Seagate

ST310014ACE

Ultra ATA Interface Drive

Product Manual

ST310014ACE

Ultra ATA Interface Drive

Product Manual

Publication Number: 100216026, Rev B, July, 2002

Contents

Figures

Introduction

This manual describes the functional, mechanical and interface specifications for the ST310014ACE. This drive provides the following key features:

- Low power consumption
- High instantaneous (burst) data-transfer rates (up to 100 Mbytes per second) using Ultra DMA mode 5
- Giant magnetoresistive (GMR) recording heads and GPRML 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
- Quiet operation
- 350 Gs nonoperating shock
- SeaTools diagnostic software performs a drive self-test that eliminates unnecessary drive returns.
- Support for S.M.A.R.T. drive monitoring and reporting
- Support for drive self-test (DST) with S.M.A.R.T. Execute Off-line Immediate
- Support for Read Multiple and Write Multiple commands
- Support for autodetection of master/slave drives that use cable select (CSEL)

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	ST310014ACE
Formatted Gbytes ($\times 10^6$ bytes)	10.0
Guaranteed sectors	20,005,650
Bytes per sector	512
Default sectors per track	63
Default read/write heads	16
Default cylinders	16,383
Physical read/write heads	1
Discs	1
Recording density BPI (bits/inch max)	376,200
Track density TPI (tracks/inch)	58,000
Areal density (Mbits/inch^2 max)	21,800
Spindle speed (RPM)	5,400
Internal data-transfer rate (Mbits/sec max)	366
I/O data-transfer rate (Mbytes/sec max)	100
ATA data-transfer modes supported	PIO modes 0–4 Multiword DMA modes 0–2 Ultra DMA modes 0–5
Cache buffer (Mbytes)	2
Height (mm max)	19.99
Width (mm max)	101.9
Length (mm max)	147.0
Weight (typical)	455 grams (1.0 lb)
Average seek time (msec typical)	12.7
Track-to-track seek time (msec typical)	1.2 (read) 2.0 (write)
Read/write seek time (msec typical)	18.0 (read) 24.9 (write)
Full-stroke seek time (msec typical)	36.8 (read); 42.0(write)
Power-on to ready (sec max)	7 sec

Drive Specification	ST310014ACE
Standby to ready (sec typical)	6.5 sec
Spindown (sec typical)	10 sec
Startup current (typical)	0.9 amps (5V), 1.9 amps (12V)
Seek power (typical)	6.0 watts
Read/Write power (typical)	5.5 watts
Idle mode power (typical)	4.5 watts
Standby mode power (typical)	1.2 watts
Sleep mode (typical)	1.0 watts
Voltage tolerance (including noise)	5V ± 5%, 12V ± 10%
Ambient temperature	0° to 60°C (op.), –40° to 70°C (nonop.)
Temperature gradient (°C per hour max)	20°C
Relative humidity (op. and nonop.)	5% to 90% (op.) 5% to 95% (nonop.)
Relative humidity gradient	30% per hour max
Wet bulb temperature (°C max)	29.4 (op.), 40.0 (nonop.)
Altitude, operating	–60.96 m to 3,048 m (–200 ft to 10,000+ ft)
Altitude, nonoperating (meters relative to mean sea level)	–121.92 m to 12,192 m (–400 ft to 40,000+ ft)
Shock, operating (Gs max at 2 msec)	63 Gs
Shock, nonoperating (Gs max at 1 and 2 msec)	350 Gs
Vibration, operating	0.5 Gs (0 to peak, 22–350 Hz)
Vibration, nonoperating	5 Gs (0 to peak, 22–350 Hz)
Drive acoustics Sound power in bels	Idle: 2.6 (typical), 2.8 (max) Seek: 2.7 (typical), 2.9 (max)
Nonrecoverable read errors	1 per 10^{13} bits read
Mean time between failures (power-on hours)	600,000
Contact start-stop cycles (25°C, 40% relative humidity)	50,000
SeaShield	No

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 ST310014ACE.

1.1 Formatted capacity

Drive Model	Formatted Gbytes	Guaranteed sectors	Bytes per sector
ST310014ACE	10.0	20,005,650	512

1.1.1 Default logical geometry

CHS Mode	Cylinders	Read/Write heads	Sectors per track
ST310014ACE	16,383	16	63

LBA Mode
When addressing drive 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
ST310014ACE	1	1

1.3 Recording and interface technology

Interface	ATA
Recording method	96/102 GPRML
Recording density BPI (bits/inch)	376,200
Track density TPI (tracks/inch)	58,000
Areal density (Mbits/inch^2 max)	21,800
Spindle speed (RPM) (± 0.2%)	5,400
Internal data-transfer rate (Mbits/sec max)	366

I/O data-transfer rate (Mbytes/sec max)	16.6 (PIO mode 4) 100 (Ultra DMA mode 5)
Interleave	1:1
Cache buffer (Mbytes)	2

1.4 Physical characteristics

Drive Specification		**ST310014ACE**
Maximum height	mm (inches)	19.99 (0.787)
Maximum width	mm (inches)	101.9 (4.01)
Maximum length	mm (inches)	147.0 (5.78)
Typical weight	grams (pounds)	455 (1.0)

1.5 Start/stop times

Power-on to Ready (sec)	6.5 (typical)
Standby to Ready (sec)	6.5 (typical)
Ready to spindle stop (sec)	10 (typical)

1.6 Seek times

Average seek time (msec typical)	12.7
Track-to-track seek time (msec typical)	1.2 (read) 2.0 (write)
Read/write seek time (msec typical)	18.0 (read) 24.9 (write)
Full-stroke seek time (msec typical)	36.8 (read); 42.0(write)
Power-on to ready (sec max)	7 sec

Seek measurements are taken with nominal power at 25°C ambient temperature. All times are measured using drive diagnostics. Seek time specifications 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.

Note. These drives are designed to meet the seek times represented in this manual consistently. 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.

1.7 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**

  The read/write actuator arm moves in a random seek mode, with 80% of the time spent seeking randomly among all the logical blocks, and 20% of the time idle. The current is measured over a 10-second period. No data is read or written during this te**st.**

- **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**
  The read/write actuator arm moves in a random read/write mode, with 80% of the time spent seeking, reading, and writing randomly among all the logical blocks, and 20% of the time idle. The current is measured over a 10-second period.

- **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.

Power Mode	Typical Watts	Typical Amps Means	
		5V	12V
Spinup	—	0.90	1.90
Seek (Random, no read/write)	6.0	0.672	0.220
Operating (read/write)	5.5	0.572	0.220
Idle	4.5	0.468	0.180
Standby	1.2	0.192	0.020
Sleep	1.0	0.157	0.018

Typical current profile

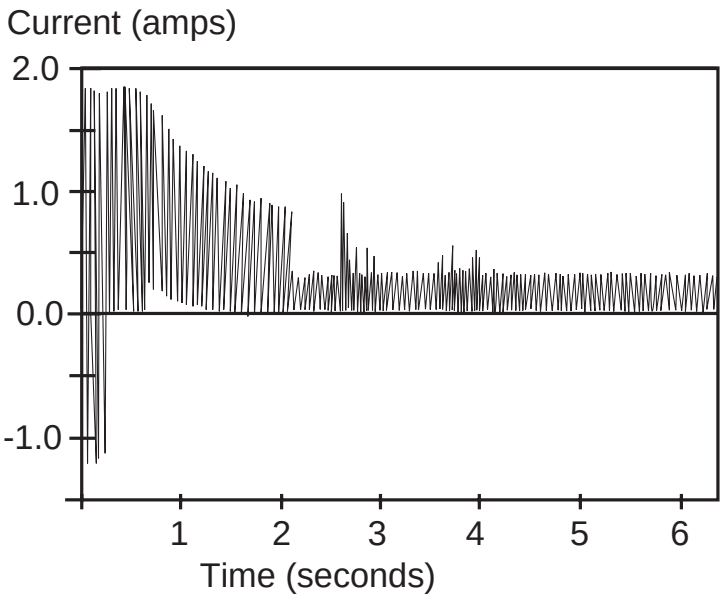

Figure 1. Typical startup and operation current profile

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 ± 5% and 12V ± 10%

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 Standby 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 65°C (149°F) within the operating ambient conditions. Recommended measurement locations are shown in Figure 3 on page 18.

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 60°C (32° to 131°F)
Nonoperating	–40° to 70°C (–40° to 158°F)

1.8.2 Temperature gradient

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

1.8.3 Humidity

1.8.3.1 Relative Humidity

Operating	5% to 90% noncondensing (30% per hour max)
Nonoperating	5% to 95% 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	–60.96 m to 3,048 m (–200 ft to 10,000+ ft)
Nonoperating	–121.92 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 350 Gs (based on nonrepetitive half-sine shock pulses of 1 and 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.

5–21 Hz	0.02-inch displacement (peak to peak)
22–350 Hz	0.5 Gs acceleration (zero to peak)
351–500 Hz	0.25 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.

5–21 Hz	0.2-inch displacement (peak to peak)
22–350 Hz	5.0 Gs acceleration (zero to peak)
351–500 Hz	1.0 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:
(Number of seeks per second = 0.4 / (average latency + average access time)

ST310014ACE

Acoustic mode	**Idle**	**Seek**
Sound power (bels)	2.6 (typ) 2.8 (max)	2.7 (typ) 2.9 (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 1,000 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^{13} bits read, max
Mean time between failures	600,000 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.

Taiwan BSMI

If this drive has the symbol of an arrow inside a circle with a six-digit identifier (D33027) below it, the drive complies with the Chinese National Standard (CNS) 13438 and meets the Electromagnetic Compatibility (EMC) Framework requirements of the Taiwanese Bureau of Standards, Metrology and Inspection (BSMI).

Korean RRL

If this drive has the Korea Ministry of Information and Communication (MIC) logo, it complies with paragraph 1 of Article 11 of the Electromagnetic Compatibility control Regulation and meets the Electromagnetic Compatibility (EMC) Framework requirements of the Radio Research Laboratory (RRL) Ministry of Information and Communication Republic of Korea.

This drive has been tested and complies with the Electromagnetic Interference/Electromagnetic Susceptibility (EMI/EMS) for Class B products. Drives are tested in a representative, end-user system by a Korean-recognized lab.

- EUT name (model numbers): ST310014ACE
- Certificate numbers: E-H011-02-1606 (B)
- Trade name or applicant: Seagate Technology
- Manufacturing date: June 2002
- Manufacturer/nationality: Singapore

Australian C-Tick (N176)

If this drive has the C-Tick marking, it complies with the Australia/New Zealand Standard AS/NZS3548 1995 and meets the Electromagnetic Compatibility (EMC) Framework requirements of the Australian Communication Authority (ACA).

1.12.3 FCC verification

This drive is intended to be contained solely within a personal computer or similar enclosure (not attached as an external device). As such, the 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, LLC 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.
- 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.
Set a jumper on pins 5 and 6 and a jumper on pins 7 and 8. Use this jumper setting *only* if the drive does not work as a master with no jumpers installed.

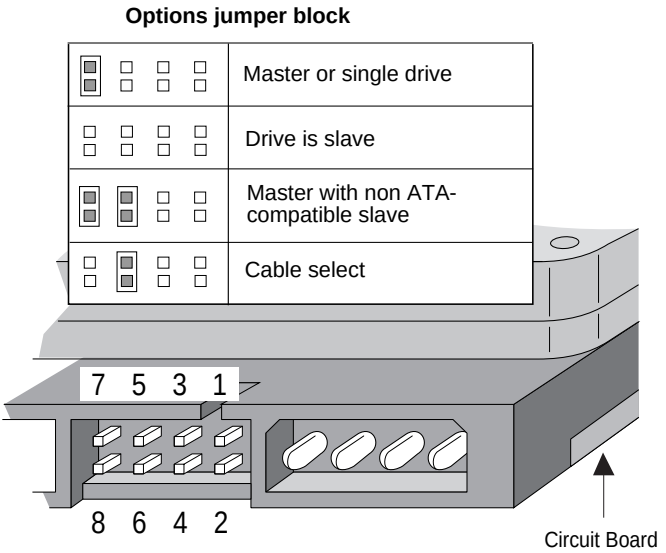

Figure 2. Master/slave jumper settings

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 16. Refer to your computer manual to determine whether your computer supports this option.

2.2.3 Ultra ATA/100 cable

An 80-conductor 40-pin cable is required to run Ultra DMA mode 3, mode 4 and mode 5. This cable uses even-numbered conductors connected to the ground pins to improve signal integrity.

Notes:

1. 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. When using a 40-pin 80-conductor cable, attach the *blue* connector to the motherboard, the *black* connector to the master drive, and the *grey* connector to the slave.

2.1 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 3 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. Insert the screws no more than 0.20 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.

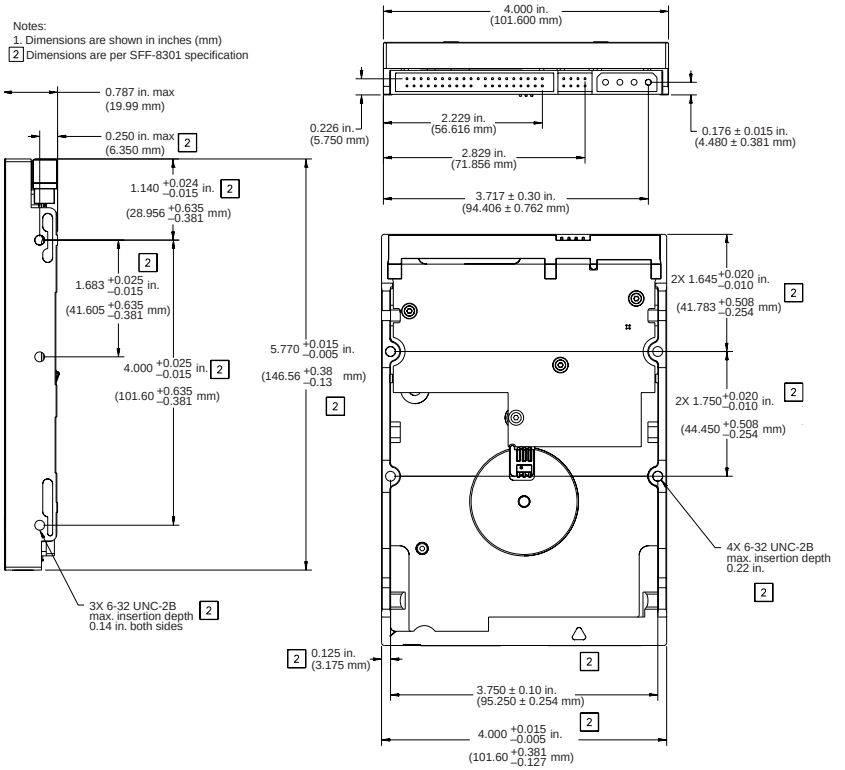

Figure 3. Mounting dimensions—top, side and end view

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 0–5. 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-Rev 6), NCITS T13 1153D,* subsequently referred to as the *Draft ATA-Rev 6 Standard.*

3.1 ATA interface signals and connector pins

Figure 4 on page 20 summarizes the signals on the ATA interface connector that the drive supports. For a detailed description of these signals, refer to the *Draft ATA-Rev 6 Standard.*

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-Rev 6 Standard.* See Section 3.1.4 on page 29 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
Read Native Max Address	$F8_H$
Recalibrate	10_H
Seek	70_H
Set Features	EF_H
Set Multiple Mode	$C6_H$
Set Max Address	$F9_H$
S.M.A.R.T.	$B0_H$
Write Buffer	$E8_H$
Write DMA	$CA_{H,}$ CB_H

Command name	Command code (in hex)
Write Multiple	$C5_H$
Write Sectors	$30_{H,}$ 31_H
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 Drive command

The Identify Drive 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-Rev 6 Standard.*

Word	Description	Value
0	Configuration information: • 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	$C837_H$
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	0004_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)	ST310014ACE
47	Maximum sectors per interrupt on Read multiple and Write multiple (32)	8010_H
48	Reserved	0000_H
49	Standard Standby timer, IORDY supported and may be disabled	$2F00_H$

Word	Description	Value
50	Device-specific standby timer value	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 (see Section 2.2.3 for related information)	1,314,312
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

Word	Description	Value
66	Recommended multiword DMA transfer cycle time per word (120 nsec)	0078_H
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	$007E_H$
81	Minor version number	0000_H
82	Command sets supported	$346B_H$
83	Command sets supported	$4B09_H$
84	Command sets support extension	4003_H
85	Command sets enabled	$xxxx_H$
86	Command sets enabled	$xxxx_H$
87	Command sets enable extension	$xxxx_H$
88	Ultra DMA support and current mode (see note following this table)	$xx3F_H$
89	Security erase time	0000_H
90	Enhanced security erase time	0000_H
91	Advanced Power Management value	0040_H

Word	Description	Value
92	Master Password Revision code	$FFFE_H$
93	Hardware Reset Value (see description following this table)	$xxxx_H$
94	Auto Acoustic Management Setting	$xxxx_H$
95–127	ATA-reserved	0000_H
128	Security Status	0001_H
129–159	Seagate-reserved	$xxxx_H$
160–254	ATA-reserved	0000_H
255	Integrity word	$xxA5_H$

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.

5 Ultra DMA mode 5 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.

13 Ultra DMA mode 5 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}

Bit Word 94

0–7 Current AAM setting

8–15 AAM Power on default

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 *(default).*

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 *(default)*

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

45_H Ultra DMA mode 5

05_H Enable advanced power management.

42_H Auto Acoustic Management

FE_H Performance Seek

80_H Quiet Acoustic Seek

55_H Disable read look-ahead (read cache) feature.

82_H Disable write cache.

AA_H Enable read look-ahead (read cache) feature *(default).*

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-Rev 6 Standard.*

SeaTools diagnostic software activates a built-in drive self-test (DST) S.M.A.R.T. command for $D4_H$ that eliminates unnecessary drive returns. The diagnostic software ships with all new drives and is also available at: http://seatools.seagate.com.

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
$D1_H$	Obsolete
$D2_H$	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 (runs DST)
$D5_H$	S.M.A.R.T. Read Log Sector
$D6_H$	S.M.A.R.T. Write Log Sector
$D7_H$	Obsolete
$D8_H$	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 LLC
920 Disc Drive, Scotts Valley, California 95066, USA

Publication Number: 100216026, Rev. B, July 2002, Printed in USA