Barracuda Series

Product Manual

3.5” Hard Disk Drives

January 11, 2012. Rev5

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CHAPTER 1 SCOPE

Welcome to the Barracuda Seagate hard disk drive. This series of drives consists of the following model : ST1000DM005 and the others. This chapter provides an overview of the contents of this manual, including the intended user, manual organization, terminology and conventions. Furthermore, a list of references and technical glossary are listed to aid the users.

1.1 User Definition

The Barracuda product manual is intended for the following users:

- Original Equipment Manufacturers (OEMs)
- Distributors

1.2 Manual Organization

This manual provides information about installation, principles of operation, and interface command implementation. It is organized into the following chapters:-

- Chapter 1 - SCOPE
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- Chapter 3 - SPECIFICATIONS
- Chapter 4 - INSTALLATION
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1.3 SATA

The ATA (Advanced Technology Attachment) interface which was developed based on the IDE (Integrated Drive Electronics) has been around from 1980's. As the PC processor speed has improved, so have the data rates of the HDD. The parallel ATA is reaching its limit of 166 MB/s data transfer rate. Serial implementation of ATA (SATA) will allow the data rate to run even faster so the processor will be utilized more efficiently. Serial ATA has been developed to provide the next generation storage interface.

SATA interface replaces 2 inch wide, 40 pin parallel interface connector with 0.25 inch wide 7 pin serial interface connector. The maximum length of the SATA interface cable can be extended to 1 meter (approximately 39 inches) compared to 18 inch of parallel ATA. SATA also allows a data transfer speed of 300 MB/s and has a roadmap up to 600 MB/s to support storage evolution of the next decade. Even though SATA will not directly interface with Parallel or traditional ATA (PATA) hardware, it is compliant with ATA protocol and therefore software compatible. The cable geometry with smaller

footprint connector reduces board space requirements and improves air flow and heat exchange inside computer systems.

SATA uses point to point connection topology and each channel works independently. There is no sharing of interface, master/slave drive configuration, and no master/slave jumper settings. This is different from Parallel ATA (PATA) architecture where 2 drives per port are supported by a shared bus and drives are designated as master or slave drive based on jumper pin or cable selection. Unlike parallel ATA, SATA drives are hot-plug and hot-swappable.

Serial ATA II: Extensions to Serial ATA 1.0a specification incorporate new features including Pin 11 Definition for Activity LED and staggered spin-up control, Phy Event Counters, Software Settings Preservation, Native Command queuing, Hot-Plugging, and port multiplier, etc.

1.4 Reference

For additional information about the AT interface, please refer to:

- ATA-2 (AT Attachment 2), Rev. 3, January 12, 1995
- ATA-3 (Attachment-3 Interface) Rev. 7b, January 27, 1997
- ATA-4 (AT Attachment with Packet Interface) Rev. 18, 19 August 1998
- ATA-5 (AT Attachment with Packet Interface) Rev. 3, 29 February 2000
- ATA-6 (AT Attachment with Packet Interface) Rev. 2a, 26 September 2001
- ATA-7 (AT Attachment with Packet Interface, Volume 1/2/3) Rev. 4b April 21, 2004
- ATA-8 (ATA/ATAPI Command Set (ATA8-ACS Rev. 6)) 25 June, 2008

For introduction about SATA interface please refer to:

- SATA 1.0 Design Guides, April 5, 2002. (URL: http://www.sata-io.org)
- Serial ATA: A comparison with Ultra ATA Technology (URL: http://www.intel.com retrieved April 18,2003)
- Serial ATA: High Speed Serialized AT Attachment, Rev. 1.0a, January 7, 2003, Serial Workgroup. (URL: http://www.sata-io.org)
- Serial ATA II: Port Multiplier 1.0 Specification**,** April 29th, 2003. (URL: http://www.sata-io.org retrieved on May 22, 2003)
- Serial ATA II: Extensions to Serial ATA 1.0a, Rev. 1.2, August 27, 2004 (URL: http://www.serialata.org)
- Serial ATA: Integrated revision, Rev. 2.5, October 27, 2005. (URL: http://www.sata-io.org)

CHAPTER 2 DESCRIPTION

This chapter summarizes general functions and key features of the Barracuda SATA drive. Moreover, it lists the standards and pertinent requirements.

2.1 Introduction

The Seagate Barracuda 3.5 inch disk drive is high capacity, high performance random access storage devices, which use non-removable 3.5-inch disk as storage media. Each disk incorporates thin film metallic media technology for enhanced performance and reliability. And for each disk surface there is a corresponding movable head actuator assembly to randomly access the data tracks and write or read the user data. The formatted storage capacities of the Barracuda are 1,000 Gigabytes and others. A Gigabyte (GB) contains one billion bytes or 8 billions bits of data.

The Barracuda drive includes the native SATA interface controller embedded in the disk drive controller chip. The drive's electrical interface is compatible with all mandatory commands within the SATA specification.

Drive size conforms to the industry standard 3.5-inch form factor. The SATA data signal cables which come in 0.5 or 1 meter long.

The Barracuda incorporates Tunneling MR head and Noise Predictive PRML (Partial Response Maximum Likelihood) signal processing technologies. These advanced technologies allow for an areal density of over 167 Gigabits per square inch and storage capacity of over 500 Gigabytes per disk. It also incorporates 48 bit LBA (logical block address) for more than 137 GB capacities.

The heads, disk(s), and actuator housing are environmentally sealed within an aluminum-alloy base and cover. As the disks spin, air circulates within this base and cover, commonly referred to as the head and disk assembly (HDA), through a high efficiency particulate filter ensuring a contamination-free environment for the heads and disks throughout the life of the drive. A disk damper has been incorporated into the HDD to reduce the disk vibration. A visco-elastic damper is clamped against the voice coil motor (VCM) assembly so as to dampen acoustic noise during accessing. A fluid bearing spindle motor is installed to significantly reduce the acoustic noise commonly found on the ball bearing motor. It further reduces the non-repeatable run out of the track allowing more tracks to be formatted.

2.2 Key Features

Key features of the Barracuda SATA hard disk drive includes:

- Formatted capacity is 500GB per Disk
    - 1-inch height form factor
    - 5,435 /7,247 RPM class
    - 8.9 ms average seek time
    - High precision rotary voice coil actuator with embedded sector servo
- Serial ATA (SATA) Interface
    - Supports SATA interface Gen I (1.5 Gbps) and Gen II (3.0 Gbps) speed
    - Native SATA device without using SATA bridge chip
    - Support SATA 1.0a and SATA II features
        - Asynchronous Signal Recovery (ASR)
        - Pin-11 Device Activity Signal (Activity LED)
        - Pin-11 Staggered Spin-up Control
        - Auto-Activate DMA Setup FIS
        - Native Command Queuing with queue depth of 32 (First Party DMA)
        - Physical Event Counters
        - Software Settings Preservation
        - SATA Device Hot Plug Capability
        - Device Initiated Power Management
        - Host Initiated Power Management
- Supports both CHS and LBA (28 and 48 bit) Addressing modes
- Supports all logical geometries as programmed by the host
- 16MB/32MB buffer memory for read and write cache.
- Transparent media defect mapping
- High performance in-line defective sector skipping
- Auto-reassignment
- Automatic error correction and retries
- On-the-fly (OTF) error correction
- Noise predictive PRML read channel
- TA (thermal asperity) detection and correction
- Dynamic anti-stiction algorithm
- Tunneling MR head
- SMART feature support
- Automatic Acoustic Management (AAM)
- Hot-plug and Hot-Swap capable
- SilentSeek™
- Noise Guard™
- Fluid Bearing Spindle Motor Technology

2.3 Standards and Regulations

The Barracuda depends upon its host equipment to provide power and appropriate environmental conditions to achieve optimum performance and compliance with applicable industry and governmental regulations. Special attention has been given in the areas of safety, power distribution, shielding, audible noise control, and temperature regulation.

The Barracuda hard disk drive satisfies the following standards and regulations:

- Underwriters Laboratory (UL): Standard 1950. Information technology equipment including business equipment.
- Canadian Standards Association (CSA): Standard C22.2 No.3000-201 Information technology equipment including business equipment.
- Technisher Überwachungs Verein (TUV): Standard EN 60 950. Information technology equipment including business equipment.

2.4 Hardware Requirements

Barracuda hard disk drive is designed for use with host computers and controllers that are ATA compatible. They are connected to a PC either by:

- Using an adapter board with SATA interface, or
- Plugging a cable from the drive directly into a PC motherboard with a SATA interface

CHAPTER 3 SPECIFICATIONS

This chapter gives a detailed description of the physical, electrical, and environmental characteristics of the Barracuda hard disk drive.

3.1 Specification Summary

Table 3-1 Specifications

DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Number of Disks	1			2		
Number of R/W heads	1		2		4	
Maximum Data Transfer Rate(MB/s)	250					
Track density (tpi)	245k					
Interface	Serial ATA3.0Gbps					
Actuator type	Rotary Voice Coil					
Servo type	Embedded Sector Servo					
Spindle speed	5,435/7,247 RPM class(Target RPM +/- 0.35%)					

3.2 Physical Specifications

Table 3-2 Physical Specifications

DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Length (mm)	147.00 Max					
Width (mm)	101.60 ± 0.25					
Height (mm)	26.10 Max					
Weight (gram)	475 ± 10%			625 ± 10%		

3.3 Logical Configurations

Table 3-3 Logical Configurations

DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Default logical mode: Number of cylinders Number of heads / cylinders Number of sectors / heads	16,383 16 63					
Total Number of logical sectors	488397168	156301488 312581808 312581808 4883971684 88397168	488397168 976773168	488397168 488397168 976773168	1953525168 1465149168	1953525168 1465149168
Capacity	250GB	80GB 160GB 160GB 250GB 250GB	320GB 500GB	320GB 320GB 500GB	1000GB 750GB	1000GB 750GB

* Maximum number of logical cylinders in CHS mode is 16,383.
Systems that incorporate more than 8.4GB per storage device must access the drive in LBA addressing mode.

3.4 Performance Specifications

Table 3-4 Performance Specification

DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Buffer size	16	8MB 8MB 16MB 8MB 16MB	16MB	8MB 16MB	32MB	32MB
Seek Time(1) (Performance mode, RD, Typ./Max) Average seek time Track to track seek time Full stroke seek time	8.9 / 10.5 ms 0.8 / 2.0 ms 18.0 / 20.0 ms					
Seek Time(1) (Performance mode, WR, Typ./Max) Average seek time Track to track seek time Full stroke seek time	10.0 / 11.5 ms 1.0 / 3.0 ms 19.0 / 22.0 ms					
Seek Time(1) (Quiet mode(2), Typ./Max) Average seek time(RD) Average seek time(WR)	12.0 / 14.0 ms 13.0 / 15.0 ms					
Data Transfer Rate: (Maximum) buffer to/from media host to/from buffer	250 MB/s 300 MB/s					
Average latency(3)	5.5 ms / 4.14ms					
Rotational Speed (4)	5,400 RPM	7,200 RPM	5,400 RPM	7,200 RPM	5,400 RPM	7,200 RPM

Power-on ready time (Typical/Max) (5)	7 / 20	8 /20	7 / 20	8 /20	10 /20	11 /20
Motor spin down time (Typical/Max) (5)	7 / 20	8 /20	7 / 20	8 /20	10 /20	11 /20

NOTES:

(1) Seek time is defined as the time from the receipt of a read, write or seek command until the actuator has repositioned and settled on the desired track with the drive operating at nominal input voltages, with nominal operating temperature, and without any external shock or vibration. Typical value is defined as: typ = avg + 3*stdev/SQRT (N), where "avg" and "stdev" stand for the averaged seek time and standard deviation of the seek time of N(N>40) samples, respectively. Average seek time is determined by averaging the time to complete 1,000 seeks of random length. Maximum seek time is determined as all the same procedure as in typical value except that the drives may operate at all operating input voltage and all temperature ranges.

(2) Quiet mode is defined for AAM (automatic Acoustic Management) mode with minimum performance.

(3) Average latency is the time required for the drive to rotate 1/2 of a revolution and on average is incurred after a seek completion prior to reading or writing user data.

(4) Actual target RPM is close to 5,400/7,200 but can be a little bit different. However, spindle control accuracy is within 0.35% of a pre-defined target RPM.

(5) Ready time is the time elapsed between the supply voltages reaching operating range and the drive being ready to accept all commands. Maximum value is defined for all operating conditions but the drive should be stored in the operating condition at least 8 hrs. The definition of the typical value and maximum value are all the same as those of the seek time.

3.5 Power Requirements

Table 3-5 Power Requirements[1]

Mode	Current (mA)				Power (Watt)	
	+5 Volts		+12 Volts			
	1D / 2D		1D / 2D		1D / 2D	
	5400rpm	7200rpm	5400rpm	7200rpm	5400rpm	7200rpm
Spin-up (Typical)			1,900/2,000	2,000/2,200		
Operating mode[2]						
Average Active idle[3]	298	225/235	163 /223	285 / 385	3.80 / 4.60	4.80 / 6.20
Average Random seek[4]	293 / 503	251/255	214 / 254	324 / 415	4.50 / 5.00	5.30 / 6.60
Average Read/Write[5]	498 / 308	422/426	159 / 409	282 / 387	5.00 / 5.70	5.70 / 7.10
Average Standby[6]	160/103(*)/ 160 / 93(*)	116 / 104(*)/ 117 / 108(*)	20 / 20(*)	20 / 20(*)	1.00 / 0.70(*)	1.00 / 0.70(*)
Average Sleep[7]	160/103(*)/ 160 / 93(*)	115 / 104 (*)/ 117 / 107 (*)	20 / 20(*)	20 / 20(*)	1.00 / 0.70(*)	1.00 / 0.70(*)

1) Operating conditions for the input voltage: +5V±5%, +12V±10%. All the power requirements for the different operating modes above are defined at nominal input voltages, with nominal operating temperature, and without any external shock or vibration. Current and power requirement is defined as the averaged value for 40 ea after running the drives for 5 minutes at the active idle status.

2) Operating mode: 40%,40%,and 20% duty for seek, RD/WR, and idle, respectively.

3) Active idle mode: spindle motor is spinning and heads are in random track location. Drive can process the next command without delay.

4) Random seek mode : 30% duty cycle seek for random logical location.

5) Read/Write: Averaged RMS current or power for a continuous read or write of a consecutive 256 sectors on a single physical track with typical host command overhead. Read or write operation should be done for the same logical location and thus the read or write duty should be less than 25%.

6) Standby: Microprocessor is powered, heads are parked, and spindle motor is stopped. Drive responds to all commands. (*) stands for slumber mode.

7) Sleep: Microprocessor is powered for minimal block, heads are parked, spindle motor is stopped. Drive responds only to hard/soft reset commands. (*) stands for slumber mode.

3.6 Environmental Specifications

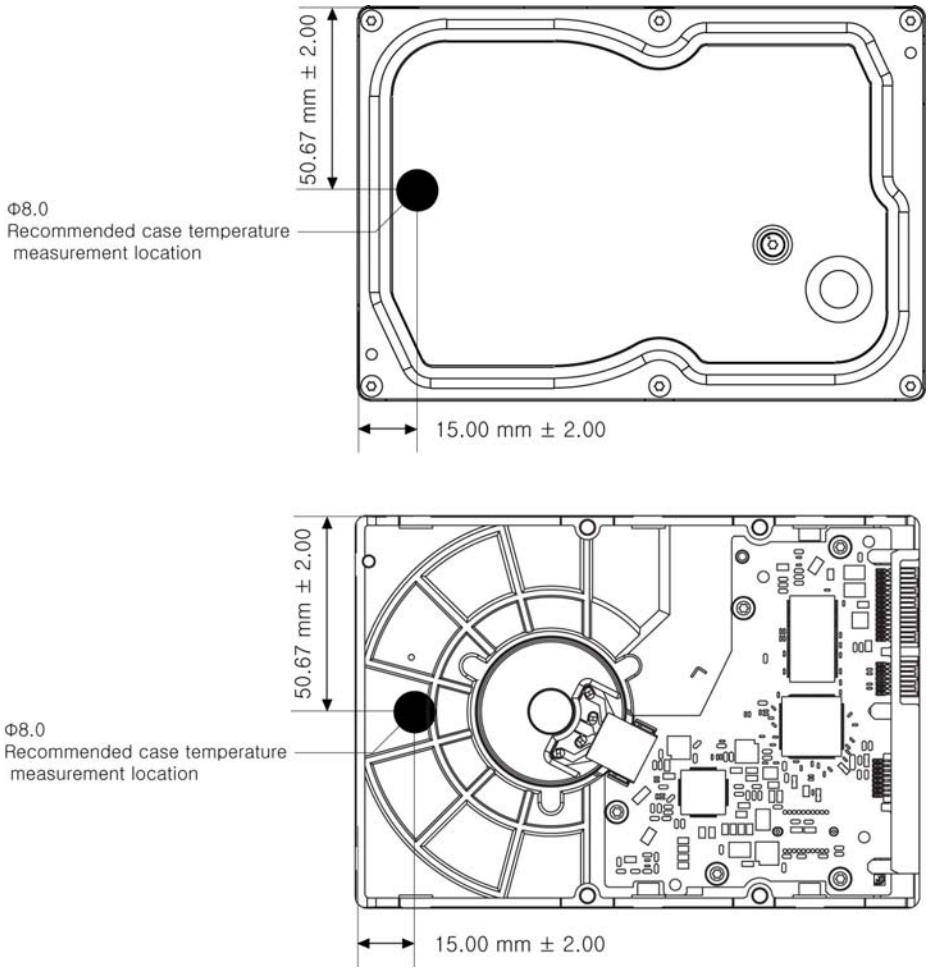
Table 3-6 Environmental Specifications

DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Ambient Temperature: Operating [1] Non-operating Max. gradient (Temp/Humidity)	0 ~ 60°C -40 ~ 70°C 20°C/15%/hr					
Relative Humidity (non condensing) Operation Non-operation	5~90 % 5~95 %					
Maximum wet bulb temperature: Operating Non-operating	30° C 40° C					
Altitude (relative to sea level): Operating Non-operating	-1,000 ~ 10,000 feet -1,000 ~ 40,000 feet					
Vibration Operating Random 10-300Hz Non-operating Random 10-500Hz	1.08 Grms 3.80 Grms					

Environmental Specifications (continued)

DESCRIPTION		STSHD253GI / STSHD085GJ / STSHD164GJ / ST160DM000 STSHD254GJ / ST250DM001 / STSHD324HI / ST500DL001 STSHD324HJ / ST320DM001 / ST500DM005 / ST1000DL004 STSHD754JI / ST1000DM005 / STSHD754JJ	
Shock (1/2 sine pulse)			
Operating			
2.0 ms		70G	
Non-operating			
2.0 ms		300G	
0.5 ms		200G	
10 ms		150G	
Rotational Shock			
Operating			
2.0 ms		2Krad/sec	
Non-operating			
2.0 ms		20Krad/sec	
1.0 ms		25Krad/sec	
Acoustic Noise	Sound Power (typ/Max$_n$)	5400rpm STSHD253GI / STSHD085GJ STSHD324HI / ST500DL001 ST1000DL004 / STSHD754JI	7200rpm STSHD164GJ / ST160DM000 STSHD254GJ / ST250DM001 STSHD324HJ / ST320DM001 ST500DM005 / STSHD754JJ ST1000DM005
	Idle	2.2/2.5	2.5/2.7
	Performance Seek	2.7/2.8	2.8/2.9
	Quiet seek	2.8/2.9	2.9/3.1

1) The drive case temperature should be lower than 69°C in an operating ambient condition.


50.67 mm ± 2.00
Φ8.0
Recommended case temperature
measurement location
15.00 mm ± 2.00
50.67 mm ± 2.00
Φ8.0
Recommended case temperature
measurement location
15.00 mm ± 2.00

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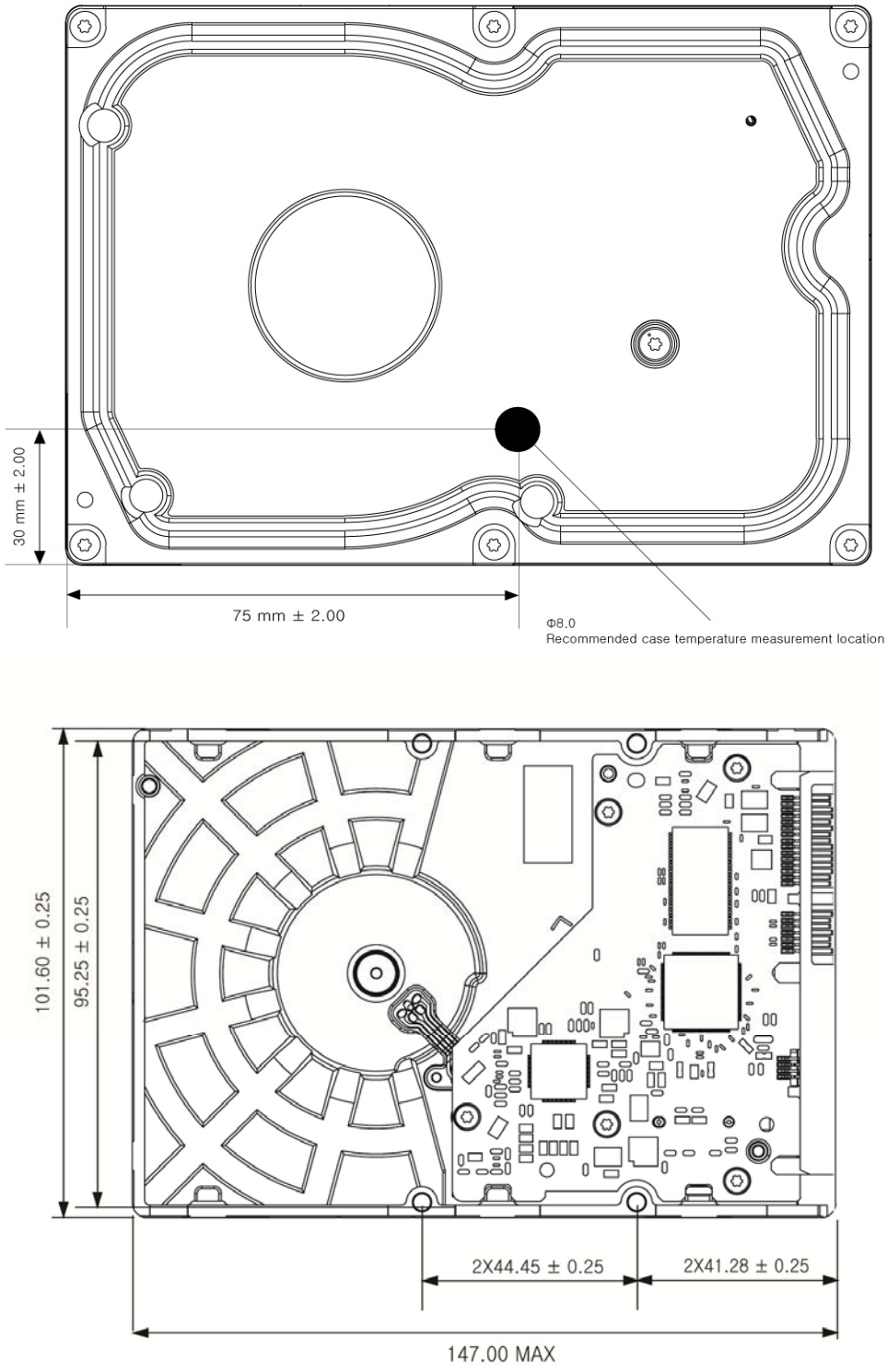

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Figure 3-1 Case Temperature Measurement Point

3.7 Reliability Specifications

Table 3-7 Reliability Specifications

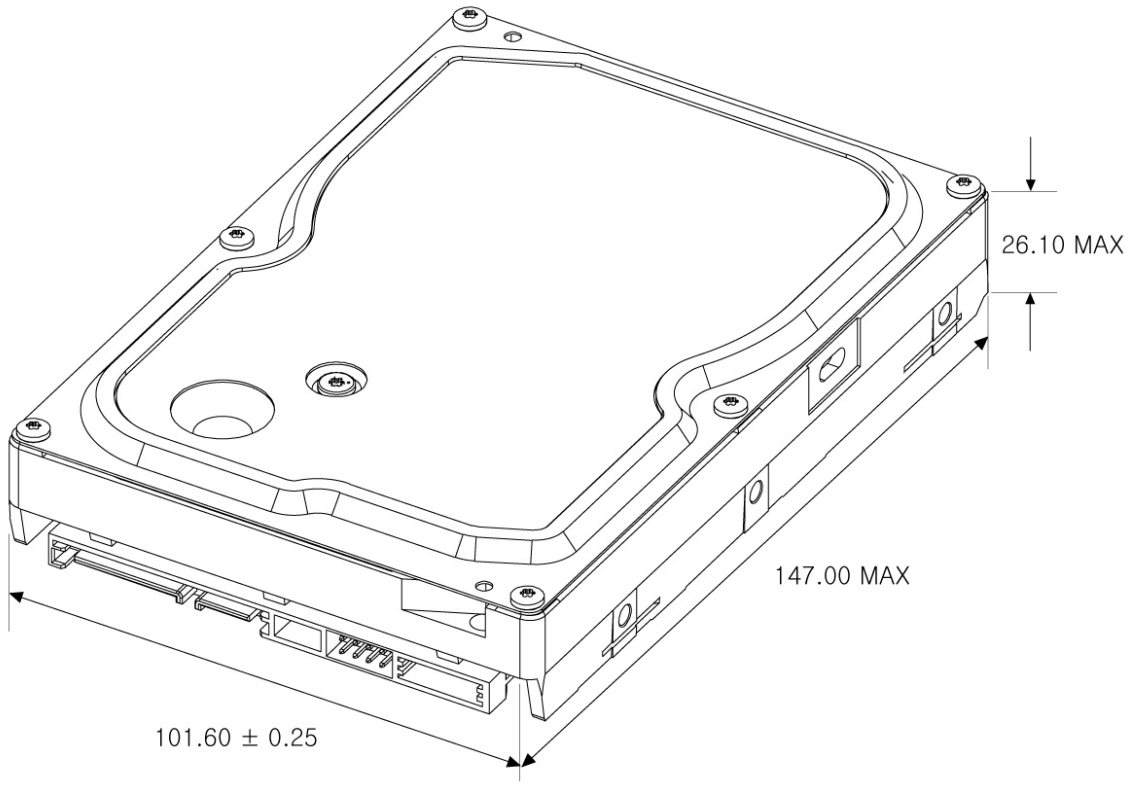
DESCRIPTION	STSHD253GI	STSHD085GJ STSHD164GJ ST160DM000 STSHD254GJ ST250DM001	STSHD324HI ST500DL001	STSHD324HJ ST320DM001 ST500DM005	ST1000DL004 STSHD754JI	ST1000DM005 STSHD754JJ
Recoverable Read Error:	<10 in 10^{11} bits					
Non-Recoverable Read Error:	<1 sector in 10^{15} bits					
MTBF (POH):	600,000 hours					
MTTR (typical):	5 minutes					
Start/Stop Cycle : Ambient	50,000					

CHAPTER 4 INSTALLATION

This chapter describes how to unpack, mount, configure, and connect a Barracuda hard disk drive. It also describes how to install the drive in systems.

4.1 Space Requirements

Figure 4-1 shows the external metric dimensions of the SATA HDD.



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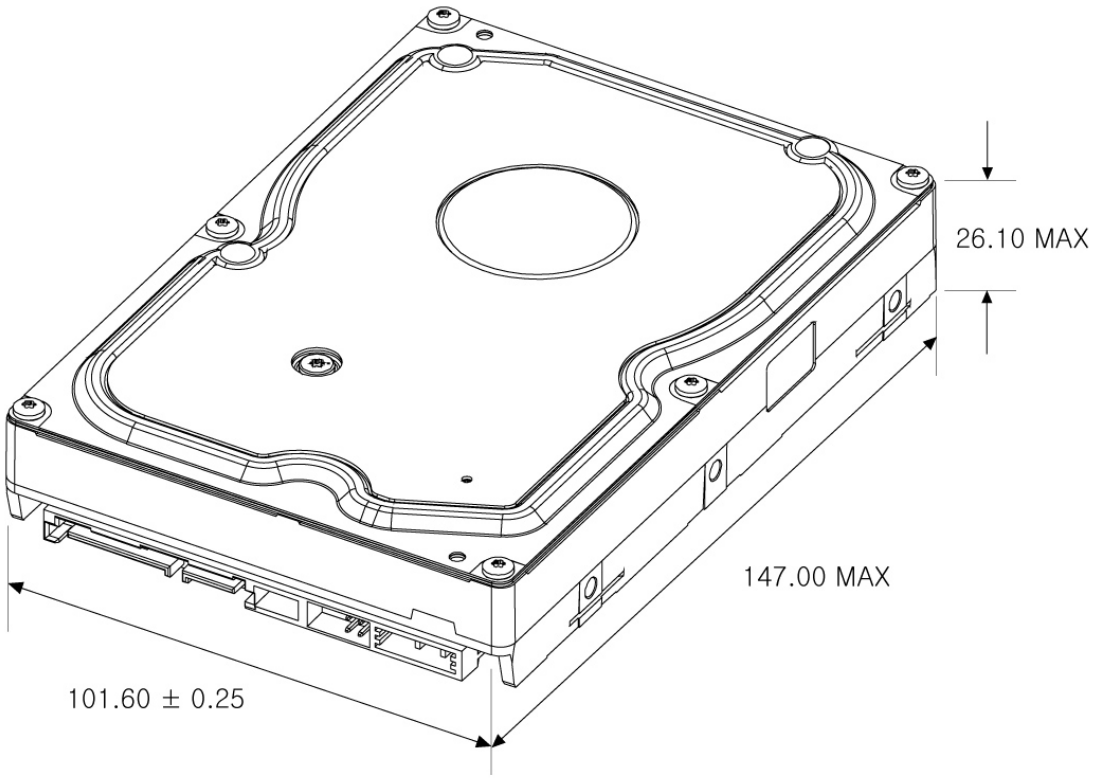


< 2D >

Figure 4-1 Mechanical Dimension

4.2 Unpacking Instructions

(1) Open the shipping container of Barracuda .

(2) Lift the packing assembly that contains the drive out of the shipping container.

(3) Remove the drive from the packing assembly. When you are ready to install the drive, remove it from the ESD (Electro Static Discharge) protection bag. Take precautions to protect the drive from ESD damage after removing it from the bag.

> **CAUTION:** During shipment and handling, the anti-static ESD protection bag prevents electronic component damage due to electrostatic discharge. To avoid accidental damage to the drive, do not use a sharp instrument to open the ESD protection bag.

(4) Save the packing material for possible future use.

4.3 Mounting

Refer to your system manual for complete mounting details.

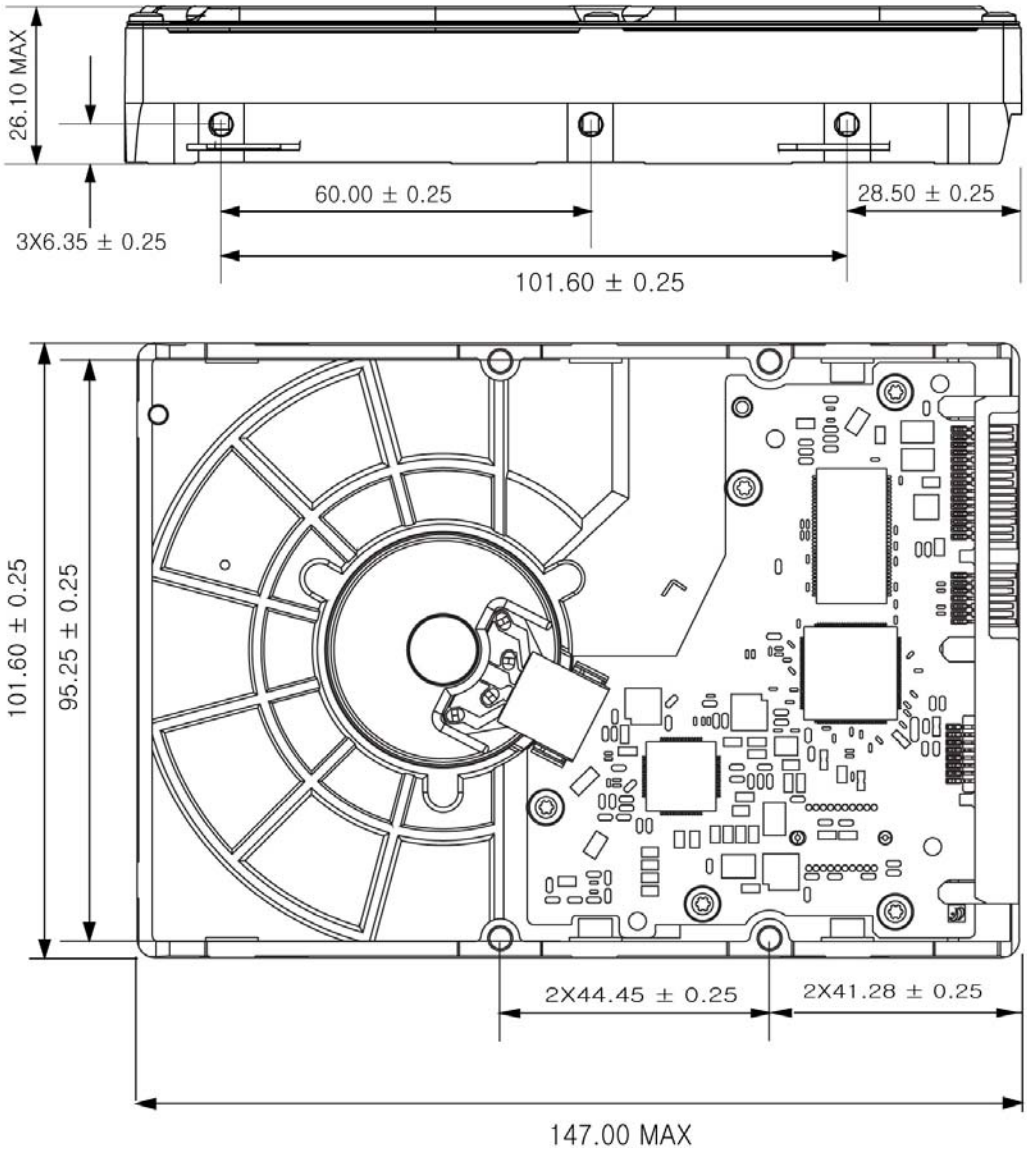
(1) Be sure that the system power is off.

(2) For mounting, use four 6-32 UNC screws.

> **CAUTION***:* To avoid stripping the mounting-hole threads, the maximum torque applied to the screws must not exceed 8.0 Kg-cm (6.95 inch-pounds).

4.3.1 Orientation

Figure 4-2 shows the physical dimensions and mounting holes located on each side of the drive. The mounting holes on Barracuda hard disk drive allows the drive to be mounted in any direction.


26.10 MAX
3X6.35 ± 0.25
60.00 ± 0.25
28.50 ± 0.25
101.60 ± 0.25
101.60 ± 0.25
95.25 ± 0.25
2X44.45 ± 0.25
2X41.28 ± 0.25
147.00 MAX

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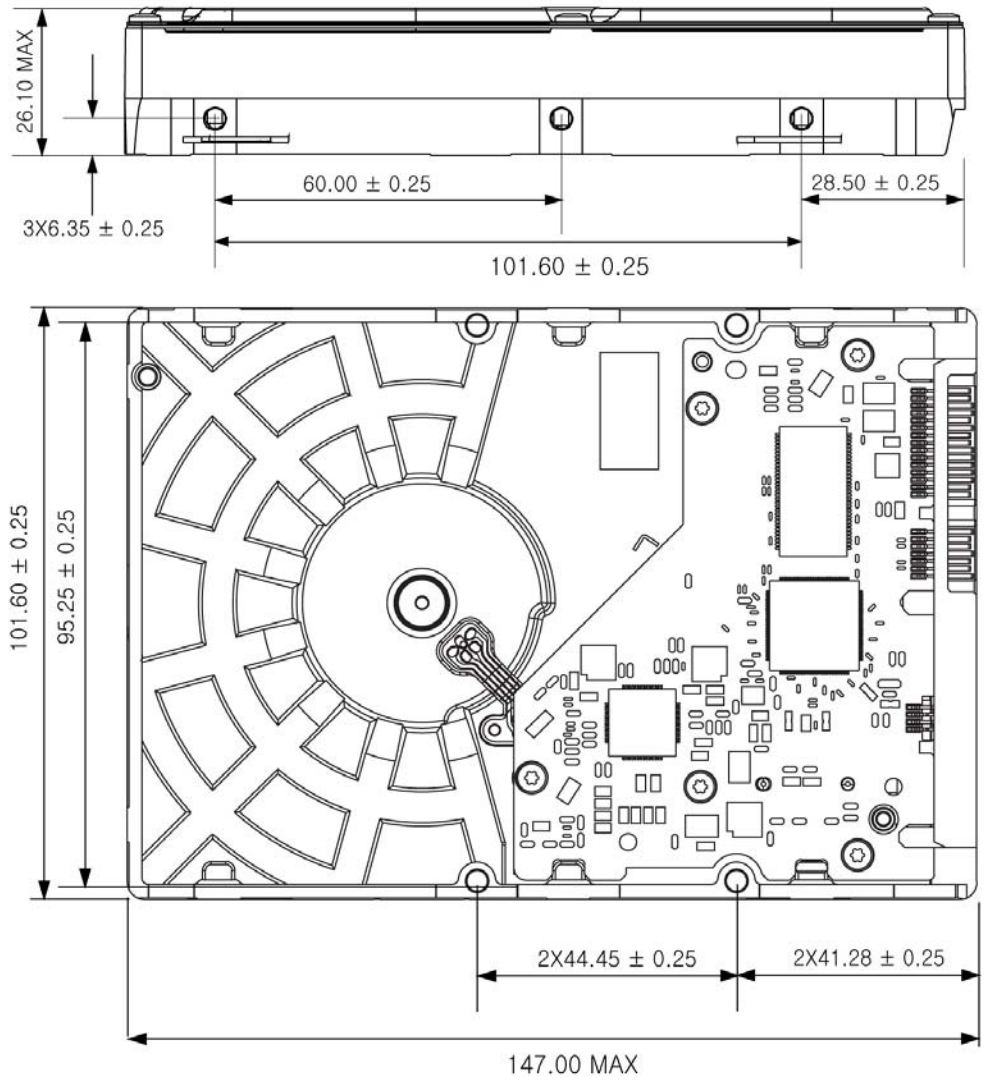
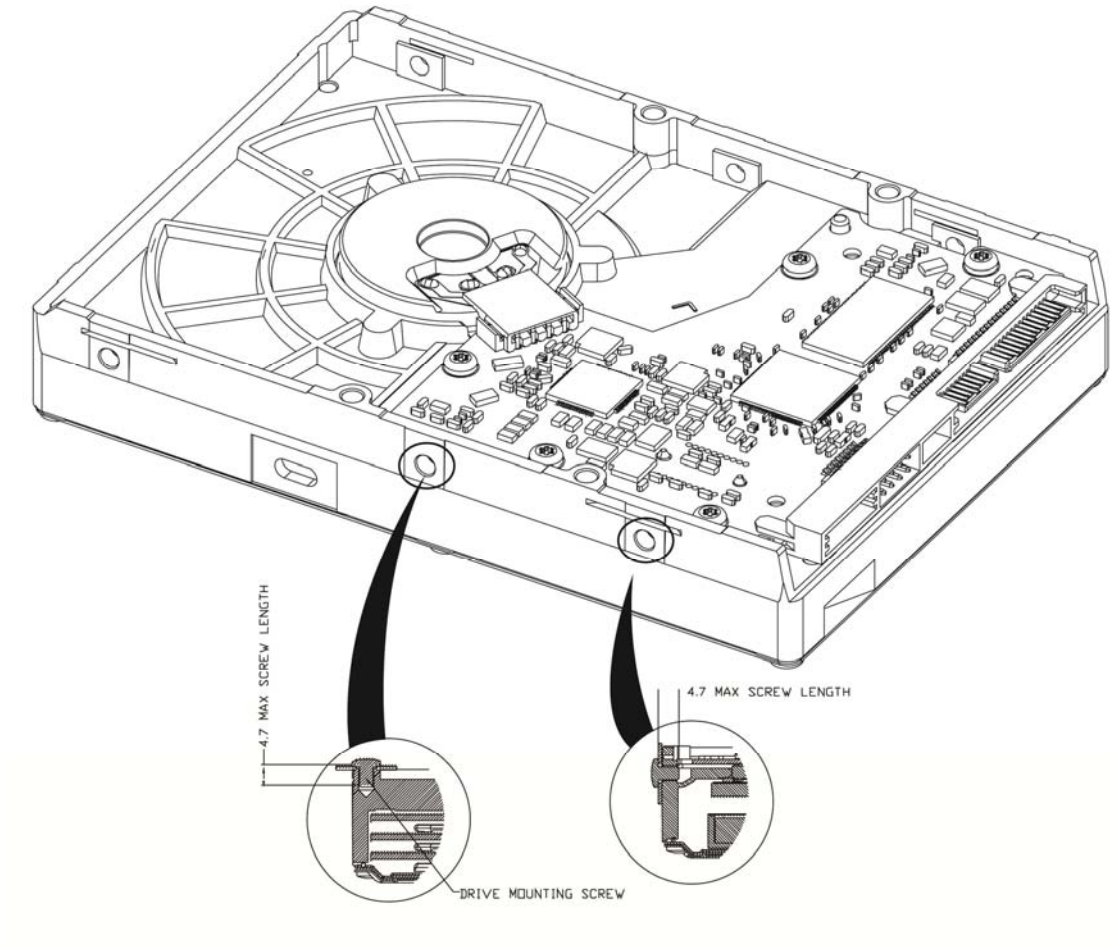


< 2D >

Figure 4-2 Mounting Dimensions

4.3.2 Clearance

The printed circuit board (PCB) is designed to be very close to the mounting holes. Do not exceed the specified length for the mounting screw described in Figure 4-3. The specified screw length allows full use of the mounting-hole threads, while avoiding damage or placing unwanted stress on the PCB.



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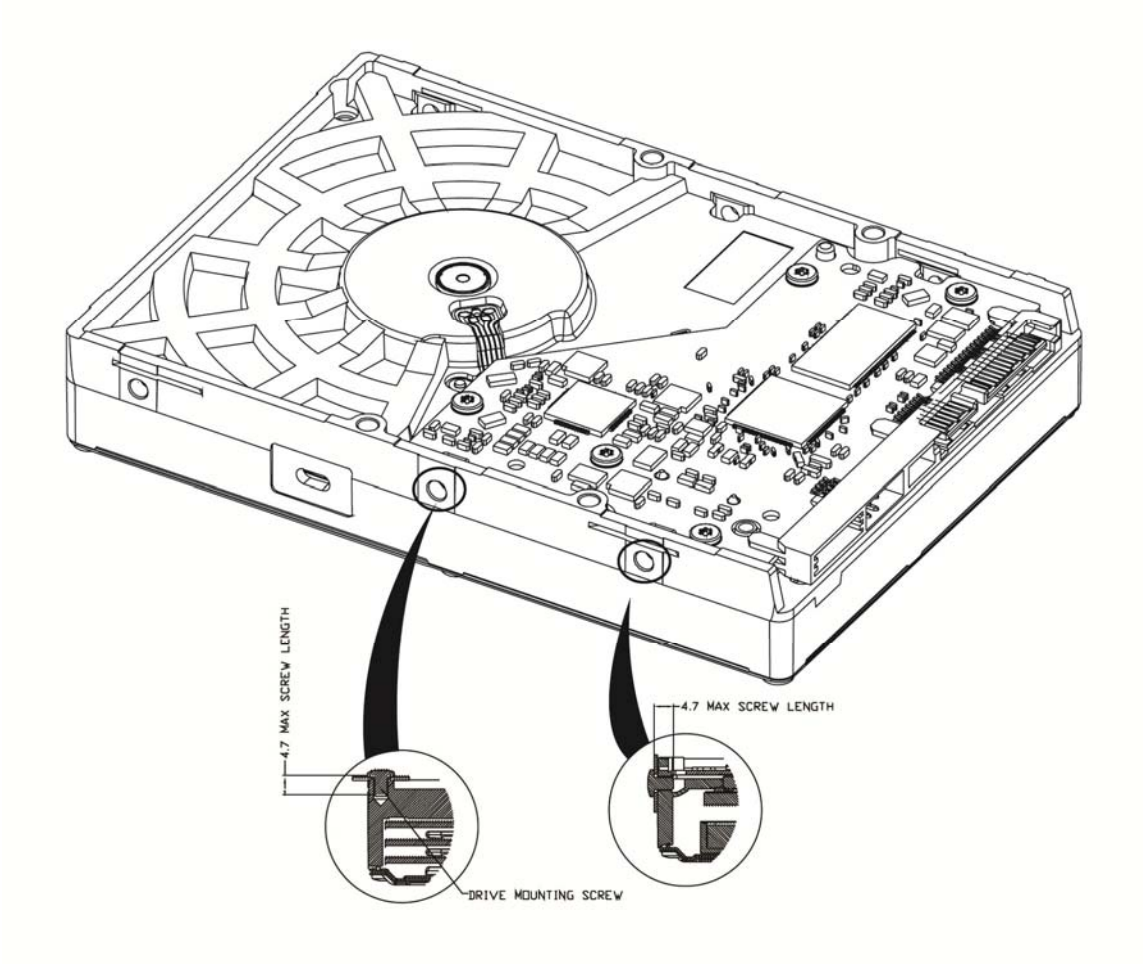

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Figure 4-3 Mounting-Screw Clearance

CAUTION: Using mounting screws that are longer than the max lengths specified in Figure 4-3 voids the warranty of the drive.

4.3.3 Ventilation

Barracuda hard disk drive is designed to operate without the need of a cooling fan provided the ambient air temperature does not exceed 60ºC. Any user-designed cabinet must provide adequate air circulation to prevent exceeding the maximum temperature.

4.4 Cable Connectors

The Interface/Power connector consists of two cables; a SATA 15-pin DC power connector, and the standard SATA 7-pin Interface connector.

4.4.1 SATA Connectivity

The SATA interface is connected with in a point to point configuration with the SATA host port. There is no master or slave relationship within the devices. Thus SATA does not require master/slave jumper. The drive interface section of the host adapter employs a new design which processed data into a serial data-control system.

Figure 4.4 illustrates the connection for the SATA.
There are two cables for SATA drives. One is for data transmission. The other is for power. Figure 4-4 illustrates (a) device signal plug connector, (b) device power plug connector, (c) signal cable receptacle connector mating with (a), and (d) power cable receptacle connector to be mated with (b). For more information, please refer to SATA Specifications cited in the reference.

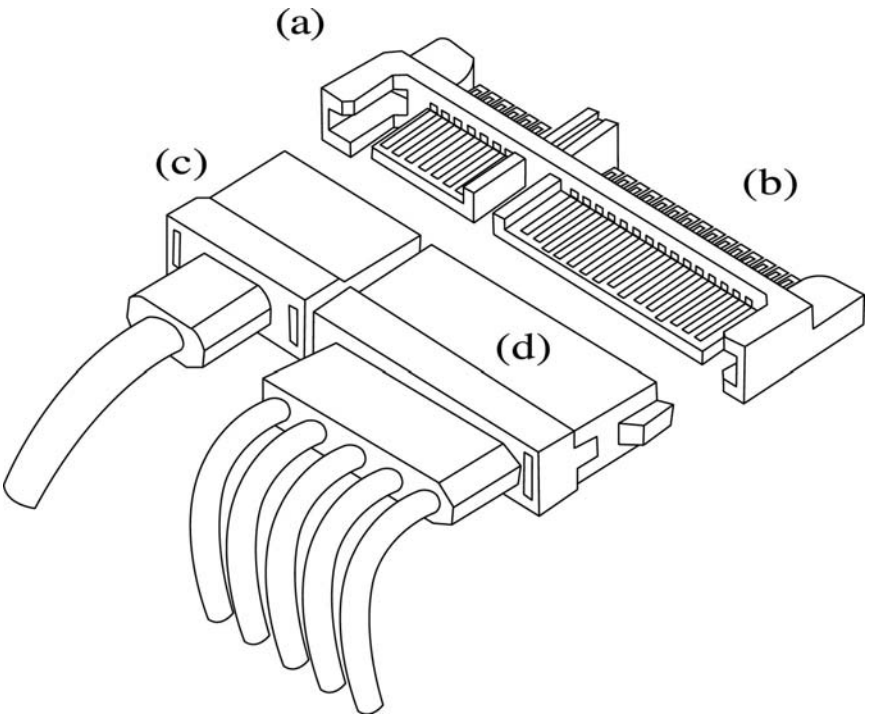


Figure 4-4 Serial ATA Connector

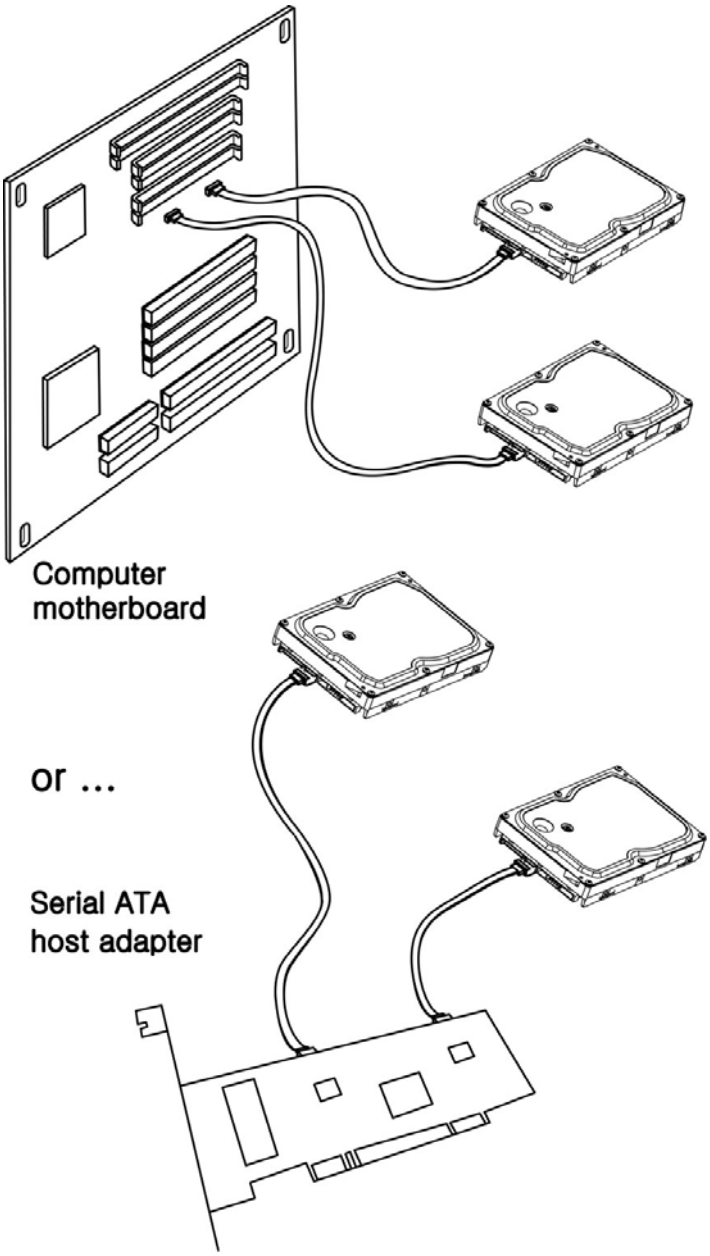


Figure 4-5 Connectivity to Drives

Figure 4-5 illustrates Connectivity of SATA to drives. It can be used with a SATA host bus adapter (lower picture) or directly into motherboard that has the SATA built-in host bus adapter (upper picture).

4.5 SATA Device Connector Definition

Please note that all pins are in a single row, with a 1.27 mm (50 mil) pitch diameter. There are three power pins for each voltage source. One pin from each voltage is utilized for pre-charge when installed in a blind-mate backplane configuration.

The notes on the mating sequence apply to the case of backplane blind mate connector.

When the drive is inserted, the ground pins and the pre-charge pins are in contact first followed by the remaining pins.

Table 4-1 lists the signals connection on the SATA interface and power connector. It is based on SATA 1.0a Specifications. Note that pin numbers is designated from the pin farthest from power segment.

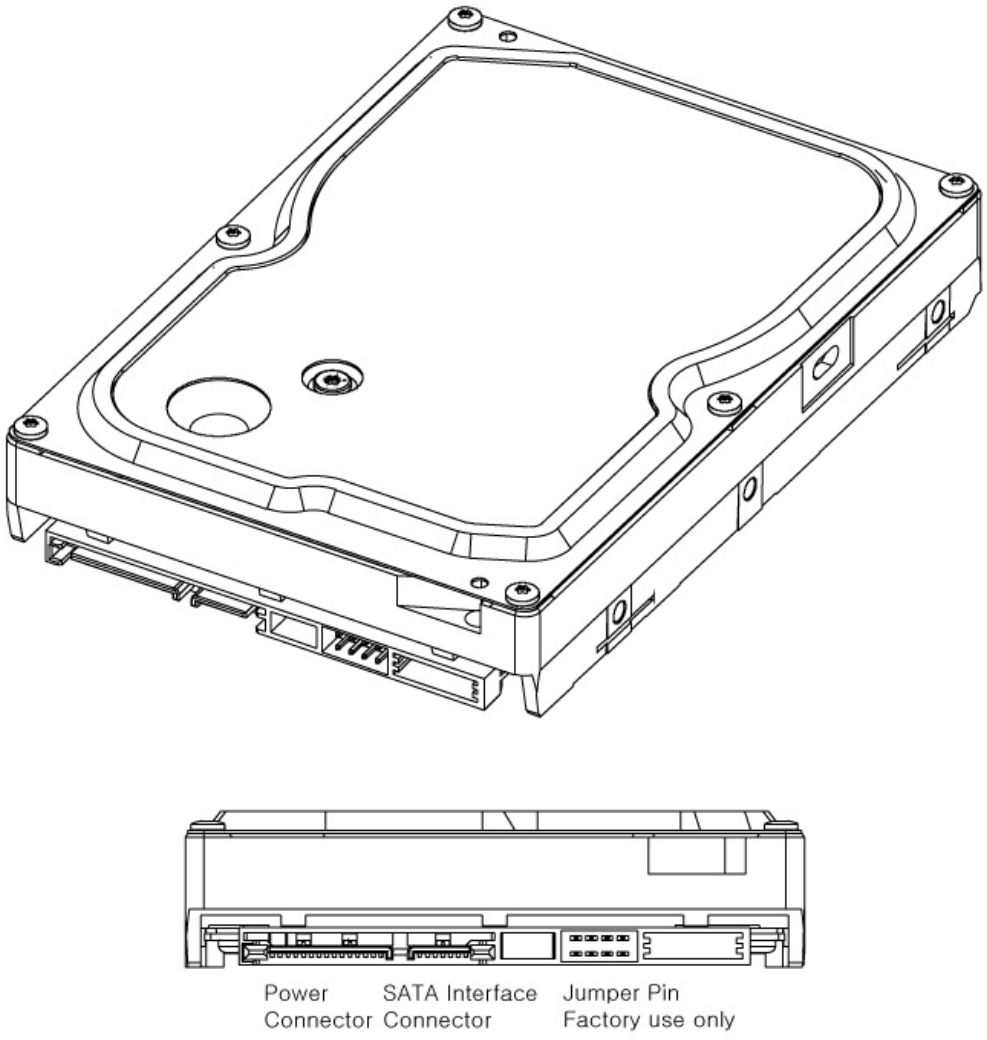
Table 4-1 SATA Connector Pin Definitions

Data Signal Connector	Pin	Function	Definition
	*S1	Ground	Ground
	S2	Rx+	Differential Signal pair
	S3	Rx-	Differential Signal pair
	*S4	Ground	Ground
	S5	Tx-	Differential Signal Pair
	S6	Tx+	Differential Signal pair
	*S7	Ground	Ground
	Key and spacing separate signal and power segment		
Power Management	P1	V_{33}	3.3 v
	P2	V_{33}	3.3 v
	*P3	V_{33}	3.3 v
	*P4	Ground	Ground
	*P5	Ground	Ground
	*P6	Ground	Ground
	*P7	V_5	5 v
	P8	V_5	5 v
	P9	V_5	5 v
	*P_{10}	Ground	Ground
	P_{11}	Device Activity / Stagger Spin-up Control	This pin was reserved in SATA 1.0a
	*P_{12}	Ground	Ground
	*P_{13}	V_{12}	12 v
	P_{14}	V_{12}	12 v
	P_{15}	V_{12}	12 v

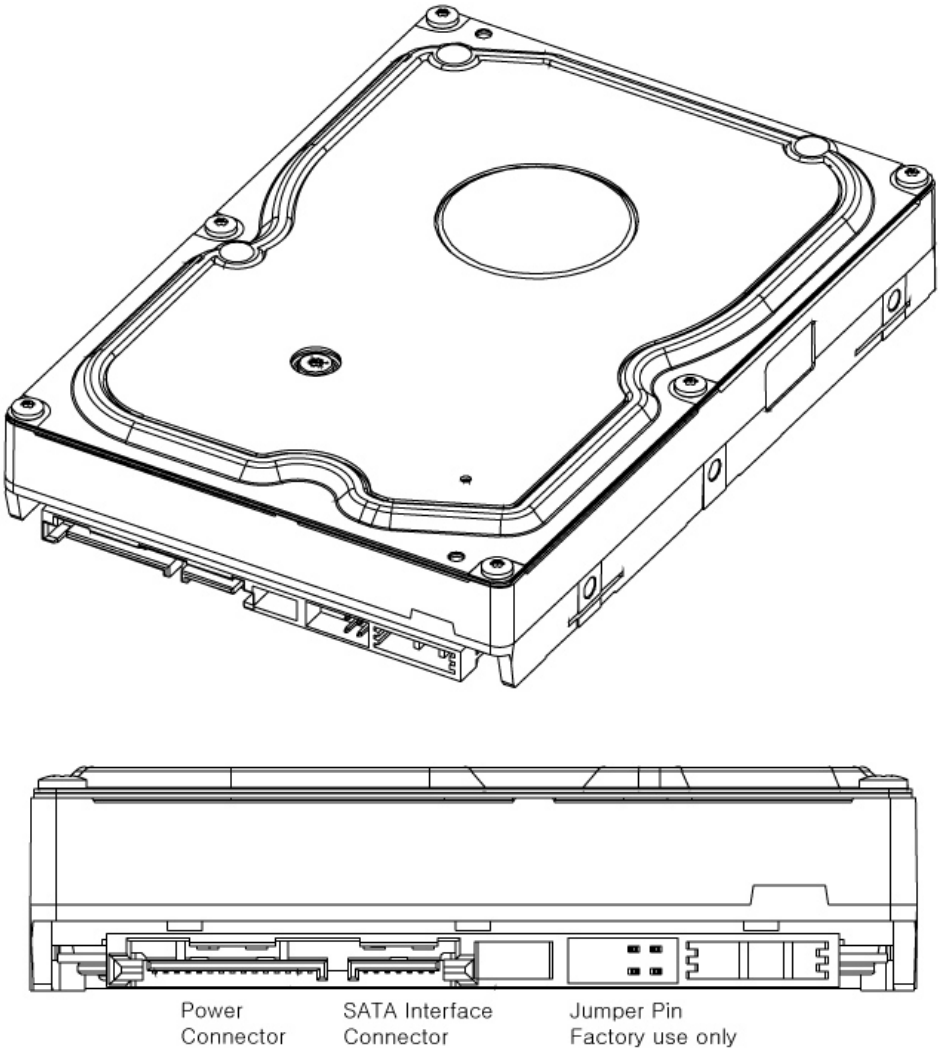
* First Mate

4.6 SATA-Bus Interface Connector

The SATA-Bus interface connector on the drive connects the drive to an SATA host bus adapter or an on-board SATA adapter in the computer. Figures 4.6 illustrates the power, SATA, and factory use only jumper.



< 1D >



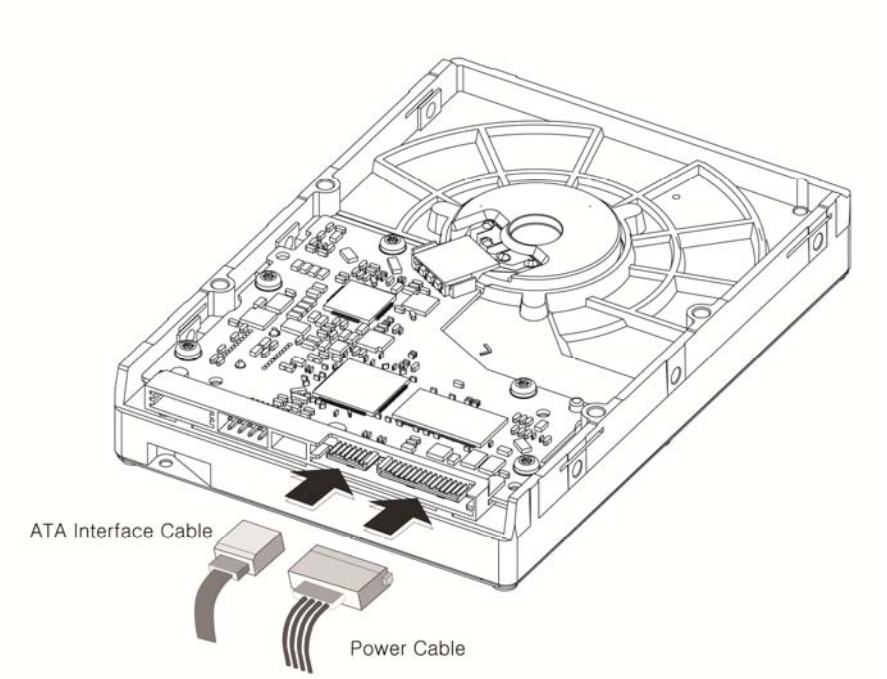
< 2D >

Figure 4-6 HDD Power, SATA Interface, and Factory Jumper Connector

4.7 Drive Installation

The Barracuda hard disk drive can be installed in a SATA compatible system.

Figure 4-7 indicates the interface and power cable connections required for proper drive installation.



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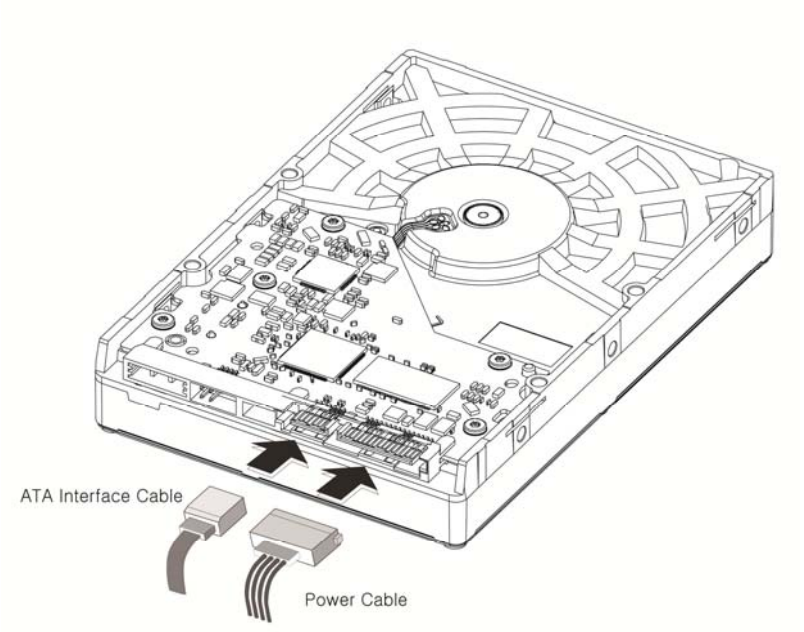


< 2D >

Figure 4-7 DC Power Connector and SATA-Bus Interface Cable Connections

CHAPTER 5 DISK DRIVE OPERATION

This chapter describes the operation of the Barracuda functional subsystems. It is intended as a guide to the operation of the drive, rather than a detailed theory of operation.

5.1 Head / Disk Assembly (HDA)

A Barracuda hard disk drive consists of a mechanical sub-assembly and a printed circuit board assembly (PCBA), as shown in Figure 5-1. This section describes the mechanism of the drive.

The head / disk assembly (HDA) contains the mechanical sub-assemblies of the drive, which are sealed between the aluminum-alloy base and cover. The HDA consists of the base casting assembly (which includes the spindle motor assembly), the disk stack assembly, the head stack assembly, and the rotary voice coil motor assembly (which includes the actuator latch assembly). The HDA is assembled in a clean room. These subassemblies cannot be adjusted or field repaired.

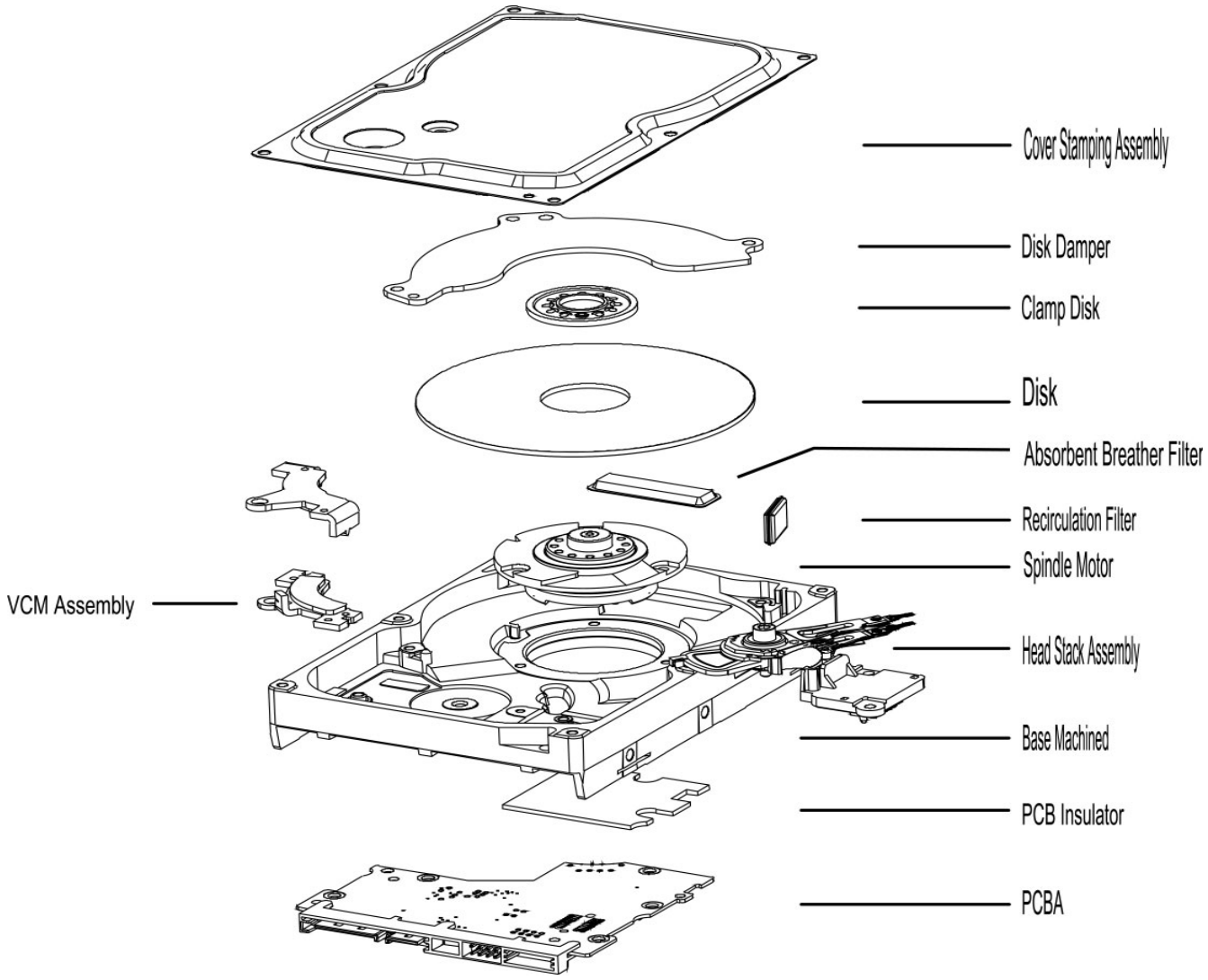
> **CAUTION:** To avoid contamination in the HDA, never remove or adjust its cover and seals. Disassembling the HDA voids your warranty**.**

5.1.1 Base Casting Assembly

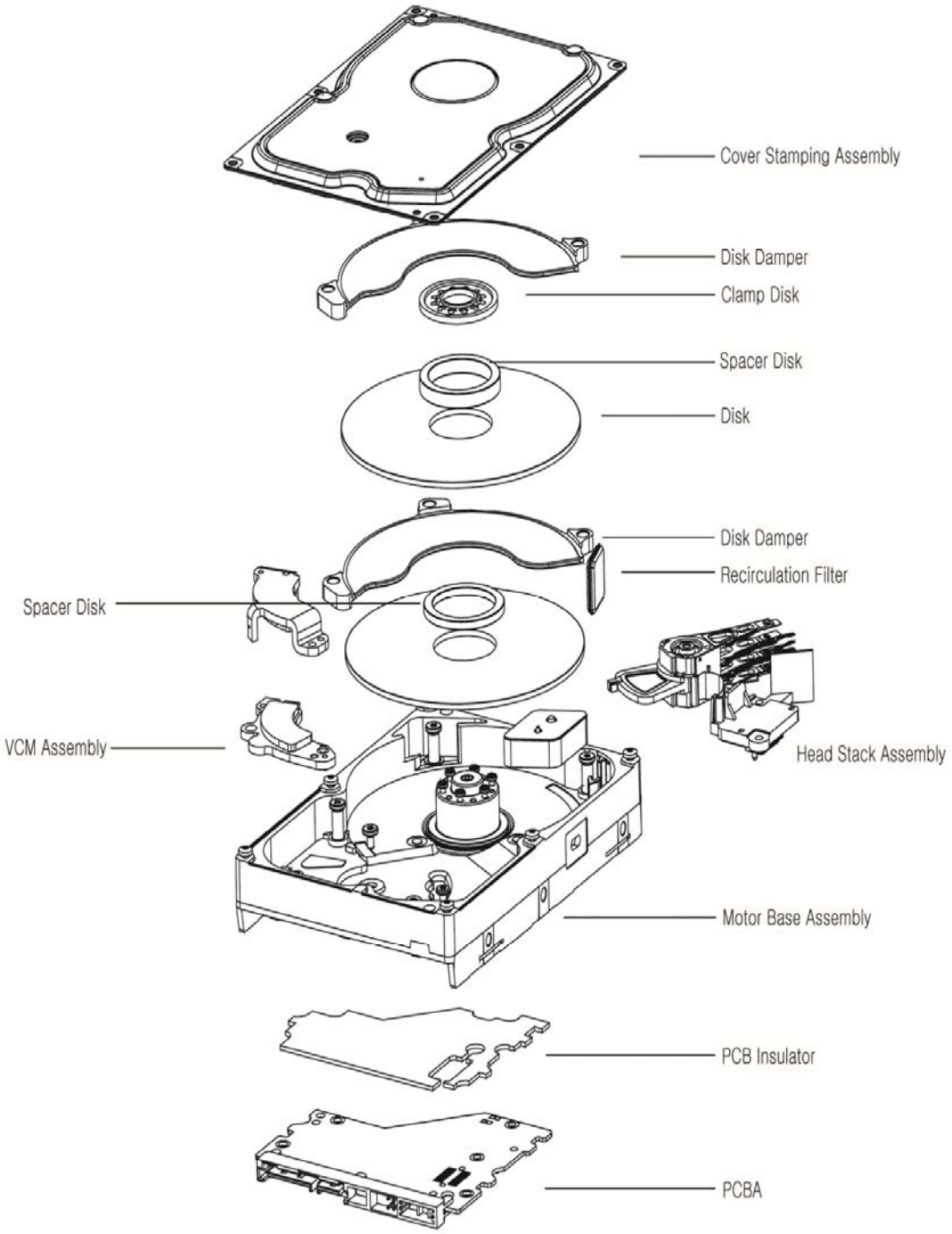
A one piece, aluminum-alloy base casting provides a mounting surface for the drive mechanism and PCBA. The base casting also serves as the flange for the spindle motor assembly. A gasket provides a sealant between the base and cover castings that enclose the drive mechanism. It keeps contaminant from entering the air stream of the disk enclosure.

5.1.2 Spindle Motor Assembly

The spindle motor assembly consists of a three-phase brushless motor, fluid dynamic bearing (FDB) assembly, and a disk mounting hub. The entire spindle motor assembly is completely enclosed in the HDA and fastened to the base casting. The drive motor rotates the spindle with disk attached shaft at around 5,425 /7234 RPM. Decelerating is accomplished through dynamic braking.


Cover Stamping Assembly
Disk Damper
Clamp Disk
Disk
Absorbent Breather Filter
Recirculation Filter
Spindle Motor
VCM Assembly
Head Stack Assembly
Base Machined
PCB Insulator
PCBA

< 1D >



< 2D >

Figure 5-1 Exploded View of Barracuda HDD

5.1.3 Disk Stack Assembly

The disk stack assembly in the Barracuda hard disk drive consists of 1 or 2 disks and its respective spacers secured on the hub of the spindle motor assembly by a disk clamp. It can contain two or four recording heads. The aluminum-alloy disks are plated with a Ni-P for corrosion resistance reason. The magnetic films are sputtered with different films of magnetic alloys. On the adjacent surface the manufacturers apply a thin film of carbon to prevent damage resulting in data loss. To minimize wear, the media are also dipped with lubricant and anti-wetting agent.

The data band is never touched by the recording heads or any component of the HDD. A dedicated zone serves as runway for the flying recording sliders during power up and power down. Once approaching a critical speed the heads are flying over the media. Until the powering up sequence is completed the actuator with heads flying over are then permitted to move to data zone.

5.1.4 Head Stack Assembly

The head stack assembly consists of recording head or heads stacked on an assembly consisting of an aluminum block and coil assembly. The voice coil which energizes a magnetic force with two magnets is pivoted around a ball bearing. The E-block/coil sub-assembly is an integral part of a machined block with an over-molded coil. Sliders containing read/write transducers are suspended on a stainless steel flexure(s) that are secured through a unique swaging process onto the E-block arms.

The flexible circuit transmits electrical signal during read or write connects the read/write heads with the PCBA via a connector through the base casting. Since the signals are very low in amplitude it gets amplified as close to the transducer with a first stage amplifier (Preamp) on circuit.

5.1.5 Voice Coil Motor and Actuator Latch Assemblies

The rotary voice coil motor consists of upper and lower permanent magnets and magnetic yokes fixed to the base casting and a rotary over-molded coil on the head stack assembly. Each magnet consists of two alternating poles and is attached to the magnet yoke. Rubber crash stops mounted on the over-molded coil and a magnetic yoke physically prevent the head(s) from moving beyond the designed inner boundary into the spindle or off the disk surface.

Accessing of the actuator between OD-ID-OD positions on the disk is accomplished by applying coil current surge from - to + then - which results in a magnetic force allowing a push-pull motion during actuation process.

5.1.6 Air Filtration System

Heads fly at a fraction of a millionth of an inch above the disk surface. Therefore, it is of utmost importance that the disk enclosures are not opened by unauthorized person or allowing air leakage through defective filter, seal etc. Seagate HDAs are prepared in the state of the art super clean room environment with all parts super-cleaned. To sustain this stringent clean air environment, the Barracuda is equipped with a high efficiency re-circulating filter which is located in the path of the airflow close to the rotating disk and is designed to trap any particles that might exist inside HDA.

5.2 Drive Electronics

Barracuda drive attain their intelligence and performance through the specialized electronic components mounted on the PCBA. The components are mounted on one side of the PCBA.

The Preamplifier IC is the only electrical component that is mounted on the flexible circuit inside the HDA. Move the Preamplifier close to the read/write transducer allows higher electrical output of electronics.

5.2.1 Digital Signal Process and Interface Controller

The processor used in the Barracuda is a 16-bit digital signal processor (DSP), with a bus controller unit (BCU), an interrupt controller unit (ICU), a general purpose timer (GPT), and SRAM.

5.2.2 Disk Controller

The Disk Controller works in conjunction with the DSP to perform the ATA interface control, buffer data flow management, disk format/read/write control, and error correction. The DSP communicates with the Disk Controller module by reading from and writing to its various internal registers.

To the DSP, the registers of the Disk Controller appear as unique memory or I/O locations that are randomly accessed and operated upon. By reading from and writing to the registers, the DSP initiates operations and examines the status of the different functional blocks. Once an operation is started, successful completion or an error condition may cause the Disk Controller to interrupt the DSP, which then examines the status registers and determines an appropriate course of action. The DSP may also poll the device to ascertain successful completion or error conditions.

The following illustrates a block diagram of DSP and Disk Controller. In the diagram (see Figure 5-2) it illustrates between the various blocks within the Disk Controller. These blocks will be referred to throughout this document.

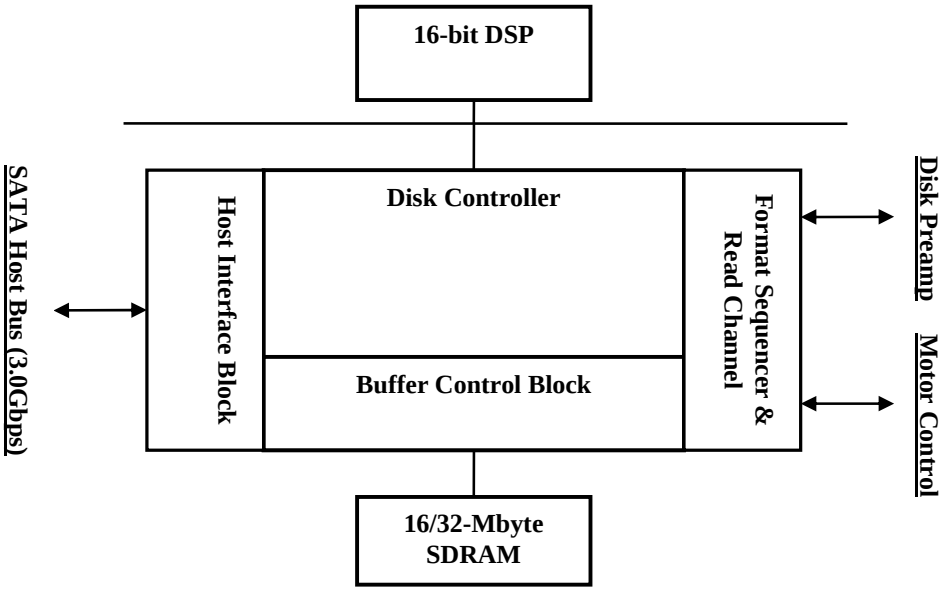


Figure 5-2 Barracuda Functional Block Diagram

5.2.2.1 The Host Interface Block

The SATA Disk Controller provides direct interface to an SATA bus. It is compatible with ATA 7 Specs. It provides a means for the host to access the Task File registers used to control the transfer of data between host memory and the disk drive.

The SATA Host Interface Block can be programmed to execute various host read/write commands either completely automatically without any DSP intervention, semi-automatically with minimal DSP intervention, or manually with the aid of the DSP.

The Disk Controller has significant advances in ATA automation. The highlights of ATA automation includes:

- Automatic data transfer management for multi-sector Read/Write commands without DSP intervention.
- Automatic execution of read commands (Auto-Read command execution) for cached data in the buffer by matching the first sector.
- Automatic Task File registers updates during automatic multi-sector transfers.
- Automatic NCQ queue tag validation

The Barracuda supports PIO, DMA, and FPDMA data transfers. The supported DMA type transfers include multi-word (MWDMA) and synchronous Ultra DMA (UDMA) transfers. The bus emulates automatically switched between 16- and 8-bit mode while performing Read Long and Write Long commands at the time of ECC byte transfers.

Additional functionality is provided in the Host Interface Block by the following features:

- Programmable transfer length for automatic ECC byte transfer on the AT bus.
- Support of both LBA and CHS Task File registers formats.
- Automatic detection of both the Software Reset and COMRESET.
- Support for PIO modes 0 through 4.
- Support for multiword DMA modes 0 through 2. Support for synchronous DMA (UDMA) transfer mode 0 through 7. (Mode 7 is referring to 150 MB/S)
- Support for First Party DMA (FPDMA) for NCQ commands.

The Buffer Control block manages the flow of data into and out of the buffer. Significant automation allows buffer activity to take place automatically during read/write operations between the host and the disk. This automation works together with automation of the Host Interface and Disk Control blocks to provide more efficient data transfer between host and disk without DSP interventions.

The Buffer Control block keeps track of buffer full and empty conditions and automatically works with the Disk Control block to stop transfers to or from the disk when necessary. In addition, transfers to or from the host are automatically stopped or started based on buffer full or empty status.

Additional functionality is provided in the Buffer Control block through the following features:

- A disk sector counter that can monitor the transfers between the disk and buffer.
- Read/Write cache support.

5.2.2.2 The Disk Control Block

The Barracuda Disk Control block manages flow of data between disk and buffer. It is capable of performing completely automated track read and write operations at a maximum data rate of 1 Gbps in NRZ data mode. Many flexible features and elements of automation have been incorporated to complement the automation contributed by the Host and Buffer blocks.

The Disk Control block consists of the programmable sequencer (Disk Sequencer), Constant Density Recording (CDR)/data split logic, disk FIFO, fault tolerant sync detect logic, and other support logic.

The programmable sequencer contains a 31-by-4 byte programmable SRAM and associated control logic, which is programmed by the user to automatically control all track format, read, and write operations. From within the sequencer micro program, the Disk Control block can automatically deal with real time functions such as defect skipping, servo burst data splitting, branching on critical buffer status and data compare operations. Once the Disk Sequencer is started, it executes each word in logical order. At the completion of the current instruction word, it either continues execute the next instruction or jumps to some other instruction based upon an internal or external condition having been met, or stops.

During instruction execution or while stopped, registers can be accessed by the DSP to obtain status information reflecting the Disk Sequencer operations taking place.

5.2.2.3 The Disk ECC Control Block

The Disk Control block supports a programmable Reed-Solomon ECC. The code is capable of correcting up to 36 bytes , or if correcting with erasure pointer up to 72 bytes. Error detection and correction is handled in the Disk Control block. Automatic on-the-fly hardware correction will take place for up to 32 bytes. Correction is guaranteed to complete before the ECC Field of the sector following the sector where the error occurred utilizing standard ATA sector size. An added feature of the Barracuda ECC block is the ability to log corrected ECC errors for error reporting. To add the data correction capability a 10-bit permuted ECC that supports high rate RLL is implemented. The user data is first encoded before the ECC is added. This will allow the ECC correction be more effectively working on the data directly coming from the media.

5.2.2.4 Power Management

Power management features are incorporated into each functional block of the Barracuda. This allows the host to control the amount of power of the specific power save states. Other power management features include:

- Independent power management control for each block.
- DSP block can be powered down and up when needed.
- Disk Sequencer and associated disk logic powered up when the Disk Sequencer is started.
- Weak pull-up structure on input pins to prevent undesirable power consumption due to floating CMOS inputs.

5.2.3 Read/Write Circuit

The Read/Write Channel control circuit provides read/write-processing functions for the drive. The Read/Write circuit receives the RD GATE and WR GATE signals, write data, and servo AGC and gates from the Disk Format Sequencer. The Read/Write Channel sends decoded read data and the read reference clock to the Disk Format Sequencer.

The Barracuda has an embedded Read Channel designed in the SOC. The Read Channel is a sampled-data digital PRML channel designed to work with the Disk Controller and read/write Preamplifier to provide the signal processing elements required to build a state of the art high density, high speed disk drive. The Read Channel block implements a Trellis-coded noise predictive PRML read channel (supporting) zone-bit recording which stores more bits on the outer disk radius.

5.3 Servo System

The Servo System controls the precise position of the read/write heads to keep them on “track”. The Servo System also compensates for write/read head offsets and thermal drifts, disk fluttering and run-out (i.e. track mis-registration or TMR), and external vibration. The Barracuda has an Embedded Sector Servo System. Positioning information is radially located in evenly spaced servo sectors on each track.

Radial position information can be provided from these sectors for each data head. Because the drive incorporates multiple data zones and each zone has a different bit density, split data fields are necessary for optimal use of the non-servo area of the disk. The servo area remains phase-coherent across the surface of the disk, even though the disk has various data zones. The main advantage of the Embedded Sector Servo System is that it eliminates the problems of static and dynamic offsets between heads on different surfaces.

The Barracuda Servo System is classified as a digital servo system because track-following and seek control, bias cancellation, and other typical tasks are done in a Digital Signal Processor (DSP).

The Servo system has three modes of operation: track-following mode, settle mode, and trajectory based control mode.

1. Track-following mode is used when heads are "on-track." This is a position loop with an integrator in the compensation.
2. Settle mode is used for all accesses; head switches, short-track seeks and long-track seeks. Settle mode is a position loop with velocity damping. Settle mode does not use feed forward.
3. Trajectory based control mode is used for acceleration and deceleration of the actuator for seeks of one or more tracks. A seek operation of this length is accomplished with a combination of position & velocity control loop as well as acceleration feed-forward. The trajectories are calculated by DSP using a pre-determined seek time according to the seek length.

5.4 Read and Write Operations

The following two sections describe the read and write data path.

5.4.1 The Read Path

The drive has one read/write head for each of the data surfaces. The signal flow for the read path starts at the read/write heads. When the magnetic flux transitions recorded on a disk pass under the head, they generate low-amplitude, differential voltages. The read/write head transfers these signals to the flexible circuit's amplifier, which amplifies the signal.

The flexible circuit transmits the pre-amplified signal from the HDA to the PCBA. The EPRML channel on the PCBA shapes, filters, detects, synchronizes, and decodes the data from the disk. The channel then sends the resynchronized data output to the Disk Format Sequencer.

The Disk Controller manages the flow of data between the Disk Format Sequencer and SATA Host Interface Block. It also controls data access for the external DRAM buffer. The Disk Sequencer module identifies the data as belonging to the target sector. After a full sector is read, the Disk Format Sequencer checks to see if it needs to apply an ECC correction to the data. The Buffer Controller manages the location of data to be stored in the DRAM buffer. Once the data buffer is full, the Buffer Manager sends signal to stop further data transfer.

The SATA Host Interface Block retrieves data from the DRAM buffer to the host. In response to a host request, the Host Interface Controller delivers data based on the transfer mode that host requested, such as PIO, DMA, or FPDMA. The DSP along with the intelligent controller firmware will manage the caching algorithm of the drive.

5.4.2 The Write Path

The signal path for the write path follows the reverse order of that for the read path. The host transmits data via the SATA bus to the SATA Interface Control block. The Buffer Controller section stores the data in the buffer and stops the data transfer if buffer is full. Because the data is transmitted to the drive at a rate that is different from the rate the drive can write data to the disk media, data is stored temporarily in the DRAM

buffer. Thus, the host can present data to the drive at a rate independent of the rate at which the drive can write data to the disk.

Upon correct identification of the target address, the data is sent to the Disk Format Sequencer, which encodes and generates an error correcting code appended to the data. The Disk Format Sequencer then converts the data to a serial bit stream. The Sequencer also generates a preamble field, inserts an address mark, and transmits the data to the ENDEC in the R/W circuit where the data is encoded into the 30/32 GCR format and pre-compensates for non-linear transition shift. The amount of write current is programmed by firmware to the preamp.

The firmware programs the Preamplifier Write Data Driver to write mode and select head. Once the Preamplifier and Write Data Driver receive a write gate signal, it transmits current reversals to the head, which generates magnetic transitions on the medium.

5.5 Firmware Features

This section describes the following firmware features:

- Read Caching
- Write Caching
- Defect Management
- Automatic Defect Allocation
- SMART (Self-monitoring and reporting technology)
- AAM (automatic Acoustic Management)

5.5.1 Read Caching

The Barracuda hard disk drive uses 16MB/32MB DRAM buffer to enhance drive performance and significantly improve system throughput. Use the SET FEATURES command to enable or disable Read Caching. Read caching anticipates host-system requests for data and stores that data for faster access in the future. When the host requests a certain segment of data, the cache firmware utilizes a pre-fetched strategy to place the additional data in advance and store the subsequent data into buffer RAM. Should the host requests this information; the data can be transferred immediately. There is a high likelihood that subsequent data is requested. Typically 50% of all disk requests are sequential. It is much faster to send data directly from DRAM buffer to host.

Read Caching stores the data in the buffer in multiple segments. The internal caching algorithm determines when to store and to clear the cache data depending upon the buffer data access history. This intelligent caching management allows the Barracuda improve performance for the application program.

The cache memory consists of an 16MB/32MB of SDRAM allocated to hold the cache data. The unit of data stored is in logical blocks; a multiple of 512-byte sectors. The following commands will void the cache information:

- IDENTIFY DRIVE (0ECh)
- FORMAT TRACK (050h)
- EXECUTE DRIVE DIAGNOSTIC (090h)
- READ LONG (023h)
- WRITE VERIFY (03Ch)
- INITIALIZE DEVICE PARAMETER (091h)

- SLEEP (099h, 0E6h)
- STANDBY IMMEDIATELY (094h,0E0h)
- READ BUFFER (0E4h)
- WRITE BUFFER (0E8h)

5.5.2 Write Caching

Write caching improves write performance by reducing delays introduced by rotational latency. When the host writes a pattern of multiple sequential data, the firmware stores the data to the cache buffer and responds with COMMAND COMPLETE to the host before it writes the data to the disk. The data is then written collectively to the drive; thereby minimizing the disk rotational latency.

If the host writes a pattern of random location, the data is stored in the buffer first. The write command posts COMMAND COMPLETE immediately when all of the write data of the command are transferred to the buffer.

If a defective sector is detected on the medium during a write, the sector is relocated in the write event. This ensures that cached data gets written properly. If the sector can not be relocated, the drive exits write caching and reports the error as "ID Not Found." If the write command of the error sector is still active, the error is reported during that command. Otherwise the drive will not continue to operate until next power cycle.

5.5.3 Defect Management

The Barracuda media is scanned for magnetic defects based on signal drop outs. After defect scanning, the defective sectors are contained in the defect list. Magnetic defects detected in the manufacturing burn-in test process will be skipped. The defected sector will be replaced by the next physical sector location. All logical sector numbers are then maintained in a sequential order with the defective areas mapped out.

5.5.4 Automatic Defect Allocation

The automatic defect allocation feature automatically maps out defective sectors encountered during normal read sector or write sector operations, after the factory burn-in test process. These types of defective sectors are typically called by grown defects because they are grown additions to the drive. During write operations, if write errors are encountered, all sectors within the target servo frame are mapped out. Original data is transferred and written into designated reserved sector areas (reassigned) determined by the HDD firmware.

5.5.5 SMART

The intent of **Self-Monitoring, Analysis and Reporting Technology** (SMART) is to protect customer data integrity and to report the condition and status of the drive. Users can interpret the SMART data to determine the health state of the drive. By monitoring and storing critical performance and calibration parameters, SMART allows users to predict the potential possibility of near-term degradation or fault condition. Providing the host system knowledge of a negative reliability condition allows the host system to alert the user of the impending risk of a potential data integrity and advise the user of appropriate action.

5.5.6 AAM

The **Automatic Acoustic Management** (AAM) is a feature which automatically allows the Barracuda to operate in one of several acoustic noise levels. This provides the user with the selecting of the desired level of acoustic noise emanating from the HDD electro-mechanical parts. Lower noise operating levels can be attained by degrading performance. When the feature is disabled, the HDD returns to optimum performance and normal but higher acoustic noise level. This feature is controlled through the Set Features command.

CHAPTER 6 SATA II INTERFACE

6.1 Introduction

The Barracuda disk drive is equipped with an industry standard SATA Interface fully supports and enhances PC mass storage requirements. The SATA interface conforms to the Serial ATA standards in Cabling, in Physical Signals, and in Logical Programming schemes. The Barracuda disk drive joins the industry premiere VLSI circuitry with ingenious programming skill that does not compromise performance or reliability. Seagate integrates and delivers the cutting edge in technology. Seagate Barracuda SATA class disk drives are designed to relieve and to enhance the I/O request processing function of system drivers.

6.1.1 SATA Terminology

The following contains some commonly proposed terminology used in SATA technology.

BACKCHANNEL-A term used to describe or refer to the transmit same-side of SATA interface, when the scope of the paragraph is addressing the receive interface. For example, when discussing the receive SATA interface on the device side, the term "backchannel" would be used to describe the transmit interface on the device side.

CHARACTER ALIGNMENT-Character alignment is a receiver action that resets the character boundary to that of the comma sequence found in the K28.5 control character of the ALIGN primitive, and establishes Dword synchronization of the incoming serial data stream.

CHARACTER SLIPPING-Character slipping is the receiver action that realigns the receiver's clock to the received bit stream by adding or removing bit times within the characters of the ALIGN primitive.

CODE VIOLATION-A code violation is an error that occurs in the reception process as a result of (1) a running disparity violation or (2) an encoded character that does not translate to a valid data or control character or (3) an encoded character that translates to a control character other than K28.5 or K28.3 in byte 0 of a Dword or (4) an encoded character that translates to any control character (valid or invalid) in bytes 1-3 of a Dword.

COMMA CHARACTER-A comma character is a control character, that when encoded, contains the comma sequence. In Serial ATA the only comma character used is K28.5, and only the ALIGN primitive contains the comma character. The comma sequence is the first seven bits of the encoded character.

COMMA SEQUENCE-The comma sequence is a seven-bit sequence of 0011111 or 1100000 in an encoded stream. The comma sequence is unique in that it appears only in a single encoded character, and furthermore, cannot appear in any subset of bits in adjacent encoded characters. This unique property allows the comma sequence to be used for determining alignment of the received data stream.

COMRESET / COMINIT-Host: Signal from the out of band detector that indicates the COMINIT out of band signal is being detected.

CONTROL CHARACTER-A control character is a combination of a byte value with the control variable equal to K.

CONTROL VARIABLE-The control variable, Z, is a flag that determines the code set to be used to interpret a data byte. The control variable has the value D (for data characters) or K (for control characters).

CRC-In Serial ATA a 32-bit CRC is calculated over the contents of a FIS. The Serial ATA CRC is the Dword in a frame that immediately precedes the EOF primitive.

DATA CHARACTER-A data character is a combination of a byte value with the control variable equal to D.

DWORD-A Dword is thirty-two (32) bits of data. A Dword may be represented as 32 bits, as two adjacent words, or as four adjacent bytes. When shown as bits the least significant bit is bit 0 and most significant bit is bit 31. The most significant bit is shown on the left. When shown as words the least significant word (lower) is word 0 and the most significant (upper) word is word 1. When shown as bytes the least significant byte is byte 0 and the most significant byte is byte 3.

DWORD SYNCHRINIZATION-The state in which a receiver has recognized the comma sequence and is producing an aligned data stream of Dwords (four contiguous bytes) from the zero-reference of the comma character.

ENCODED CHARACTER-An encoded character is the output of the 8b/10b encoder – the result of encoding a character. An encoded character consists of 10 bits, where bit 0 is the most significant bit and bit 9 is the least significant. The bits in an encoded character are symbolically referred to as "*abcdeifghj*" where "a" corresponds to bit 0 and "j" corresponds to bit 9.

ELASTICITY BUFFER-The elasticity buffer is a portion of the receiver where character slipping and/or character alignment is performed.

FIRST PARTY DMA ACCESS-First-party DMA access is a method by which a device accesses host memory.

FIRST PARTY DMA MODE (FPDMA)- A device which is operating in First-party DMA mode uses First-party DMA as a primary communications method between the host and the device. A software driver uses legacy mode commands to place the device into First-party DMA mode of operation. The legacy-mode command to place the device into the First-party DMA mode of operation and the command protocol used between a device and host when in First-party DMA mode are not specified by this specification.

FIRST DATA PHASE- The FPDMA Data Phase is the period from the reception of a DMA Setup FIS until either the exhaustion of the associated data transfer count or the assertion of the ERR bit in the shadow Status register.

FIS-Stands for Frame Information Structure.

FRAME UNFIORMATION STRUCTURE-The user payload of a frame, does not include the SOF, CRC, and EOF delimiters.

Frame-A frame is an indivisible unit of information exchanged between a host and device. A frame consists of a SOF primitive, a Frame Information Structure, a CRC calculated over the contents of the FIS, and an EOF primitive-

LEGACY MODE-Legacy mode is the mode of operation which provides software-*transparent communication of commands* and status between a host and device using the ATA Command Block and Control Block registers.

LEGAL CHARACTER-Legal character is one for which there exists a valid decoding, either into the data character or control character fields. Due to running disparity constraints not all 10-bit combinations result in a legal character. Additional usage restrictions in Serial ATA result in a further reduction in the SATA defined control character space.

OOB SIGNAL DETECTOR-This block decodes Out of Band signal from the high speed input signal path.

PRIMITIVE-A primitive is a single Dword of information that consists of a control character in byte 0 followed by three additional data characters in bytes 1-3.

SHADOW REGISTER BLOCK REGISTERS-Shadow Register Block registers are interface registers used for delivering commands to the device or posting status from the device.

SQUELCH-This block establishes a limit so that detection of a common mode signal can be properly accomplished.

WORD-A word is sixteen (16) bits of data. A word may be represented as 16 bits or as two adjacent bytes. When shown as bits the least significant bit is bit 0 and most significant bit is bit 15. The most significant bit is shown on the left. When shown as bytes the least significant byte (lower) byte is byte 0 and the most significant byte (upper) byte is byte 1.

6.2 Physical Interface

For information please consult the document entitled "Serial ATA Revision 2.5" released on October 27, 2005 available from the Internet http://www.sata-io.org/ still retrievable on May 11, 2006. Section 7 of the document contains physical layer specifications related topics.

6.3 Signal Summary

For details, please consult the document entitled "Serial ATA Revision 2.5" released on October 27, 2005 available from the Internet http://www.sata-io.org/ still retrievable on May 11, 2006.

6.3.1 Signal Descriptions

For data packets and additional information please consult the document entitled "Serial ATA Revision 2.5" released on October 27, 2005 available from the Internet http://www.sata-io.org/ still retrievable on May 11, 2006.

A device can operate in either of two addressing modes, CHS or LBA, on a command-by-command basis. The CHS mode is supported for legacy command access only. The task file registers contains the Cylinder, Head, and Sector information of a requested location. Because the disk drive has its own mapping, the CHS mode is translated into disk drive physical address by the HDD firmware. There is no direct relationship of the CHS that can be accessed from the host.

This CHS term defines the addressing mode of the device as being by physical sector address. The physical sector address is made up of three fields: the sector number, the head number and the cylinder number. Sectors are numbered from 1 to a device specific maximum value, which cannot exceed 255. Heads are numbered from 0 to a device specific maximum value, which cannot exceed 15. Cylinders are numbered from 0 to a device specific maximum value, which cannot exceed 65,535. Typically, sequential access to the media is accomplished by treating the sector number as the least significant portion, the head number as the mid portion, and the cylinder number as the most significant portion of the CHS address.

In LBA mode the sectors on the device are assumed to be linearly mapped with an initial definition of: LBA 0 = (Cylinder 0, head 0, and sector 1). Irrespective of translate mode geometry set by the host, the LBA address of a given sector does not change:

6.3.2 I/O Register - Address

The communication to or from drive is through the SATA interface. To the host system the SATA drive emulates a parallel ATA drive. As such, the following registers are not accessed directly host to drive. The registers are set through the Serial Interface.

The Control Block registers are used for drive control and to post-alternate status. I/O port function and its selection address are tabulated.

I/O registers

Command Block registers	
When read	**When written**
Data	Data
Error	Features Current Features Previous
Sector Count Current Sector Count Previous	Sector Count Current Sector Count Previous
LBA Low Current LBA Low Previous	LBA Low Current LBA Low Previous
LBA Mid Current LBA Mid Previous	LBA Mid Current LBA Mid Previous
LBA High Current LBA High Previous	LBA High Current LBA High Previous
Device	Device
Status	Command
Control Block registers	
Alternate Status	Device Control

6.3.3 Control Block Register Descriptions

6.3.3.1 Alternate Status Register (ex. 3F6h)

This register contains the same information as the Status register in the Command Block register. The only difference is that reading this register does not imply interrupt acknowledgment nor does it clear a pending interrupt.

7	6	5	4	3	2	1	0
BSY	DRDY	#	#	DRQ	Obsolete	Obsolete	ERR

NOTE: See 6.3.4.10 for definitions of the bits in this register.

6.3.3.2 Device Control Register (ex. 3F6h)

The bits in this register are as follows:

7	6	5	4	3	2	1	0
HOB	R	R	R	R	SRST	nIEN	0

- **HOB** is the High Order Byte used for host to access the Extended Registers in the 48-bit LBA mode
- **SRST** is the host software reset bit. The drive is held reset when this bit is set. If two disk drives are daisy chained on the interface, this bit resets both simultaneously.
- **nIEN** is the enable bit for the drive interrupts to the host. When nIEN=0, and the drive is selected, INTRQ is enabled through a tri-state buffer. When nIEN=1, or the drive is not selected, the INTRQ signal is in a high impedance state.
- **R** is for reserved

6.3.4 Command Block Register Descriptions

6.3.4.1 Data Register (Ex. 1F0h)

This 16-bit register is used to transfer data blocks between the device data buffer and the host. It is also the register through which sector information is transferred on a Format Track command. Data transfers may be either PIO or DMA.

6.3.4.2 Features Register and Feature Extended Register (Ex. 1F1h)

This register is command specific and used to enable and disable features of the interface (e.g., by the Set Features command to enable and disable caching). The Feature Extended Register contains the upper byte of the Feature Register.

6.3.4.3 Sector Number Register and Sector Number Extended Register (Ex. 1F3h)

In **CHS** mode this register contains the starting sector number for any disk data access for the subsequent command. The sector number is from 1 to the maximum number of sectors per track. In **LBA** mode this register contains bits 0-7 of the LBA. The Sector Number Extended Register is for bits 25-31 of the 48-bit LBA.
See the command descriptions for the contents of the register at command completion (whether successful or unsuccessful).

6.3.4.4 Error Register (Ex. 1F1h)

This register contains status from the last command executed by the drive or a Diagnostic Code.
At the completion of any command except Execute Drive Diagnostic, the contents of this register are valid when ERR=1 in the Status register.

Following a power-on, a reset, or completion of an Execute Drive Diagnostic command, this register contains a Diagnostic Code.

7	6	5	4	3	2	1	0
#	#	#	#	#	ABRT	#	#

- **ABRT (Aborted Command)** indicates the requested command has been aborted due to a drive status error (Not Ready, Write Fault, etc.) or because the command code is invalid.
- # Indicates the content of this bit is command dependent.

NOTE: Unused bits are cleared to zero.

6.3.4.5 Sector Count Register and Sector Count Extended Register (Ex. 1F2h)

This register contains the number of sectors of data requested to be transferred on a read or write operation between the host and the drive. In 28-bit addressing, if the value in this register is zero, a count of 256 sectors is specified. In 48-bit addressing, the Sector Count Register is the low order byte of the 16-bit sector count value and the Sector Count Extended Register is the high order byte of the 16-bit sector count value.

If this register is zero at command completion, the command was successful. If not successfully completed, the register contains the number of sectors, which need to be transferred in order to complete the request.

The contents of this register may be defined otherwise on some commands (e.g., Initialize Drive Parameters command, Format Track command).

6.3.4.6 Cylinder High Register and Cylinder High Extended Register (Ex. 1F5h)

In **CHS** mode the Cylinder High Register contains the high order bits of the starting cylinder address for any disk access. In **LBA** mode the Cylinder High Register contains bits 16-23 of the LBA. The Cylinder High Extended Register contains bits 40-47 of the 48-bit LBA.

At the end of the command, this register is updated to reflect the current disk address. The most significant bits of the cylinder address are loaded into the Cylinder High register.

6.3.4.7 Cylinder Low Register and Cylinder Low Extended Register (Ex. 1F4h)

In **CHS** mode the Cylinder Low Register contains the low order 8 bits of the starting cylinder address for any disk access. In **LBA** mode the Cylinder Low Register contains bits 8-15 of the LBA. The Cylinder Low Extended Register contains bits 32-39 of the 48-bit LBA. At the end of the command, this register is updated to reflect the current disk address.

6.3.4.8 Command Register (Ex. 1F7h)

This register contains the command code being sent to the drive. Command execution begins immediately after this register is written. The executable commands, the command codes, and the necessary parameters for each command are listed.

6.3.4.9 Device Register (Ex. 1F6h)

This register contains the drive and head numbers. When executing an Initialize Drive Parameters command, the content of this register defines the number of heads minus 1.

7	6	5	4	3	2	1	0
Obsolete	LBA	Obsolete	DEV	#	#	#	#

- **DEV** is reserved.
- Bit0-bit3 is defined for the binary coded address of the head to be selected in **CHS** mode(e.g. if H3 through HS0 are 0011b, respectively, then head 3 will be selected). HS3 is the most significant bit. In 28 bit **LBA** mode bit0-3 HS3 contains bits 24-27 of the LBA. After command completion, this register is updated to reflect the currently selected disk address.

- **LBA** is to select the Logical Block Addressing Mode. When LBA=0, disk addressing is by **CHS** mode. When LBA=1, disk addressing is by **LBA** mode. This bit was set to zero when the ATA drive didn't support LBA mode.

6.3.4.10 Status Register (Ex. 1F7h)

This register contains the drive status. The contents of this register are updated at the completion of each command. When BSY is cleared, the other bits in this register become valid within 400 nsec. If BSY=1, no other bits in this register are valid. If the host reads this register when an interrupt is pending, it is considered to be the interrupt acknowledge. Any pending interrupt is cleared whenever this register is read.

7	6	5	4	3	2	1	0
BSY	DRDY	#	#	DRQ	Obsolete	Obsolete	ERR

- **BSY (Busy)** is set whenever the drive has access to the Command Block registers. The host should not access the Command Block registers when BSY=1. When BSY=1, a read of any Command Block register returns the contents of the Status register
- **DRDY (Drive Ready)** indicates that the drive is capable of responding to a command. When there is an error, this bit does not change until the host reads the Status register. Then the bit again indicates the current readiness of the drive. This bit clears at power-on and remains clear until the drive is ready to accept the command.
- **DRQ (Data Request)** indicates that the drive is ready to transfer a word or byte of data between the host and the drive.
- **ERR (Error)** indicates that an error occurred during execution of the previous command. The bits in the Error register have additional information regarding the cause of the error.

CHAPTER 7 SATA II FEATURE SET

This section describes the SATA II feature set supported in the Seagate Barracuda drive.

7.1 Device Activity Signal

Barracuda implemented the Device Activity Signal on the SATA power connector pin-11. The implementation is based on the SATA II specification. This activity signal is used for indicating the drive activities, including the queued and non-queued commands. For the host can use this signal to indicate the command activity.

7.2 Staggered Spin-up Disable Control

Barracuda implemented the staggered spin-up disable control by using the SATA power connector pin-11. This pin is multiplexed with the Device Activity Signal support. On power up this pin is used for the spin-up control. After the device is connected with the host, this pin is used for the Device Activity.

Before the device spins up its media, devices that support staggered spin-up disable control shall detect whether pin 11 is asserted low by the host. If pin 11 is asserted low the device shall disable staggered spin-up and immediately initiate media spin-up. If pin 11 is not connected in the host (floating), devices that support staggered spin-up disable through pin 11 shall enable staggered spin-up.

7.3 Auto-Activate in DMA Setup FIS

Barracuda implemented the option for the Auto-Activate in DMA Setup FIS. With this feature enabled, the DMA Setup FIS is automatically activated. This automation help improve the efficiency of the DMA data transfer. This feature can be enabled by the SATA Set Feature command.

If the Set Feature is not issued, the DMA Setup FIS is not automatically activated.

7.4 Native Command Queuing (NCQ)

Barracuda supports the NCQ feature of the SATA II command interface. The NCQ feature is unique in the SATA II implementation which helps device improve the system performance. The implementation is fully compliant with the SATA II specification.

The drive implements the NCQ with its proprietary hardware and firmware to enhance the command performance. The NCQ hardware automatically receives the NCQ commands from the host. The hardware verifies the duplication of the tag number and report tag duplicated error immediately. The automation of the hardware and firmware handles the NCQ command from its reception to the reordering and command execution. The drive intelligent firmware is capable of sorting the physical address of the incoming commands and decides the execution order for the best performance.

If the NCQ command is executed with error, the drive will report the error information from the Read Log Extended log page 10h. This is special log page for the NCQ command error reporting. The details of the error information are defined in the SATA II specification.

When the commands of queue and non-queue are mixed, the Barracuda drive will report command error. This will ensure the queue sequence is correctly received.

Two ATA commands are added for this NCQ support:

Read FPDMA Queued (60h)
Write FPDMA Queued (61h)

The Set Device Bits (SDB) FIS is also used for indicating the completed NCQ command(s). The bits in this FIS signify the completed tag. This SDB FIS is used for reporting error when there is a problem read or write to the disk.

7.5 Phy Event Counters

Barracuda implemented the SATA II Phy Event Counter option. This command utilizes the Read Log Extended command page 11h to report the counter of the SATA interface physical events.

Table 7-1 Phy Event Counter Supports

Identifier (Bits 11:0)	Mandatory/ Optional	Supported	Description
000h	Mandatory	Y	No counter value; marks end of counters in the page
001h	Mandatory	Y	Command failed due to an ICRC error
002h	Optional	N	Data FIS R_ERR ending status (transmitted and received)
003h	Optional	N	Data FIS R_ERR ending status (transmitted only)
004h	Optional	N	Data FIS R_ERR ending status (received only)
005h	Optional	N	Non-data FIS R_ERR ending status (transmitted and received)
006h	Optional	N	Non-data FIS R_ERR ending status (transmitted only)
007h	Optional	N	Non-data FIS R_ERR ending status (received only)
008h	Optional	Y	Non-data FIS retries (transmitted)
009h	Optional	Y	Transitions from drive PhyRdy to drive PhyNRdy
00Ah	Mandatory	Y	Signature D2H Register FISes sent due to a COMRESET
00Bh	Optional	Y	CRC errors within the FIS (received)
00Dh	Optional	Y	Non-CRC errors within the FIS (received)
00Fh	Optional	N	Data FIS R_ERR ending status due to CRC errors (received)
010h	Optional	N	Data FIS R_ERR ending status due to non-CRC errors (received)
012h	Optional	N	Non-data FIS R_ERR ending status due to CRC errors (received)
013h	Optional	N	Non-data FIS R_ERR ending status due to non-CRC errors (received)

7.6 Software Settings Preservation

Barracuda supports SATA II Software Settings Preservation requirements. The settings of the following items will be preserved across device receiving of COMRESET. This will ensure the device operates on the intended settings even if the COMRESET is received. A SATA bus may generates COMRESET on a Asynchronous Signal Loss (ASL) case which may be caused by noise on the bus. The Software Settings Preservation feature can ensure the device continuing its operation on the ASL event.

The settings preserved are as list:

- Initialize Device Parameters
- Power Management Feature Set
- Security Mode State
    - Security Freeze Lock
    - Security Unlock
- Set Address Max (Ext)
- Set Features
    - Write Cache
    - Set Transfer Mode
    - Read Look-Ahead
- Set Multiple Mode

7.7 SATA Power Management

Barracuda supports SATA power management from the SATA I and SATA II specifications. The SATA power management is designed to conserve interface power usage when the bus is not active. There are two power management requests: PM Partial and PM Slumber. These two states can be requested by either the host or the device. When entering the Partial state, the device is required to exit to normal state in 10 us, while the exit from Slumber state is limited to 10 ms.

The device will respond to the host PM requests and enter the PM mode when requested. The host may request the PM Partial or PM Slumber at and end of command execution.

The device will also issues PM request when this feature is enabled by the host. The host enables the PM feature by a Set Feature command with proper feature data. After the feature is enabled, the device will make a PM request when entering the Standby or Sleep modes.

CHAPTER 8 ATA COMMAND DESCRIPTIONS

8.1 Command Table

Commands are issued to the drive through SATA interface, by way of a Command Packet. This table list commands supported by the Barracuda HDD. Extended commands are unique to the 48-bit Address feature set.

Table 8-1 Command Code Parameters

Command			Parameter Used									
Class	DESCRIPTION	CODE	FE	SC	LL	LM	LH	DE	SC Pre	LL Pre	LM Pre	LH Pre
1	Check Power Mode	E5h		y				y				
1	Download Micro code	92h										
1	Device Configuration Overlay	B1h										
1	Execute Device Diagnostic	90h										
1	Flush Cache	E7h										
1	Flush Cache Extended	EAh										
1	Format Track *3	50h		y	y	y	y	y				
1	Initialize Device Parameters *3	91h		y	y	y	y	y				
1	Identify Device	ECh										
1	Idle	E3h		y								
1	Idle Immediate	E1h										
1	NOP	00h										
1	Read Buffer	E4h										
1	Read DMA	C8h		y	y	y	y	y				
1	Read DMA Extended	25h		y	y	y	y	y	y	y	y	y
2	Read FPDMA Queued	60h	y	y	y	y	y	y	y	y	y	y
1	Read Log Extended	2Fh		y	y	y		y	y		y	
1	Read Long *3	22h			y	y	y	y				
1	Read Multiple	C4h		y	y	y	y	y				
1	Read Multiple Extended	29h		y	y	y	y	y	y	y	y	y
1	Read Native Max Address	F8h										
1	Read Native Max Address Extended	27h										
1	Read Sector(s)	20h		y	y	y	y	y				
1	Read Sector(s) Extended	24h		y	y	y	y	y	y	y	y	y
1	Read Verify *3	40h		y	y	y	y	y				
1	Read Verify Extended *3	41h		y	y	y	y	y	y	y	y	y
1	Recalibrate *3	10h										
1	Security Disable Password	F6h										
1	Security Erase Prepare	F3h										

1	Security Erase Unit	F4h											
1	Security Freeze Lock	F5h											
1	Security Set Password	F1h											
1	Security Unlock	F2h											
1	Seek *3	70h											
1	Set Features	EFh	y	y									
1	Set Max Address	F9h			y	y	y	y					
1	Set Max Address Extended	37h			y	y	y			y	y	y	
1	Set Multiple Mode	C6h		y									
1	Sleep	E6h											
1	SMART	B0h	y	y	y	y	y						
1	Standby	E2h		y									
1	Standby Immediate	E0h											
1	Write Buffer	E8h											
1	Write DMA	CAh		y	y	y	y	y					
1	Write DMA Extended	35h		y	y	y	y	y	y	y	y	y	
2	Write FPDMA Queued	61h	y	y	y	y	y	y	y	y	y	y	
1	Write Log Extended	3Fh		y	y	y	y		y	y	y	y	
1	Write Multiple	C5h		y	y	y	y	y					
1	Write Multiple Extended	39h		y	y	y	y		y	y	y	y	
1	Write Sector(s)	30h		y	y	y	y	y					
1	Write Sector(s) Extended	34h		y	y	y	y		y	y	y	y	

Legend:

LH = LBA High
LM = LBA Middle
LL = LBA Low
DE = Device register
FE = Feature register
SC = Sector Count register
Pre = Previous
y The register contains a valid parameter for this command.
Type 1 is ATA-7 commands; type 2 is SATA II commands
*3 It is created for compatibility reason.

8.2 Command Descriptions

8.2.1 Check Power Mode (E5h)

This command checks the power mode.

If the drive is in, going to, or recovering from the Standby Mode, the drive sets BSY, sets the Sector Count register to 00h, clears BSY, and generates an interrupt.

If the drive is in the Idle Mode, the drive sets BSY, sets the Sector Count register to FFh, clears BSY, and generates an interrupt.

8.2.2 Download Micro Code (92h)

This command enables the host to alter the drive's Micro-code. The data transferred using this command is vendor specific.

8.2.3 Device Configuration Overlay (B1h)

The Device Configuration Overlay feature set allows a utility program to modify some of the optional commands, modes, and feature sets that a device reports as supported in the Identify Device command response as well as the capacity reported. Individual Device Configuration Overlay feature set commands are identified by the value placed in the Features register. The following table illustrates these features.

Table 8-2 Device Configuration Overlay Feature Register Values

Value	Command
C0h	Device Configuration Restore
C1h	Device Configuration Freeze Lock
C2h	Device Configuration Identify
C3h	Device Configuration Set
00h-BFh,C4h-FFh	Reserved

The Device Configuration Restore command disables any setting previously made by a Device.

The Device Configuration Freeze Lock command prevents accidental modification of the Device Configuration Overlay settings. After successful execution of a Device Configuration Freeze Lock Command, all Device Configuration Set, Device Configuration Freeze Lock, Device Configuration Identify command, and Device Configuration Restore commands shall be aborted by the device. The Device Configuration Freeze Lock condition will be cleared only after a power-down.

The Device Configuration Identify command returns a 512 byte data structure via PIO data-in transfer. The content of this data structure indicates the selectable commands, modes, and feature sets that the device is capable of supporting. Should a Device Configuration Set command be issued reducing the capabilities, the response to a Device Configuration Identify command will reflect the reduced set of capabilities accordingly.

The Device Configuration Set command allows a device manufacturer or a PC manufacturer to reduce the set of optional commands, modes, or feature sets supported by a device as indicated by a Device Configuration Identify command. The Device Configuration Set Command transfers an overlay that modifies some of the bits in words 63, 82, 83, 84, and 88 of the Identify Device command. When the bits in these words are cleared, the device shall no longer support the indicated command, mode, or feature set. If a bit is set in the overlay transmitted by the device that is not set in the overlay received from a Device Configuration Identify command, then no action is taken for that bit. Modifying the maximum LBA of the device also changes the address value returned by a Read Native Max Address, or Read Native Max Address Ext command.

Table 8-3 Device Configuration Identify data structure

Word	Content
0	Data structure revision
1	Multiword DMA modes supported 15-3 Reserved 2 1 = Reporting support for Multiword DMA mode 2 and below is allowed 1 1 = Reporting support for Multiword DMA mode 1 and below is allowed 0 1 = Reporting support for Multiword DMA mode 0 is allowed
2	Ultra DMA modes supported 15-7 Reserved 6 1 = Reporting support for Ultra DMA mode 6 and below is allowed 5 1 = Reporting support for Ultra DMA mode 5 and below is allowed 4 1 = Reporting support for Ultra DMA mode 4 and below is allowed 3 1 = Reporting support for Ultra DMA mode 3 and below is allowed 2 1 = Reporting support for Ultra DMA mode 2 and below is allowed 1 1 = Reporting support for Ultra DMA mode 1 and below is allowed 0 1 = Reporting support for Ultra DMA mode 0 is allowed
3-6	Maximum LBA
7	Command set/feature set supported 15-14 Reserved 13 1 = Reporting support for SMART Conveyance self-test is allowed 12 1 = Reporting support for SMART Selective self-test is allowed 11 1 = Reporting support for Forced Unit Access is allowed 10 Reserved 9 1 = Reporting support for Streaming feature set is allowed 8 1 = Reporting support for 48-bit Addressing feature set is allowed 7 1 = Reporting support for Host Protected Area feature set is allowed 6 1 = Reporting support for Automatic acoustic management is allowed 5 1 = Reporting support for READ/WRITE DMA QUEUED commands is allowed 4 1 = Reporting support for Power-up in Standby feature set is allowed 3 1 = Reporting support for Security feature set is allowed 2 1 = Reporting support for SMART error log is allowed 1 1 = Reporting support for SMART self-test is allowed 0 1 = Reporting support for SMART feature set is allowed
8	Serial ATA command /feature set supported 15-5 Reserved 4 1 = Reporting support for software settings preservation 3 1 = Reporting support for asynchronous notification (reserved) 2 1 = Reporting support for interface power management 1 1 = Reporting support for non-zero buffer offsets in DMA Setup FIS (reserved) 0 1 = Reporting support for native command queuing
9	Reserved for serial ATA
10-191	Reserved
192-254	VU
255	Integrity word 15-8 Checksum 7-0 Signature

8.2.4 Execute Device Diagnostics (90h)

This command performs the internal diagnostic tests implemented by the drive. The Diagnostic Code written to the Error register is a unique 8-bit code.

Table 8-4 Diagnostic Codes

Code	Description
01h	No error detected
02h	Formatter device error
03h	Sector buffer error
04h	ECC circuitry error
05h	Controlling microprocessor error

8.2.5 Flush Cache (E7h, EAh: extended)

This command is used by the host to request the drive to flush the write cache. If write is to be flushed, all data cached will be written to the media. The BSY bit will remain set to one until all data has been successfully written or error occurs.

8.2.6 Format Track (50h)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose.

8.2.7 Identify Device (ECh)

The Identify Device command enables the host to receive parameter information from the device. When the command is issued, prepares to transfer the 256 words of device identification data to the host, sets the DRQ bit, clears the BSY bit, and generates an interrupt. The host can then transfer the data by reading the Data register. The parameter words in the buffer have the arrangement and meanings defined. All reserved bits or words will remain to be zero.

Some parameters are defined as a group of bits. A word which is defined as a set of bits is transmitted with the indicated bits on the respective data bus bit (e.g., bit 15 appears on DD15).

Other parameters are defined as a sixteen-bit value. A word which is defined as a sixteen bit value places the most significant bit of the value on bit DD15 and the least significant bit on bit DD0.

Some parameters can be defined as a 32-bit value (e.g., words 57 and 58). Such fields are transferred using two word transfers. The device first transfers the least significant bits, bits 15 through 0 of the value, on bits DD15 through DD0 respectively. After the least significant bits have been transferred, the most significant bits, bits 31 through 16 of the value, are transferred on DD15 through DD0 respectively.

Some parameters are defined as a string of ASCII characters. For the string “Copyright,” the character ‘C’ is the first byte, ‘o’ is the 2nd byte, etc. When such fields are transferred, the order of transmission is:

- 1st character (‘C’) is on bits DD15 through DD8 of the first word
- 2nd character (‘o’) is on bits DD7 through DD0 of the first word
- 3rd character (‘p’) is on bits DD15 through DD8 of the second word
- 4th character (‘y’) is on bits DD7 through DD0 of the second word, etc.

Table 8-5 IDENTIFY DEVICE information

Word	Content	Description
0	0040h	General configuration bit-significant information: 15 0=ATA device, set to 0 14-8 Retired 7 1=removable media device, set to 0 6 1=not removable controller and/or device, set to 1 5-3 Retired 2 Reserved 1 Retired 0 Reserved
1	XXXXh	Number of logical cylinders
2	0	Reserved
3	00XXh	Number of logical heads
4-5	0	Retired
6	003Fh	Number of logical sectors per logical track
7-8	0	Reserved for CFA
9	0	Retired
10-19		Serial number (20 ASCII characters, 0 = not specified)
20	0003h	Retired
21	4000h	Retired
22	0004h	Number of ECC bytes (Device native length is selected via set feature command.)
23-26		Firmware revision (8 ASCII characters)
27-46		Model number (40 ASCII characters)
47	8010h	15-8 80h 7-0 Maximum number of sectors that shall be transferred per interrupt on READ/WRITE MULTIPLE commands
48	0000h	Reserved
49	2F00h	Capabilities 15-14 Reserved 13 1=Standby timer values as specified in this standard are supported 0=Standby timer values shall be managed by the device 12 Reserved 11 1=IORDY supported 0=IORDY may be supported 10 1=IORDY may be disabled 9 LBA supported 8 DMA supported 7-0 Retired
50	4000h	Capabilities
51	0200h	PIO data transfer cycle timing mode (Obsolete)
52	0200h	DMA data transfer cycle timing mode (Obsolete)
53	0007h	15-3 Reserved 2 1=the fields reported in word 88 are valid 1 1=the fields reported in words 64-70 are valid 0 1=the fields reported in words 54-58 are valid (Obsolete)
54	XXXXh	Number of current logical cylinders (Obsolete)
55	XXXXh	Number of current logical heads (Obsolete)
56	XXXXh	Number of current logical sectors per track (Obsolete)
57-58	XXXXh	Current capacity in sectors, Word 57 specifies the low world of the capacity (Obsolete)
59	0XXXh	Current Multiple setting. Bit assignments 15-9 Reserved 8 1=Multiple sector setting is valid 7-0 xxh=Current setting for number of sectors

Word	Content	Description
60-61	XXXXh	Total number of user addressable sectors (LBA mode only)
62	0000h	Obsolete
63	XX07h	Multiword DMA Transfer Capability 15-8 Multiword DMA transfer mode select 7-0 Multiword DMA transfer modes supported (support mode 0 , 1 and 2)
64	0003h	Flow Control PIO Transfer modes supported 15-8 Reserved 7-0 PIO modes supported ('11b' = PIO Mode 3 and 4 Supported)
65	0078h	Minimum Multiword DMA transfer cycle time per word 15-0 Cycle time in nanoseconds (120ns, 16.6MB/S)
66	0078h	Manufacturer's recommended Multiword DMA transfer cycle time 15-0 Cycle time in nanoseconds (120ns, 16.6MB/S)
67	0078h	Minimum PIO transfer cycle time without flow control 15-0 Cycle time in nanoseconds (120ns, 16.6MB/S)
68	0078h	Minimum PIO transfer cycle time with IORDY flow control 15-0 Cycle time in nanoseconds (120ns, 16.6MB/S)
69-69	0000h	Reserved
71-74	0000h	Reserved
75	001fh	Queue depth 15-5 Reserved 4-0 Maximum queue depth-1
76	1F06h	Serial ATA capabilities 15-11 Reserved 10 Supports Phy event counters 9 Supports receipt of host-initiated interface power management requests 8 Supports native command queuing 7-3 Reserved 2 Supports Serial ATA Gen-2 signaling speed (3.0Gbps) 1 Supports Serial ATA Gen-1 signaling speed (1.5Gbps) 0 Reserved (cleared to 0)
77	0000h	Reserved for future Serial ATA definition
78	004Ch	Serial ATA feature supported 15-7 Reserved 6 Supports software settings preservation 5 Reserved 4 Supports in-order data delivery 3 Supports device supports initiating interface power management 2 Supports DMA Setup Auto-Activate optimization 1 Supports non-zero buffer offsets in DMA Setup FIS 0 Reserved (set to 0)
79	0040h	Serial ATA feature enabled 15-7 Reserved 6 Software settings preservation enabled 5 Reserved 4 In-order data delivery enabled 3 Device initiating interface power management enabled 2 DMA Setup Auto-Activate optimization enabled 1 Non-zero buffer offsets in DMA Setup FIS enabled 0 Reserved (set to 0)
80	01FFh	Major version number 15-0 ATA-1, ATA-2, ATA-3 and ATA/ATAPI-4, 5, 6, 7
81	0028h	Minor version number 15-0 ATA/ATAPI-7 X3T13 1532D revision 0
82	746Bh	Command set supported. 15 Obsolete 14 1=NOP command supported

Word	Content	Description
		13 1=READ BUFFER command supported 12 1=WRITE BUFFER command supported 11 Obsolete 10 1=Host Protected Area feature set supported 9 1=DEVICE RESET command supported 8 1=SERVICE interrupt supported 7 1=Release interrupt supported 6 1=Look-ahead supported 5 1=Write cache supported 4 1=supports PACKET Command feature set 3 1=Power Management feature set supported 2 1=Removable Media feature set supported 1 1=Security Mode feature set supported 0 1=SMART feature set supported
83	7F69h	Command sets supported. 15 Shall be set to zero 14 Shall be set to one 13 1=FLUSH CACHE Ext supported 12 1=Mandatory FLUSH CACHE command supported 11 1=Device Configuration Overlay features supported 10 1=48 bit address feature supported 9 1-Automatic Acoustic feature supported 8 1=SET MAX Security feature supported 7 1=Set Address Offset Reserved Area Boot, INCITS TR27:2001 6 1=SET FEATURES subcommand required to spin-up after power-up. 5 1=Power up standby feature set supported 4 1=Removable media status notification feature set supported 3 1=Advanced Power Management feature set supported 2 1=CFA feature set supported 1 1=READ/WRITE DMA QUEUED supported 0 1=DOWNLOAD MICROCODE command supported
84	4123h	Command set/feature supported extension. 15 Shall be set to 0 14 Shall be set to 1 13 1=IDLE IMMEDIATE with UNLOAD FEATURE supported 12 Reserved for technical report 11 Reserved for technical report 10 1=URG bit supported for WRITE STREAM DMA EXT and WRITE STREAM EXT 9 1=URG bit supported for READ STREAM DMA EXT and READ STREAM EXT 8 64-bit World wide name supported 7 1=Write DMA Queued FUA Ext command supported 6 1=Write DMA FUA Ext and Write Multiple FUA Ext command supported 5 1=General purpose logging feature set supported 4 1=Streaming feature set supported 3 1=Media Card Pass Through command feature set supported 2 1=Media serial number supported 1 1=SMART self-test supported 0 1=SMART error logging supported
85	7469h	Command set/feature enabled. (The default manufacturing setting is as below) 15 Obsolete 14 1=NOP command enabled 13 1=READ BUFFER command enabled 12 1=WRITE BUFFER command enabled 11 Obsolete 10 1=Host Protected Area feature set enabled

Word	Content	Description
		9 1=DEVICE RESET command enabled 8 1=SERVICE interrupt enabled 7 1=Release interrupt enabled 6 1=Look-ahead enabled 5 1=Write cache enabled 4 1=PACKET Command feature set enabled (Should be cleared to 0) 3 1=Power Management feature set enabled 2 1=Removable Media feature set enabled 1 1=Security Mode feature set enabled 0 1=SMART feature set enabled
86	BC41h	Command set/feature enabled. 15-14 Reserved 13 1=FLUSH CACHE EXT command supported 12 1=FLUSH CACHE command supported 11 1=Device Configuration Overlay features supported 10 1=48 bit address feature supported 9 1-Automatic Acoustic Management feature set enabled 8 1=SET MAX security feature enabled by SET MAX SET PASSWORD 7 1=Set Address Offset Reserved Area Boot, INCITS TR27:2001 6 1= SET FEATURES subcommand required to spin-up after power-up. 5 1=Power-Up Standby feature set enabled 4 1=Removable media status notification feature set enabled 3 1=Advanced Power Management feature set enabled 2 1=CFA feature set enabled 1 1=READ/WRITE DMA QUEUED supported 0 1=DOWNLOAD MICROCODE command supported
87	4123h	Command set/feature default. 15 Shall be set to 0 14 Shall be set to 1 13 1=IDLE IMMEDIATE with UNLOAD FEATURE supported 12 Reserved for technical report 11 Reserved for technical report 10 1=URG bit supported for WRITE STREAM DMA EXT and WRITE STREAM EXT 9 1=URG bit supported for READ STREAM DMA EXT and READ STREAM EXT 8 64-bit World wide name supported 7 1=WRITE DMA QUEUED FUA EXT command supported 6 1=WRITE DMA FUA EXT and WRITE MULTIPLE FUA EXT command supported 5 General Purpose logging feature set supported 4 1=Valid CONFIGURATION STREAM command has been executed 3 1=Media Card Pass Through command feature set enabled 2 1=Media serial number is valid 1 1=SMART self-test supported 0 1=SMART error logging supported
88	XX3Fh	Ultra DMA transfer modes 15-8 Current active Ultra DMA transfer mode 15 Ultra DMA mode 7 14 Ultra DMA mode 6 13 Ultra DMA mode 5 12 Ultra DMA mode 4 11 Ultra DMA mode 3 10 Ultra DMA mode 2 9 Ultra DMA mode 1 8 Ultra DMA mode 0 7-0 Ultra DMA transfer mode is supported

Word	Content	Description
		7 Ultra DMA mode 7 6 Ultra DMA mode 6 5 Ultra DMA mode 5 4 Ultra DMA mode 4 3 Ultra DMA mode 3 2 Ultra DMA mode 2 1 Ultra DMA mode 1 0 Ultra DMA mode 0
89	0000h	Time required for Security Erase Unit completion
90	0000h	Time required for Enhanced Security Erase completion
91	0040h	Current Advanced Power Management value
92	FFFEh	Master Password Revision Code
93	0000h	COMRESET result.
94	xxxxh	AAM 15-8 Vendor's recommended acoustic management value 7-0 Current acoustic management value
95	0000h	Stream Minimum Request Size
96	0000h	Streaming Transfer Time - DMA
97	0000h	Streaming Access Latency - DMA and PIO
98-99	0000h	Streaming Performance Granularity
100-103	xxxxh	Maximum User LBA for 48-bit address (100=LSB)
104	0000h	Streaming Transfer Time - PIO
105	0000h	Reserved
106	0000h	Physical sector size / Logical Sector Size
107		Inter-seek delay for ISO-7779 acoustic testing in microseconds
108	xxxxh	World wide name 15-12 NAA (3:0) 5 IEEE OUI (23:12)
109	xxxxh	WWN 15-4 IEEE OUI (11:0) 5 Unique ID (35:32)
110	xxxxh	Unique ID (31:16)
111	xxxxh	Unique ID (15:0)
112-115	xxxxh	Reserved for world wide name extension to 128 bits
116	0000h	Reserved for technical report
117-118	xxxxh	Words per Logical Sector
119-126	0000h	Reserved
127	0000h	Removable Media Status Notification feature set support
128	0021h	Security status 15-9 Reserved 8 Security level 0=High, 1=Maximum 7-6 Reserved 5 1=Enhanced security erase supported 4 1=Security count expired 3 1=Security frozen 2 1=Security locked 1 1=Security enabled 0 1=Security supported
129-159	0000h	Vendor specific
160	0000h	CFA power mode 1
161-175	0000h	Reserved for CFA
176-205	0000h	Current media serial number
206-254	0000h	Reserved
255	xxxxh	Integrity word 15-8 Checksum 5 Signature (A5h)

8.2.8 Idle (E3h)

This command causes the drive to enter the Idle Mode, clear BSY, and generate an interrupt. The interrupt is generated even though the drive may not have fully transitioned to Idle Mode.

If the drive is already spinning, the spin-up sequence is not executed.

If the Sector Count register is non-zero, then the automatic Idle Mode sequence is enabled, and the timer begins counting down immediately. If the Sector Count register is zero, the automatic power down sequence is disabled.

After the drive enters Idle Mode, it automatically transitions to Standby Mode upon expiration of a prescribed 1 minute spin-down timer.

Table 8-6 Automatic Standby Timer Periods

Sector Count Register Contents	Corresponding Time-Out Period
0 (00h)	Timeout Disabled
1-240 (01h-FOh)	(value * 5) seconds
241-251 (F1h-FBh)	(value - 240) * 30 minutes
252 (FCh)	21 minutes
253 (FDh)	8 hours
254 (FEh)	Reserved
255 (FFh)	21 minutes 15 seconds

8.2.9 Idle Immediate (E1h)

This command causes the drive to enter Idle Mode, clear BSY, and generate an interrupt. The interrupt is generated even though the drive may not have fully transitioned to Idle Mode.

8.2.10 Initialize Device Parameters (91h)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose. The use of this command is beyond the ATA standard and not recommended by the manufacture.

This command enables the host to set the number of sectors per track and the number of heads minus 1, per cylinder. Upon receipt of the command, the drive sets BSY, saves the parameters, clears BSY, and generates an interrupt.

The only two register values used by this command are the Sector Count register which specifies the number of sectors per track, and the Drive/Head register which specifies the number of heads minus 1. The sector count and head values are not checked for validity by this command. If they are invalid, no error will be posted until an illegal access is made by some other command.

8.2.11 NOP (00h)

The NOP command is always responded with command aborted.

8.2.12 Read Buffer (E4h)

The Read Buffer command enables the host to read the current contents of the drive's sector buffer. When this command is issued, the drive sets up the sector buffer for a read operation, sets DRQ, clears BSY, and generates an interrupt. The host then reads up to 512 bytes of data from the buffer.

The Read Buffer and Write Buffer commands are synchronized so that sequential Write Buffer (E8h) and Read Buffer commands access the same 512 bytes within the buffer.

8.2.13 Read DMA (C8h, 25h: extended)

This command executes in a manner similar to the Read Sector(s) command except for the drive issues only one interrupt per command to indicate that data transfer has stopped and the status is available.

Any unrecoverable error encountered during execution of a Read DMA command results in the termination of data transfer prior to the sector where the error was detected. The drive generates an interrupt to indicate that data transfer has terminated and status is available. The error posting is the same as that for the Read Sector(s) command.

8.2.14 Read FPDMA Queued (60h)

This command is implemented according to the Serial ATA II: Extension to Serial ATA 1.0a, Revision 1.2 specification. The purpose of this command is for the host to issue a Native Command Queue (NCQ) read commands. This command allows device to reorder the command issued in a sequence of the queue. The command is returned based on the device’s determine of the location sequence.

The Barracuda drive implemented a queue depth of 32. This will allow host to issue up to 32 NCQ commands (combined read and write commands).

If the drive enters NCQ mode and a non-queue command is received, the drive will respond with error to inform host a queue command been overlapped with non-queue. If a queue tag is not finished and another same tag command is received, the drive will response with error to inform host a duplicated tag is received.

Error information is reported according to the SATA II specification. A read Log Extended command with log page 10 is required to retrieve the error information

.

8.2.15 Read Log Extended (2Fh)

This command returns the specified log to the host. The device shall interrupt for each DRQ block transferred. See ATA 7 document for command details.

8.2.16 Read Long (22h)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose. The use of this command is beyond the ATA standard and not recommended by the manufacture.

The Read Long command performs similarly to the Read Sectors command except that it returns the data and the ECC bytes appended to the data field of the desired sector. During a Read Long command, the drive does not check the ECC bytes to determine if there has been a data error. Only single sector Read Long operations are supported.

The transfer of the ECC bytes shall be 8 bits wide and 4 or device native ECC bytes length.

8.2.17 Read Multiple Command (C4h, 29h: extended)

The Read Multiple command performs similarly to the Read Sectors command except interrupts are not generated on every sector, but on the transfer of a block which contains the number of sectors defined by a Set Multiple command.

Command execution is identical to the Read Sectors operation except that the numbers of sectors as defined by a Set of Multiple command are transferred without intervening interrupts. DRQ qualification of the transfer is required only at the start of the data block, not on each sector.

The block count of sectors to be transferred without intervening interrupts is programmed by the Set Multiple Mode command, which should be executed prior to the Read Multiple command. When the Read Multiple command is issued, the Sector Count register contains the number of sectors (not the number of blocks or the block count) requested.

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

n = Remainder (Sector Count / Block Count)

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

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

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

Subsequent blocks are transferred only if the error was a correctable data error. All other errors cause the command to stop after transfer of the block, which contained the error. Interrupts are generated when DRQ is set at the beginning of each block.

8.2.18 Read Native Max Address (F8h, 27h :extended)

This command returns the native maximum address. The native maximum address is the highest address accepted by the device in the factory default condition. The native maximum address is the maximum address that is valid when using the SET MAX ADDRESS command.

8.2.19 Read Sector(s) (20h, 24h: extended)

This command reads from 1 to 256 sectors as specified in the Sector Count register. A sector counts of 0 requests all 256 sectors if the command is Read Sectors (not Read Sector Extended). The transfer begins at the sector specified in the Sector Number register.

If the drive is not already on the desired track, an implied seek is performed. Once at the desired track, the drive searches for the appropriate ID field.

If the ID is read correctly, the data address mark shall be recognized within a specified number of bytes, or the Address Mark Not Found error is posted. DRQ is always set prior to data transfer, regardless of the presence or absence of an error condition.

At command completion, the Command Block registers contain the address of the last sector read. If an error occurs, the read terminates at the sector where the error occurred. The Command Block registers contain the address of the sector where the error occurred.

8.2.20 Read Verify Sector(s) (40h, 41h: extended)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose. The use of this command is beyond the ATA standard and not recommended by the manufacturer.

This command is identical to the Read Sectors command, except that DRQ is never set, and no data is transferred to the host.

When the requested sectors have been verified, the drive clears BSY and generates an interrupt. Upon command completion, the Command Block registers contain the address of the last sector verified. If an error occurs, the Verify terminates at the sector where the error occurred.

The Command Block registers contain the address of where the error occurred. The Sector Count register contains the number of sectors not yet verified.

8.2.21 Recalibrate (10h)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose. The use of this command is beyond the ATA standard and not recommended by the manufacturer.

This command moves the read/write heads from anywhere on the disk to cylinder 0. Upon receipt of the command, the drive issues seek to cylinder zero. The drive then waits for seek to complete before updating status, clearing BSY, and generating an interrupt. If the drive cannot reach cylinder 0, it posts a Track 0 Not Found error.

8.2.22 Security Disable Password (F6h)

The SECURITY DISABLE PASSWORD command transfers 512 bytes of data from the host. In Table 6-6 it defines the content of the security password. If the password selected by word 0 matches the password previously saved by the device, the device shall unlock mode. This command shall not change the Master password. The Master password shall be reactivated only when a User password is set.

Table 8-7 Security password content

Word	Content		
0	Control word.		
	Bit 0	Identifier	0= compare User password 1= compare Master password
	Bit (15:1)	Reserved	
1-16	Password (32 bytes)		
17-255	Reserved		

8.2.23 Security Erase Prepare (F3h)

The SECURITY ERASE PREPARE command shall be issued immediately before the SECURITY ERASE UNIT command to enable device erasing and unlocking. This command prevents accidental loss of data on the device.

8.2.24 Security Erase Unit (F4h)

This command transfers 512 bytes of data from the host. Table 6-7 defines the content of this information. If the password does not match the password previously saved by the device, the device shall reject the command with by abortion.

Table 8-8 Security Erase Unit Password

Word	Content		
0	Control word.		
	Bit 0	Identifier	0= compare User password 1= compare Master password
	Bit 1	Erase mode	0= Normal erase 1= Enhanced erase
	Bit (15:2)	Reserved	
1-16	Password (32 bytes)		
17-255	Reserved		

8.2.25 Security Freeze Lock (F5h)

The SECURITY FREEZE LOCK command shall set the device to frozen mode. After command completion any other commands that update the device Lock mode shall be command aborted. Frozen mode shall be disabled by power-off or hardware reset. If SECURITY FREEZE LOCK shall be issued when the device is in frozen mode, the command executes and the device shall remain in frozen mode.

Commands disabled by SECURITY FREEZE LOCK are as follows:

SECURITY SET PASSWORD
SECURITY UNLOCK
SECURITY DISABLE PASSWORD
SECURITY ERASE PREPARE
SECURITY ERASE UNIT

8.2.26 Security Set Password (F1h)

This command transfers 512 bytes of data from the host. Table defines the content of this information. The data transferred controls the function of this command. It also defines the interaction of the identifier and security level bits.

Table 8-9 Security Set Password data content

Word	Content		
0	Control word.		
	Bit 0	Identifier	0= set User password 1= set Master password
	Bit (7:1)	Reserved	
	Bit 8	Security level	0= High 1= Maximum
	Bit (15:2)	Reserved	
1-16	Password (32 bytes)		
17	Master Password Revision Code (valid if word 0 bit 0 = 1)		
18-255	Reserved		

Table 8-10 Identifier and security level bit interaction

Identifier	Level	Command result
User	High	The password supplied with the command shall be saved as the new User password. The Lock mode shall be enabled from the next power-on or hardware reset. The device shall then be unlocked by either the User password or the previously set Master password.
User	Medium	The password supplied with the command shall be saved as the new User password. The Lock mode shall be enabled from the next power-on or hardware reset. The device shall then be unlocked by only the User password. The Master password previously set is still stored in the device but shall not be used to unlock the device.
Master	High or Medium	Maximum This combination shall set a Master password but shall not enable or disable the Lock mode. The security level is not changed. Master password revision code set to the value in Master Password Revision Code field.

8.2.27 Security Unlock (F2h)

This command transfers 512 bytes of data from the host. If the Identifier bit is set to Master and the device is in high security level, then the password supplied shall be compared with the stored Master password. If the device is in maximum security level then the unlock shall be rejected.

If the Identifier bit is set to the user then the device needs to compare the supplied password with the stored User password.

If the password compare fails then the device shall return command aborted to the host and decrements the unlock counter. This counter shall be initially set to five and shall be decremented for each password mismatch when SECURITY UNLOCK is issued and the device is locked. When this counter reaches zero then SECURITY UNLOCK and SECURITY ERASE UNIT commands shall be command aborted until a power-on reset or a hardware reset. SECURITY UNLOCK commands issued when the device is unlocked have no effect on the unlock counter.

8.2.28 Seek (7xh)

This command has become obsolete in the ATA7 specification. The supporting of this command is just for backward compatibility purpose.

8.2.29 Set Features (EFh)

This command is used by the host to establish the following parameters, which affect the execution of certain drive features as shown below.

Table 8-11 Set Features Register Definitions

Code	Description
02h	Enable Write Cache
03h	Set transfer mode based on value in Sector Count register
06h	Enable Power-Up in Standby Mode
07h	Power-Up in Standby feature set device spin up
10h	Enable use of SATA features SC=02: DMA Setup FIS Auto Activate automation SC=03: Device-initiated interface power state transition SC=06: Software Settings Preservation
42h	Enable Automatic Acoustic Management feature set.
44h	Obsolete (Set VU ECC length)
55h	Disable read look-ahead feature
82h	Disable Write Cache
86h	Disable Power-Up in Standby Mode
90h	Disable use of SATA features SC=02: DMA Setup FIS Auto Activate automation SC=03: Device-initiated interface power state transition SC=06: Software Settings Preservation
AAh	Enable read look-ahead feature
BBh	Obsolete (Set 4-byte ECC length)
C2h	Disable Automatic Acoustic Management feature set.
D2h-DFh	VU Features
F0h-FFh	VU Features

When the drive receives this command, it checks the contents of the Feature register, clears BSY, and generates an interrupt. If the value in the Feature register is not supported or is invalid, the drive posts an Aborted Command error.

A host can choose the transfer mechanism by Set Transfer Mode and specifying a value in the Sector Count register in feature 03. The upper 5 bits define the type of transfer, and the low order 3 bits encode the mode value. Refer to the following table for details.

Table 8-12 Transfer Mode Values

Mode	Bits(7:3)	Bits(2:0)
PIO default mode	00000	000
PIO default mode, disable IORDY	00000	001
PIO flow control transfer mode	00001	mode
Multiword DMA mode	00100	mode
Ultra DMA mode	01000	mode
Mode = transfer mode number		

Setting of the UDMA mode will not alter the speed of the SATA interface transfer. SATA transfer speed is depending upon the negotiated interface speed of either Gen II 3.0 Gbps or Gen I 1.5 Gbps. The mode setting in the Set Feature command is for backward compatibility purpose.

8.2.30 Set Max Address (F9h, 37h: extended)

Set Max Address command is for device implement the Host Protected Area feature set. The drive maximum address can be changed according to the command issued from the host. The Set Max command has the following subcommands:

Table 8-13 Set Max Feature Register Values

Feature Value	Command
0	Obsolete
1	SET MAX SET PASSWORD
2	SET MAX LOCK
3	SET MAX UNLOCK
4	SET MAX FREEZE LOCK
05-FFh	Reserved

8.2.31 Set Multiple Mode (C6h)

This command enables the drive to perform Read and Write Multiple operations and establishes the block count for these commands.

The Sector Count register is loaded with the number of sectors per block. Drives support block sizes of 2, 4, 8, and 16 sectors. If the Sector Count register contains a valid value and the block count is supported, the value is loaded for all subsequent Read Multiple and Write Multiple commands and execution of those commands is enabled. If a block count is not supported, an Aborted Command error is posted, and Read Multiple and Write Multiple commands are disabled.

At power-on, or after a hardware reset, the default mode is Read and Write Multiple disabled. And on software reset, the default mode of Read and Write Multiple will not be changed.

8.2.32 Sleep (E6h)

This command is the only way to cause the drive to enter Sleep Mode. The drive is spun down, and when it is stopped, BSY is cleared, an interrupt is generated, and the interface becomes inactive.

The only way to recover from Sleep mode without a reset or power-on is for the host to issue a software reset.

A drive shall not power-on in Sleep Mode nor remain in Sleep Mode following a reset sequence. If the drive is already spun down, the spin down sequence is not executed.

8.2.33 Standby (E2h)

This command causes the drive to set BSY, enter the Standby Mode, clear BSY, and assert INTRQ. INTRQ is asserted even though the device may not have fully transitioned to Standby Mode.

If the Sector Count register is non-zero, then the Standby Timer is enabled. The value in the Sector Count register shall be used to determine the time programmed into the Standby Mode.

The value in the Sector Count register when the STANDBY command is issued shall determine the time period programmed into the Standby Timer.

8.2.34 SMART (B0h)

Individual SMART commands are identified by the value placed in the Feature resister. Below depicts these Feature register values.

Table 8-14 SMART Feature Registers Values

Feature Value	Command
D0h	SMART READ DATA
D1h	Obsolete (SMART Read Threshold)
D2h	SMART ENABLE/DISABLE ATTRIBUTE AUTOSAVE
D3h	Obsolete (SMART Save Attribute Value)
D4h	SMART EXECUTE OFF-LINE IMMEDIATE
D5h	SMART READ LOG SECTOR
D6h	SMART WRITE LOG SECTOR
D7h	Obsolete
D8h	SMART ENABLE OPERATIONS
D9h	SMART DISABLE OPERATIONS
DAh	SMART RETURN STATUS
DBh	Obsolete (Enable/Disable Auto Offline Scan)
DCh-DDh	Reserved
DEh	Reserved (Initialize SMART Variables)
DFh	Reserved

8.2.34.1 Smart disable operations (D9h)

This command disables all SMART capabilities within the device including any timer and event count functions related to this feature. After receipt of this command the device shall disable all SMART operations. SMART data shall no longer be monitored or saved by the device. The state of SMART (either enabled or disabled) shall be preserved by the device across power cycles.

After receipt of this command by the device, all other SMART commands (including SMART DISABLE OPERATIONS commands), with the exception of SMART ENABLE OPERATIONS, are disabled and invalid and shall be command aborted by the device.

8.2.34.2 Smart enable/disable attribute auto-save (D2h)

This command enables and disables the optional attribute auto-save feature of the device. Depending upon the implementation, this command may either allow the device, after some vendor specified event, to automatically save its updated attribute values to non-volatile memory; or this command may cause the auto-save feature to be disabled. The state of the attribute auto-save feature (either enabled or disabled), shall be preserved by the device across power cycles.

A value of zero written by the host into the device's Sector Count register before issuing this command shall cause this feature to be disabled. Disabling this feature does not preclude the device from saving SMART data to non-volatile memory during some other normal operation such as during a power-on sequence or during an error recovery sequence.

A value of F1h written by the host into the device's Sector Count Register before issuing this command shall cause this feature to be enabled. Any other meaning of this value or any other non-zero value written by the host into this register before issuing this command may differ from device to device.

8.2.34.3 Smart enable operations (D8h)

This command enables all SMART capabilities within the device. Prior to receipt of this command SMART data are neither monitored nor saved by the device. The state of SMART (either enabled or disabled) shall be preserved by the device across power cycles. Once enabled, the receipt of subsequent SMART ENABLE OPERATIONS commands shall not affect any SMART data or functions.

8.2.34.4 Smart execute off-line immediate (D4h)

This command causes the device to immediately initiate the activities that collect SMART data in an off-line mode and then save this data to the device's non-volatile memory.

During execution of its off-line activities the device shall not set BSY nor clear DRDY.

If the device is in the process of performing its set of off-line data collection activities (as a result of receiving a SMART EXECUTE OFF-LINE IMMEDIATE command from the host), and is interrupted by any new command from the host except a SMART DISABLE OPERATIONS, SMART EXECUTE OFF-LINE IMMEDIATE, or STANDBY IMMEDIATE command, the device shall suspend or abort its off-line data collection activities and service the host within two seconds after receipt of the new command. After

servicing the interrupting command from host the device may immediately re-initiate or resume its off-line data collection activities without any additional commands from host

If the device is in the process of performing its off-line data collection activities and is interrupted by a STANDBY IMMEDIATE command from the host, the device shall suspend or abort its off-line data collection activities, and service the host within two seconds after receipt of the command. After receiving a new command that causes the device to exit a power saving mode, the device shall initiate or resume off-line data collection activities without any additional commands from the host unless the device aborted these activities.

If the device is in the process of performing its off-line data collection activities and is interrupted by a SMART DISABLE OPERATIONS command from the host, the device shall suspend or abort its off-line data collection activities and service the host within two seconds after receipt of the command. Upon receipt of the next SMART ENABLE OPERATIONS command the device may, after the next vendor specified event, either re-initiate its off-line data collection activities or resume those activities from where they had been previously suspended.

If the device is in the process of performing its off-line data collection activities and is interrupted by a SMART EXECUTE OFF-LINE IMMEDIATE command from the host, the device shall abort its off-line data collection activities and service the host within two seconds after receipt of the command. The device shall then re-initiate its off-line data collection activities in response to the new EXECUTE OFF-LINE IMMEDIATE command.

8.2.34.5 Smart read data (D0h)

This command returns the Device SMART data structure to the host.

Table 8-15 Device SMART Data Structure

Byte	F/V	Descriptions
0	V	Data Structure Revision Number
2	V	1st Device Attribute
14	V	2nd Device Attribute
26	V	3rd Device Attribute
…	…	…
350	V	30th Device Attribute
362	V	Off-line data collection status
363	X	Self-test execution status byte
364-365	V	Total time in seconds to complete off-line data collection activity
366	X	Vendor specific
367	F	Off-line data collection capability
368-369	F	SMART capability
370	F	Error logging capability 7-1 Reserved 0 1=Device error logging supported
371	X	Vendor specific
372	F	Short self-test routine recommended polling time (in minutes)
373	F	Extended self-test routine recommended polling time (in minutes)
370-385	R	Reserved
386-510	X	Vendor specific
511	V	Data structure checksum

Key:

F = the content of the byte is fixed and does not change.

V = the content of the byte is variable and may change depending on the state of the device or the commands executed by the device.

X = the content of the byte is vendor specific and may be fixed or variable.

R = the content of the byte is reserved and shall be zero.

Data Structure Revision Number

The Data Structure Revision Number identifies which version of this data structure is implemented by the device. This revision number identifies both the Attribute Value and Attribute Threshold Data structures.

SMART Attribute Data

The data structure of the SMART attribute table is defined for a block of 12-byte length. Total number of the attributes is 30. Each attribute defines Attribute ID, Status Flag, Attribute Value, and Vendor Specific bytes. The Attribute ID is range from 01h to FFh. The Vendor Specific bytes are not defined in these specifications.

Byte	Definition
00	Attribute ID Number
01-02	Status Flag
03	Attribute Value
04-11	Vendor Specific Attribute Information

These data structures contain information which facilitates the monitoring of key drive indicators in order to determine when the drive has deteriorated to the point at which it may impact the reliability of the host system.

The attribute Status Flags are:

Table 8-16 SMART Attribute Status Flags

Bit	Name	Description
0	Pre failure/advisory	0= an attribute value less than or equal to its corresponding attribute threshold indicates an advisory condition where the usage or age of the device has exceeded its intended design life period. 1= an attribute value less than or equal to its corresponding attribute threshold indicates a pre-failure condition where imminent loss of data is being predicted.
1	On-line data collection	1= the attribute value is updated during normal operation of the device or during both normal operation and off-line testing.
2	Performance	1= Attributes that characterizes a performance aspects of the drive, degradation of which may indicate imminent drive failure, such as data throughput, seek times, spin up time, etc.
3	Error rate	1= Attribute that is based on the expected, non-fatal errors that are inherent in disk drives, increases in which may indicate imminent drive failure, such as ECC errors, seek errors, etc.
4	Event count	1= Attribute that counts events, of which an excessive number of which may indicate imminent drive failure, such as number of re-allocated sectors, etc.
5	Self-preserving	This type is used to specify an attribute that is collected and saved by the drive automatically. 1= It is a self-preserving attribute type.
6-15	Reserved	

Each attribute data structure is assigned an attribute ID. Any non-zero value in the attribute ID number indicates an active attribute. Valid values for this byte are found from 0x01 through 0xff. The attribute defined for Barracuda are as follows:

Table 8-17 SMART Attribute Data List

Attribute ID	Definition	Monitor
1	Raw read error rate	Errors during read operations.
3	Spin up time	Spin up time in millisecond
4	Spindle motor on count	On/off count.
5	Number of Auto Reassign sectors	Reassigned sector count.
7	Seek error rate	Errors during seek operations.
8	Seek time performance	Off-line random seek time
9	Drive run time.	How long drive works.
10	Spin up retry count	Retry count
11	Recalibration counter	Emergency parking counter
12	Power cycle count	Total power cycles.
187	Uncorrectable ECC error	Number of ECC error
194	Temperature.	Pre amp die temperature
195	ECC on the fly	ECC count for read operation
196	Re-allocate sector event	Read scan uncorrectable read error
197	Pending sector count	Off-line scan pending sectors
198	Uncorrectable sector count	Off-line scan uncorrectable sectors.
199	UDMA CRC error rate	CRC Errors during UDMA transfer
200	Write error rate	Errors during write operations.
201	Soft error rate	Soft errors during read operations.
202	SATA down speed counter	SATA link speed is dropped to 1.5G by Comreset

Off-line data collection status

The value of the off-line data collection status byte defines the current status of the off-line activities of the device. Table6-15 lists the values and their respective definitions.

Table 8-18 Off-line Data Collection Status Values

Value	Definition
00h or 80h	Off-line data collection activity was never started.
01h	Reserved
02h or 82h	Off-line data collection activity was completed without error.
03h	Reserved
04h or 84h	Off-line data collection Activity was suspended by an interrupting command from host
05h or 85h	Off-line data collection Activity was aborted by an interrupting command from host
06h or 86h	Off-line data collection Activity was aborted by the device with a fatal error.
07h-3Fh	Reserved

40h-7Fh	Vendor specific
81h	Reserved
83h	Reserved
87h-BFh	Reserved
C0h-FFh	Vendor specific

The total time in seconds to complete off-line data collection activity word specifies how may seconds the device requires to complete its sequence of off-line data collection activity. Valid values for this word are from 0001h to FFFFh.

Self-test execution status byte The self-test execution status byte reports the execution status of the self-test routine.

Bits (3:0) (Percent Self-Test Remaining) The value in these bits indicates an approximation of the percent of the self-test routine remaining until completion in ten percent increments. Valid values are 9 through 0. A value of 0 indicates the self-test routine is complete. A value of 9 means 90% of total test time remaining.

Bits (7:4) (Self-test Execution Status) The value in these bits indicates the current Self-test execution status.

Table 8-19 Self-test Execution Status Values

Value	Description
0	The previous self-test routine completed without error or no self-test has ever been run
1	The self-test routine was aborted by the host
2	The self-test routine was interrupted by the host with a hardware or software reset
3	A fatal error or unknown test error occurred while the device was executing its self-test routine and the device was unable to complete the self-test routine.
4	The previous self-test completed having a test element that failed and the test element that failed is not known.
5	The previous self-test completed having the electrical element of the test failed.
6	The previous self-test completed having the servo (and/or seek) test element of the test failed.
7	The previous self-test completed having the read element of the test failed.
8	The previous self-test completed having a test element that failed and the device is suspected of having handling damage.
9-14	Reserved.
15	Self-test routine in progress.

Total time to complete off-line data collection

The total time in seconds to complete off-line data collection activity word specifies how many seconds the device requires completing the sequence of off-line data collection activity. Valid values for this word are from 0001h to FFFFh.

Off-line data collection capability

The following describes the definition for the off-line data collection capability bits. If the value of all of these bits is equal to zero, then this device implements no off-line data collection.

- Bit 0 (EXECUTE OFF-LINE IMMEDIATE implemented bit) – If the value of this bit equals one, then the SMART EXECUTE OFF-LINE IMMEDIATE command is implemented by this device. If the value of this bit equals zero, then the SMART EXECUTE OFF-LINE IMMEDIATE command is not implemented by this device.

- Bit 1 (vendor specific)

- Bit 2 (abort/restart off-line by host bit) – If the value of this bit equals one, then the device shall abort all off-line data collection activity initiated by an SMART EXECUTE OFF-LINE IMMEDIATE command upon receipt of a new command. Off-line data collection activity must be restarted by a new SMART EXECUTE OFF-LINE IMMEDIATE command from the host. If the value of this bit equals zero, the device shall suspend off-line data collection activity after an interrupting command and resume off-line data collection activity after some vendor-specified event.

- Bit 3 (off-line read scanning implemented bit) - If this bit is cleared to zero, the device does not support off-line read scanning. If this bit is set to one, the device supports off-line read scanning

- Bit 4 (self-test implemented bit) – If this bit is cleared to zero, the device does not implement the Short and Extended self-test routines. If this bit is set to one, the device implements the Short and Extended self-test routines.

- Bit 7-5 (reserved).

SMART capability

The following describes the definition for the SMART capability bits. If the value of all of these bits is equal to zero, then this device does not implement automatic saving of SMART data.

- Bit 0 (power mode SMART data saving capability bit) – If the value of this bit equals one, the device shall save its SMART data prior to going into a power saving mode (Idle, Standby, or Sleep) or immediately upon return to Active or Idle mode from a Standby mode. If the value of this bit equals zero, the device shall not save its SMART date prior to going into a power saving mode (Idle, Standby, or Sleep) or immediately upon return to Active or Idle mode from a Standby mode.

- Bit 1 (SMART data auto-save after event capability bit) – The value of this bit shall be equal to one for devices complying with this standard.

- Bits 2-15(reserved).

Self-test routine recommended polling time

The self-test routine recommended polling time shall be equal to the number of minutes that is the minimum recommended time before which the host should first poll for test completion status. Actual test time could be several times this value. Polling before this time could extend the self-test execution time or abort the test depending on the state of bit 2 of the off-line data capability bits.

The data structure checksum is the two's compliment of the result of a simple eight-bit addition of the first 511 bytes in the data structure.

8.2.34.6 SMART read log sector (D5h)

This command returns the indicated log sectors to the host.

8.2.34.7 SMART return status (DAh)

This command is used to communicate the reliability status of the device to the host at the host's request. If a threshold exceeded condition is not detected by the device, the device shall set the Cylinder Low register to 4Fh and the Cylinder High register to C2h. If the device detects a threshold-exceeded condition, the device shall set Cylinder Low register to F4h and Cylinder High register to 2Ch

8.2.34.8 SMART write log sector (D6h)

This command writes number of 512-byte data sectors to the indicated log sector.

8.2.35 Standby (E2h)

This command causes the drive to enter Standby Mode. See 6.6.3 for the protocol. The drive may return the interrupt before the transition to Standby Mode is completed.

If the drive is already spun down, the spin down sequence is not executed.

8.2.36 Standby Immediate (E0h)

This command causes the drive to enter Standby Mode. See 6.6.3 for the protocol. The drive may return the interrupt before the transition to Standby Mode is completed.

If the drive is already spun down, the spin down sequence is not executed.

8.2.37 Write Buffer (E8h)

This command enables the host to overwrite the contents of the drive's sector buffer with any data pattern desired. See 6.6.2 for the protocol.

The Read Buffer and Write Buffer commands is synchronized within the drive so that sequential Write Buffer and Read Buffer commands access the same 512 bytes within the buffer.

8.2.38 Write DMA (CAh, 35h:extended)

This command executes in a similar manner to Write Sector(s) except the drive issues only one interrupt per command to indicate that data transfer has terminated and status is available.

Any error encountered during Write DMA execution results in the termination of data transfer. The drive issues an interrupt to indicate that data transfer has terminated and the status is available in the Error register. The error posting is the same as that for the Write Sector(s) command.

8.2.39 Write FPDMA Queued (61h)

This command is implemented according to the Serial ATA II: Extension to Serial ATA 1.0a, Revision 1.2 specification. The purpose of this command is for the host to issue a Native Command Queue (NCQ) write commands. This command allows device to reorder the command issued in a sequence of the queue. The command is returned based on the device's determine of the location sequence.

The Barracuda drive implemented a queue depth of 32. This will allow host to issue up to 32 NCQ commands (combined read and write commands).

If the drive enters NCQ mode and a non-queue command is received, the drive will respond with error to inform host a queue command been overlapped with non-queue. If a queue tag is not finished and another same tag command is received, the drive will response with error to inform host a duplicated tag is received.

Error information is reported according to the SATA II specification. A read Log Extended command with log page 10 is required to retrieve the error information.

8.2.40 Write Long (32h)

This command is obsolete in the ATA7 specification. The supporting of this command is for backward compatibility purpose. The use of this command is beyond the ATA standard and not recommended by the manufacturer.

This command is similar to the Write Sectors command, except that it writes the data and the ECC bytes directly from the sector buffer; the drive does not generate the ECC bytes itself. Only single sector Write Long operations are supported. The transfer of the ECC bytes shall be 8 bits wide and 4 or device native ECC bytes length.

8.2.41 Write Multiple Command (C5h, 39h: extended)

This command is similar to the Write Sectors command. Interrupts are not presented on each sector but on the transfer of a block which contains the number of sectors defined by Set Multiple.

Command execution is identical to the Write Sectors operation, except that the numbers of sectors defined by the Set Multiple command are transferred without intervening interrupts. DRQ qualification of the transfer is required only at the start of the data block, not on each sector.

The block count of sectors to be transferred without intervening interrupts is programmed by the Set Multiple Mode command, which shall be executed prior to the Read Multiple command.

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

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

n = Remainder (Sector Count / Block Count)

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

Disk errors encountered during execution of Write Multiple commands are posted after the attempted disk write of the block. Interrupts are generated when DRQ is set at the beginning of each block or partial block.

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

8.2.42 Write Sector(s) (30h, 34h: extended)

This command writes from 1 to 256 sectors, as specified in the Sector Count register (a sector count of zero requests 256 sectors), beginning at the specified sector. Refer to Section 6.7 for the DRQ, IRQ and BSY protocol on data transfers.

If the drive is not already on the desired track, an implied seek is performed. Once at the desired track, the drive searches for the appropriate ID field.

If retries are disabled and two index pulses have occurred without error-free reading of the requested ID, an ID Not Found error is posted.

If retries are enabled, up to a predefined number of attempts may be made to read the requested ID before posting an error.

If the ID is read correctly, the data loaded in the buffer is written to the data field of the sector, followed by the ECC bytes. Upon command completion, the Command Block registers contain the cylinder, head, and sector number of the last sector written in CHS mode or the logical block address in LBA mode.

If an error occurs during a write of more than one sector, writing terminates at the sector where the error occurs. The Command Block registers contain the cylinder, head, and sector number of the sector where the error occurred in CHS mode or the logical block address in LBA mode. The host may then read the command block to determine what error has occurred and on which sector it occurred.

CHAPTER 9 MAINTENANCE

9.1 General Information

The Seagate Barracuda HDD attains high reliability and quality performance through their innovative design and extensive use of latest microelectronic technology. Their outstanding rugged design allows fast, easy sub-assembly replacement without adjustments outside the factory. However, one needs to treat them as high precision delicate ESD sensitive equipment. Inappropriate handling particularly during HDD installation can cause problems which may lead to catastrophic data integrity issues.

9.2 Maintenance Precautions

1. When servicing a drive, the authorized service technician should observe the following precautions to avoid damage to the drive or personal injury. Please obey all Safety, ESD, handling rules as the HDDs are very delicate equipment.

2. Never attempt to open the sealed compartment of the Barracuda. You will highly contaminate the drive leading to head crash and lose product warranty.

3. Do not lift the Barracuda by the HDD bezel (optional) or by the PCB.

4. Handle the HDD with utmost care as the components inside can be damaged, otherwise. Although the recording heads have been retracted away from the data band of the media during machine power off, one can cause heads to slap on the media by tapping it, for example, with a screw driver. This short duration shock may look as seemingly innocuous as gentle banging the drive tower. This can result in another potential damages. This can cause wiring bonding losing contact etc. on the IC.

5. Avoid electro-static discharge (ESD) when handling the Barracuda drives. It is recommended to wear an ESD wrist strap.

6. Avoid being in contact physically close to ESD or ground the ESD sensitive components on the PCB which is located at the bottom side. It does not take much electrostatic potential to damage these components.

7. Observe the environmental operating and storage requirements specified for this product. See section 3.6 for details.

8. If it becomes necessary to move your computer system, turn off the power to allow heads retrieve away from the data zone to park the heads in landing zone and latch the actuator. Please wait approximately 20 seconds after disengaging power to ensure that the motor motion and latching action comes to a complete stop.

9. Back up the stored data regularly. Seagate assumes no responsibility for any data loss from computer misuse or virus. For information about back-up and restore procedures, consult your PC Operating system manual.

9.3 Service and Repair

To determine the warranty for a specific drive, use a web browser to access the following web page http://www.seagate.com/www/en-us/support/warranty_&_returns_assistance
From this page, click on the “Verify Your Warranty” link. You will be asked to provide the drive serial number, model number (or part number) and country of purchase. The system will display the warranty information for your drive
.

CHAPTER 10 GLOSSARY

The following contains useful acronyms or abbreviations described in this manual.

Abbreviation	Description
AAM	Automatic Acoustic Management
AGC	Automatic Gain Control
ASC	Asymmetry Correction Circuit- refers to amplitude symmetry correction
ATA	Advanced Technology Attachment
Bit	lowest count of information (8 bits= 1 Byte)
BPI	Bits per lineal inch
Byte	8 bits of data
CHS	Cylindrical Head Sector
dB	Decibel
DMA	Direct Memory Access
ECC	Error Correction Code
FCI	Flux change per lineal inch (magnetic transitions)
FIR	Finite Impulse Response
GB	Giga byte (1 billion bytes of data)
Hz	Hertz (cycle/ sec)
IDE	Integrated Drive Electronics
KB	1,000 bytes of data
Lb	Weight in pounds
LBA	Logical block address
M	Meter (39.37")
mA	(.001 Ampere)
Mb/s	1 million of bits of data transferred in a given second
MB/s	1 million bytes of data transferred in a given second
MTBF	Mean time between failure
MTTF	Mean time to failure
mV	(.001 volt)
ns	(1 billionth of a second)
PIO	Programmed I/O, a method of transferring data between two devices
	This uses the computer's main processor as part of the data path.
PRML	Partial Response Max. Likelihood encoding to increase linear density.
RPM	revolution per minute
SATA	Serial Advanced Technology Attachment
SMART	Self monitoring Analyzing Reporting Technology
TPI	Tracks Per Inch
V	Volt
W	Watts

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