



.....

Barracuda ATA II Family

.....

ST330630A, ST320420A

.....

ST315320A, ST310210A

.....

Ultra ATA Interface Drives

.....

Product Manual

.....

.....
Barracuda ATA II Family
.....

ST330630A, ST320420A
.....

ST315320A, ST310210A
.....

Ultra ATA Interface Drives
.....

Product Manual
.....

BARRACUDA

© 2000 Seagate Technology, Inc. All rights reserved

Publication Number: 20400151-001, Rev. B, May 2000

Seagate, Seagate Technology, the Seagate logo and Barracuda are registered trademarks of Seagate Technology, Inc. Other product names are registered trademarks or trademarks of their owners.

Seagate reserves the right to change, without notice, product offerings or specifications. No part of this publication may be reproduced in any form without written permission from Seagate Technology, Inc.

Contents

Introduction	1
Specification summary table	2
1.0 Drive specifications	5
1.1 Formatted capacity	5
1.1.1 Default logical geometry	5
1.2 Physical organization	5
1.3 Recording and interface technology	6
1.4 Physical characteristics	6
1.5 Seek time	6
1.6 Start/stop times	7
1.7 Power specifications	7
1.7.1 Power consumption	7
1.7.2 Conducted noise	10
1.7.3 Voltage tolerance	10
1.7.4 Power-management modes	10
1.8 Environmental tolerances	11
1.8.1 Ambient temperature	11
1.8.2 Temperature gradient	12
1.8.3 Humidity	12
1.8.4 Altitude	12
1.8.5 Shock	12
1.8.6 Vibration	13
1.9 Drive acoustics	13
1.10 Electromagnetic immunity	14
1.11 Reliability	14
1.12 Agency certification	15
1.12.1 Safety certification	15
1.12.2 Electromagnetic compatibility	15

1.12.3 FCC verification	15
2.0 Configuring and mounting the drive	17
2.1 Handling and static-discharge precautions	17
2.2 Jumper settings	18
2.2.1 Master/slave configuration	18
2.2.2 Cable-select option	19
2.2.3 Alternate capacity jumper	19
2.2.4 Ultra ATA/66 cable	19
2.3 Drive mounting	19
3.0 ATA interface	21
3.1 ATA interface signals and connector pins	21
3.1.1 Supported ATA commands	23
3.1.2 Identify Device command	24
3.1.3 Set Features command	29
3.1.4 S.M.A.R.T. commands	30

Figures

Figure 1. Typical startup and operation current profile	9
Figure 2. Master/slave jumper settings	18
Figure 3. Mounting dimensions—top, side and end view	20
Figure 4. I/O pins and supported ATA signals.	22

Introduction

This manual describes the functional, mechanical and interface specifications for the ST330630A, ST320420A, ST315320A and the ST310210A. These drives provide the following key features:

- Low power consumption
- Quiet operation
- High instantaneous (burst) data-transfer rates (up to 66.6 Mbytes per second) using Ultra DMA mode 4
- 7,200-RPM spindle speed and 2-Mbyte buffer combine for superior desktop performance
- 300 Gs nonoperating shock
- GMR recording heads and EPRML technology, which provide the drives with increased areal density
- State-of-the-art cache and on-the-fly error-correction algorithms
- Full-track multiple-sector transfer capability without local processor intervention
- Support for S.M.A.R.T. drive monitoring and reporting
- Support for Read Multiple and Write Multiple commands
- Support for autodetection of master/slave drives that use cable select (CSEL)
- The SeaShield® protective cover shields the drive against electrostatic discharge (ESD) and other handling damage. It also includes installation instructions and jumper settings.

Specification summary table

The specifications listed in this table are for quick reference. For details on specification measurement or definition, see the appropriate section of this manual.

Drive Specification	ST330630A	ST320420A	ST315320A	ST310210A
Guaranteed Mbytes ($\times 10^6$ bytes)	30,606	20,404	15,303	10,202
Guaranteed sectors	59,777,640	39,851,760	29,888,820	19,925,880
Bytes per sector	512			
Default sectors per track	63			
Default read/write heads	16	16	16	16
Default cylinders	16,383	16,383	16,383	16,383
Physical read/write heads	6	4	3	2
Discs	3	2	2	1
Recording density BPI (bits/inch max)	357,452			
Track density TPI (tracks/inch)	21,368			
Areal density (Mbits/inch ² max)	7,638			
Spindle speed (RPM)	7,200			
Internal data-transfer rate (Mbits/sec max)	364			
I/O data-transfer rate (Mbytes/sec max)	66.6			
ATA data-transfer modes supported	PIO modes 0–4 Multiword DMA modes 0–2 Ultra DMA modes 0–4			
Cache buffer	2 Mbytes			
Height (mm max)	26.1			
Width (mm max)	101.8			
Length (mm max)	147.0			
Weight (typical)	544 grams (1.2 lb)			
Average latency (msec)	4.16 msec			
Power-on to ready (sec typical)	11 sec			

Drive Specification	ST330630A	ST320420A	ST315320A	ST310210A
Standby to ready (sec typical)	10 sec			
Startup current (typical) 12V (peak)	2.4 amps	2.0 amps		
Track-to-track seek time (msec typical)	1.2			
Average seek time (read, msec typical)	8.2			
Full-stroke seek time (msec max)	17.8 (read), 19.3 (write)			
Seek power (typical)	12.5 watts	11.6 watts		
Read/Write power (typical)	9.7 watts	8.5 watts		
Idle mode (typical)	8.0 watts	7.0 watts		
Standby mode	1.5 watts (typical), 1.7 watts (max)			
Sleep mode	0.8 watts (typical), 0.9 watts (max)			
Voltage tolerance (including noise)	5V \pm 5% – 0.7 amps max 12V + 10%, – 5% – 2.4 amps max			
Ambient temperature	0° to 55°C (op.), –40° to 65°C (nonop.) 5° to 55°C (op. for FDB motor)			
Temperature gradient (°C per hour max)	20°C			
Relative humidity (op. and nonop.)	8% to 80% (op.) 5% to 90% (nonop.)			
Relative humidity gradient	30% per hour max			
Wet bulb temperature (°C max)	29.4 (op.), 29.4 (nonop.)			
Altitude, operating	–122 m to 3,048 m (–400 ft to 10,000+ ft)			
Altitude (meters below mean sea level, max)	–122 m to 12,192 m (–400 ft to 40,000+ ft)			
Shock, operating (Gs max at 2 msec)	63			
Shock, nonoperating (Gs max at 2 msec)	300 Gs			

Drive Specification	ST330630A	ST320420A	ST315320A	ST310210A
Vibration, operating	0.5 Gs (0 to peak, 5–300 Hz)			
Vibration, nonoperating	5 Gs (0 to peak, 5–300 Hz)			
Drive acoustics Sound pressure (dBA) Idle mode Seek mode	34.0 (typical), 39.0 (max) 39.0 (typical), 43.5 (max)			
Nonrecoverable read errors	1 per 10 ¹⁴ bits read			
Mean time between failures (power-on hours)	500,000			
Contact start-stop cycles (25°C, 40% relative humidity)	50,000			
SeaShield	Yes			

1.0 Drive specifications

Unless otherwise noted, all specifications are measured under ambient conditions, at 25°C, and nominal power. For convenience, the phrases *the drive* and *this drive* are used throughout this manual to indicate the ST330630A, ST320420A, ST315320A and the ST310210A.

1.1 Formatted capacity

Drive Model	Guaranteed Mbytes (1 Mbyte = 10 ⁶ bytes)	Guaranteed sectors	Bytes per sector
ST330630A	30,606	59,777,640	512
ST320420A	20,404	39,851,760	512
ST315320A	15,303	29,888,820	512
ST310210A	10,202	19,925,880	512

1.1.1 Default logical geometry

CHS Mode	Cylinders	Read/Write heads	Sectors per track
ST330630A	16,383	16	63
ST320420A	16,383	16	63
ST315329A	16,383	16	63
ST310210A	16,383	16	63

LBA Mode

When addressing these drives in LBA mode, all blocks (sectors) are consecutively numbered from 0 to $n-1$, where n is the number of guaranteed sectors as defined above.

1.2 Physical organization

Drive Model	Read/Write heads (GMR)	Number of discs
ST330630A	6	3
ST320420A	4	2
ST315320A	3	2
ST310210A	2	1

1.3 Recording and interface technology

Interface	ATA
Recording method	16/17 EPRML
Recording density BPI (bits/inch)	357,452
Track density TPI (tracks/inch)	21,368
Areal density (Mbits/inch ² max)	7,638
Spindle speed (RPM) ($\pm 0.2\%$)	7,200
Internal data-transfer rate (Mbits/sec max)	364
I/O data-transfer rate (Mbytes/sec max)	16.6 (PIO mode 4) 66.6 (Ultra DMA mode 4)
Interleave	1:1
Cache buffer	2 Mbytes

1.4 Physical characteristics

Drive Specification	ST330630A, ST320420A, ST315320A, ST310210A
Maximum height (mm) (inches)	26.1 1.028
Maximum width (mm) (inches)	101.8 4.020
Maximum length (mm) (inches)	147.0 5.78
Typical weight (grams) (pounds)	544 1.2

1.5 Seek time

Seek measurements are taken with nominal power at 25°C ambient temperature. All times are measured using drive diagnostics. The specifications in the table below are defined as follows:

- Track-to-track seek time is an average of all possible single-track seeks in both directions.
- Average seek time is a true statistical random average of at least 5,000 measurements of seeks between random tracks, less overhead.

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

Typical seek times (msec)	Read	Write
Track-to-track	1.2	1.9
Average	8.2	9.5
Full-stroke (max)	17.8	19.3
Average latency: 4.16 msec	—	—

Note. These drives are designed to consistently meet the seek times represented in this manual. Physical seeks, regardless of mode (such as track-to-track and average) are expected to meet or exceed the noted values. However, due to the manner in which these drives are formatted, benchmark tests that include command overhead or measure logical seeks may produce results that vary from these specifications.

1.6 Start/stop times

Power-on to Ready (sec)	11 (typical)
Standby to Ready (sec)	10 (typical)
Ready to spindle stop (sec)	8 (typical)

1.7 Power specifications

The drive receives DC power (+5V or +12V) through a four-pin standard drive power connector.

1.7.1 Power consumption

Power requirements for the drives are listed in the table on page 9. Typical power measurements are based on an average of drives tested, under nominal conditions, using 5.0V input voltage at 25°C ambient temperature.

- **Spinup power**

Spinup power is measured from the time of power-on to the time that the drive spindle reaches operating speed.

- **Seek Mode**

During seek mode, the read/write actuator arm moves toward a specific position on the disc surface and does not execute a read or

write operation. Servo electronics are active. Seek mode power represents the worst-case power consumption, using only random seeks with read or write latency time. This mode is not typical and is provided for worst-case information.

- **Read/Write power and current**

Read/write power is measured with the heads on track, based on a 16-sector write followed by a 32-msec delay, then a 16-sector read followed by a 32-msec delay.

- **Operating power and current**

Operating power is measured using 40 percent random seeks, 40 percent read/write mode (1 write for each 10 reads) and 20 percent drive inactive.

- **Idle mode power**

Idle mode power is measured with the drive up to speed, with servo electronics active and with the heads in a random track location.

- **Standby mode**

During Standby mode, the drive accepts commands, but the drive is not spinning, and the servo and read/write electronics are in power-down mode.

ST320420A, ST315320A and ST310210A		Typical Amps RMS	
Power Mode	Typical Watts RMS	5V	12V
Spinup	—	—	2.0 (peak)
Seeking (Random, no read/write)	11.6	0.605	0.713
Operating (read/write)	8.5	0.609	0.449
Idle	7.0	0.480	0.384
Standby	1.5	0.258	0.007
Sleep	0.8	0.149	0.007
ST330630A		Typical Amps RMS	
Power Mode	Typical Watts RMS	5V	12V
Spinup	—	—	2.4 (peak)
Seeking (Random, no read/write)	12.5	0.602	0.793
Operating (read/write)	9.7	0.619	0.544
Idle	8.0	0.533	0.473
Standby	1.5	0.254	0.006
Sleep	0.8	0.145	0.006

1.7.1.1 Typical current profile

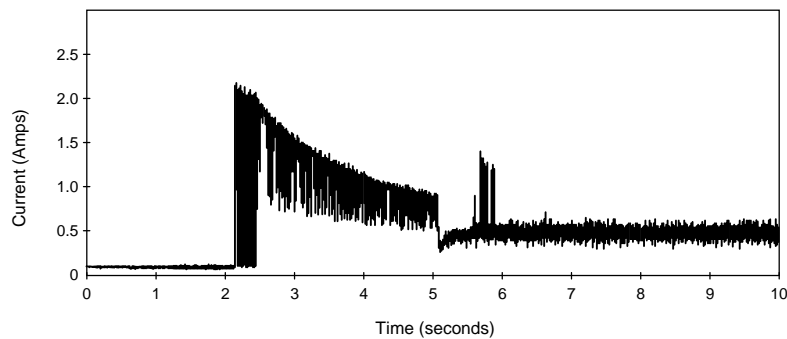


Figure 1. Typical startup and operation current profile

1.7.2 Conducted noise

Input noise ripple is measured at the host system power supply across an equivalent 80-ohm resistive load on the +12 volt line or an equivalent 15-ohm resistive load on the +5 volt line.

- Using 12-volt power, the drive is expected to operate with a maximum of 120 mV peak-to-peak square-wave injected noise at up to 10 MHz.
- Using 5-volt power, the drive is expected to operate with a maximum of 100 mV peak-to-peak square-wave injected noise at up to 10 MHz.

Note. Equivalent resistance is calculated by dividing the nominal voltage by the typical RMS read/write current.

1.7.3 Voltage tolerance

Voltage tolerance (including noise):

5V \pm 5% 0.7 amps max

12V + 10%, - 5% 2.4 amps max

1.7.4 Power-management modes

The drive provides programmable power management to provide greater energy efficiency. In most systems, you can control power management through the system setup program. The drive features the following power-management modes:

Power Modes	Heads	Spindle	Buffer
Active	Tracking	Rotating	Enabled
Idle	Tracking	Rotating	Enabled
Standby	Parked	Stopped	Enabled
Sleep	Parked	Stopped	Disabled

- **Active mode**

The drive is in Active mode during the read/write and seek operations.

- **Idle mode**

The buffer remains enabled, and the drive accepts all commands and returns to Active mode any time disc access is necessary.

- **Standby mode**

The drive enters Standby mode when the host sends a Standby Immediate command. If the host has set the standby timer, the drive can also enter Standby mode automatically after the drive has been inactive for a specifiable length of time. The standby timer delay is established using a Standby or Idle command. In Standby mode, the drive buffer is enabled, the heads are parked and the spindle is at rest. The drive accepts all commands and returns to Active mode any time disc access is necessary.

- **Sleep mode**

The drive enters Sleep mode after receiving a Sleep command from the host. In Sleep mode, the drive buffer is disabled, the heads are parked and the spindle is at rest. The drive leaves Sleep mode after it receives a Hard Reset or Soft Reset from the host. After receiving a reset, the drive exits Sleep mode and enters Active mode with all current translation parameters intact.

- **Idle and Standby timers**

Each time the drive performs an Active function (read, write or seek), the standby timer is reinitialized and begins counting down from its specified delay times to zero. If the standby timer reaches zero before any drive activity is required, the drive makes a transition to Standby mode. In both Idle and Standby mode, the drive accepts all commands and returns to Active mode when disc access is necessary.

1.8 Environmental tolerances

1.8.1 Ambient temperature

Ambient temperature is defined as the temperature of the environment immediately surrounding the drive. Actual drive case temperature should not exceed 69°C (156°F) within the operating ambient conditions. Recommended measurement locations are shown in Figure 3 on page 20.

Above 1,000 feet (305 meters), the maximum temperature is derated linearly to 112°F (44°C) at 10,000 feet (3,048 meters).

Operating	0° to 55°C (32° to 131°F)
	5° to 55°C (41° to 131°F) Fluid dynamic bearing motor (FDB)
Nonoperating	−40° to 65°C (−40° to 149°F)

1.8.2 Temperature gradient

Operating/Nonoperating 20°C/hr (36°F/hour) max,
without condensation

1.8.3 Humidity

1.8.3.1 Relative Humidity

Operating 8% to 80% noncondensing (30% per hour max)

Nonoperating 5% to 90% noncondensing (30% per hour max)

1.8.3.2 Wet bulb temperature

Operating 29.4°C (84°F) max

Nonoperating 40.0°C (104°F) max

1.8.4 Altitude

Operating -122 m to 3,048 m (-400 ft to 10,000+ ft)

Nonoperating -122 m to 12,192 m (-400 ft to 40,000+ ft)

1.8.5 Shock

All shock specifications assume that the drive is mounted securely with the input shock applied at the drive mounting screws. Shock may be applied in the X, Y or Z axis.

1.8.5.1 Operating shock

These drives comply with the performance levels specified in this document when subjected to a maximum operating shock of 63 Gs (based on half-sine shock pulses of 2 msec). Shocks should not be repeated more than two times per second.

1.8.5.2 Nonoperating shock

The nonoperating shock level that the drive can experience without incurring physical damage or degradation in performance when subsequently put into operation is 300 Gs (based on a nonrepetitive half-sine shock pulse of 2 msec duration).

1.8.6 Vibration

All vibration specifications assume that the drive is mounted securely with the input vibration applied at the drive mounting screws. Vibration may be applied in the X, Y or Z axis.

1.8.6.1 Operating vibration

The following table lists the maximum vibration levels that the drive may experience while meeting the performance standards specified in this document.

5–22 Hz	0.010-inch displacement (zero to peak)
22–300 Hz	0.5 Gs acceleration (zero to peak)

1.8.6.2 Nonoperating vibration

The following table lists the maximum nonoperating vibration that the drive may experience without incurring physical damage or degradation in performance when subsequently put into operation.

5–22 Hz	0.10-inch displacement (zero to peak)
22–300 Hz	5.0 Gs acceleration (zero to peak)

1.9 Drive acoustics

Drive acoustics are measured as overall A-weighted acoustic sound power levels (no pure tones). All measurements are generally consistent with ISO document 7779. Sound power measurements were taken under essentially free-field conditions over a reflecting plane. For all tests, the drive was oriented with the cover facing upward.

Note. For seek mode tests, the drive was placed in seek mode only. The number of seeks per second is defined by the following equation:

$$(\text{Number of seeks per second} = 0.4 / (\text{average latency} + \text{average access time}))$$

Acoustic mode	Idle mode	Seek mode
Sound pressure (dBA)	34.0 (typ) 39.0 (max)	39.0 (typ) 43.5 (max)

1.10 Electromagnetic immunity

When properly installed in a representative host system, the drive operates without errors or degradation in performance when subjected to the radio frequency (RF) environments defined in the following table:

Test	Description	Performance Level	Reference Standard
Electrostatic discharge	Contact, HCP, VCP: ± 4 kV; Air: ± 8 kV	B	EN 61000-4-2: 95
Radiated RF immunity	80 to 1000 MHz, 3 V/m, 80% AM with 1 kHz sine 900 MHz, 3 V/m, 50% pulse modulation @ 200 Hz	A	EN 61000-4-3: 96 ENV 50204: 95
Electrical fast transient	± 1 kV on AC mains, ± 0.5 kV on external I/O	B	EN 61000-4-4: 95
Surge immunity	± 1 kV differential, ± 2 kV common, AC mains	B	EN 61000-4-5: 95
Conducted RF immunity	150 kHz to 80 MHz, 3 Vrms, 80% AM with 1 kHz sine	A	EN 61000-4-6: 97
Voltage dips, interrupts	0% open, 5 seconds 0% short, 5 seconds 40%, 0.10 seconds 70%, 0.01 seconds	C C C B	EN 61000-4-11: 94

1.11 Reliability

Nonrecoverable read errors	1 per 10^{14} bits read, max
Mean time between failures	500,000 power-on hours (nominal power, 25°C ambient temperature)
Contact start-stop cycles	50,000 cycles (at nominal voltage and temperature, with 60 cycles per hour and a 50% duty cycle)
Preventive maintenance	None required

1.12 Agency certification

1.12.1 Safety certification

The drives are recognized in accordance with UL 1950 and CSA C22.2 (950) and meet all applicable sections of IEC950 and EN 60950 as tested by TUV North America.

1.12.2 Electromagnetic compatibility

Hard drives that display the CE mark comply with the European Union (EU) requirements specified in the Electromagnetic Compatibility Directive (89/336/EEC). Testing is performed to the levels specified by the product standards for Information Technology Equipment (ITE). Emission levels are defined by EN 55022, Class B and the immunity levels are defined by EN 55024.

Seagate uses an independent laboratory to confirm compliance with the EC directives specified in the previous paragraph. Drives are tested in representative end-user systems. Although CE-marked Seagate drives comply with the directives when used in the test systems, we cannot guarantee that all systems will comply with the directives. The drive is designed for operation inside a properly designed enclosure, with properly shielded I/O cable (if necessary) and terminators on all unused I/O ports. Computer manufacturers and system integrators should confirm EMC compliance and provide CE marking for their products.

Australian C-Tick (N176)

If these models have the C-Tick marking, they comply with the Australia/New Zealand Standard AS/NZS3548 1995 and meet the Electromagnetic Compatibility (EMC) Framework requirements of the Australian Communication Authority (ACA).

1.12.3 FCC verification

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

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

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

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

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

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

2.0 Configuring and mounting the drive

This section contains the specifications and instructions for configuring and mounting the drive.

2.1 Handling and static-discharge precautions

After unpacking, and before installation, the drive may be exposed to potential handling and electrostatic discharge (ESD) hazards. Observe the following standard handling and static-discharge precautions:

Caution:

- The SeaShell™ replaces electrostatic discharge (ESD) bags. The SeaShell package is a shock-ribbed, transparent clamshell enclosure that limits a drive's exposure to ESD and also protects against external shocks and stresses. The design permits attaching cables, software loading and label/barcode scanning without removing the drive from the SeaShell. This minimizes handling damage. Keep the drive in the SeaShell package until you are ready for installation.
- The drive has a cover called SeaShield®. Do not remove this permanent cover—it protects the drive from electrostatic discharge (ESD) and minor impact damage. The SeaShield cover also includes installation instructions and jumper settings. Removing the SeaShield voids the warranty.
- Before handling the drive, put on a grounded wrist strap, or ground yourself frequently by touching the metal chassis of a computer that is plugged into a grounded outlet. Wear a grounded wrist strap throughout the entire installation procedure.
- Handle the drive by its edges or frame *only*.
- The drive is extremely fragile—handle it with care. Do not press down on the drive top cover.
- Always rest the drive on a padded, antistatic surface until you mount it in the computer.
- Do not touch the connector pins or the printed circuit board.
- Do not remove the factory-installed labels from the drive or cover them with additional labels. Removal voids the warranty. Some factory-installed labels contain information needed to service the drive. Other labels are used to seal out dirt and contamination.

2.2 Jumper settings

2.2.1 Master/slave configuration

The options jumper block shown in Figure 2 is used to configure the drive for operation. It is the 8-pin dual header between the interface connector and the power connector. Use the following settings to configure the drive as a master or a slave.

Master or single drive. The drive is configured at the factory for a master or single-drive operation with a jumper set on pins 7 and 8.

Drive as slave. Remove all jumpers.

Drive as master with a non-ATA-compatible slave.

Use this jumper setting *only* if the drive does not work as a master with no jumpers installed.

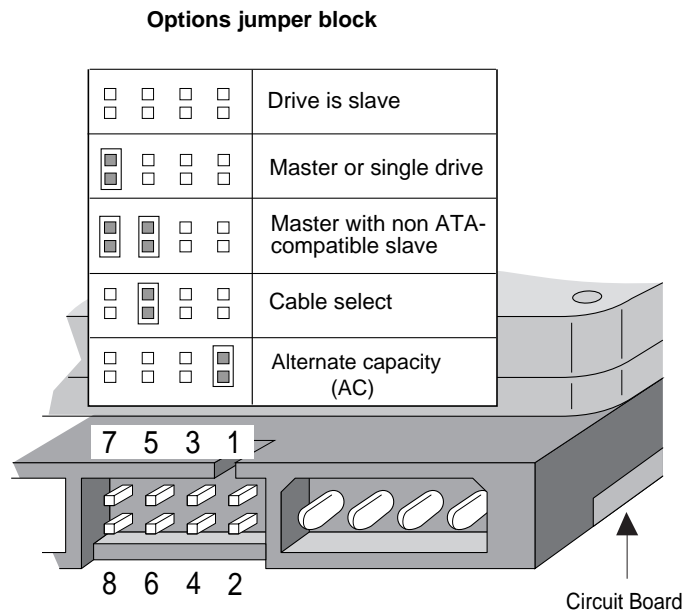


Figure 2. Master/slave jumper settings

2.2.2 Cable-select option

Computers that use cable-select determine the master and slave drives by selecting or deselecting pin 28, CSEL, on the interface bus. Master and slave drives are determined by their physical position on the cable. To enable cable select, set a jumper on pins 5 and 6 as shown in Figure 2 on page 18. Refer to your computer manual to determine whether your computer supports this option.

2.2.3 Alternate capacity jumper

Some older computers may “hang” if their BIOS detects a hard drive that has more than 4,092 cylinders at startup. To eliminate this problem, the drive includes a capacity-limiting jumper that sets the drive’s default translation geometry to 4,092 cylinders. This limits the drive’s capacity to 2.1 Gbytes unless third-party software is used.

2.2.4 Ultra ATA/66 cable

An 80-conductor 40-pin cable is required to run Ultra DMA mode 3 and mode 4. This cable uses even-numbered conductors connected to the ground pins to improve signal integrity.

Note. The drive supports both host and drive cable detection. The host detects the 80-conductor cable by sampling pin 34, CBLID–, on the interface bus. The drive detects the 80-conductor cable by sensing a capacitor at the host side through the CBLID– signal. The result is reported in a Fast Rise Detected bit (bit 13 of word 93 in the Identify drive parameter block).

2.3 Drive mounting

You can mount the drive in any orientation using four screws in the side-mounting holes or four screws in the bottom-mounting holes. See Figure 4 on page 20 for drive mounting dimensions. Follow these important mounting precautions when mounting the drive:

- Allow a minimum clearance of 0.030 inches (0.76 mm) around the entire perimeter of the drive for cooling.
- Use only 6-32 UNC mounting screws.
- The screws should be inserted no more than 0.200 inch (5.08 mm) into the bottom mounting holes and no more than 0.14 inch (3.55 mm) into the side mounting holes.
- Do not overtighten the mounting screws (maximum torque: 6 inch-lb).
- Do not use a drive interface cable that is more than 18 inches long.

Note. Dimensions are shown in mm (inches)

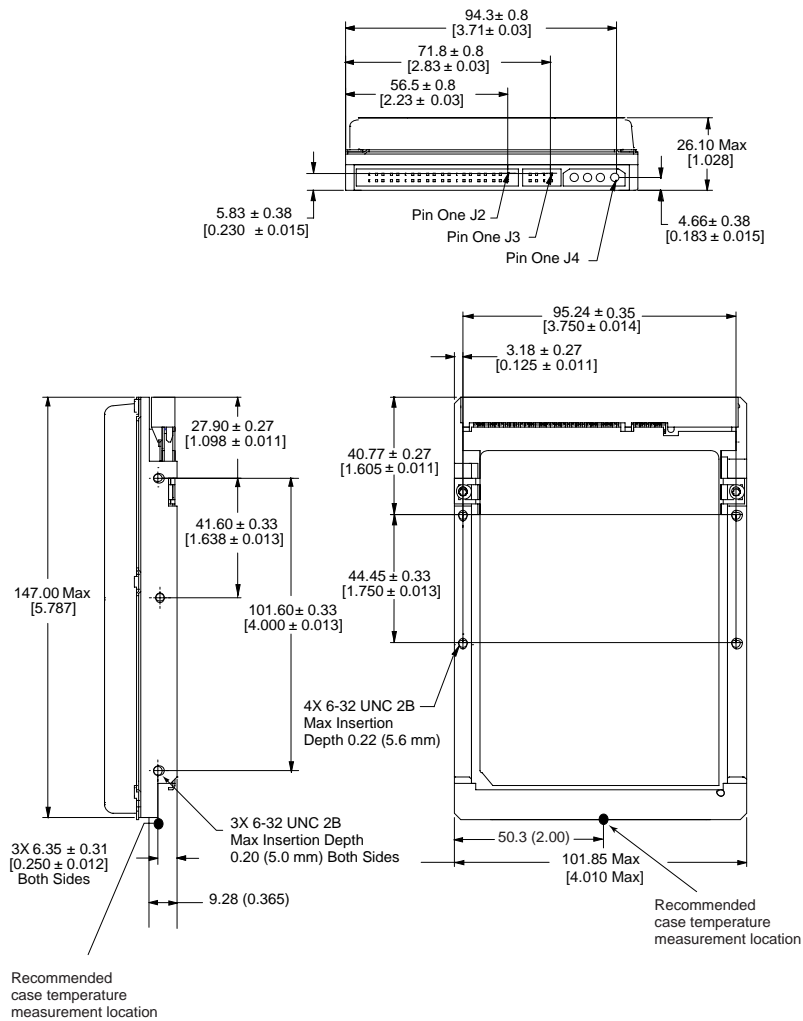


Figure 3. Mounting dimensions—top, side and end view

3.0 ATA interface

These drives use the industry-standard ATA task file interface that supports 16-bit data transfers. It supports ATA programmed input/output (PIO) modes 0–4; multiword DMA modes 0–2, and Ultra DMA modes 0–4. The drive also supports the use of the IORDY signal to provide reliable high-speed data transfers.

You can use a daisy-chain cable to connect two drives to a single AT host bus. For detailed information about the ATA interface, refer to the draft of *AT Attachment with Packet Interface Extension (ATA/ATAPI-4)*, *NCITS T13 1153D*, subsequently referred to as the *Draft ATA-4 Standard*.

3.1 ATA interface signals and connector pins

Figure 4 on page 22 summarizes the signals on the ATA interface connector that the drive supports. For a detailed description of these signals, refer to the *Draft ATA-4 Standard*.

Drive pin #	Signal name	Host pin # and signal description
1	Reset	1 Hardware Reset
2	Ground	2 Ground
3	DD7	3 Host Data Bus Bit 7
4	DD8	4 Host Data Bus Bit 8
5	DD6	5 Host Data Bus Bit 6
6	DD9	6 Host Data Bus Bit 9
7	DD5	7 Host Data Bus Bit 5
8	DD10	8 Host Data Bus Bit 10
9	DD4	9 Host Data Bus Bit 4
10	DD11	10 Host Data Bus Bit 11
11	DD3	11 Host Data Bus Bit 3
12	DD12	12 Host Data Bus Bit 12
13	DD2	13 Host Data Bus Bit 2
14	DD13	14 Host Data Bus Bit 13
15	DD1	15 Host Data Bus Bit 1
16	DD14	16 Host Data Bus Bit 14
17	DD0	17 Host Data Bus Bit 0
18	DD15	18 Device Data (15:0)
19	Ground	19 Ground
20	(removed)	20 (No Pin)
21	DMARQ	21 DMA Request
22	Ground	22 Ground
23	DIOW- STOP	23 Device I/O Write: Stop Ultra DMA Burst
24	Ground	24 Ground
25	DIOR- HDMARDY- HSTROBE	25 Device I/O Read: Host Ultra DMA Ready: Host Ultra DMA Data Strobe
26	Ground	26 Ground
27	IORDY- DDMARDY- DSTROBE	27 I/O Channel Ready Device Ultra DMA Ready Device Ultra DMA Data Strobe
28	CSEL	28 Cable Select
29	DMACK-	29 DMA Acknowledge
30	Ground	30 Ground
31	INTRQ	31 Device Interrupt
32	IOCS16-	32 Reserved
33	DA1	33 Host Address Bus Bit 1
34	PDIAG- CBLID-	34 Passed Diagnostics Cable Assembly Type Identifier
35	DA0	35 Device Address (2:0)
36	DA2	36 Device Address (2:0)
37	CS0-	37 Chip Select (1:0)
38	CS1-	38 Chip Select (1:0)
39	DASP-	39 Drive Active/Slave Present
40	Ground	40 Ground

Pins 28, 34 and 39 are used for master-slave communication (details shown below).

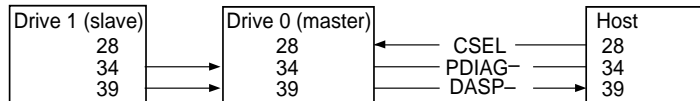


Figure 4. I/O pins and supported ATA signals

3.1.1 Supported ATA commands

The following table lists ATA-standard commands that the drive supports. For a detailed description of the ATA commands, refer to the *Draft ATA-4 Standard*. See Section 3.2.4 on page 30 for details and subcommands used in the S.M.A.R.T. implementation.

Command name	Command code (in hex)
ATA-standard commands	
Download Microcode	92 _H
Execute Device Diagnostics	90 _H
Flush Cache	E7 _H
Format Track	50 _H
Identify Device	EC _H
Initialize Device Parameters	91 _H
Read Buffer	E4 _H
Read DMA	C8 _H , C9 _H
Read Multiple	C4 _H
Read Sectors	20 _H , 21 _H
Read Verify Sectors	40 _H , 41 _H
Recalibrate	10 _H
Seek	70 _H
Set Features	EF _H
Set Multiple Mode	C6 _H
S.M.A.R.T.	B0 _H
Write Buffer	E8 _H
Write DMA	CA _H , CB _H
Write Multiple	C5 _H
Write Sectors	30 _H , 31 _H

Command name	Command code (in hex)
ATA-standard power-management commands	
Check Power Mode	98 _H or E5 _H
Idle	97 _H or E3 _H
Idle Immediate	95 _H or E1 _H
Sleep	99 _H or E6 _H
Standby	96 _H or E2 _H
Standby Immediate	94 _H or E0 _H
ATA-standard security commands	
Security Set Password	F1 _H
Security Unlock	F2 _H
Security Erase Prepare	F3 _H
Security Erase Unit	F4 _H
Security Freeze Lock	F5 _H
Security Disable Password	F6 _H

3.1.2 Identify Device command

The Identify Device command (command code EC_H) transfers information about the drive to the host following power up. The data is organized as a single 512-byte block of data, whose contents are shown in the table on page 25. All reserved bits or words should be set to zero. Parameters listed with an “x” are drive-specific or vary with the state of the drive. See Section 1 of this manual for default parameter settings.

The following commands contain drive-specific features that may not be included in the *Draft ATA-4 Standard*.

Word	Description	Value
0	Configuration information: <ul style="list-style-type: none"> • Bit 15: 0 = ATA; 1 = ATAPI • Bit 7: removable media • Bit 6: removable controller • Bit 0: reserved 	0C5A _H
1	Number of logical cylinders	16,383
2	ATA-reserved	0000 _H
3	Number of logical heads	16
4	Retired	0000 _H
5	Retired	0000 _H
6	Number of logical sectors per logical track: 63	003F _H
7–9	Retired	0000 _H
10–19	Serial number: (20 ASCII characters, 0000 _H = none)	ASCII
20	Retired	0000 _H
21	Retired	0400 _H
22	Obsolete	0000 _H
23–26	Firmware revision (8 ASCII character string, padded with blanks to end of string)	x.xx
27–46	Drive model number: (40 ASCII characters, padded with blanks to end of string)	ST330630A ST320420A ST315320A ST310210A
47	(Bits 7–0) Maximum sectors per interrupt on Read multiple and Write multiple (16)	8010 _H
48	Reserved	0000 _H
49	Standard Standby timer, IORDY supported and may be disabled	2F00 _H

Word	Description	Value
50	ATA-reserved	0000 _H
51	PIO data-transfer cycle timing mode	0200 _H
52	Retired	0200 _H
53	Words 54–58, 64–70 and 88 are valid	0007 _H
54	Number of current logical cylinders	xxxx _H
55	Number of current logical heads	xxxx _H
56	Number of current logical sectors per logical track	xxxx _H
57–58	Current capacity in sectors	xxxx _H
59	Number of sectors transferred during a Read Multiple or Write Multiple command	xxxx _H
60–61	Total number of user-addressable LBA sectors available	ST330630A = 59,777,640 ST320420A = 39,851,760 ST315320A = 29,888,820 ST310210A = 19,925,880
62	Retired	0000 _H
63	Multiword DMA active and modes supported (see note following this table)	xx07 _H
64	Advanced PIO modes supported (modes 3 and 4 supported)	0003 _H
65	Minimum multiword DMA transfer cycle time per word (120 nsec)	0078 _H
66	Recommended multiword DMA transfer cycle time per word (120 nsec)	0078 _H

Word	Description	Value
67	Minimum PIO cycle time without IORDY flow control (240 nsec)	00F0 _H
68	Minimum PIO cycle time with IORDY flow control (120 nsec)	0078 _H
69–74	ATA-reserved	0000 _H
75	Queue depth	0000 _H
76–79	ATA-reserved	0000 _H
80	Major version number	001E _H
81	Minor version number	0000 _H
82	Command sets supported	306B _H
83	Command sets supported	4001 _H
84	Command sets support extension	4000 _H
85	Command sets enabled	30xx _H
86	Command sets enabled	0001 _H
87	Command sets enable extension	4000 _H
88	Ultra DMA support and current mode (see note following this table)	xx1F _H
89	Security erase time	0000 _H
90	Enhanced security erase time	0000 _H
91–92	ATA-reserved	0000 _H
93	Hardware Reset Value (see description following this table)	4000 _H
94–127	ATA-reserved	0000 _H

Word	Description	Value
129–159	Seagate-reserved	xxxx _H
160–255	ATA-reserved	0000 _H

Note. See the bit descriptions below for words 63, 88 and 93 of the Identify Drive data:

Description (if bit is set to 1)

Bit Word 63

- 0 Multiword DMA mode 0 is supported.
- 1 Multiword DMA mode 1 is supported.
- 2 Multiword DMA mode 2 is supported.
- 8 Multiword DMA mode 0 is currently active.
- 9 Multiword DMA mode 1 is currently active.
- 10 Multiword DMA mode 2 is currently active.

Bit Word 88

- 0 Ultra DMA mode 0 is supported.
- 1 Ultra DMA mode 1 is supported.
- 2 Ultra DMA mode 2 is supported.
- 3 Ultra DMA mode 3 is supported.
- 4 Ultra DMA mode 4 is supported.
- 8 Ultra DMA mode 0 is currently active.
- 9 Ultra DMA mode 1 is currently active.
- 10 Ultra DMA mode 2 is currently active.
- 11 Ultra DMA mode 3 is currently active.
- 12 Ultra DMA mode 4 is currently active.

Bit Word 93

- 13 1 = 80-conductor cable detected, CBLID above V_{IH}
0 = 40-conductor cable detected, CBLID below V_{IL}

3.1.3 Set Features command

This command controls the implementation of various features that the drive supports. When the drive receives this command, it sets BSY, checks the contents of the Features register, clears BSY and generates an interrupt. If the value in the register does not represent a feature that the drive supports, the command is aborted. Power-on default has the read look-ahead and write caching features enabled. The acceptable values for the Features register are defined as follows:

02 _H	Enable write cache (<i>default</i>).
03 _H	Set transfer mode (based on value in Sector Count register). Sector Count register values:
00 _H	Set PIO mode to default (PIO mode 2).
01 _H	Set PIO mode to default and disable IORDY (PIO mode 2).
08 _H	PIO mode 0
09 _H	PIO mode 1
0A _H	PIO mode 2
0B _H	PIO mode 3
0C _H	PIO mode 4 (<i>default</i>)
20 _H	Multiword DMA mode 0
21 _H	Multiword DMA mode 1
22 _H	Multiword DMA mode 2
40 _H	Ultra DMA mode 0
41 _H	Ultra DMA mode 1
42 _H	Ultra DMA mode 2
43 _H	Ultra DMA mode 3
44 _H	Ultra DMA mode 4
55 _H	Disable read look-ahead (read cache) feature.
82 _H	Disable write cache.
AA _H	Enable read look-ahead (read cache) feature (<i>default</i>).

Note. At power-on, or after a hardware or software reset, the default values of the features are as indicated above.

3.1.4 S.M.A.R.T. commands

S.M.A.R.T. provides near-term failure prediction for disc drives. When S.M.A.R.T. is enabled, the drive monitors predetermined drive attributes that are susceptible to degradation over time. If self-monitoring determines that a failure is likely, S.M.A.R.T. makes a status report available to the host. Not all failures are predictable. S.M.A.R.T. predictability is limited to the attributes the drive can monitor. For more information on S.M.A.R.T. commands and implementation, see the *Draft ATA-4 Standard*.

This drive is shipped with S.M.A.R.T. features disabled. You must have a recent BIOS or software package that supports S.M.A.R.T. to enable this feature. The table below shows the S.M.A.R.T. command codes that the drive uses.

Code in Features Register	S.M.A.R.T. Command
D0 _H	S.M.A.R.T. Read Data
D1 _H	Vendor-specific
D2 _H	S.M.A.R.T. Enable/Disable Attribute Autosave
D3 _H	S.M.A.R.T. Save Attribute Values
D4 _H	S.M.A.R.T. Execute Off-line Immediate
D7 _H	Vendor-specific
D8 _H	S.M.A.R.T. Enable Operations
D9 _H	S.M.A.R.T. Disable Operations
DA _H	S.M.A.R.T. Return Status

Note. If an appropriate code is not written to the Features Register, the command is aborted and 0x04 (abort) is written to the Error register.



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

Publication Number: 20400151-001, Rev. B, Printed in USA