figure 83 Transmitter Eye Measurement at High Data Rates with Receiver Equalization**

During transmitter eye diagram measurement, the duty cycle distortion in the clock path will be removed before extracting the data path Eye Diagram. Duty cycle correction (DCC) methodology will be described in the Conformance Test Suite.

### 10.2.5 Receiver Eye Diagram Specification

The Receiver Eye Diagram Specification shown below defines the worst-case Eye that the Receiver shall tolerate while injected at the Rx pads. This Eye Diagram Specification applies to Receivers operating at data rates above 1.5 Gbps.



1707

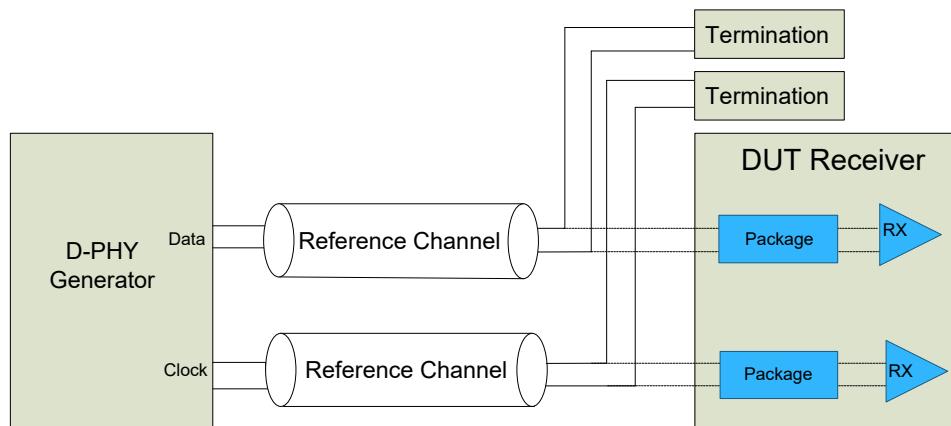
**Figure 84 Receiver Eye Diagram Specification**

1708

**Table 54 Receiver Eye Diagram Specification**

Bit Error Rate	T <sub>EYE-RX</sub>	V <sub>DIF-RX</sub>
10 <sup>-12</sup>	0.5 UI	40 mV

1709



**Figure 85 Receiver Eye Diagram Validation Setup**

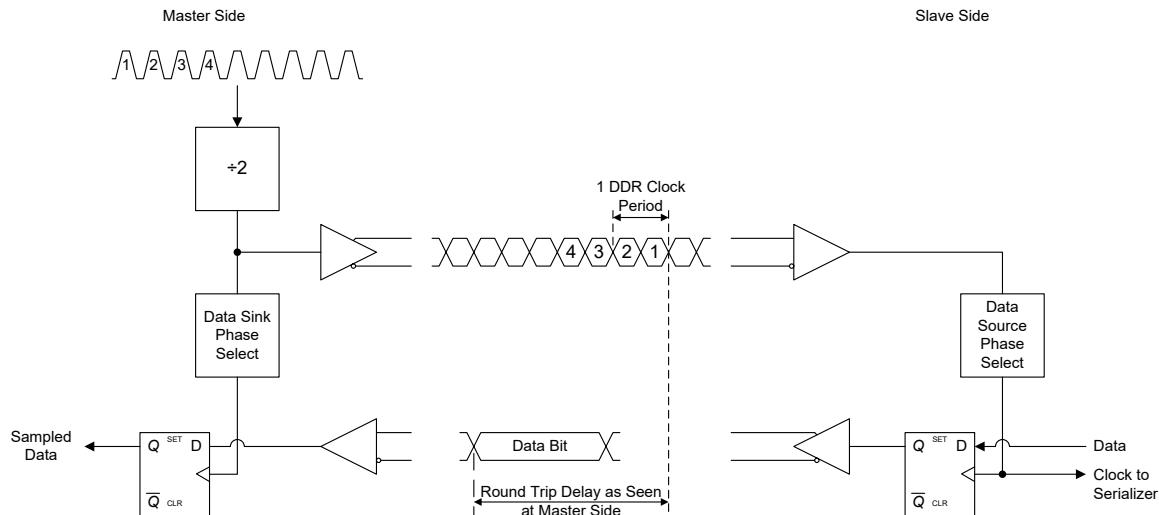
## 10.3 Reverse High-Speed Data Transmission Timing

This Section only applies to Half-Duplex Lane Modules that include Reverse High-Speed Data Transmission functionality and only DDR Clock operation.

A Lane enters the Reverse High-Speed Data Transmission mode by means of a Link Turnaround procedure as specified in [Section 6.5](#). Reverse Data Transmission is not source-synchronous; the Clock signal is driven by the Master side while the Data Lane is driven by the Slave side. The Slave Side transmitter shall send one data bit every two periods of the received Clock signal. Therefore, for a given Clock frequency, the Reverse direction data rate is one-fourth the Forward Direction data rate. The bit period in this case is defined to be  $4 \cdot UI_{INST}$ .  $UI_{INST}$  is the value specified for the full-rate forward transmission.

Note that the clock source frequency may change between transmission bursts. The Reverse Direction data rate depends on the clock source frequency. It is one-fourth of the Forward Direction data rate. The Reverse direction data rate can be altered by changing the frequency of the Clock Lane. For example, the clock source frequency can be reduced for Reverse Data Transmission if the needed data rate in Reverse Direction is less than one-fourth of the Forward Direction data rate. The change of the clock source frequency is described in [Section 9.12.5.6](#) in the CSI-2 Specification [[MIPI02](#)]. However, all Data Lanes shall be in a Low-Power state before changing the clock source frequency. The electrical and timing characteristics of an HS-TX or HS-RX implementation in the Reverse High-Speed Data Transmission mode should conform to the maximum supported High-Speed data rate in Reverse Direction.

The conceptual overview of Reverse HS Data Transmission is shown in [Figure 86](#).



**Figure 86 Conceptual View of HS Data Transmission in Reverse Direction**

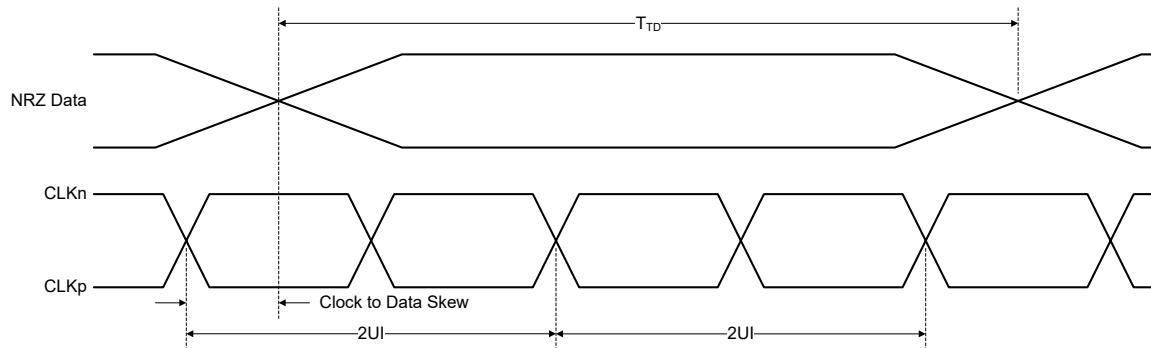
There are four possible phase relationships between clock and data signals in the Reverse direction. The Clock phase used to send data is at the discretion of the Slave side, but once chosen it shall remain fixed throughout that data transmission burst. Signal delays in the interconnect, together with internal signal delays in the Master and Slave Modules, cause a fixed, but unknown, phase relationship in the Master Module between received (Reverse) Data and its own (Forward) Clock. Therefore, the Reverse traffic arriving at the Master side may not be phase aligned with the Forward Direction clock.

Synchronization between Clock and Data signals is achieved with the Sync sequence sent by the Slave during the Start of Transmission (SoT). The Master shall include sufficient functionality to correctly sample the received data given the instantaneous UI variations of the Clock sent to the Slave.

1738 Reverse transmission by the Slave side is one-fourth of the Forward Direction speed, based on the Forward  
1739 Direction Clock as transmitted via the Clock Lane. This ratio makes it easy to find a suitable phase at the  
1740 Master Side for Data recovery of Reverse direction traffic.

1741 The known transitions of the received Sync sequence shall be used to select an appropriate phase of the  
1742 clock signal for data sampling. Thus, there is no need to specify the round trip delay between the source of  
1743 the clock and the receiver of the data.

1744 The timing of the Reverse transmission as seen at the Slave side is shown in **Figure 87**.



1745

**Figure 87 Reverse High-Speed Data Transmission Timing at Slave Side**

## 10.4 Operating Modes: Data Rate and Channel Support Guidance

1746 This Section serves as a guide for achievable system-level performance.

1747 **Table 55** shows possible configurations of a transmitter, receiver, and channel that can be supported based  
1748 on the D-PHY specification.

**Table 55 Operating Modes and Guidance**

Data Rate	Transmitter		Receiver Equalization	Receiver Termination	Reference Channel	Notes
	Swing	De-emphasis				
≤ 11.0 Gbps	Default	EQ2	CTLE	80–125 Ω	Short	2
≤ 9.0 Gbps	Default	EQ2	CTLE	80–125 Ω	Standard	—
≤ 6.0 Gbps	Default	EQ2	CTLE	80–125 Ω	Long	—
≤ 6.5 Gbps	Default	EQ2	None	80–125 Ω	Short	1
≤ 4.5 Gbps	Default	EQ2	None	80–125 Ω	Standard	—
≤ 2.5 Gbps	Default	EQ2	None	80–125 Ω	Long	—
≤ 2.5 Gbps	Default	None	None	80–125 Ω	Standard	—
≤ 3.5 Gbps	Half Swing	EQ1	None	80–125 Ω	Short	—
≤ 2.0 Gbps	Half Swing	EQ1	None	80–125 Ω	Standard	—
≤ 1.0 Gbps	Half Swing	EQ1	None	80–125 Ω	Long	—
≤ 1.5 Gbps	Half Swing	EQ1	None	Unterminated	Short/Standard	—
≤ 1.0 Gbps	Half Swing	EQ1	None	Unterminated	Long	—
≤ 1.5 Gbps	Half Swing	None	None	Unterminated	Short	—
≤ 1.0 Gbps	Half Swing	None	None	Unterminated	Standard	—
≤ 0.75 Gbps	Half Swing	None	None	Unterminated	Long	—

**Note:**

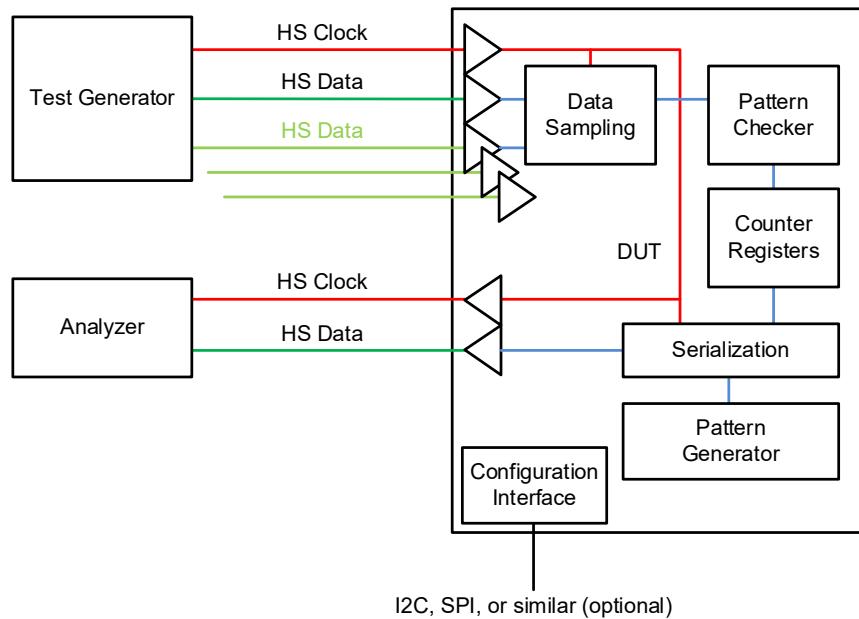
1. For certain channel conditions, there is margin to operate D-PHY above 4.5 Gbps, also without CTLE. 6.5 Gbps is possible with a short channel, but this Specification does not detail any parameters beyond 4.5 Gbps. Implementers are left to extend operation to this higher data rate.
2. For certain channel conditions, there is margin to operate D-PHY above 9.0 Gbps with CTLE. 11.0 Gbps is possible with a short channel, but this Specification does not detail any parameters beyond 9.0 Gbps.

## 11 Regulatory Requirements

1749

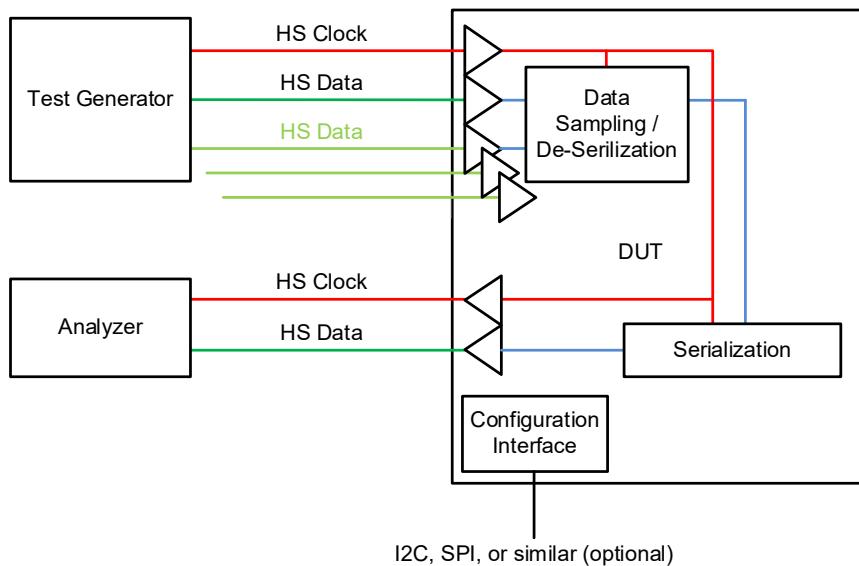
All MIPI D-PHY based devices should be designed to meet the applicable regulatory requirements.

## 12 Built-In HS Test Mode (Informative)



1750

**Figure 88 Testing with Pattern Checkers and Generators**



1751

**Figure 89 Alternative Testing with Loopback Mode**

## 12.1 Introduction

1752 The standardized built-in test mode simplifies testing of the PHY layer of an Rx and a Tx. It may also be  
1753 used for production testing, verification, interoperability testing, and self-testing. It requires a minimum set  
1754 of registers to contain error and bit counters (see **Figure 88**), or alternatively support loopback testing (see  
1755 **Figure 89**). The test mode is a PHY layer mode. As a result, use of the test mode should not require any  
1756 protocol layers. It focuses on HS testing, and does not cover LP or ALP mode operations or the transitions  
1757 in and out of HS mode. This new mode will simplify the HS testing, and allows using the same or even less  
1758 complicated / expensive equipment for testing new features such as SSC, Jitter, and equalization.

1759 The HS test mode allows testing the tolerance of:

- 1760 • Jitter
- 1761 • SSC parameters
- 1762 • Equalization parameters
- 1763 • HS amplitude and offset
- 1764 • Clock to Data timing
- 1765 • Intra-Lane timing, if the device allows multi-Lane testing
- 1766 • Cross talk, if the device allows multi-Lane testing

1767 It does not allow testing of:

- 1768 • LP and ALP mode timing and levels
- 1769 • LP-HS and ALP-HS timings
- 1770 • ULPS mode timings and levels
- 1771 • Protocol specific parameters

## 12.2 Entering the HS Test Mode

1772 Since the protocol should not be involved in entering the HS test mode, a simple pattern or sequence of  
1773 Line states is defined to enter the test mode.

1774 The LP Trigger Escape Entry Code sequence from **Table 10** (01011101) should be used to enter the test  
1775 mode when operating in LP mode. An ALP Control Burst with Control Code from **Table 12**  
1776 (0101110110100010) should be used when operating in ALP mode.

1777 If the device allows configuration via an external interface, then the test mode may also be activated by a  
1778 configuration sequence via the external interface. In this case the vendor should publish the sequence  
1779 required to activate the test mode.

1780 In HS test mode the Rx of the device should expect HS data. If comparators and (bit- and error-) counters  
1781 to determine BER are built in, then these registers should be reset and the device should do the Clock-Data  
1782 alignment as soon as it detects the alignment pattern a HS clock/2 pattern on all tested lanes. For a multi-  
1783 Lane device this feature can be used to determine which Lane(s) is/are tested. The Tx side should do the  
1784 same as the test generator. It should send the initializing sequence for the HS test mode followed by the  
1785 alignment pattern.

## 12.3 HS Test Mode

After the alignment pattern the test generator should send a sync word on all tested data lanes (00011101) to allow the device to do the symbol synchronization. On the Clock Lane the clock pattern should be sent continuously. The test pattern is vendor specific and can be one or more of the following

- PRBS (PRBS 9 is preferred, Degree:  $x^0+x^5+x^9$ )
- The conformance pattern (see CTS for definition)
- An application specific pattern.

The PRBS9 is the preferred pattern. If the device supports this then for interoperability can be ensured. The definition of the pattern checkers follows the description of Section 12 of the C-PHY Specification [[MIPI01](#)]. For a clarification of the implementation, the following pattern should be expected with a register initialized to 01111111 (Q9:Q1):

```
11111111_10000011_11011111_00010111_
00110010_00001001_01001110_11010001_
11100111_11001101_10001010_10010001_
11000110_11010101_11000100_11000100_
01000000_00100001_00011000_01001110_
01010101_10000110_11110100_11011100_
10001010_00010101_10100111_11101100_
10010010_11011111_10010011_01010011_
00110000_00011000_11001010_00110100_
10111111_10100010_11000111_01011001_
01100111_10001111_10111010_00001101_
01011101_11011000_00101101_0111101_
01010100_00001010_01010111_10010111_
01110000_00111001_11010010_01111010_
11101010_00100100_00110011_10000101_
11101101_10011010_00011101_1110000//1
11111111_00000111_10111110_00101110_
01100100_00010010_10011101_10100011_
11001111_10011011_00010101_00100011_
10001101_10101011_10001001_10001000_
10000000_01000010_00110000_10011100_
10101011_00001101_11101001_10111001_
00010100_00101011_01001111_11011001_
00100101_10111111_00100110_10100110_
01100000_00110001_10010100_01101001_
01111111_01000101_10001110_10110010_
11001111_00011111_01110100_00011010_
11011011_10110000_01011010_11111010_
10101000_00010100_10101111_00101110_
11100000_01110011_10100100_11110101_
11010100_01001000_01100111_00001011_
11011011_00110100_00111011_110000//11
11111110
```

The repetition period is 511 bits, and it starts with eight ones of the PRBS9 sequence based on seed of 01111111 (Q9:Q1). In the PRBS9 sequence shown above, every repetition period is separated by a red slash ('/'), and every byte is separated by an underscore ('\_').

If a vendor specific pattern is used, then the device vendor should supply the specification of the test pattern. Comparable results will be obtained in case that this pattern is balanced and the transition density is close to the value for a PRBS9 or the conformance pattern.

1835 In case of internal pattern checkers, it is possible for the test generator and the pattern checkers to lose  
1836 synchronization. In this case the BER will never get back to 0 again, even if the data is recognized properly  
1837 again. In this case there are two possibilities:

- 1838 • One can be that the pattern checkers do a re-initialization with the default seed and wait for the  
1839 seed pattern in case of a PRBS as test pattern, or wait for the first word(s) in the test pattern. In  
1840 this case, the first word(s) should be somehow unique. The detection of a lost synchronization may  
1841 be done internally, if too many errors occur (threshold vendor specific).
- 1842 • The second possibility to re-initialize a synchronization loss may be to interrupt the clock. In this  
1843 case, the re-initialization can be triggered from external by stopping the clock. The device should  
1844 not exit from HS Test mode. The de-serialization may be restarted by a sync word followed by the  
1845 test pattern. An interruption of the clock should reset the PRBS generators, and the device should  
1846 wait again for the sync pattern. The interruption detection time should set equal to the  $T_{CLK-MISS}$   
1847 time (see **Table 18**).

1848 In case of using loopback (see **Figure 89**) for test mode, the test pattern should be send back via one or  
1849 more Tx lanes (defined by the vendor). The loopback data signal should be retimed with the received clock.  
1850 By this filtering, any jitter on data will be removed, while the clock received by the Rx should be routed  
1851 through without any retiming.

1852 Note: For PHY interoperability (without testing equipment), it is required that at least one device have  
1853 integrated pattern generators and checkers (see **Figure 88**), and that both devices support the same test  
1854 pattern. In this case, implementing the pattern-generators-and-checker method is recommended as this  
1855 gives more flexibility then the loopback mode.

1856 The equalization setting should be kept constant since the last HS setting before activating the test mode.  
1857 Tx testing can be done by using a test generator applying the necessary pattern for Tx testing (see CTS).  
1858 Triggering the Tx HS test pattern generation requires activating the test mode via an external interface. If  
1859 the test mode was triggered by a test generator via the Rx side of the device, then the Tx needs to send the -  
1860 same data as received by Rx (loopback) or the counter values (error checkers).

1861 In case of using pattern checkers and counter register, the vendor should specify how to access these  
1862 registers. Access to these counters can be implemented either via an external interface such as I2C or SPI,  
1863 or else the device should send the counter values via its one D-PHY Tx Lane. The counters should have  
1864 enough depth to allow at least 20 seconds of operation without overrun. In case of overflow the counters  
1865 should start over with 0. The bit/frame counter register can contain a bit counter or a frame counter, in  
1866 which the vendor needs to specify the factor between counter value and number of received bits. The error  
1867 counter always should contain the number of errors. To support Tx testing of devices that support the test  
1868 mode via pattern checkers, the Tx lanes can send the bit/error counters as continuous data stream; or, if the  
1869 values of the counters are not sent via the Link, it can automatically send a test pattern specified by the  
1870 device vendor.

## 12.4 Special Case: Multi-Lane Testing

1871 If the device allows using PRBS as test pattern on more than one Lane, each Lane should use a different  
1872 seed. Lane 0 should use 0xFF, Lane 1 should use 0xFE, and so on, to have different data crossing the Link  
1873 on each Lane. This allows cross talk to be tested. If an application-specific pattern is used, these patterns  
1874 should also be constructed such that they are different from Lane to Lane. The exact definition of  
1875 application-specific test patterns is left to the device vendor, and must be documented by the device vendor.

## 12.5 Exiting from HS Test Mode

1876 After entering the test mode, the device should remain in test mode until directed to leave test mode, for  
1877 example by an LP11 state applied for at least 500 ms, or by the device being power cycled.

1878 If it is possible to configure the test mode via an external interface, then the same interface can also be used  
1879 to exit the test mode. In this case, the device vendor must document the exit sequence.

## Annex A Logical PHY-Protocol Interface Description (Informative)

The PHY Protocol Interface (PPI) is used to make a connection between the PHY Lane Modules and the higher protocol layers of a communication stack. The interface described here is intended to be generic and application independent.

This annex is informative only. Conformance to the D-PHY specification does not depend on any portion of the PPI defined herein. Because of that, this annex avoids normative language and does not use words like “shall” and “should.” Instead, present tense language has been used to describe the PPI, utilizing words like “is” and “does.” The reader may find it helpful to consider this annex to be a description of an example implementation, rather than a specification. The signaling interface described in this annex, The PHY Protocol Interface (PPI) is optional. However, if a module includes the PPI Interface, it shall implement it as described in this annex.

This PPI is optimized for controlling a D-PHY and transmitting and receiving parallel data. The interface described here is defined as an on-chip connection, and does not attempt to minimize signal count or define timing parameters or voltage levels for the PPI signals.

### A.1 Signal Description

**Table 56** defines the signals used in the PPI. For a PHY with multiple Data Lanes, a set of PPI signals is used for each Lane. Each signal has been assigned into one of six categories: High-Speed transmit signals, High-Speed receive signals, Escape Mode transmit signals, Escape Mode receive signals, control signals, and error signals. Bi-directional High-Speed Data Lanes with support for Bi-directional Escape Mode include nearly all of the signals listed in the table. Unidirectional Lanes or Clock Lanes include only a subset of the signals. The direction of each signal is listed as “I” or “O”. Signals with the direction “I” are PHY inputs, driven from the Protocol. Signals with the direction “O” are PHY outputs, driven to the Protocol. For this logical interface, most clocks are described as being generated outside the PHY, although any specific PHY may implement the clock circuit differently.

The “Categories” column in **Table 56** indicates for which Lane Module types each signal applies. The category names are described in **Table 1** and are summarized here for convenience. Each category is described using a four-letter acronym, defined as <Side, HS-capabilities, Escape-Forward, Escape-Reverse>. The first letter, Side, can be M (Master) or S (Slave). The second letter, High-Speed capabilities, can be F (Forward data), R (Reverse and Forward data), or C (Clock). The third and fourth letters indicate Escape Mode capability in the Forward and Reverse directions, respectively. For Data Lanes, the third letter can be A (All) or E (Events – Triggers and ULPS only), while the fourth letter can be A (All, including LPDT), E (Events, triggers and ULPS only), Y (Any but not None: so A or E) or N (None). For a Data Lane, any of the four identification letters can be replaced by an X, to indicate that each of the available options is appropriate. For a Clock Lane, only the first letter can be X, while the other three letters are always CNN.

The signal description includes options for the designer to choose a data path width to simplify the task of timing closure between the D-PHY and high-level protocol logic.

The protocol and D-PHY will select data path widths as described in **Table 56** that are most appropriate for the operation. The bus width selection is based on logical binary input as explained in TxDataWidthHS[1:0] and RxDataWidthHS[1:0]. Bus width can be modified based on operational requirements after the completion of the current burst. It is not necessary for the PPI data path width of the transmit function in one IC to match the PPI data path width of the receive function in another IC. The D-PHY has the ability to transmit and receive any integer number of words greater than zero, regardless of the width of the PPI Tx and Rx data paths. A set of data-valid signals accompany each set of data transferred over the PPI to indicate which words contain valid data to transmit or which words contain data that was actually received from the channel.

**Table 56 PPI Signals**

<b>Symbol</b>	<b>Dir</b>	<b>Categories</b>	<b>Description</b>
<b>High-Speed Transmit Signals</b>			
TxWordClkHS	O	MXXX SRXX	<p>High-Speed Transmit Word Clock.</p> <p>This is used to synchronize PPI signals in the high-speed transmit clock domain. It is recommended that all transmitting Lane Modules share one TxWordClkHS signal. The frequency of TxWordClkHS is dependent upon the width of the High-Speed Transmit Data, as follows:</p> <ul style="list-style-type: none"> <li>• 8-bit width, TxDataHS[7:0], the High-Speed Transmit Word Clock is exactly 1/8 the high-speed data rate.</li> <li>• 16-bit width, TxDataHS[15:0], the High-Speed Transmit Word Clock is exactly 1/16 the high-speed data rate.</li> <li>• 32-bit width, TxDataHS[31:0], the High-Speed Transmit Word Clock is exactly 1/32 the high-speed data rate.</li> </ul>
TxDataWidthHS[1:0]	I	MXXX SRXX	<p>High-Speed Transmit Data bus Width Select.</p> <p>Selects the bus width of TxDataHS:</p> <ul style="list-style-type: none"> <li>• TxDataWidthHS[1:0] = 00: 8-bit, TxDataHS[7:0].</li> <li>• TxDataWidthHS[1:0] = 01: 16-bit, TxDataHS[15:0]</li> <li>• TxDataWidthHS[1:0] = 10: 32-bit, TxDataHS[31:0]</li> <li>• TxDataWidthHS[1:0] = 11: not used, reserved.</li> </ul> <p>An implementation may support any data width - one fixed width, or subset of widths or all widths defined above.</p>
TxDataHS[7:0], or TxDataHS[15:0], or TxDataHS[31:0]	I	MXXX SRXX	<p>High-Speed Transmit Data bus.</p> <p>High-speed data to be transmitted. If the TxWordValidHS signals indicate that more than 8 bits are to be transmitted, then the byte transmission order over the physical interface is TxDataHS[7:0] followed by TxDataHS[15:8] followed by TxDataHS[23:16] followed by TxDataHS[31:24]. Data is captured on rising edges of TxWordClkHS. The following signals are defined for the High-Speed Transmit Data bus based on the width of the transmit data path:</p> <ul style="list-style-type: none"> <li>• 8-bit width – TxDataHS[7:0]</li> <li>• 16-bit width – TxDataHS[15:0]</li> <li>• 32-bit width – TxDataHS[31:0]</li> </ul> <p>An implementation may support any data width - one fixed width, or subset of widths or all widths defined above. The LSB will be transmitted as the first bit and the MSB will be transmitted as the last bit.</p>

Symbol	Dir	Categories	Description
TxWordValidHS[0], or TxWordValidHS[1:0], or TxWordValidHS[3:0]	I	MXXX SRXX	<p>High-Speed Transmit Word Data Valid.</p> <p>When the High-Speed Transmit Data width is greater than 8 bits it is necessary to indicate which 8-bit segments contain valid transmit data to be able to transmit any number of words. The following TxWordValidHS signals are defined based on the width of the transmit data path:</p> <ul style="list-style-type: none"> <li>• 8-bit width – TxWordValidHS[0]</li> <li>• 16-bit width – TxWordValidHS[1:0]</li> <li>• 32-bit width – TxWordValidHS[3:0]</li> </ul> <p>The following Transmit Word Data Valid signals indicate which bits of the TxDataHS data bus contain valid data to transmit as follows:</p> <ul style="list-style-type: none"> <li>• TxWordValidHS[0] – TxDataHS[7:0] contains valid data to be transmitted</li> <li>• TxWordValidHS[1] – TxDataHS[15:8] contains valid data to be transmitted</li> <li>• TxWordValidHS[2] – TxDataHS[23:16] contains valid data to be transmitted</li> <li>• TxWordValidHS[3] – TxDataHS[31:24] contains valid data to be transmitted.</li> </ul> <p>For an 8-bit transmit data width, TxWordValidHS[0] is driven to 0x1 when TxRequestHS is asserted.</p> <p>For a 16-bit transmit data width with multiple words being transferred, TxWordValidHS[1:0] is driven to 0x3 on the first word of the data transfer and either 0x1 or 0x3 on the last word of the data transfer. If there are more than 2 words transferred, TxWordValidHS[1:0] is driven to 0x3 for all of the middle word data transfers. If only one word is being transferred, TxWordValidHS[1:0] is driven to either 0x1 or 0x3.</p> <p>For a 32-bit transmit data width with multiple words being transferred, TxWordValidHS[3:0] is driven to 0xF on the first word of the data transfer and either 0x1, 0x3, 0x7, or 0xF on the last word of the data transfer. If there are more than 4 words transferred, TxWordValidHS[3:0] is driven to 0xF for all of the middle word data transfers. If only one word is being transferred, TxWordValidHS[3:0] is driven to either 0x1, 0x3, 0x7, or 0xF.</p>
TxEqActiveHS	I	MXXX	This is a level sensitive flag indicating the equalization active state. When this flag is high, it indicates the equalization is enabled. When this flag is low, it indicates the equalization is disabled.
TxEqLevelHS	I	MXXX	This is a level sensitive flag indicating the equalization level. When this flag is low (i.e., zero), it indicates a low level of equalization (3.5 dB +/- 1 dB) is active. When this flag is high (i.e., one), it indicates a high level of equalization (7 dB +/- 1 dB) is active.

Symbol	Dir	Categories	Description
TxRequestHS	I	MXXX SRXX MCNN	<p>High-Speed Transmit Request and Data Valid.</p> <p>A low-to-high transition on TxRequestHS causes the Lane Module to initiate a Start-of-Transmission sequence. A high-to-low transition on TxRequest causes the Lane Module to initiate an End-of-Transmission sequence.</p> <p>For Clock Lanes, this active high signal causes the Lane Module to begin transmitting a High-Speed clock.</p> <p>For Data Lanes, this active high signal also indicates that the protocol is driving valid data on TxDataHS to be transmitted. The Lane Module accepts the data when both TxRequestHS and TxReadyHS are active on the same rising TxWordClkHS clock edge. The protocol always provides valid transmit data when TxRequestHS is active. Once asserted, TxRequestHS remains high until the data has been accepted, as indicated by TxReadyHS.</p> <p>TxRequestHS is only asserted while TxRequestEsc is low.</p> <p>A low-to-high transition on TxRequestHS can only happen when Stopstate is asserted.</p> <p>The protocol layer asserts TxRequestHS for the Clock Lane at the same clock cycle or in previous clock cycles of the TxRequestHS of the data Lanes. The protocol layer asserts TxRequestHS for the Clock Lane for every cycle that TxRequestHS is asserted for the data Lanes. The PHY guarantees TCLK-PRE and TCLK-POST timing parameters.</p> <p>The TxRequestHS for Clock Lane will be kept asserted after the TxRequestHS for data Lanes have been de-asserted, for cases of applications where continued availability of the clock is necessary.</p> <p>The assertion of this signal is mutually exclusive with the assertion of the TxSkewCalHS, TxAlternateCalHS, and TxRequestEsc signals.</p>
TxReadyHS	O	MXXX SRXX MCNN	<p>High-Speed Transmit Ready.</p> <p>For Clock Lanes, this active high signal indicates that the Lane is currently transmitting a High-Speed clock.</p> <p>For data Lanes, this active high signal indicates that TxDataHS is accepted by the Lane Module to be serially transmitted.</p> <p>TxReadyHS is valid on rising edges of TxWordClkHS.</p> <p>Optionally, TxReadyHS can be used during deskew calibration to indicate that SoT has ended and data Lanes are transmitting deskew burst (clock pattern).</p>

Symbol	Dir	Categories	Description
TxDATATransferEnHS	I	MXXX	<p>High-Speed Tx Data Transfer Enable.</p> <p>This active high signal that is synchronous to TxWordClkHS indicates to the PHY that TxDATAHS is valid. When this signal is de-asserted and Preamble is disabled, the PHY must remain in the HS-Zero State even if TxReadyHS is asserted. If Preamble is enabled, the PHY must remain in the Preamble state even if TxReadyHS is asserted until TxDATATransferEnHS is asserted. Once asserted, the protocol layer can only deassert this signal when TxRequestHS is also de-asserted. TxDATATransferEnHS can be tied high, if the protocol layer does not support High Speed Tx Data Transfer Enable, or if it does not want to throttle TxDATAHS at the beginning of a HS data transfer.</p>
TxSkewCalHS	I	MXXX	<p>High-Speed Transmit Skew Calibration.</p> <p>This is an optional signal to initiate the periodic deskew burst at the transmitter.</p> <p>A low-to-high transition on TxSkewCalHS causes the PHY to initiate the transmission of a skew calibration pattern. A high-to-low transition on TxSkewCalHS causes the PHY to end the transmission of a skew calibration pattern, and initiate an end-of-transmission sequence.</p> <p>Note that TxSkewCalHS is used to generate both the initial and periodic skew calibration patterns.</p> <p>The assertion of this signal is mutually exclusive with the assertion of the TxRequestHS, TxAlternateCalHS, and TxRequestEsc signals.</p> <p>When TxSkewCalHS is asserted, TxRequestHS will be asserted on the Clock Lane. All data Lanes for a Link can initiate the deskew pattern at the same time.</p>
TxAlternateCalHS	I	MXXX	<p>High-Speed Transmit Alternate Calibration.</p> <p>This is an optional signal to initiate the alternate calibration sequence at the transmitter.</p> <p>A low-to-high transition on TxAlternateCalHS causes the PHY to initiate an alternate calibration sequence.</p> <p>A high-to-low transition on TxAlternateCalHS causes the PHY to stop the alternate calibration sequence and initiate an end-of-transmission sequence.</p> <p>The assertion of this signal is mutually exclusive with the assertion of the TxRequestHS, TxSkewCalHS, and TxRequestEsc signals.</p> <p>When TxAlternateCalHS is asserted, TxRequestHS will be asserted on the Clock Lane. All data Lanes for a Link can initiate alternate calibration sequence at the same time. It is up to the protocol layer to ensure TxAlternateCalHS is only asserted after the initial deskew pattern and before any High Speed data transfers.</p>

Symbol	Dir	Categories	Description
<b>High-Speed Receive Signals</b>			
RxWordClkHS	O	MRXX SXXX	<p>High-Speed Receive Word Clock.</p> <p>This is used to synchronize signals in the high-speed receive clock domain. The RxWordClkHS is generated by dividing the recovered high-speed clock. The frequency of RxWordClkHS is dependent upon the width of the High-Speed Receive Data, as follows:</p> <ul style="list-style-type: none"> <li>• 8-bit width, RxDataHS[7:0], the High-Speed Receive Word Clock is exactly 1/8 the high-speed received data rate.</li> <li>• 16-bit width, RxDataHS[15:0], the High-Speed Receive Word Clock is exactly 1/16 the high-speed received data rate.</li> <li>• 32-bit width, RxDataHS[31:0], the High-Speed Receive Word Clock is exactly 1/32 the high-speed received data rate.</li> </ul> <p>For links with multiple data Lanes, the PHY will implement one RxWordClkHS signal per Lane.</p>
RxDataWidthHS[1:0]	I	MRXX SXXX	<p>High-Speed Receive Data Width Select.</p> <p>Selects the bus width of RxDataHS:</p> <ul style="list-style-type: none"> <li>• RxDataWidthHS[1:0] = 00: 8-bit, RxDataHS[7:0]</li> <li>• RxDataWidthHS[1:0] = 01: 16-bit, RxDataHS[15:0]</li> <li>• RxDataWidthHS[1:0] = 10: 32-bit, RxDataHS[31:0]</li> <li>• RxDataWidthHS[1:0] = 11: not used, reserved.</li> </ul> <p>An implementation may support any data width - one fixed width, or subset of widths or all widths defined above.</p>
RxDataHS[7:0], or RxDataHS[15:0], or RxDataHS[31:0]	O	MRXX SXXX	<p>High-Speed Receive Data.</p> <p>High-speed data received by the Lane Module. If the RxValidHS signals indicate that more than 8 bits were received, then the byte reception order over the physical interface is RxDataHS[7:0] followed by RxDataHS[15:8] followed by RxDataHS[23:16] followed by RxDataHS[31:24]. Data is transferred on rising edges of RxWordClkHS. The following signals are defined for the High-Speed Receive Data based on the width of the receive data path:</p> <ul style="list-style-type: none"> <li>• 8-bit width – RxDataHS[7:0]</li> <li>• 16-bit width – RxDataHS[15:0]</li> <li>• 32-bit width – RxDataHS[31:0]</li> </ul> <p>An implementation may support any data width - one fixed width, or subset of widths or all widths defined above. The LSB will be received as the first bit and the MSB will be received as the last bit.</p>

Symbol	Dir	Categories	Description
RxValidHS[0], or RxValidHS[1:0], or RxValidHS[3:0]	O	MRXX SXXX	<p>High-Speed Receive Data Valid.</p> <p>This active high signal indicates that the Lane Module is driving data to the protocol layer on the RxDataHS output. There is no “RxReadyHS” signal, and the protocol layer is expected to capture RxDataHS on every rising edge of RxWordClkHS where any RxValidHS bit is asserted. There is no provision for the protocol layer to slow down (“throttle”) the receive data.</p> <p>The following High-Speed Receive Data Valid signals are defined based on the width of the receive data path:</p> <ul style="list-style-type: none"> <li>• 8-bit width – RxValidHS[0]</li> <li>• 16-bit width – RxValidHS[1:0]</li> <li>• 32-bit width – RxValidHS[3:0]</li> </ul> <p>The following High-Speed Receive Data Valid signals indicate which bits of the RxDataHS data bus contain valid data as follows:</p> <ul style="list-style-type: none"> <li>• RxValidHS[0] – RxDataHS[7:0] contains valid data that was received from the channel</li> <li>• RxValidHS[1] – RxDataHS[15:8] contains valid data that was received from the channel</li> <li>• RxValidHS[2] – RxDataHS[23:16] contains valid data that was received from the channel</li> <li>• RxValidHS[3] – RxDataHS[31:24] contains valid data that was received from the channel.</li> </ul> <p>For links with more than one data Lane, it is possible that each data Lane’s RxValidHS low-to-high and high-to-low transition may be in a different RxWordClkHS cycle.</p> <p>RxValidHS is not asserted for high speed deskew bursts or alternate calibration sequences. RxValidHS is not asserted if ErrSotSyncHS is asserted.</p> <p>If the PHY does not support EOT processing, all bits of RxValidHS[0], RxValidHS[1:0], or RxValidHS[3:0] are asserted when there is valid data received from the channel.</p>
RxActiveHS	O	MRXX SXXX	<p>High-Speed Reception Active.</p> <p>This active high signal indicates that the Lane Module is actively receiving a High-Speed transmission from the Lane interconnect.</p> <p>There is no timing relationship between Stopstate being de-asserted and RxActiveHS being asserted. Likewise, there is no relationship between Stopstate being asserted and RxActiveHS being de-asserted.</p> <p>When receiving any high speed data transfer including Alternate Calibration or high speed deskew pattern, RxActiveHS is asserted.</p>

<b>Symbol</b>	<b>Dir</b>	<b>Categories</b>	<b>Description</b>
RxSyncHS	O	MRXX SXXX	<p>Receiver Synchronization Observed.</p> <p>This active high signal indicates that the Lane Module has seen an appropriate synchronization event. In a typical High-Speed transmission, RxSyncHS is high for one cycle of RxWordClkHS at the beginning of a High-Speed transmission when RxActiveHS is first asserted.</p> <p>RxSyncHS is asserted even if ErrSotHS is asserted. RxSyncHS is not asserted if ErrSotSyncHS is asserted.</p>
RxDetectEobHS	I	MRXX SXXX	<p>Receiver Detection Of End Of Burst</p> <p>When using ALP mode, this active high signal is an indication from the protocol that it has detected the end of the current high speed data burst. When using ALP mode, the HS-Trail and the ALP Stop Line states are not reliably detectable by the PHY, when receiving a high speed data burst. Therefore, it is necessary for the protocol to detect the end of the burst and indicate this to the PHY. After observing this signal being driven active, the PHY will end the current high speed data reception operation.</p> <p>Once driven active, this signal remains active until the Stopstate signal is asserted by the PHY.</p>
RxClkActiveHS	O	SCNN	<p>Receiver Clock Active.</p> <p>This asynchronous, active high signal indicates that a Clock Lane is receiving a DDR Clock signal.</p> <p>There is no timing relationship between Stopstate being de-asserted and RxClkActiveHS being asserted. Likewise, there is no relationship between Stopstate being asserted and RxClkActiveHS being de-asserted.</p>
RxDDRClkHS	O	SCNN	<p>Receiver DDR Clock.</p> <p>This is the clock received on the Clock Lane, and may be used by the protocol, if required. This signal is low whenever RxClkActiveHS is de-asserted.</p> <p>This signal is defined for backward-compatibility purposes only. For higher data rates, it is anticipated that impairment to this clock will be considerable. Therefore, it is advisable for this clock to not be used.</p>
RxSkewCalHS	O	SXXX	<p>High-Speed Receive Skew Calibration.</p> <p>This optional active high signal indicates that the high speed deskew burst is being received. RxSkewCalHS is asserted when the all-ones sync pattern is received, and is de-asserted when the PHY has detected an LP-11 when using LP mode, or ALP Stop when using ALP mode.</p> <p>RxSkewCalHS is not asserted for the Alternate Calibration Sequence.</p>

<b>Symbol</b>	<b>Dir</b>	<b>Categories</b>	<b>Description</b>
RxAlternateCalHS	O	SXXX	<p>High-Speed Receive Alternate Calibration Sequence.</p> <p>This optional active high signal indicates that the alternate Calibration Sequence is being received. RxAlternateCalHS is asserted when the "11110000" sync pattern is received, and is de-asserted when the PHY has detected an LP-11 when using LP mode, or ALP Stop when using ALP mode.</p>
RxErrorCalHS	O	SXXX	<p>High-Speed Receive Calibration Error.</p> <p>This optional asynchronous active high signal indicates that the high speed calibration ended with errors.</p> <p>This signal is asserted if the initial deskew calibration (RxSkewCalHS is asserted) or alternate calibration (RxAlternateCalHS is asserted) has not completed successfully. If it is asserted in any of the initial calibrations, proper received data cannot be expected, and the system takes an implementation-specific action to resolve the condition.</p> <p>This signal can also be asserted if periodic deskew (RxSkewCalHS is asserted) or preamble sequence did not complete successfully. It is implementation-specific how the system responds to this condition.</p> <p>RxErrorCalHS signal continues to be asserted until a new calibration sequence is received, or the PHY is disabled and re-enabled.</p>

Symbol	Dir	Categories	Description
<b>Escape Mode Transmit Signals</b>			
TxClkEsc	I	MXXX SXXY	<p>Escape Mode Transmit Clock.</p> <p>This clock is directly used to time escape sequences on the PPI.</p> <p>For LP mode, the period of this clock determines the phase times for Low-Power signals as defined in <b>Section 6.6.2</b>. It is therefore constrained by the normative part of the D-PHY specification. See <b>Section 9</b> Note that the TurnRequest signal is synchronous to this clock and this clock is included for any module that supports Bi-directional High-Speed operation, even if that module does not support transmit or Bi-directional Escape Mode.</p> <p>For ALP mode, this clock is not used to time the signaling on the serial line. Although not required, gains in efficiency of a given implementation can be achieved by requiring this clock to be phase and frequency aligned with the TxWordClkHS clock.</p>

Symbol	Dir	Categories	Description
TxRequestEsc	I	MXXX SXXY	<p>Escape Mode Transmit Request.</p> <p>This active high signal is used to request escape sequences.</p> <p>Once an escape sequence starts, the Lane continues driving the escape sequence until TxRequestEsc is de-asserted. For LP implementations, this signal is asserted together with exactly one of TxLpdteEsc, TxUlpsEsc, or one bit of TxTriggerEsc, or alternatively the TxRequestTypeEsc. For ALP implementations, this signal is asserted together with TxRequestTypeEsc.</p> <p>The requirements for the deassertion of TxRequestEsc are as follows:</p> <ul style="list-style-type: none"> <li>• When transmitting low power data, TxRequestEsc is de-asserted after TxReadyEsc is asserted for the final byte of data.</li> <li>• When requesting ULPS entry, TxRequestEsc is de-asserted Twakeup time after UlpsActiveNot is de-asserted in response to TxUlpsExit being asserted.</li> <li>• When transmitting a trigger, TxRequestEsc is de-asserted at any time after the request is made. If the PHY has not completed the transmission of the trigger command at the time that TxRequestEsc is de-asserted, the PHY will complete the transmission then drive Mark-1 and LP-11 in LP mode, or drive HS-Trail and ALP Stop in ALP mode. If the PHY has completed the transmission of the trigger command and TxRequestEsc is not de-asserted, the PHY will transmit either the required space state, or the optional dummy data bytes in order to generate clocks on RxClkEsc of the receiver until TxRequestEsc is de-asserted, at which time the PHY will complete the current transmission then drive Mark-1 and LP-11 in LP mode, or drive HS-Trail and ALP Stop in ALP mode.</li> </ul> <p>The assertion of this signal is mutually exclusive with the assertion of the TxRequestHS, TxSkewCalHS, and TxAlternateCalHS signals.</p> <p>A low-to-high transition on TxRequestEsc can only happen when Stopstate is asserted.</p>

Symbol	Dir	Categories	Description
TxRequestTypeEsc[3:0]	I	MXXX SXXY	<p>Escape Mode Transmit Request Type.</p> <p>This signal is required for ALP implementations and optional for LP implementations. When implemented with LP implementations, it can be used in place of the TxLpdteEsc, TxUlpsEsc, and TxTriggerEsc signals.</p> <p>This signal indicates the type of transmit that is being requested. It is driven at the same time as TxRequestEsc and remains active until Stopstate is asserted. The encoding of this signal is provided in <b>Table 12</b>.</p> <p>The encoding of this signal is as follows:</p> <ul style="list-style-type: none"> <li>• 0000: Reserved. Assert this value when not using this signal for LP implementations.</li> <li>• 0001: Ultra low power state (ULPS)</li> <li>• 0010: Undefined-1 mode</li> <li>• 0011: Undefined-2 mode</li> <li>• 0100: Reset trigger</li> <li>• 0101: Unknown 3 trigger - Entry sequence for HS Test mode</li> <li>• 0110: Unknown 4 trigger</li> <li>• 0111: Unknown 5 trigger</li> <li>• 1000: Reserved</li> <li>• 1001: Reserved</li> <li>• 1010: Wakeup pulse (not for initiating ULPS exit)</li> <li>• 1011 – 1111: Reserved</li> </ul>
TxLpdteEsc	I	MXAX SXXA	<p>Escape Mode Transmit Low-Power Data.</p> <p>For LP implementations, this active high signal is asserted with TxRequestEsc to cause the Lane Module to enter Low-Power data transmission mode. The Lane Module remains in this mode until TxRequestEsc is de-asserted.</p> <p>TxUlpsEsc and all bits of TxTriggerEsc are low when TxLpdteEsc is asserted.</p> <p>For ALP implementations, this signal is unused and if present, must be driven low when using ALP mode.</p>
TxUlpsExit	I	MXXX SXXY MCNN	<p>Transmit ULP Exit Sequence.</p> <p>This active high signal is asserted when ULP state is active and the protocol is ready to leave ULP state. This signal is synchronous to TxClkEsc.</p> <p>When in LP mode, the PHY exits the ULP state by first driving Mark-1 after TxUlpsExit is asserted. After this, when TxRequestEsc is de-asserted, the PHY drives LP-11.</p> <p>When in ALP mode, the PHY exits the ULP state by first driving ALP Wake after TxUlpsExit is asserted. After this, when TxRequestEsc is de-asserted, the PHY drives ALP Stop.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
TxUlpsEsc	I	MXXX SXXY	<p>Escape Mode Transmit Ultra-Low Power State.</p> <p>For LP implementations, this active high signal is asserted with TxRequestEsc to cause the Lane Module to enter the Ultra-Low Power State. The Lane Module remains in this mode until TxRequestEsc is de-asserted.</p> <p>TxLpdtEsc and all bits of TxTriggerEsc are low when TxUlpsEsc is asserted.</p> <p>For ALP implementations, this signal is unused and if present, must be driven low when using ALP mode.</p>
TxTriggerEsc[3:0]	I	MXXX SXXY	<p>Escape Mode Transmit Trigger 0-3.</p> <p>For LP implementations, one of these active high signals is asserted with TxRequestEsc to cause the associated Trigger to be sent across the Lane interconnect. In the receiving Lane Module, the same bit of RxTriggerEsc is then asserted and remains asserted until the Lane interconnect returns to Stop state, which happens when TxRequestEsc is de-asserted at the transmitter.</p> <p>Only one bit of TxTriggerEsc is asserted at any given time, and only when TxLpdtEsc and TxUlpsEsc are both low.</p> <p>TxTriggerEsc[0] corresponds to Reset-Trigger.</p> <p>TxTriggerEsc[1] corresponds to Entry sequence for HS Test mode Trigger.</p> <p>TxTriggerEsc[2] corresponds to Unknown-4 Trigger.</p> <p>TxTriggerEsc[3] corresponds to Unknown-5 Trigger.</p> <p>For ALP implementations, this signal is unused and if present, must be driven low when using ALP mode.</p>
TxDataEsc[7:0]	I	MXAX SXXA	<p>Escape Mode Transmit Data.</p> <p>This is the eight bit Escape Mode data to be transmitted in Low-Power data transmission mode. The signal connected to TxDataEsc[0] is transmitted first. Data is captured on rising edges of TxClkEsc.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
TxValidEsc	I	MXAX SXXA	<p>Escape Mode Transmit Data Valid.</p> <p>This active high signal indicates that the protocol is driving valid data on TxDataEsc to be transmitted. The Lane Module accepts the data when TxRequestEsc, TxValidEsc and TxReadyEsc are all active on the same rising TxClkEsc clock edge.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
TxReadyEsc	O	MXAX SXXA	<p>Escape Mode Transmit Ready.</p> <p>This active high signal indicates that TxDataEsc is accepted by the Lane Module to be serially transmitted. TxReadyEsc is valid on rising edges of TxClkEsc.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
<b>Escape Mode Receive Signals</b>			
RxClkEsc	O	MXXY SXXX	<p>Escape Mode Receive Clock.</p> <p>This signal is used to transfer received data to the protocol during LP mode and ALP mode.</p> <p>In LP mode, this signal is generated from the two Low-Power signals in the Lane interconnect. Because of the asynchronous nature of Escape Mode data transmission, this signal may not be periodic. The number of pulses of this signal is limited to the activity on the lines, so it is advisable that this signal not be used as clock for the protocol layer.</p> <p>In ALP mode, this clock is generated by dividing the recovered high-speed clock, and is exactly 1/8 the high-speed received data rate.</p>
RxLpdteEsc	O	MXXA SXAX	<p>Escape Low-Power Data Receive mode.</p> <p>This active high signal is asserted to indicate that the Lane Module is in Low-Power data receive mode. While in this mode, received data bytes are driven onto the RxDataEsc output when RxValidEsc is active. The Lane Module remains in this mode with RxLpdteEsc asserted until a Stop state is detected on the Lane interconnect.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
RxUlpsEsc	O	MXXY SXXX	<p>Escape Ultra-Low Power (Receive) mode.</p> <p>This active high signal is asserted to indicate that the Lane Module has entered the Ultra-Low Power State, due to the detection of a received ULPS command. The Lane Module remains in this mode with RxUlpsEsc asserted until a Stop state is detected on the Lane interconnect.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
RxTriggerEsc[3:0]	O	MXXY SXXX	<p>Escape Mode Receive Trigger 0-3.</p> <p>These active high signals indicate that a trigger event has been received. The asserted RxTriggerEsc signal remains active until a Stop state is detected on the Lane interconnect.</p> <p>RxTriggerEsc[0] corresponds to Reset-Trigger.</p> <p>RxTriggerEsc[1] corresponds to Entry sequence for HS Test mode Trigger.</p> <p>RxTriggerEsc[2] corresponds to Unknown-4 Trigger.</p> <p>RxTriggerEsc[3] corresponds to Unknown-5 Trigger.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
RxWakeup	O	MXXY SXXX	<p>Receiver Wakeup Pulse Detected.</p> <p>For ALP mode implementations, this active high signal indicates that an ALP Wake Pulse is currently being detected.</p> <p>This signal is driven directly from the analog ALP-ED and is not timed to any PPI signal.</p>
RxDataEsc[7:0]	O	MXXA SXAX	<p>Escape Mode Receive Data.</p> <p>This is the eight-bit Escape Mode Low-Power data received by the Lane Module. The signal connected to RxDataEsc[0] was received first. Data is transferred on rising edges of RxClkEsc.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
RxValidEsc	O	MXXA SXAX	<p>Escape Mode Receive Data Valid.</p> <p>This active high signal indicates that the Lane Module is driving valid data to the protocol on the RxDataEsc output. There is no "RxReadyEsc" signal, and the protocol is expected to capture RxDataEsc on every rising edge of RxClkEsc where RxValidEsc is asserted. There is no provision for the protocol to slow down ("throttle") the receive data.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
Control Signals			
TurnRequest	I	XRXX XFXY	<p>Turnaround Request.</p> <p>This active high signal is used to indicate that the protocol desires to initiate a Bi-directional data Lane Turnaround, to allow the other side to begin transmissions. TurnRequest is valid on rising edge of TxClkEsc. TurnRequest is only meaningful for a Bi-directional data Lane Module that is currently the transmitter (Direction=0). If the Bi-directional data Lane Module is in receive mode (Direction=1), this signal is ignored.</p> <p>A low-to-high transition on TurnRequest can only happen when Stopstate is asserted.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
Direction	O	XRXX XFXY	<p>Transmit/Receive Direction.</p> <p>This signal is used to indicate the current direction of the Lane interconnect. When Direction=0, the Lane is in transmit mode (0=Output). When Direction=1, the Lane is in receive mode (1=Input).</p> <p>When using LP mode, when transitioning from TX to RX, the direction changes state after completion of a successful BTA procedure, as indicated by the detection of Mark-1 followed by LP-11. When transitioning from RX to TX, the direction changes state after the TTA-SURE time has been met, and the local driver starts transmitting LP-00. Any abnormalities during the BTA procedure can result in contention conditions, requiring the protocol layer to implement mechanisms to detect and resolve.</p> <p>When using ALP mode, when transitioning from TX to RX, the direction changes state when the first data burst is received, after the turnaround completes. When transitioning from RX to TX, the direction changes state after detection of HS-Trail at the end of the bus turnaround burst command.</p>
TurnDisable	I	XRXX XFXY	<p>Disable Turnaround.</p> <p>This signal is used to prevent a Bi-directional data Lane from going into transmit mode, even if it observes a Turnaround request on the Lane interconnect. This is useful to prevent a potential “lock-up” situation when a Unidirectional Lane Module is connected to a Bi-directional Lane Module.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
ForceRxmode	I	MRXX MXXY SXXX	<p>Force Lane Module Into Receive mode / Wait for Stop state.</p> <p>This signal allows the protocol to initialize a Lane Module, or force a Bi-directional Lane Module, into receive mode. This signal is used during initialization or to resolve a contention situation. When this signal is high, the Lane Module immediately transitions into receive Control mode and waits for a Stop state to appear on the Lane interconnect. When used for initialization, this signal will be released (i.e., driven low) only when the Dp &amp; Dn inputs are in Stop state for a time <math>T_{INIT}</math>, or longer.</p> <p>The assertion of ForceRxmode and ForceTxStopmode are mutually exclusive.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
ForceTxStopmode	I	MXXX SRXX SXXY	<p>Force Lane Module Into Transmit mode / Generate Stop state.</p> <p>This signal allows the protocol to force a Lane Module into transmit mode and Stop state during initialization or following an error situation, e.g. expired time out. When this signal is high, the Lane Module immediately transitions into transmit mode and the module state machine is forced into the Stop state.</p> <p>The protocol layer does not assert TxRequestEsc, TxRequestHS, or Turnrequest for an implementation-specific period of time after the deassertion of ForceTxStopMode, in order to create a safe margin for the PHY to be able to accept a new request.</p> <p>The assertion of ForceRxmode and ForceTxStopmode are mutually exclusive.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
Stopstate	O	XXXX XCNN	<p>Lane is in Stop state.</p> <p>This active high signal indicates that the Lane Module, regardless of whether the Lane Module is a transmitter or a receiver, is currently in Stop state.</p> <p>When using LP mode, this indicates that the PHY Line levels are in the LP-11 state, and the PHY state machine is in the stop state and ready to receive a request for the next operation. Also, the protocol may use this signal to indirectly determine if the PHY Line levels are in the LP-11 state.</p> <p>When using ALP mode, this indicates that the PHY Line levels are in the ALP Stop state, and the PHY state machine is in the stop state and ready to receive a request for the next operation. Also, the protocol may use this signal to indirectly determine if the PHY Line levels are in the ALP Stop state.</p> <p>For LP mode, a Master will not assert this signal during initialization until after LP 11 has been driven for the required <math>T_{INIT}</math> time.</p> <p>For LP mode, a Slave will not assert this signal during initialization until after LP 11 has been detected for the required <math>T_{INIT}</math> time.</p> <p>For ALP mode, a Master will not assert this signal during initialization until after ALP Wake has been driven for the required <math>T_{INIT}</math> time.</p> <p>For ALP mode, a Slave will not assert this signal during initialization until after ALP Wake has been detected for the required <math>T_{INIT}</math> time.</p>

Symbol	Dir	Categories	Description
Enable	I	XXXX XCNN	<p>Enable Lane Module.</p> <p>This active high signal forces the Lane Module out of “shutdown”. All Line drivers, receivers, terminators, and contention detectors are turned off when Enable is low. Furthermore, while Enable is low, all other PPI inputs are ignored, and all PPI outputs are driven to the default inactive state. Enable is a level sensitive signal and does not depend on any clock.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
AlpMode	I	XXXX XCNN	<p>Alternate Low Power Mode Selection.</p> <p>This signal indicates when alternate low power signaling option is being used. When AlpMode = 0, low power signaling mode is being used. When AlpMode = 1, Alternate low power signaling mode is being used.</p> <p>Note that this signal should only change state while the Enable signal is not active.</p>
TxUlpsClk	I	MCNN	<p>Transmit Ultra-Low Power State on Clock Lane.</p> <p>This active high signal is asserted to cause a Clock Lane Module to enter the Ultra-Low Power State. The Lane Module remains in this mode until TxUlpsClk is de-asserted.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
RxUlpsClkNot	O	SCNN	<p>Receive Ultra-Low Power State on Clock Lane.</p> <p>This active low signal is asserted to indicate that the Clock Lane Module has entered the Ultra-Low Power State due to the detection of a request to enter the ULP state. The Lane Module remains in this mode with RxUlpsClkNot asserted until a Stop state is detected on the Lane Interconnect.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>

Symbol	Dir	Categories	Description
UlpsActiveNot	O	XXXX XCNN	<p>ULP State (not) Active.</p> <p>This active low signal is asserted to indicate that the Lane is in ULP state.</p> <p>For a transmitter, this signal is asserted after TxUlpsEsc and TxRequestEsc (TxUlpsClk for a Clock Lane) are asserted. The transmitting PHY continues to supply TxClkEsc until UlpsActiveNot is asserted. In order to leave ULP state, the transmitter first drives TxUlpsExit high, then waits for UlpsActiveNot to become high (inactive). At that point, the transmitting PHY is active and has started transmitting a Mark-1 when using LP mode, or ALP Wake when using ALP mode, on the Lines. The protocol waits for a time Twakeup and then drives TxRequestEsc (TxUlpsClk) inactive to return the Lane to Stop state.</p> <p>For a receiver, this signal indicates that the Lane is in ULP state. When entering the ULP state, RxUlpsEsc (or RxUlpsClkNot for a Clock Lane) is asserted to indicate the detection of the ULPS command and entry into the ULP state, followed by the assertion of the UlpsActiveNot, indicating that the PHY is in the ULP state. When exiting the ULP state, this signal is de-asserted to indicate that the PHY has detected a Mark-1 when using LP mode, or ALP Wake when using ALP mode, to initiate the exit from the ULP state. After the required TWAKEUP, the RxUlpsEsc, or RxUlpsClkNot for a Clock Lane, is de-asserted to indicate the PHY has exited the ULP state and the PHY has detected an LP-11 when using LP mode, or ALP Stop when using ALP mode.</p> <p>The function of this signal is the same for both LP mode and ALP mode.</p>
TxHSIdleClkHS	I	MXXX	<p>HS-Idle State Start.</p> <p>This is an optional, asynchronous, active high signal to initiate the HS-Idle State at the transmitter. The assertion of TxHSIdleClkHS directs the PHY to start HS-Idle-Post sub-state and drive HS-0 on all Data Lanes. This is followed by the Clock Lane driving HS-0, instead of a valid clock. The deassertion of TxHSIdleClkHS directs the PHY to stop driving HS-0 and start driving a valid clock on the Clock Lane. This is followed by the data Lanes ending the transmission of HS-0 and driving valid data.</p> <p>TxHSIdleClkHS is only asserted when TxHSIdleClkReadyHS is de-asserted. TxHSIdleClkHS is only de-asserted when TxHSIdleClkReadyHS is asserted.</p> <p>When TxHSIdleClkHS is being asserted, the TxRequestHS will not be de-asserted.</p> <p>Note that the HS-Idle function is not supported when using ALP mode.</p>

Symbol	Dir	Categories	Description
TxHSIdleClkReadyHS	O	MXXX	<p>Clock Ready to Exit HS-Idle-ClkHS0 Sub-State.</p> <p>This is an optional, asynchronous, active high signal that indicates that the transmitter is currently in the HS-Idle state. A low level on TxHSIdleClkReadyHS indicates that the transmitter is not in HS-Idle State, or not ready to exit HS-Idle-ClkHS0 sub-state. A high level on TxHSIdleClkReadyHS indicates that the transmitter is ready to exit HS-Idle-ClkHS0 sub-state.</p> <p>Note that the HS-Idle function is not supported when using ALP mode.</p>
<b>Error Signals</b>			
ErrSotHS	O	MRXX SXXX	<p>Start-of-Transmission (SoT) Error.</p> <p>If the High-Speed SoT leader sequence is corrupted, but in such a way that proper synchronization can still be achieved, this active high signal is asserted for one cycle of RxWordClkHS. This is considered to be a “soft error” in the leader sequence and confidence in the payload data is reduced.</p> <p>When there is a Start-of-Transmission (SoT) Error, ErrSotHS is asserted in the same cycle as RxSyncHS is asserted.</p>
ErrSotSyncHS	O	MRXX SXXX	<p>Start-of-Transmission Synchronization Error.</p> <p>If the High-Speed SoT leader sequence is corrupted in a way that proper synchronization cannot be expected, this active high signal is asserted for one cycle of RxWordClkHS.</p> <p>When ErrSotSyncHS is asserted, RxSyncHS, ErrSotHS, and RxValidHS is not asserted.</p>
ErrEsc	O	MXXY SXXX	<p>Escape Entry Error.</p> <p>If an unrecognized escape entry command is received in LP mode, this asynchronous active high signal is asserted and remains asserted until the next transaction starts, so that the protocol can properly process the error.</p>
ErrSyncEsc	O	MXXA SXAX	<p>Low-Power Data Transmission Synchronization Error.</p> <p>If the number of bits received during a LP data transmission is not a multiple of eight when the transmission ends, this asynchronous active high signal is asserted and remains asserted until the next transaction starts, so that the protocol can properly process the error.</p>
ErrControl	O	MXXY SXXX	<p>Control Error.</p> <p>This asynchronous active high signal is asserted when an incorrect Line state sequence is detected in LP and ALP modes. Once asserted, this signal remains asserted until the next transaction starts, so that the protocol can properly process the error.</p> <p><b>Section A.18</b> describes the LP and ALP signaling error sequences that require this signal to be asserted, as well as error sequences that can optionally result in this signal being asserted. Sequences that can optionally result in this signal being asserted are implementation specific.</p>

Symbol	Dir	Categories	Description
ErrContentionLP0	O	MXXX SXXY	<p>LP0 Contention Error.</p> <p>This asynchronous active high signal is asserted when the Lane Module detects a contention situation on a Line while trying to drive the Line low, in LP mode only.</p> <p>In case of a contention detection, this signal is asserted and remains asserted until the protocol resolves the contention through the usage of ForceTxStopMode or ForceRxMode. For a given implementation, contention conditions occurring in a very short period of time may not be detectable. Such conditions do not necessarily require intervention from the protocol.</p>
ErrContentionLP1	O	MXXX SXXY	<p>LP1 Contention Error.</p> <p>This asynchronous active high signal is asserted when the Lane Module detects a contention situation on a Line while trying to drive the Line high, in LP mode only.</p> <p>In case of a contention detection, this signal is asserted and remains asserted until the protocol resolves the contention through the usage of ForceTxStopMode or ForceRxMode. For a given implementation, contention conditions occurring in a very short period of time may not be detectable. Such conditions do not necessarily require intervention from the protocol.</p>

1925

**Table 57** summarizes the signals that are affected by the choice of the transmit data path width.

**Table 57 Tx HS PPI Signals, Impact of Data Path Width**

	<b>8-bit</b>	<b>16-bit</b>	<b>32-bit</b>
<b>Tx HS Word Clock Rate</b>	1/8 the HS bit rate	1/16 the HS bit rate	1/32 the HS bit rate
<b>Tx HS Data Path</b>	TxDATAHS[7:0]	TxDATAHS[15:0]	TxDATAHS[31:0]
<b>HS Transmit Word Valid</b>	TxWordValidHS[0] → TxDATAHS[7:0]	TxWordValidHS[0] → TxDATAHS[7:0]; TxWordValidHS[1] → TxDATAHS[15:8]	TxWordValidHS[0] → TxDATAHS[7:0]; TxWordValidHS[1] → TxDATAHS[15:8]; TxWordValidHS[2] → TxDATAHS[23:16]; TxWordValidHS[3] → TxDATAHS[31:24]

1926

**Table 58** summarizes the signals that are affected by the choice of the transmit data path width.

**Table 58 Rx HS PPI Signals, Impact of Data Path Width**

	<b>8-bit</b>	<b>16-bit</b>	<b>32-bit</b>
<b>Rx HS Word Clock Rate</b>	1/8 the HS bit rate	1/16 the HS bit rate	1/32 the HS bit rate
<b>Rx HS Data Path</b>	RxDATAHS[7:0]	RxDATAHS[15:0]	RxDATAHS[31:0]
<b>HS Receive Word Valid</b>	RxValidHS[0] → RxDATAHS[7:0]	RxValidHS[0] → RxDATAHS[7:0]; RxValidHS[1] → RxDATAHS[15:8]	RxValidHS[0] → RxDATAHS[7:0]; RxValidHS[1] → RxDATAHS[15:8]; RxValidHS[2] → RxDATAHS[23:16]; RxValidHS[3] → RxDATAHS[31:24]

## A.2 PHY Enable Processes

The Figures in this Section illustrate the processes of enabling a PHY:

- **Figure 90** shows the process of enabling a Master PHY when using LP mode
- **Figure 91** shows the process of enabling a Master PHY when using ALP mode
- **Figure 92** shows the process of enabling a Slave PHY when using LP mode
- **Figure 93** shows the process of enabling a Slave PHY when using ALP mode

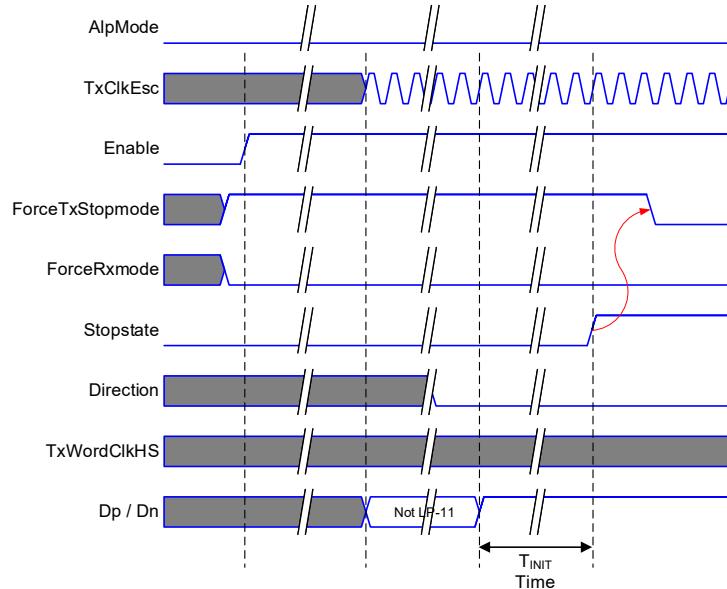


Figure 90 Example Master PHY Enable, LP Mode

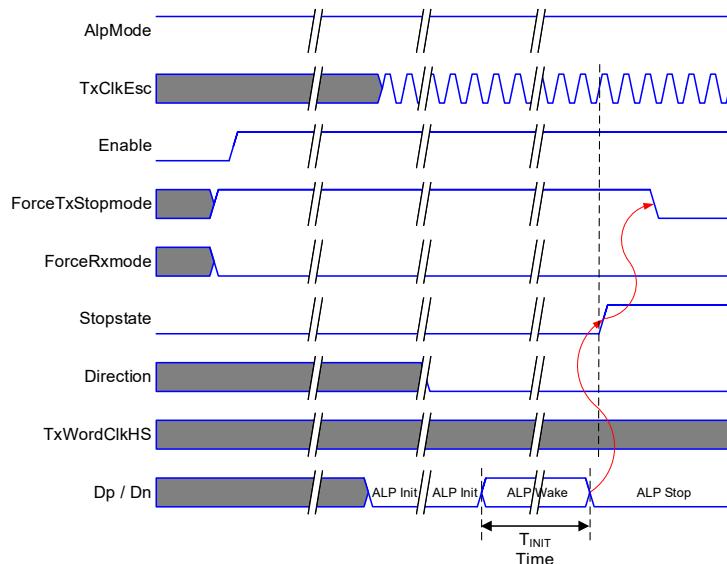
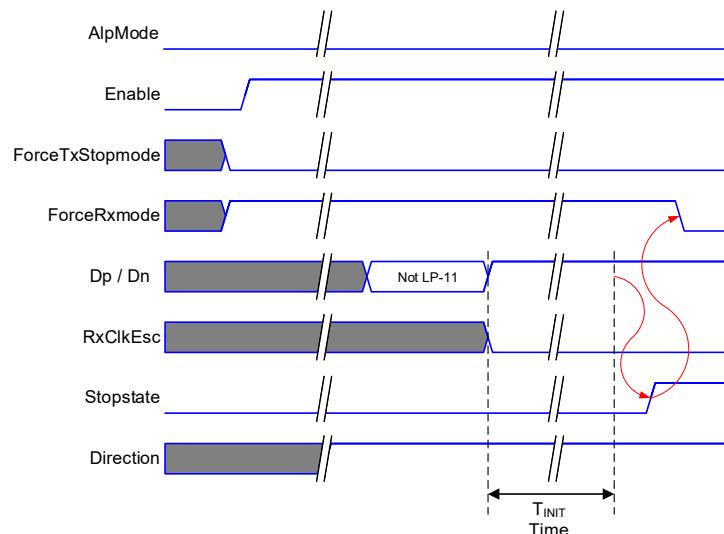
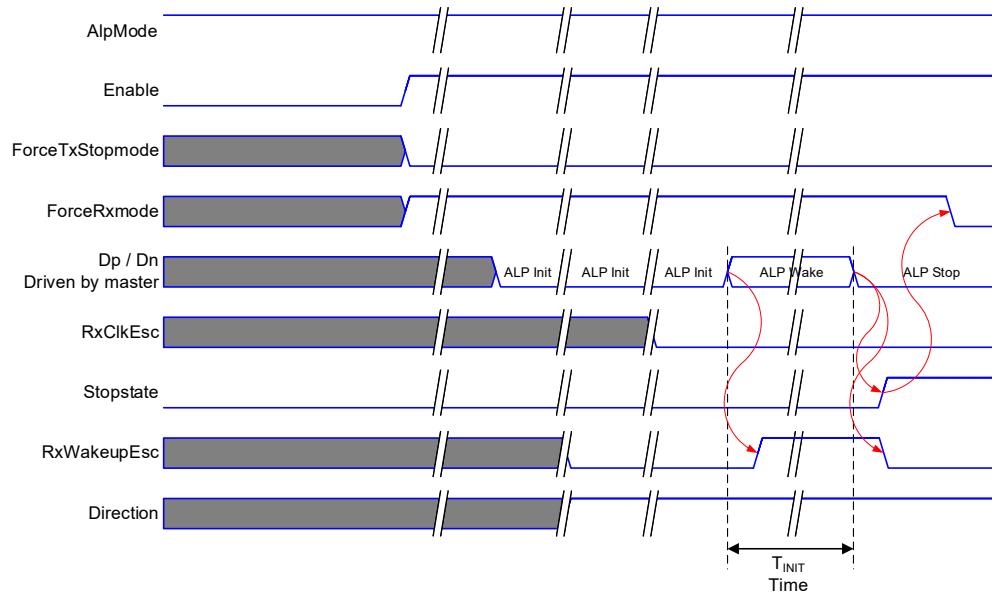


Figure 91 Example Master PHY Enable, ALP Mode



1934

**Figure 92 Example Slave PHY Enable, LP Mode**

1935

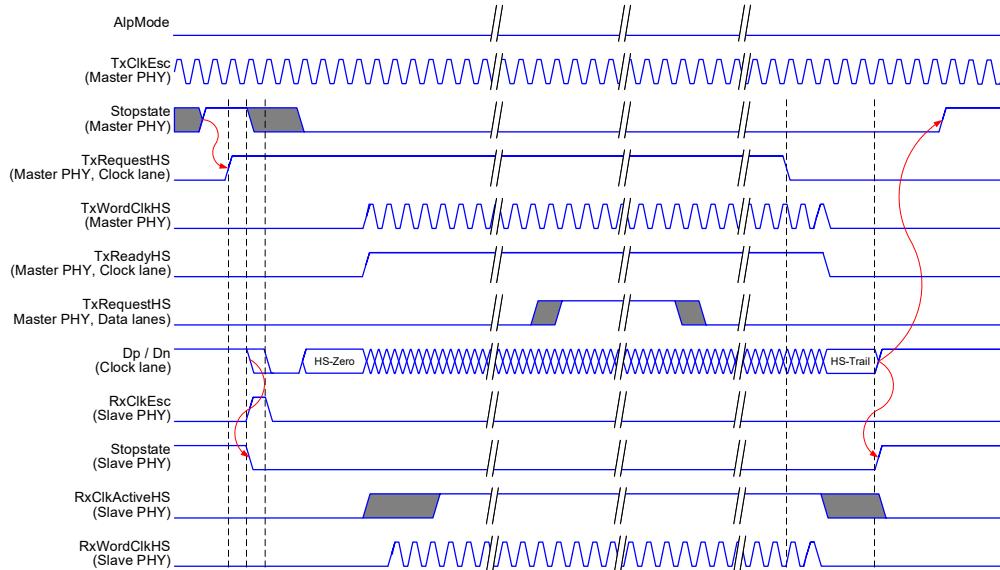
**Figure 93 Example Slave PHY Enable, ALP Mode**

### A.3 High-Speed Clock Enable

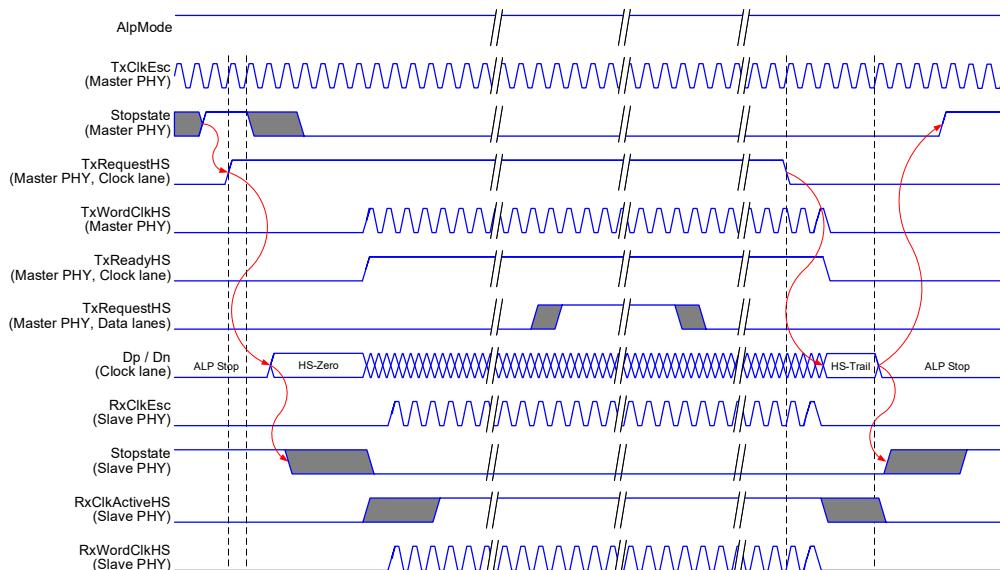
**Figure 94** shows an example of enabling the Clock Lane to transmit the high speed clock, when using LP mode.

**Figure 95** shows an example of enabling the Clock Lane to transmit the high speed clock, when using ALP mode.

It should be noted that the TxRequestHS for the Clock Lane is always asserted when TxRequestHS is asserted for any data Lane.



**Figure 94 Example High Speed Clock Enable, LP Mode**



**Figure 95 Example High Speed Clock Enable, ALP Mode**

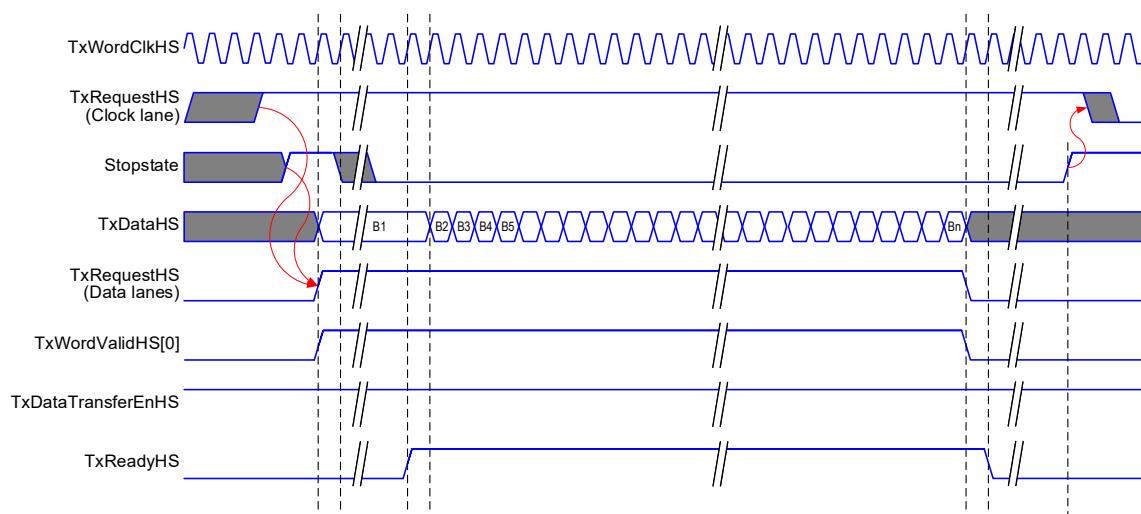
## A.4 High-Speed Transmit from the Master Side

The Figures in this Section are examples of high speed data transfers from the Master side using 8-, 16-, and 32-bit data bus widths. The behavior of these transfers is identical for LP and ALP modes. It should be noted that these examples do not use the High-Speed Tx Data Transfer Enable function, and therefore TxDataTransferEnHS is tied high.

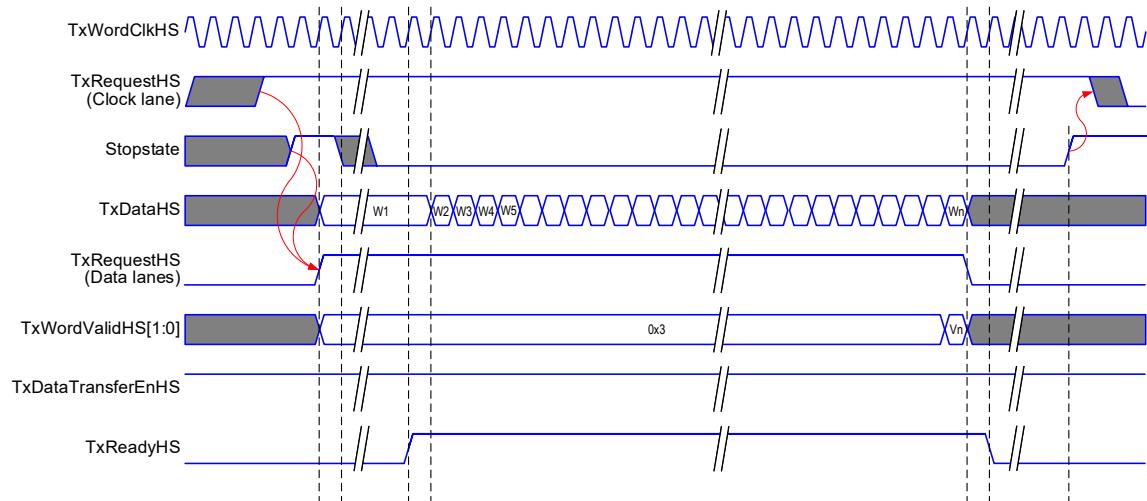
**Figure 96** shows a High-Speed transmission on the Master side using an 8-bit data bus. While TxRequestHS is low, the Lane Module ignores the value of TxDataHS. To begin transmission, the protocol drives TxDataHS with the first byte of data and asserts TxRequestHS. This data byte is accepted by the PHY on the first rising edge of TxWordClkHS with TxReadyHS also asserted. At this point, the protocol supplies a new valid data byte or ends the transmission. After the last data byte has been transferred to the Lane Module, TxRequestHS is driven low to cause the Lane Module to stop the transmission and enter Stop state. The minimum number of bytes transmitted could be as small as one.

**Figure 97** shows a High-Speed transmission on the Master side using a 16-bit data bus. In this example, TxWordValidHS[1:0] is driven to 0x3 until the final word is driven. On the last word, TxWordValidHS may be 0x1 or 0x3.

**Figure 98** shows a High-Speed transmission on the Master side using a 32-bit data bus. In this example, TxWordValidHS[3:0] is driven to 0xF until the final word is driven. On the last word, TxWordValidHS may be 0x1, 0x3, 0x7, or 0xF.

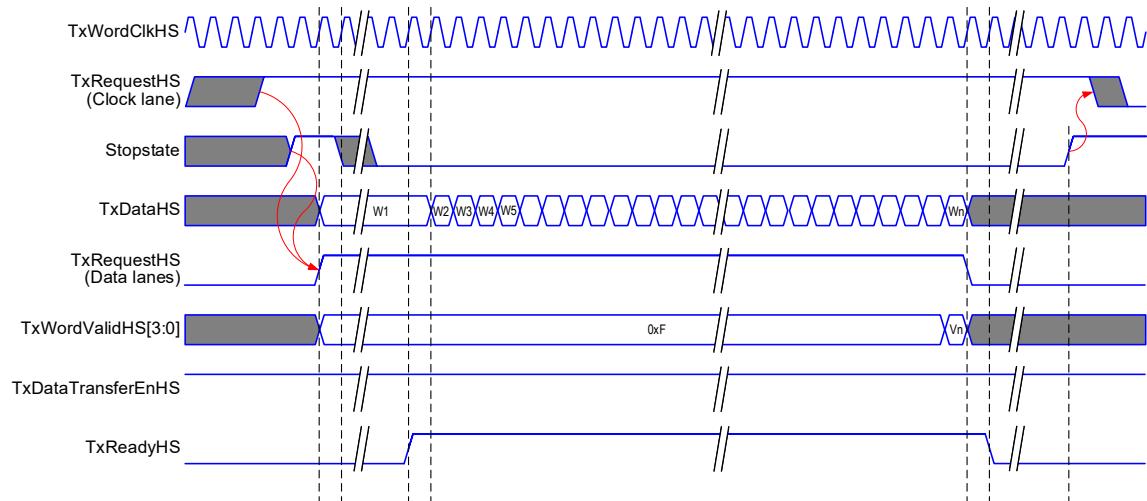


**Figure 96 Example High-Speed Transmission from the Master Side: 8-Bit Bus Width**



1963

**Figure 97 Example High-Speed Transmission from the Master Side: 16-Bit Bus Width**



1964

**Figure 98 Example High-Speed Transmission from the Master Side: 32-bit Bus Width**

## A.5 High-Speed Receive at the Slave Side

The Figures in this Section are examples of high speed data transfers to the Slave side using 8-, 16-, and 32-bit data bus widths. The RxActiveHS signal indicates that a receive operation is occurring. A normal reception starts with a pulse on RxSyncHS followed by valid receive data on subsequent cycles of RxWordClkHS. Note that the protocol is prepared to receive all the data. There is no method for the receiving protocol to pause or slow data reception. Note that there is not necessarily a direct timing relationship required between RxActiveHS and RxSyncHS, and between RxActiveHS and RxValidHS. In these diagrams, RxActiveHS is shown as asserted at the same time as RxSyncHS. It is also valid for RxActiveHS to be asserted prior to RxSyncHS being asserted. If a start of transmission error takes place, ErrSotHS will be asserted in the same cycle as RxSyncHS is asserted. Note that in cases where ALP mode is implemented, the protocol is required to drive the RxDetectEobHS signal to end the transfer.

- **Figure 99** shows an example of a High-Speed reception at the Slave side using an 8-bit data bus, when using LP mode.
- **Figure 100** shows an example of a High-Speed reception at the Slave side using an 8-bit data bus, when using ALP mode.
- **Figure 101** shows a High-Speed reception at the Slave side using a 16-bit data bus, when using LP mode. In this example, RxValidHS[1:0] is driven to 0x3 until the final word is driven. On the last word, RxValidHS may be 0x1 or 0x3.
- **Figure 102** shows a High-Speed reception at the Slave side using a 16-bit data bus, when using ALP mode.
- **Figure 103** shows a High-Speed reception at the Slave side using a 32-bit data bus, when using LP mode. In this example, RxValidHS[3:0] is driven to 0xF until the final word is driven. On the last word, RxValidHS may be 0x1, 0x3, 0x7, or 0xF.
- **Figure 104** shows a High-Speed reception at the Slave side using a 32-bit data bus, when using ALP mode.

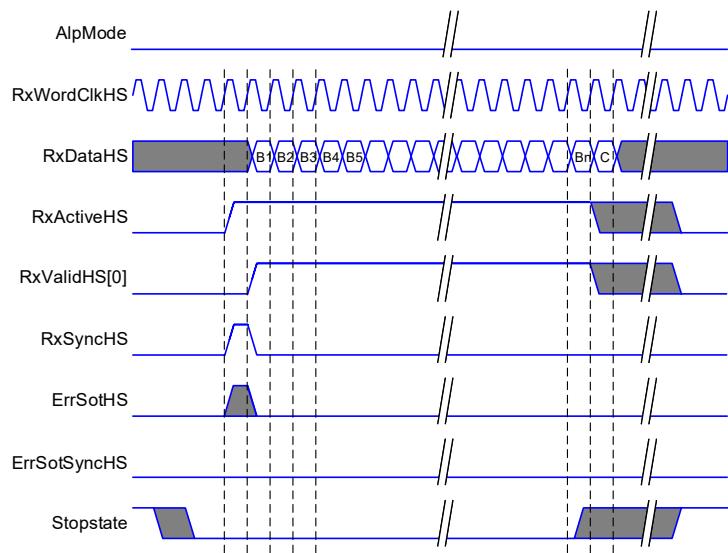
If EoT Processing is performed inside the PHY, the RxActiveHS and RxValidHS signals transition low following the last valid data byte, Bn. See **Figure 99**.

If EoT processing is not performed in the PHY, one or more additional bytes are presented after the last valid data byte. The first of these additional bytes, shown as byte “C” in **Figure 99**, is all ones or all zeros. Subsequent bytes may or may not be present, and can be any value. For a PHY that does not perform EoT processing, the RxActiveHS and RxValidHS signals transition low simultaneously sometime after byte “C” is received. Once these signals have transitioned low, they remain low until the next High-Speed data reception begins.

**Figure 105** shows an example of a high speed transfer with a Start-of-Transmission Synchronization Error, when using LP mode.

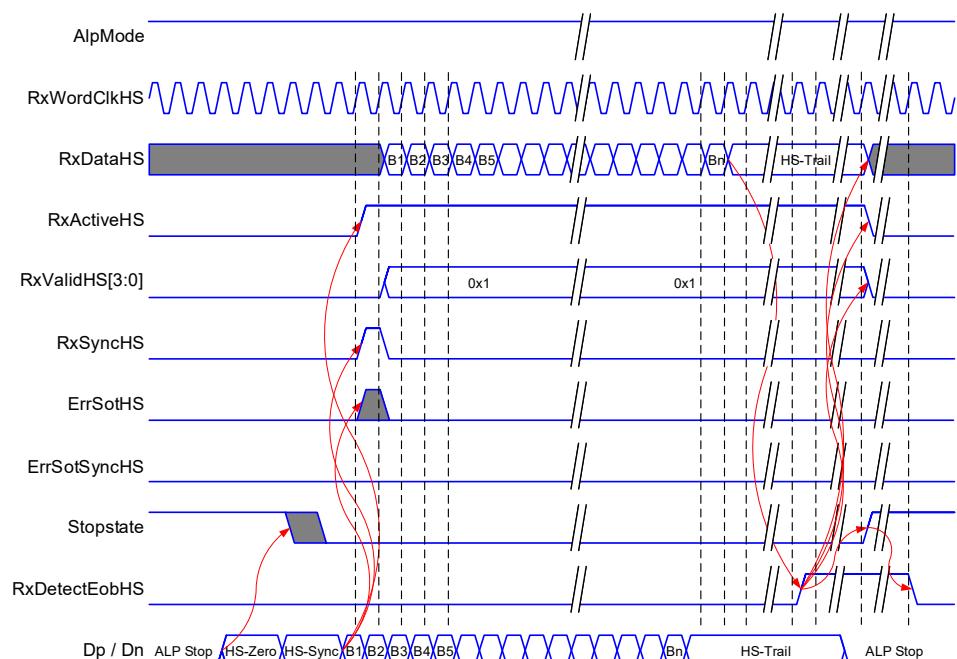
**Figure 106** shows an example of a high speed transfer with a Start-of-Transmission Synchronization Error, when using ALP mode.

2001



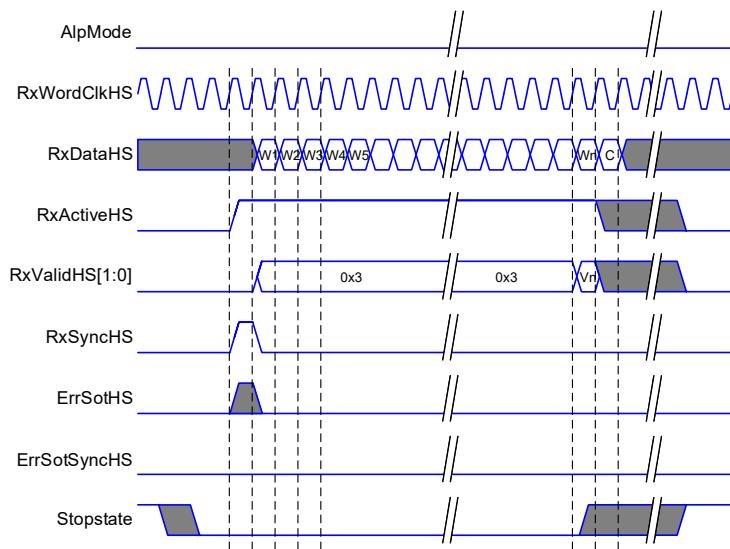
**Figure 99 Example High-Speed Receive on Slave Side: 8-Bit Bus, LP Mode**

2002

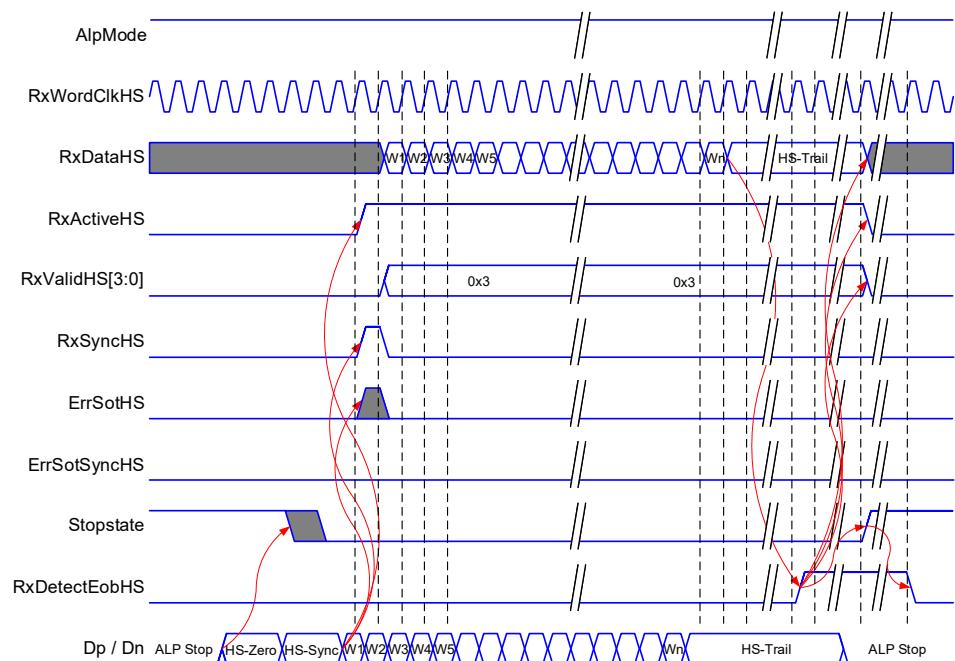


**Figure 100 Example High-Speed Receive on Slave Side: 8-Bit Bus, ALP Mode**

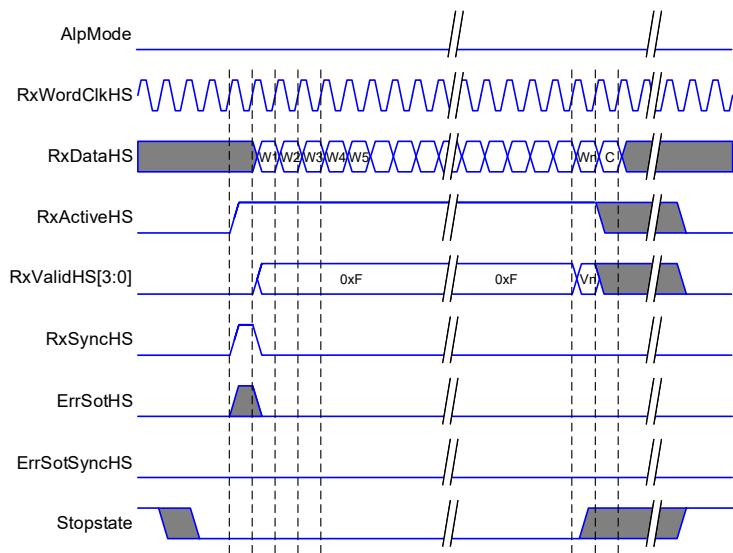
2003

**Figure 101 Example High-Speed Receive on Slave Side: 16-Bit Bus, LP Mode**

2004

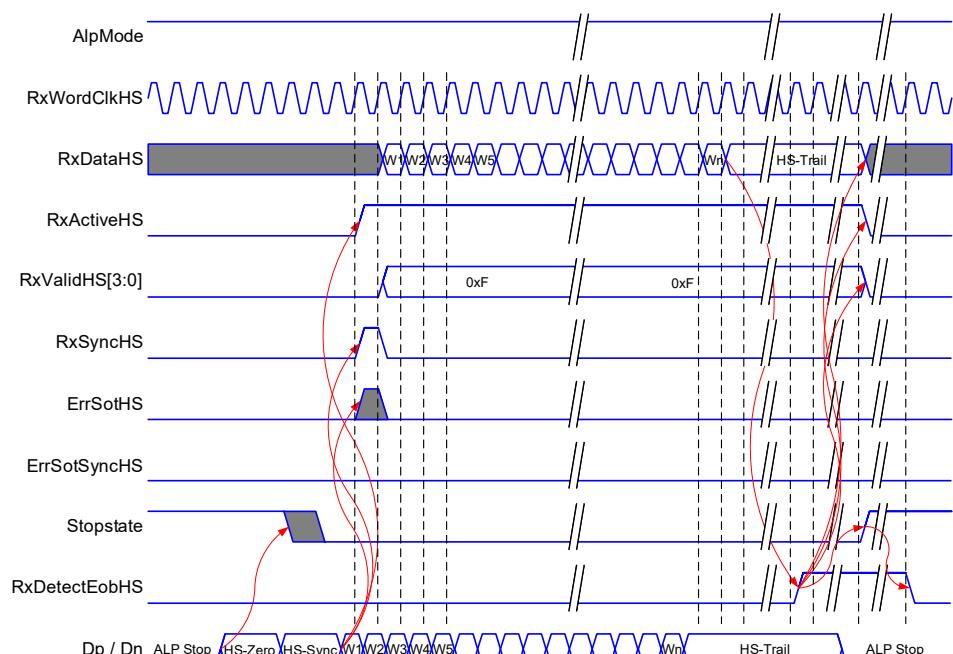
**Figure 102 Example High-Speed Receive on Slave Side: 16-Bit Bus, ALP Mode**

2005



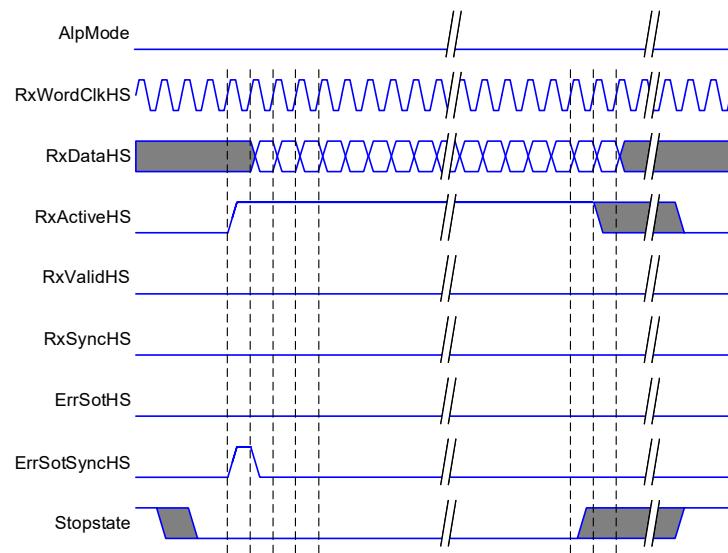
**Figure 103 Example High-Speed Receive on Slave Side: 32-Bit Bus, LP Mode**

2006

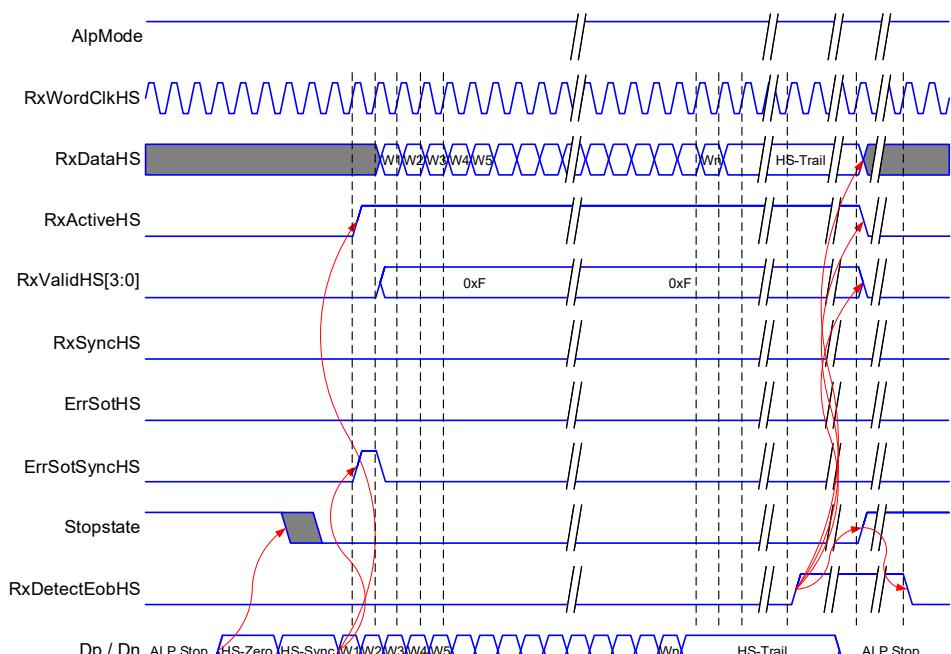


**Figure 104 Example High-Speed Receive on Slave Side: 32-Bit Bus, ALP Mode**

2007

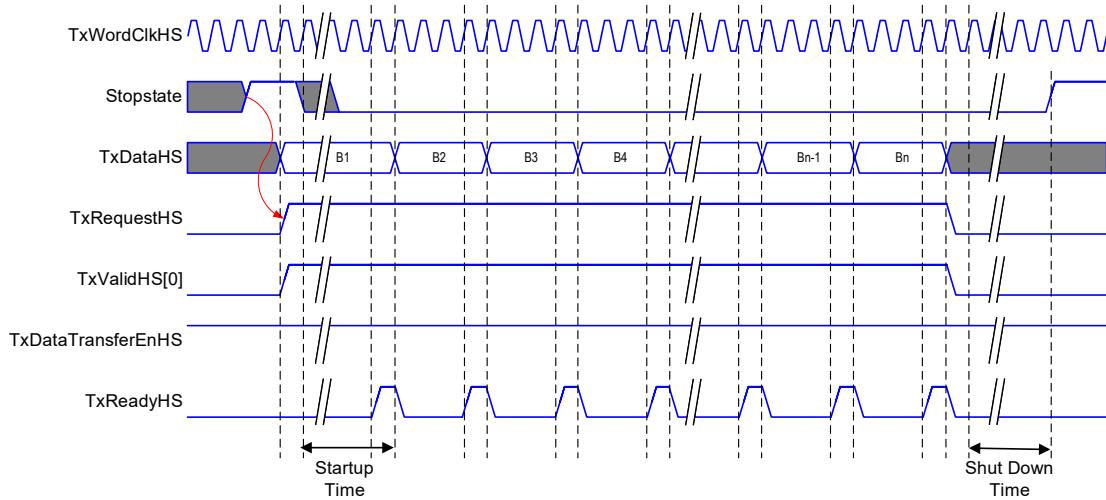
**Figure 105 Example High-Speed Receive with an ErrSotSyncHS, LP Mode**

2008

**Figure 106 Example High-Speed Receive with an ErrSotSyncHS, ALP Mode**

2009  
2010  
2011  
A Slave in Reverse Direction transmits at one-fourth the data rate of the Master. Because of this, the TxReadyHS signal is not constant high for a transmitting Slave. Otherwise, the transmission is very much like that seen at the PPI interface of a transmitting Master-side Lane Module.

2012  
2013  
**Figure 107** shows an example of a High-Speed transmission from the Slave side using an 8-bit data bus. The behavior of these transfers is identical for LP and ALP modes.



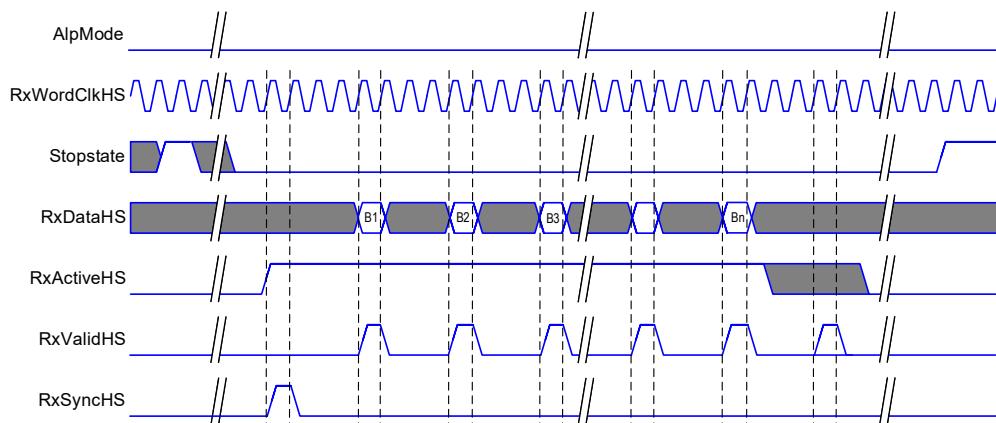
**Figure 107 Example High-Speed Transmit from the Slave Side: 8-Bit Bus Width**

## A.7 High-Speed Receive at the Master Side

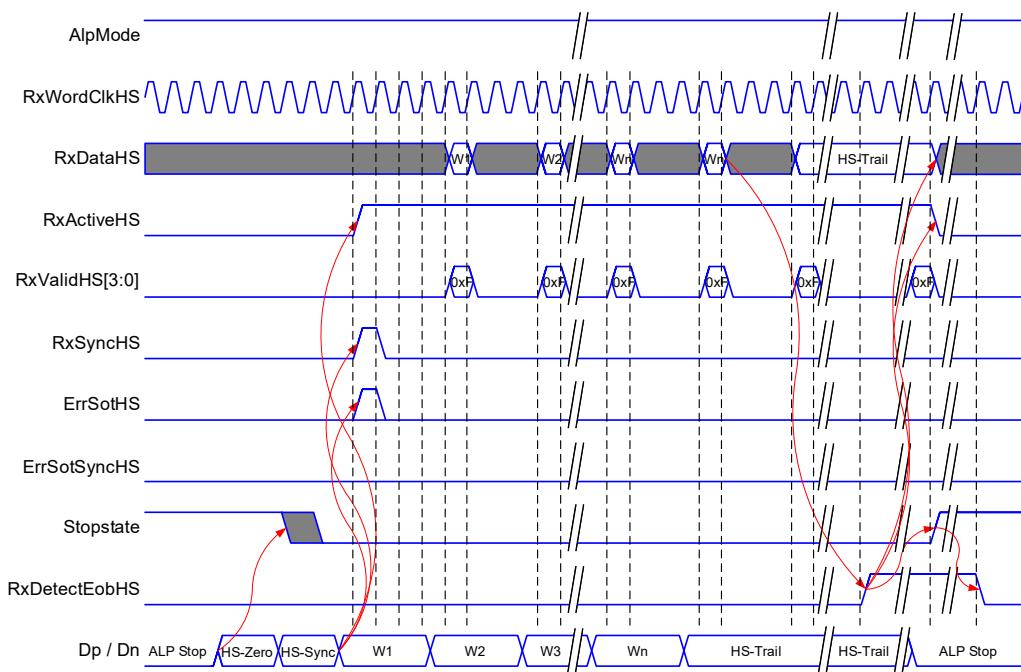
Because a Slave is restricted to transmitting at one-fourth the bandwidth of a Master, the RxValidHS signal is only asserted one out of every four cycles of RxWordClkHS during a High-Speed receive operation at the Master side. Note that there is not necessarily a direct timing relationship between RxActiveHS and RxSyncHS, and between RxActiveHS and RxValidHS. In these diagrams, RxActiveHS is shown as asserted at the same time as RxSyncHS. It is also valid for RxActiveHS to be asserted prior to RxSyncHS.

**Figure 108** shows an example of a High-Speed reception at the Master side using an 8-bit data bus, when using LP mode. Note that, depending on the bit rate, there may be one or more extra pulses on RxValidHS after the last valid byte, Bn, is received.

**Figure 109** shows an example of a High-Speed reception at the Master side using an 8-bit data bus, when using ALP mode. Note that in cases where ALP mode is implemented, the protocol is required to drive the RxDetectEobHS signal to end the transfer.



**Figure 108 Example High-Speed Receive at the Master Side: 8-Bit Bus, LP Mode**

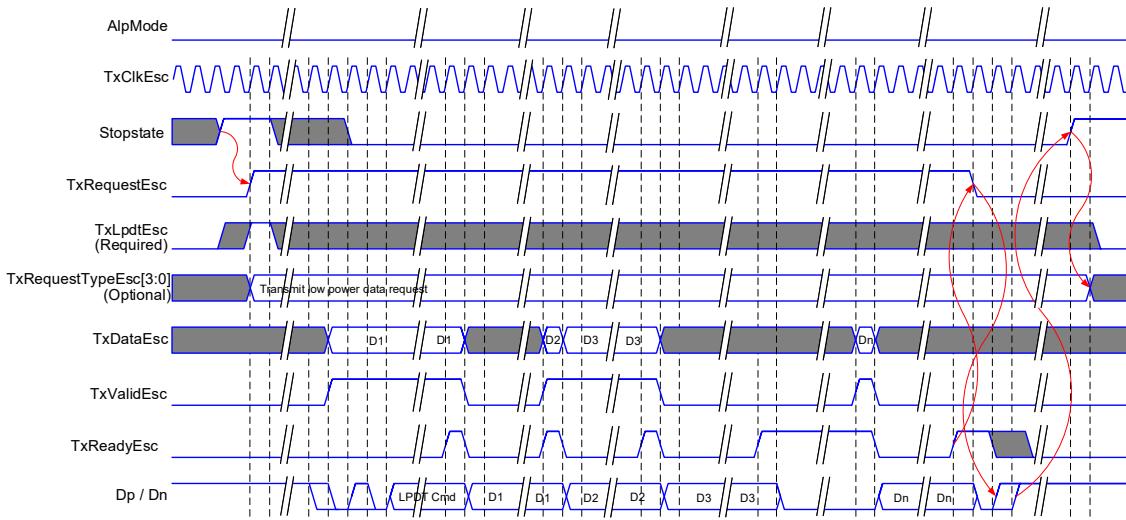


**Figure 109 Example High-Speed Receive at the Master Side: 8-Bit Bus, ALP Mode**

## A.8 Low-Power Data Transmission

For Low-Power data transmission the TxClkEsc is used instead of TxDDRClkHS-I/Q and TxWordClkHS. Furthermore, while the High-Speed interface signal TxRequestHS serves as both a transmit request and a data valid signal, on the Low-Power interface two separate signals are used. The Protocol directs the Data Lane to transmit low-power data by asserting TxRequestEsc with TxLpdEsc high. The Low-Power transmit data is transferred on the TxDataEsc lines when TxValidEsc and TxReadyEsc are both active at a rising edge of TxClkEsc. The byte is transmitted in the time after the TxDataEsc is accepted by the Lane Module (TxValidEsc = TxReadyEsc = high) and therefore the TxClkEsc continues running for some minimum time after the last byte is transmitted. The Protocol knows the byte transmission is finished when TxReadyEsc is asserted. After the last byte has been transmitted, the protocol de-asserts TxRequestEsc to end the Low-Power data transmission. This causes TxReadyEsc to return low, after which the TxClkEsc clock is no longer needed. Whenever TxRequestEsc transitions from high-to-low, it always remains in the low state for a minimum of two TxClkEsc clock cycles.

**Figure 110** shows an example Low-Power data transmission operation, when using LP mode.

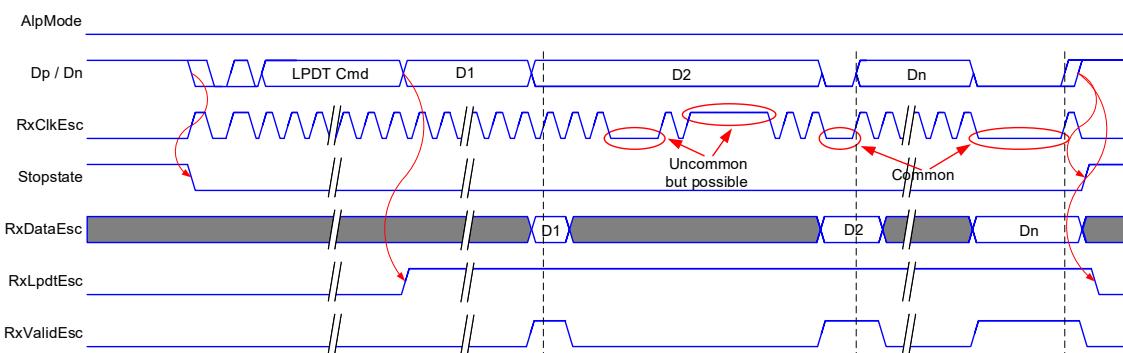


**Figure 110 Example Low-Power Data Transmission, LP Mode**

## A.9 Low-Power Data Reception

**Figure 111** shows an example Low-Power data reception when using LP mode. In this example, a Low-Power escape “clock” is generated from the Lane Interconnect by the logical exclusive-OR of the Dp and Dn lines. This “clock” is used within the Lane Module to capture the transmitted data. In this example, the “clock” is also used to generate RxClkEsc.

The signal RxLpdteEsc is asserted when the LPDT command is detected and stays high until the Lane returns to Stop state, indicating that the transmission has finished. It is important to note that because of the asynchronous nature of Escape Mode transmission, the RxClkEsc signal can stop at any time in either the high or low state. This is most likely to happen just after a byte has been received, but it could happen at other times as well.



**Figure 111 Example Low-Power Data Reception, LP Mode**

## A.10 Bi-Directional Data Lane Turnaround

If the Master side and Slave side data Lane Modules are both Bi-directional, it is possible to turn around the Link for High-Speed and/or Escape Mode signaling. As explained in [Section 6.5](#), which side is allowed to transmit is determined by passing a “token” back and forth. That is, the side currently transmitting passes the token to the receiving side. If the receiving side acknowledges the Turnaround request, as indicated by driving the appropriate Line state, the direction is switched.

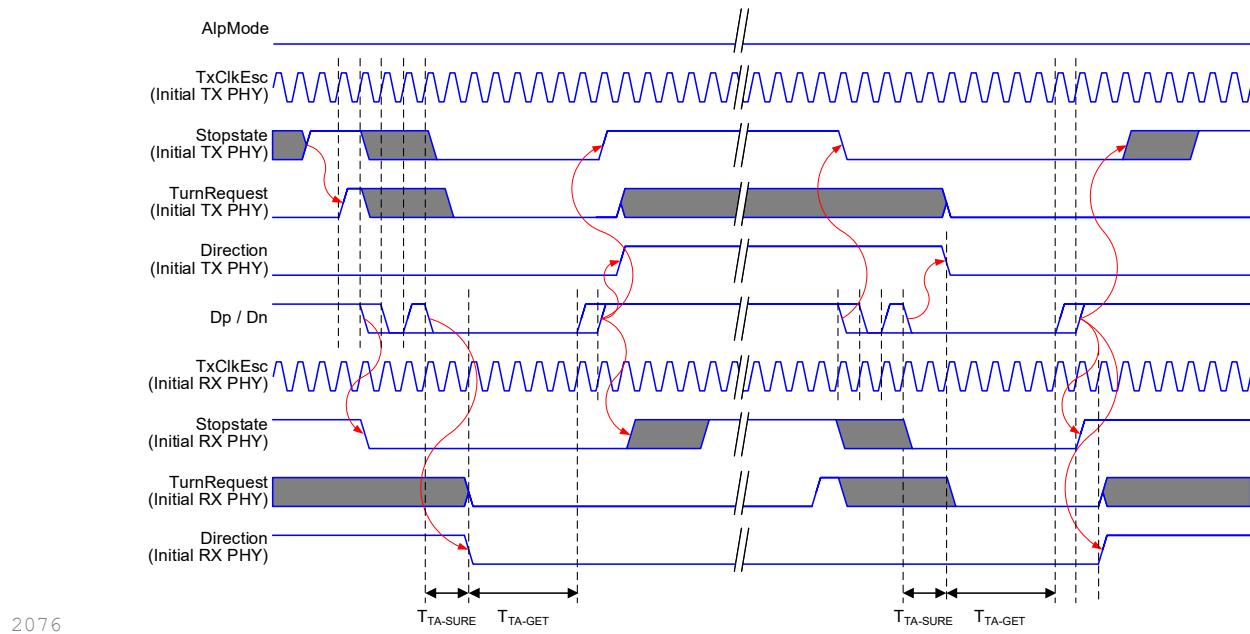
Note that in these diagrams, the signals labeled as “Initial TX PHY” are those associated with the PHY that is initially configured as a transmitter, and is initiating the turnaround. Similarly, the signals labeled as “Initial RX PHY” are those associated with the PHY that is initially configured as a receiver.

[Figure 112](#) shows an example of two turn-around events when using LP mode. At the beginning, the near end PHY is the transmitter, as shown by Direction=0. When the protocol on this side wishes to turn the Lane around (i.e. give the token to the other side), it asserts TurnRequest for at least one cycle of TxClkEsc. This initiates the Turnaround procedure. The far end PHY acknowledges the Turnaround request by driving the LP-10, and then the LP-11 on the Lines. When this happens, the local Direction signal changes from transmit (0) to receive (1).

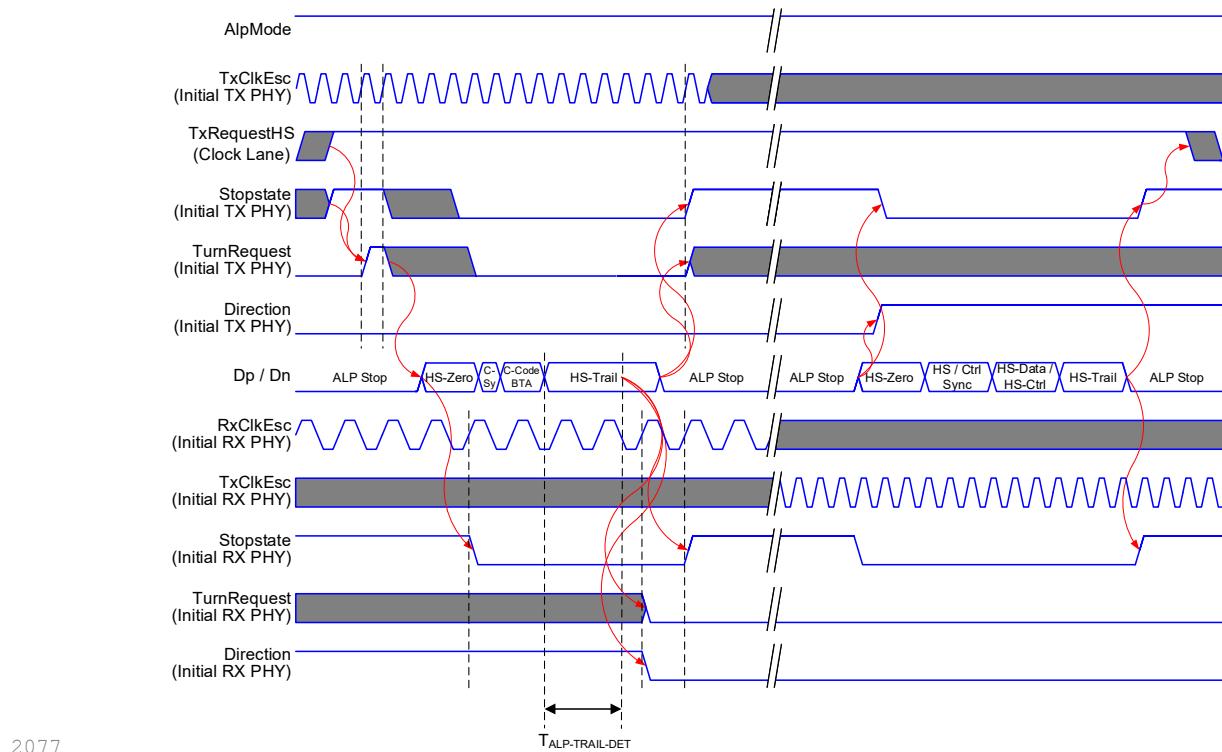
Later in the example of [Figure 112](#), the far end PHY initiates a Turnaround request, passing the token back to the local side. When this happens, the local Direction signal changes back to transmit (0). Note that there is no prescribed way for a receiver to request access to the Link. The current transmitter is in control of the Link direction and decides when to turn the Link around, passing control to the receiver.

If the far end PHY does not acknowledge the turn-around request, the Direction signal does not change.

[Figure 35](#) shows an example of a single turn-around event from a near end PHY to a far end PHY, when using ALP mode. The process is the same, just reversed for a turn-around event from the far end PHY to the near end PHY. Note that in the case of an ALP implementation, the far end PHY acknowledges the Turnaround request by sending any kind of burst. When this happens, the local Direction signal changes from transmit (0) to receive (1).



**Figure 112 Example Bi-Directional Data Lane Turnaround Transmit-to-Receive and Back to Transmit, LP Mode**



**Figure 113 Example Bi-Directional Data Lane Turnaround Transmit-to-Receive, ALP Mode**

## A.11 Trigger Command

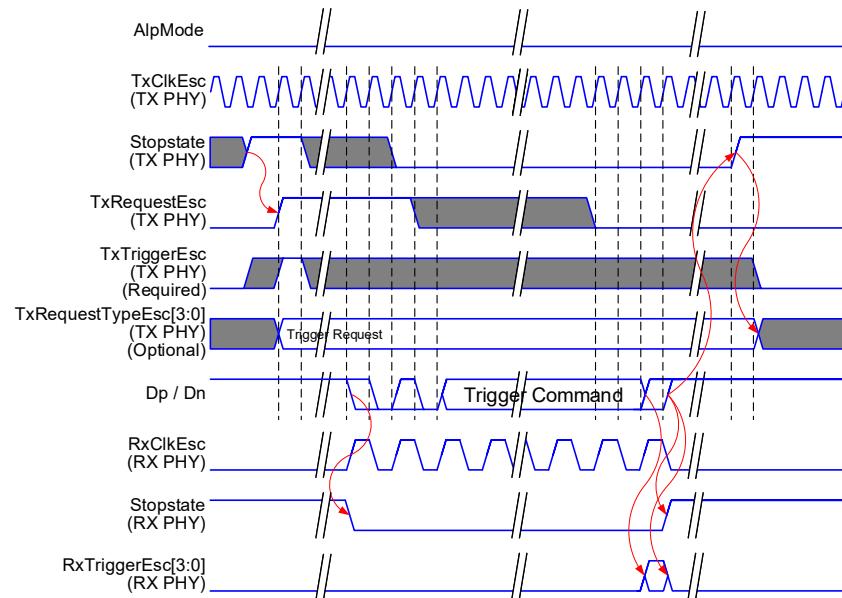
**Figure 114** illustrates an example of the scenario where the near end PHY has not completed the transmission of the trigger command at the time that the TxRequestEsc signal is de-asserted when using LP mode. In this scenario, the near end PHY will complete the transmission, then driven Mark-1 and LP-11.

**Figure 115** illustrates an example of the scenario where the near end PHY has completed the transmission of the trigger command and the TxRequestEsc signal is still asserted when using LP mode. In this scenario, the near end PHY will transmit the required space state, until the TxRequestEsc signal is de-asserted, at which time the near end PHY will drive Mark-1 and LP-11.

**Figure 116** illustrates an example of the scenario where the near end PHY has completed the transmission of the trigger command and the TxRequestEsc signal is still asserted while using LP mode. In this scenario, the near end PHY will transmit the optional dummy bytes in order to generate clocks on RxClkEsc of the far end receiver, until the TxRequestEsc signal is de-asserted, at which time the near end PHY will complete the transmission of the current byte then drive Mark-1 and LP-11. Note that the implementation of the transmission of the optional dummy bytes is implementation specific, and the data used for the dummy bytes is not required to be driven on the PPI interface.

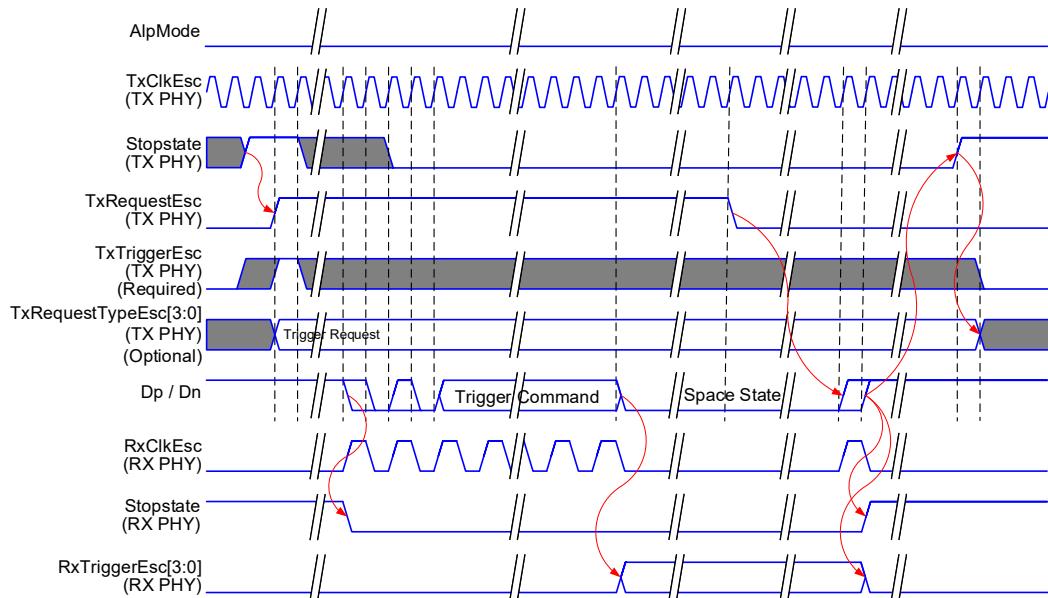
**Figure 117** illustrates an example of the scenario where a trigger command is initiated when using ALP mode.

Note that in these diagrams, the signals labeled as “TX PHY” are those associated with the PHY that is currently configured as a transmitter. Similarly, the signals labeled as “RX PHY” are those associated with the PHY that is currently configured as a receiver.



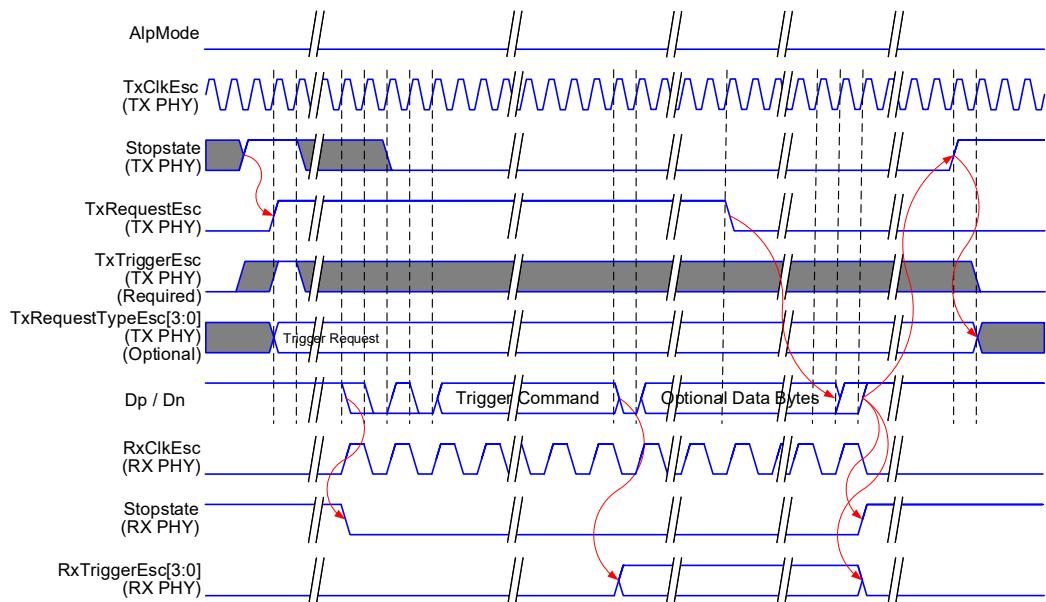
2097

**Figure 114 Example Trigger Command With TxRequestEsc De-asserted Before Command Completion, LP Mode**



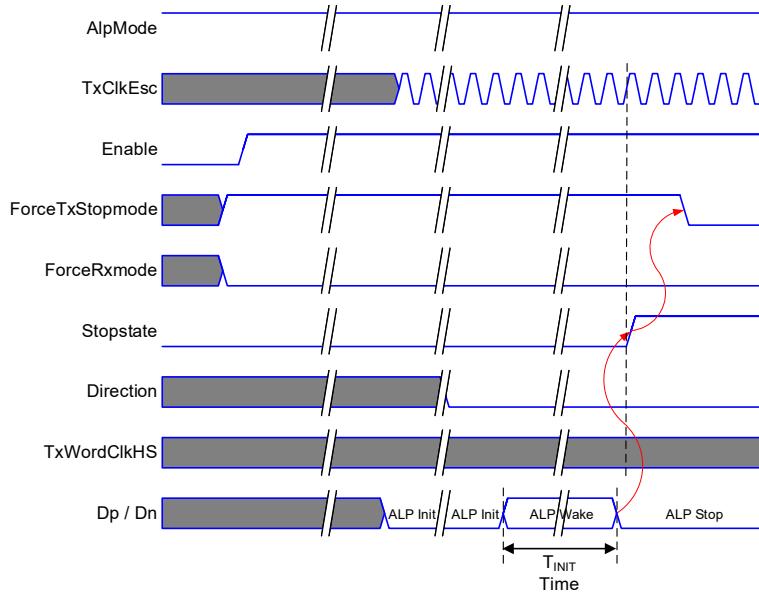
2098

**Figure 115 Example Trigger Command With TxRequestEsc De-asserted After Command Completion And Transmitting Space State, LP Mode**



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**Figure 116 Example Trigger Command With TxRequestEsc De-asserted After Command Completion And Transmitting Optional Data Bytes, LP Mode**



2100

**Figure 117 Example Trigger Command, ALP Mode**

## A.12 ULPS Transition

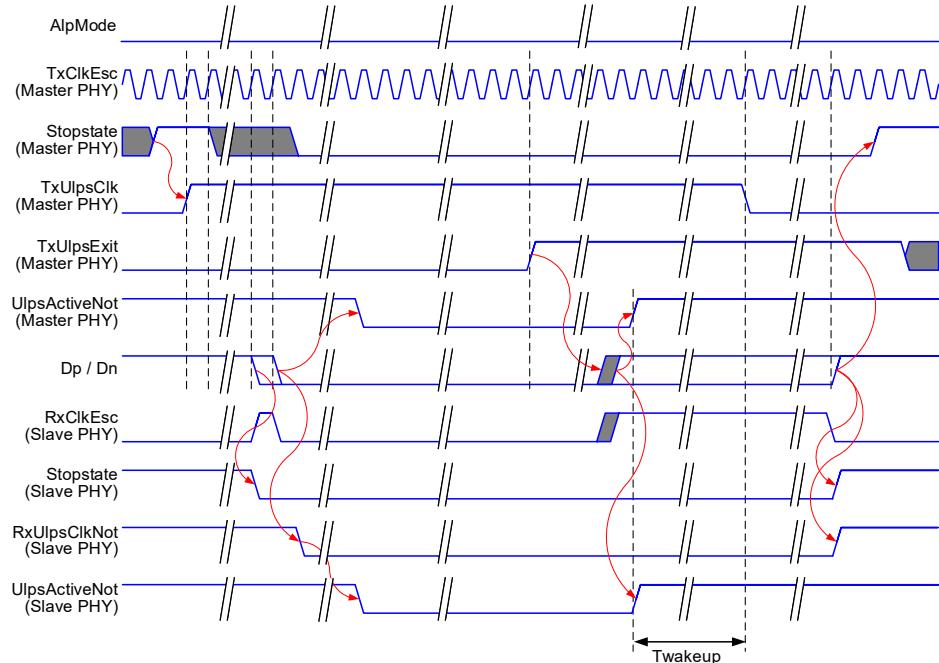
**Figure 118** illustrates examples of the sequences for entering and exiting the ULPS state for a Clock Lane when using LP mode.

**Figure 119** illustrates examples of the sequences for entering and exiting the ULPS state for a Clock Lane when using ALP mode.

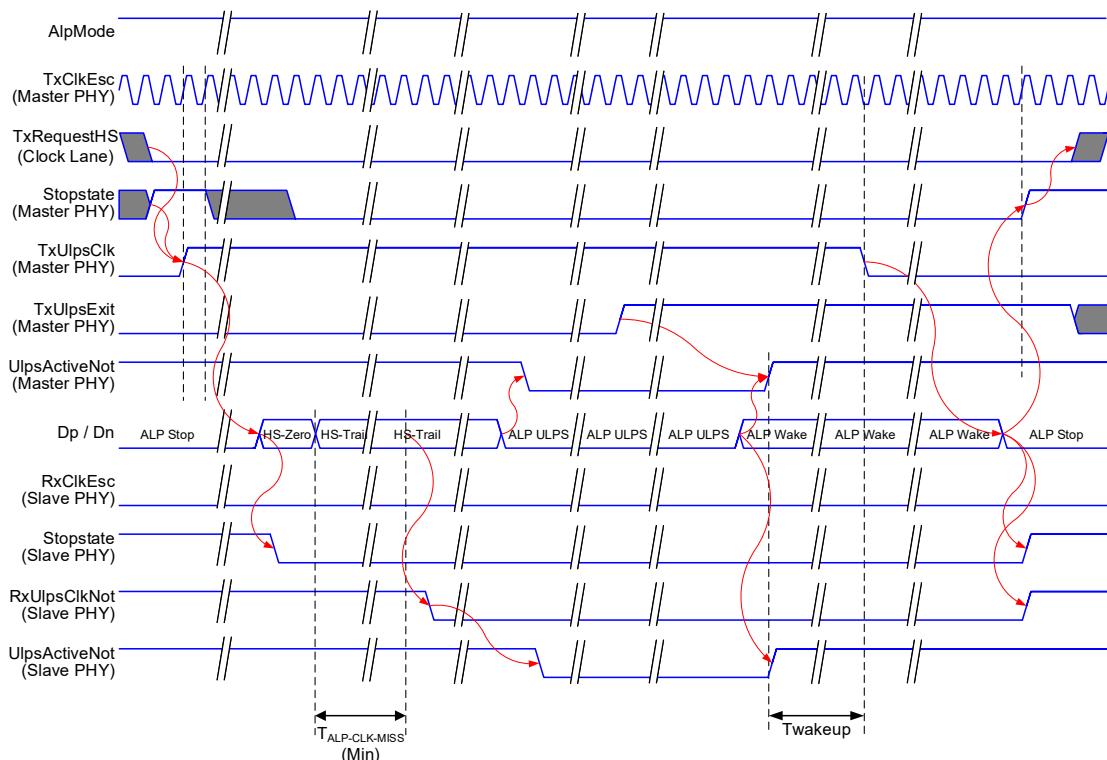
**Figure 120** illustrates examples of the sequences for entering and exiting the ULPS state for a data Lane when using LP mode.

**Figure 121** illustrates examples of the sequences for entering and exiting the ULPS state for a data Lane when using ALP mode.

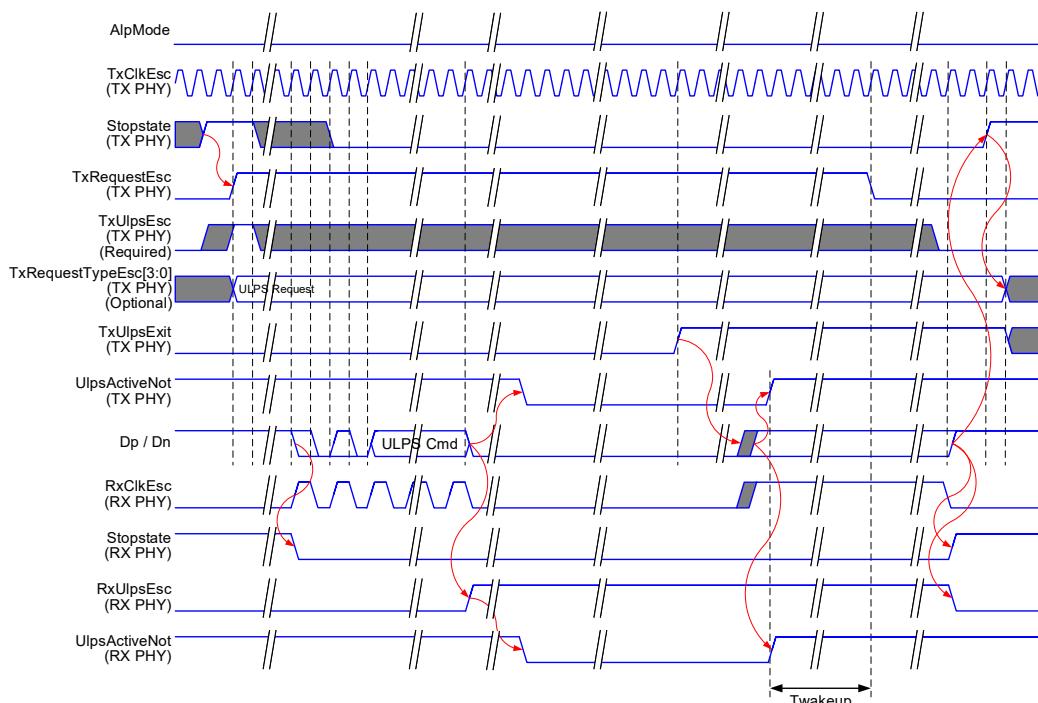
Note that in these diagrams, the signals labeled as “TX PHY” are those associated with the PHY that is currently configured as a transmitter. Similarly, the signals labeled as “RX PHY” are those associated with the PHY that is currently configured as a receiver.



**Figure 118 Example Clock Lane ULPS Entry and Exit, LP Mode**



**Figure 119 Example Clock Lane ULPS Entry and Exit, ALP Mode**



**Figure 120 Example Data Lane ULPS Entry and Exit, LP Mode**

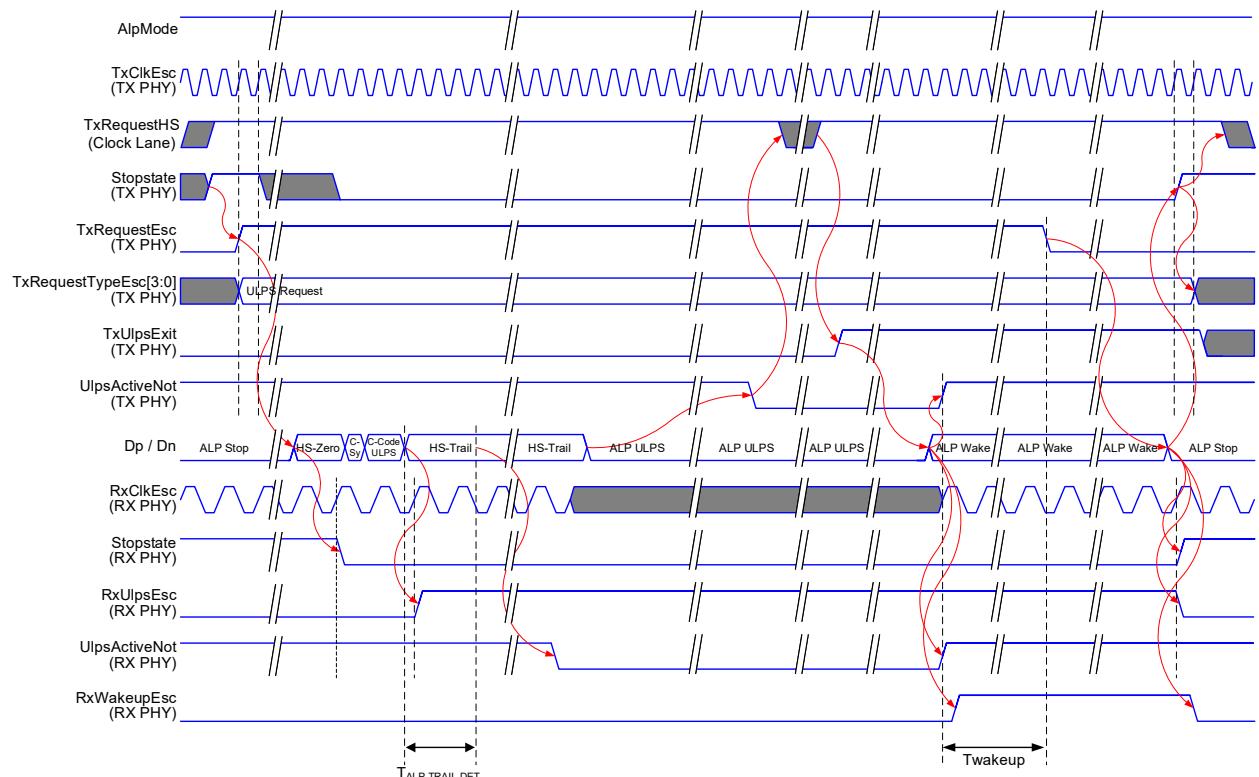


Figure 121 Example Data Lane ULPS Entry and Exit, ALP Mode

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### A.13 ALP Wakeup Pulse

Figure 122 illustrates an example of the sequences for generating an ALP wakeup pulse for a data lane.  
Note that in these diagrams, the signals labeled as “TX PHY” are those associated with the PHY that is currently configured as a transmitter. Similarly, the signals labeled as “RX PHY” are those associated with the PHY that is currently configured as a receiver.

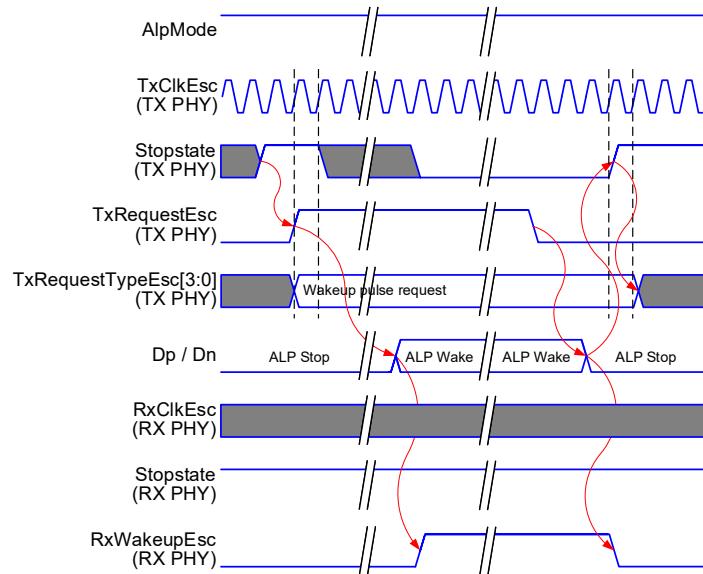


Figure 122 Example Data Lane ALP Wakeup Pulse

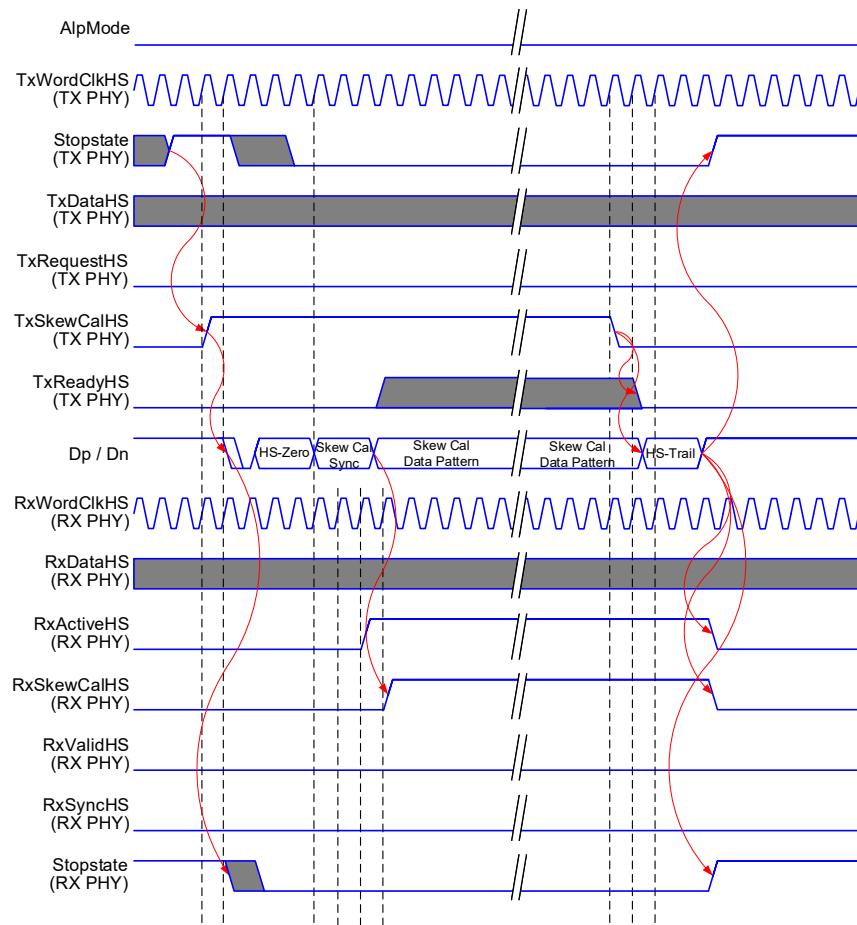
## A.14 Calibration

Initiation of deskew calibration from the transmitter is done using the TxSkewCalHS pin on the PPI interface. This signal can be used for both initial and the optional periodic deskew. Receiver deskew can be by-passable using the receiver configuration control. It is possible for the RxWordClkHS to vary in frequency and duty cycle during the deskew operation. If the RxWordClkHS is varied, the period variation from clock period to clock period will not be reduced by more than 0.5 UI with respect to the nominal period of RxWordClkHS. Note that there is not necessarily a direct timing relationship between RxActiveHS and RxSkewCalHS. In these diagrams, RxActiveHS is shown as asserted at the same time or one cycle before RxSkewCalHS. It is also valid for RxActiveHS to be asserted more than one clock cycle before RxSyncHS.

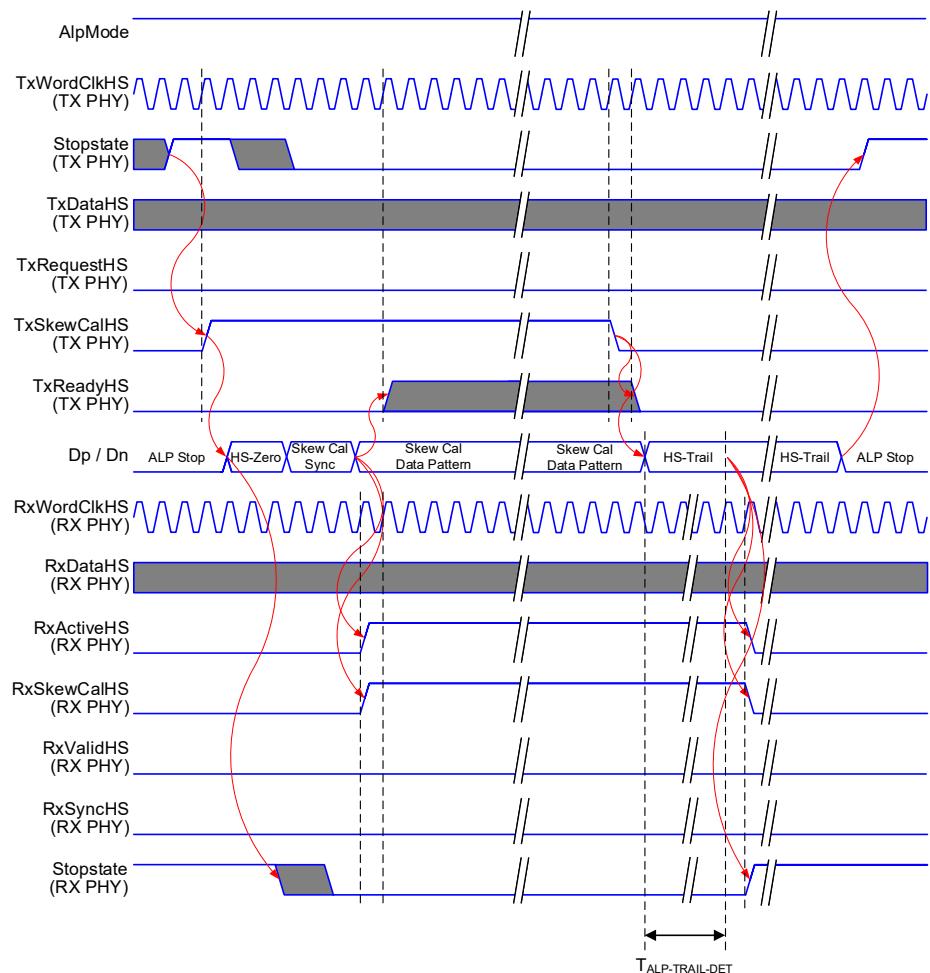
**Figure 123** shows the PPI signals as they operate during skew calibration in high-speed data transmission, when using LP mode.

**Figure 124** shows the PPI signals as they operate during skew calibration in high-speed data transmission, when using ALP mode.

Note that in these diagrams, the signals labeled as “TX PHY” are those associated with the PHY that is currently configured as a transmitter. Similarly, the signal labeled as “RX PHY” are those associated with the PHY that is currently configured as a receiver.



**Figure 123 Skew Calibration, LP Mode**



2139

**Figure 124 Skew Calibration, ALP Mode**

## A.15 High Speed Transmit and Receive with HS-Idle Function

2140 *Figure 125* illustrates High Speed data transmission and reception utilizing the HS-Idle function. Note that  
2141 the HS-Idle function is only supported in LP mode. RxWordClkHS is derived from the HS clock, and is  
2142 either at 1 or 0 level during the HS-Idle State. RxActiveHS and RxValidHS are similar to normal operation,  
2143 and are not de-asserted during the HS-Idle State. HS data reception starts with a pulse on RxSyncHS at the  
2144 beginning of the HS Date Burst after the HS-Idle State.

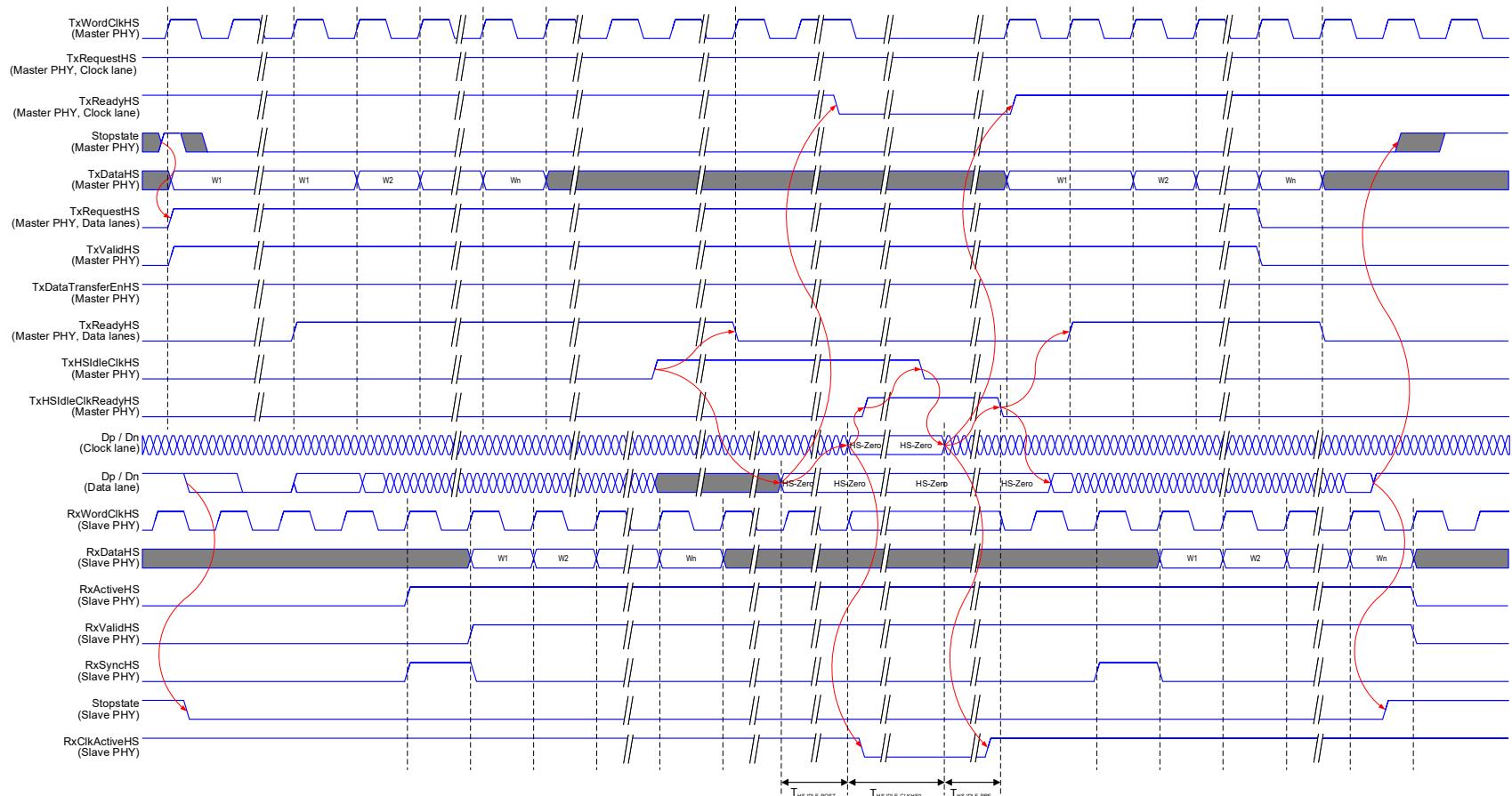


Figure 125 High Speed Transmission and Reception with HS-Idle Function

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2146

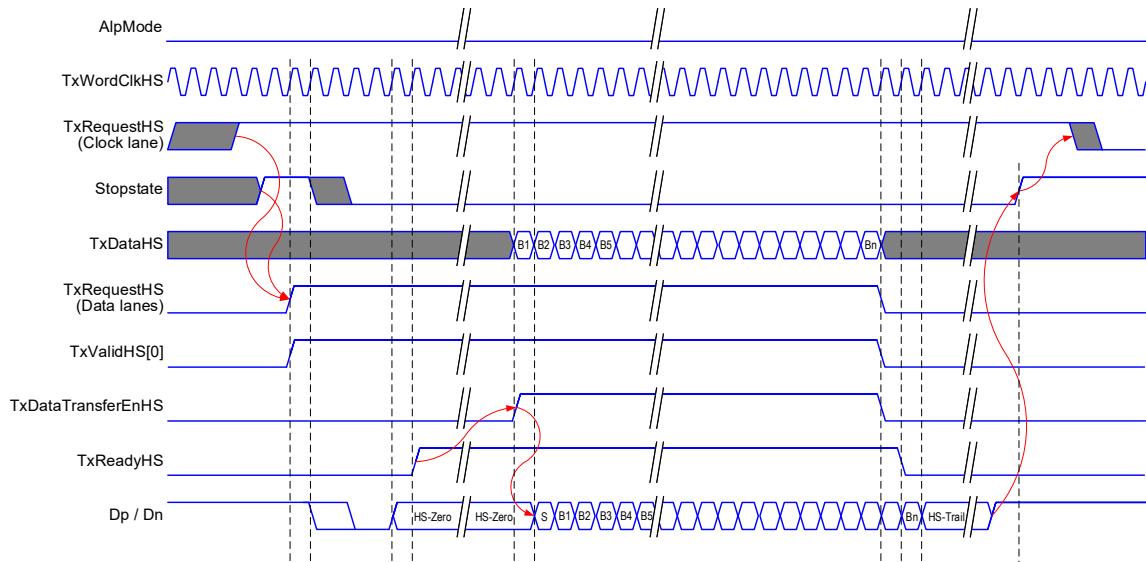
## A.16 High Speed Transmit Data Transfer Enable (No Preamble Sequence)

High-speed data transfers without a Preamble sequence can use the TxDataTransferEnHS signal to hold the PHY in an HS-Zero state until the protocol layer is ready to transfer data on TxDataHS, as follows:

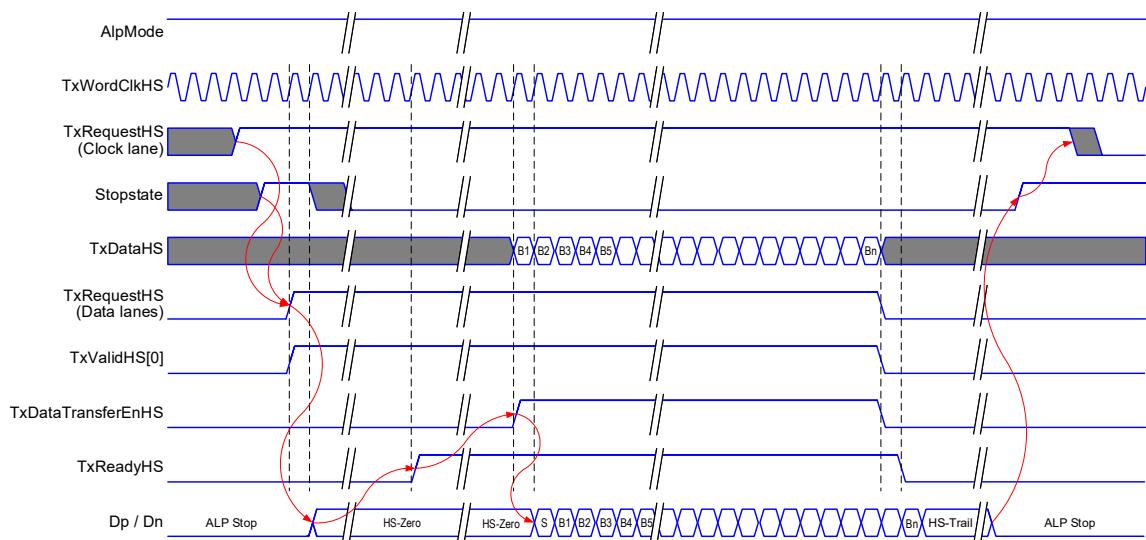
1. The protocol layer asserts TxRequestHS to the PHY.
2. The PHY drives the low-power signaling sequence, followed by the HS-Zero state.
3. When the PHY is ready for high-speed data, the PHY asserts TxReadyHS to the protocol layer.  
Note that the PHY controls the duration of the HS-Zero state. The PHY continues to drive HS-Zero until TxDataTransferEnHS is de-asserted.
4. When the protocol layer observes that TxReadyHS is asserted, the protocol layer begins to transfer valid TxDataHS and asserts TxDataTransferEnHS to the PHY.
5. When the PHY detects that TxDataTransferEnHS is asserted, it samples the TxDataHS, and sends the Leader sequence(s) and then the high-speed data.
6. When there is no more high-speed data to transmit, the protocol layer de-asserts TxDataTransferEnHS and TxRequestHS.

*Figure 126* shows a High-speed data transfer without Preamble sequence when using LP mode.

*Figure 127* shows a High-speed data transfer without Preamble sequence when using ALP mode.



**Figure 126 High Speed Data Transfer Enable with no Preamble, LP Mode**



**Figure 127 High Speed Data Transfer Enable with no Preamble, ALP Mode**

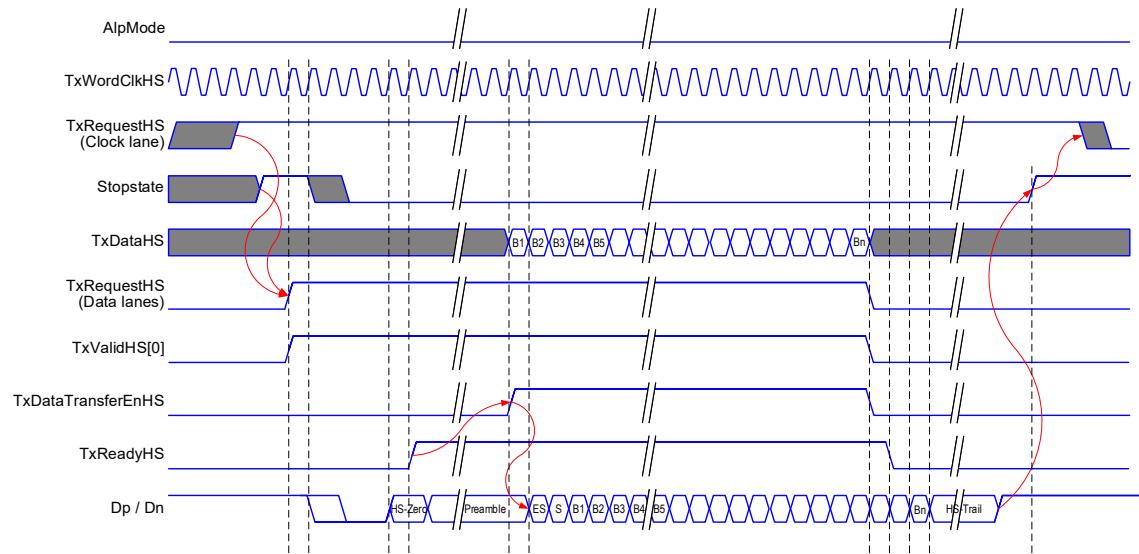
## A.17 High Speed Transmit Data Transfer Enable with Preamble Sequence

High-speed data transfers with a Preamble sequence can use the TxDataTransferEnHS signal to keep the PHY transmitting the Preamble sequence until the protocol layer is ready to transfer data on TxDataHS, as follows:

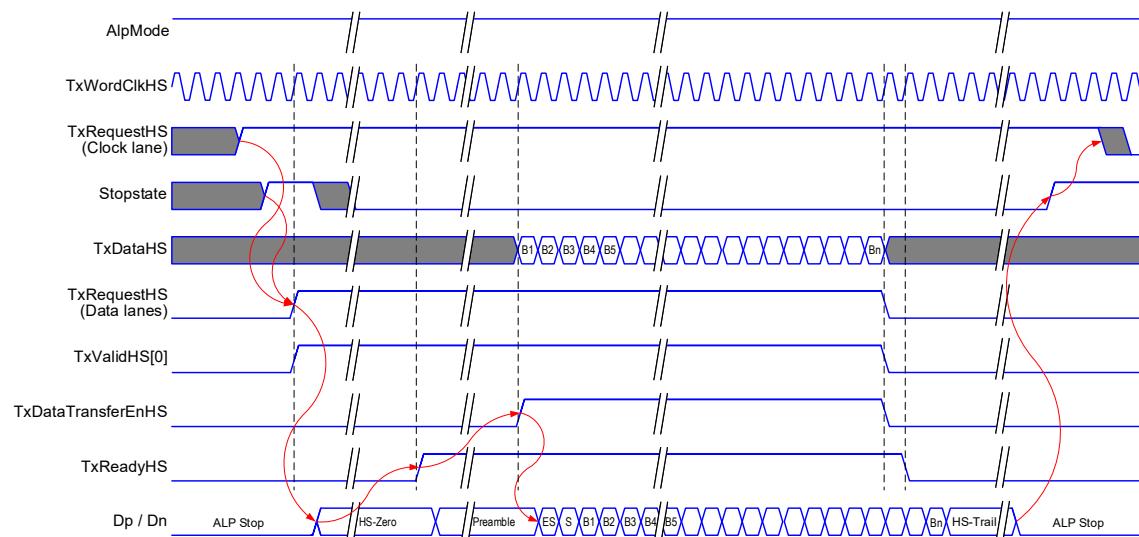
1. The protocol layer asserts TxRequestHS to the PHY
2. The PHY drives the low-power signaling sequence, followed by the HS-Zero state.
3. When the PHY is ready for high-speed data, the PHY asserts TxReadyHS to the protocol layer.  
Note that the PHY controls the duration of Preamble sequence as a function of TxDataTransferEnHS being asserted, while also maintaining the Preamble sequence timing parameters in **Table 20**.
4. When the protocol layer observes that TxReadyHS is asserted, the protocol layer begins to transfer valid TxDataHS and asserts TxDataTransferEnHS to the PHY.
5. When the PHY detects that TxDataTransferEnHS is asserted, it samples the TxDataHS and sends the Extended Sync pattern (ES), the Leader sequence (S), and then the high-speed data.
6. When there is no more high speed data to transmit, the protocol layer de-asserts TxDataTransferEnHS and TxRequestHS.

**Figure 128** shows a High-speed data transfer with Preamble sequence when using LP mode.

**Figure 129** shows a High-speed data transfer with Preamble sequence when using ALP mode.



**Figure 128 High Speed Data Transfer Enable with Preamble, LP Mode**



**Figure 129 High Speed Data Transfer Enable with Preamble, ALP Mode**

## A.18 LP and ALP Line Sequence Errors Reported By ErrControl

2183     Table 59 summarizes all valid LP signaling sequences, and error sequences that are derived from each. For  
2184     each error sequence, the “ErrControl Assertion Req / Opt” column indicates if the sequence is required to  
2185     assert ErrControl, or can optionally assert ErrControl for a given implementation.

2186     Table 60 summarizes potential ALP error sequences. For each error sequence, the “ErrControl Assertion  
2187     Req / Opt” column indicates if the sequence is required to assert ErrControl, or can optionally assert  
2188     ErrControl for a given implementation.

2189

**Table 59 ErrControl Assertion Requirements LP Mode**

Sequence ID	LP Sequence	Notes	ErrControl Assertion Req / Opt
HS-VLD	LP11, LP01, LP00, HS Data, LP11	Valid HS LP sequence	n/a
HS-ERR1	LP11, LP01, LP11	Sequence ending prematurely	Required
HS-ERR2	LP11, LP01, LP10, Anything	Simultaneous LP signal transitions	Optional
HS-ERR3	LP11, LP01, LP00, HS Data, LP01/LP10, LP11	Invalid transition to LP11. <i>Note that LP01 or LP10 could be detected by the receiver for a short period of time when transitioning from LP00 to LP11.</i>	Optional
ESC-VLD	LP11, LP10, LP00, LP01, LP00, LP CTRL/Data, LP10, LP11	Valid escape LP sequence	n/a
ESC-ERR1	LP11, LP10, LP11	Sequence ending prematurely	Required
ESC-ERR2	LP11, LP10, LP01, Anything	Simultaneous LP signal transitions	Optional
ESC-ERR3	LP11, LP10, LP00, LP11	Simultaneous LP signal transitions	Optional
ESC-ERR4	LP11, LP10, LP00, LP01, LP11	Sequence ending prematurely	Required
ESC-ERR5	LP11, LP10, LP00, LP01, LP10, Anything	Simultaneous LP signal transitions	Optional
ESC-ERR6	LP11, LP10, LP00, LP01, LP00, LP11	Simultaneous LP signal transitions	Optional
ESC-ERR7	LP11, LP10, LP00, LP01, LP00, LP CTRL/Data, LP01, LP11	Incorrect exit sequence	Optional
ESC-ERR9	LP11, LP10, LP00, LP01, LP00, LP CTRL/Data, LP11	Simultaneous LP signal transitions	Optional
TRN-VLD	LP11, LP10, LP00, LP10, LP00, Turnaround, LP10, LP11	Valid turnaround LP sequence	n/a
TRN-ERR1	LP11, LP10, LP11	Sequence ending prematurely	Required
TRN-ERR2	LP11, LP10, LP01, Anything	Simultaneous LP signal transitions	Optional
TRN-ERR3	LP11, LP10, LP00, LP11	Simultaneous LP signal transitions	Optional
TRN-ERR4	LP11, LP10, LP00, LP10, LP11	Sequence ending prematurely	Required
TRN-ERR5	LP11, LP10, LP00, LP10, LP01, Anything	Simultaneous LP signal transitions	Optional
TRN-ERR6	LP11, LP10, LP00, LP10, LP00, Turnaround, LP01, Anything	Incorrect exit sequence	Optional
TRN-ERR7	LP11, LP10, LP00, LP10, LP00, Turnaround, LP11	Simultaneous LP signal transitions	Optional
OTH-ERR1	LP11, LP00, Anything	Simultaneous LP signal transitions	Optional

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**Table 60 ErrControl Assertion Requirements, ALP Mode**

<b>Sequence ID</b>	<b>ALP Sequence</b>	<b>Notes</b>	<b>ErrControl Assertion Req / Opt</b>
TRN-ERR1	Bus turnaround control code not immediately followed by HS-Trail.	–	Required
TRG-ERR1	Trigger control code not immediately followed by HS-Trail.	–	Required
ULP-ERR1	ULPS control code not immediately followed by HS-Trail.	–	Required
OTH-ERR1	Invalid control code.	–	Optional

## Annex B Interconnect Design Guidelines (Informative)

This Annex contains design guidelines in order to meet the interconnect requirements as specified in **Section 8**.

### B.1 Practical Distances

For mobile applications, the maximum Lane flight time is defined at 2 ns. Assuming less than 100 ps wiring delay within the RX-TX modules each, the physical distance that can be bridged with external interconnect is around  $54 \text{ cm}/\sqrt{\epsilon}$ . For most practical PCB and flex materials this corresponds to maximum distances around 25–30 cm.

For IoT applications, the Lane flight time can be determined based on the signal propagation speed and the interconnect length. For example: a Lane with a 4 m total length and a signal propagation speed of one-half of the speed of light in vacuum, has a Lane flight time of approximately 27 ns. For the IoT channel, the maximum total flight time can be as large as 40 ns considering all variables.

### B.2 RF Frequency Bands: Interference

On one side of the Lane there are the RF interference frequencies, which disturb the signals of the Lane. Most likely the dominant interferers are the transmit band frequencies of wireless interconnect standards. On the other side there are the frequencies for which generated EMI by the Lane should be as low as possible because very weak signals in these bands must be received by the radio IC. Some important frequency bands are:

Transmit Bands

- GSM 850 (824-849 MHz)
- GSM 900 (880-915 MHz)
- GSM DCS (1710-1785 MHz)
- GSM PCS (1850-1910 MHz)
- WCDMA (1920-1980 MHz)
- FLASH-OFDM, GSM (450 MHz)

Receive Bands:

- GSM 850 (869-894 MHz)
- GSM 900 (925-960 MHz )
- GSM DCS (1805-1880 MHz)
- GSM PCS (1930-1990 MHz)
- WCDMA (2110-2170 MHz)
- GPS (1574-1577 MHz)

It is important to identify the lowest interference frequency with significant impact, as this sets ' $f_{INT,MIN}$ '. For this specification,  $f_{INT,MIN}$  is decided to be 450 MHz, because this frequency will most likely be used as the new WCDMA band in the USA in the future.

### B.3 Transmission Line Design

2223 In most cases the transmission lines will either be designed as striplines and/or micro-striplines. The  
2224 coupling between neighboring lines within a pair is small if the distance between them is  $>2x$  the dielectric  
2225 thickness. For the separation of multiple pairs it is highly recommended to interleave the pairs with a  
2226 ground or supply Line in order to reduce coupling.

### B.4 Reference Layer

2227 In order to achieve good signal integrity and low EMI it is recommended that either a ground plane or a  
2228 ground signal is in close proximity of any signal Line.

### B.5 Printed-Circuit Board

2229 For boards with a large number of conductor layers the dielectric spacing between layers may become so  
2230 small that it would be hard to meet the characteristic impedance requirements. In those cases a micro-  
2231 stripline in the top or bottom layers may be a better solution.

### B.6 Flex-foils

2232 Either two conductor layers or a reasonable connected cover layer makes it much easier to meet the  
2233 specifications

### B.7 Series Resistance

2234 The DC series resistance of the interconnect should be less than  $5 \Omega$  in order to meet the specifications. It is  
2235 strongly recommended to keep the resistance in the ground connection below  $0.2 \Omega$ . Furthermore, it is  
2236 recommended that the DC ground shift be less than 50 mV, which may require an even lower value if a  
2237 large current is flowing through this ground. The lower this ground series resistance value can be made, the  
2238 better it is for reliability and robustness.

### B.8 Connectors

2239 Connectors usually cause some impedance discontinuity. It is important to carefully minimize these  
2240 discontinuities by design, especially with respect to the through-connection of the reference layer. Although  
2241 connectors are typically rather small in size, the wrong choice can mess-up signals completely. Please note  
2242 that the contact resistance of connectors is part of the total series resistance budget and should therefore be  
2243 sufficiently low.

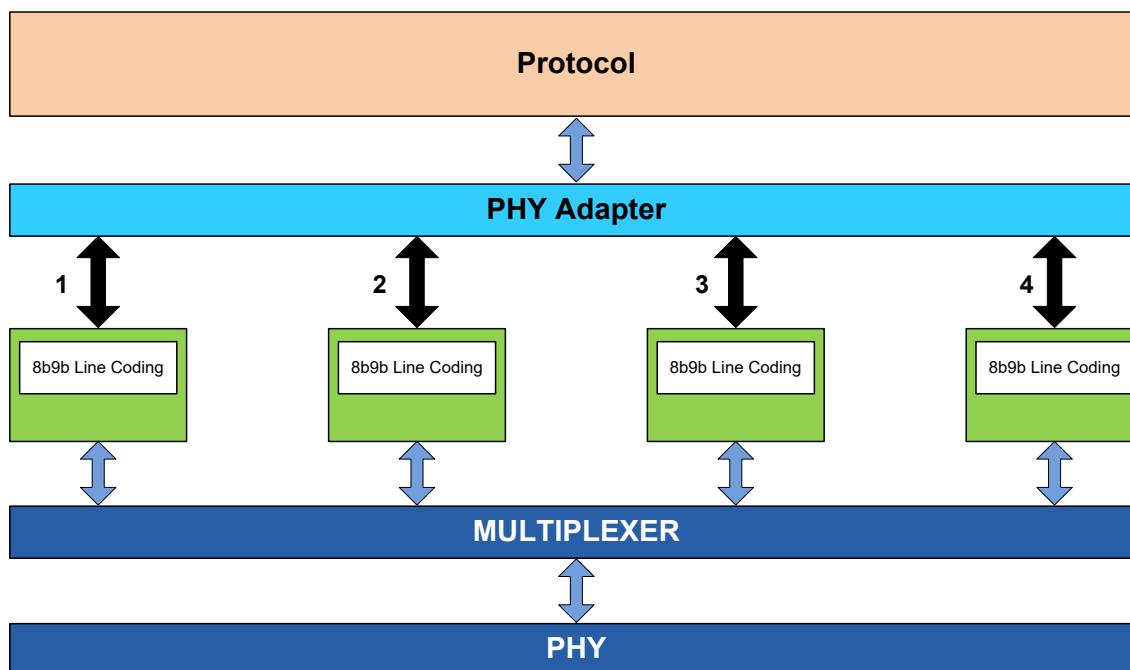
## Annex C 8b9b Line Coding for D-PHY (Normative)

Raw data transmission without constraining the data set does not allow in-band control signaling (control symbols inserted into the data stream) during transmission. Line coding conditions the possible bit sequences on the wires and provides reserved codes to include additional control features. Useful additional features may be, for example, idle symbols, specific-event identifiers, sync patterns, and protocol markers.

Comma codes, bit sequences that do not appear anywhere in the data stream (in the absence of bit errors) unless these are intentionally transmitted, provide synchronization features and are very useful to increase robustness.

Furthermore, a Line-coding scheme that guarantees a minimum edge density improves the signaling quality and enables skew calibration in the PHY.

**Figure 130** shows how the Line coding sub-layer fits into the standard hierarchy. The Line coding can be considered as a separate sub-layer on top of the basic D-PHY. Optimizations by merging layers are allowed if the resulting solution complies with the PHY specification. These optimization choices are left to implementers.



**Figure 130 Line Coding Layer Example**

Note that the Line coding sub-layer is optional. Protocols may exploit only the baseline PHY without Line coding. This feature is provided for compatibility with existing protocols. However, in case a protocol decides to use Line coding, it shall be implemented as described in this annex.

The PHY-protocol interface above the Line coding sub-layer (EPPI) is very similar to the PPI. Some additional signals enable a more functional and flexible control of the PHY with Line Coding. For details of the EPPI see Section C.5.

## C.1 Line Coding Features

The 8b9b Line coding scheme provides features to both the PHY and protocol layers.

### C.1.1 Enabled Features for the Protocol

- Comma code marker for special protocol features
- Word synchronization/resynchronization during transmission bursts
- Automatic idling support; no need for TX to always provide valid data during transmission
- Possibility for future PHY compatible PHY-Protocol Interface (PPI)

### C.1.2 Enabled Features for the PHY

- On-the-fly word resynchronization
- Simplification of EoT signaling
- Reduced latency
- Automatic idle symbol insertion and removal in absence of data
- Skew calibration in the RX possible

## C.2 Coding Scheme

This Section describes the details of the coding scheme.

### C.2.1 8b9b Coding Properties

The 8b9b coding has the following properties:

- All code words are nine bits long. Data is encoded byte-wise into 9-bit words, which corresponds to a 12.5% coding overhead.
- Sixteen regular exception codes, i.e. code words that do not appear as regular data words, but require word sync for reliable recognition, are available.
- Six unique exception codes, i.e. code words that do not appear within any sliding window except when that code word is transmitted, are available.
- Guaranteed minimum edge density of at least two polarity transitions per word. Therefore, each word contains at least two ones and two zeros.
- Simple logical functions for encoding and decoding
- Run length is limited to a maximum of seven bits. Data codes have a maximum run length of five bits, unique exception codes have run lengths of six or seven bits.

### C.2.2 Data Codes: Basic Code Set

Assume the following notation for the input data word and the coded data word:

- 8-bit data byte: [B<sub>1</sub> B<sub>2</sub> B<sub>3</sub> X<sub>1</sub> X<sub>2</sub> Q<sub>1</sub> Q<sub>2</sub> Q<sub>3</sub>]
- 9-bit code word: [B<sub>1</sub> X<sub>1</sub> Y<sub>1</sub> Y<sub>2</sub> B<sub>2</sub> B<sub>3</sub> Y<sub>3</sub> Y<sub>4</sub> X<sub>2</sub>]

The 256 data codes are denoted by Dxxx, where xxx is the value of the corresponding 8-bit data byte.

The 8-bit data byte shall be the input for the encoding, and result of the decoding, function. There can be any arbitrary bijective 8b-to-8b logical transformation function between real source data bytes from the protocol and the input data bytes for encoding, as long as the inverse function is present at the receiver side. If such a function is used, it shall be defined in the protocol specification.

The bits {B<sub>1</sub>, B<sub>2</sub>, B<sub>3</sub>, X<sub>1</sub>, X<sub>2</sub>} appear directly in the code words as can be seen in the code word structure.

{Q<sub>1</sub>, Q<sub>2</sub>, Q<sub>3</sub>} are the remaining three bits in the data byte, which are encoded into {Y<sub>1</sub>, Y<sub>2</sub>, Y<sub>3</sub>, Y<sub>4</sub>} using {X<sub>1</sub>, X<sub>2</sub>}. The decoding of {Y<sub>1</sub>, Y<sub>2</sub>, Y<sub>3</sub>, Y<sub>4</sub>} into {Q<sub>1</sub>, Q<sub>2</sub>, Q<sub>3</sub>} does not require {X<sub>1</sub>, X<sub>2</sub>}.

2298 The relation between  $Q_i$ ,  $X_i$  and  $Y_i$  is shown in **Table 61**.

2299 **Table 61 Encoding Table for 8b9b Line Coding of Data Words**

8-bit Data Byte								9-bit Code Word, Y bits			
B <sub>1</sub>	B <sub>2</sub>	B <sub>3</sub>	X <sub>1</sub>	X <sub>2</sub>	Q <sub>1</sub>	Q <sub>2</sub>	Q <sub>3</sub>	Y <sub>1</sub>	Y <sub>2</sub>	Y <sub>3</sub>	Y <sub>4</sub>
x	x	x	1	1	1	1	0	0	1	0	0
			0							1	1
			x	0	1	0				0	1
				1	0	0				1	0
x	x	x	1	1	1	1	1	1	0	0	0
			0							1	1
			x	0	1	1				0	1
				1	0	1				1	0
x	x	0	x	0	0	0		1	1	0	1
		1						0	0		
		0	x	0	0	1		1	1	1	0
		1						0	0		

**Note:**

$x = \text{don't care}$

2300 The logical relation for encoding between  $\{Q_1, Q_2, Q_3, X_1, X_2\}$  and  $\{Y_1, Y_2, Y_3, Y_4\}$  is given by the  
2301 following equations:

$$Y_1 = (\sim Q_1 \& \sim Q_2 \& \sim X_1) | (Q_1 \& Q_3) | (Q_2 \& Q_3)$$

$$Y_2 = (\sim Q_1 \& \sim Q_2 \& \sim X_1) | (Q_1 \& \sim Q_3) | (Q_2 \& \sim Q_3)$$

$$Y_3 = (Q_1 \& \sim Q_2) | (Q_1 \& Q_2 \& \sim X_2) | (\sim Q_2 \& Q_3)$$

$$Y_4 = (\sim Q_1 \& Q_2) | (Q_1 \& Q_2 \& \sim X_2) | (\sim Q_1 \& \sim Q_3)$$

2306 The logical relation for decoding between  $\{Y_1, Y_2, Y_3, Y_4\}$  and  $\{Q_1, Q_2, Q_3\}$  is:

$$Q_1 = (Y_1 \wedge Y_2) \& \sim(\sim Y_3 \& Y_4)$$

$$Q_2 = (Y_1 \wedge Y_2) \& \sim(Y_3 \& \sim Y_4)$$

$$Q_3 = (Y_1 \& \sim Y_2) | (Y_1 \& Y_2 \& Y_3) | (\sim Y_1 \& \sim Y_2 \& Y_3)$$

$$= (Y_1 \& \sim Y_2) | (\sim(Y_1 \wedge Y_2) \& Y_3)$$

2311 These logical functions show that the encoding and decoding can be implemented with a few dozen logic  
2312 gates and therefore do not require additional hardware such as a lookup table or storage of history data.

### C.2.3 Unique Exception Codes (Comma Codes)

Unique means that these codes are uniquely identifiable in the data stream because these sequences do not occur in any encoding or across word boundaries, assuming no bits are corrupted. The data-encoding scheme described in **Section C.2.2** enables a very simple run-length limit based unique exception code mechanism.

There are four code sequences available, called Type A Comma codes, with a run length of six bits, and two code sequences, called Type B Comma codes, with a run length of seven bits. Currently, four Comma codes are sufficient to cover the required features and therefore only Type A Comma codes are used. Type B Comma codes are reserved for future use.

**Table 62 Comma Codes**

Type	Run Length, bits	Code Name	Comma Code	Feature
Type A	6	C600	0 1111 1100	Protocol
		C611	1 0000 0011	EoT
		C610	1 0000 0010	Idle/Sync 1
		C601	0 1111 1101	Idle/Sync 2
Type B	7	C701	1 0000 0001	Reserved 1
		C710	0 1111 1110	Reserved 2

### C.2.4 Regular Exception Codes

The normal data set does not use all codes with a maximum run-length of five bits. There are two combinations of the  $\{X_i, Y_i\}$  bits that do not appear in any data code word that are available as regular exception codes. Since Comma Codes are defined to have a run-length of six or seven bits, this gives three freely usable bits per code word and results in  $2^3=8$  different Regular Exception Codes. The syntax of the Regular Exception Code words is given in **Table 63**, where the bits  $B_1$ ,  $B_2$  and  $B_3$  can have any binary value.

**Table 63 Regular Exception Code Structure**

	X <sub>1</sub>	Y <sub>1</sub>	Y <sub>2</sub>			Y <sub>3</sub>	Y <sub>4</sub>	Y <sub>2</sub>	Code Name
B <sub>1</sub>	0	1	1	B <sub>2</sub>	B <sub>3</sub>	0	0	1	C410-C417
B <sub>1</sub>	1	0	0	B <sub>2</sub>	B <sub>3</sub>	1	1	0	C400-C407

These code words are not unique sequences like the Comma codes described in **Table 62**, but can only be used as exception codes if word sync is already accomplished. These codes are currently reserved and not yet allocated to any function.

### C.2.5 Complete Coding Scheme

The complete code table can be found in **Table 65**.

### C.3 Operation with the D-PHY

The Line coding impacts the payload of transmission bursts. Section C.3.1 described the generic issues for both HS and LP transmission. Section C.3.2 and Section C.3.3 describe specific details for HS and LP transmission, respectively.

#### C.3.1 Payload: Data and Control

The payload of a HS or LP transmission burst consists of concatenated serialized 9-bit symbols, representing both data and control information.

##### C.3.1.1 Idle/Sync Comma Symbols

Idle/Sync Comma code words can be present as symbols within the payload of a transmission burst. These symbols are inserted either on specific request of the protocol, or autonomously when there is a transmission request but there is no valid data available either at the beginning, or anywhere, during transmission. The Idle pattern in the latter case is an alternating C601 and C610 sequence, until there is valid data available to transmit, or transmission has ended. Idle periods may begin with either of the two prescribed Idle symbols. The RX-side PHY shall remove Idle/Sync symbols from the stream and flag these events to the protocol.

##### C.3.1.2 Protocol Marker Comma Symbol

Comma symbol C600 (Protocol Marker) is allocated for use by protocols on top of the D-PHY. This symbol shall be inserted in the stream on request of the TX-side protocol and flagged by the receiving PHY to the RX-side protocol.

##### C.3.1.3 EoT Marker

Comma symbol C611 is allocated as the EoT Marker symbol.

#### C.3.2 Details for HS Transmission

##### C.3.2.1 SoT

The SoT procedure remains the same as the raw data D-PHY SoT. See Section 6.4.2. The SoT sequence itself is NOT encoded, but can be easily recognized.

The first bit of the first transmitted code symbol of a burst shall be aligned with the rising edge of the DDR Clock.

##### C.3.2.2 HS Transmission Payload

The transmitted burst shall consist of concatenated serialized 9-bit symbols as described in Section C.3.1.

The TX-side PHY can idle by sending the Idle sequences as described in Section C.3.1.1

##### C.3.2.3 EoT

The TX-side PHY shall insert an EoT marker symbol at the moment the request for HS transmission is withdrawn. The transmitter can pad additional bits after this EoT-Marker symbol before actually switching to LP mode (EoT sequence).

The RX-side PHY shall remove the EoT-Marker symbol and any additional bits appearing after it. Note that with Line coding, EoT-processing by backtracking on LP-11 detection to avoid (unreliable) non-payload bits on the PPI is no longer required as the EoT marker symbol notifies the RX-side PHY before the End-of-Transmission.

### C.3.3 Details for LP Transmission

#### C.3.3.1 SoT

2362 The start of LP transmission is identical to basic D-PHY operation.

#### C.3.3.2 LP Transmission Payload

2363 The transmitted burst shall consist of concatenated serialized 9-bit symbols as described in Section C.3.1.

2364 During LPDT, the TX-side PHY can idle in two ways: either it can send the Idle sequences as described in  
2365 Section C.3.1.1 and implicitly provide a clock signal to the RX-side PHY, or it can pause the transmission  
2366 by keeping the Lines at LP-00 (Space) for a certain period of time between bits, which interrupts the clock  
2367 on the RX side, but minimizes power consumption.

#### C.3.3.3 EoT

2368 The TX-side PHY shall insert an EoT marker symbol at the moment the request for LP transmission is  
2369 withdrawn. The TX-side PHY can pad additional (spaced-one-hot) bits after the EoT-Marker symbol before  
2370 actually ending the transmission by switching via Mark to Stop state (End of LPDT procedure).

2371 The RX-side PHY shall remove the EoT-marker symbol and any additional bits appearing after it.

## C.4 Error Signaling

2372 The usage of a Line code scheme enables the detection of many signaling errors. These errors include:

- Non-existing code words
- Non-aligned Comma symbols
- EoT detection without detection of EoT-Marker

2376 Detection and flagging of errors is not required, but may help the protocol to recover faster from an error  
2377 situation.

## C.5 Extended PPI

The interface to the protocol shall be extended with functional handles (TX) and flags (RX) to manage the usage of Comma symbols. Whenever necessary, the transmitting PHY can hold the data delivery from the protocol to the TX PHY with the TxReadyHS or TxReadyEsc signal. This is already provided for in the current PPI.

The PPI shall be extended with a TX Valid signal for HS data transmission, TxValidHS. Encoded operation allows for Idling of the Link when there is no new valid data. If the transmitter is ready and the provided data is not valid, an Idle symbol shall be inserted into the stream. Note, contrary to the basic PHY PPI, the Valid signals for a coded PHY can be actively used to manage the data on both TX and RX sides. This arrangement provides more flexibility to the PHY and Protocol layers. For LPDT, this Valid signaling already exists in the PPI. Addition of TxValidHS signal eliminates the constraint in the PPI description for TxRequestHS that “protocol always provides valid data”.

On the RX side, errors may be flagged to the protocol in case unexpected sequences are observed. Although many different errors are detectable, it is not required that all these errors flags be implemented. The number of error flags implemented depends on the cost/benefit trade-off to be made by the implementer. These error features do not impact conformance of the D-PHY. The signals are mentioned here for informative purposes only.

All control signals shall remain synchronous to the TxWordClk, or RxWordClk. The control signal clock frequency shall be equal to or greater than  $1/(n * 9)$  of the serial bit rate, where n is the data bus width in bytes.

**Table 64** lists the additional signals for the PPI on top of the coding sub-layer (EPPI) for an 8-bit interface only.

2399

**Table 64 Additional Signals for (Functional) PPI**

<b>Symbol</b>	<b>Dir</b>	<b>Categories</b>	<b>Description</b>
TxProMarkerEsc	I	MXAX (SXXX)	Functional handle to insert a Protocol-marker symbol in the serial stream for LPDT. Active HIGH signal
TxProMarkerHS	I	MXXX (SRXX)	Functional handle to insert a Protocol-marker symbol in the serial stream for HS transmission. Active HIGH signal
TxValidHS	I	MXXX (SRXX)	Functional handle for the protocol to hold on providing data to the PHY without ending the HS transmission. In the case of a continued transmission request without Valid data, the PHY coding layer inserts Idle symbols. Active HIGH signal
RxAlignErrorEsc	O	SXAX (MXXA)	Flag to indicate that a Comma code has been observed in the LPDT stream that was not aligned with the assumed word boundary. Active HIGH signal (optional)
RxAlignErrorHS	O	SXXX (MRXX)	Flag to indicate that a Comma code has been observed during HS reception that was not aligned with the assumed word boundary. Active HIGH signal (optional)
RxBadSymbolEsc	O	SXAX (MXXA)	Flag to indicate that a non-existing symbol was received using LPDT. Active HIGH signal (optional)
RxBadSymbolHS	O	SXXX (MRXX)	Flag to indicate that a non-existing symbol was received in HS mode. Active HIGH signal (optional)
RxEoTErrorEsc	O	SXAX (MXXA)	Flag to indicate that at EoT, after LP transmission, a transition to LP-11 has been detected without being preceded by an EoT-marker symbol. Active HIGH signal (optional)
RxEoTErrorHS	O	SXXX (MRXX)	Flag to indicate that at EoT, after HS transmission, a transition to LP-11 has been detected without being preceded by an EoT-marker symbol. Active HIGH signal (optional)
RxIdleEsc	O	SXAX (MXXA)	Indication flag that Idle patterns are observed at the Lines during LPDT. Active HIGH signal (optional)
RxIdleHS	O	SXXX (MRXX)	Indication flag that Idle patterns are observed at the Lines in HS mode. Active HIGH signal (optional)
RxProMarkerEsc	O	SXAX (MXXA)	Functional flag to know that a Protocol-marker symbol occurred in the serial stream using LPDT. This is communicated to the protocol synchronous with the data, exactly at the position where it occurred. Therefore, the interface either shows a flag plus non-valid data or no-flag with valid data. Active HIGH signal
RxProMarkerHS	O	SXXX (MRXX)	Functional flag to know that a Protocol-marker symbol occurred in the serial stream for HS mode. This is communicated to the protocol synchronous with the ByteClk, exactly at the position where it occurred. Therefore, the interface either shows a flag plus non-valid data or no-flag with valid data. Active HIGH signal

## C.6 Complete Code Set

2400

*Table 65* contains the complete code set.

2401

**Table 65 Code Set (8b9b Line Coding)**

<b>Name</b>	<b>Type</b>	<b>8-bit Data Byte</b>							<b>9-bit Symbol</b>									
		<b>B<sub>1</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>X<sub>1</sub></b>	<b>X<sub>2</sub></b>	<b>Q<sub>1</sub></b>	<b>Q<sub>2</sub></b>	<b>Q<sub>3</sub></b>	<b>B<sub>1</sub></b>	<b>X<sub>1</sub></b>	<b>Y<sub>1</sub></b>	<b>Y<sub>2</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>Y<sub>3</sub></b>	<b>Y<sub>4</sub></b>	<b>X<sub>2</sub></b>
D000	Data	0	0	0	0	0	0	0	0	0	0	1	1	0	0	0	1	0
D001	Data	0	0	0	0	0	0	0	1	0	0	1	1	0	0	1	0	0
D002	Data	0	0	0	0	0	0	1	0	0	0	0	1	0	0	0	1	0
D003	Data	0	0	0	0	0	0	1	1	0	0	1	0	0	0	0	1	0
D004	Data	0	0	0	0	0	1	0	0	0	0	0	1	0	0	1	0	0
D005	Data	0	0	0	0	0	1	0	1	0	0	1	0	0	0	1	0	0
D006	Data	0	0	0	0	0	1	1	0	0	0	0	1	0	0	1	1	0
D007	Data	0	0	0	0	0	1	1	1	0	0	1	0	0	0	1	1	0
D008	Data	0	0	0	0	1	0	0	0	0	0	1	1	0	0	0	1	1
D009	Data	0	0	0	0	1	0	0	1	0	0	1	1	0	0	1	0	1
D010	Data	0	0	0	0	1	0	1	0	0	0	0	1	0	0	0	1	1
D011	Data	0	0	0	0	1	0	1	1	0	0	1	0	0	0	0	1	1
D012	Data	0	0	0	0	1	1	0	0	0	0	0	1	0	0	1	0	1
D013	Data	0	0	0	0	1	1	0	1	0	0	1	0	0	0	1	0	1
D014	Data	0	0	0	0	1	1	1	0	0	0	0	1	0	0	0	0	1
D015	Data	0	0	0	0	1	1	1	1	0	0	1	0	0	0	0	0	1
D016	Data	0	0	0	1	0	0	0	0	0	0	1	0	0	0	0	0	1
D017	Data	0	0	0	1	0	0	0	1	0	1	0	0	0	0	1	0	0
D018	Data	0	0	0	1	0	0	1	0	0	1	0	1	0	0	0	1	0
D019	Data	0	0	0	1	0	0	1	1	0	1	1	0	0	0	0	1	0
D020	Data	0	0	0	1	0	1	0	0	0	1	0	1	0	0	1	0	0
D021	Data	0	0	0	1	0	1	0	1	0	1	1	0	0	0	1	0	0
D022	Data	0	0	0	1	0	1	1	0	0	1	0	1	0	0	1	1	0
D023	Data	0	0	0	1	0	1	1	1	0	1	1	0	0	0	1	1	0
D024	Data	0	0	0	1	1	0	0	0	0	1	0	0	0	0	0	1	1
D025	Data	0	0	0	1	1	0	0	1	0	1	0	0	0	0	1	0	1
D026	Data	0	0	0	1	1	0	1	0	0	1	0	1	0	0	0	1	1
D027	Data	0	0	0	1	1	1	0	1	1	0	1	1	0	0	0	0	1
D028	Data	0	0	0	1	1	1	0	0	0	1	0	1	0	0	1	0	1
D029	Data	0	0	0	1	1	1	0	1	0	1	1	0	0	0	1	0	1

<b>Name</b>	<b>Type</b>	<b>8-bit Data Byte</b>							<b>9-bit Symbol</b>									
		<b>B<sub>1</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>X<sub>1</sub></b>	<b>X<sub>2</sub></b>	<b>Q<sub>1</sub></b>	<b>Q<sub>2</sub></b>	<b>Q<sub>3</sub></b>	<b>B<sub>1</sub></b>	<b>X<sub>1</sub></b>	<b>Y<sub>1</sub></b>	<b>Y<sub>2</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>Y<sub>3</sub></b>	<b>Y<sub>4</sub></b>	<b>X<sub>2</sub></b>
D030	Data	0	0	0	1	1	1	1	0	0	1	0	1	0	0	0	0	1
D031	Data	0	0	0	1	1	1	1	1	0	1	1	0	0	0	0	0	1
D032	Data	0	0	1	0	0	0	0	0	0	0	0	1	1	0	1	0	1
D033	Data	0	0	1	0	0	0	0	1	0	0	1	1	0	1	1	0	0
D034	Data	0	0	1	0	0	0	1	0	0	0	0	1	0	1	0	1	0
D035	Data	0	0	1	0	0	0	1	1	0	0	1	0	0	1	0	1	0
D036	Data	0	0	1	0	0	1	0	0	0	0	0	0	1	0	1	1	0
D037	Data	0	0	1	0	0	1	0	1	0	0	1	0	0	1	1	0	0
D038	Data	0	0	1	0	0	1	1	0	0	0	0	1	0	1	1	1	0
D039	Data	0	0	1	0	0	1	1	1	0	0	1	0	0	1	1	1	0
D040	Data	0	0	1	0	1	0	0	0	0	0	0	1	1	0	1	0	1
D041	Data	0	0	1	0	1	0	0	1	0	0	1	1	0	1	1	0	1
D042	Data	0	0	1	0	1	0	1	0	0	0	0	1	0	1	0	1	1
D043	Data	0	0	1	0	1	0	1	1	0	0	1	0	0	1	0	1	1
D044	Data	0	0	1	0	1	1	0	0	0	0	0	1	0	1	1	0	1
D045	Data	0	0	1	0	1	1	0	1	0	0	1	0	0	1	1	0	1
D046	Data	0	0	1	0	1	1	1	0	0	0	0	1	0	1	0	0	1
D047	Data	0	0	1	0	1	1	1	1	0	0	1	0	0	1	0	0	1
D048	Data	0	0	1	1	0	0	0	0	0	0	1	0	0	0	1	0	1
D049	Data	0	0	1	1	0	0	0	1	0	1	0	0	0	1	1	0	0
D050	Data	0	0	1	1	0	0	1	0	0	1	0	1	0	1	0	1	0
D051	Data	0	0	1	1	0	0	1	1	0	1	1	0	0	1	0	1	0
D052	Data	0	0	1	1	0	1	0	0	0	1	0	1	0	1	1	0	0
D053	Data	0	0	1	1	0	1	0	1	0	1	1	0	0	1	1	0	0
D054	Data	0	0	1	1	0	1	1	0	0	1	0	1	0	1	1	1	0
D055	Data	0	0	1	1	0	1	1	1	0	1	1	0	0	1	1	1	0
D056	Data	0	0	1	1	1	0	0	0	0	1	0	0	0	1	0	1	1
D057	Data	0	0	1	1	1	0	0	1	0	1	0	0	0	1	1	0	1
D058	Data	0	0	1	1	1	0	1	0	0	1	0	1	0	1	0	1	1
D059	Data	0	0	1	1	1	0	1	1	0	1	1	0	0	1	0	1	1
D060	Data	0	0	1	1	1	1	0	0	0	1	0	1	0	1	1	0	1
D061	Data	0	0	1	1	1	1	0	1	0	1	1	0	0	1	1	0	1
D062	Data	0	0	1	1	1	1	1	0	0	1	0	1	0	1	0	0	1
D063	Data	0	0	1	1	1	1	1	1	0	1	1	0	0	1	0	0	1

Name	Type	8-bit Data Byte							9-bit Symbol								
		B <sub>1</sub>	B <sub>2</sub>	B <sub>3</sub>	X <sub>1</sub>	X <sub>2</sub>	Q <sub>1</sub>	Q <sub>2</sub>	B <sub>1</sub>	X <sub>1</sub>	Y <sub>1</sub>	Y <sub>2</sub>	B <sub>2</sub>	B <sub>3</sub>	Y <sub>3</sub>	Y <sub>4</sub>	X <sub>2</sub>
D064	Data	0	1	0	0	0	0	0	0	0	1	1	1	0	0	1	0
D065	Data	0	1	0	0	0	0	0	1	0	0	1	1	1	0	1	0
D066	Data	0	1	0	0	0	0	1	0	0	0	0	1	1	0	0	1
D067	Data	0	1	0	0	0	0	1	1	0	0	1	0	1	0	0	1
D068	Data	0	1	0	0	0	1	0	0	0	0	0	1	1	0	1	0
D069	Data	0	1	0	0	0	1	0	1	0	0	1	0	1	0	1	0
D070	Data	0	1	0	0	0	1	1	0	0	0	0	1	1	0	1	1
D071	Data	0	1	0	0	0	1	1	1	0	0	1	0	1	0	1	1
D072	Data	0	1	0	0	1	0	0	0	0	0	1	1	1	0	0	1
D073	Data	0	1	0	0	1	0	0	1	0	0	1	1	1	0	1	0
D074	Data	0	1	0	0	1	0	1	0	0	0	0	1	1	0	0	1
D075	Data	0	1	0	0	1	0	1	1	0	0	1	0	1	0	0	1
D076	Data	0	1	0	0	1	1	0	0	0	0	0	1	1	0	1	0
D077	Data	0	1	0	0	1	1	0	1	0	0	1	0	1	0	1	0
D078	Data	0	1	0	0	1	1	1	0	0	0	0	1	1	0	0	1
D079	Data	0	1	0	0	1	1	1	1	0	0	1	0	1	0	0	1
D080	Data	0	1	0	1	0	0	0	0	0	1	0	0	1	0	0	1
D081	Data	0	1	0	1	0	0	0	1	0	1	0	0	1	0	1	0
D082	Data	0	1	0	1	0	0	1	0	0	1	0	1	1	0	0	1
D083	Data	0	1	0	1	0	0	1	1	0	1	1	0	1	0	0	1
D084	Data	0	1	0	1	0	1	0	0	0	1	0	1	1	0	1	0
D085	Data	0	1	0	1	0	1	0	1	0	1	1	0	1	0	1	0
D086	Data	0	1	0	1	0	1	1	0	0	1	0	1	1	0	1	0
D087	Data	0	1	0	1	0	1	1	1	0	1	1	0	1	0	1	0
D088	Data	0	1	0	1	1	0	0	0	0	1	0	0	1	0	0	1
D089	Data	0	1	0	1	1	0	0	1	0	1	0	0	1	0	1	0
D090	Data	0	1	0	1	1	0	1	0	0	1	0	1	1	0	0	1
D091	Data	0	1	0	1	1	0	1	1	0	1	1	0	1	0	0	1
D092	Data	0	1	0	1	1	1	0	0	0	1	0	1	1	0	1	0
D093	Data	0	1	0	1	1	1	0	1	0	1	1	0	1	0	1	0
D094	Data	0	1	0	1	1	1	1	0	0	1	0	1	1	0	0	1
D095	Data	0	1	0	1	1	1	1	1	0	1	1	0	1	0	0	1
D096	Data	0	1	1	0	0	0	0	0	0	0	1	1	1	1	0	1
D097	Data	0	1	1	0	0	0	0	1	0	0	1	1	1	1	1	0

<b>Name</b>	<b>Type</b>	<b>8-bit Data Byte</b>							<b>9-bit Symbol</b>									
		<b>B<sub>1</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>X<sub>1</sub></b>	<b>X<sub>2</sub></b>	<b>Q<sub>1</sub></b>	<b>Q<sub>2</sub></b>	<b>Q<sub>3</sub></b>	<b>B<sub>1</sub></b>	<b>X<sub>1</sub></b>	<b>Y<sub>1</sub></b>	<b>Y<sub>2</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>Y<sub>3</sub></b>	<b>Y<sub>4</sub></b>	<b>X<sub>2</sub></b>
D098	Data	0	1	1	0	0	0	1	0	0	0	0	1	1	1	0	1	0
D099	Data	0	1	1	0	0	0	1	1	0	0	1	0	1	1	0	1	0
D100	Data	0	1	1	0	0	1	0	0	0	0	0	1	1	1	1	0	0
D101	Data	0	1	1	0	0	1	0	1	0	0	0	1	0	1	1	1	0
D102	Data	0	1	1	0	0	1	1	0	0	0	0	1	1	1	1	1	0
D103	Data	0	1	1	0	0	1	1	1	0	0	1	0	1	1	1	1	0
D104	Data	0	1	1	0	1	0	0	0	0	0	0	1	1	1	1	0	1
D105	Data	0	1	1	0	1	0	0	1	0	0	1	1	1	1	1	0	1
D106	Data	0	1	1	0	1	0	1	0	0	0	0	1	1	1	1	0	1
D107	Data	0	1	1	0	1	0	1	1	0	0	0	1	0	1	1	0	1
D108	Data	0	1	1	0	1	1	0	0	0	0	0	0	1	1	1	1	0
D109	Data	0	1	1	0	1	1	0	1	0	0	1	0	1	1	1	0	1
D110	Data	0	1	1	0	1	1	1	0	0	0	0	1	1	1	0	0	1
D111	Data	0	1	1	0	1	1	1	1	0	0	1	0	1	1	0	0	1
D112	Data	0	1	1	1	0	0	0	0	0	0	1	0	0	1	1	0	1
D113	Data	0	1	1	1	0	0	0	1	0	1	0	0	1	1	1	0	0
D114	Data	0	1	1	1	0	0	1	0	0	1	0	1	1	1	0	1	0
D115	Data	0	1	1	1	0	0	1	1	0	1	1	0	1	1	0	1	0
D116	Data	0	1	1	1	0	1	0	0	0	1	0	1	1	1	1	0	0
D117	Data	0	1	1	1	0	1	0	1	0	1	1	0	1	1	1	0	0
D118	Data	0	1	1	1	0	1	1	0	0	1	0	1	1	1	1	1	0
D119	Data	0	1	1	1	0	1	1	1	0	1	1	0	1	1	1	1	0
D120	Data	0	1	1	1	1	0	0	0	0	1	0	0	1	1	0	1	1
D121	Data	0	1	1	1	1	0	0	1	0	1	0	0	1	1	1	0	1
D122	Data	0	1	1	1	1	0	1	0	0	1	0	1	1	1	0	1	1
D123	Data	0	1	1	1	1	0	1	1	0	1	1	0	1	1	0	1	1
D124	Data	0	1	1	1	1	1	0	0	0	1	0	1	1	1	1	0	1
D125	Data	0	1	1	1	1	1	0	1	0	1	1	0	1	1	1	0	1
D126	Data	0	1	1	1	1	1	1	0	0	1	0	1	1	1	0	0	1
D127	Data	0	1	1	1	1	1	1	1	0	1	1	0	1	1	0	0	1
D128	Data	1	0	0	0	0	0	0	0	1	0	1	1	0	0	0	1	0
D129	Data	1	0	0	0	0	0	0	1	1	0	1	1	0	0	1	0	0
D130	Data	1	0	0	0	0	0	1	0	1	0	0	1	0	0	0	1	0
D131	Data	1	0	0	0	0	0	1	1	1	0	1	0	0	0	0	1	0

Name	Type	8-bit Data Byte							9-bit Symbol									
		B <sub>1</sub>	B <sub>2</sub>	B <sub>3</sub>	X <sub>1</sub>	X <sub>2</sub>	Q <sub>1</sub>	Q <sub>2</sub>	Q <sub>3</sub>	B <sub>1</sub>	X <sub>1</sub>	Y <sub>1</sub>	Y <sub>2</sub>	B <sub>2</sub>	B <sub>3</sub>	Y <sub>3</sub>	Y <sub>4</sub>	X <sub>2</sub>
D132	Data	1	0	0	0	0	1	0	0	1	0	0	1	0	0	1	0	0
D133	Data	1	0	0	0	0	1	0	1	1	0	1	0	0	0	1	0	0
D134	Data	1	0	0	0	0	1	1	0	1	0	0	1	0	0	1	1	0
D135	Data	1	0	0	0	0	1	1	1	1	0	1	0	0	0	1	1	0
D136	Data	1	0	0	0	1	0	0	0	1	0	1	1	0	0	0	1	1
D137	Data	1	0	0	0	1	0	0	1	1	0	1	1	0	0	1	0	1
D138	Data	1	0	0	0	1	0	1	0	1	0	0	1	0	0	0	1	1
D139	Data	1	0	0	0	1	0	1	1	1	0	1	0	0	0	0	1	1
D140	Data	1	0	0	0	1	1	0	0	1	0	0	1	0	0	1	0	1
D141	Data	1	0	0	0	1	1	0	1	1	0	1	0	0	0	1	0	1
D142	Data	1	0	0	0	1	1	1	0	1	0	0	1	0	0	0	0	1
D143	Data	1	0	0	0	1	1	1	1	1	0	1	0	0	0	0	0	1
D144	Data	1	0	0	1	0	0	0	0	1	1	0	0	0	0	0	0	1
D145	Data	1	0	0	1	0	0	0	1	1	1	0	0	0	0	1	0	0
D146	Data	1	0	0	1	0	0	1	0	1	1	0	1	0	0	0	1	0
D147	Data	1	0	0	1	0	0	1	1	1	1	1	0	0	0	0	1	0
D148	Data	1	0	0	1	0	1	0	0	1	1	0	1	0	0	1	0	0
D149	Data	1	0	0	1	0	1	0	1	1	1	1	0	0	0	1	0	0
D150	Data	1	0	0	1	0	1	1	0	1	1	0	1	0	0	1	1	0
D151	Data	1	0	0	1	0	1	1	1	1	1	1	0	0	0	1	1	0
D152	Data	1	0	0	1	1	0	0	0	1	1	0	0	0	0	0	1	1
D153	Data	1	0	0	1	1	0	0	1	1	1	0	0	0	0	1	0	1
D154	Data	1	0	0	1	1	0	1	0	1	1	0	1	0	0	0	1	1
D155	Data	1	0	0	1	1	0	1	1	1	1	1	0	0	0	0	1	1
D156	Data	1	0	0	1	1	1	0	0	1	1	0	1	0	0	1	0	1
D157	Data	1	0	0	1	1	1	0	1	1	1	1	0	0	0	1	0	1
D158	Data	1	0	0	1	1	1	1	0	1	1	0	1	0	0	0	0	1
D159	Data	1	0	0	1	1	1	1	1	1	1	1	1	0	0	0	0	1
D160	Data	1	0	1	0	0	0	0	0	1	0	1	1	0	1	0	1	0
D161	Data	1	0	1	0	0	0	0	1	1	0	1	1	0	1	1	0	0
D162	Data	1	0	1	0	0	0	1	0	1	0	0	1	0	1	0	1	0
D163	Data	1	0	1	0	0	0	1	1	1	0	1	0	0	1	0	1	0
D164	Data	1	0	1	0	0	1	0	0	1	0	0	1	0	1	1	0	0
D165	Data	1	0	1	0	0	1	0	1	1	0	1	0	0	1	1	0	0

<b>Name</b>	<b>Type</b>	<b>8-bit Data Byte</b>							<b>9-bit Symbol</b>									
		<b>B<sub>1</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>X<sub>1</sub></b>	<b>X<sub>2</sub></b>	<b>Q<sub>1</sub></b>	<b>Q<sub>2</sub></b>	<b>Q<sub>3</sub></b>	<b>B<sub>1</sub></b>	<b>X<sub>1</sub></b>	<b>Y<sub>1</sub></b>	<b>Y<sub>2</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>Y<sub>3</sub></b>	<b>Y<sub>4</sub></b>	<b>X<sub>2</sub></b>
D166	Data	1	0	1	0	0	1	1	0	1	0	0	1	0	1	1	1	0
D167	Data	1	0	1	0	0	1	1	1	1	0	1	0	0	1	1	1	0
D168	Data	1	0	1	0	1	0	0	0	1	0	1	1	0	1	0	1	1
D169	Data	1	0	1	0	1	0	0	1	1	0	1	1	0	1	1	0	1
D170	Data	1	0	1	0	1	0	1	0	1	0	0	1	0	1	0	1	1
D171	Data	1	0	1	0	1	0	1	1	1	0	1	0	0	1	0	1	1
D172	Data	1	0	1	0	1	1	0	0	1	0	0	1	0	1	1	0	1
D173	Data	1	0	1	0	1	1	0	1	1	0	1	0	0	1	1	0	1
D174	Data	1	0	1	0	1	1	1	0	1	0	0	1	0	1	0	0	1
D175	Data	1	0	1	0	1	1	1	1	1	0	1	0	0	1	0	0	1
D176	Data	1	0	1	1	0	0	0	0	1	1	0	0	0	0	1	0	1
D177	Data	1	0	1	1	0	0	0	1	1	1	0	0	0	1	1	0	0
D178	Data	1	0	1	1	0	0	1	0	1	1	0	1	0	1	0	1	0
D179	Data	1	0	1	1	0	0	1	1	1	1	1	0	0	1	0	1	0
D180	Data	1	0	1	1	0	1	0	0	1	1	0	1	0	1	1	0	0
D181	Data	1	0	1	1	0	1	0	1	1	1	1	0	0	1	1	0	0
D182	Data	1	0	1	1	0	1	1	0	1	1	0	1	0	1	1	1	0
D183	Data	1	0	1	1	0	1	1	1	1	1	1	0	0	1	1	1	0
D184	Data	1	0	1	1	1	0	0	0	1	1	0	0	0	1	0	1	1
D185	Data	1	0	1	1	1	0	0	1	1	1	0	0	0	1	1	0	1
D186	Data	1	0	1	1	1	0	1	0	1	1	0	1	0	1	0	1	1
D187	Data	1	0	1	1	1	0	1	1	1	1	1	0	0	1	0	1	1
D188	Data	1	0	1	1	1	1	0	0	1	1	0	1	0	1	1	0	1
D189	Data	1	0	1	1	1	1	0	1	1	1	1	0	0	1	1	0	1
D190	Data	1	0	1	1	1	1	1	0	1	1	0	1	0	1	0	0	1
D191	Data	1	0	1	1	1	1	1	1	1	1	1	1	0	0	1	0	0
D192	Data	1	1	0	0	0	0	0	0	1	0	1	1	1	0	0	1	0
D193	Data	1	1	0	0	0	0	0	1	1	0	1	1	1	0	1	0	0
D194	Data	1	1	0	0	0	0	1	0	1	0	0	1	1	0	0	1	0
D195	Data	1	1	0	0	0	0	1	1	1	0	1	0	1	0	0	1	0
D196	Data	1	1	0	0	0	1	0	0	1	0	0	1	1	0	1	0	0
D197	Data	1	1	0	0	0	1	0	1	1	0	1	0	1	0	1	0	0
D198	Data	1	1	0	0	0	1	1	0	1	0	0	1	1	0	1	1	0
D199	Data	1	1	0	0	0	1	1	1	1	0	1	0	1	0	1	1	0

Name	Type	8-bit Data Byte							9-bit Symbol								
		B <sub>1</sub>	B <sub>2</sub>	B <sub>3</sub>	X <sub>1</sub>	X <sub>2</sub>	Q <sub>1</sub>	Q <sub>2</sub>	B <sub>1</sub>	X <sub>1</sub>	Y <sub>1</sub>	Y <sub>2</sub>	B <sub>2</sub>	B <sub>3</sub>	Y <sub>3</sub>	Y <sub>4</sub>	X <sub>2</sub>
D200	Data	1	1	0	0	1	0	0	1	0	1	1	1	0	0	1	1
D201	Data	1	1	0	0	1	0	0	1	1	0	1	1	1	0	1	0
D202	Data	1	1	0	0	1	0	1	0	1	0	0	1	1	0	0	1
D203	Data	1	1	0	0	1	0	1	1	1	0	1	0	1	0	0	1
D204	Data	1	1	0	0	1	1	0	0	1	0	0	1	1	0	1	0
D205	Data	1	1	0	0	1	1	0	1	1	0	1	0	1	0	1	0
D206	Data	1	1	0	0	1	1	1	0	1	0	0	1	1	0	0	1
D207	Data	1	1	0	0	1	1	1	1	1	0	1	0	1	0	0	1
D208	Data	1	1	0	1	0	0	0	0	1	1	0	0	1	0	0	1
D209	Data	1	1	0	1	0	0	0	1	1	1	0	0	1	0	1	0
D210	Data	1	1	0	1	0	0	1	0	1	1	0	1	1	0	0	1
D211	Data	1	1	0	1	0	0	1	1	1	1	1	0	1	0	0	1
D212	Data	1	1	0	1	0	1	0	0	1	1	0	1	1	0	1	0
D213	Data	1	1	0	1	0	1	0	1	1	1	1	0	1	0	1	0
D214	Data	1	1	0	1	0	1	1	0	1	1	0	1	1	0	1	0
D215	Data	1	1	0	1	0	1	1	1	1	1	1	0	1	0	1	1
D216	Data	1	1	0	1	1	0	0	0	1	1	0	0	1	0	0	1
D217	Data	1	1	0	1	1	0	0	1	1	1	0	0	1	0	1	0
D218	Data	1	1	0	1	1	0	1	0	1	1	0	1	1	0	0	1
D219	Data	1	1	0	1	1	0	1	1	1	1	1	0	1	0	0	1
D220	Data	1	1	0	1	1	1	0	0	1	1	0	1	1	0	1	0
D221	Data	1	1	0	1	1	1	0	1	1	1	1	0	1	0	1	0
D222	Data	1	1	0	1	1	1	1	0	1	1	0	1	1	0	0	1
D223	Data	1	1	0	1	1	1	1	1	1	1	1	0	1	0	0	1
D224	Data	1	1	1	0	0	0	0	0	1	0	1	1	1	1	0	1
D225	Data	1	1	1	0	0	0	0	1	1	0	1	1	1	1	0	0
D226	Data	1	1	1	0	0	0	0	1	0	0	0	1	1	1	0	1
D227	Data	1	1	1	0	0	0	1	1	1	0	1	0	1	1	0	1
D228	Data	1	1	1	0	0	1	0	0	1	0	0	1	1	1	1	0
D229	Data	1	1	1	0	0	1	0	1	1	0	1	0	1	1	1	0
D230	Data	1	1	1	0	0	1	1	0	1	0	0	1	1	1	1	0
D231	Data	1	1	1	0	0	1	1	1	1	0	1	0	1	1	1	0
D232	Data	1	1	1	0	1	0	0	0	1	0	1	1	1	1	0	1
D233	Data	1	1	1	0	1	0	0	1	1	0	1	1	1	1	1	0

<b>Name</b>	<b>Type</b>	<b>8-bit Data Byte</b>							<b>9-bit Symbol</b>									
		<b>B<sub>1</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>X<sub>1</sub></b>	<b>X<sub>2</sub></b>	<b>Q<sub>1</sub></b>	<b>Q<sub>2</sub></b>	<b>Q<sub>3</sub></b>	<b>B<sub>1</sub></b>	<b>X<sub>1</sub></b>	<b>Y<sub>1</sub></b>	<b>Y<sub>2</sub></b>	<b>B<sub>2</sub></b>	<b>B<sub>3</sub></b>	<b>Y<sub>3</sub></b>	<b>Y<sub>4</sub></b>	<b>X<sub>2</sub></b>
D234	Data	1	1	1	0	1	0	1	0	1	0	0	1	1	1	0	1	1
D235	Data	1	1	1	0	1	0	1	1	1	0	1	0	1	1	0	1	1
D236	Data	1	1	1	0	1	1	0	0	1	0	0	1	1	1	1	0	1
D237	Data	1	1	1	0	1	1	0	1	1	0	1	0	1	1	1	0	1
D238	Data	1	1	1	0	1	1	1	0	1	0	0	1	1	1	0	0	1
D239	Data	1	1	1	0	1	1	1	1	1	0	1	0	1	1	0	0	1
D240	Data	1	1	1	1	0	0	0	0	1	1	0	0	0	1	1	0	1
D241	Data	1	1	1	1	0	0	0	1	1	1	0	0	1	1	1	0	0
D242	Data	1	1	1	1	0	0	1	0	1	1	0	1	1	1	0	1	0
D243	Data	1	1	1	1	0	0	1	1	1	1	1	0	1	1	0	1	0
D244	Data	1	1	1	1	0	1	0	0	1	1	0	1	1	1	1	0	0
D245	Data	1	1	1	1	0	1	0	1	1	1	1	0	1	1	1	0	0
D246	Data	1	1	1	1	0	1	1	0	1	1	0	1	1	1	1	1	0
D247	Data	1	1	1	1	0	1	1	1	1	1	1	0	1	1	1	1	0
D248	Data	1	1	1	1	1	0	0	0	1	1	0	0	1	1	0	1	1
D249	Data	1	1	1	1	1	0	0	1	1	1	0	0	1	1	1	0	1
D250	Data	1	1	1	1	1	0	1	0	1	1	0	1	1	1	0	1	1
D251	Data	1	1	1	1	1	0	1	1	1	1	1	0	1	1	0	1	1
D252	Data	1	1	1	1	1	1	0	0	1	1	0	1	1	1	1	0	1
D253	Data	1	1	1	1	1	1	0	1	1	1	1	0	1	1	1	0	1
D254	Data	1	1	1	1	1	1	1	0	1	1	0	1	1	1	0	0	1
D255	Data	1	1	1	1	1	1	1	1	1	1	1	0	1	1	0	0	1
C400	Rsvd	Does not represent data							0	1	0	0	0	0	0	1	1	0
C401	Rsvd	Does not represent data							0	1	0	0	0	0	1	1	1	0
C402	Rsvd	Does not represent data							0	1	0	0	1	0	1	1	0	
C403	Rsvd	Does not represent data							0	1	0	0	1	1	1	1	0	
C404	Rsvd	Does not represent data							1	1	0	0	0	0	0	1	1	0
C405	Rsvd	Does not represent data							1	1	0	0	0	0	1	1	1	0
C406	Rsvd	Does not represent data							1	1	0	0	1	0	1	1	0	
C407	Rsvd	Does not represent data							1	1	0	0	1	1	1	1	0	
C410	Rsvd	Does not represent data							0	0	1	1	0	0	0	0	1	
C411	Rsvd	Does not represent data							0	0	1	1	0	1	0	0	1	
C412	Rsvd	Does not represent data							0	0	1	1	1	0	0	0	1	
C413	Rsvd	Does not represent data							0	0	1	1	1	1	0	0	1	

Name	Type	8-bit Data Byte							9-bit Symbol								
		B <sub>1</sub>	B <sub>2</sub>	B <sub>3</sub>	X <sub>1</sub>	X <sub>2</sub>	Q <sub>1</sub>	Q <sub>2</sub>	Q <sub>3</sub>	B <sub>1</sub>	X <sub>1</sub>	Y <sub>1</sub>	Y <sub>2</sub>	B <sub>2</sub>	B <sub>3</sub>	Y <sub>3</sub>	Y <sub>4</sub>
C414	Rsvd	Does not represent data							1	0	1	1	0	0	0	0	1
C415	Rsvd	Does not represent data							1	0	1	1	0	1	0	0	1
C416	Rsvd	Does not represent data							1	0	1	1	1	0	0	0	1
C417	Rsvd	Does not represent data							1	0	1	1	1	1	0	0	1
C600	Protocol	Does not represent data							0	1	1	1	1	1	1	1	0
C611	EoT	Does not represent data							1	0	0	0	0	0	0	1	1
C601	Idle/Sync1	Does not represent data							0	1	1	1	1	1	1	0	1
C610	Idle/Sync2	Does not represent data							1	0	0	0	0	0	0	1	0
C701	Reserved	Does not represent data							1	0	0	0	0	0	0	0	1
C710	Rsvd	Does not represent data							0	1	1	1	1	1	1	1	0

**Note:**

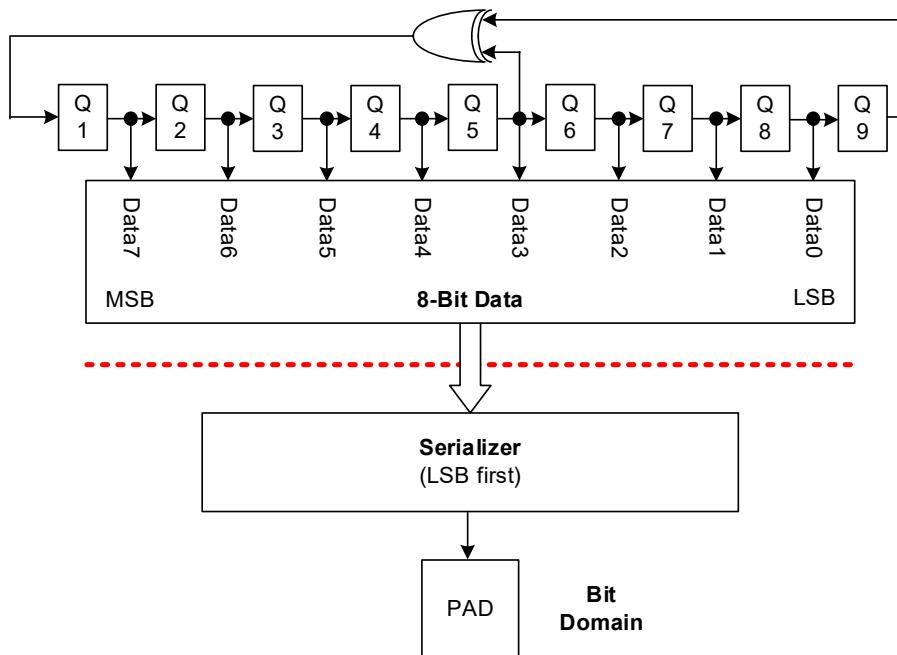
*Rsvd* = Reserved

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## Annex D Description of the PRBS9 Generator

The PRBS9 generator is used for calibration (*Section 6.13*) and for the HS Test mode (*Section 12.3*). Per ITU-150 [ITUT01], the data stream is generated by a shift register set with the following feedback:  $x^0 + x^5 + x^9$ .

The generator is connected to the serializer as shown in *Figure 131*.



2402

**Figure 131 PRBS Generator and Connection to the Serializer**

With the seed of 011111111 [Q9:Q1], the following data stream is produced (repetition length 511 bits):

```

2404 11111111_10000011_11011111_00010111_00110010_00001001_01001110_11010001_
2405 11100111_11001101_10001010_10010001_11000110_11010101_11000100_11000100_
2406 01000000_00100001_00011000_01001110_01010101_10000110_11110100_11011100_
2407 10001010_00010101_10100111_11101100_10010010_11011111_10010011_01010011_
2408 00110000_00011000_11001010_00110100_10111111_10100010_11000111_01011001_
2409 01100111_10001111_10111010_00001101_01101101_11011000_00101101_01111101_
2410 01010100_00001010_01010111_10010111_01110000_00111001_11010010_01111010_
2411 11101010_00100100_00110011_10000101_11101101_10011010_00011101_1110000/_1_
2412 11111111_00000111_10111110_00101110_01100100_00010010_10011101_10100011_
2413 11001111_10011011_00010101_00100011_10001101_10101011_10001001_10001000_
2414 10000000_01000010_00110000_10011100_10101011_00001101_11101001_10111001_
2415 00010100_00101011_01001111_11011001_00100101_10111111_00100110_10100110_
2416 01100000_00111001_10010100_01101001_01111111_01000101_10001110_10110010_
2417 11001111_00011111_01110100_00011010_11011011_10110000_01011010_11111010_
2418 10101000_00010100_10101111_00101110_11100000_01110011_10100100_11110101_
2419 11010100_01001000_01100111_00001011_11011011_00110100_00111011_110000/_11_
2420 11111110

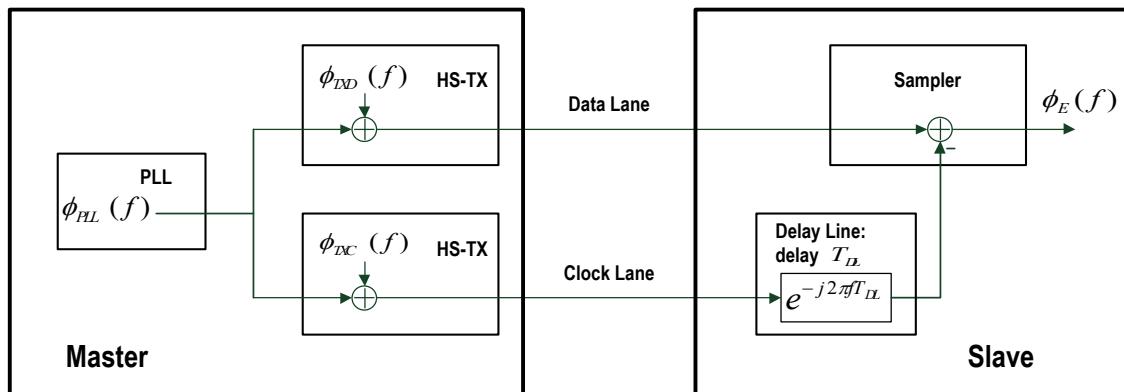
```

The repetition period is 511 bits, and it starts with eight ones of the PRBS9 sequence (based on seed of 011111111 [Q9:Q1]). In the PRBS9 sequence shown above, every repetition period is separated by a red slash ('/'), and every byte is separated by an underscore ('\_').

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## Annex E RX Data to Clock Random Jitter Tolerance Design Guideline (Informative)

This Annex shows the impact of a delay line in the Clock Lane receiver in the Slave on the RX Data to Clock Random Jitter Tolerance  $RJ_{RX}$  specified in [Section 10.2](#).  $T_{DL}$  is the delay of the delay line, and it impacts  $RJ_{RX}$ .  $T_{DL}$  should be minimized to limit its impact on  $RJ_{RX}$ .  $T_{DL}$  has a similar impact in the RX Data to Clock Deterministic Jitter Tolerance  $DJ_{RX}$ . Without showing the analysis, minimizing  $T_{DL}$  has a similar advantage for  $DJ_{RX}$ .



**Figure 132 Phase Noise Contributors in D-PHY Clock Topology**

[Figure 132](#) shows the main phase noise contributors in the D-PHY clock topology. The clock from the PLL is used in the HS-TX of the Data Lane and the Clock Lane in the Master. The spectral phase noise of the PLL output clock  $\phi_{PLL}(f)$  is added to the HS-TX intrinsic spectral phase noises  $\phi_{TXD}(f)$  and  $\phi_{TxC}(f)$  of the Data and Clock Lane, respectively. The clock signal passes through a delay line  $T_{DL}$ , ranging from 1 UI to 4 UI in this analysis, in the Clock Lane receiver of the Slave.  $T_{DL}$  is modeled by the delay function  $e^{-j2\pi f T_{DL}}$ . A sampler in the Data Lane receiver of the Slave samples the data signal using the output clock signal delayed by  $T_{DL}$ . The spectral phase noise error  $\phi_E(f)$  at the sampler results from the Clock Lane spectral phase noise subtracted from the Data Lane spectral phase noise, resulting in the equation:

$$\phi_E(f) = \phi_{PLL}(f) \cdot (1 - e^{-j2\pi f T_{DL}}) + \phi_{TXD}(f) - \phi_{TxC}(f) \cdot e^{-j2\pi f T_{DL}}$$

Since all phase noise contributions are assumed uncorrelated, the variance of the phase noise error at the sampler is the Root Sum Squared of the phase noises at the sampler, as expressed by the equation:

$$\phi_{E_{RMS}}^2 = \int (S_{\phi_{PLL}}(f) \cdot |(1 - e^{-j2\pi f T_{DL}})|^2) \cdot df + \int S_{\phi_{TXD}}(f) \cdot df + \int S_{\phi_{TxC}}(f) \cdot df$$

where  $S_{\phi_{PLL}}(f)$ ,  $S_{\phi_{TXD}}(f)$ , and  $S_{\phi_{TxC}}(f)$  represent the double-sideband power spectral density of  $\phi_{PLL}(f)$ ,  $\phi_{TXD}(f)$ , and  $\phi_{TxC}(f)$  respectively.

$RJ_{RX}$  at the sampler is expressed by the equation:

$$RJ_{RX,RMS} = \frac{\phi_{E_{RMS}}}{2\pi f_c}$$

where  $f_c$  is the center frequency for phase noise calculation.

2447     Figure 133 shows a phase jitter estimation example using simplified models of the PLL phase noise and  
 2448     the HS-TX intrinsic phase noise. Note that the center frequency, the PLL phase noise, and the HS-TX  
 2449     intrinsic phase noise are implementation specific.

```

fc      = 12e9;          % center frequency (Hz)
fres    = 1e4;           % frequency resolution (Hz)
fnum    = fc/2/fres;

UI      = 83.33e-12;     % unit interval (sec)

Sphpll_f1M_db = -75;   % double-sideband phase noise spectral density of PLL 3rd order term at 1MHz (dBrd^2/Hz)
Sphpll_t1M_db = -65;   % double-sideband phase noise spectral density of PLL 2nd order term at 1MHz (dBrd^2/Hz)

Sphtx_f1M_db  = -135;  % double-sideband phase noise spectral density of TX 1st order term at 1MHz (dBrd^2/Hz)
Sphtx_t1M_db  = -135;  % double-sideband phase noise spectral density of TX 0th order term at 1MHz (dBrd^2/Hz)

%%%%%%%%%%%%%
freq     = zeros(fnum,1);
Sphpll  = zeros(fnum,1);
Sphtx   = zeros(fnum,1);
Sphpll_1UI = zeros(fnum,1);
Sphpll_2UI = zeros(fnum,1);
Sphpll_3UI = zeros(fnum,1);
Sphpll_4UI = zeros(fnum,1);

freq = linspace(fres,fc,fnum);

for i=1:1:fnum,
    Sphpll(i) = 10^(Sphpll_f1M_db/10) *1e18 / freq(i)^3 + 10^(Sphpll_t1M_db/10) *1e12 / freq(i)^2 ;
    Sphtx(i)  = 10^(Sphtx_f1M_db /10) *1e6 / freq(i)  + 10^(Sphtx_t1M_db /10) ;
end;

Ncyc_1UI_abs = abs( 1 - exp(-j*2*pi*freq*UI*1) );
Ncyc_2UI_abs = abs( 1 - exp(-j*2*pi*freq*UI*2) );
Ncyc_3UI_abs = abs( 1 - exp(-j*2*pi*freq*UI*3) );
Ncyc_4UI_abs = abs( 1 - exp(-j*2*pi*freq*UI*4) );

for i=1:1:fnum,
    Sphpll_1UI(i) = Sphpll(i) * Ncyc_1UI_abs(i)^2 ;
    Sphpll_2UI(i) = Sphpll(i) * Ncyc_2UI_abs(i)^2 ;
    Sphpll_3UI(i) = Sphpll(i) * Ncyc_3UI_abs(i)^2 ;
    Sphpll_4UI(i) = Sphpll(i) * Ncyc_4UI_abs(i)^2 ;
end;

jpll_1UI = sqrt( sum(Sphpll_1UI)*fres ) / 2 / pi / fc;
jpll_2UI = sqrt( sum(Sphpll_2UI)*fres ) / 2 / pi / fc;
jpll_3UI = sqrt( sum(Sphpll_3UI)*fres ) / 2 / pi / fc;
jpll_4UI = sqrt( sum(Sphpll_4UI)*fres ) / 2 / pi / fc;
jtx     = sqrt( sum(Sphtx) )*fres ) / 2 / pi / fc;

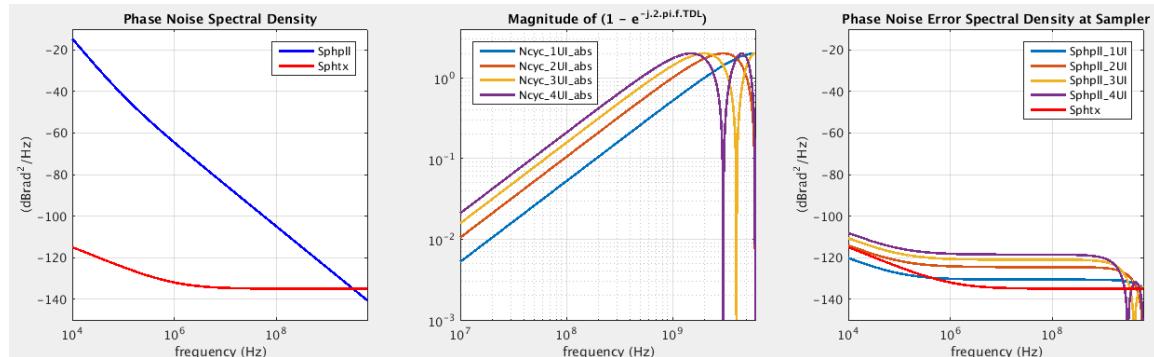
jerr_1UI = sqrt( jpll_1UI^2 + 2 * jtx^2 );
jerr_2UI = sqrt( jpll_2UI^2 + 2 * jtx^2 );
jerr_3UI = sqrt( jpll_3UI^2 + 2 * jtx^2 );
jerr_4UI = sqrt( jpll_4UI^2 + 2 * jtx^2 );

```

2450

**Figure 133 Phase Jitter Estimation Example**

2451 **Figure 134** shows the resulting phase noises and phase noise error spectral densities. The PLL phase noise  
 2452 spectral density and the HS-TX intrinsic phase noise spectral density are shown at the left. The magnitudes  
 2453 of the function  $(1 - e^{-j2\pi f T_{DL}})$ , with delays  $T_{DL}$  ranging from 1 UI to 4 UI, are shown in the center. The  
 2454 phase noise error spectral densities at the sampler are shown at the right. A larger  $T_{DL}$  results in a larger  
 2455 phase noise error.



**Figure 134 Phase Noise Contributions and Error at Sampler**

2456 By integrating the phase noise error spectral density and transforming it into phase jitter, the contribution to  
 2457 the RX Data to Clock Random Jitter Tolerance  $RJ_{RX}$  can be calculated as listed in **Table 66**.  $RJ_{RX}$  is  
 2458 increased with increasing  $T_{DL}$ .

**Table 66 Impact of Phase Noise on  $RJ_{RX}$**

RJ at Sampler	Delay of Slave Clock Delay Line			
	1 UI	2 UI	3 UI	4 UI
$RJ_{RMSS}$ due to HS-TX phase noise	0.183 ps			
$RJ_{RMSS}$ due to PLL phase noise	0.203 ps	0.295 ps	0.364 ps	0.423 ps
$RJ_{RX,RMSS}$ Root Sum Squared	0.329 ps	0.392 ps	0.447 ps	0.495 ps
$RJ_{RX}$ @ BER=10 <sup>-12</sup>	4.627 ps	5.518 ps	6.285 ps	6.970 ps

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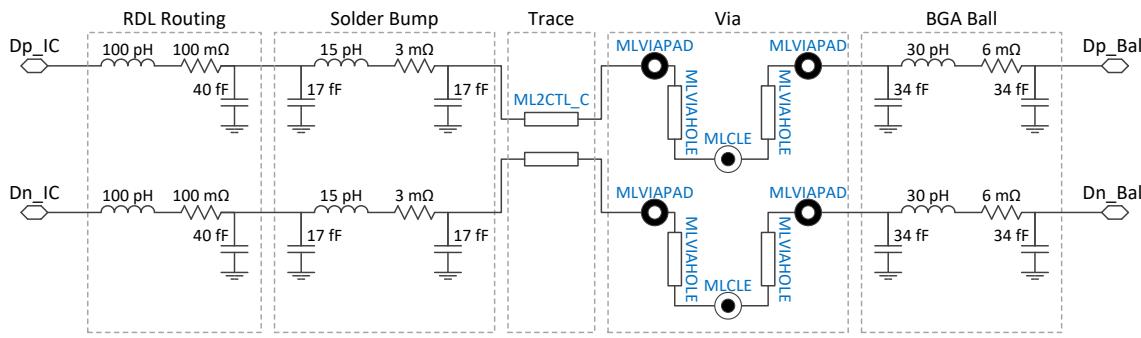
## Annex F Reference Package Model Description

### F.1 Introduction

The reference package models parasitic elements of an IC package that contains a transmitter or receiver IC. A description of the model is provided so design and test engineers can estimate the impact that the IC package has on signal quality.

### F.2 Low Level Description of the Reference Models

The reference package model is a simulation model representing the physical elements of an IC package that contains a PHY Lane Module. *Figure 135* is a circuit diagram that shows the components that model the example package. The example package was chosen as a suitable reference to include the physical effect of package parasitics. It is based on an example flip chip package described in the technical paper “Electrical Analysis of IC Packaging with Emphasis on Different Ball Grid Array Packages” [IEEE01].



**Figure 135 Reference Package Model Circuit Diagram**

In addition to inductors, capacitors, and resistors, some elements in the reference package model circuit diagram of *Figure 135* represent physical elements on the package substrate. These elements are: ML2CTL\_C transmission line, MLVIAPAD via pad, MLVIAHOLE via hole, and MLCLE via clearance that are multilayer library models used in ADS (Advanced Design System). *Table 67* defines the properties of the MLSUBSTRATE2 substrate model on which these elements are placed.

ADS was used for the generation of the reference package model S-parameter model, which is provided. Other tools providing comparable results can be used similarly. No guidance is provided on how to transfer the used ADS model parameters, listed in the tables below, for other tools.

**Table 67 MLSUBSTRATE2: Package Model Substrate Properties**

Parameter Name	Description	Value	Units
—	Name of substrate	Subst1	—
Er	Relative dielectric constant for the substrate	3.4	—
H	Height of substrate	1.29	mil
TanD	Dielectric loss tangent, tan δ	0.00531	—
T[1]	Metal thickness	0.59	mil
T[2]		0	
Cond[1]	Conductivity	5.8E+7	S/m
Cond[2]		1.0E+50	
LayerType[1]	Type of the metal layer: blank, signal, ground, power	signal	—
LayerType[2]		ground	
Rough	Roughness	0	mil

2477  
2478

The package trace is modeled as a transmission line, which is designated as ML2CTL\_C in the schematic. **Table 68** defines the properties of the transmission line consisting of coupled lines on the Subst1 substrate.

**Table 68 ML2CTL\_C: Coupled Line Properties**

Parameter Name	Description	Value	Units
—	Name of transmission line	Clin1	—
Subst	Substrate name	Subst1	—
Length	Line length	100	mil
W	Width of conductors	0.98	mil
S	Spacing	1.96	mil
Layer	Layer number of all conductors	1	—
ReuseRLGC	Reuse RLGC matrices stored in RLGC_File:	no	—

2479 The pads, MLVIAPAD, are placed on the Subst1 substrate, and have properties defined in **Table 69**.

**Table 69 MLVIAPAD: Via Pad Properties**

Parameter Name	Description	Value	Units
—	Names of via pads	Pad1, Pad2, Pad3, Pad4, Pad5, Pad6	—
Subst	Substrate name	Subst1	—
DiamVia	Via diameter	2.5	mil
DiamPad	Pad diameter	4.1	mil
Layer	Layer number	1	—
Angle	Input pin to output pin angle	180	degrees

2480 The via holes, MLVIAHOLE, are placed on the Subst1 substrate, and have properties defined in **Table 70**.

**Table 70 MLVIAHOLE: Via Hole Properties**

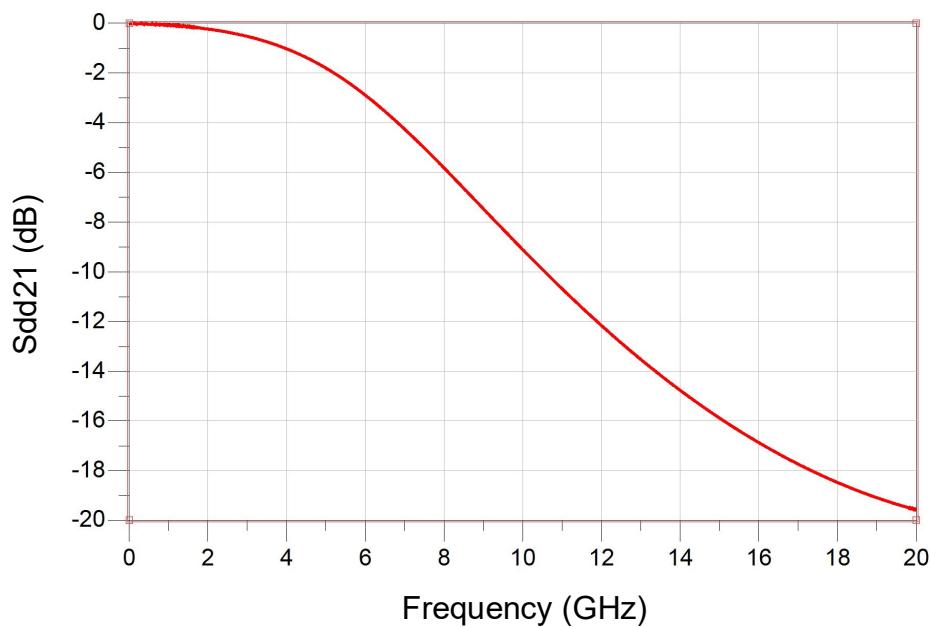
Parameter Name	Description	Value	Units
—	Names of via holes	Via1, Via2, Via3, Via4, Via5, Via6	—
Subst	Substrate name	Subst1	—
DiamVia	Via diameter	2.5	mil
T	Plating thickness	0.5	mil
Cond[1]	Conductivity	5.8E+7	S/m
Layer1	Starting layer number	1	—
Layer2	Ending layer number	2	—

2481 The via clearances on the far side, MLCLE, are placed on the Subst1 substrate, and have properties defined  
 2482 in **Table 71**.

**Table 71 MLCLE: Via Clearance Properties**

Parameter Name	Description	Value	Units
—	Names of via clearances	Clear1, Clear2, Clear3	—
Subst	Substrate name	Subst1	—
DiamClear	Clearance diameter	8.2	mil
DiamPad	Pad diameter	6.2	mil
Layer	Layer number of the clearance	2	—

2483 The insertion loss of the reference package model plus CPAD of 1.0 pF is shown in **Figure 136** for  
 2484 informative purposes. **Figure 137** is the simulation circuit used to create **Figure 136**.



2485

**Figure 136 Insertion Loss of Reference Package Model Plus C<sub>PAD</sub>**

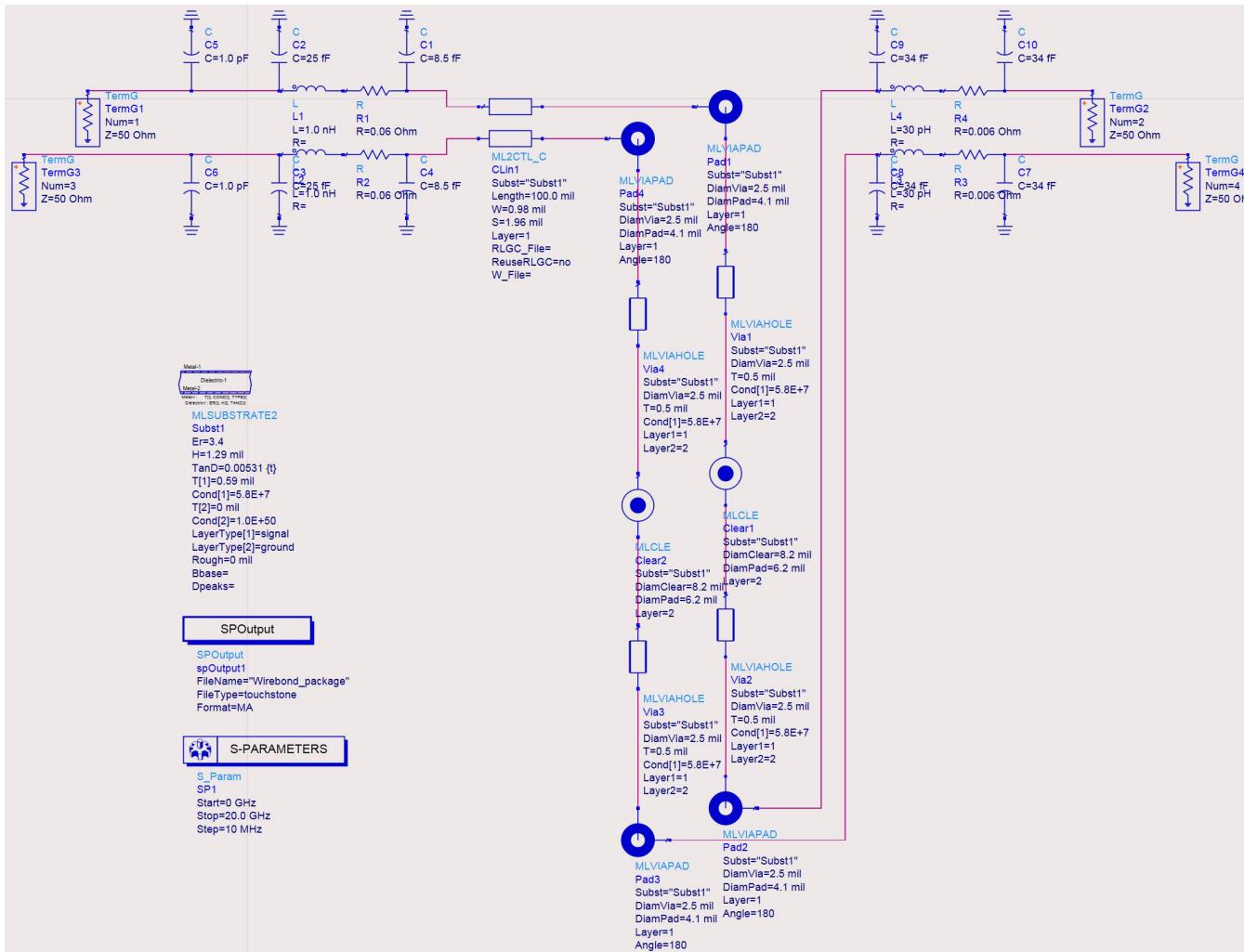
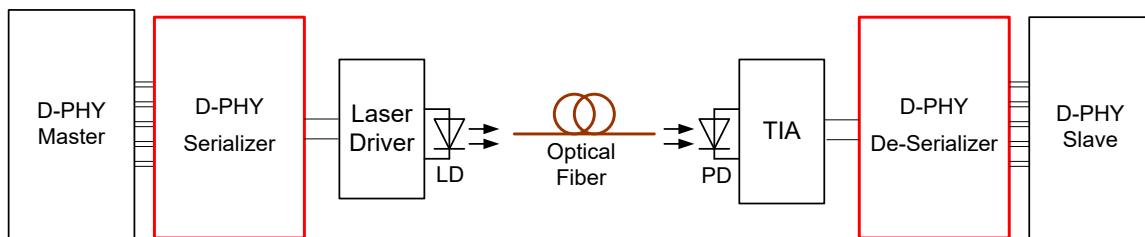


Figure 137 Example Simulation Circuit Diagram for Insertion Loss of Reference Package Model Plus  $C_{PAD}$

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## Annex G Optical Link Support

### G.1 System Setup



**Figure 138 Typical System Setup with Optical Interconnect**

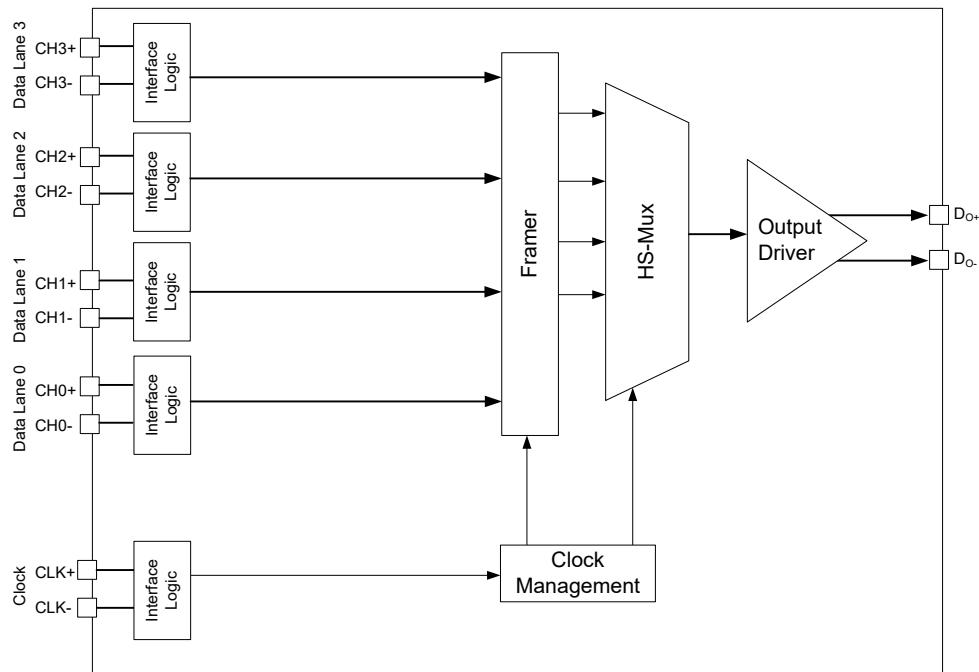
2488 **Figure 138** shows a typical setup for a D-PHY system using an optical link.

2489 The setup consists of a D-PHY Master providing the master clock and data lanes, and a serializer which  
2490 multiplexes the data content of N data lanes into a single bit stream with embedded clock. The HS clock  
2491 provided on the master Clock Lane is used as a reference for the clock multiplying unit in the serializer.  
2492 The single bit stream is then converted from an electrical signal to an optical signal by means of a laser  
2493 driver and a laser diode (LD) connected to it.

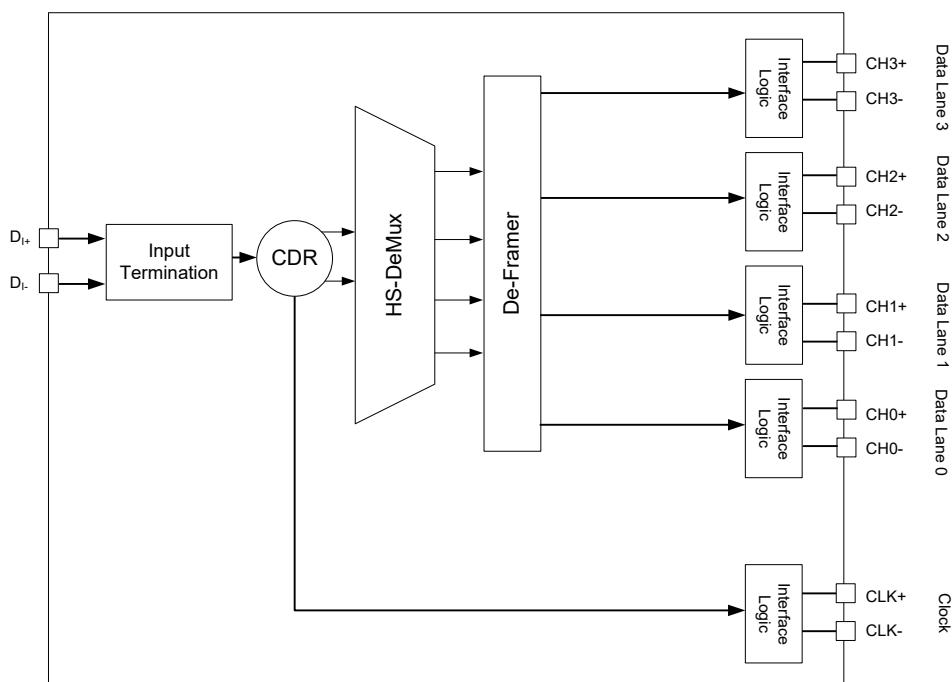
2494 The optical signal transmitted through the optical fiber is converted back to an electrical signal by means of  
2495 a photo diode (PD) and a transimpedance amplifier (TIA). The de-serializer synchronizes to the clock  
2496 embedded in the serial data stream and de-multiplexes the data content of N data lanes. The output of the  
2497 de-serializer to the D-PHY Slave is composed of a set of N D-PHY-compliant data lanes and a D-PHY  
2498 compliant Clock Lane which replicates the D-PHY signal input to the serializer.

2499 An optical link implemented in this manner provides a transparent interface between a D-PHY Master and  
2500 a D-PHY Slave.

## G.2 Serializer and De-Serializer Block Diagrams



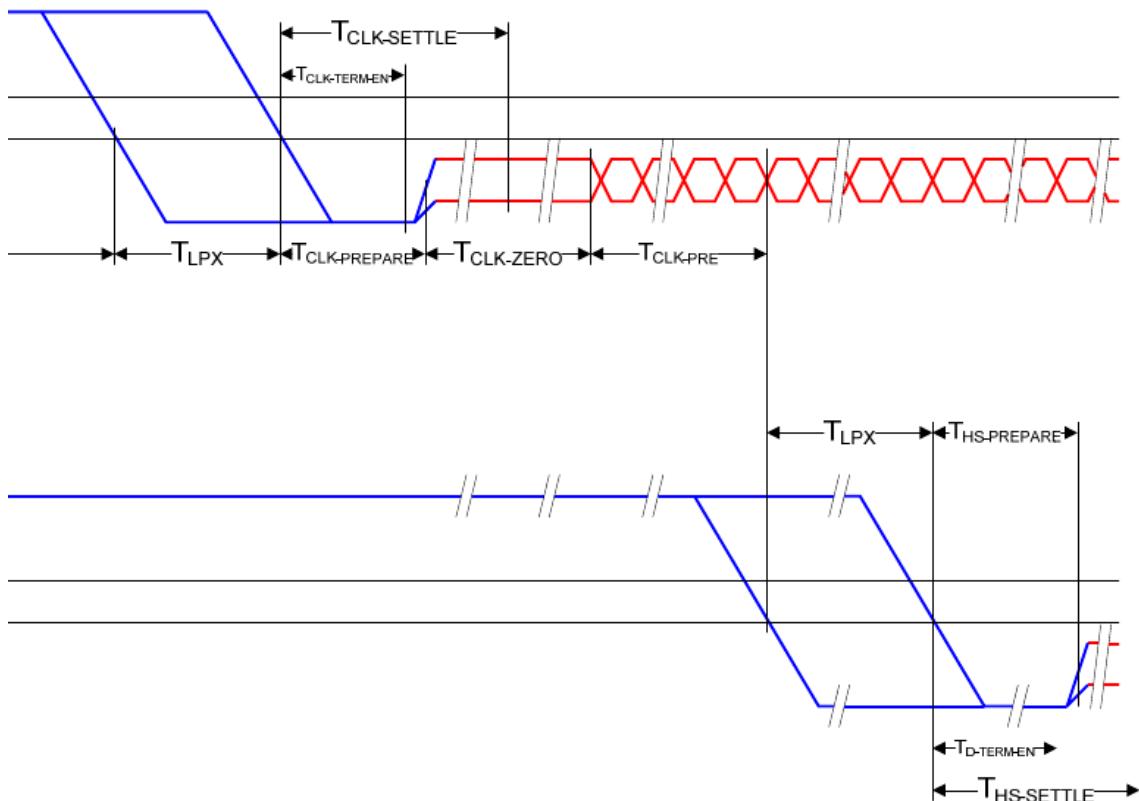
**Figure 139 Block Diagram of Typical Serializer for Optical Link**



**Figure 140 Block Diagram of Typical De-Serializer for Optical Link**

2503 **Figure 139** and **Figure 140** show typical block diagrams for serializers and de-serializers used to  
2504 implement the optical link.

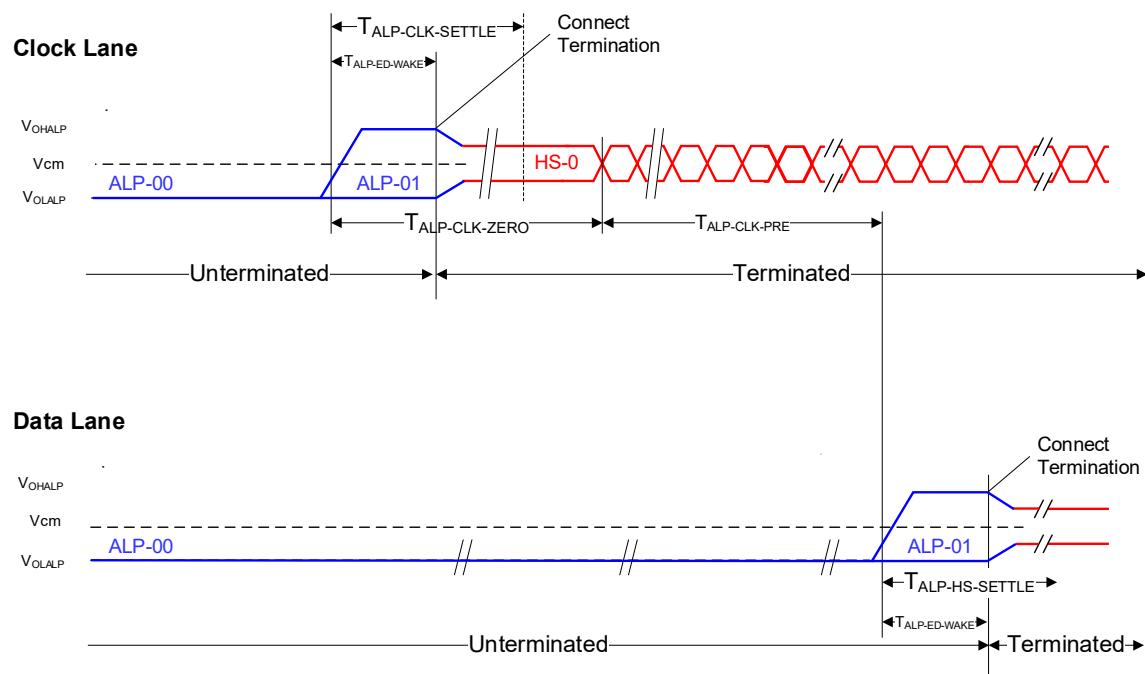
### G.3 Timing Constraints



**Figure 141 Delay Between Start of HS Clock and HS Data Transmission Without Optical Link in LP Mode**

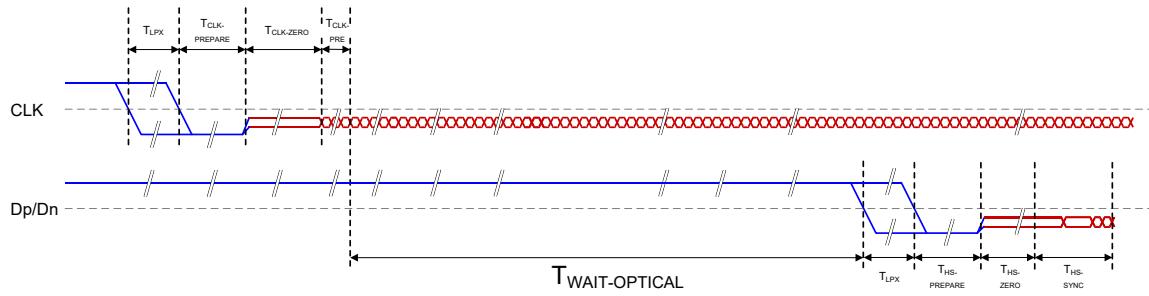
2505

**Figure 141** shows that in a purely electrical D-PHY interconnect, there is a timing delay between the start of HS clock transmission and the start of HS data transmission equal to the sum of  $T_{CLK-PRE} + T_{LPX} + T_{HS-SETTLE}$ . However if an optical link is added as shown in **Figure 138**, then the serializer's clock multiplying unit (typically a PLL) and the de-serializer's clock and data recovery (CDR) require synchronization times that exceed this timing delay. In **Figure 141**, LP mode signalling is used. In cases where ALP mode is being used instead of LP mode, conceptually the same restriction applies as shown in **Figure 142**.



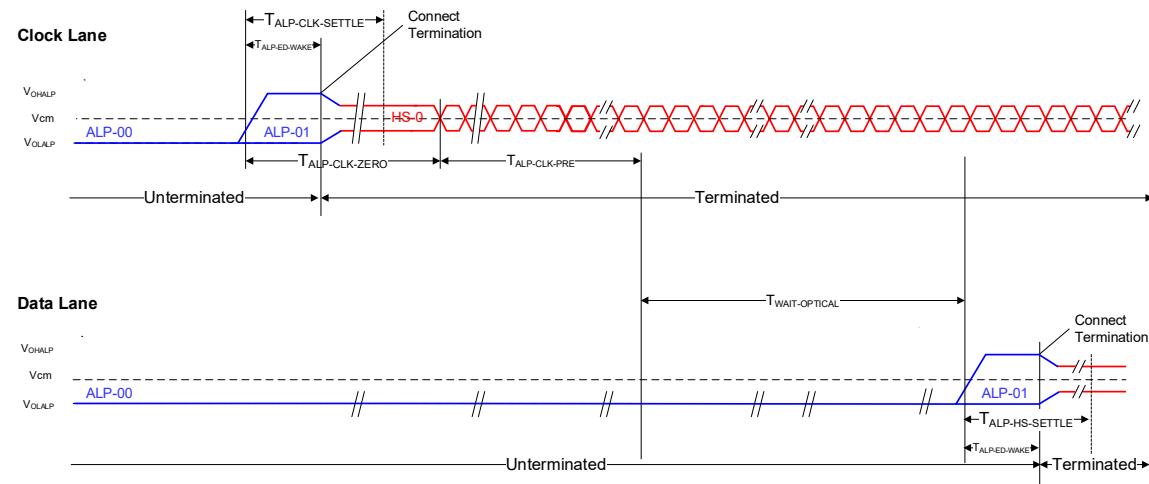
**Figure 142 Delay Between Start of HS Clock and HS Data Transmission Without Optical Link in ALP Mode**

Therefore, for an optical D-PHY interconnect an additional wait time  $T_{WAIT-OPTICAL}$  should be inserted before any HS data is transmitted, in order to provide enough timing headroom for the optical link to establish synchronization.



**Figure 143 Delay Between Start of HS Clock and HS Data Transmission With Optical Link in LP Mode**

**Figure 143** illustrates the additional wait time  $T_{WAIT-OPTICAL}$  inserted between the end of  $T_{CLK-PREPARE}$  and the beginning of  $T_{LPX}$  of the first data lane scheduled to switch from STOP state to HS data mode. Conceptually the same applies when ALP mode is used, as illustrated in **Figure 144**. The additional wait time  $T_{WAIT-OPTICAL}$  should be inserted between the end of  $T_{ALP-CLK-PREPARE}$  and the beginning of  $T_{ALP-ED-WAKE}$  of the first data lane scheduled to switch from STOP state to HS data mode.



**Figure 144 Delay Between Start of HS Clock and HS Data Transmission With Optical Link in ALP Mode**

The additional wait time  $T_{WAIT-OPTICAL}$  ensures that the optical link is fully synchronized by the time the first data lane switches from the STOP state to HS data mode. If the duration of the inserted  $T_{WAIT-OPTICAL}$  is too short, then the optical link will not be able to correctly transmit the beginning of the next HS data burst, resulting in loss of state information and of HS data.

## G.4 System Constraints

### G.4.1 Bus Turnaround

2528 Due to the optical link's inherently unidirectional nature, bus turnaround (BTA) may not be supported with  
 2529 an optical link.

### G.4.2 Equalization (De-emphasis), Deskewing, and Spread Spectrum Clocking

2530 Equalization (de-emphasis), deskewing and Spread Spectrum Clocking may be supported by the optical  
 2531 link manufacturer. This must be stated in the corresponding datasheet of the optical link. If these features  
 2532 are included in the optical link, then the electrical inputs of the optical link should follow the D-PHY  
 2533 specification for a D-PHY RX, and the electrical outputs of the optical link should follow the specification  
 2534 for a D-PHY TX for these features. System integrators should take care to ensure compliance during  
 2535 implementation.

### G.4.3 $T_{WAIT-OPTICAL}$

2536 *Table 72* specifies  $T_{WAIT-OPTICAL}$ , the parameter for additional wait time for synchronization of the optical  
 2537 link.

**Table 72 Timing with Optical Link**

Parameter	Description	Min	Units
$T_{WAIT-OPTICAL}$	Additional wait time for synchronization of the optical link	150,000	UI (lane data bit)

### G.4.4 LP and ALP Mode

2538 After start of the HS clock, the Clock Lane stays active in HS mode and runs at the same frequency  
 2539 regardless of HS, LP, or ALP mode on any Data Lane.

2540 On Data Lanes, dynamic switching between LP mode and ALP mode is not supported in optical links.

## Annex H Dynamic LP-ALP Mode Operation (Informative)

As previously described, within both TX and RX five main processes can be distinguished: High-Speed Transmission, LP mode, ALP mode, Calibration, and Initialization. *Figure 47* is the operational flow diagram that describes those processes.

Two operational modes are defined for High-Speed transmission:

- **LP and HS operating modes** as described in *Section 6.3.1* and
- **ALP and HS operating modes** as described in *Section 6.3.2*.

System implementers decide which of the two modes is set by default for Link initialization. This section defines an option to dynamically switch between these two operational modes after initialization.

Dynamic LP-ALP mode operation can be used in a Link that supports both LP and ALP modes. It enables a dynamic switch between LP mode and ALP mode without the need for separate initializations. A Dynamic LP-ALP mode operation is initiated by an ALP Control Burst with a dedicated 16-bit Control-Code, which is defined in *Section H.1.1*. This code informs the receiver that after completion of the HS-Trail of the ongoing ALP Control Burst, the Data Lane transitions to LP mode in case of a “Switch to LP mode” Entry Control Burst, or to ALP mode in case of a “Switch to ALP mode” Entry Control Burst. A Clock Lane remains in the LP or ALP mode as configured upon initialization, as Clock Lanes don’t support control codes.

The process and requirements for Dynamic LP-ALP mode switching are as follows:

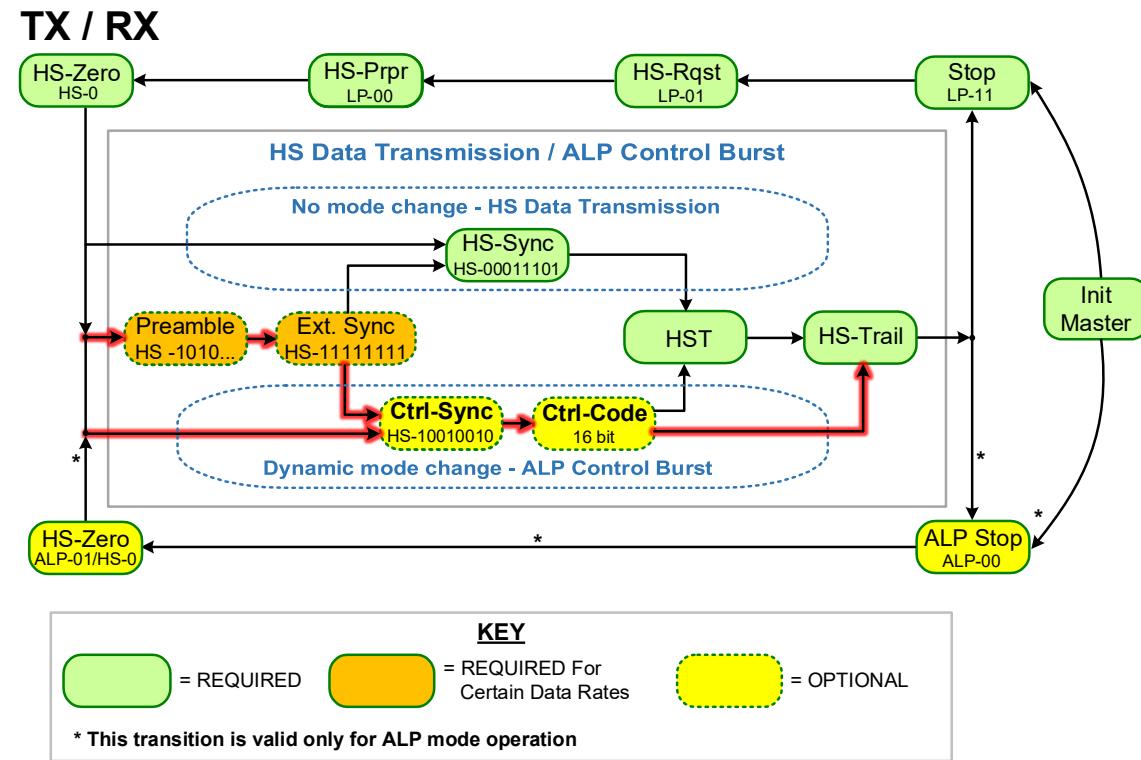
- Both the transmitter and the receiver support Dynamic LP-ALP mode.
- During initialization, the system is configured for LP or ALP mode operation as described in *Section 6.11*.
  - Transmitter and receiver are configured adequately to ensure that they interoperate, i.e., that the related PPI signal settings of both are consistent in their LP-ALP mode selection.
  - The mode of operation at initialization is determined by PPI signal AlpMode as defined in *Table 58*. Note that this signal determines only the mode at initialization, and should only change state while the Enable PPI signal is not active.
- An ALP Control Burst with dedicated Control-Codes is used to dynamically switch between LP and ALP modes.
- The ALP Control Burst for Dynamic LP-ALP mode switching is an extension to the Escape Mode sequences in ALP Mode, as described in *Section 6.6.5*, using the same PPI control signals: TxRequestEsc and TxRequestTypeEsc.

Dynamic LP-ALP mode switching enables implementers to trade off reduced power in LP-11 Stop state with faster entry/exit times obtained with ALP-00 Stop state. More information can be found in the protocol specifications.

## H.1 Description of Operation

The system is configured for a specific operation mode at power-up, i.e., either LP mode or ALP mode. If Dynamic LP-ALP mode operation is supported, then a Link can dynamically switch between LP mode and ALP mode after initialization. Switching between modes is achieved through Control Bursts using special Control-Codes, sent after the Control-Sync and prior to the HS-Trail.

This concept is illustrated in the state machine in *Figure 145*, which shows a subset of *Figure 47*. As shown by this state machine, the Dynamic LP-ALP mode operation uses a Control Burst to send the proper Control-Code to the receiver.



**Figure 145 Dynamic LP-ALP Mode Operation**

### H.1.1 Control-Code Definitions

Dynamic LP-ALP mode operation uses two Control-Codes to signal an impending mode switch to the receiver. *Table 73* shows the mapping of the Dynamic LP-ALP mode Control-Codes and the TxRequestTypeEsc PPI Code.

**Table 73 Dynamic LP-ALP Control-Cod Definitions**

Dynamic LP-ALP Mode Control Action	ALP Control-Code	TxRequestTypeEsc PPI Code	Description
Switch to LP mode	11100001 00011110	1001	Dynamic LP-ALP mode: The current ALP Control Burst ends in LP mode, Link will transition to LP and HS operating mode.
Switch to ALP mode	11100010 00011101	1000	Dynamic LP-ALP mode: The current HS Control Burst ends in ALP mode, Link will transition to ALP and HS operating mode.

**Note:**

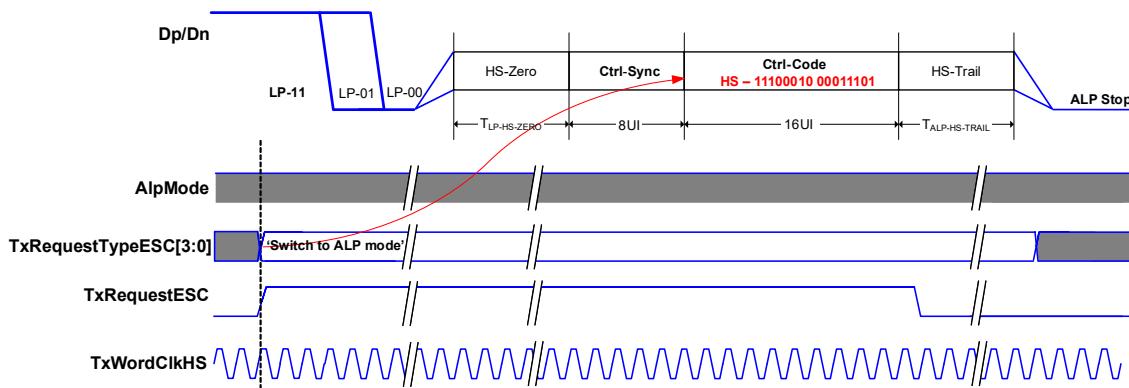
The two Dynamic LP-ALP mode Control-Codes are defined in addition to the ALP Control-Codes, as described in *Table 12* in *Section 6.6.5*, and in addition to the Fast Turnaround Control-Code as described in *Section 6.5.2*.

### H.1.2 Transition from LP to ALP Mode

This section describes the Dynamic LP-ALP mode transition from LP to ALP mode. It is important to note that the LP to ALP mode transition is not done directly from the LP-11 Stop state to the ALP-00 Stop state; instead, it is done via a Control Burst which sends the Control-Code “Switch to ALP mode”. *Figure 146* shows an example of the PPI signals for the Control Burst for Dynamic LP-ALP mode transition.

The control of the dynamic transition from LP to ALP is enabled by the PPI signals sequence:

- **Transition from LP Mode to HS Burst:** TxRequestEsc goes high to initiate the exit from LP-11. At the same time, TxRequestTypeEsc PPI Code is set to send the Control Code, which determines that the ALP Control Burst will end in ALP mode.
- **Transition from HS Burst to ALP Mode:** After Control Burst is completed, both TX and RX transition to ALP mode as described in *Section 6.4.5*.



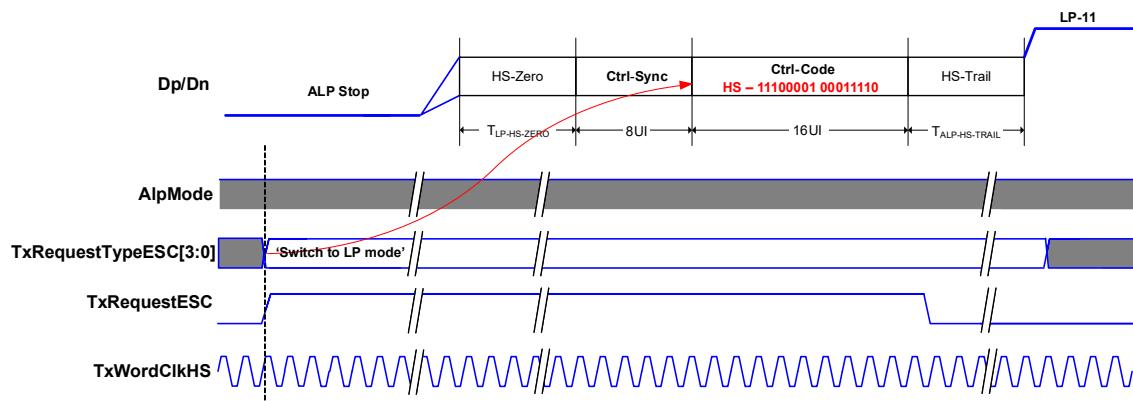
**Figure 146 Dynamic LP-ALP Mode Transition from LP to ALP Mode**

### H.1.3 Transition from ALP to LP Mode

This section describes the Dynamic LP-ALP mode transition from ALP mode to LP mode. It is important to note that the ALP to LP mode transition is not done directly from the ALP-00 Stop to LP-11 Stop state; instead, it is done via an ALP Control Burst, which sends the Control-Code “Switch to LP mode”. **Figure 147** shows an example of the PPI signals for the ALP Control Burst for Dynamic LP-ALP mode transition.

The control of the dynamic transition from ALP to LP is enabled by the PPI signals sequence:

- **Transition from ALP Mode to HS Burst:** TxRequestEsc goes high to initiate the exit from ALP mode. At the same time, TxRequestTypeEsc PPI Code is set to send the Control Code, which determines that the HS Burst will end in LP mode.
- **Transition from HS Burst to LP Mode:** After ALP Control Burst is completed, both Tx and Rx transition to LP mode as described in **Section 6.4.3**.



**Figure 147 Dynamic LP-ALP Mode Transition from ALP to LP Mode**

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