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Barracuda 18XL Family:
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ST318436LW/LC/LWV/LCV
.....

ST318426LW/LC, ST318416N/W
.....

ST39236LW/LC/LWV/LCV
.....

ST39226LW/LC, ST39216N/W
.....

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Product Manual, Volume 1
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ST39226LW/LC, ST39216N/W
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Product Manual, Volume 1
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Publication number: 77767535, Rev. B
September 2000

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Revision status summary sheet

Revision	Date	Writer/Engineer	Sheets Affected
Rev. A	01/18/2000	D. Ashby/B. Reynolds	1/1, v thru viii, 1-98.
Rev. B	09/12/2000	K. Schweiss/ B. Reynolds	front cover, ii, 1, 5, 7, 9-10, 31-33, 60, 64-65, 78, 85-87, and backcover.

Notice.

Product Manual 77767535 is Volume 1 of a two volume document with the SCSI Interface information in the Volume 2 SCSI Interface Product Manual, part number 75789509.

If the SCSI Interface information is needed the Volume 2 Interface Manual should be ordered, part number 75789509.

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1.0 Scope

This manual describes the Seagate Technology®, LLC. Barracuda 18XL™ disc drives.

Barracuda 18XL drives support the small computer system interface (SCSI) as described in the ANSI SCSI, SCSI-2, and SCSI-3 (Fast-20, Fast-40, and Fast-80) interface specifications to the extent described in this manual.* Ultra, Ultra2, and Ultra160 are the names Seagate calls these interfaces. The *SCSI Interface Product Manual* (part number 75789509) describes general SCSI interface characteristics of this and other families of Seagate drives.

From this point on in this product manual the reference to Barracuda 18XL models is referred to as “the drive” (unless references to individual models are necessary).

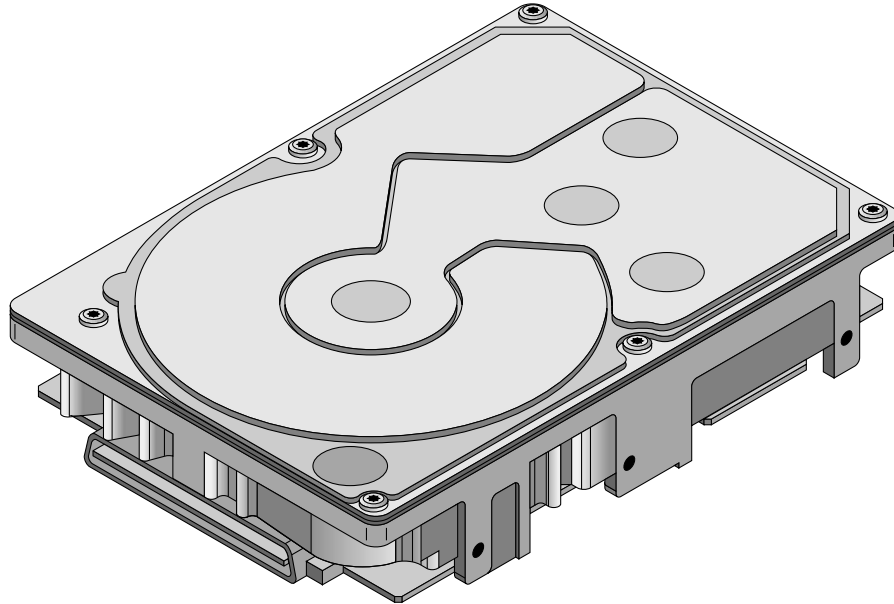


Figure 1. Barracuda 18XL family drive (model “LC” version with 80-pin SCSI I/O connector shown)

*The ANSI specifications have now replaced the terms “SCSI,” “SCSI-2,” and “SCSI-3” with “SCSI.”

2.0 Applicable standards and reference documentation

The drive has been developed as a system peripheral to the highest standards of design and construction. The drive depends upon its host equipment to provide adequate power and environment in order to achieve optimum performance and compliance with applicable industry and governmental regulations. Special attention must be given in the areas of safety, power distribution, shielding, audible noise control, and temperature regulation. In particular, the drive must be securely mounted in order to guarantee the specified performance characteristics. Mounting by bottom holes must meet the requirements of Section 8.4.

2.1 Standards

The Barracuda 18XL family complies with Seagate standards as noted in the appropriate sections of this Manual and the Seagate *SCSI Interface Product Manual*, part number 75789509 (Vol. 2).

The Barracuda 18XL disc drive is a UL recognized component per UL1950, CSA certified to CAN/CSA C22.2 No. 950-95, and VDE certified to VDE 0805 and EN60950.

2.1.1 Electromagnetic compatibility

The drive, as delivered, is designed for system integration and installation into a suitable enclosure prior to use. As such the drive is supplied as a subassembly and is not subject to Subpart B of Part 15 of the FCC Rules and Regulations nor the Radio Interference Regulations of the Canadian Department of Communications.

The design characteristics of the drive serve to minimize radiation when installed in an enclosure that provides reasonable shielding. As such, the drive is capable of meeting the Class B limits of the FCC Rules and Regulations of the Canadian Department of Communications when properly packaged. However, it is the user's responsibility to assure that the drive meets the appropriate EMI requirements in their system. Shielded I/O cables may be required if the enclosure does not provide adequate shielding. If the I/O cables are external to the enclosure, shielded cables should be used, with the shields grounded to the enclosure and to the host controller.

2.1.2 Electromagnetic susceptibility

As a component assembly, the drive is not required to meet any susceptibility performance requirements. It is the responsibility of those integrating the drive within their systems to perform those tests required and design their system to ensure that equipment operating in the same system as the drive or external to the system does not adversely affect the performance of the drive. See also Section 5.1.1 and Table 2, DC power requirements.

2.2 Electromagnetic compliance

Seagate uses an independent laboratory to confirm compliance to the directives/standard(s) for CE Marking and C-Tick Marking. The drive was tested in a representative system for typical applications. The selected system represents the most popular characteristics for test platforms. The system configurations include:

- Typical current use microprocessor
- 3.5-inch floppy disc drive
- Keyboard
- Monitor/display
- Printer
- External modem
- Mouse

Although the test system with this Seagate model complies to the directives/standard(s), we cannot guarantee that all systems will comply. The computer manufacturer or system integrator shall confirm EMC compliance and provide CE Marking and C-Tick Marking for their product.

Electromagnetic compliance for the European Union

If this model has the CE Marking it complies with the European Union requirements of the Electromagnetic Compatibility Directive 89/336/EEC of 03 May 1989 as amended by Directive 92/31/EEC of 28 April 1992 and Directive 93/68/EEC of 22 July 1993.

Australian C-Tick

If this model 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 Australia's Spectrum Management Agency (SMA).

2.3 Reference documents

<i>Barracuda 18XL Installation Guide (for LW/LC/LWV/LCV)</i>	Seagate P/N 75789511
<i>Safety and Regulatory Agency Specification</i>	Seagate P/N 75789512
<i>SCSI Interface Product Manual</i>	Seagate P/N 75789509

ANSI small computer system interface (SCSI) document numbers:

X3.131-1994	SCSI-2
T10/1302D	SPI-3
X3T10/1143D	EPI
T10/1236D	SPC-2
T10/999D	SBC
T10/1157D	SAM-2

SFF-8046 Specification for 80-pin connector for SCSI disk drives

SCA-2 EIA Specification ANSI/EIA

Package Test Specification	Seagate P/N 30190-001 (under 100 lb.)
Package Test Specification	Seagate P/N 30191-001 (over 100 lb.)
Specification, Acoustic Test Requirements, and Procedures	Seagate P/N 30553-001

In case of conflict between this document and any referenced document, this document takes precedence.

3.0 General description

Barracuda 18XL drives combine magnetoresistive (GMR) heads, partial response/maximum likelihood (PRML) read channel electronics, embedded servo technology, and a SCSI-3 (Fast-20, Fast 40, and Fast-80) interface to provide high performance, high capacity data storage for a variety of systems including engineering workstations, network servers, mainframes, and supercomputers.

Fast-20, Fast-40, and Fast-80 (also known as Ultra SCSI, Ultra-2 SCSI, and Ultra160 SCSI, respectively) are negotiated transfer rates. These transfer rates will occur only if your host adapter also supports these data transfer rates. This drive also operates at SCSI-1 and SCSI-2 data transfer rates for backward compatibility with non-Fast-20/Fast-40/Fast-80 capable SCSI host adapters.

Note. ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

Table 1 lists the features that differentiate the various Barracuda 18XL models.

Table 1: Drive model number vs. differentiating features

Model number	Number of heads	I/O circuit type [1]	Number of I/O connector pins	Number of I/O data bus bits	Data buffer size
ST318436LW	6	multimode (SE/LVD)	68	16	2 MB
ST318436LC	6	multimode (SE/LVD)	80	16	2 MB
ST318436LWV	6	multimode (SE/LVD)	68	16	4 MB
ST318436LCV	6	multimode (SE/LVD)	80	16	4 MB
ST318426LW	6	multimode (SE/LVD)	68	16	1 MB [2]
ST318426LC	6	multimode (SE/LVD)	80	16	1 MB [2]
ST318416N	6	single-ended	50	8	2 MB
ST318416W	6	single-ended	68	16	2 MB
ST39236LW	3	multimode (SE/LVD)	68	16	2 MB
ST39236LC	3	multimode (SE/LVD)	80	16	2 MB
ST39236LWV	3	multimode (SE/LVD)	68	16	4 MB
ST39236LCV	3	multimode (SE/LVD)	80	16	4 MB
ST39226LW	3	multimode (SE/LVD)	68	16	1 MB [2]
ST39226LC	3	multimode (SE/LVD)	80	16	1 MB [2]
ST39216N	3	single-ended	50	8	2 MB
ST39216W	3	single-ended	68	16	2 MB

[1] See Section 9.6 for details and definitions.

[2] Fast-80/Ultra160 mode not supported by this model.

The drive records and recovers data on 3.0-inch (74 mm) non-removeable discs.

The drive supports the Small Computer System Interface (SCSI) as described in the ANSI SCSI SPI-3 interface specifications to the extent described in this manual (volume 1), which defines the product performance characteristics of the Barracuda 18XL family of drives, and the *SCSI Interface Product Manual* (volume 2), part number 75789509, which describes the general interface characteristics of this and other families of Seagate SCSI drives.

The drive's interface supports multiple initiators, disconnect/reconnect, self-configuring host software, and automatic features that relieve the host from the necessity of knowing the physical characteristics of the targets (logical block addressing is used).

The head and disc assembly (HDA) is sealed at the factory. Air circulates within the HDA through a non-replaceable filter to maintain a contamination-free HDA environment.

Refer to Figure 2 for an exploded view of the drive. This exploded view is for information only—never disassemble the HDA and do not attempt to service items in the sealed enclosure (heads, media, actuator, etc.) as this requires special facilities. The drive contains no replaceable parts. Opening the HDA voids your warranty.

Barracuda 18XL drives use a dedicated landing zone at the innermost radius of the media to eliminate the possibility of destroying or degrading data by landing in the data zone. The drive automatically goes to the landing zone when power is removed.

An automatic shipping lock prevents potential damage to the heads and discs that results from movement during shipping and handling. The shipping lock automatically disengages when power is applied to the drive and the head load process begins.

Barracuda 18XL drives decode track 0 location data from the servo data embedded on each surface to eliminate mechanical transducer adjustments and related reliability concerns.

A high-performance actuator assembly with a low-inertia, balanced, patented, straight-arm design provides excellent performance with minimal power dissipation.

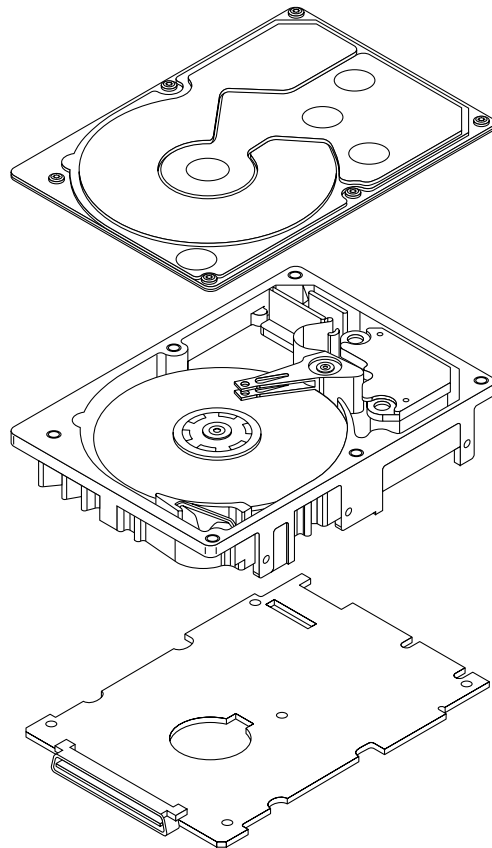


Figure 2. Barracuda 18XL family drive

3.1 Standard features

The Barracuda 18XL family has the following standard features:

- Integrated SCSI controller
- SCSI multimode single-ended or low voltage differential drivers and receivers
- 8 bit or 16 bit I/O data bus models available
- Asynchronous and synchronous data transfer protocol
- Firmware downloadable via SCSI interface
- Selectable sector sizes from 512 to 4,096 bytes/sector in multiples of 2 bytes/sector
- Programmable drive capacity
- Programmable sector reallocation scheme
- Flawed sector reallocation at format time
- Programmable auto write and read reallocation
- Reallocation of defects on command (post format)
- Enhanced ECC correction capability up to 240 bits
- Sealed head and disc assembly
- No preventative maintenance or adjustment required
- Dedicated laser textured head landing zone
- Embedded servo data rather than a separate servo data surface
- Self diagnostics performed when power is applied to the drive
- 1:1 Interleave
- Zoned bit recording (ZBR)
- Vertical, horizontal, or top down mounting
- Dynamic spindle brake
- 2 MByte data buffer standard (1 Mbyte on some drives, see Table 1) or 4 Mbyte optional
- Hot plug compatibility
- Low audible noise for office environment
- Low power consumption

3.2 Media characteristics

The media used on the drive has a diameter of approximately 3.0 inches (74 mm). The aluminum substrate is coated with a thin film magnetic material, overcoated with a proprietary protective layer for improved durability and environmental protection.

3.3 Performance

- Supports industry standard Fast-20, Fast-40, and Fast-80 SCSI interfaces (also called “Ultra SCSI,” “Ultra-2 SCSI,” and “Ultra160 SCSI,” respectively)

Note. ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

- Programmable multi-segmentable cache buffer (see Section 4.4)
- 7200 RPM spindle. Average latency = 4.17 msec
- Command queuing of up to 64 commands
- Background processing of queue
- Supports start and stop commands (spindle stops spinning)

3.4 Reliability

- 1,200,000 hour MTBF (mature)
- LSI circuitry
- Balanced low mass rotary voice coil actuator
- Incorporates industry-standard Self-Monitoring, Analysis and Reporting Technology (S.M.A.R.T.)
- Incorporates Seek To Improve Reliability algorithm (STIR)
- 5-year warranty

3.5 Unformatted and formatted capacities

Formatted capacity depends on the number of spare reallocation sectors reserved and the number of bytes per sector. The following table shows the standard OEM model read capacities data. Total LBAs = read capacity data (shown below) +1.

	Formatted data block size 512 bytes/sector [1] [2]
ST318436	35,885,167 (223906Fh) (18.373 GB)
ST318426	35,885,167 (223906Fh) (18.373 GB)
ST318416	35,885,167 (223906Fh) (18.373 GB)
ST39236	17,942,583 (111C837h) (9.186 GB)
ST39226	17,942,583 (111C837h) (9.186 GB)
ST39216	17,942,583 (111C837h) (9.186 GB)

Notes.

- [1] Sector size selectable at format time. Users having the necessary equipment may modify the data block size before issuing a format command and obtain different formatted capacities than those listed. See Mode Select command and Format command in the *SCSI Interface Product Manual*, part number 75789509.
- [2] User available capacity depends on spare reallocation scheme selected. The number of data tracks per sparing zone and the number of alternate sectors (LBAs) per sparing zone can be determined by using the Mode Sense command and reading Mode Page 03h. Total LBAs(h) x 200(h) = total byte capacity.

3.6 Programmable drive capacity

Using the Mode Select command, the drive can change its capacity to something less than maximum. See the Mode Select Parameter List table in the *SCSI Interface Product Manual*, part number 75789509. Refer to the Parameter list block descriptor number of blocks field. A value of zero in the number of blocks field indicates that the drive shall not change the capacity it is currently formatted to have. A number in the number of blocks field that is less than the maximum number of LBAs changes the total drive capacity to the value in the block descriptor number of blocks field. A value of FF FF FF FF in the number of blocks field restores the drive capacity to the maximum capacity.

3.7 Factory installed accessories

OEM Standard drives are shipped with the *Barracuda 18XL Installation Guide*, part number 75789511, and the *Safety and Regulatory Agency Specification*, part number 75789512, (unless otherwise specified). The factory also ships with the drive a small bag of jumper plugs used for the J2, J5, and J6 option select jumper headers.

3.8 Options (factory installed)

All customer requested options are incorporated during production or packaged at the manufacturing facility before shipping. Some of the options available are (not an exhaustive list of possible options):

- Other capacities can be ordered depending on sparing scheme and sector size requested.
- 4 Mbyte optional buffer size.
- Single unit shipping pack. The drive is normally shipped in bulk packaging to provide maximum protection against transit damage. Units shipped individually require additional protection as provided by the single unit shipping pack. Users planning single unit distribution should specify this option.
- The *Barracuda 18XL Installation Guide*, part number 75789511, and the *Safety and Regulatory Agency Specification*, part number 75789512, are included with each standard OEM drive shipped, but extra copies may be ordered.

3.9 Accessories (user installed)

The following accessories are available.

- Single unit shipping pack.

4.0 Performance characteristics

4.1 Internal drive characteristics (transparent to user)

	ST318436	ST318426	ST318416	ST39236	ST39226	ST39216	
Drive capacity	18.373	18.373	18.373	9.186	9.186	9.186	Gbyte (formatted, rounded off values)
Read/write heads	6	6	6	3	3	3	
Bytes/track	213	213	213	213	213	213	Kbytes (average, rounded off values)
Bytes/surface	3,642	3,642	3,642	3,642	3,642	3,642	Mbytes (unformatted, rounded off values)
Tracks/surface (total)	14,384	14,384	14,384	14,384	14,384	14,384	Tracks (user accessible)
Tracks/inch	18,145	18,145	18,145	18,145	18,145	18,145	TPI
Peak bits/inch	328	328	328	328	328	328	KBPI
Internal data rate	195-315	195-315	195-315	195-315	195-315	195-315	Mbits/sec (variable with zone)
Disc rotational speed	7,200	7,200	7,200	7,200	7,200	7,200	r/min \pm 0.5%
Average rotational latency	4.17	4.17	4.17	4.17	4.17	4.17	msec
Recording code	16/17	16/17	16/17	16/17	16/17	16/17	EPR4

4.2 SCSI performance characteristics (visible to user)*

The values given in Section 4.2.1 apply to all models of the Barracuda 18XL family unless otherwise specified. Refer to Section 9.10 and to the *SCSI Interface Product Manual*, part number 75789509, for additional timing details.

4.2.1 Access time [8]*

		Including controller overhead (without disconnect) [1] [4]			
		Drive level (18.373 GB models)		Drive level (9.186 GB models)	
		Read	Write	Read	Write
		msec		msec	
Average	– Typical [3]	6.0	6.5	6.0	6.5
Single Track	– Typical [3]	0.70	0.70	0.70	0.70
Full Stroke	– Typical [3]	10.50	11.00	10.50	11.0

4.2.2 Format command execution time (minutes) [1]*

	18.373 GB models	9.186 GB models
Maximum (with verify)	30	15
Maximum (no verify)	15	7.5

4.2.3 Generalized performance characteristics

Data buffer transfer rate to/from disc media (one 512-byte sector):

	18.373 GB models	9.186 GB models	
Min. [4]*	24.7	24.7	MByte/sec
Avg. [4]	32.1	32.1	MByte/sec
Max. [4]	39.4	39.4	MByte/sec

*[] All notes for Section 4.2 are listed at end of Section 4.2.3.

Data buffer transfer rate to/from disc media: (< 1 track):

		18.373 GB models	9.186 GB models	
Min.	[4]	18.5	18.5	MByte/sec
Avg.	[4]	23.9	23.9	MByte/sec
Max.	[4]	29.4	29.4	MByte/sec

SCSI interface data transfer rate (asynchronous, 15 bit SCSI bus) [5]:

Maximum instantaneous	5 Mbytes/sec [6]
Maximum average	5 Mbytes/sec [7]

Target sustainable transfer rate:

Average	22
Maximum	25
Minimum	15

Synchronous transfer rate:

16 bit SE I/O data bus models	40 Mbytes/sec (Fast-40 or Ultra-2)
16 bit LVD I/O data bus models	160 Mbytes/sec (Fast-80 or Ultra160) [9]

Sector Sizes:

Default	512 byte user data blocks
Variable	512 to 4,096 bytes per sector in multiples of 2 bytes per sector. If n (number of bytes per sector requested) is odd, then n-1 sectors will be used.

Read/write consecutive sectors on a track	Yes
Flaw reallocation performance impact (for flaws reallocated at format time using the spare sectors per sparing region reallocation scheme)	Negligible
Command overhead time for head switch in sequential mode	918 μsec
Command overhead time for cylinder switch in sequential mode	918 μsec
Command overhead, sequential read, tagged	8 μsec
Command overhead, sequential W/R, untagged	8 μsec
Average rotational latency	4.17 msec

Notes for Section 4.2.

- [1] Execution time measured from receipt of the last Byte of the Command Descriptor Block (CDB) to the request for a Status Byte Transfer to the Initiator (excluding connect/disconnect).
- [2] Maximum times are specified over the worst case conditions of temperature, voltage margins and drive orientation. When comparing specified access times, care should be taken to distinguish between typical access times and maximum access times. The best comparison is obtained by system benchmark tests conducted under identical conditions. Maximum times do not include error recovery.
- [3] Typical Access times are measured under nominal conditions of temperature, voltage, and horizontal orientation as measured on a representative sample of drives.
- [4] Assumes no errors and no sector has been relocated.
- [5] Rate measured from the start of the first sector transfer to or from the Host.
- [6] Assumes system ability to support the rates listed and no cable loss.
- [7] Simulated.
- [8] Access time = controller overhead + average seek time
Access to data = controller overhead + average seek time + latency time
- [9] ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

4.3 Start/stop time

After DC power at nominal voltage has been applied, the drive typically becomes ready for media access commands within 15 seconds if the Motor Start Option is disabled (i.e. the motor starts as soon as the power has been applied). Maximum is 25 seconds. If a recoverable error condition is detected during the start sequence, the drive executes a recovery procedure which may cause the time to become ready to exceed 15, but to become ready within 25 seconds. During spin up to ready time, the drive responds to some commands over the SCSI interface in less than 1.5 seconds after application of power. Stop time is typically <10 seconds from removal of DC power. Maximum is <20 seconds.

If the Motor Start Option is enabled, the internal controller accepts the commands listed in the *SCSI Interface Product Manual* less than 3 seconds after DC power has been applied. After the Motor Start Command has been received the drive becomes ready for normal operations within 13 seconds typically (excluding an error recovery procedure). The Motor Start Command can also be used to command the drive to stop the spindle (see *SCSI Interface Product Manual*, part number 75789509).

There is no power control switch on the drive.

4.4 Prefetch/multi-segmented cache control

The drive provides prefetch (read look-ahead) and multi-segmented cache control algorithms that in many cases can enhance system performance. "Cache" as used herein refers to the drive buffer storage space when it is used in "cache" operations. To select prefetch and cache features the host sends the Mode Select command with the proper values in the applicable bytes in Mode Page 08h (see *SCSI Interface Product Manual*, part number 75789509). Prefetch and cache operation are independent features from the standpoint that each is enabled and disabled independently via the Mode Select command. However, in actual operation the prefetch feature overlaps cache operation somewhat as is noted in Section 4.5.1 and 4.5.2.

All default cache and prefetch Mode parameter values (Mode Page 08h) for standard OEM versions of this drive family are given in Table 9a.

4.5 Cache operation

The buffer can be divided into logical segments (Mode Select Page 08h, byte 13) from which data is read and to which data is written. The drive maintains a table of logical block disk medium addresses of the data stored in each segment of the buffer. If cache operation is enabled (RCD bit = 0 in Mode Page 08h, byte 2, bit 0. See *SCSI Interface Product Manual*, part number 75789509), data requested by the host with a Read command is retrieved from the buffer (if it is there), before any disc access is initiated. If cache operation is not enabled, the buffer (still segmented with required number of segments) is still used, but only as circular buffer segments during disc medium read operations (disregarding Prefetch operation for the moment). That is, the drive does not check in the buffer segments for the requested read data, but goes directly to the medium to retrieve it. The retrieved data merely passes through some buffer segment on the way to the host. On a cache "miss", all data transfers to the host are in accordance with "buffer-full" ratio rules. On a cache "hit" the drive ignores the "buffer-full" ratio rules. See explanations associated with Mode page 02h (disconnect/reconnect control) in the *SCSI Interface Product Manual*, part number 75789509.

The following is a simplified description of a read operation with cache operation enabled:

Case A - A Read command is received and the first logical block (LB) is already in cache:

1. Drive transfers to the initiator the first LB requested plus all subsequent contiguous LB's that are already in the cache. This data may be in multiple segments.
2. When a requested LB is reached that is not in any cache segment, the drive fetches it and any remaining requested LBs from the disc and puts them in a segment of the cache. The drive transfers the remaining requested LBs from the cache to the host in accordance with the disconnect/reconnect specification mentioned above.
3. If the prefetch feature is enabled, refer to Section 4.5.2 for operation from this point.

Case B - A Read command requests data, the first LB of which is not in any segment of the cache:

1. The drive fetches the requested LB's from the disc and transfers them into a segment, and from there to the host in accordance with the disconnect/reconnect specification referred to in case A.
2. If the prefetch feature is enabled, refer to Section 4.5.2 for operation from this point.

Each buffer segment is actually a self-contained circular storage (wrap-around occurs), the length of which is an integer number of disc medium sectors. The wrap-around capability of the individual segments greatly enhances the buffer's overall performance as a cache storage, allowing a wide range of user selectable configurations, which includes their use in the prefetch operation (if enabled), even when cache operation is disabled (see Section 4.5.2). The number of segments may be selected using the Mode Select command, but the size can not be directly selected. Size is selected only as a by-product of selecting the segment number specification. The size in Kbytes of each segment is not reported by the Mode Sense command page 08h, bytes 14 and 15. The value 0XFFFF is always reported. If a size specification is sent by the host in a Mode Select command (bytes 14 and 15) no new segment size is set up by the drive, and if the "STRICT" bit in Mode page 00h (byte 2, bit 1) is set to one, the drive responds as it does for any attempt to change unchangeable parameters (see *SCSI Interface Product Manual*, part number 75789509). The drive supports operation of any integer number of segments from 1 to 16.

4.5.1 Caching write data

Write caching is a write operation by the drive that makes use of a drive buffer storage area where the data to be written to the medium is stored in one or more segments while the drive performs the write command.

The same buffer space and segmentation is used as set up for read functions. The buffer segmentation scheme is set up or changed independently, having nothing to do with the state of RCD. When a write command is issued, if RCD=0, the cache is first checked to see if any logical blocks that are to be written are already stored in the cache from a previous read or write command. If there are, the respective cache segments are cleared. The new data is cached for subsequent Read commands.

If the number of write data logical blocks exceeds the size of the segment being written into, when the end of the segment is reached, the data is written into the beginning of the same cache segment, overwriting the data that was written there at the beginning of the operation. However, the drive does not overwrite data that has not yet been written to the medium.

If write caching is enabled (WCE=1), then the drive may return GOOD status on a write command after the data has been transferred into the cache, but before the data has been written to the medium. If an error occurs while writing the data to the medium, and GOOD status has already been returned, a deferred error will be generated. Write commands that have returned GOOD status but still have uncommitted data in the cache are treated similarly to a normal queued command and therefore occupy a command queue slot. This may temporarily reduce the number of commands that may be queued by the host until the write data has been written to the medium.

The Synchronize Cache command may be used to force the drive to write all cached write data to the medium. Upon completion of a Synchronize Cache command, all data received from previous write commands will have been written to the medium. The Start/Stop command with the stop bit set will force a sync cache operation before the drive stops.

Table 9a shows Mode default settings for the drives.

4.5.2 Prefetch operation

If the Prefetch feature is enabled, data in contiguous logical blocks on the disc immediately beyond that which was requested by a Read command can be retrieved and stored in the buffer for immediate transfer from the buffer to the host on subsequent Read commands that request those logical blocks (this is true even if "cache" operation is disabled). Though the prefetch operation uses the buffer as a "cache", finding the requested data in the buffer is a prefetch "hit", not a "cache" operation "hit". Prefetch is enabled using Mode Select page 08h, byte 12, bit 5 (Disable Read Ahead - DRA bit). DRA bit = 0 enables prefetch. Since data that is prefetched replaces data already in some buffer segment(s), the host can limit the amount of prefetch data to optimize system performance. The max prefetch field (bytes 8 and 9) limits the amount of prefetch. The drive does not use the prefetch "ceiling" field (bytes 10 and 11).

During a prefetch operation, the drive crosses a cylinder boundary to fetch more data only if the Discontinuity (DISC) bit is set to one in bit 4 of byte 2 of Mode parameters page 08h.

4.5.3 Optimizing cache performance for desktop and server applications

Desktop and server applications require different drive caching operations for optimal performance. This means it is difficult to provide a single configuration that meets both of these needs. In a desktop environment,

you want to configure the cache to respond quickly to repetitive accesses of multiple small segments of data without taking the time to “look ahead” to the next contiguous segments of data. In a server environment, you want to configure the cache to provide large volumes of sequential data in a non-repetitive manner. In this case, the ability of the cache to “look ahead” to the next contiguous segments of sequential data is a good thing.

The Performance Mode (PM) bit controls the way the drive switches the cache buffer into different modes of segmentation. In “server mode” (PM bit = 0), the drive can increase the number of cache buffer segments above the value defined in Mode Page 8, Byte 13, as needed to optimize the performance, based on the command stream from the host. In “desktop mode” (PM bit = 1), the number of segments is maintained at the value defined in Mode Page 8, Byte 13, at all times. For additional information about the PM bit, refer to the Unit Attention Parameters page (00h) of the Mode Sense command (1Ah) in the SCSI Interface Manual, part number 75789509.

The base cache buffer configuration for desktop or server environments needs to be set correctly by the host system. This involves setting the PM bit in Mode Page 0, Byte 2, as well as the number of cache buffer segments in Mode Page 8, Byte 13. The firmware default values are set to desktop mode (PM bit = 1), and the number of cache buffer segments set to 16 (10h). The OEM saved values for drives with LW, W, and N interfaces are the same as the firmware default values. For drives with the LC interface, the OEM saved values are changed to server mode (PM bit=0), and the number of cache buffer segments are set to 3 (03h). Refer to Tables 9a through 9f in Section 9.3.2 for drive default values for the PM bit in Mode Page 0, Byte 2 and the number of cache buffer segments in Mode Page 8, Byte 13.

	Caching Parameters page (08h) Byte 13 (Number of Cache Segments)	Unit Attention Parameters page (00h) Byte 2, Bit 7 (PM bit)
Desktop mode	10h (16 segments -- default for LW, W, and N models)	1
Server mode	03h (3 segments -- default for LC models)	0

5.0 Reliability specifications

The following reliability specifications assume correct host/drive operational interface, including all interface timings, power supply voltages, environmental requirements and drive mounting constraints (see Section 8.4).

Seek Errors	Less than 10 in 10^8 seeks
Read Error Rates [1]	
Recovered Data	Less than 10 errors in 10^{12} bits transferred (OEM default settings)
Unrecovered Data	Less than 1 sector in 10^{15} bits transferred (OEM default settings)
Miscorrected Data	Less than 1 sector in 10^{21} bits transferred
MTBF	1,200,000 hours
Service Life	5 years
Preventive Maintenance	None required

Note.

[1] Error rate specified with automatic retries and data correction with ECC enabled and all flaws reallocated.

5.1 Error rates

The error rates stated in this specification assume the following:

- The drive is operated per this specification using DC power as defined in this manual (see Section 6.2).
- The drive has been formatted with the SCSI FORMAT commands.
- Errors caused by media defects or host system failures are excluded from error rate computations. Refer to Section 3.2, "Media Characteristics."

5.1.1 Environmental interference

When evaluating systems operation under conditions of Electromagnetic Interference (EMI), the performance of the drive within the system shall be considered acceptable if the drive does not generate an unrecoverable condition.

An unrecoverable error, or unrecoverable condition, is defined as one that:

- Is not detected and corrected by the drive itself;
- Is not capable of being detected from the error or fault status provided through the drive or SCSI interface; or
- Is not capable of being recovered by normal drive or system recovery procedures without operator intervention.

5.1.2 Read errors

Before determination or measurement of read error rates:

- The data that is to be used for measurement of read error rates must be verified as being written correctly on the media.
- All media defect induced errors must be excluded from error rate calculations.

5.1.3 Write errors

Write errors can occur as a result of media defects, environmental interference, or equipment malfunction. Therefore, write errors are not predictable as a function of the number of bits passed.

If an unrecoverable write error occurs because of an equipment malfunction in the drive, the error is classified as a failure affecting MTBF. Unrecoverable write errors are those which cannot be corrected within two attempts at writing the record with a read verify after each attempt (excluding media defects).

5.1.4 Seek errors

A seek error is defined as a failure of the drive to position the heads to the addressed track. There shall be no more than ten recoverable seek errors in 10^8 physical seek operations. After detecting an initial seek error, the drive automatically performs an error recovery process. If the error recovery process fails, a seek positioning error (15h) is reported with a Medium error (3h) or Hardware error (4h) reported in the Sense Key. This is an unrecoverable seek error. Unrecoverable seek errors are classified as failures for MTBF calculations. Refer to the *SCSI Interface Product Manual*, part number 75789509, for Request Sense information.

5.2 Reliability and service

You can enhance the reliability of Barracuda 18XL disc drives by ensuring that the drive receives adequate cooling. Section 6.0 provides temperature measurements and other information that may be used to enhance the service life of the drive. Section 8.3.1 provides recommended air-flow information.

5.2.1 Mean time between failure

The production disc drive shall achieve an MTBF of 1,200,000 hours when operated in an environment that ensures the case temperatures specified in Section 6.4.1, Table 3, Column 2 are not exceeded. Short-term excursions up to the specification limits of the operating environment will not affect MTBF performance. Continual or sustained operation at case temperatures above the values shown in Table 3, Column 2 may degrade product reliability.

The following expression defines MTBF

$$\text{MTBF per measurement period} = \frac{\text{Estimated power-on operating hours in the period}}{\text{Number of drive failures in the period}}$$

Estimated power-on operation hours means power-up hours per disc drive times the total number of disc drives in service. Each disc drive shall have accumulated at least nine months of operation. Data shall be calculated on a rolling average base for a minimum period of six months.

Drive failure means any stoppage or substandard performance caused by drive malfunction.

5.2.2 Preventive maintenance

No routine scheduled preventive maintenance shall be required.

5.2.3 Service life

The drive shall have a useful service life of five years. Depot repair or replacement of major parts is permitted during the lifetime (see Section 5.2.4).

5.2.4 Service philosophy

Special equipment is required to repair the drive HDA. In order to achieve the above service life, repairs must be performed only at a properly equipped and staffed service and repair facility. Troubleshooting and repair of PCBAs (Printed Circuit Board Assemblies) in the field is not recommended, because of the extensive diagnostic equipment required for effective servicing. Also, there are no spare parts available for this drive. Drive warranty is voided if the HDA is opened.

5.2.5 Service tools

No special tools are required for site installation or recommended for site maintenance. Refer to Section 5.2.4. The depot repair philosophy of the drive precludes the necessity for special tools. Field repair of the drive is not practical since there are no user purchasable parts in the drive.

5.2.6 Hot plugging Barracuda 18XL disc drives

The ANSI SPI-3 (T10/1302D) document defines the physical requirements for removal and insertion of SCSI devices on the SCSI bus. Four cases are addressed. The cases are differentiated by the state of the SCSI bus when the removal or insertion occurs.

- Case 1 All bus devices powered off during removal or insertion
- Case 2 RST signal asserted continuously during removal or insertion
- Case 3 Current I/O processes not allowed during insertion or removal
- Case 4 Current I/O process allowed during insertion or removal, except on the device being changed

Seagate Barracuda disc drives support all four hot plugging cases. Provision shall be made by the system such that a device being inserted makes power and ground connections prior to the connection of any device signal contact to the bus. A device being removed shall maintain power and ground connections after the disconnection of any device signal contact from the bus (see SFF-8046, SCA-2 specification).

It is the responsibility of the systems integrator to assure that no hazards from temperature, energy, voltage, or ESD potential are presented during the hot connect/disconnect operation.

All I/O processes for the SCSI device being inserted or removed shall be quiescent. All SCSI devices on the bus shall have receivers that conform to the SPI-3 standard.

If the device being hot plugged uses single-ended (SE) drivers and the bus is currently operating in low voltage differential (LVD) mode, then all I/O processes for all devices on the bus must be completed, and the bus quiesced, before attempting to hot plug. Following the insertion of the newly installed device, the SCSI host adapter must issue a Bus Reset, followed by a synchronous transfer negotiation. Failure to perform the SCSI Bus Reset could result in erroneous bus operations.

The SCSI bus termination and termination power source shall be external to the device being inserted or removed.

End users should not mix devices with high voltage differential (HVD) drivers and receivers and devices with SE, LVD, or multimode drivers and receivers on the same SCSI bus since the common mode voltages in the HVD environment may not be controlled to safe levels for SE and LVD devices (see ANSI SPI-3).

The disc drive spindle must come to a complete stop prior to completely removing the drive from the cabinet chassis. Use of the Stop Spindle command or partial withdrawal of the drive, enough to be disconnected from the power source, prior to removal are methods for insuring that this requirement is met. During drive insertion, care should be taken to avoid exceeding the limits stated in Section 6.4.4, "Shock and vibration," of this manual.

5.2.7 S.M.A.R.T.

S.M.A.R.T. is an acronym for Self-Monitoring Analysis and Reporting Technology. This technology is intended to recognize conditions that indicate a drive failure and is designed to provide sufficient warning of a failure to allow data back-up before an actual failure occurs.

Note. The firmware will monitor specific attributes for degradation over time but cannot predict instantaneous drive failures.

Each attribute has been selected to monitor a specific set of failure conditions in the operating performance of the drive, and the thresholds are optimized to minimize "false" and "failed" predictions.

Controlling S.M.A.R.T.

The operating mode of S.M.A.R.T. is controlled by the DEXCPT bit and the PERF bit of the "Informational Exceptions Control Mode Page" (1Ch). The DEXCPT bit is used to enable or disable the S.M.A.R.T. process. Setting the DEXCPT bit will disable all S.M.A.R.T. functions. When enabled, S.M.A.R.T. will collect on-line data as the drive performs normal read/write operations. When the PERF bit is set, the drive is considered to be in "On-line Mode Only" and will not perform off-line functions.

The process of measuring off-line attributes and saving data can be forced by the RTZ (return to zero) command. Forcing S.M.A.R.T. will reset the timer so that the next scheduled interrupt will be two hours.

The drive can be interrogated by the host to determine the time remaining before the next scheduled measurement and data logging process will occur. This is accomplished by a log sense command to log page 0x3E. The purpose is to allow the customer to control when S.M.A.R.T. interruptions occur. As described above, forcing S.M.A.R.T by the RTZ command will reset the timer.

Performance impact

S.M.A.R.T. attribute data will be saved to the disc for the purpose of recreating the events that caused a predictive failure. The drive will measure and save parameters once every two hours subject to an idle period on the SCSI bus. The process of measuring off-line attribute data and saving data to the disc is uninterruptable and the maximum delay is summarized below:

Maximum processing delay

	On-line only delay DEXCPT = 0, PERF = 1	Fully enabled delay DEXCPT = 0, PERF = 0
S.M.A.R.T. delay times, 18.373 Gb models	160 milliseconds	300 milliseconds
S.M.A.R.T. delay times, 9.186 Gb models	110 milliseconds	200 milliseconds

Reporting control

Reporting is controlled in the “Informational Exceptions Control Page” (1Ch). Subject to the reporting method, the firmware will issue to the “host” an 01-5D00 sense code. The error code is preserved through bus resets and power cycles.

Determining rate

S.M.A.R.T. monitors the rate at which errors occur and signals a predictive failure if the rate of degraded error rate increases to an unacceptable level. To determine rate, error events are logged and compared to the number of total operations for a given attribute. The interval defines the number of operations over which to measure the rate. The counter that keeps track of the current number of operations is referred to as the Interval Counter.

S.M.A.R.T. measures error rate, hence for each attribute the occurrence of an “error” is recorded. A counter keeps track of the number of errors for the current interval. This counter is referred to as the Failure Counter.

Error rate is simply the number of errors per operation. The algorithm that S.M.A.R.T. uses to record rates of error is to set thresholds for the number of errors and the interval. If the number of errors exceeds the threshold before the interval expires, then the error rate is considered to be unacceptable. If the number of errors does not exceed the threshold before the interval expires, then the error rate is considered to be acceptable. In either case, the interval and failure counters are reset and the process starts over.

Predictive failures

S.M.A.R.T. signals predictive failures when the drive is performing unacceptably for a period of time. The firmware keeps a running count of the number of times the error rate for each attribute is unacceptable. To accomplish this, a counter is incremented whenever the error rate is unacceptable and decremented (not to exceed zero) whenever the error rate is acceptable. Should the counter continually be incremented such that it reaches the predictive threshold, a predictive failure is signaled. This counter is referred to as the Failure History Counter. There is a separate Failure History Counter for each attribute.

5.2.8 Drive Self Test (DST)

Drive Self Test (DST) is a technology designed to recognize drive fault conditions that qualify the drive as a failed unit. DST validates the functionality of the drive at a system level. If DST encounters an error, it reports a fault condition. If the drive fails the test, remove it from service and return it to Seagate for service.

5.2.8.1 DST Failure Definition

The drive will present a “diagnostic failed” condition through the diagnostic log page if a functional failure is encountered during DST. There is no attempt to raise or lower recovery thresholds or to predict errors. All retries and recovery processes are enabled during the test. If data is recoverable, no failure condition will be reported regardless of the retry level required to recover the data.

The following conditions are considered DST failure conditions:

- Persistent seek error after retries are exhausted
- Persistent track-follow error after retries are exhausted
- Persistent read error after retries are exhausted
- Persistent write error after retries are exhausted.

Recovered errors will not be reported as diagnostic failures.

5.2.8.2 Implementation

This section provides all of the information necessary to implement the DST function on this drive.

5.2.8.2.1 State of the drive prior to testing

The host is responsible for spinning the drive before issuing the Send Diagnostic command. While not technically part of DST, a persistent Not Ready condition also qualifies the drive to be returned to Seagate as a failed drive.

A Drive Not Ready condition is reported by the drive under the following conditions:

- Motor will not spin
- Motor will not lock to speed
- Servo will not lock on track
- Drive cannot read configuration tables from the disc

A Drive Not Ready will cause the drive to return a check condition with a sense code of 02, an error code of 04, and an ASQC of 00, 01, 02, 03, or 04.

5.2.8.2.2 Invoking DST

To invoke DST, submit the Send Diagnostic command with the appropriate Function Code (001b for the short test or 010b for the extended test) in bytes 1, bits 5, 6, and 7. Refer to the *SCSI Interface Product Manual, Volume 2*, part number 75789509, for additional information about invoking DST.

5.2.8.2.3 Check condition

Fault conditions are reported using one of two mechanisms. The two mechanisms are mutually exclusive—a failure reported by a check condition will not update the log, and a failed report in the log will not produce a check condition.

1. Check Condition status is reported in any of the following cases:
 - Command is not valid (sense data xx xx xx),
 - Drive is not ready (sense data 02, 04, [ASQC: 00, 01, 02, 03, or 04], and
 - The drive is not able to update the log (sense data xx xx xx).
2. Failure Report through the Log Sense command.

5.2.8.2.4 Immediate and non-immediate modes

The host can specify when the drive returns status. Status can be returned at the conclusion of the command (non-immediate mode) or can be returned immediately (immediate mode). In immediate mode, the nexus completes with good status immediately after the command has been validated and the log has been updated. In non-immediate mode, the drive will disconnect from the bus and reconnect at the conclusion of the command.

5.2.8.2.5 Short and extended tests

DST has two testing options—short and extended. These testing options are described in the following two subsections.

Short test (Function Code: 001b)

The purpose of the short test is to provide a time-limited test that tests as much of the drive as possible within 120 seconds. The short test does not scan the entire media surface, but does some fundamental tests and scans portions of the media. A complete read/verify scan is not performed and only factual failures will report a fault condition. This option provides a quick confidence test of the drive. Future revisions of the DST algorithms

may improve the effectiveness of the short test to find problems more quickly, but in no case will the drive report a fault condition unless it encounters an actual drive failure.

Each test consists of three segments:

1. Electrical

The drive will read, write, then read a series of sectors that have been allocated in a non-user-accessible area of the drive. These sectors have been certified at the factory and defective sectors spared. Sequential sectors will be read, written with a different pattern, then re-read. Each head will be exercised and the data pattern used will be unique for each head. If any read or write operation fails after retries, the test fails.

2. Servo

This segment executes 4,500 random reads. If any seek fails after retries, DST classifies this as a failure.

3. Read/verify scan

Beginning with logical block address (LBA) 0, the drive scans the user data areas. ECC and retries are used and all defect management, including the grown list, is used. The scan continues until the time allowed for the short test has elapsed. If the read of any sector produces an error, DST classifies this as a failure.

Short Test Correlation

The short test retains a correlation rate of at least 90% with drives tested and classified in the factory, with the exclusion of media defects. The test reports as “good” at least 90% of drives judged “good” by Seagate tests and reports as “bad” at least 90% of drives judged “bad” by Seagate tests for reasons other than media defects.

Extended test (Function Code: 010b)

The objective of the extended test option is to empirically test critical drive components. For example, the seek tests and on-track operations test the positioning mechanism. The read operation tests the read head element. and the write element is tested through read/write/read operations. The integrity of the media is checked through a read/verify scan of the media. Motor functionality is tested by default as a part of these tests.

The extended option performs various tests on the drive and scans every LBA of the drive. The anticipated length of this test is reported through the Mode Control page.

You can selected which test you want to run through the Function Code field of the Send Diagnostic command. Each test consists of three segments:

1. Electrical

The drive will read, write, then read a series of sectors that have been allocated in a non-user-accessible area of the drive. These sectors have been certified at the factory and defective sectors spared. Sequential sectors will be read, written with a different pattern, then re-read. Each head will be exercised and the data pattern used will be unique for each head. If any read or write operation fails after retries, the test fails.

2. Servo

This segment performs random seek and read tests. During the random seek test, the drive executes 4500 random seeks. If any of these seeks fail, after retries, DST classifies this as a failure. During the random read test, the drive executes 4,500 random reads across the full user-accessible area of the drive. ECC and retries are used. All defect management, including the grown list, is used. If the read of any sector produces an error, DST classifies this as a failure.

3. Read/verify scan

Beginning with logical block address (LBA) 0 and continuing through the maximum LBA, the drive scans all user data areas. ECC and retries are used and all defect management, including the grown list, is used. If the read of any sector produces an error, DST classifies this as a failure.

Extended Test Correlation

The extended test retains a correlation rate of at least 90% with drives tested and classified in the factory. The test reports as “good” at least 90% of the drive judged “good” by Seagate tests and reports as “bad” at least 90% of drives judged “bad” by Seagate tests.

5.2.8.2.6 Log page entries

When the drive begins DST, it creates a new entry in the Self-test Results Log page. The new entry is created by inserting a new self-test parameter block at the beginning of the self-test results log parameter section of the log page. Existing data will be moved to make room for the new parameter block. The drive reports 20 parameter blocks in the log page. If there are more than 20 parameter blocks, the least recent parameter block will be deleted. The new parameter block will be initialized as follows:

1. The Function Code field is set to the same value as sent in the DST command.
2. The Self-Test Results Value field is set to Fh.
3. The drive will store the log page to non-volatile memory.

After completing the first two self-test segments, the drive will change the value in the Self-Test Results Value field to Eh, update the log page in non-volatile memory with this new value, and begin the third self-test segment. Only the Self-Test Results Value field is changed as a result of this update.

After a self-test is complete or has been aborted, the drive updates the Self-Test Results Value field in its Self-Test Results Log page in non-volatile memory. The host may use Log Sense to read the results from up to the last 20 self-tests performed by the drive. The self-test results value is a 4-bit field that reports the results of the test. If the field is zero, the drive passed with no errors detected by the DST. If the field is not zero, the test failed for the reason reported in the field.

5.2.8.2.7 Self-Test Progress Indicator

Self-test progress is reported through the Request Sense command with the Self-Test Progress Indicator (STPI) bit set.

5.2.8.2.8 Abort

There are several ways to abort a diagnostic. Power-on Reset and SCSI Reset are two mechanisms you can use. You can also issue a Send Diagnostic command with an abort code in the function field to abort a currently-executing diagnostic. The log data will report an aborted command.

5.2.9 Product warranty

Beginning on the date of shipment to customer and continuing for a period of five years, Seagate warrants that each product (including components and subassemblies) or spare part that fails to function properly under normal use due to defect in materials or workmanship or due to nonconformance to the applicable specifications will be repaired or replaced, at Seagate's option and at no charge to customer, if returned by customer at customer's expense to Seagate's designated facility in accordance with Seagate's Warranty Procedure. Seagate will pay for transporting the repair or replacement item to customer. For more detailed warranty information refer to the Standard terms and conditions of Purchase for Seagate products.

Shipping

When transporting or shipping a drive, a Seagate approved container must be used. Keep your original box. They are easily identified by the Seagate Approved Package label. Shipping a drive in a non-approved container voids the drive warranty.

Seagate repair centers may refuse receipt of components improperly packaged or obviously damaged in transit. Contact your Authorized Seagate Distributor to purchase additional boxes. Seagate recommends shipping by an air-ride carrier experienced in handling computer equipment.

Product repair and return information

Seagate customer service centers are the only facilities authorized to service Seagate drives. Seagate does not sanction any third-party repair facilities. Any unauthorized repair or tampering with the factory-seal voids the warranty.

6.0 Physical/electrical specifications

This section provides information relating to the physical and electrical characteristics of the Barracuda 18XL drive.

6.1 AC power requirements

None.

6.2 DC power requirements

The voltage and current requirements for a single drive are shown in the following table. Values indicated apply at the drive power connector. The single ended power requirements includes the internal disc drive SCSI I/O termination. The table shows current values in Amperes. See also Figure 3c for current values vs. number of I/O operations.

Table 2: DC power requirements

18.373 GB drives	Notes	ST318436				ST318426		ST318416	
		LW/LC-LVD		LWV/LCV-LVD		LW/LC-LVD		N/W-SE	
Voltage		+5 V	+12 V	+5 V	+12 V	+5 V	+12 V	+5 V	+12 V
Regulation	[5][2]	±5%	±5%	±5%	±5%	±5%	±5%	±5%	±5%
Average idle current DC \bar{X}	[1]	0.80	0.30	0.80	0.30	0.80	0.30	0.80	0.30
Maximum starting current (peak DC) (peak AC)	[3] [3]	1.0 2.7	2.4 2.7	1.0 2.7	2.4 2.7	1.0 2.7	2.4 2.7	1.0 2.7	2.4 2.7
Delayed motor start (max) DC	[1][4]	0.70	0.05	0.70	0.05	0.70	0.05	0.70	0.05
Peak operating current Typical DC \bar{X} Maximum DC Maximum (Peak)	[1][6] [1]	0.90 1.10 1.60	0.60 0.70 2.50	0.90 1.10 1.60	0.60 0.70 2.50	0.90 1.10 1.60	0.60 0.70 2.50	0.90 1.10 1.60	0.60 0.70 2.50
9.186 GB drives	Notes	ST39236				ST39226		ST39216	
		LW/LC-LVD		LWV/LCV-LVD		LW/LC-LVD		N/W-SE	
Voltage		+5 V	+12 V	+5 V	+12 V	+5 V	+12 V	+5 V	+12 V
Regulation	[5][2]	±5%	±5%	±5%	±5%	±5%	±5%	±5%	±5%
Average idle current DC \bar{X}	[1]	0.80	0.25	0.80	0.25	0.80	0.25	0.80	0.25
Maximum starting current (peak DC) (peak AC)	[3] [3]	1.0 2.4	1.7 2.4	1.0 2.4	1.7 2.4	1.0 2.4	1.7 2.4	1.0 2.4	1.7 2.4
Delayed motor start (max) DC	[1][4]	0.70	0.05	0.70	0.05	0.70	0.05	0.70	0.05
Peak operating current Typical DC \bar{X} Maximum DC Maximum (Peak)	[1][6] [1]	0.90 1.00 1.40	0.50 0.80 2.30	0.90 1.00 1.40	0.50 0.80 2.30	0.90 1.00 1.40	0.50 0.80 2.30	0.90 1.00 1.40	0.50 0.80 2.30

Notes.

- [1] Measured with average reading DC ammeter. Instantaneous +12 V current peaks will exceed these values. Power supply is at nominal voltages.
- [2] For +12 V, a -10% droop is permissible during initial start of spindle, and must return to ±5% before 7,200 rpm is reached. The ±5% must be maintained after the drive signifies that its power-up sequence has been completed and that the drive is able to accept selection by the host initiator.
- [3] See +12 V current profile in Figure 3a.
- [4] This condition occurs when the Motor Start Option is enabled and the drive has not yet received a Start Motor command.

- [5] See Section 6.2.1 “Conducted Noise Immunity.” Specified voltage tolerance is inclusive of ripple, noise, and transient response.
- [6] Operating condition is defined as random 8 block reads at 162 I/Os per second. Current and power specified at nominal voltages. Decreasing +5 V supply by +5% increases 5 V current by 2.31%.

General Notes from Table 2:

1. Minimum current loading for each supply voltage is not less than 4% of the maximum operating current shown.
2. The +5 and +12 volt supplies shall employ separate ground returns.
3. Where power is provided to multiple drives from a common supply, careful consideration for individual drive power requirements should be noted. Where multiple units are powered on simultaneously, the peak starting current must be available to each device.

6.2.1 Conducted noise immunity

Noise is specified as a periodic and random distribution of frequencies covering a band from DC to 10 MHz. Maximum allowed noise values given below are peak to peak measurements and apply at the drive power connector.

- +5 V = 250 mV pp from 0 to 100 kHz and 100 mV pp from 100 kHz to 10 MHz.
- +12 V = 250 mV pp from 0 to 100 kHz and 100 mV pp from 100 kHz to 10 MHz.

6.2.2 Power sequencing

The drive does not require power sequencing. The drive protects against inadvertent writing during power-up and down. Daisy-chain operation requires that power be maintained on the terminated drive to ensure proper termination of the peripheral I/O cables. To automatically delay motor start based on the target ID (SCSI ID) enable the Delay Motor Start option and disable the Enable Motor Start option on the J2 connector. See Section 8.1 for pin selection information. To delay the motor until the drive receives a Start Unit command, enable the Enable Motor Start option on the J2 connector.

6.2.3 Current profile

Figures 3a and 3b identify the drive +5 V and +12 V current profile. The current during the various times is as shown:

- T - Power is applied to the drive.
- T1 - Controller self tests are performed.
- T2 - Spindle begins to accelerate under current limiting after performing drive internal diagnostics. See Note 1 of Table 2.
- T3 - The heads move from the landing zone to the data area.
- T4 - The adaptive servo calibration sequence is performed.
- T5 - Calibration is complete and the drive is ready for reading and writing.

Note. All times and currents are typical. See Table 2 for maximum current requirements.

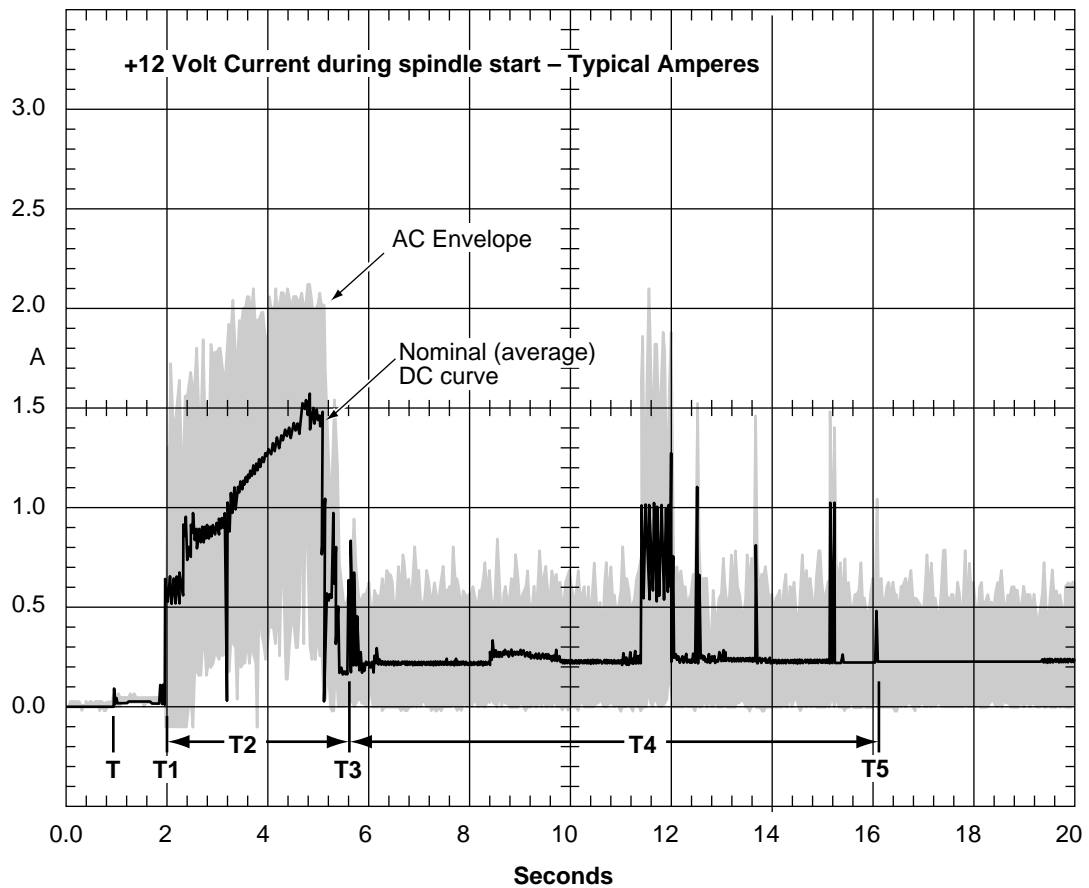


Figure 3a. Typical Barracuda 18XL family drive +12 V current profile

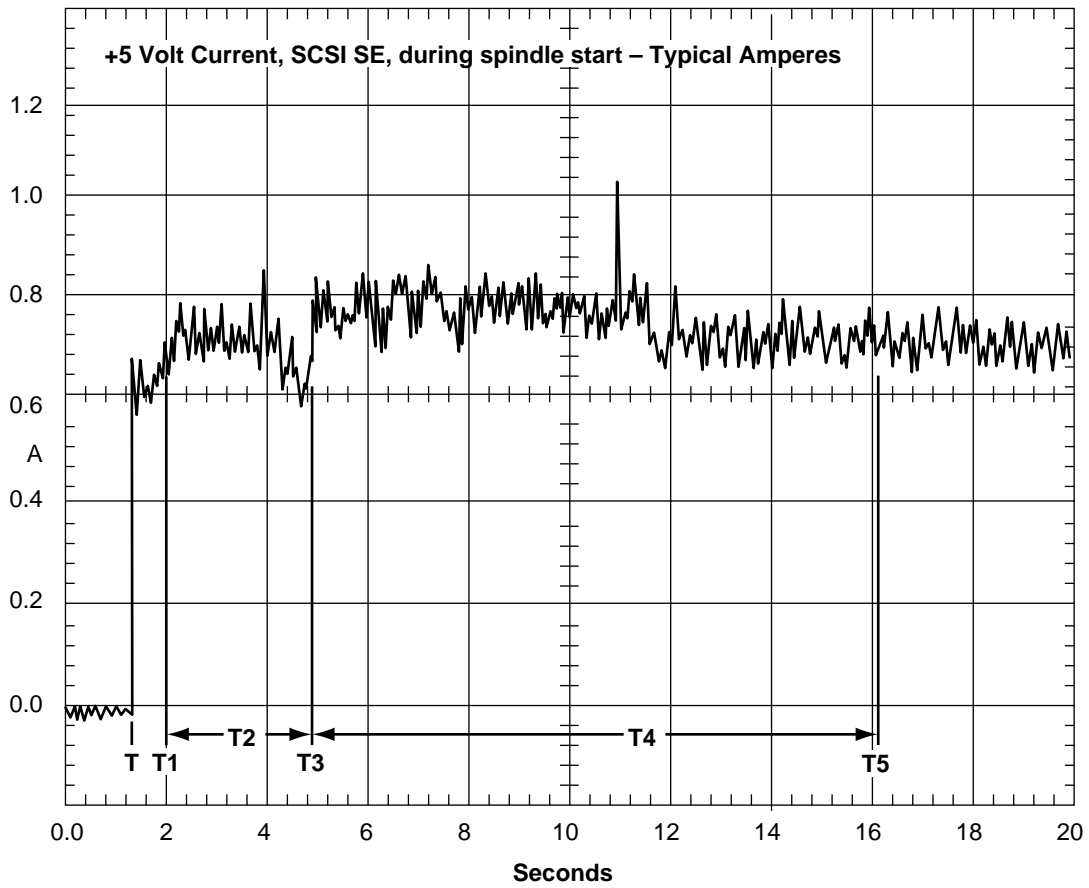


Figure 3b. Typical Barracuda 18XL family drive +5 V current profile

6.3 Power dissipation

To obtain drive typical operating random read (8 blocks) power dissipation at nominal voltages, refer to Figures 3c and 3d. The drive user can decide for themselves what number of I/O operations constitutes a typical number of I/O operations for their installation. Multiply Watts times 3.4123 to obtain BTUs per hour. Typical power dissipation under idle conditions for LVD models is 6.9 Watts (23.54 BTUs per hour).

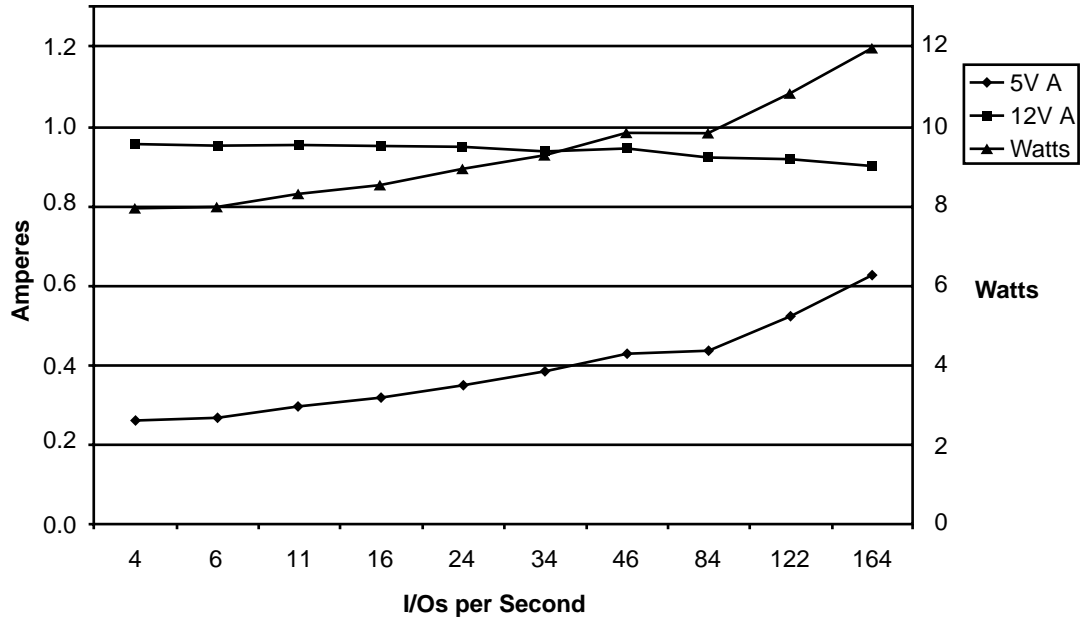


Figure 3c. DC current and power vs. input/output operations per second for ST318436 drives (LVD only)

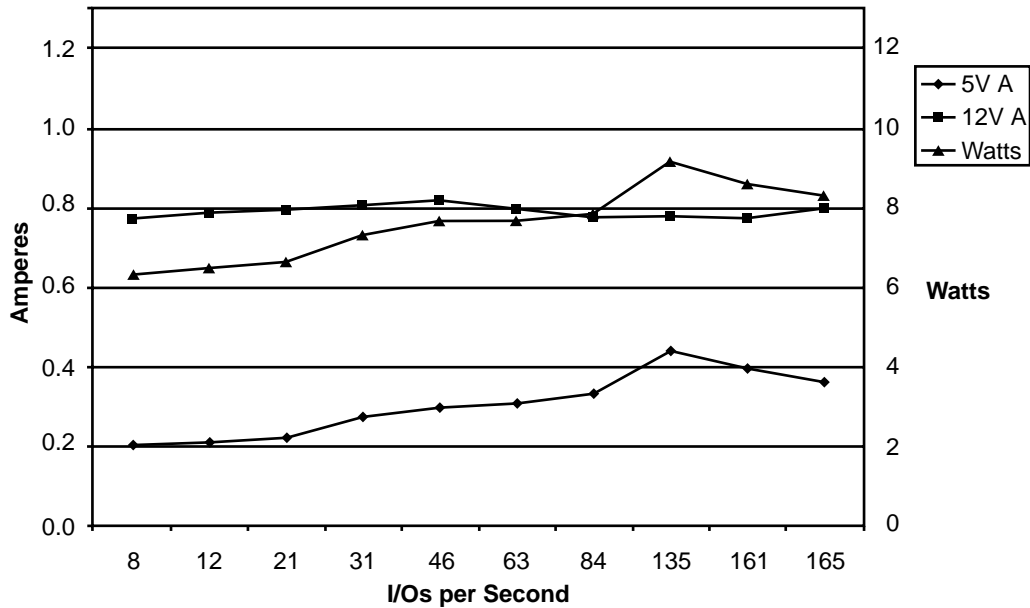


Figure 3d. DC current and power vs. input/output operations per second for ST39236 drives (SE only)

6.4 Environmental limits

Temperature and humidity values experienced by the drive must be such that condensation does not occur on any drive part. Altitude and atmospheric pressure specifications are referenced to a standard day at 58.7°F (14.8°C). Maximum Wet Bulb temperature is 82°F (28°C).

6.4.1 Temperature

a. Operating

With cooling designed to maintain the case temperatures of Table 3, Column 2, the drive meets all specifications over a 41°F to 131°F (5°C to 55°C) drive ambient temperature range with a maximum temperature gradient of 36°F (20°C) per hour. The enclosure for the drive should be designed such that the temperatures at the locations specified in Table 3, column 1 are not exceeded. Air flow may be needed to achieve these temperature values (see Section 8.3 and 8.3.1). Operation at case temperatures [4] above these values may adversely affect the drives ability to meet specifications.

The MTBF specification for the drive is based on operating in an environment that ensures that the case temperatures specified in Table 3, column 2 are not exceeded. Occasional excursions to drive ambient temperatures of 131°F (55°C) or 41°F (5°C) may occur without impact to specified MTBF. Air flow may be needed to achieve these temperatures (see Section 8.3.1). Continual or sustained operation at case temperatures above these values may degrade MTBF.

To confirm that the required cooling for the Barracuda electronics and HDA is provided, place the drive in its final mechanical configuration, perform random write/read operations. After the temperatures stabilize, measure the case temperature of the components listed in Table 3 (see notes [2] and [3]).

Operation of the drive at the maximum case temperature is intended for short time periods only. Continuous operation at the elevated temperatures will reduce product reliability.

Table 3: PCBA (Printed Circuit Board Assembly) and HDA temperatures

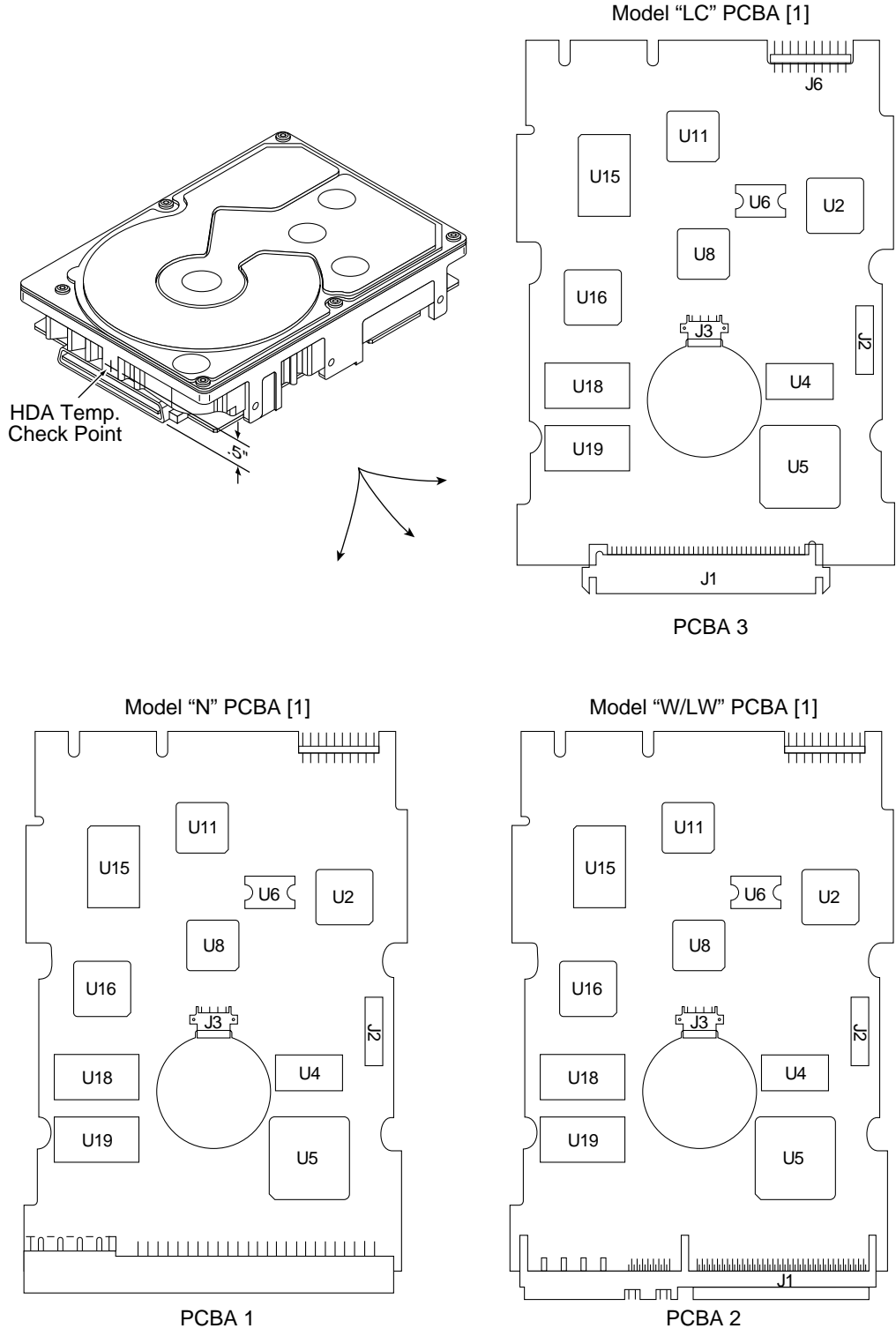
Items in Figure 4	Column 1 Maximum case [4] temperatures (°C) operating (55° ambient) [2]	Column 2 Maximum allowable case [4] temperatures (°C) [5] to meet MTBF spec.
HDA [3]	65°C	45°C
U5	123°C	103°C
U2	123°C	103°C
U8	105°C	85°C
U11	105°C	85°C

Note.

- [1] Section 8.3.1 describes the air-flow patterns to be used to meet case temperatures in column 2. Air flow should be opposite that shown in Section 8.3.1. Air velocity should be adequate to ensure that the case temperatures in Column 2 are not exceeded during drive operation.
- [2] The temperatures in Column 1 are calculated and may not reflect actual operating values. Sufficient cooling air may be required to ensure that these values are not exceeded.
- [3] Measure HDA temp at point labeled "HDA" on Figure 4.
- [4] PCBA mounted integrated circuit case.
- [5] Temperatures measured under 22.5°C ambient conditions.

b. Non-operating

−40° to 158°F (−40° to 70°C) package ambient with a maximum gradient of 45°F (25°C) per hour. This specification assumes that the drive is packaged in the shipping container designed by Seagate for use with drive.



[1]Bottom side of PCBA

Figure 4. Locations of PCBA components listed in Table 3

6.4.2 Relative humidity

The values below assume that no condensation on the drive occurs.

a. Operating

5% to 95% non-condensing relative humidity with a maximum gradient of 10% per hour.

b. Non-operating

5% to 95% non-condensing relative humidity.

6.4.3 Effective altitude (sea level)

a. Operating

–1,000 to +10,000 feet (–300 to +3,000 meters)

b. Non-operating

–1,000 to +40,000 feet (–300 to +12,200 meters)

6.4.4 Shock and vibration

Shock and vibration limits specified in this document are measured directly on the drive chassis. If the drive is installed in an enclosure to which the stated shock and/or vibration criteria is applied, resonances may occur internally to the enclosure resulting in drive movement in excess of the stated limits. If this situation is apparent, it may be necessary to modify the enclosure to minimize drive movement.

The limits of shock and vibration defined within this document are specified with the drive mounted by any of the four methods shown in Figure 5, and in accordance with the restrictions of Section 8.4. Orientation of the side nearest the LED may be up or down.

6.4.4.1 Shock

a. Operating—normal

The drive, as installed for normal operation, shall operate error free while subjected to intermittent shock not exceeding 15 Gs at a maximum duration of 11 msec (half sinewave). Shock may be applied in the X, Y, or Z axis.

b. Operating—abnormal

Equipment, as installed for normal operation, does not incur physical damage while subjected to intermittent shock not exceeding 15 Gs at a maximum duration of 11 msec (half sinewave). Shock occurring at abnormal levels may promote degraded operational performance during the abnormal shock period. Specified operational performance will continue when normal operating shock levels resume. Shock may be applied in the X, Y, or Z axis. Shock is not to be repeated more than two times per second.

c. Non-operating

The limits of non-operating shock shall apply to all conditions of handling and transportation. This includes both isolated drives and integrated drives.

The drive subjected to nonrepetitive shock not exceeding 150 Gs at a maximum duration of 11 msec (half sinewave) shall not exhibit device damage or performance degradation. Shock may be applied in the X, Y, or Z axis.

The drive subjected to nonrepetitive shock not exceeding 250 Gs at a maximum duration of 2 msec (half sinewave) does not exhibit device damage or performance degradation. Shock may be applied in the X, Y, or Z axis.

d. Packaged

Disc drives shipped as loose load (not palletized) general freight will be packaged to withstand drops from heights as defined in the table below. For additional details refer to Seagate specifications 30190-001 (under 100 lbs/45 kg) or 30191-001 (over 100 lbs/45 Kg).

Package size	Packaged/product weight	Drop height
<600 cu in (<9,800 cu cm)	Any	60 in (1524 mm)
600-1800 cu in (9,800-19,700 cu cm)	0-20 lb (0 to 9.1 kg)	48 in (1219 mm)
>1800 cu in (>19,700 cu cm)	0-20 lb (0 to 9.1 kg)	42 in (1067 mm)
>600 cu in (>9,800 cu cm)	20-40 lb (9.1 to 18.1 kg)	36 in (914 mm)

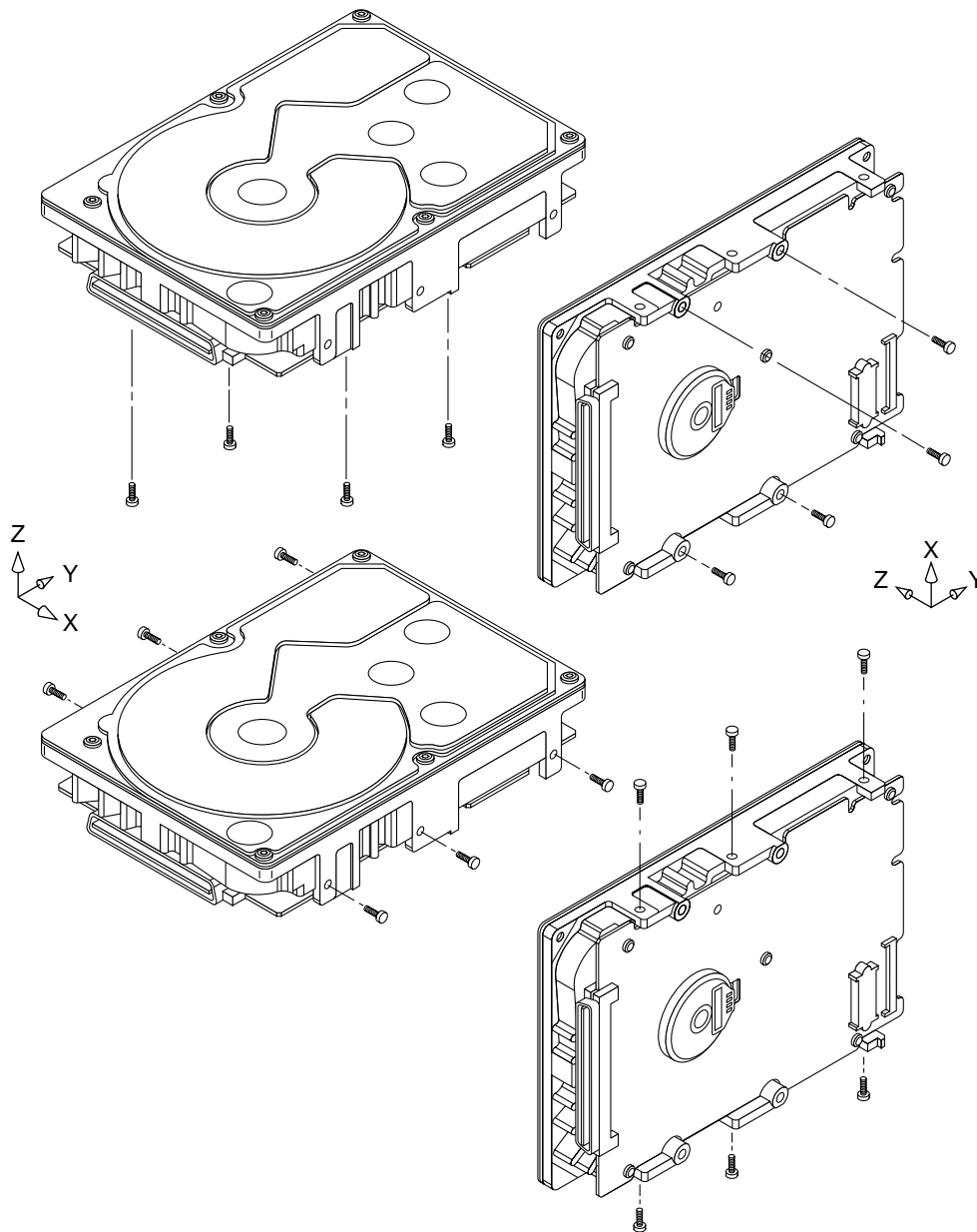


Figure 5. Recommended mounting

6.4.4.2 Vibration

a. Operating - normal

The drive as installed for normal operation, shall comply with the complete specified performance while subjected to continuous vibration not exceeding

5-22 Hz @ 0.045 inches (1.12 mm) displacement

22-300 Hz @ 1.1 G

300-350 Hz @ 0.83 G

Vibration may be applied in the X, Y, or Z axis.

b. Operating - abnormal

5-22 Hz @ 0.061 inches (1.12 mm) displacement

22-300 Hz @ 1.5 G (X, Y, or Z axis)

300-350 Hz @ 1.125 G

c. Non-operating

The limits of non-operating vibration shall apply to all conditions of handling and transportation. This includes both isolated drives and integrated drives.

The drive shall not incur physical damage or degraded performance as a result of continuous vibration not exceeding

5-22 Hz @ 0.100 inches (2.5 mm) displacement

22-400 Hz @ 2.5 G

Vibration may be applied in the X, Y, or Z axis.

6.4.5 Air cleanliness

The drive is designed to operate in a typical office environment with minimal environmental control.

6.4.6 Acoustics

Sound power during idle mode shall be 3.5 (mean) bels typical when measured to Seagate's 30553-001 specification.

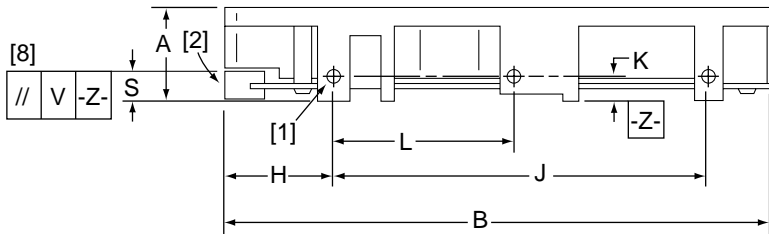
6.4.7 Electromagnetic susceptibility

See Section 2.1.2.

6.5 Mechanical specifications

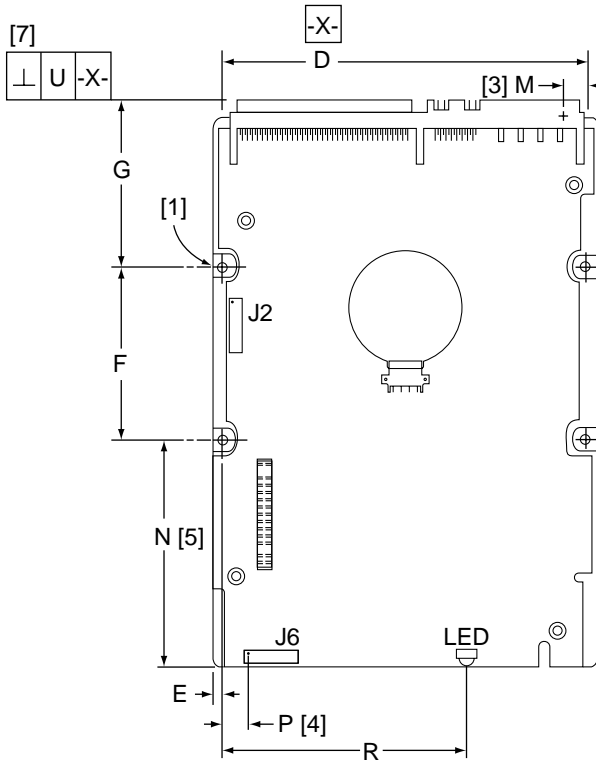
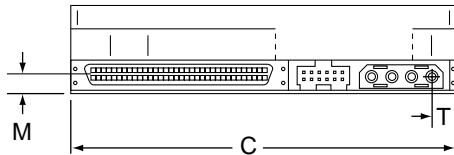
The following nominal dimensions are for information only. Refer to Figures 6a and 6c for detailed (toleranced) mounting configuration dimensions. See Section 8.4, "Drive mounting."

Height:	1.000 in	25.4 mm
Width:	4.000 in	101.6 mm
Depth:	5.75 in	146.05 mm
Weight:	1.5 pounds	0.68 kilograms



Notes:

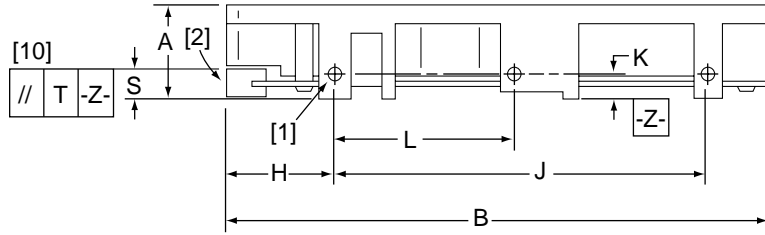
- [1] Mounting holes three on each side, 6-32 UNC. Max screw length into side of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm). Mounting holes four on bottom, 6-32 UNC. Max screw length into bottom of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm).
- [2] Power and interface connectors can extend past the "B" dimension by 0.040 in. (1.02 mm).
- [3] Centerline of pad for Pin 1 of power connector.
- [4] Centerline of pad for Pin 1 of J6.
- [5] Dimension "N" is from drive mounting hole to end of drive chassis (not the PCBA).
- [6] Nominal values. These cannot be added to any toleranced dimension to achieve a valid toleranced dimension.
- [7] Maximum connector non-perpendicularity to side planes pointed to by X.
- [8] Maximum amount of non-parallelism with plane -Z-.



Dimension Table

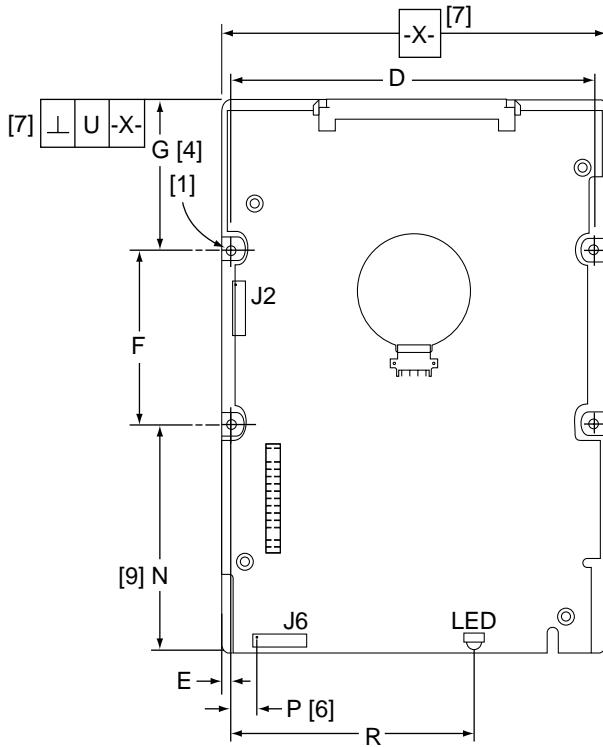
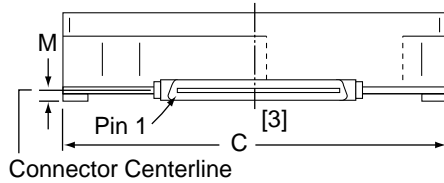
	Inches	Millimeters
A	1.028 max	26.10 max
B	5.787 max	146.99 max
C	4.000 ± .010	101.60 ± .25
D	3.750 ± .010	95.25 ± .25
E	.125 ± .010	3.18 ± .25
F	1.750 ± .010	44.45 ± .25
G	1.625 ± .020	41.28 ± .50
H	1.122 ± .020	28.50 ± .50
J	4.000 ± .010	101.60 ± .25
K	.250 ± .010	6.35 ± .25
L	1.638 ± .010	41.60 ± .25
M	.143 ± .020	3.63 ± .50
N	2.38 ± .005	60.45 ± .13
P	.405 [6]	10.29 [6]
R	2.265 [6]	52.53 [6]
S	.315 ± .010	8.00 ± .25
T	.278 ± .010	7.06 ± .25
U	.015 max	0.38 max
V	.015 max	0.38 max

Figure 6a. Mounting configuration dimensions for "W," "LW," and "LWV" model



Notes:

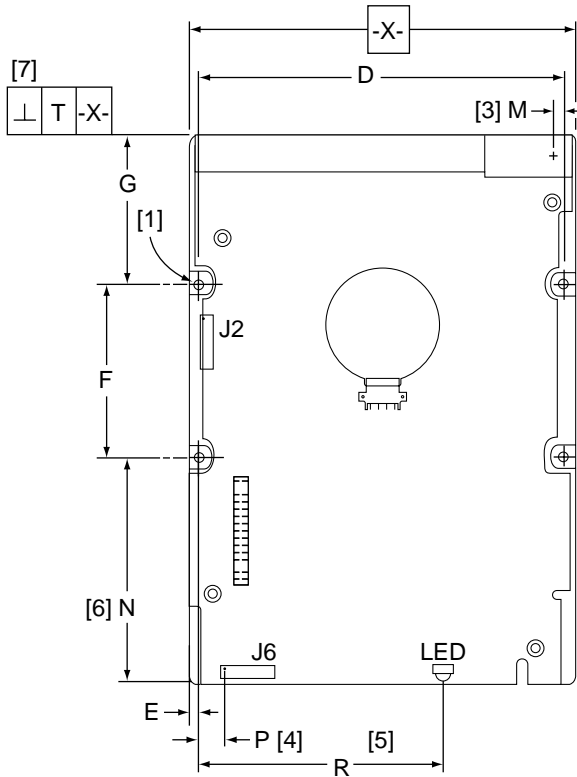
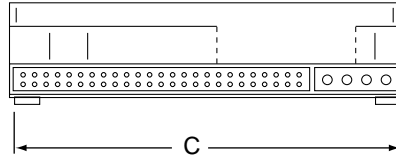
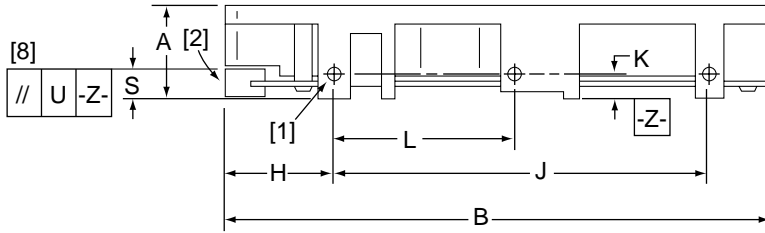
- [1] Mounting holes three on each side, 6-32 UNC. Max screw length into side of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm). Mounting holes four on bottom, 6-32 UNC. Max screw length into bottom of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm).
- [2] Interface connector is flush with the end of drive within ± 0.020 in. (.5 mm). The interface connector location may extend beyond HDA dimension "B" by 0.020 in. (.5 mm).
- [3] Connector J1 is centered (side to side) on drive within ± 0.020 in. (.508 mm).
- [4] Dimension "G" is from bottom rear drive mounting holes center(s) to the face of the connector at the center of the drive. It is also the dimension to the end of the drive HDA.
- [5] Dimensions "G" and "S" are unique requirements for SCA drives only, required for conformance with latest SFF Spec #8337.
- [6] Centerline of pad for Pin 1 of J6.
- [7] Maximum connector non-perpendicularity to side planes pointed to by X.
- [8] Nominal values. These cannot be added to any toleranced dimension to achieve a valid toleranced dimension.
- [9] Dimension "N" is from drive mounting hole to end of drive chassis (not to the end of the PCBA).
- [10] Maximum amount of non-parallelism with plane -Z-.



Dimension Table

	Inches		Millimeters	
A	1.028	max	26.10	max
B	5.787	max	146.99	max
C	4.000	$\pm .010$	101.60	$\pm .25$
D	3.750	$\pm .010$	95.25	$\pm .25$
E	.125	$\pm .010$	3.18	$\pm .25$
F	1.750	$\pm .010$	44.45	$\pm .25$
[5] G	1.625	$\pm .020$	41.28	$\pm .50$
H	1.122	$\pm .020$	28.50	$\pm .50$
J	4.000	$\pm .010$	101.60	$\pm .25$
K	.250	$\pm .010$	6.35	$\pm .25$
L	1.638	$\pm .010$	41.60	$\pm .25$
M	0.181	+ .015 - .010	4.597	+ .38 - .25
N	2.38	$\pm .005$	60.45	$\pm .13$
P	.405	[8]	10.29	[8]
R	2.265	[8]	52.53	[8]
S	.319	$\pm .010$	8.10	$\pm .25$
[7] T	.015	max	.38	max
U	.015	max	.38	max

Figure 6b. Mounting configuration dimensions for "LC" and "LCV" model



Notes:

- [1] Mounting holes three on each side, 6-32 UNC. Max screw length into side of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm). Mounting holes four on bottom, 6-32 UNC. Max screw length into bottom of drive 0.15 in. (3.81 mm). Screw tightening torque 6.0 in-lb (.675 NM) max with minimum thread engagement of 0.12 in. (3.05 mm).
- [2] The power interface connectors can extend beyond HDA dimension "B" by 0.040 in. (1.02 mm).
- [3] Centerline of pad for Pin 1 of power connector.
- [4] Centerline of pad for Pin 1 of J6.
- [5] Nominal values. These cannot be added to any toleranced dimension to achieve a valid toleranced dimension.
- [6] Dimension "N" is from drive mounting hole to end of drive chassis (not to the end of the PCBA).
- [7] Maximum connector non-perpendicularity side planes pointed to by -X-.
- [8] Maximum amount of non-parallelism with plane -Z-.

Dimension Table

	Inches		Millimeters	
A	1.028	max	26.10	max
B	5.787	max	146.99	max
C	4.000	± .015	101.60	± .25
D	3.750	± .010	95.25	± .25
E	.125	± .010	31.75	± .25
F	1.750	± .010	44.45	± .25
G	1.625	± .020	41.28	± .50
H	1.122	± .020	28.50	± .50
J	4.000	± .010	101.60	± .25
K	.250	± .010	6.35	± .25
L	1.638	± .010	41.60	± .25
M	.143	± .020	3.63	± .50
N	2.38	± .005	60.45	± .13
P	.405	[5]	10.29	[5]
R	2.265	[5]	52.53	[5]
S	.335	± .010	8.50	± .25
T	.015	max	.38	max
U	.015	max	.38	max

Figure 6c. Mounting configuration dimensions for "N" models

7.0 Defect and error management

The drive, as delivered, complies with this specification. The read error rate and specified storage capacity are not dependent upon use of defect management routines by the host (initiator).

Defect and error management in the SCSI system involves the drive internal defect/error management and SCSI systems error considerations (errors in communications between Initiator and the drive). Tools for use in designing a defect/error management plan are briefly outlined in this section, with references to other sections where further details are given.

7.1 Drive internal defects

During the initial drive format operation at the factory, media defects are identified, tagged as being unusable, and their locations recorded on the drive primary defects list (referred to as the "P" list and also as the ETF defect list). At factory format time, these known defects are also reallocated, that is, reassigned to a new place on the medium and the location listed in the defects reallocation table. The "P" list is not altered after factory formatting. Locations of defects found and reallocated during error recovery procedures after drive shipment are listed in the "G" list (defects growth list). The "P" and "G" lists may be referenced by the initiator using the Read Defect Data command (refer to the *SCSI Interface Product Manual*, part number 75789509).

7.2 Drive error recovery procedures

Whenever an error occurs during drive operation, the drive, if programmed to do so, performs error recovery procedures to attempt to recover the data. The error recovery procedures used depend on the options previously set up in the error recovery parameters mode page. Error recovery and defect management may involve the use of several SCSI commands, the details of which are described in the *SCSI Interface Product Manual*. The drive implements selectable error recovery time limits such as are required in video applications. For additional information on this, refer to the Error Recovery Page table in the *SCSI Interface Product Manual*, which describes the Mode Select/Mode Sense Error Recovery parameters.

The error recovery scheme supported by the drive provides a means to control the total error recovery time for the entire command in addition to controlling the recovery level for a single LBA. The total amount of time spent in error recovery for a command can be limited via the Recovery Time Limit bytes in the Error Recovery Mode Page. The total amount of time spent in error recovery for a single LBA can be limited via the Read Retry Count or Write Retry Count bytes in the Error Recovery Mode Page.

The drive firmware error recovery algorithms consist of 12 levels for read recoveries and 16 levels for writes.

Table 4 equates the Read and Write Retry Count with the maximum possible recovery time for read and write recovery of individual LBAs. The times given do not include time taken to perform reallocations, if reallocations are performed. Reallocations are performed when the ARRE bit (for reads) or AWRE bit (for writes) is one, the RC bit is zero, and the Recovery Time Limit for the command has not yet been met. Time needed to perform reallocation is not counted against the Recovery Time Limit.

The Read Continuous (RC) bit, when set to one, requests the disc drive to transfer the requested data length without adding delays (for retries or ECC correction) that may be required to insure data integrity. The disc drive may send erroneous data in order to maintain the continuous flow of data. The RC bit should only be used when data integrity is not a concern and speed is of utmost importance. If the Recovery Time Limit or retry count is reached during error recovery, the state of the RC bit is examined. If the RC bit is set, the drive will transfer the unrecovered data with no error indication and continue to execute the remaining command. If the RC bit is not set, the drive will stop data transfer with the last good LBA, and report a "CHECK CONDITION, UNRECOVERED READ ERROR."

Table 4: Read and write retry count maximum recovery times [1]

Read retry count	Maximum recovery time per LBA (cumulative, msec)	Write retry count	Maximum recovery time per LBA (cumulative, msec)
0	108.73	0	92.0
1	125.46	1	117.1
2	426.56	2	125.46
3	460.02	3	150.55
4	526.93	4	301.10
5	593.84	5	359.65
6	677.48	6	593.84
7	802.94	7	618.94
8	836.4	8	660.76
9	911.68	9	685.85
10	2,371.24	10	1,735.68
11 (default)	3,422.04	11	1,760.76
		12	1,769.12
		13	1,794.2
		14	1,944.68
		15	2,003.2

[1] These values are subject to change (for general information only).

Setting these retry counts to a value below the default setting could result in an increased unrecovered error rate which may exceed the value given in this product manual. A setting of zero results in the drive not performing error recovery.

For example, suppose the read/write recovery page has the RC bit = 0, the read retry count set to four, and the recovery time limit (Mode Sense Page 01, bytes 10, 11) is set to FF FF hex (maximum). A four LBA read command is allowed to take up to 526.68 msec recovery time for each of the four LBAs in the command. If the recovery time limit (Mode Sense Page 01, bytes 10, 11) is set to 00 C8 hex (200 milliseconds decimal) a four LBA read command is allowed to take up to 200 milliseconds for all error recovery within that command. The use of the recovery time limit field (Mode Sense Page 01, bytes 10,11) allows finer granularity on control of the time spent in error recovery. The Recovery Time Limit only starts counting when the drive is executing error recovery and it restarts on each command. Therefore, each command's total recovery time is subject to the Recovery Time Limit. Note: A RTL of zero (0) will use the drive default value of FF FF. Minimum RTL is achieved by specifying the RTL set to 00 01.

7.3 SCSI systems errors

Information on the reporting of operational errors or faults across the interface is given in the *SCSI Interface Product Manual*, part number 75789509. Message Protocol System is described in the *SCSI Interface Product Manual*. Several of the messages are used in the SCSI systems error management system. The Request Sense command returns information to the host about numerous kinds of errors or faults. The Receive Diagnostic Results reports the results of diagnostic operations performed by the drive.

Status returned by the drive to the Initiator is described in the *SCSI Interface Product Manual*. Status reporting plays a role in the SCSI systems error management and its use in that respect is described in sections where the various commands are discussed.

8.0 Installation

The first thing to do when installing a drive is to set the drive ID (select) on the SCSI bus and set up certain operating options. This is usually done by installing small shorting jumpers on the pins of connectors J2 and J6 on the Printed Circuit Board Assembly (PCBA) (or J5 on the “LW” models), or via the drive to host I/O signals on “LC” models. Some users connect cables to J6 or J5 and perform the set-up using remote switches.

Configure drive options

For option jumper locations and definitions refer to Figures 7a, 7b, and 7d. Drive default mode parameters are not normally needed for installation. Refer to Section 9.3.2 for default mode parameters if they are needed.

- Ensure that the SCSI ID of the drive is not the same as the host adapter. Most host adapters use SCSI ID 7. ID 7 is the highest priority on both 8 and 16 bit data buses.
- If multiple devices are on the bus set the drive SCSI ID to one that is not presently used by other devices on the bus.
- If the drive is the only device on the bus, attach it to the end of the SCSI bus cable. On “LC” and “LW” models, external terminators must be provided by the user, systems integrator or host equipment manufacturer.
- If the drive is attached to a bus that contains other devices, and if the new drive is not attached to the end of the bus, no terminators are needed.

Note. For additional information about terminator requirements, refer to Sections 9.8 and 9.9.

- Set all appropriate option jumpers for desired operation prior to power on. If jumpers are changed after power has been applied, recycle the drive power to make the new settings effective.
- Installation instructions are provided by host system documentation or with any additionally purchased drive installation software. If necessary see Section 10 for Seagate support services telephone numbers.
- Do not remove the manufacturer’s installed labels from the drive and do not cover with additional labels, as the manufacturer labels contain information required when servicing the product.

Formatting

- It is not necessary to low level format this drive. The drive is shipped from the factory low level formatted in 512 byte sectors.
- Reformat the drive if a different spare sector allocation scheme is selected.
- High level format the drive involves assigning one or more partitions or logical drives to the drive volume. Follow the instructions in the system manuals for the system into which the drive is to be installed.
- Systems that have Windows 95 Operating System version 950B (this has FAT 32) or later do not need to partition the drive in order to access the total capacity of the drive.

8.1 Drive ID/option select header

Figures 7a and 7b show views of the drive ID select jumper connectors. Figure 7d shows the option select jumper connector for all models. Figure 7b shows a rear view of model drives for the purpose of showing J5 of the drive. Both J5 and J6 have pins for selecting drive ID and for connecting the remote LED cable. Only one or the other should be used, although using both at the same time would not damage the drive. The notes following the figures describe the functions of the various jumper positions on the connectors J2, J5 and J6. See your local sales representative for suggested part number. A bag with the two jumper plug types is shipped with the standard OEM drives.

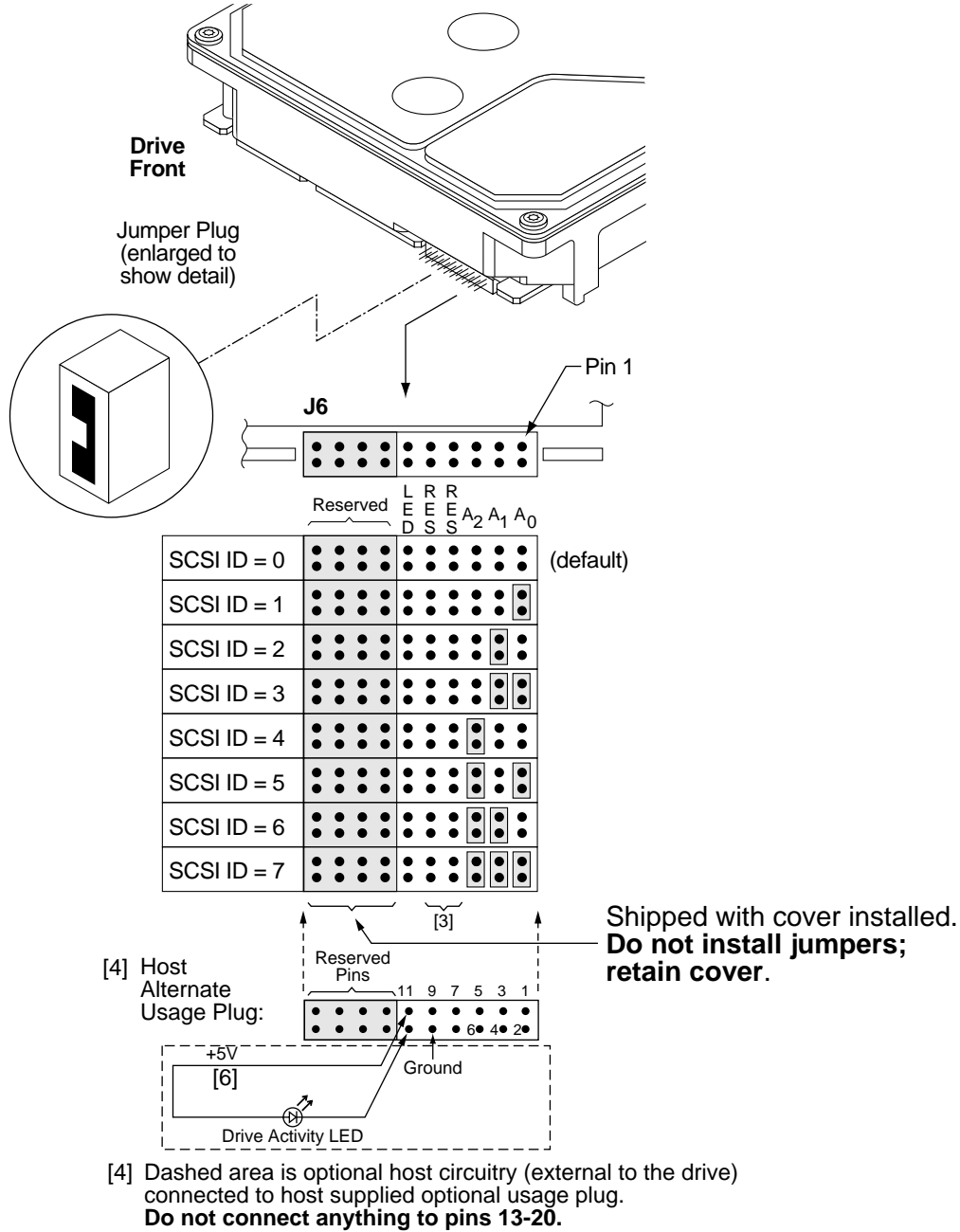


Figure 7b. Barracuda 18XL family drive ID select header J6 for N model (J6 Pins 1–12)

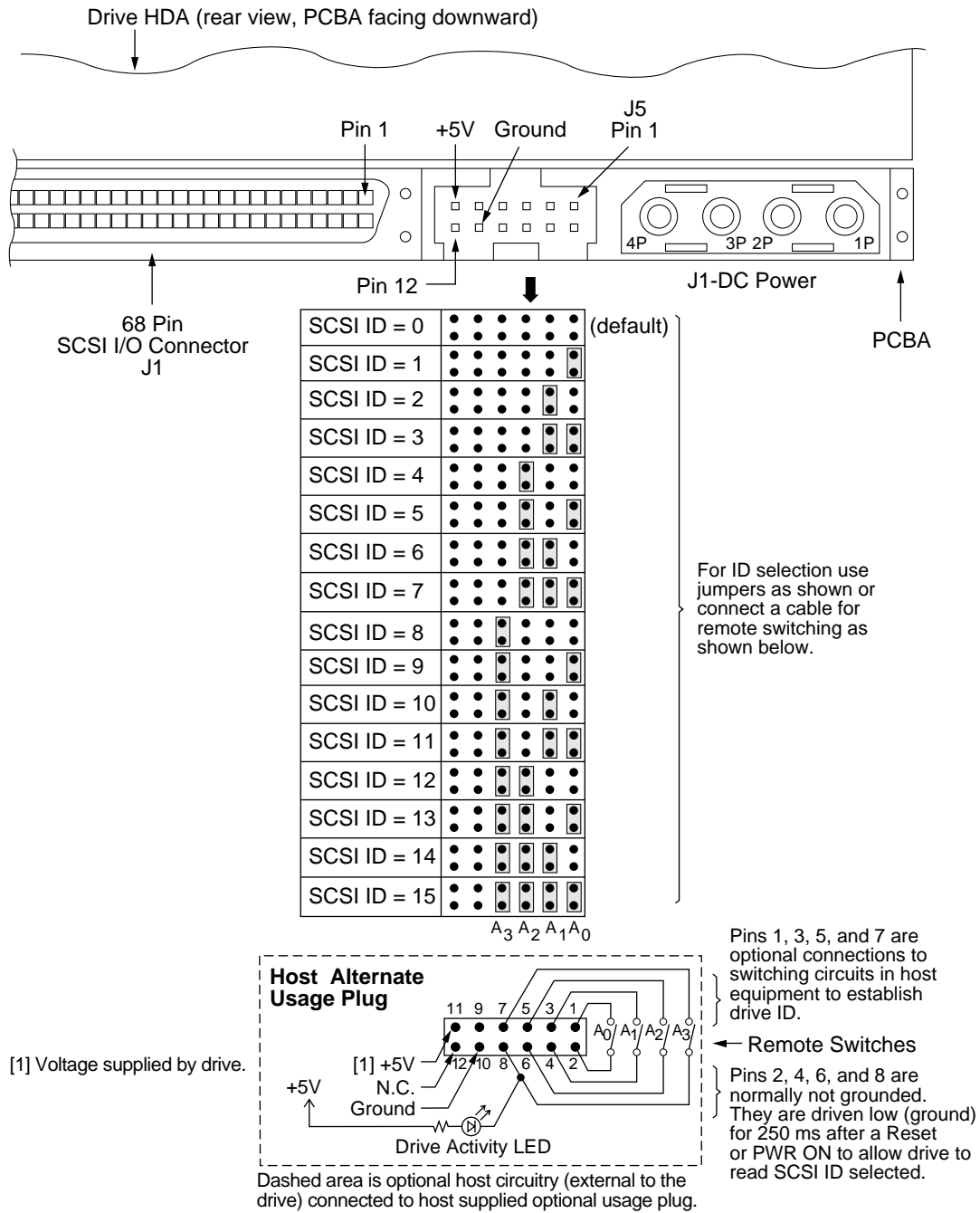
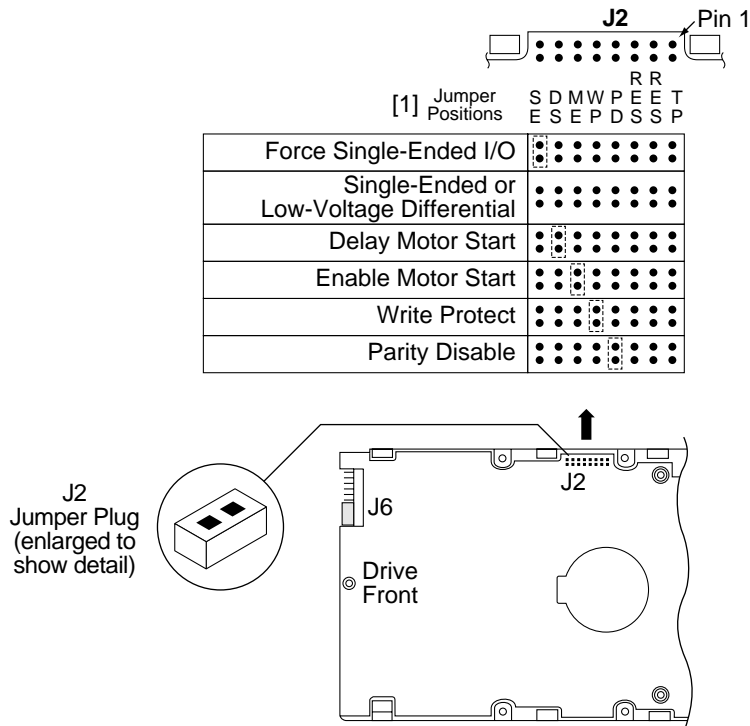


Figure 7c. Barracuda 18XL family drive ID select header J5 for W/LW/LWV models (J5 Pins 1–12)



[1] Jumper position names shown here are not marked on the PCBA. They are shown here for reference only. Additional information on these functions is in Section 8.1.1.

Figure 7d. Barracuda 18XL family drive option select header (for LW/LC/LWV/LCV models)

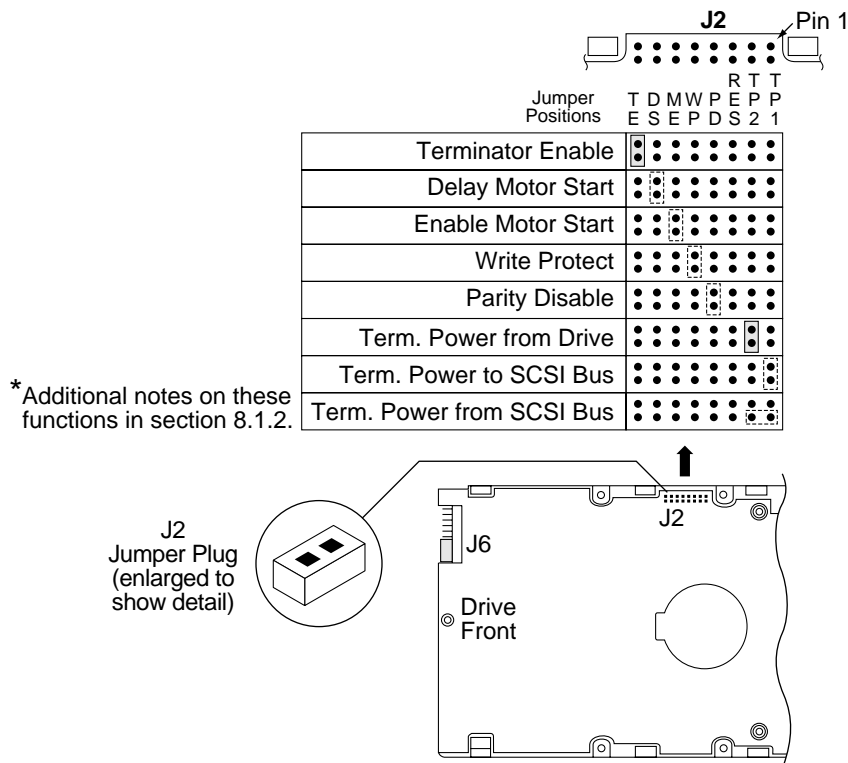


Figure 7e. Barracuda 18XL family drive option select header (for N and W models)

8.1.1 Function description

J2

jumper

installation Jumper function description

TE (Applies only to “N” and “W” models)

<u>On</u>	With the jumper installed, the onboard (non-removable) terminator circuits are enabled (connected to the I/O lines). Default is jumper installed.
Off	Terminator circuits not enabled (not connected to I/O lines).

SE

On	Forces drive to use single-ended I/O drivers/receivers only.
Off	Drive can operate on the interface in low voltage differential mode or single-ended, depending on the voltage state of the I/O “DIFFSNS” line. Default is no jumper on.

DS ME

<u>Off</u>	<u>Off</u>	Spindle starts immediately after power up— Default setting.
Off	On	Drive spindle does not start until Start Unit command received from host.
On	Off	Spindle Startup is delayed by SCSI ID times 12 seconds after power is applied, i.e., drive 0 spindle starts immediately when DC power connected, drive 1 starts after 12 second delay, drive 2 starts after 24 second delay, etc.
On	On	Drive spindle starts when Start Unit command received from host. Delayed start feature is overridden and does not apply when ME jumper is installed.

WP

On	Entire drive is write protected.
<u>Off</u>	Drive is not write protected. Default is no WP jumper installed.

PD

On	Parity checking and parity error reporting by the drive is disabled.
<u>Off</u>	Drive checks for parity and reports result of parity checking to host. Default is PD jumper not installed.

RES (2)

<u>Off</u>	Reserved jumper position. Default is no jumper installed.
------------	---

TP (Not for “LC” model)

Off	No terminator power is connected to drive terminators or SCSI bus I/O cable. ¹ No jumpers on is factory default .
On	Drive supplies power to SCSI bus I/O cable. ¹ A jumper on the TP position may be needed to power external terminators (see Section 9.8 and Figure 10a).

TP1 and TP2 (Applies only to “N” and “W” models)

On	This horizontally-positioned jumper across the two TP positions furthest from the PCB edge, connects terminator power from SCSI bus I/O Termpower cable ² to the drive’s internal terminators (for single-ended I/O only).
Off	See above explanations for TP jumpers.

1. See Figure 7d and 7e for pins used for Termpower.
2. See Figure 7d for pins used for Termpower.

8.2 Drive orientation

The balanced rotary arm actuator design of the drive allows it to be mounted in any orientation. All drive performance characterization, however, has been done with the drive in horizontal (discs level) and vertical (drive on its side) orientations, and these are the two preferred mounting orientations.

8.3 Cooling

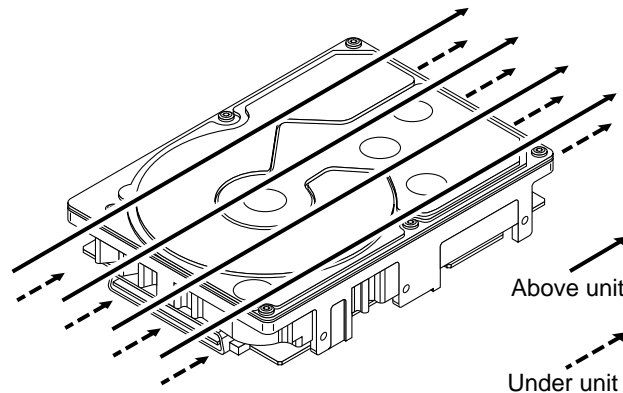
Cabinet cooling must be designed by the customer so that the ambient temperature immediately surrounding the drive will not exceed temperature conditions specified in Section 6.4.1, "Temperature." Specific consideration should be given to make sure adequate air circulation is present around the printed circuit board (PCBA) to meet the requirements of Section 6.4.1, "Temperature."

8.3.1 Air flow

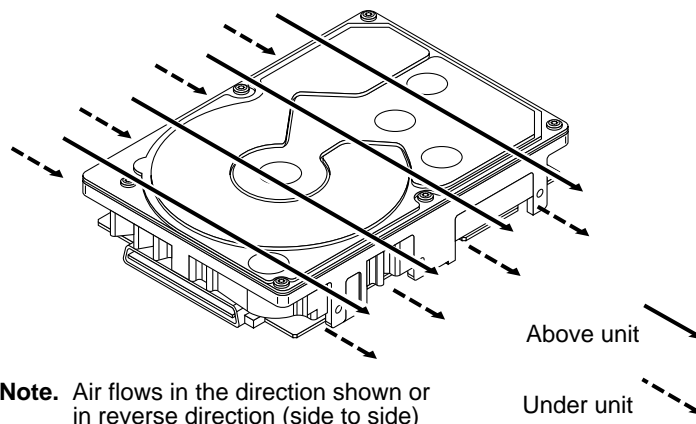
The rack, cabinet, or drawer environment for the Barracuda 18XL drive must provide heat removal from the electronics and head and disc assembly (HDA). You should confirm that adequate heat removal is provided using the temperature measurement guidelines described in Section 6.4.1.

Forced air flow may be required to keep temperatures at or below the specified case temperatures of Table 3, Column 2, in which case the drive should be oriented, or air flow directed, so that the least amount of air flow resistance is created while providing air flow to the electronics and HDA. Also, the shortest possible path between the air inlet and exit should be chosen to minimize the travel length of air heated by the drive and other heat sources within the rack, cabinet, or drawer environment.

If forced air is determined to be necessary, possible air-flow patterns are shown in Figure 8. The air-flow patterns are created by one or more fans, either forcing or drawing air as shown in the illustrations. Conduction, convection, or other forced air-flow patterns are acceptable as long as the temperature measurement guidelines of Section 6.4.1 are met.



Note. Air flows in the direction shown (front to back) or in reverse direction (back to front)



Note. Air flows in the direction shown or in reverse direction (side to side)

Figure 8. Air flow (suggested)

8.4 Drive mounting

When mounting the drive using the bottom holes (x-y plane in Figure 5) care must be taken to ensure that the drive is not physically distorted due to a stiff non-flat mounting surface. The allowable mounting surface stiffness is 80 lb/in (14.0 N/mm). The following equation and paragraph define the allowable mounting surface stiffness:

$$K = \frac{F}{x} = 80\text{lb/in (14.0 N/mm)}$$

where 'k' represents the mounting surface stiffness (units of lb/in or N/mm), and 'x' represents the out-of-plane mounting surface distortion (units of inches or millimeters). The out-of-plane distortion ('x') is determined by defining a plane with three of the four mounting points fixed and evaluating the out-of-plane deflection of the fourth mounting point when a known force is applied to the fourth point.

Note. Before mounting the drive in any kind of 3.5-inch to 5.25-inch adapter frame, verify with Seagate Technology that the drive can meet the shock and vibration specifications given herein while mounted in such an adapter frame. Adapter frames that are available may not have a mechanical structure capable of mounting the drive so that it can meet the shock and vibration specifications listed in this manual.

8.5 Grounding

Signal ground (PCBA) and HDA ground are connected together in the drive and cannot be separated by the user. The equipment in which the drive is mounted is connected directly to the HDA and PCBA with no electrically isolating shock mounts. If it is desired for the system chassis to not be connected to the HDA/PCBA ground, the systems integrator or user must provide a nonconductive (electrically isolating) method of mounting the drive in the host equipment.

Increased radiated emissions may result if you do not provide the maximum surface area ground connection between system ground and drive ground. This is the system designer's and integrator's responsibility.

9.0 Interface requirements

9.1 General description

This section describes in essentially general terms the interface requirements supported by the Barracuda 18XL. No attempt is made to describe all of the minute details of conditions and constraints that must be considered by designers when designing a system in which this family of drives can properly operate. Seagate declares that the drives operate in accordance with the appropriate ANSI Standards referenced in various places herein, with exceptions as noted herein or in the *Seagate SCSI Interface Product Manual*, part number 75789509.

9.2 SCSI interface messages supported

Table 5 lists the messages supported by the SCSI-2 and SCSI-3 modes of the Barracuda 18XL family drives.

Table 5: SCSI messages supported by Barracuda 18XL family drives

Message name	Message code	Supported by Barracuda 18XL
Abort	06h	Y
Abort-tag	0Dh	Y
Bus device reset	0Ch	Y
Clear queue	0Eh	Y
Command complete	00h	Y
Continue I/O process	12h	Y
Disconnect	04h	Y
Extended messages	01h [1]	Y
Identify	80h-FFh	Y
Ignore wide residue (two bytes)	23h	Y
Initiate recovery	0Fh	N
Initiator detected error	05h	Y
Linked command complete	0Ah	Y
Linked command complete with flag	0Bh	Y
Message parity error	09h	Y
Message reject	07h	Y
Modify data pointer	[1]	N
No operation	08h	Y
Parallel protocol request	[1]	Y
Queue tag messages (two bytes)		
Head of queue tag	21h	Y
Ordered queue tag	22h	Y
Simple queue tag	20h	Y
Release recovery	10h	N
Restore pointers	03h	Y
Save data pointer	02h	Y
Synchronous data transfer req.	[1]	Y
Target transfer disable	13h	Y
Terminate I/O process	11h	N
Wide data transfer request	[1]	Y

Notes.

[1] Extended messages (see the *SCSI Interface Product Manual*, part number 75789509).

9.3 SCSI interface commands supported

Table 6 following lists the SCSI interface commands that are supported in the Barracuda 18XL Family drives.

Table 6: Commands supported by Barracuda 18XL family drive

Command name	Command code	Supported by Barracuda 18XL
Change definition	40h	N
Compare	39h	N
Copy	18h	N
Copy and verify	3Ah	N
Format unit [1]	04h	Y
Block Format		N
Bytes from index		Y
Physical sector format		Y
DPRY bit supported		N
DCRT bit supported		Y
STPF bit supported		Y
IP bit supported		Y
DSP bit supported		Y
IMMED bit supported		Y
VS (vendor specific)		N
Inquiry (see Table 7 for Inquiry data)	12h	Y
Date code page (C1h)		Y
Device Behavior page (C3h)		Y
Firmware numbers page (C0h)		Y
Implemented operating def page (81h)		Y
Jumper settings page (C2h)		Y
Supported Vital product data page (00h)		Y
Unit serial number page (80h)		Y
Lock-unlock cache	36h	N
Log select	4Ch	Y
DU bit		N
DS bit		Y
TSD bit		Y
ETC bit		N
TMC bit		N
LP bit		N
Log sense	4Dh	Y
Cache statistics page (37h)		Y
Non-medium error page (06h)		Y
Pages supported list (00h)		Y
Power-on time page (3Eh)		Y
Read error counter page (03h)		Y
Drive self-test page (10h)		Y
S.M.A.R.T. attribute log page (30h)		Y
Verify error counter page (05h)		Y
Write error counter page (02h)		Y
Mode select (same pages as Mode Sense command)	15h	Y [2]
Mode select (10)	55h	Y
Capacity Programming		Y
Mode sense	1Ah	Y [2]

Table 6: Commands supported by Barracuda 18XL family drive (Continued)

Command name	Command code	Supported by Barracuda 18XL
Caching parameters page (08h)		Y
Control mode page (0Ah)		Y
Disconnect/reconnect (02h) (DTDC, DIMM not used)		Y
Error recovery page (01h)		Y
Format page (03h)		Y
Information exceptions control page (1Ch)		Y
Notch and Partition Page (0Ch)		N
Power condition page (1Ah)		Y
Rigid disc drive geometry page (04h)		Y
Unit attention page (00h)		Y
Verify error recovery page (07h)		Y
Xor Control page (10h)		N
Mode sense (10)	5Ah	Y
Prefetch	34h	N
Read	08h	Y
Read defect data (12)	B7h	Y
Read buffer (modes 0, 2, 3 supported)	3Ch	Y
Read capacity	25h	Y
Read defect data (10)	37h	Y
Read extended	28h	Y
DPO bit supported		Y
FUA bit supported		Y
Read long	3Eh	Y
Reassign blocks	07h	Y
Rebuild	81h	N
Receive diagnostic results	1Ch	Y
Supported diagnostics pages (00h)		Y
Translate page (40h)		Y
Regenerate	82h	N
Release	17h	Y
Release (10)	57h	Y
Request sense	03h	Y
Actual retry count bytes		Y
Deferred error supported		Y
Extended sense		Y
Field pointer bytes		Y
Reserve	16h	Y
3rd party reserve		Y
Extent reservation		N
Reserve (10)	56h	Y
3rd part reserve		Y
Extent reservation		N
Rezero unit	01h	Y
Search data equal	31h	N
Search data high	30h	N
Search data low	32h	N
Seek	0Bh	Y

Table 6: Commands supported by Barracuda 18XL family drive (Continued)

Command name	Command code	Supported by Barracuda 18XL
Seek extended	2Bh	Y
Send diagnostics	1Dh	Y
Supported diagnostics pages (00h)		Y
Translate page (40h)		Y
DST (logical unit self-test diagnostics)		Y
Set limits	33h	N
Start unit/stop unit (spindle ceases rotating) (1Bh)	1Bh	Y
Synchronize cache	35h	Y
Test unit ready	00h	Y
Verify	2Fh	Y
DPO bit supported		Y
BYTCHK bit supported		Y
Write	0Ah	Y
Write and verify	2Eh	Y
DPO bit supported		Y
BYTCHK bit supported		Y
Write buffer (modes 0, 2, supported)	3Bh	Y
Firmware download option (modes 5, 7 supported) [3]		Y
Write extended	2Ah	Y
DPO bit supported		Y
FUA bit support		Y
Write long	3Fh	Y
Write same	41h	Y
PB data		N
LB data		N
XDRead	52h	N
XDWrite	50h	N
XDWrite extended	80h	N
XPWrite	51h	N

- [1] The drive can format to sector sizes from 512 to 2,048 bytes/sector in multiples of 2 bytes/sector.
- [2] Table 9a shows how individual bits are set and which are changeable by the host.
- [3] **WARNING:** A power loss during flash programming can result in firmware corruption. This usually makes the drive inoperable.

Table 7 lists the Standard Inquiry command data that the drive should return to the initiator per the format given in the *SCSI Interface Product Manual*, part number 75789509, Inquiry command section.

Table 7: Barracuda 18XL family drive Standard Inquiry data

Bytes	Data (HEX)																
0-15	00	00	[03] ¹	[12] ²	8B	00	01	3E	53	45	41	47	41	54	45	20	VENDOR ID
16-31	53	54	[33] ³	[31] ³	[38] ³	[34] ³	[33] ³	[36] ³	[4C] ³	[57] ³	[20] ³	20	20	20	20	20	PRODUCT ID
32-47	R#	R#	R#	R#	S#	S#	S#	S#	S#	S#	S#	S#	00	00	00	00	
48-63	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
64-79	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
80-95	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
96-111	00	43	6F	70	79	72	69	67	68	74	20	28	63	29	20	[31]	COPYRIGHT
112-127	[39]	[39]	[39] ⁴	20	53	65	61	67	61	74	65	20	41	6C	6C	20	NOTICE
128-143	72	69	67	68	74	73	20	72	65	73	65	72	76	65	64	20	

[]¹ 03 means SCSI-3 implemented. Change Definition command not supported.

[]² 01 means response data in SCSI-1 format and has compatibility with Common Command Set data.
02 means response data in SCSI-2/SCSI-3 format. In addition, 12 indicates that the drive uses the hierarchical addressing mode to assign LUNs to logical units. Default is 12.

R# Four ASCII digits representing the product Firmware Version number. The Firmware Release Number is also given in the Vital Product Data page C0h, together with servo firmware release numbers.

S# Eight ASCII digits representing the eight digits of the product serial number.

[]³ Bytes 18 through 26 reflect model of drive. Shown here are hex values for Model ST318436LW. The hex values for bytes 18 through 26 for the various models are listed below.

Model number	Bytes 18-26 hex values
ST318436LW	33 31 38 34 33 36 4C 57 20
ST318436LC	33 31 38 34 33 36 4C 43 20
ST318436LWV	33 31 38 34 33 36 4C 57 56
ST318436LCV	33 31 38 34 33 36 4C 43 56
ST318426LW	33 31 38 34 32 36 4C 57 20
ST318426LC	33 31 38 34 32 36 4C 43 20
ST318416N	33 31 38 34 31 36 4E 20 20
ST318416W	33 31 38 34 31 36 57 20 20
ST39236LW	33 39 32 33 36 4C 57 20 20
ST39236LC	33 39 32 33 36 4C 43 20 20
ST39236LWV	33 39 32 33 36 4C 57 56 20
ST39236LCV	33 39 32 33 36 4C 43 56 20
ST39226LW	33 39 32 32 36 4C 57 20 20
ST39226LC	33 39 32 32 36 4C 43 20 20
ST39216N	33 39 32 31 36 4E 20 20 20
ST39216W	33 39 32 31 36 57 20 20 20

[]⁴ Copyright Year - changes with actual year.

9.3.1 Inquiry Vital Product data

Instead of the standard Inquiry data shown in Table 7, the initiator can request several Vital Product Data pages by setting the Inquiry command EVPD bit to one. The *SCSI Interface Product Manual*, part number 75789509, lists the Vital Product Data pages and describes their formats. A separate Inquiry command must be sent to the drive for each Vital Product Data page the initiator wants the drive to send back.

Table 8 shows the Vital Product Data pages for the drives of this product manual. “Y” means reporting that particular parameter is supported, but it may be different for each drive.

Table 8: Vital product data pages

Byte	Page	Supported
Unit serial number page 80h		
0	Peripheral qualifier/peripheral device type	—
1	Page code number	80
2	Reserved	00
3	Page length	14
4-23	Product serial number	Y
Implemented operating definition page 81h		
0	Peripheral qualifier/peripheral device type	—
1	Page code number	81
2	Reserved	00
3	Page length	03
4	SAVIMP=0, current operating definition	Y
5	SAVIMP=0, default operating definition	Y
6	SAVIMP=0, supported operating definition	Y
Firmware numbers page C0h		
0	Peripheral qualifier/peripheral device type	—
1	Page code number	C0
2	Reserved	00
3	Page length	38
4-11	SCSI firmware release number	Y
12-19	Servo firmware release number	Y
20-27	SAP block point numbers (major/minor)	Y
28-31	Servo firmware release date	Y
32-35	Servo firmware release year	Y
36-43	SAP firmware release number	Y
44-47	SAP firmware release date	Y
48-51	SAP firmware release year	Y
52-55	SAP manufacturing key	Y
56-59	Servo firmware product families and product family member IDs	Y
Data code page C1h		
0	Peripheral qualifier/peripheral device type	Y
1	Page code number	C1
2	Reserved	00
3	Page length	10
4-11	Manufacture (ETF) date—MMDDYYYY	Y
12-19	SCSI firmware release date—MMDDYYYY	Y

Table 8: Vital product data pages (Continued)

Byte	Page	Supported
Jumper settings page C2h		
0	Peripheral qualifier/peripheral device type	Y
1	Page code number	C2
2	Reserved	00
3	Page length	02
4	SCSI ID, delayed motor start, motor start, write protect, parity enable	Y
5	Terminator enable	[1]

[1] “N” and “W” models support Terminator Enable.

Vital Product data pages C3h, D1h, and D2h are supported vendor-specific pages. Descriptions of their usage are not available at this time.

9.3.2 Mode Sense data

The Mode Sense command provides a means for the drive to report its operating parameters to the initiator. The drive maintains four sets of Mode parameters: Default values, Saved values, Current values and Changeable values.

Default values are hard coded in the drive firmware that is stored in flash EPROM nonvolatile memory on the drive PCBA. Default values can be changed only by downloading a complete set of new firmware into the flash EPROM. An initiator can request and receive from the drive a list of Default values and use those in a Mode Select command to set up new Current and Saved values, where the values are changeable.

Saved values are stored on the disk media using a Mode Select command. Only parameter values that are allowed to be changed can be changed by this method. See “Changeable values” defined below. Parameters in the Saved values list that are not changeable by the Mode Select command get their values from the Default values storage.

Current values are volatile values currently being used by the drive to control its operation. A Mode Select command can be used to change these values (only those that are changeable). Originally, they are installed from Saved or Default values after a power on reset, hard reset, or Bus Device Reset message.

Changeable values form a bit mask, stored in nonvolatile memory, that dictates which of the Current values and Saved values can be changed by a Mode Select command. A “one” allows a change to a corresponding bit; a “zero” allows no change. For example, in Table 9a refer to Mode page 01, in the row entitled “CHG”. These are hex numbers representing the changeable values for Mode page 01. Note that bytes 04, 05, 06, and 07 are not changeable, because those fields are all zeros. If some changeable code had a hex value EF, that equates to the binary pattern 1110 1111. If there is a zero in any bit position in the field, it means that bit is not changeable. Bits 7, 6, 5, 3, 2, 1, and 0 are changeable, because those bits are all ones. Bit 4 is not changeable.

Though the drive always reports non-zero values in bytes 00 and 01, those particular bytes are never changeable.

The Changeable values list can only be changed by downloading new firmware into the flash EPROM.

On standard OEM drives the Saved values are taken from the Default values list and stored into the Saved values storage location on the media prior to shipping.

When a drive is powered up, it takes Saved values from the media and stores them to the Current values storage in volatile memory. It is not possible to change the Current values (or the saved values) with a Mode Select command before the drive is up to speed and is “ready.” An attempt to do so results in a “Check Condition” status being returned.

Note. Because there may be several different versions of drive control firmware in the total population of drives in the field, the Mode Sense values given in the following tables may not exactly match those of some drives.

The following tables list the values of the data bytes returned by the drive in response to the Mode Sense command pages (see the *SCSI Interface Product Manual*, P/N 75789509).

- Definitions:** SAV = Saved value
 DEF = Default value. Standard drives are shipped configured this way.
 CHG = Changeable bits; indicates if current and saved values are changeable.

Table 9a: Mode sense data, ST318436 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23
Mode Sense Data	9F	00	10	08	02	23	90	70	00	00	02	00												
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																							
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF												
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF												
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF												
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00								
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00								
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00	00								
03 SAV	83	16	01	68	00	00	00	02	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00
03 DEF	83	16	01	68	00	00	00	02	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
04 SAV	84	16	00	38	30	06	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	06	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF												
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF												
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF												
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00				
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00				
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00				
0A SAV	8A	0A	02	00	00	00	00	00	00	00	04	E7												
0A DEF	8A	0A	02	00	00	00	00	00	00	00	04	E7												
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00												
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04												
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04												
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00												
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01												
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01												
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF												
00 SAV	80	02	[2]	00																				
00 DEF	80	02	80	00																				
00 CHG	80	02	F7	40																				

Notes []. See Section 9.3.2.1.

Table 9b: Mode sense data, ST318426 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	
Mode Sense Data	9F	00	10	08	02	23	90	70	00	00	20	00													
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																								
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF													
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00	00									
03 SAV	83	16	01	68	00	00	00	02	00	00	01	A0	02	00	00	01	00	36	00	36	40	00	00	00	
03 DEF	83	16	01	68	00	00	00	02	00	00	01	A0	02	00	00	01	00	36	00	36	40	00	00	00	
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
04 SAV	84	16	00	38	30	06	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	06	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF													
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00	00				
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00	00				
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00					
0A SAV	8A	0A	02	00	00	00	00	00	00	00	04	E7													
0A DEF	8A	0A	02	00	00	00	00	00	00	00	04	E7													
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00													
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00													
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF													
00 SAV	80	02	[2]	00																					
00 DEF	80	02	80	00																					
00 CHG	80	02	F7	40																					

Notes []. See Section 9.3.2.1.

Table 9c: Mode sense data, ST318416 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	
Mode Sense Data	9F	00	10	08	02	23	90	70	00	00	02	00													
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																								
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF													
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00									
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00									
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00	00									
03 SAV	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 DEF	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
04 SAV	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF													
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00					
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00					
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00					
0A SAV	8A	0A	02	00	00	00	00	00	00	00	04	E7													
0A DEF	8A	0A	02	00	00	00	00	00	00	00	04	E7													
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00													
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00													
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF													
00 SAV	80	02	[2]	00																					
00 DEF	80	02	80	00																					
00 CHG	80	02	F7	40																					

Notes []. See Section 9.3.2.1.

Table 9d: Mode sense data, ST39236 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	
Mode Sense Data	9F	00	10	08	01	11	C8	38	00	00	02	00													
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																								
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF													
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00										
03 SAV	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 DEF	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
04 SAV	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF													
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00	00				
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00	00				
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00					
0A SAV	8A	0A	02	00	00	00	00	00	00	00	02	52													
0A DEF	8A	0A	02	00	00	00	00	00	00	00	02	52													
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00													
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00													
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF													
00 SAV	80	02	[2]	00																					
00 DEF	80	02	80	00																					
00 CHG	80	02	F7	40																					

Notes []. See Section 9.3.2.1.

Table 9e: Mode sense data, ST39226 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23
Mode Sense Data	9F	00	10	08	01	11	C8	38	00	00	02	00												
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																							
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF												
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF												
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF												
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00								
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00	00								
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00	00								
03 SAV	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00
03 DEF	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
04 SAV	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF												
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF												
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF												
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00				
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00				
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00				
0A SAV	8A	0A	02	00	00	00	00	00	00	00	02	52												
0A DEF	8A	0A	02	00	00	00	00	00	00	00	02	52												
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00												
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04												
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04												
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00												
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01												
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01												
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF												
00 SAV	80	02	[2]	00																				
00 DEF	80	02	80	00																				
00 CHG	80	02	F7	40																				

Notes []. See Section 9.3.2.1.

Table 9f: Mode sense data, ST39216 values

Bytes	00	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	
Mode Sense Data	9F	00	10	08	01	11	C8	38	00	00	02	00													
Mode Page	<-----Mode Page Headers and Parameter Data Bytes----->																								
01 SAV	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 DEF	81	0A	C0	0B	F0	00	00	00	0F	00	FF	FF													
01 CHG	81	0A	FF	FF	00	00	00	00	FF	00	FF	FF													
02 SAV	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 DEF	82	0E	80	80	00	0A	00	00	00	00	00	00	00	00	00										
02 CHG	82	0E	FF	FF	00	00	00	00	00	00	00	00	87	00	00										
03 SAV	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 DEF	83	16	0A	7D	00	00	00	07	00	00	01	A1	02	00	00	01	00	36	00	36	40	00	00	00	
03 CHG	83	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	
04 SAV	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 DEF	84	16	00	38	30	03	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	1C	05	00	00
04 CHG	84	16	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00	00
07 SAV	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 DEF	87	0A	00	0B	F0	00	00	00	00	00	FF	FF													
07 CHG	87	0A	0F	FF	00	00	00	00	00	00	FF	FF													
08 SAV	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	[3]	00	00	00	00	00	00					
08 DEF	88	12	14	00	FF	FF	00	00	FF	FF	FF	FF	80	10	00	00	00	00	00	00					
08 CHG	88	12	B5	00	00	00	FF	FF	FF	FF	00	00	A0[1]	FF	00	00	00	00	00	00					
0A SAV	8A	0A	02	00	00	00	00	00	00	00	02	52													
0A DEF	8A	0A	02	00	00	00	00	00	00	00	02	52													
0A CHG	8A	0A	03	F1	00	00	00	00	00	00	00	00													
1A SAV	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A DEF	9A	0A	00	03	00	00	00	01	00	00	00	04													
1A CHG	9A	0A	00	03	00	00	00	00	00	00	00	00													
1C SAV	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C DEF	9C	0A	00	00	00	00	00	00	00	00	00	01													
1C CHG	9C	0A	8D	0F	FF	FF	FF	FF	FF	FF	FF	FF													
00 SAV	80	02	[2]	00																					
00 DEF	80	02	80	00																					
00 CHG	80	02	F7	40																					

Notes []. See Section 9.3.2.1.

9.3.2.1 Notes for tables 9a through 9f

- [1] Though byte 12, bit 7 (A0) is shown as changeable, the FSW function governed by that bit is not implemented by this drive.
- [2] Page 0, Byte 2, Bit 7 is defined as the Performance Mode (PM) bit. When set to zero (Server mode), the SCSI firmware is performance optimized for server applications. When the bit is set to one (Desktop mode), the SCSI firmware is performance optimized for desktop applications. The firmware default condition for the PM bit is set to one for Desktop mode. During the manufacturing process, the Saved value of the PM bit remains set to the firmware default condition (one) for drives with the LW and LWV interface. Drives manufactured with all other interfaces (N, W, LC, LCV) save the Saved value of the PM bit set to the Server mode (zero).
- [3] When the Performance Mode bit (Page 0, Byte 2, Bit 7) is set to Server mode (zero), the Number of Cache Segments should be set to three. When the Performance Mode bit is set to Desktop mode (one), the Number of Cache Segments should be set to sixteen (10h).

9.4 SCSI bus conditions and miscellaneous features supported

Asynchronous SCSI bus conditions supported by the drive are listed below. These conditions cause the SCSI device to perform certain actions and can alter the SCSI bus phase sequence. Other miscellaneous operating features supported are also listed here. Refer to the *SCSI Interface Product Manual*, part number 75789509, for details.

Table 10: SCSI bus conditions and other miscellaneous features

Supported	Conditions or feature
Y	50, 68, and 80 pin interface connectors
Y	1 Mbyte data buffer
N	Active termination disabled via jumper
Y	Terminator power from drive power connector and to SCSI bus option
Y	Terminator power from drive power connector option
Y	Terminator power from SCSI bus pin 26 option
Y	Terminator power from SCSI I/O cable pin 26
Y	Active termination enabled (N and W models only)
N	Adaptive caching
Y	Adaptive read look-ahead
Y	Arbitrating system
Y	ASYNC burst rate of 5 Mbytes/sec.—single-ended
Y	Asynchronous data transfer
N	Asynchronous event notification
Y	Attention condition
Y	Audio video recovery scheme
N	Automatic adaptive cache (customer unique option)
Y	Capacity programming
Y	Command overhead less than 500 USEC, typ.
Y	Contingent allegiance condition
Y	Deferred error handling
Y	Delayed motor start
Y	Disconnect/reconnect
Y	Embedded servo
Y	Firmware downloadable via SCSI interface
Y	Flag and link bits in control byte supported
Y	Format progress indication
Y	Full automatic read and write reallocation
Y	Hot plugging, with bus active
Y	Immediate status on Format Unit command
Y	Immediate status on Start/Stop command
Y	Immediate status on Synchronize cache
Y	Linked commands—customer unique options
Y	Low voltage differential SCSI (LVD)
Y	Motor start enable
Y	Multi-initiator
Y	Multi-mode drivers/receivers (single-ended/differential)
Y	Parameter rounding
Y	Power management, SCSI-3
Y	Queue tagging (up to 64 Que tags supported)

Supported	Conditions or feature
Y	Read look ahead crossing cylinder boundaries
N	Relative addressing—customer unique options
Y	Reporting actual retry count in Extended Sense bytes 15, 16 and 17.
Y	Reset condition
Y	RPS (rotational position seek/sort)
Y	S2 bit
SCA-2	SCA connector (optional)
Y	SCSI ID accessibility to front end (J6)
Y	SCSI-3 SPI compliant
Y	Variable Sector size, 512 to 4,096 in 2 byte multiples
Y	Segmented caching
Y	S.M.A.R.T. (Self-Monitoring Analysis and Reporting Technology)
N	Sparing scheme per cylinder
N	Sparing scheme per track
N	Sparing scheme per volume
Y	Sparing scheme per zone
Y	Strict bit support
Y	Sustained transfer rate of 3 Mbytes/sec.—single-ended
N	Sync spindles—rotational position offset
N	Synchronized (locked) spindle operation
Y	Synchronous data transfer
Y	Tagged command queuing 64 deep
Y	Target initiated SDTR
N	TTD/CIOP
Y	Ultra SCSI, 20 Mbytes/sec.
Y	Ultra-2 SCSI, 40 Mbytes/sec.
Y	Ultra160 SCSI, 80 Mbytes/sec. (LVD, single transition only) [1]
Y	Ultra160 SCSI, 160 Mbytes/sec. (LVD, double transition only) [1]
Y	Write protected
N	Zero latency read

Supported	Status supported
Y	Good
Y	Check condition
Y	Condition met/good
Y	Busy
Y	Intermediate/good
Y	Intermediate/condition met/good
Y	Reservation conflict
Y	Queue full
N	Auto contingent allegiance active

[1] ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

9.5 Synchronous data transfer

9.5.1 Synchronous data transfer periods supported

Table 11 and Section 9.5.2 list Synchronous Data transfer periods supported by the drive. The data transfer period to be used by the drive and the initiator is established by an exchange of messages during the Message Phase of operation. See the section “Extended Message” on message protocol in the *SCSI Interface Product Manual*, part number 75789509. Byte 3 of the message format lists a transfer period factor. The factors possible and equivalent transfer periods are listed in Table 11.

Table 11: Synchronous data transfer periods for drive

Transfer period factor	Transfer period (nanoseconds)
00h-09h	Reserved [1]
0Ah	Transfer period equals 25 ns [2]
0Bh	Transfer period equals 30.3 ns [2]
0Ch	Transfer period equals 50 ns [3]
0Dh-18h	Transfer period equals the transfer period factor * 4 [3]
19h-31h	Transfer period equals the transfer period factor * 4 [4]
32h-FFh	Transfer period equals the transfer period factor * 4 [5]
05h	Transfer period equals 12.5 ns [6]

Notes.

- [1] Faster timings may be allowed by future SCSI parallel interface standards.
- [2] Fast-40 data transfer rates that have a period equal to 25 ns or 30.3 ns.
- [3] Fast-20 data transfer rates that have a period of ≤ 96 ns and ≥ 50 ns.
- [4] Fast-10 data transfer rates that have a period of ≤ 196 ns and ≥ 100 ns.
- [5] Fast-5 data transfer rates that have a period of ≤ 1020 ns and ≥ 200 ns.
- [6] Fast-80 data transfer rates that have a period equal to 12.5 ns.

9.5.2 REQ/ACK offset

The maximum value supported by the Barracuda 18XL family drives for REQ/ACK offset is 15 (0Fh).

9.6 Physical interface

Figures 9a and 9b show the locations of the drive physical interface components for the various models of the drive. Shown are the locations of the DC power connector, the SCSI interface connector, and the drive select and option select headers.

Details of the physical, electrical and logical characteristics are given in sections following, while the SCSI operational aspects of Seagate drive interfaces are given in the *SCSI Interface Product Manual*, part number 75789509.

This section describes the connectors, cables, signals, terminators and bus timing of the DC and SCSI I/O interface. See Section 9.8 and Section 9.9 for additional terminator information.

9.6.1 DC cable and connector

With the exception of the “LC” drives, the drive receives DC power through a 4 pin connector (see Figure 9a for pin assignment) mounted at the rear of the main PCBA. Recommended part numbers of the mating connector are listed below, but equivalent parts may be used.

Type of cable	Connector	Contacts (20-14 AWG)
14 AWG	MP 1-480424-0	AMP 60619-4 (Loose Piece) AMP 61117-4 (Strip)

Model “LC” receives power through the 80 pin I/O connector. See Table 13d.

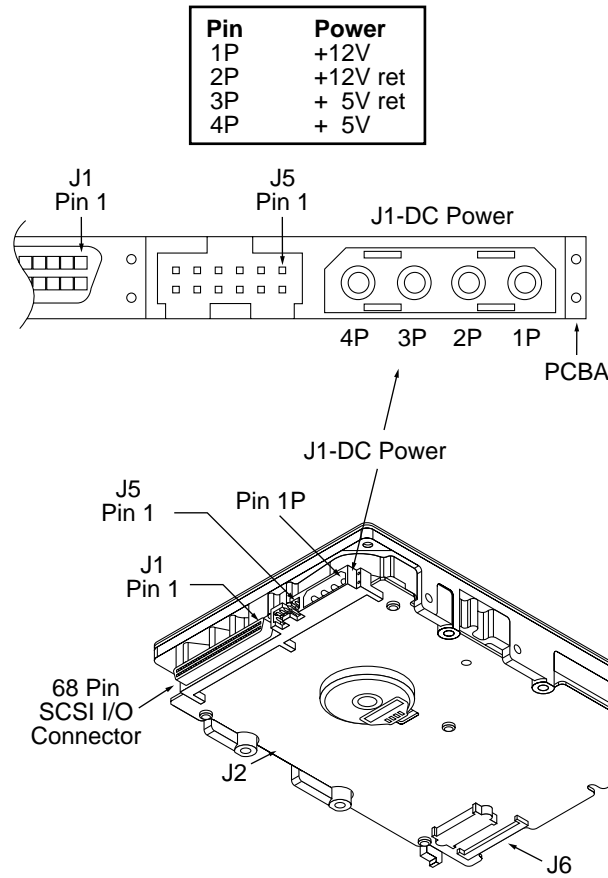
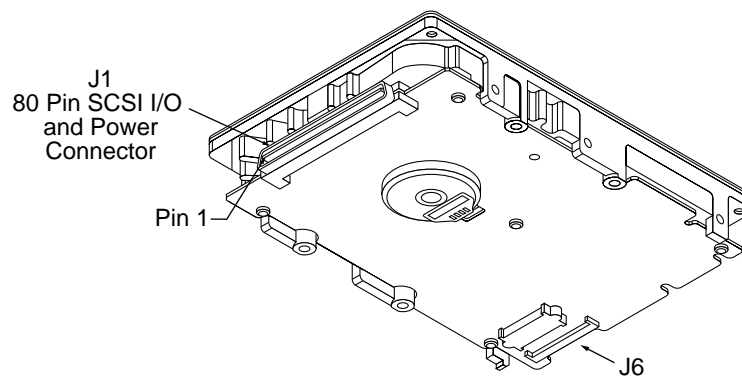


Figure 9a. Model “LW” and “LWV” drive physical interface (68 pin J1 SCSI I/O connector)



Note: See Table 13d for DC power pin assignments.

Figure 9b. Model “LC” and “LCV” drive physical interface (80 pin J1 SCSI I/O connector and DC power connector)

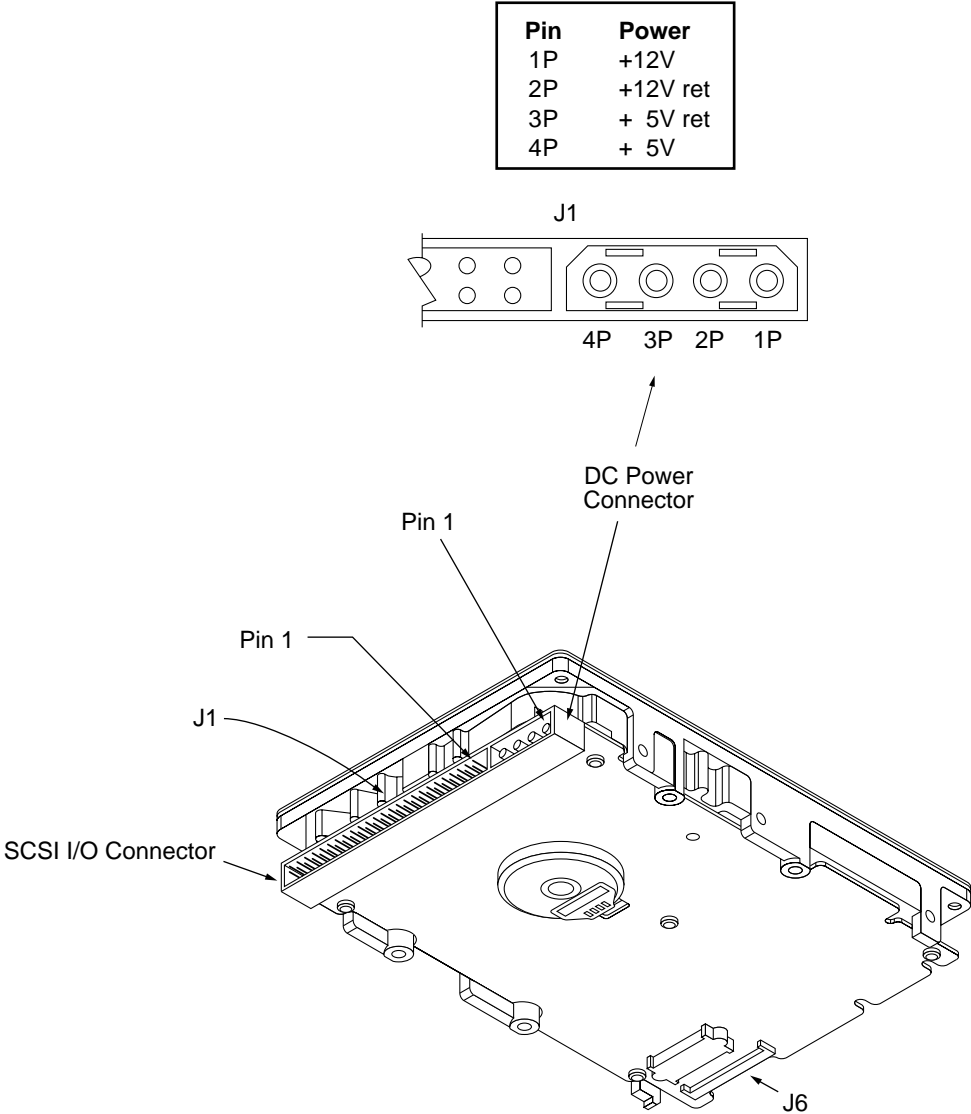


Figure 9c. Models "N" and "W" drive physical interface

9.6.2 SCSI interface physical description

The drive models described by this product manual support the physical interface requirements of the SCSI Parallel Interface-2 (SPI-3) and EPI standards as defined in American National Standard documents T10/1302D and X3T10/1143D, and operate compatibly at the interface with devices that only support earlier single-ended SCSI-2 and SCSI-3 standards. It should be noted that this is only true if the systems engineering has been correctly done, and if earlier SCSI-2 and SCSI-3 devices respond in an acceptable manner (per applicable SCSI Standards) to reject newer SCSI-3 protocol extensions that they don't support. Low voltage differential (LVD) circuits are not compatible with high voltage differential (HVD).

The family of drives in this manual supports the single-ended and low voltage differential physical interconnects (hereafter referred to as SE and LVD, respectively) as described in the ANSI SPI-3 and EPI standards.

The drives typically operate on a daisy-chain interface in which other SCSI devices are also operating. Devices on the daisy chain must all operate in the same mode, either SE or LVD, but not a mixture of these. On the interface daisy chain, all signals are common between all devices on the chain, or bus, as it is also called. This daisy chain of SCSI devices must be terminated at both ends with the proper impedance in order to operate correctly. Intermediate SCSI devices shall not be terminated. Models "LC" and "LW" have no onboard termination circuits. Some type of external termination circuits must be provided for these drives by the end user or designers of the equipment into which the drives will be integrated. See SPI-3 and EPI standards for the maximum number of devices that can successfully operate at various interface transfer rates on SE and LVD daisy chains.

"LC" model drives plug into PCBA or bulkhead connectors in the Host. They may be connected in a daisy-chain by the host backplane wiring or PCBA circuit runs that have adequate DC current carrying capacity to support the number of drives plugged into the PCBA or bulkhead connectors. A single 80 pin I/O connector cable cannot support the DC current needs of several drives, so no daisy chain cables beyond the bulkhead connectors should be used. A single drive connected via a cable to a host 80 pin I/O connector is not recommended.

Table 12 shows the interface transfer rates supported by the various drive models defined in this manual.

Table 12: Interface transfer rates supported

Interface type/drive models		Maximum transfer rate					
		Asynchronous	Fast-5	Fast-10	Fast-20	Fast-40	Fast-80 [3]
SE	"LW," "LC," "LWV," "LCV," "N," "W"	yes	yes	yes	yes	no	no
LVD (ST) [1]	"LW," "LC," "LWV," "LCV"	yes	yes	yes	yes	yes	no
LVD (DT) [2]	"LW," "LC," "LWV," "LCV"	no	yes	yes	yes	yes	yes

Notes.

- [1] ST = Single Transition (latching data only on the assertion edge of the REQ/ACK signal)
- [2] DT = Double Transition (latching data on both the assertion edge and the negated edge of the REQ/ACK signal)
- [3] ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

9.6.3 SCSI interface cable requirements

The characteristics of cables used to connect SCSI-3 parallel interface devices are discussed in detail in ANSI Standard T10/1302D (SPI-3) and X3T10/1143D. The cable characteristics that must be considered when interconnecting the drives described in this manual in a SCSI-3 parallel, daisy-chain interconnected system are:

- characteristic impedance (see section 6.1)
- propagation delay (see section 6.1)
- cumulative length (see sections 6.4 and 6.5)
- stub length (see sections 6.4 and 6.5)
- device spacing (see sections 6.4 and 6.5)

To minimize discontinuances and signal reflections, cables of different impedances should not be used in the same bus. Implementations may require trade-offs in shielding effectiveness, cable length, number of loads and spacing, transfer rates, and cost to achieve satisfactory system operation. If shielded and unshielded cables are mixed within the same SCSI bus, the effect of impedance mismatch must be carefully considered. Proper impedance matching is especially important in order to maintain adequate margin at Fast-20, Fast-40, and Fast-80 SCSI transfer rates.

Note. For LVD operation, twisted pair cables are recommended. For LVD Fast-40 operation, twisted pair cables are *strongly* recommended. For Fast-80 operation, twisted pair cables are *required*.

Note. ST318426LW/LC and ST39226LW/LC models do not support Fast-80/Ultra160.

For “LC” models:

The 80 pin connector option is intended for use on drives that plug directly into a PCBA or wall/bracket mounted connector in the host equipment. In such installations, all backplane wiring segments are subject to the electromagnetic concepts presented in Standard T10/1302D (SPI-3). For “LC” model drives, installations with connectors on cables are not recommended.

9.6.4 Mating connectors

Part numbers for the different type connectors that mate with the various Barracuda 18XL I/O connectors are given in the sections following.

9.6.4.1 Mating connectors for “W,” “LW,” and “LWV” models

The nonshielded cable connector shall be a 68 conductor connector consisting of two rows of 34 male contacts with adjacent contacts 0.050 inch (1.27 mm) apart.

Recommended mating flat cable connector part numbers are:

Amp Model 786096-7	Female, 68-pin, panel mount
Amp Model 786090-7	Female, 68-pin, cable mount
Amp Model 749925-5	(50 mil conductor centers, 28 or 30 AWG wire) Use two, 34 conductor, 50 mil center flat cable with this connector. This type connector can only be used on cable ends. [1]
Amp Model 88-5870-294-5	W/O Strain Relief (25 mil conductor centers, 30 AWG wire). Use either on cable ends or in cable middle section for daisy-chain installations [1].
Amp Model 1-480420-0	Power connector 4 circuit housing
Berg 69307-012	12-position, 2 x 6, 2 mm receptacle housing

[1] See Figure 10a.

The drive device connector is a nonshielded 68 conductor connector consisting of two rows of 34 female pins with adjacent pins 50 mils apart. The connector is keyed by means of its shape (see Figure 11a).

9.6.4.2 Mating connectors for “LC” and “LCV” models

The nonshielded connector shall be an 80 conductor connector consisting of two rows of 40 contacts with adjacent contacts 50 (1.27 mm) mils apart (see Figure 11b). I/O connection using a cable is not recommended. The length and size of the host equipment DC power carrying conductors from the DC power source to the host equipment 80 pin disk drive interface connector(s) should be strictly designed according to proper power transmission design concepts. No possibility for the equipment user to attach an 80 pin cable/connector should be allowed, since the length of the DC power carrying conductors could not be controlled and therefore could become too long for safe power transmission to the drive. Daisy-chain 80 conductor cables should especially not be allowed, since the power-carrying conductors on the 80 conductor interface were not intended to support a series of drives.

To insure that both drive connector and host equipment mating connector mate properly, both drive connector and host equipment mating connector must meet the provisions of “SFF-8046 Specification for 80-pin connector for SCSI Disk Drives.”

9.6.4.3 Mating connectors for “N” models

The nonshielded cable connector shall be a 50 conductor connector consisting of two rows of 25 female contacts with adjacent contacts 100 mils apart.

Recommended mating flat cable connector part numbers are:

Closed end	3M-3425-7000	W/O Strain Relief, No Center Key
(for cable ends) [1]	3M-3425-7050	With Strain Relief, No Center Key
	Dupont-66900-290	With Strain Relief, With Center Key
Open end	3M-3425-6000	W/O Strain Relief, No Center Key
(In daisy-chain) [1]	3M-3425-6050	With Strain Relief, No Center Key
	Dupont-66900-250	With Strain Relief, With Center Key

[1] See Figure 10b.

The drive device connector is a nonshielded 50 conductor connector consisting of two rows of 25 male pins with adjacent pins 100 mils apart. The connector is keyed (see Figure 11c).

Mating panel mount connector: 3M-CHE-2050-J01A10-KLE.

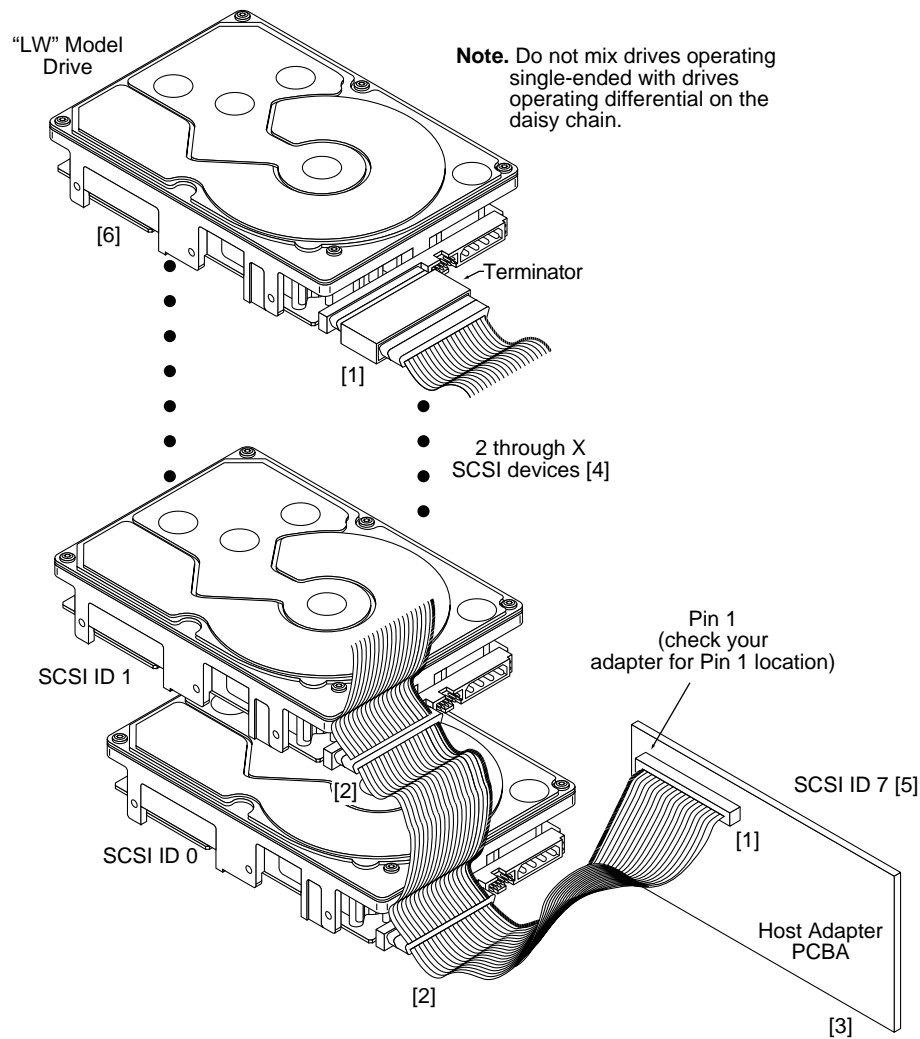
Recommended mating 80-position PCBA mount connectors:

Straight-in connector		Hot plug version (with ground guide-pin)	
Seagate P/N:	77678703		
Amp US P/N:	2-557103-1	787311-1	with polarization
	or 94-0680-02-1		
Amp US P/N:	2-557103-2	787311-2	without polarization
	or 94-0680-02-2		
Amp Japan P/N:	5-175475-9		

Right-angle to PCBA connectors

Seagate P/N: 77678559 Amp US P/N: 2-557101-1 Amp Japan P/N: 5-175474-9

For additional information call Amp. FAX service at 1-800-522-6752.



- [1] Closed-end type 68 pin connector used. Terminator required.
- [2] Open end type (in-line application) connector used. No terminator.
- [3] Host need not be on the end of the daisy-chain. Another device can be on the end with the terminator, the host having no terminator.
- [4] Total interface cable length must not exceed that specified in ANSI Standard T10/1302D (including host adapter/initiator). The cable length restriction limits the total number of devices allowed.
- [5] SCSI ID7 has highest arbitration priority. For "LW" models, priority is ID7 to ID0, then ID15 to ID8 (ID 8 very lowest).
- [6] Last drive on the daisy chain.

Figure 10a. SCSI daisy chain interface cabling for "LW" model drives

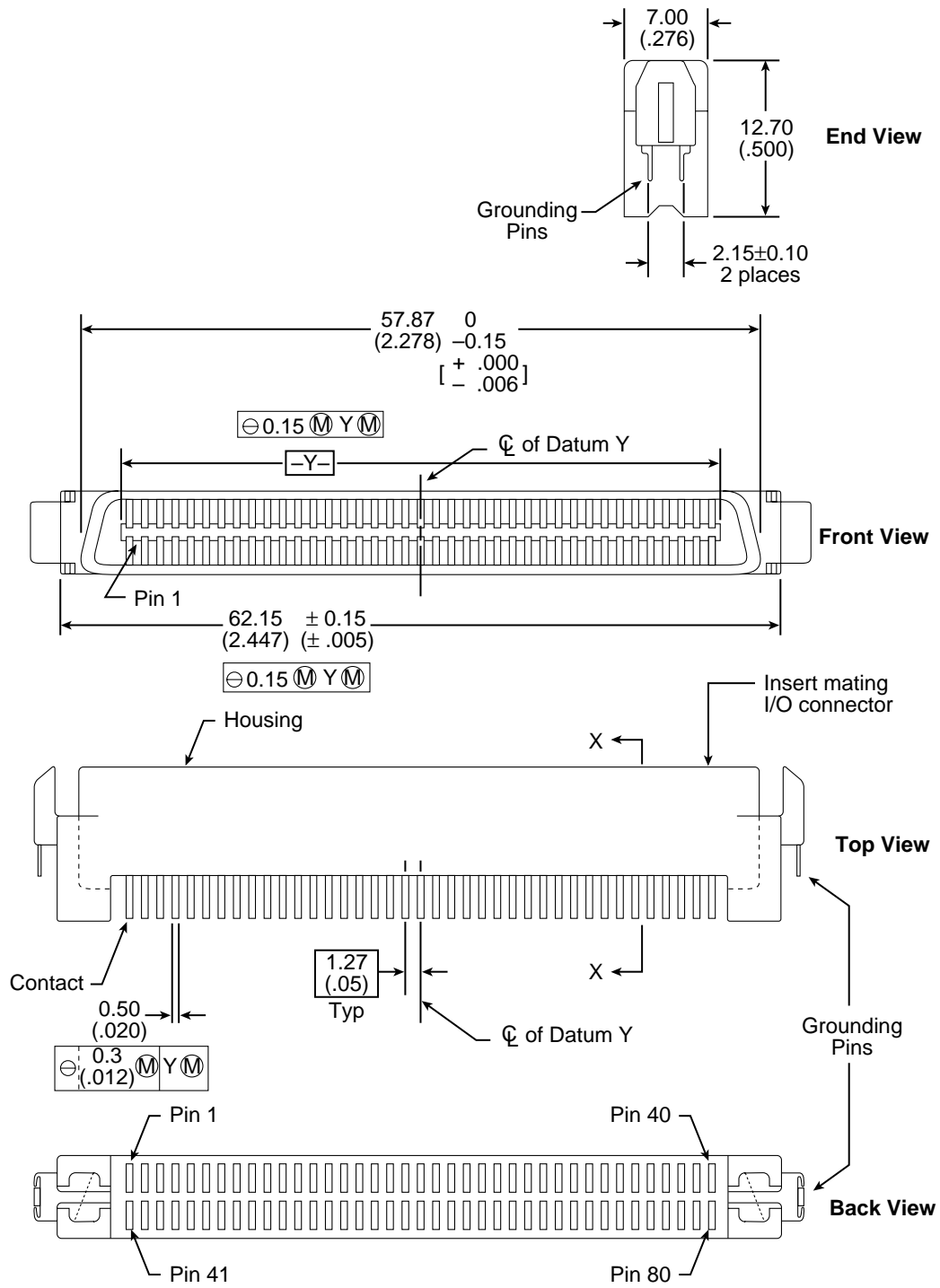


Figure 11b. Nonshielded 80 pin SCSI "SCA-2" connector, used on "LC" models

Table 13a: “LW” models SE operation 68 conductor cable signal/pin assignments (Nonshielded connector)[11]

Note. The minus sign next to the signal indicates asserted state is the low voltage of the two levels used for logic signals.

Signal name [1]	Connector contact number [3]	Cable conductor number [2]		Connector contact number [3]	Signal name [1]
Signal Return	1	1	2	35	-DB12
Signal Return	2	3	4	36	-DB13
Signal Return	3	5	6	37	-DB14
Signal Return	4	7	8	38	-DB15
Signal Return	5	9	10	39	-DBP1
Signal Return	6	11	12	40	-DB0
Signal Return	7	13	14	41	-DB1
Signal Return	8	15	16	42	-DB2
Signal Return	9	17	18	43	-DB3
Signal Return	10	19	20	44	-DB4
Signal Return	11	21	22	45	-DB5
Signal Return	12	23	24	46	-DB6
Signal Return	13	25	26	47	-DB7
Signal Return	14	27	28	48	-DBP
GND	15	29	30	49	GND
GND	16	31	32	50	GND
TermPwr	17	33	34	51	TermPwr
TermPwr	18	35	36	52	TermPwr
Reserved	19	37	38	53	Reserved
GND	20	39	40	54	GND
Signal Return	21	41	42	55	-ATN
GND	22	43	44	56	GND
Signal Return	23	45	46	57	-BSY
Signal Return	24	47	48	58	-ACK
Signal Return	25	49	50	59	-RST
Signal Return	26	51	52	60	-MSG
Signal Return	27	53	54	61	-SEL
Signal Return	28	55	56	62	-C/D
Signal Return	29	57	58	63	-REQ
Signal Return	30	59	60	64	-I/O
Signal Return	31	61	62	65	-DB8
Signal Return	32	63	64	66	-DB9
Signal Return	33	65	66	67	-DB10
Signal Return	34	67	68	68	-DB11

Notes []: See page following Table 13f.

Table 13b: “LW” models differential cable 68 conductor signal/pin assignments (Nonshielded connector) [11]

Note. The minus sign next to the signal indicates asserted state is the low voltage of the two levels used for logic signals.

Signal name [1]	Connector contact number [3]	Cable conductor number [2]		Connector contact number [3]	Signal name [1]
+DB12	1	1	2	35	-DB12
+DB13	2	3	4	36	-DB13
+DB14	3	5	6	37	-DB14
+DB15	4	7	8	38	-DB15
+DBP1	5	9	10	39	-DBP1
+DB0	6	11	12	40	-DB0
+DB1	7	13	14	41	-DB1
+DB2	8	15	16	42	-DB2
+DB3	9	17	18	43	-DB3
+DB4	10	19	20	44	-DB4
+DB5	11	21	22	45	-DB5
+DB6	12	23	24	46	-DB6
+DB7	13	25	26	47	-DB7
+DBP	14	27	28	48	-DBP
GND	15	29	30	49	GND
DIFFSNS [8]	16	31	32	50	GND
TermPwr	17	33	34	51	TermPwr
TermPwr	18	35	36	52	TermPwr
Reserved	19	37	38	53	Reserved
GND	20	39	40	54	GND
+ATN	21	41	42	55	-ATN
GND	22	43	44	56	GND
+BSY	23	45	46	57	-BSY
+ACK	24	47	48	58	-ACK
+RST	25	49	50	59	-RST
+MSG	26	51	52	60	-MSG
+SEL	27	53	54	61	-SEL
+C/D	28	55	56	62	-C/D
+REQ	29	57	58	63	-REQ
+I/O	30	59	60	64	-I/O
+DB8	31	61	62	65	-DB8
+DB9	32	63	64	66	-DB9
+DB10	33	65	66	67	-DB10
+DB11	34	67	68	68	-DB11

Notes []: See page following Table 13f.

Table 13c: "LC" SE models, 80 pin I/O connector pin assignments (nonshielded connector) [11]

Signal name [1]	Connector contact number [3]	Signal number [3]	Contact name[1]
12 V CHARGE	1	41	12 V GND
12 V	2	42	12 V GND
12 V	3	43	12 V GND
12 V	4	44	MATED 1
NC [10]	5	45	NC [10]
NC [10]	6	46	DIFFSNS [8]
-DB11	7	47	Signal Return
-DB10	8	48	Signal Return
-DB9	9	49	Signal Return
-DB8	10	50	Signal Return
-I/O	11	51	Signal Return
-REQ	12	52	Signal Return
-C/D	13	53	Signal Return
-SEL	14	54	Signal Return
-MSG	15	55	Signal Return
-RST	16	56	Signal Return
-ACK	17	57	Signal Return
-BSY	18	58	Signal Return
-ATN	19	59	Signal Return
-DBP	20	60	Signal Return
-DB7	21	61	Signal Return
-DB6	22	62	Signal Return
-DB5	23	63	Signal Return
-DB4	24	64	Signal Return
-DB3	25	65	Signal Return
-DB2	26	66	Signal Return
-DB1	27	67	Signal Return
-DB0	28	68	Signal Return
-DP1	29	69	Signal Return
-DB15	30	70	Signal Return
-DB14	31	71	Signal Return
-DB13	32	72	Signal Return
-DB12	33	73	Signal Return
+5 V	34	74	MATED 2
+5 V	35	75	5 V GND
+5 V	36	76	5 V GND
NC [10]	37	77	ACTIVE LED OUT [4] [9]
RMT-START [5] [9]	38	78	DLYD-START [6] [9]
SCSI ID (0) [7] [9]	39	79	SCSI ID (1) [7] [9]
SCSI ID (2) [7] [9]	40	80	SCSI ID (3) [7] [9]

Notes []: See page following Table 13f.

Table 13d: "LC" differential models, 80 pin I/O connector pin assignments (nonshielded connector) [11]

Signal name [1]	Connector contact number [3]	Signal number [3]	Contact name [1]
12 V CHARGE	1	41	12 V GND
12 V	2	42	12 V GND
12 V	3	43	12 V GND
12 V	4	44	MATED 1
NC [10]	5	45	NC [10]
NC [10]	6	46	DIFFSNS [8]
-DB11	7	47	+DB11
-DB10	8	48	+DB10
-DB9	9	49	+DB9
-DB8	10	50	+DB8
-I/O	11	51	+I/O
-REQ	12	52	+REQ
-C/D	13	53	+C/D
-SEL	14	54	+SEL
-MSG	15	55	+MSG
-RST	16	56	+RST
-ACK	17	57	+ACK
-BSY	18	58	+BSY
-ATN	19	59	+ATN
-DBP	20	60	+DBP
-DB7	21	61	+DB7
-DB6	22	62	+DB6
-DB5	23	63	+DB5
-DB4	24	64	+DB4
-DB3	25	65	+DB3
-DB2	26	66	+DB2
-DB1	27	67	+DB1
-DB0	28	68	+DB0
-DP1	29	69	+DP1
-DB15	30	70	+DB15
-DB14	31	71	+DB14
-DB13	32	72	+DB13
-DB12	33	73	+DB12
+5 V	34	74	MATED 2
+5 V	35	75	5 V GND
+5 V	36	76	5 V GND
NC [10]	37	77	ACTIVE LED OUT [4] [9]
RMT-START [5] [9]	38	78	DLYD-START [6] [9]
SCSI ID (0) [7] [9]	39	79	SCSI ID (1) [7] [9]
SCSI ID (2) [7] [9]	40	80	SCSI ID (3) [7] [9]

Notes []: See page following Table 13f.

Table 13e: "N" model, single-ended I/O, 50 conductor, signal/contact assignments

Signal name [1]	Connector contact number [13]	Cable conductor number [12]		Connector contact number [13]	Signal name [1]
GND	1	1	2	2	-DB0
GND	3	3	4	4	-DB1
GND	5	5	6	6	-DB2
GND	7	7	8	8	-DB3
GND	9	9	10	10	-DB4
GND	11	11	12	12	-DB5
GND	13	13	14	14	-DB6
GND	15	15	16	16	-DB7
GND	17	17	18	18	-DBP
GND	19	19	20	20	GND
GND	21	21	22	22	GND
GND	23	23	24	24	GND
NC [10]	25*	25	26	26	TERMPWR
GND	27	27	28	28	GND
GND	29	29	30	30	GND
GND	31	31	32	32	-ATN
GND	33	33	34	34	GND
GND	35	35	36	36	-BSY
GND	37	37	38	38	-ACK
GND	39	39	40	40	-RST
GND	41	41	42	42	-MSG
GND	43	43	44	44	-SEL
GND	45	45	46	46	-C/D
GND	47	47	48	48	-REQ
GND	49	49	50	50	-I/O

***CAUTION:** Connector contact 25 must not be connected to ground at the host end or the drive end of the cable. If the I/O cable should accidentally be plugged in upside down, terminator power on pin 26 will be shorted to ground.

Notes []: See page following Table 13f.

Table 13f: “W” model, single-ended I/O cable, 68 conductor, signal/contact assignments

Signal name [1]	Connector contact number [3]	Cable conductor number [2]		Connector contact number [3]	Signal name [1]
GND	1	1	2	35	-DB12
GND	2	3	4	36	-DB13
GND	3	5	6	37	-DB14
GND	4	7	8	38	-DB15
GND	5	9	10	39	-DBP1
GND	6	11	12	40	-DB0
GND	7	13	14	41	-DB1
GND	8	15	16	42	-DB2
GND	9	17	18	43	-DB3
GND	10	19	20	44	-DB4
GND	11	21	22	45	-DB5
GND	12	23	24	46	-DB6
GND	13	25	26	47	-DB7
GND	14	27	28	48	-DBP
GND	15	29	30	49	GND
GND	16	31	32	50	GND
TermPwr	17	33	34	51	TermPwr
TermPwr	18	35	36	52	TermPwr
Reserved	19	37	38	53	Reserved
GND	20	39	40	54	GND
GND	21	41	42	55	-ATN
GND	22	43	44	56	GND
GND	23	45	46	57	-BSY
GND	24	47	48	58	-ACK
GND	25	49	50	59	-RST
GND	26	51	52	60	-MSG
GND	27	53	54	61	-SEL
GND	28	55	56	62	-C/D
GND	29	57	58	63	-REQ
GND	30	59	60	64	-I/O
GND	31	61	62	65	-DB8
GND	32	63	64	66	-DB9
GND	33	65	66	67	-DB10
GND	34	67	68	68	-DB11

Notes []: See page following this Table.

Notes [] for Tables 13a through 13f.

- [1] See Section 9.7.1 or 9.7.2 for detailed electrical characteristics of these signals.
- [2] The conductor number refers to the conductor position when using 0.025-inch (0.635 mm) centerline flat ribbon cable. Other cables types may be used to implement equivalent contact assignments.
- [3] Connector contacts are on 0.050 inch (1.27 mm) centers.
- [4] Front panel LED signal; indicates drive activity for host front panel hard drive activity indicator.
- [5] Asserted by host to enable Motor Start option (enables starting motor via SCSI bus command).
- [6] Asserted by host to enable Delayed Motor Start option (motor starts at power on or after a delay of 12 seconds times drive ID). This and [5] above are mutually exclusive options.
- [7] Binary code on A3, A2, A1 and A0 asserted by host to set up SCSI bus ID in drive.
- [8] GND provides a means for differential devices to detect the presence of a single ended device on the bus. Drive will not operate I/O bus at Ultra-2 or Ultra160 data rates if this is grounded.
- [9] Signals [4] through [7] are used in place of installing jumpers and cables on option select connectors J2 and J6. See Section 8.1.1 notes.
- [10] "NC" means no connection.
- [11] 8 bit devices which are connected to the 16 data bit differential I/O shall leave the following signals open:
-DB12 -DB13 -DB14 -DB15 -DBP1 -DB8 -DB9 -DB10 -DB11,
+DB12 +DB13 +DB14 +DB15 +DBP1 +DB8 +DB9 +DB10 +DB11.
8 bit devices which are connected to the 16 data bit single-ended I/O shall have the following signals connected as shown:
to ground: +DB12 +DB13 +DB14 +DB15 +DBP1 +DB8 +DB9 +DB10 +DB11,
open circuit: -DB12 -DB13 -DB14 -DB15 -DBP1 -DB8 -DB9 -DB10 -DB11.
All other signals should be connected as shown.
- [12] The conductor number refers to the conductor position (right to left in Figure 10b) when using 0.050 inch (1.27 mm) centerline flat ribbon cable. Other cable types may be used to implement equivalent contact assignments.
- [13] Connector contacts are on 0.100 inch (2.54 mm) centers.

9.7 Electrical description

“LC” models use the single connection attachment (SCA) connector. This 80-pin connector is designed to plug directly into a back panel or plane. No external cables are required. Active terminators on the back panel must be provided by the user. This connector is not recommended where cabling is required.

“LC” and “LW” models are Multimode drives. That is, their I/O circuits can operate as either single-ended or low voltage differential drivers/receivers (selectable using the I/O “DIFFSENS” line). They require external terminators. See Section 9.7.2 for additional information on these models.

“N” and “W” models use single-ended interface signals. These signals must be terminated with 110-ohm active termination circuits at each end of the total cable. Single-ended circuits use open collector or three state drivers. These models can be configured to provide the SCSI termination.

Note. The SCSI protocol chip drives the upper eight data and parity bits of the SCSI bus even when operating in narrow (eight bit) mode. This is normal operation for this chip. If the unused data bit signals are connected to conductors that extend out beyond this drive’s SCSI connector, correct termination must be provided for these unused signals at the device/system at each end of the bus onto which this drive is connected. Termination is required to control radiated emissions and conducted noise on other SCSI bus signals.

9.7.1 Single-ended drivers/receivers

For “N” and “W” models which use single-ended drivers and receivers, typical circuits are shown in Figure 12. Terminator circuits (Note [1]) are to be enabled only when the disc drive is first or last in the daisy-chain.

Transmitter characteristics

Single-ended drives use an ANSI SCSI compatible open collector single-ended driver. This driver is capable of sinking a current of 48 mA with a low level output voltage of 0.4 volt.

Receiver characteristics

Single-ended drives use an ANSI SCSI single-ended receiver with hysteresis gate or equivalent as a line receiver.

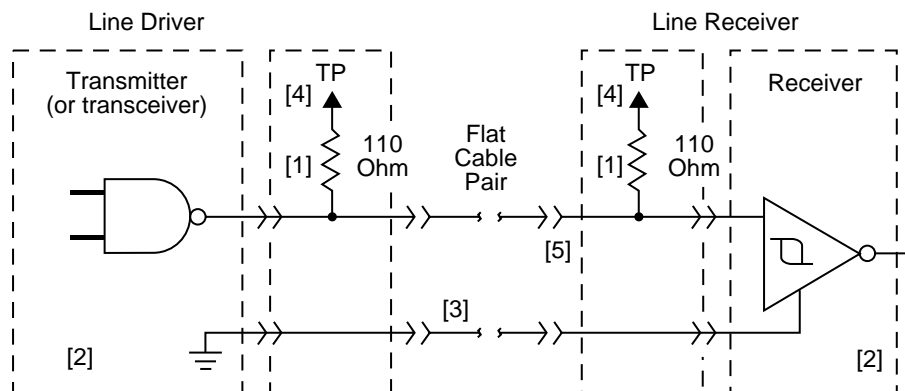


Figure 12. Single-ended transmitters and receivers on “N” and “W” models

Notes.

- [1] Part of active terminator circuits. Non-removable LSI terminators, enabled in the drive (models “N” and “W” only) with jumper plug **TE** when it is first or last in the daisy-chain.
- [2] ANSI SCSI compatible circuits.
- [3] Total interface cable length should not exceed that specified in ANSI Standard T10/1302D.
- [4] Source of drive terminator power is an active circuit which has an input source voltage selected by jumper plug **TP**. See Figure 7d. Applies to “N” and “W” models.
- [5] Interface signal levels and logical sense at the drive I/O connector for “N” and “W” models are defined as follows:
 - Vil (low-level input voltage) = 1.0 V maximum (signal true); minimum = Vss – 0.5 V.
 - Vih (high-level input voltage) = 1.9 V minimum (signal false); maximum = Vdd +0.5V.
 - Vihys (Input Hysteresis) = 425 mV minimum

See ANSI Standard T10/1302D (SPI-3) for detailed electrical specifications.

9.7.2 Multimode—SE or LVD alternative

“LW” and “LC” models have I/O circuits that can operate either in single-ended (SE) or low voltage differential mode (LVD). When the interface “DIFFSNS” line is between 0 V and .6 V, the drive interface circuits operate single-ended and up to and including 20 M transfers/s (Fast-20 or Ultra-1 SCSI). When “DIFFSNS” is between +0.7 V and +1.9 V, the drive interface circuits operate low voltage differential and up to and including 80 M transfers/sec or less. This arrangement is not intended to allow dynamically changing transmission modes, but rather to prevent incompatible devices from attempting to interoperate. Multimode I/O circuits used by “LC” and “LW” devices do not operate at high voltage differential levels and should never be exposed to high voltage differential environments unless the common mode voltages in the environment are controlled to safe levels for single-ended and low voltage differential devices (see the ANSI SPI-3 specification T10/1302D).

Multimode signals

Multimode circuit SE alternative logic sense and signal level characteristics are described as follows:

Vil (low-level input voltage) = 1.0 V maximum (signal true); minimum = Vss – 0.5 V

Vih (high-level input voltage) = 1.9 V minimum (signal false); maximum = Vdd +0.5V

Vihys (Input Hysteresis) = 425 mV minimum

Multimode circuit LVD alternative signal characteristics are not the same as high voltage differential signals (HVD). This drive does not support HVD. It should never be connected to an HVD bus. The SCA-2, 80-pin connector signal/pin assignments are shown in Tables 13b and 13d, but the electrical characteristics of the signals are not the same. “LC” and “LW” model drives do not have onboard terminators. The Multimode signal lines (either SE or LVD) should be terminated with 110 ohm active terminator circuits at each end of the total cable. Termination of the I/O lines must be provided for by the Host equipment designers or end users.

The SE and differential alternatives are mutually exclusive.

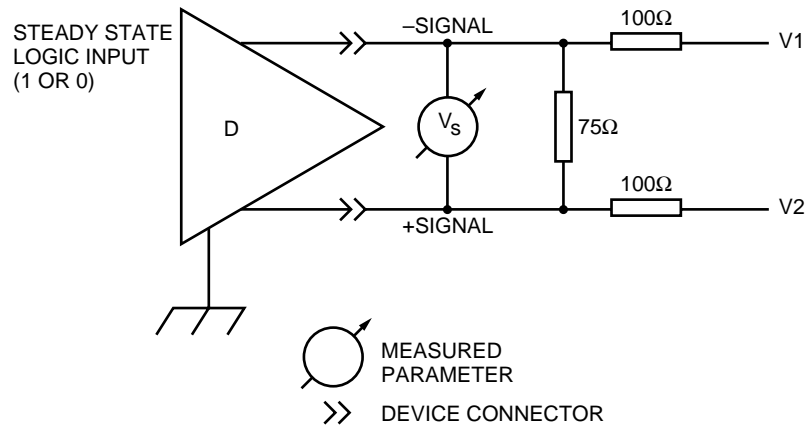
Output characteristics

Each LVD signal (V_s) driven by LVD interface drivers shall have output characteristics as described in this section when measured at the disc drive connector (refer to figure 13). A signal that is “released” goes to the negated (false or logic 0) state because the bias of the terminator pulls the signal levels to the negated state. Refer to paragraphs 7.2.2, and Annex A of ANSI SPI-3 specification, T10/1302D for details. The output characteristics shall additionally conform to EIA RS-485.

Table 14: Drive steady state limits and conditions (T10/1302D, Annex A, Table A.2)

Test parameter V_s	Test conditions (figure 13)	Minimum (mV)	Maximum (mV)
V_A Differential output voltage magnitude (asserted) [1]	$V_1=1.056$ V, $V_2=0.634$ V	375	800
	$V_1=1.866$ V, $V_2=1.444$ V	375	800
V_N Differential output voltage magnitude (negated) [1]	$V_1=1.056$ V, $V_2=1.444$ V	375	800
	$V_1=1.866$ V, $V_2=1.444$ V	375	800
V_A Differential output voltage magnitude (asserted)	All four above conditions	$0,69 \times V_N + 50$	$1,45 \times V_N - 65$

[1] The test circuit (figure 13) is approximately equivalent to two terminators creating the normal system bias.



Note. Resistors are $\pm 0.1\%$

Figure 13. LVD steady-state output voltage test circuit (T10/1302D, Annex A, Figure 1)

Input characteristics

Each signal (V_s) received by LVD interface receiver circuits shall have the following input characteristics when measured at the disk drive connector:

Steady state Low level output voltage* = $0.030\text{ V} = < V_s = < 3.6\text{ V}$ (signal negation/logic 0)

Steady state High level output voltage* = $-3.6\text{ V} = < V_s = < -0.030\text{ V}$ (signal assertion/logic 1)

Differential voltage = $\pm 0.30\text{ V}$ minimum with common-mode voltage ranges $0.700\text{ V} = < V_{cm} = < 1.800\text{ V}$. (T10/1302D, SPI-3)

*These voltages shall be measured between the output terminal and the SCSI device's logic ground reference.

Input characteristics shall additionally conform to EIA RS-485-983.

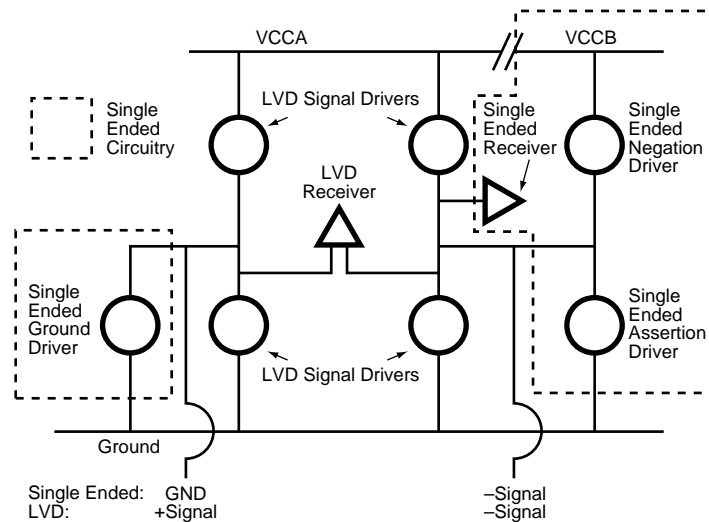


Figure 14. Typical SE-LVD alternative transmitter receiver circuits

9.8 Terminator requirements

“N” and “W” models have active, permanently mounted LSI terminator circuits on board the PCB.

All single initiator/single target (non-daisy-chain) applications require that the Initiator and disc drive be terminated. Daisy-chain applications require that only the units at each end of the daisy-chain be terminated. All other peripherals on the chain must not be terminated (see Figure 10a).

Note. Remove drive terminator enabling jumper **TE** where terminators are not required. Removal of terminator power source selection jumper **TP** (see Figure 7d) does not disconnect the terminator resistors from the circuit.

It is required that ANSI SCSI-2 Standard's Alternative 2 termination (active termination) be used for applications with single-ended mode, especially if the bus will be operated at transfer rates above 5 Mbytes/sec.

Note. ACTIVE TERMINATORS ARE REQUIRED FOR USE IN THE DAISY CHAIN AS DESCRIBED ABOVE. PASSIVE TERMINATORS SHALL NOT BE USED AT ANY TRANSFER SPEED. ACTIVE AND PASSIVE TERMINATORS SHALL NOT BE MIXED ON THE SAME SCSI BUS.

Drive models “LW” and “LC” do not have internal terminators available. The user, systems integrator or host equipment manufacturer must provide a terminator arrangement external to the drive. For “LW” models, terminator modules can be purchased that plug between the SCSI I/O cable and the drive I/O connector or on the end of a short I/O cable stub extending past the last cable connector.

ANSI Standard X3T10/1143D contains additional details about SCSI bus terminator and terminator power requirements.

9.9 Terminator power

“LW” model drives

You can configure terminator power in two different ways. See Section 8.1 for illustrations that show how to place jumpers enabling each of the following terminator power configurations:

1. The external terminator accepts terminator power through SCSI bus pins 17, 18, 51, and 52.
2. Drive supplies terminator power to the SCSI bus on pins 17, 18, 51, and 52.

SCSI devices providing terminator power (TERMPWR) must have the following characteristics:

8-bit SCSI	V TERM = 4.25 V to 5.25 V 800 mA minimum source drive capability 1.0 A maximum
16-bit SCSI	V TERM = 4.25 V to 5.25 V 1,500 mA minimum source drive capability 3.0 A maximum

“LC” model drives

These drives cannot furnish terminator power because no conductors in the 80-pin I/O connector are devoted to terminator power.

“N” and “W” model drives

You can configure terminator power in four different ways. See Section 8.1 for illustrations that show how to place jumpers enabling each of the following terminator power configurations:

1. Drive accepts terminator power through SCSI bus pins:
 - “N” Models Pin 26
 - “W” Models Pins 17, 18, 51, and 52
2. Drive supplies power to the SCSI bus.
3. Drive provides terminator power for optional internal terminator resistors using the drive's power connector.
4. Drive provides power to its own terminators and to the SCSI bus terminator power line.

SCSI devices providing terminator power (TERMPWR) must have the following characteristics:

8-bit SCSI	V TERM = 4.25 V to 5.25 V 800 mA minimum source drive capability 1.0 A maximum
16-bit SCSI	V TERM = 4.25 V to 5.25 V 1,500 mA minimum source drive capability 3.0 A maximum

9.10 Disc drive SCSI timing

Table 15: Disc drive SCSI timing

These values are not current Barracuda 18XL values, but are listed for information only.

Description	Waveform symbol [1]	Waveform table [1]	Typical timing
Target Select Time (no Arbitration)	T00	N/A	<1.4 μ s
Target Select Time (with Arbitration)	T01	4.5-1,2	1.93 μ s
Target Select to Command	T02	4.5-1	3.77 μ s
Target Select to MSG Out	T03	4.5-2	1.57 μ s
Identify MSG to Command	T04	4.5-3	3.36 μ s
Command to Status	T05	4.5-5	Command Dependent
Command to Data (para. In)	T06	4.5-9	Command Dependent
Command to Data (para. Out)	T07	4.5-10	Command Dependent
Command to Data (Write to Data Buffer)	T08	4.5-10	Command Dependent
Command to Disconnect MSG	T09	4.5-6	Command Dependent
Disconnect MSG to Bus Free	T10	4.5-6,14	0.52 μ s
Disconnect to Arbitration (for Reselect) This measures disconnected CMD overhead	T11	4.5-6	Command Dependent
Target win Arbitration (for Reselect)	T12	4.5-7	3.00 μ s
Arbitration to Reselect	T13	4.5-7	1.60 μ s
Reselect to Identify MSG In	T14	4.5-7	1.39 μ s
Reselect Identify MSG to Status	T15	4.5-8	Command Dependent
Reselect Identify MSG to Data (media)	T16	4.5-11	Command Dependent
Data to Status	T17	4.5-15	Command Dependent
Status to Command Complete MSG	T18	4.5-5,8,15	0.98 μ s
Command Complete MSG to Bus Free	T19	4.5-5,8,15	0.51 μ s
Data to Save Data Pointer MSG	T20	4.5-14	4.00 μ s
Save Data Pointer MSG to Disconnect MSG	T21	4.5-14	0.79 μ s
Command Byte Transfer	T22	4.5-4	0.04 μ s
Next Command Byte Access:		4.5-4	
Next CDB Byte Access (Byte 2 of 6)	T23.6.2	4.5-4	0.58 μ s
Next CDB Byte Access (Byte 3 of 6)	T23.6.3	4.5-4	0.12 μ s
Next CDB Byte Access (Byte 4 of 6)	T23.6.4	4.5-4	0.12 μ s
Next CDB Byte Access (Byte 5 of 6)	T23.6.5	4.5-4	0.12 μ s
Next CDB Byte Access (Byte 6 of 6)	T23.6.6	4.5-4	0.12 μ s
Next CDB Byte Access (Byte 2 of 10)	T23.10.2	4.5-4	0.59 μ s
Next CDB Byte Access (Byte 3 of 10)	T23.10.3	4.5-4	0.11 μ s \pm 1 μ s

Table 15: Disc drive SCSI timing

These values are not current Barracuda 18XL values, but are listed for information only.

Description	Waveform symbol [1]	Waveform table [1]	Typical timing
Next CDB Byte Access (Byte 4 of 10)	T23.10.4	4.5-4	0.12 μ s \pm 1 μ s
Next CDB Byte Access (Byte 5 of 10)	T23.10.5	4.5-4	0.11 μ s \pm 1 μ s
Next CDB Byte Access (Byte 6 of 10)	T23.10.6	4.5-4	0.11 μ s \pm 1 μ s
Next CDB Byte Access (Byte 7 of 10)	T23.10.7	4.5-4	0.13 μ s \pm 1 μ s
Next CDB Byte Access (Byte 8 of 10)	T23.10.8	4.5-4	0.12 μ s \pm 1 μ s
Next CDB Byte Access (Byte 9 of 10)	T23.10.9	4.5-4	0.12 μ s \pm 1 μ s
Next CDB Byte Access (Byte 10 of 10)	T23.10.10	4.5-4	0.12 μ s \pm 1 μ s
Data In Byte Transfer (parameter)	T24	4.5-12	0.04 μ s
Data Out Byte Transfer (parameter)	T25	4.5-13	0.04 μ s
Next Data In Byte Access (parameter)	T26	4.5-12	0.12 μ s
Next Data Out Byte Access (parameter)	T27	4.5-13	0.12 μ s
Data In Byte Transfer (media) [2]	T28	4.5-12	0.04 μ s
Data Out Byte Transfer (media) [2]	T29	4.5-13	0.04 μ s
Next Data In Byte access (media [2])	T30	4.5-12	0.12 μ s
Next Data Out Byte access (media [2])	T31	4.5-13	0.12 μ s
MSG IN Byte Transfer	T32	4.5-5,7,8,14,15	0.04 μ s
MSG OUT Byte Transfer	T33	4.5-2	0.04 μ s
STATUS Byte Transfer	T34	4.5-5,8,15	0.04 μ s
Synchronous Data Transfer Characteristics:			
Request Signal Transfer Period [3]	–	–	various (800 ns max)

Notes.

- [1] See the *SCSI Interface Product Manual*, part number 75789509.
- [2] Maximum SCSI asynchronous interface transfer rate is given in Section 4.2.3 of this manual.
- [3] Synchronous Transfer Period is determined by negotiations between an Initiator and a Drive. The Drive is capable of setting periods as given in Section 9.5. See also the Synchronous Data Transfer section and the Extended Messages section in the *SCSI Interface Product Manual*, for a description of synchronous data transfer operation.

10.0 Seagate Technology support services

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www.seagate.com for information about Seagate products and services. Worldwide support is available 24 hours daily by e-mail for your disc or tape questions.

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For support, questions and comments: reseller.seagate.com/benefits/T1.html or 1-877-271-3285 (toll-free) 9 A.M. to 7 P.M. (eastern time) Monday through Friday.

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SeaBOARD® is a computer bulletin board system that contains information about Seagate disc and tape drive products and is available 24 hours daily. Set your communications software to eight data bits, no parity and one stop bit (8-N-1).

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SeaFONE® (1-800-SEAGATE) is Seagate's toll-free number (1-800-732-4283) to access our automated self-help services. Using a touch-tone phone, you can find answers to service phone numbers, commonly asked questions, troubleshooting tips and specifications for disc drives and tape drives 24 hours daily. International callers can reach this service by dialing +1-405-936-1234.

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Presales Support

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If you need help installing your drive, consult your dealer. Dealers are familiar with their unique system configurations and can help you with system conflicts and other technical issues. If you need additional help, you can talk to a Seagate technical support specialist. Before calling, note your system configuration and drive model number (ST#####).

SeaTDD™ (+1-405-936-1687) is a telecommunications device for the deaf (TDD). You can send questions or comments 24 hours daily and exchange messages with a technical support specialist from 8:00 A.M. to 11:45 A.M. and 1:00 P.M. to 6:00 P.M. (central time) Monday through Friday.

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Canada			
<i>Memofix*</i>	1-800-636-6349	+1-905-660-4936 or	+1-905-660-4951 www.memofix.com
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Denmark	80 88 12 66
France	0 800-90 90 52
Germany	0 800-182 6831
Ireland	1 800-55 21 22
Italy	800-790695
Netherlands	0 800-732 4283
Norway	800-113 91
Poland	00 800-311 12 38
Spain	900-98 31 24
Sweden	0 207 90 073
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Appendix A. Sense keys and additional sense codes supported

Sense key	Description	Supported
0h	No sense	Y
1h	Recovered error	Y
2h	Not ready	Y
3h	Media error	Y
4h	Hardware error	Y
5h	Illegal request	Y
6h	Unit attention	Y
7h	Data protect	Y
9h	Firmware error	Y
Bh	Aborted command	Y
Ch	Equal	N
Dh	Volume overflow	N
Eh	Miscompare	Y

Additional sense code and qualifier

Bytes		Description	Supported
12	13		
00	00	No additional information	Y
01	00	No index/sector signal	Y
02	00	No seek complete	Y
03	00	Write fault	Y
04	00	Drive not ready, no additional information	Y
04	01	Drive not ready, in spin-up mode	Y
04	02	Drive not ready, waiting for initialization command	Y
04	03	Drive not ready, human intervention required	Y
04	04	Drive not ready, format in process	Y
04	09	Drive self-test in progress	Y
05	00	No drive response when selected	N
06	00	Track 0 not found	N
07	00	More than one drive selected	N
08	00	Drive communication failure	N
08	01	Drive communication timeout	Y
08	02	Drive communication parity error	N
09	00	Track following error	Y
09	04	Head select fault	N
0A	00	Error log overrun	N
0B	00	Warning (S.M.A.R.T.)	Y
0C	00	Write error	Y
0C	01	Write error recovered by reallocation	Y
0C	02	Write error, reallocation failed	Y
10	00	ID CRC error	N
11	00	Unrecovered read error	Y
11	01	Read retries exhausted	N

Bytes		Description	Supported
12	13		
11	02	Error too long to correct	N
11	04	Unrecoverable read error, autoreallocation failed	Y
12	00	No address mark in ID field	N
13	00	No address mark in data field	N
14	00	Sector not found	N
14	01	No record found	Y
15	00	Seek positioning error	N
15	01	Mechanical positioning error	Y
15	02	Positioning error determined by reading media	N
16	00	Data synchronization mark error	Y
17	00	Data recovered without ECC or retries	N
17	01	Data recovered with retries	Y
17	02	Data recovered with positive head offset	Y
17	03	Data recovered with negative head offset	Y
17	05	Data recovered with previous sector ID	N
17	06	Data recovered without ECC	N
18	00	Data recovered with ECC	Y
18	01	Data recovered with ECC and retries	Y
18	02	Data recovered with ECC, retries, and autoreallocation	Y
18	05	Recovered reassignment	N
18	07	Recovered data with ECC, data rewritten	N
19	00	Error in defect list	Y
19	01	Defect list not available	N
19	02	Error in P-list	N
19	03	Error in G-list	N
1A	00	Parameter overrun	Y
1B	00	Synchronous transfer error	N
1C	00	Defect list not found	Y
1C	01	P-list not found	N
1C	02	G-list not found	N
1D	00	Compare error with verify	Y
1E	00	Recovered ID error	N
20	00	Drive received invalid operation code	Y
21	00	LDA out of range	Y
24	00	CDB with invalid bit	Y
25	00	CDB with invalid LUN	Y
26	00	CDB with invalid field	Y
26	01	CDB with unsupported parameter	N
26	02	CDB with invalid parameter	Y
26	03	CDB with unsupported threshold parameter	Y
26	97	Invalid field parameter—TMS firmware tag	Y
26	98	Invalid field parameter—check sum	Y
26	99	Invalid field parameter—firmware tag	Y
27	00	Write protected	Y

Bytes		Description	Supported
12	13		
29	00	Power-on or pin 40 bus reset occurred	N
29	01	Power-on occurred	Y
29	02	SCSI bus reset occurred	Y
29	03	Bus Device Reset function occurred	Y
29	04	Device internal reset occurred	Y
29	05	Transceiver mode changed to single-ended	Y
29	06	Transceiver mode changed to LVD	Y
2A	00	Parameters changed by another initiator	N
2A	01	Mode select parameters changed by another initiator	Y
2A	02	Log parameters changed	Y
2A	03	Reservation Preempted	N
2C	00	Command sequence error	Y
2F	00	Tagged commands cleared by another initiator	Y
31	00	Format command failed	Y
32	00	Defect locations not available	Y
37	00	Rounded parameter error	Y
39	00	Saved parameters not supported	N
3D	00	Identify message with invalid bits	N
3E	03	Logical unit failed self-test	Y
3F	00	Target operation command changed	Y
3F	01	Microcode changed	N
3F	02	SCSI-1/SCSI-2 change	N
3F	0F	Echo buffer overwritten	Y
3F	90	Invalid CAP block	Y
40	00	Target operating conditions have changed	N
40	01	DRAM parity error detected	Y
40	93	Error in write to flash	N
42	00	Power on or self test error	Y
43	00	Message reject error	Y
44	00	Internal controller error	Y
45	00	Selection or reselection error	Y
47	00	Bus parity error	Y
48	00	Initiator detected error	Y
49	00	Initiator received invalid message from drive	Y
4E	00	Drive attempted overlapped commands	Y
5B	00	Log exception—factory option	Y
5B	01	Threshold condition met—factory option	Y
5B	02	Log counter reached maximum value—factory option	Y
5B	03	Log list codes all used—factory option	N
5C	00	RPL status change, drive lost synchronization	N
5D	FF	False failure prediction threshold exceeded	Y
65	00	Voltage Fault	Y
80	00	General firmware error qualifier	Y
81	00	Reassign power fail recovery failed	Y

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Seagate Technology, LLC.
920 Disc Drive, Scotts Valley, California 95066-4544, USA
Publication Number: 77767535, Rev. B, Printed in USA