Differential Magnetoresistive Sensor FP 212 L 100-22

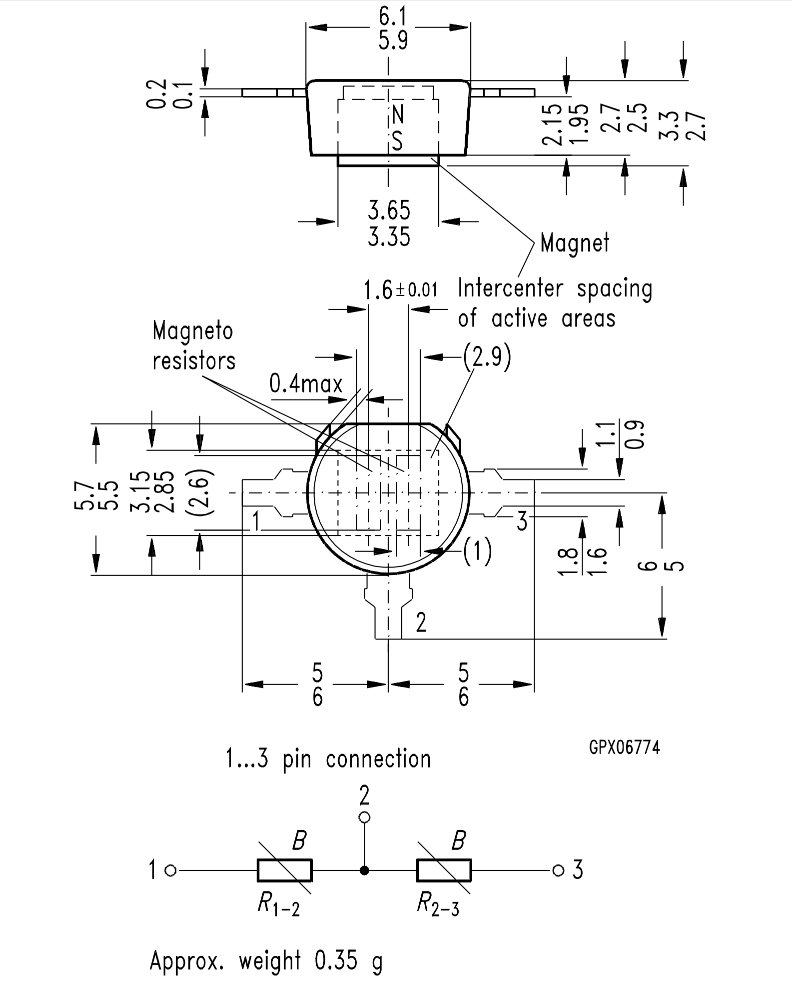
Version 2.0

Features

- High output voltage
- High operating temperature
- Robust plastic housing
- Biasing magnet build in
- Signal amplitude is speed independent
- Marking silver

Typical Applications

- Detection of speed
- Detection of position
- Detection of sense of rotation
- Angle encoder
- Linear position sensing



Dimensions in mm

Type	Ordering Code
FP 212 L 100-22	Q65212-L1004

The differential magnetoresistive sensor FP 212 L 100-22 consists of two series coupled magneto resistors (L-type InSb/NiSb semiconductor resistors whose value can be magnetically controlled) which are mounted onto an insulated ferrite substrate. The sensor is encapsulated in a plastic package and has three connecting terminals.

The basic resistance of the total system is $2 \times 100\ \Omega$. A permanent magnet which supplies a biasing magnetic field is fixed on the base of the sensor.

Absolute Maximum Ratings

Parameter	Symbol	Limit Values	Unit
Operating temperature	T_A	– 40 / + 140	°C
Storage temperature	T_{stg}	– 40 / + 150	°C
Power dissipation[1)]	P_{tot}	450	mW
Supply voltage[2)]	V_{IN}	10	V
Insulation voltage between terminals and magnet	V_I	> 60	V
Thermal conductivity (when soldered)	G_{thA}	≥ 5	mW/K

Electrical Characteristics (T_A = 25 °C)

Nominal supply voltage	$V_{IN\ N}$	5	V
Total resistance, ($\delta = \infty$, $I \leq 1$ mA)	$R_{1\text{-}3}$	220…400	Ω
Center symmetry[3)] ($\delta = \infty$)	M	≤ 10	%
Offset voltage[4)] (at $V_{IN\ N}$ and $\delta = \infty$)	V_0	≤ 130	mV
Open circuit output voltage[5)] ($V_{IN\ N}$ and δ = 0.2 mm)	$V_{out\ pp}$	> 1000	mV
Cut-off frequency	f_c	> 20	kHz

Measuring Arrangements

By approaching a soft iron part close to the sensor a change in its resistance is obtained. The potential divider circuit of the magneto resistor causes a reduction in the temperature dependence of the output voltage V_{OUT}.

1) Corresponding to diagram $P_{tot} = f(T_A)$
2) Corresponding to diagram $V_{IN} = f(T_A)$
3)

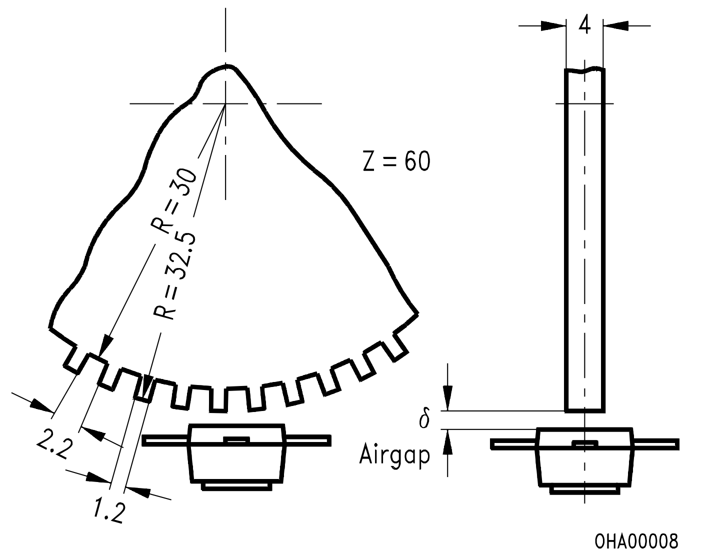
$$M = \frac{R_{1-2} - R_{2-3}}{R_{1-2}} \times 100\% \text{ for } R_{1\text{-}2} > R_{2\text{-}3}$$

4) Corresponding to measuring circuit in **Fig. 2**
5) Corresponding to measuring circuit in **Fig. 2** and arrangement as shown in **Fig. 1**

1. Digital Revolution Counting

For digital revolution counting, the sensor should be actuated by a magnetically soft iron toothed wheel. The tooth spacing should correspond to about twice the magneto resistor intercenter spacing i.e 2×1.6 mm (see **Figure 1**).

The two resistors of the sensor are supplemented by two additional resistors in order to obtain the sensor output voltage as a bridge voltage V_{OUT}. The output voltage V_{OUT} without excitation then is 0 V when the offset is compensated.



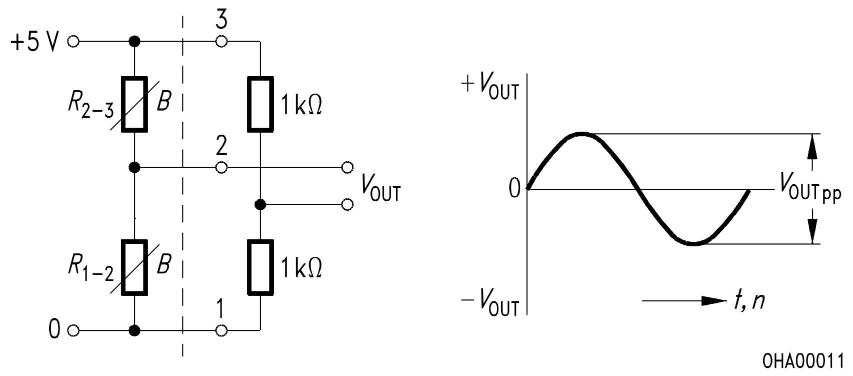


Figure 1
Schematic Representation of a Toothed Wheel actuating an FP 212 L 100-22

Figure 2
Measuring Circuit and Output Voltage V_{OUT} Waveform

2. Linear Distance Measurement

To convert small distances into a proportional electric signal, a small soft iron part of definite width (e.g. b = 1.8 mm) is moved over the face of the sensor.

Proportional signals for distances up to 1.5 mm can be obtained in this way. The sinusoidal output signal gives a voltage proportional to distance in the zero crossover region (see **Figure 3**).

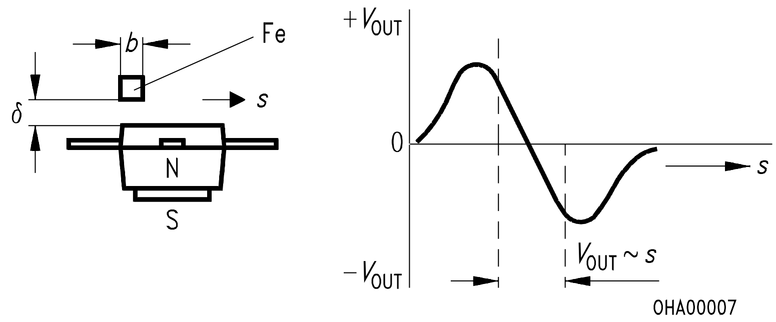
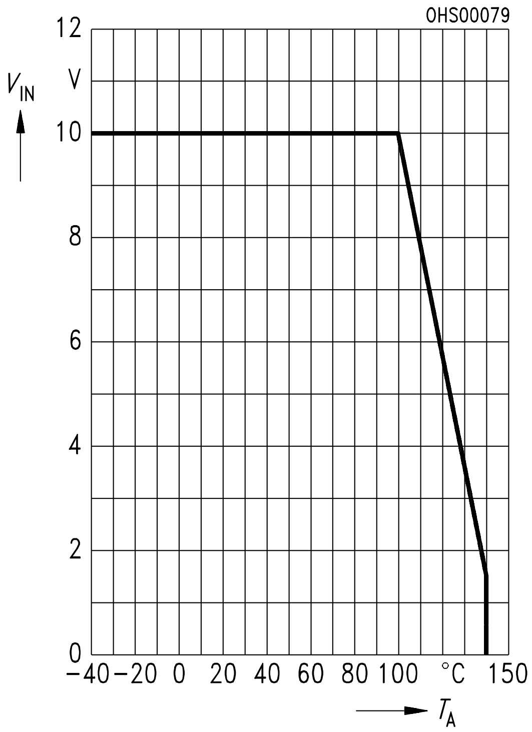
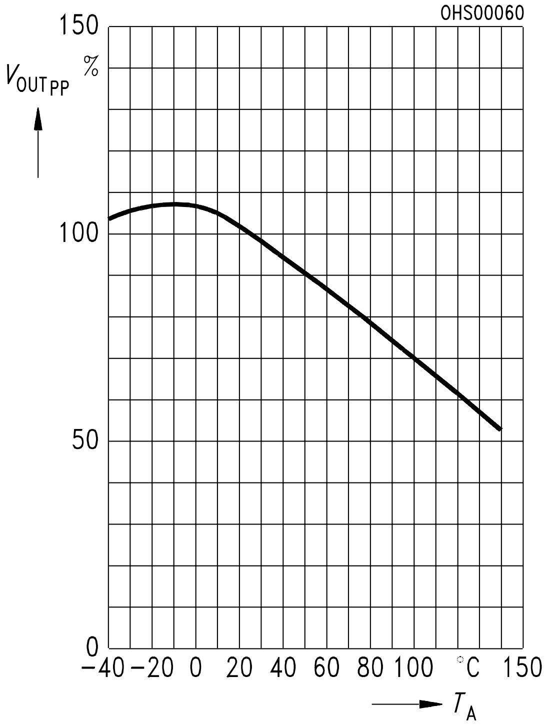


Figure 3
Measuring Arrangement for Analogue Application

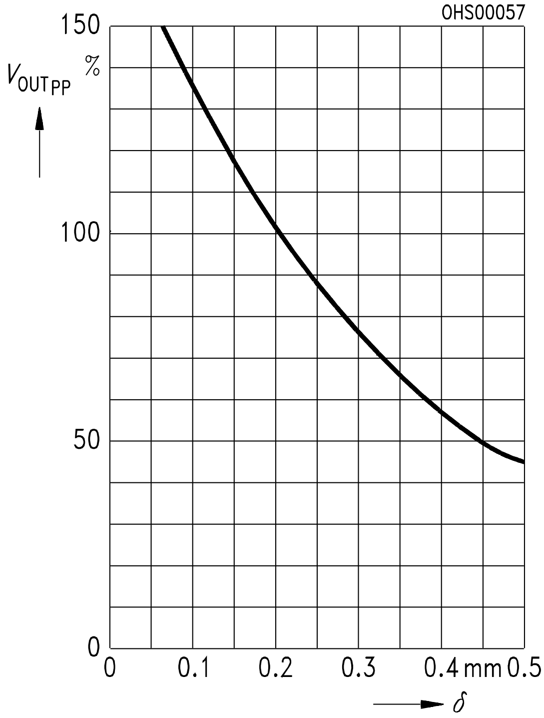
Maximum supply voltage versus temperature
$V_{IN} = f(T_A)$



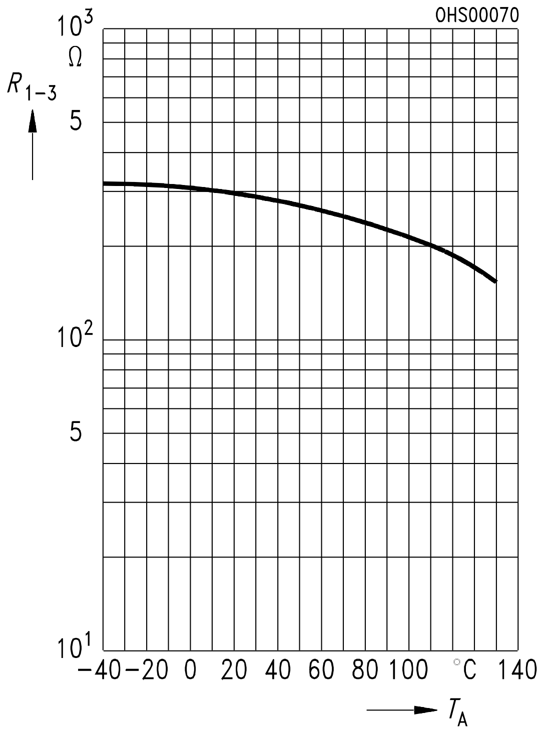
Output voltage (typical) versus temperature $V_{OUTpp} = f(T_A)$, $\delta = 0.2$ mm
V_{OUTpp} at $T_A = 25$ °C ≙ 100%



Output voltage (typical) versus airgap $V_{OUTpp} = f(\delta)$, $T_A = 25$ °C
V_{OUTpp} at $\delta = 0.2$ mm ≙ 100%



Total resistance (typical) versus temperature
$R_{1\text{-}3} = f(T_A)$, $\delta = \infty$



Max. power dissipation versus temperature
$P_{tot} = f(T_A)$, $\delta = \infty$