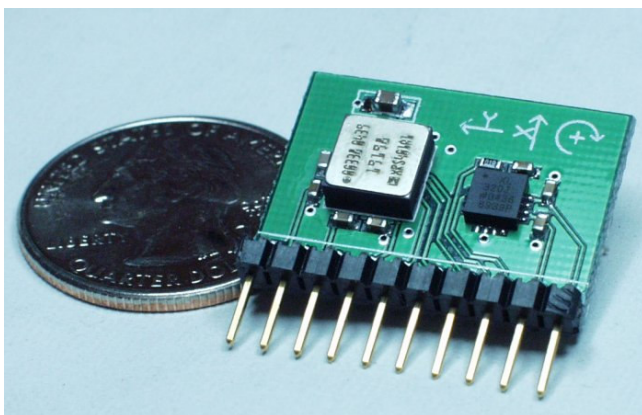
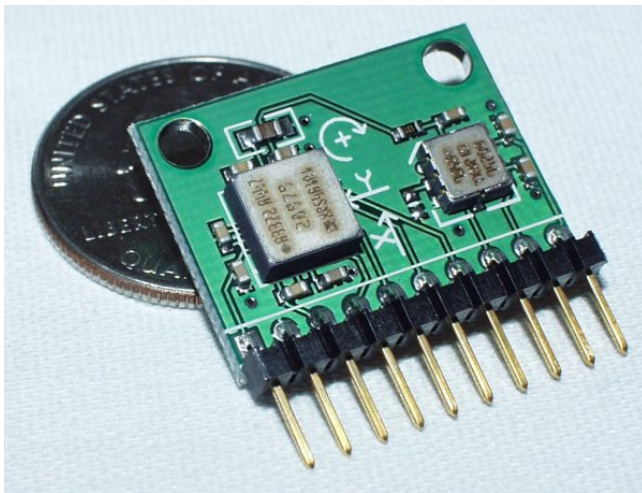


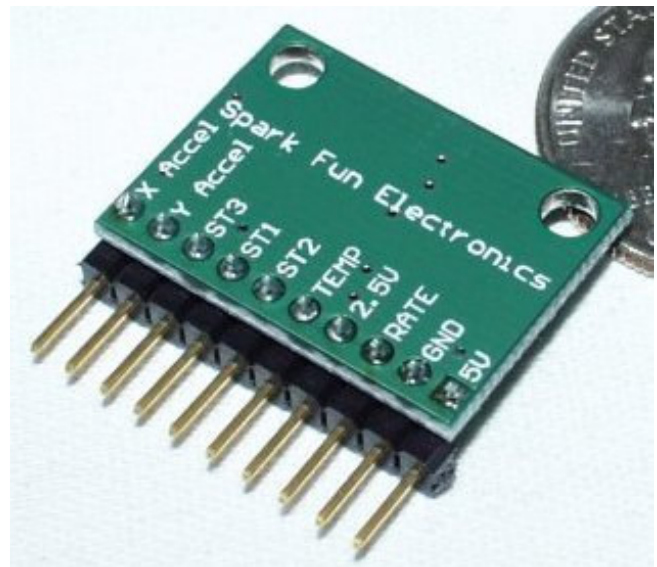
## IMU Combo Board



**2 Degree of Freedom Gyroscope/  
Accelerometer Combination**  
4/12/2005

### 1 Overview

The new ADXRS Gyro and ADXL Tilt sensors from Analog Devices are great new MEMs technology sensors. This module was developed to get these great sensors into the hands of hobbyists, engineers, and students. The footprint was made as small as possible, while retaining the most raw form of output from the sensors allowing the module to be used for any purpose the imagination can fathom. This module is ideal for reverse pendulum robots (the Segway is a perfect example) or with Unmanned Aerial Vehicle control (detect the roll of a plane for aileron correction).



### 2 Interface Specifications

Both sensors output an analog voltage representing the relative reading.

1. **5V** : 5 volt regulated power
2. **GND** : Ground Connection
3. **Rateout** : Gyro analog output
4. **2.5V Out** : Internal 2.5V precision output
5. **Temp** : Internal precision temperature
6. **ST2** : Self test 2 (Gyro)
7. **ST1** : Self test 1 (Gyro)

## IMU Combo v2

8. **ST3** : Self test 3 (Accelerometer)
9. **Y Accel** : Y axis acceleration output
10. **X Accel** : X axis acceleration output

### 3 Pin Definitions

**Rateout** : The ADXRS401 outputs 15mV/°/s or 15mV per degree per second. The ADXRS will output 2.5V on the Rateout pin while sitting still. When you rotate the module, this pin will fluctuate around 2.5V depending on how fast you rotate it. With a good ADC, you will be able to detect very small rotations/fluctuations.

**2.5V Out** : This pin connects to the internal precision 2.5V reference. Use this reference to compare it to your ADC readings to increase accuracy.

**Temp** : The ADXRS401 includes a precision temperature sensor for temperature compensation for increased accuracy. The Temp pin will output 2.5V at 27°C and will vary 8.4mV/°C.

**ST2** : Used to internally self-test the gyro.

**ST1** : Used to internally self-test the gyro.

**ST3** : Used to internally self-test the accelerometer.

**Y-Accel** : This pin will output 2.5V when laying flat on a table - perpendicular to the earth's surface. The output will change 312mV/g for the ADXL320 and 1000mV/g for the ADXL203. That is, for every gravity of acceleration on the Y axis, you will see a 312mV (or 1000mV) change on the 2.5V output.

**X-Accel** : Identical to Y-Accel, but in the perpendicular X axis. When perpendicular to the earth's surface, the ADXL320 X Accel pin (or similarly the Y Accel pin) will output 2.188V or 2.812 depending on orientation (+/- 180 degrees of tilt). Based on these values and the performance of your ADC, you will be able to very accurately detect tilt to a fraction of a degree. The ADXL203 has a much higher swing voltage of 1000mV/g (1.5V at -1g and 3.5V at +1g) and will provide greater resolution compared to the ADXL320 on the same ADC.

Of course you should always read the data-sheets specific to the ADXRS and ADXL sensors on your IMU Combo Board for more detailed information on the output specifications.

### 4 Increasing ADC Performance

The accuracy of your system will depend completely on your ADC. The higher the number of bits, the better resolution you can achieve. For instance, if you have a 10-bit ADC (common on most PICs/AVRs) you can detect

$$5V / 1024 = 4.88mV \text{ per bit}$$

4.88mV changes. If you have a 12-bit ADC

$$5V / 4096 = 1.22mV \text{ per bit}$$

or 1.22mV changes. Obviously you will be hindered greatly if your system is noisy or poorly decoupled. Use low noise voltage regulators and lots of decoupling capacitors.

#### 4.1 Decreasing the ADC Window

One common trick to increasing performance is by shrinking the window on which the Analog to Digital Converter operates. For instance, the PIC16F88 has two pins that serve as Vref- and Vref+. These are the upper and lower limits of the Voltage Reference on the ADC. You will need to read heavily into the datasheet for your specific micro, not all micros have both upper and lower Vref pins. The 16F88 can be set within specs to 1.5V and 3.5V. This gives us a *much* smaller window thus a more accurate measurement system:

$$2V / 1024 = 1.95mV \text{ per bit}$$

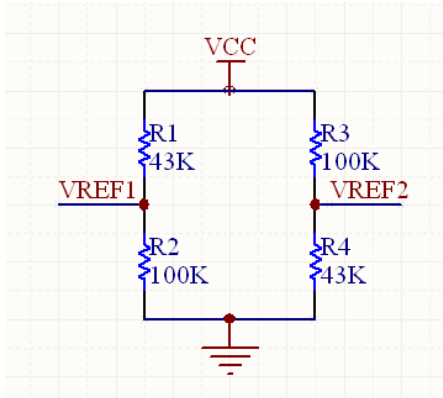
We effectively improved the performance of the ADC simply by decreasing the window in which we are measuring.

You will need to consider that you will saturate the ADC if you try to do an ADC on voltages that are less than 1.5V or greater than 3.5V, but just keep this in the back of your mind. Using

## IMU Combo v2

the Gyro and Accelerometer for reverse pendulum or UAV applications, you will need to detect very minute changes many times a second. Therefore, the firmware should be able to take care of special cases where the ADC saturates (the ‘uh-oh’ function should be called).

To set the  $V_{ref\pm}$  pins, a simple resistor divider circuit can be used:



### 4.2 Finding more ADC Channels

Many micros only have 3-4 ADC channels. Some PICs have as many as 8. But what do you do if you need more? There are devices called Analog Multiplexers that allow you to expand one ADC channel to 8 ADC channels. The 4051 IC (search Digikey “4051 dip mux”) allows you to multiplex one ADC channel to 8 different sources using 3 control pins. You get to read 8 ADC devices while only needing 1 ADC pin and 3 control pins (8 for the price of 4!).

### 4.3 Amplifying the Outputs

The analog signals can be amplified using a simple, single-supply opamp. Search Digikey for “OPA340 DIP”. It is a TI opamp that is sufficient for signal amplification and ADC interfacing.

