LPMS-B2

Reference Manual

Version 1.0

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I. INTRODUCTION

Welcome to the LP-RESEARCH Motion Sensor (LPMS) reference manual.

In this manual we will explain everything you need to know to set up the LPMS hardware, install its software and get started with integrating the sensor in your own software project. We have put a lot of effort into making the LPMS a great product, but we are always eager to improve and work on new developments. If you have any further questions or comments regarding this manual please feel free to contact us anytime.

For more information on the LPMS or other product series, please refer to datasheets and user manuals, available from the LP-RESEARCH website at the following address: `http://www.lp-research.com`.

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III. DOCUMENT REVISION HISTORY

Date	Revision	Changes
01-March-2016	1.0	- Initial release.

IV. INTRODUCTION

Measurement Output

The LP-RESEARCH Motion Sensor (LPMS) is a miniature, multi-purpose inertial measurement unit. We designed the unit to be as small as possible so that it can be used in a wide range of applications, from measuring the human motion to the stabilization of ground vehicles or airplanes. The unit can measure orientation in 360 degrees about all three global axes. Measurements are taken digitally and transmitted to a data analysis system in the form of orientation quaternion or Euler angles. Whereas Euler angles are one way of describing the orientation of an object, a quaternion allows orientation measurement without encountering the so-called Gimbal's lock. This is achieved by using a four-element vector to express orientation around all axes without being limited by singularities. A more in-depth explanation of the quaternion output of the LPMS will follow further on in this manual. Optionally an LPMS can be equipped with a barometric pressure sensor to extend the application range of the sensor and to be used e.g. in connection with a GPS unit for global position measurements.

Technical Background

To measure the orientation of an object, the sensor internally uses three different sensing units(four if the optional pressure sensor is used). These units are micro-electro-mechanical system (MEMS) sensors that integrate complex mechanical and electronic capabilities on a miniaturized device. The units used in the LPMS for orientation determination are a 3-axis gyroscope (detecting angular velocity), a 3-axis accelerometer (detecting the directing of the earth's gravity field) and a 3-axis magnetometer to measure the direction of the earth magnetic field. In principle orientation data about all three room axes can be determined by integrating the angular velocity data from the gyroscope. However through the integration step the error from the gyroscope measurements, although it might be very small, has an exponential influence on the calculation causing the resulting angle values to drift. Therefore we correct the orientation data from the gyroscope with information from the accelerometer (roll and pitch) and magnetometer (yaw) to calculate orientation information of high accuracy and stability while guaranteeing fast sampling rates. We combine the orientation information from the three sensing units using a complementary filter in conjunction with an extended Kalman filter (EKF), resulting in the so-called LP-Filter. The Kalman filter allows us to reduce the measurement error especially in case of regular movements (e.g. human gait analysis, vehicle vibration analysis etc.). The internal sampling and filtering rate of the sensor is 400Hz. The data stream frequency is independent from the sampling and processing rate and can be adjusted depending on the selected communication interface.

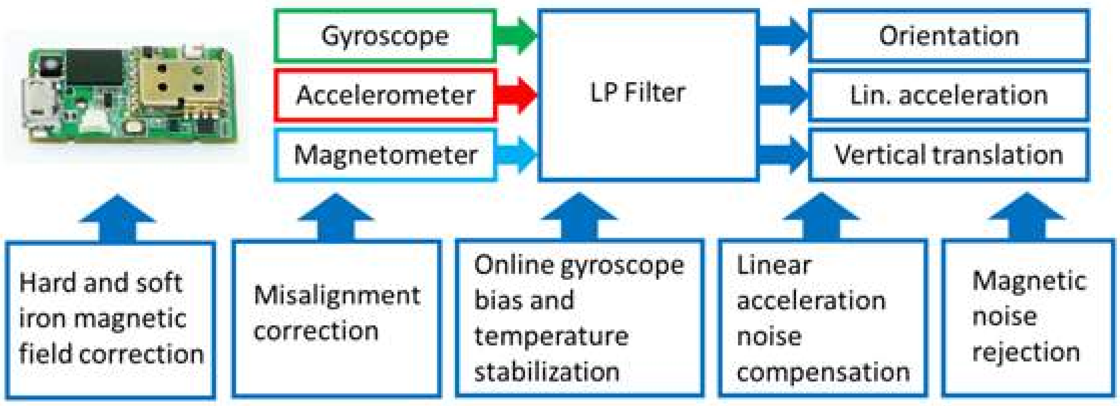

Figure 1 - Overview block diagram of the different components of the LPMS system.

Calibration

For accurate operation the sensor needs to be calibrated. The calibration procedure includes the determination of gyroscope bias and gain, gyroscope movement threshold, accelerometer misalignment, accelerometer offset and gain, and magnetometer interference bias and gain. As the earth magnetic field can be distorted by metal or electromagnetic sources within the vicinity of the sensor, the re-calibration of the magnetic sensor and re-calculation of the magnetic reference vector of the sensor might be necessary when using the sensor in different locations or under varying experiment environments. Later in this manual we will describe in detail the necessary calibration procedures necessary to guarantee the accuracy of the measurements done by the sensor. We tried to automate the calibration procedures as far as possible inside the firmware of the sensor to make the usage as convenient as possible for users.

To compensate the effects of a noisy earth magnetic field the LPMS is able to dynamically adjust the intensity of the magnetometer compensation to the impact of magnetic environment noise.

Size and Run-times

During development of the LPMS we tried to make the unit as small as possible to allow a large variety of application areas. The actual sensing units, microcontroller hardware and bluetooth module are integrated into one main-board with a 6-layer PCB design. The LPMS-B2 main board is a standalone module consisting all necessary sensing and communication capability

Application Areas

The LPMS is suitable for a wide range of applications. One of the applications focuses for a small scale motion sensor is the measurement of human movement for injury rehabilitation, gait cycle analysis, surgical skill training etc. The sensor can also be effectively used in the field of virtual reality, navigation, robotics, or for measuring vehicle dynamics. If more than one sensor is used for a sensor network the motion of complex objects as necessary in cinematic motion capturing or animation movie production is possible.

V. DEVICE SPECIFICATIONS

Common Parameters for all LPMS Models

Parameter	Value
Orientation measurement range	360 ° about all axes
Resolution	< 0.05 °
Accuracy	< 2 ° RMS (dynamic), < 0.5 ° (static)
Accelerometer	3-axis, ±20 / ±40 / ±80 / ±160 m/s^2, 16 bits
Gyroscope	3-axis, ±250 / ±500 / ±2000 °/s, 16 bits
Magnetometer	3-axis, ±4/±8/±12/±16 Gauss, 16 bits
Gyroscope noise	0.007 (dps/√Hz)
Maximum impact resistance	10,000 g
Pressure sensor	300-1100 hPa Pressure sensor is optional for all models
Available output data	Raw data / Euler angle / Quaternion / Linear acceleration / Vertical/Heave displacement (optional) / Barometric pressure (optional) / Altitude (optional) / Temperature (optional)
Internal sampling / processing rate	400 Hz

Device Specific Parameters and Connectors

LPMS-B2

Specifications

Unit type	LPMS-B2 (standard)	LPMS-B2 (OEM version)
Interface type	Bluetooth 4.1 Classic and Low Energy[1]	
Maximum baud rate	921600 Baud	
Communication protocol	LPBUS	
Size	39x39x8 mm	16x31x4 mm
Weight	12 g	2 g
Bluetooth	Bluetooth 4.1 Smart Ready BT Module type: BT53	
Communication distance	Range up to 80m (Line of Sight)	
Maximum data transmission rate	400Hz	
Latency	15 ms	
Power consumption	150 mW @ 3.3V	
Power supply	Lithium battery ~6 h (3.7 V @ 230mAh)	3.7V DC
Temperature range	-20..+60 ℃	-40..+80 ℃
Connector	Micro USB, type B	

1. Currently under development

LPMS-B2 Main Connector

Connector type: Micro-USB type B female

Pin no.	**1**	**2**	**3**	**4**	**5**
Function	Vcc	None	None	None	GND

NOTE: This connector is used for recharging the LPMS-B2 battery. Power is internally supplied to the LPMS-B2 by a rechargeable battery contained inside the LPMS-B2 case. 5V power from a usb connector can be directly apply to the connector.

Charging Status

LED Color (Firmware 2.0.0)	LED Color (Firmware > 2.0.1)	Status
Red	Red	The battery capacity is less than 20%
Green	Blue	The battery capacity is 20% ~ 90%
Blue	Green	The battery is fully charged

NOTE: LED will light up according to charging status listed in the table above even when the sensor connection is established. The total recharging time normally takes 2~3 hours.

VI. OPERATION

Powering Up and Operation Modes

LPMS-B2 is switched on by pressing its power button. The blue LED light up when operation power is supplied to the device. The sensor will take roughly 3s to initialize following by led blinking with an interval of 1s. The sensor is now ready for pairing and connection.

Operational state	LED Status / Color
Initializing	Blue (3s)
Ready for pairing	Blinking 1Hz Blue or Red indicating low battery
Streaming Mode	Fade in 1s Fade out 2s Blue or Red indicating low battery
Command Mode	Blinking 10Hz Blue
Firmware update	Blinking 10Hz Blue following by Blinking 50Hz Green

Internally LPMS has two different communication modes:

Mode	Description
Command mode **(default at power-on)**	In command mode the functionality of the sensor is accessed command-by-command. Measurement data is transferred from the sensor to the user by a special command. This mode is suitable for making adjustments to the parameter settings of the sensor and synchronized data-transfer. Blue LED blinking with a frequency of 10Hz in this mode.
Streaming mode	In streaming mode data is continuously sent from the sensor to the host. This mode is suitable for simple and high-speed data acquisition. Sensor parameters cannot be set in this mode. Blue/Red LED fades in and out in this mode

NOTE:The sensor is set to **command mode by default after powering on**. Streak9jg mode may be set via the corresponding LPBUS command.

Host Device Communication

Bluetooth Classic

To connect to the sensor, a Bluetooth connection request must be sent to the Bluetooth MAC address of LPMS-B2. This MAC address is displayed as sensor device ID in the LpmsControl application.

Users should connect to the Bluetooth module of LPMS-B2 using a standard class 2 Bluetooth host interface that supports SPP (serial protocol profile). A key-code for pairing is not normally required. Should you be asked for a key-code anyway, enter “1234”. Establishing a connection with the sensor usually takes around 2 to 5 seconds. The Bluetooth device name of the sensor for device discovery is LPMSB2-XXXXXX where the Xs are replaced by the last 6 characters of the bluetooth MAC address. The baudrate of the Bluetooth connection is 921600bit/s.

NOTE: Bluetooth communication always uses the LPBUS binary format for input / output.

Orientation Data

The LPMS sensor calculates the orientation difference between a fixed sensor coordinate system and a global reference coordinate system. The local and the global reference coordinate systems used are defined as right handed Cartesian coordinate systems with:

- X positive when pointing to the magnetic west
- Y positive when pointing to the magnetic south
- Z positive when pointing up (gravity points vertically down with -1g)

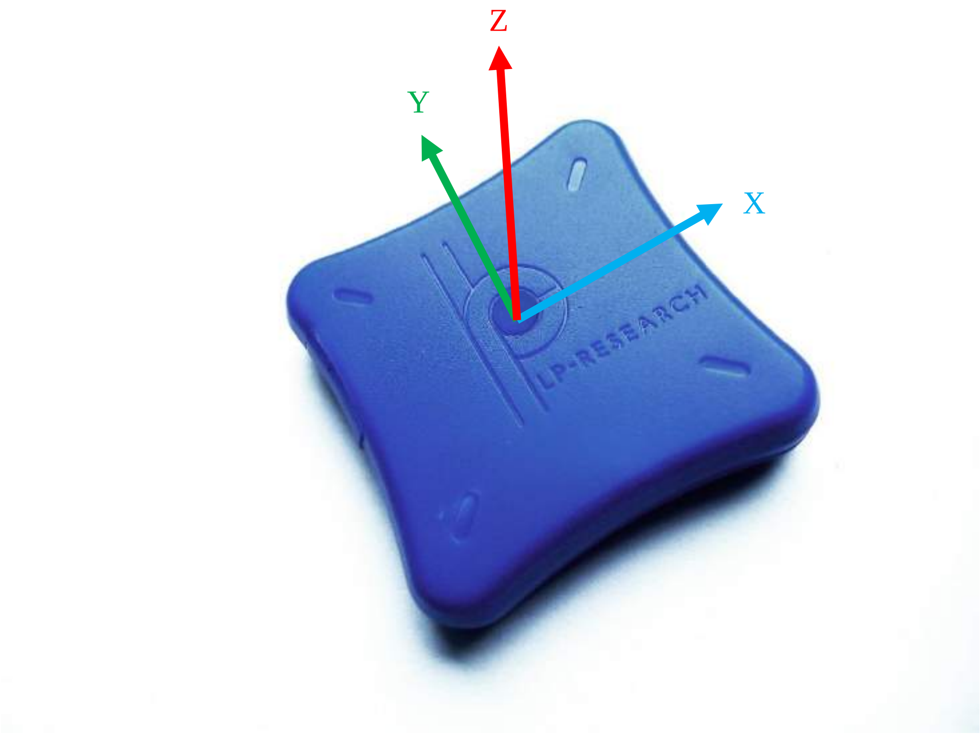

Figure 3 - Axis orientation of LPMS-B2. The direction of the x, y, z-axis (roll, pitch, yaw) of the sensor is displayed on its label.

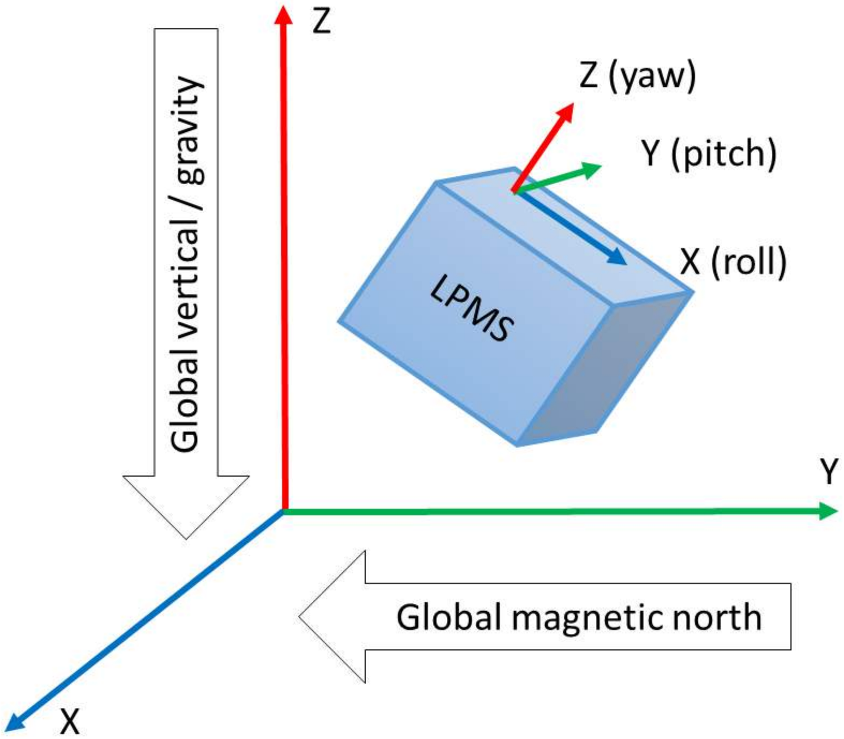

Figure 4 - Relationship between local sensor coordinate system and global coordinates.

See Figure 3and Figure 4 displaying the orientation and relationship of local sensor and earth global coordinate systems. The 3D orientation output is defined as the orientation between the body-fixed coordinate system and the global coordinate system, using the global coordinate system as reference.

A positive rotation is always right-handed, i.e. defined according to the right hand rule (corkscrew rule). This means a positive rotation is defined as clockwise in the direction of the axis of rotation.

The definition used for Euler angles in this document is equivalent to roll, pitch, yaw/heading. The Euler angles are of ZYX global type (subsequent rotation around global Z, Y and X axis, also known as aerospace sequence).

ϕ = Rotation around global X, defined from -180 °...180 °

θ = Rotation around Y, defined from -90 °...90 °

ψ = Rotation around Z, defined from -180 °...180 °

NOTE: Due to the definition of Euler angles there is a mathematical singularity when the sensor-fixed X-axis is pointing up or down in the global reference frame (i.e. pitch approaches+/-90).

This singularity is not present in quaternion output.

Sensor Orientation Alignment Modes

Heading reset

Often it is important that the global Z-axis remains along the vertical (defined by local gravity vector), but the global X-axis has to be in a particular direction. In this case a heading reset may be used. When performing a heading reset, the new global reference frame is chosen such that the global X-axis points in the direction of the sensor while keeping the global Z-axis vertical (along gravity, pointing upwards). In other words: The global Z-axis point upwards along gravity, where the X and Y axis orthogonally form a perpendicular plane.

NOTE: After a heading reset, the yaw may not be exactly zero, this occurs especially when the X-axis is close to the vertical. This is caused by the definition of the yaw when using Euler angles, which becomes unstable when the pitch approaches +/-90 deg.

Object reset

The object reset function aims to facilitate in aligning the LPMS coordinate frame (S)with the coordinate frame of the object to which the sensor is attached (O). After an object reset, the S coordinate frame is changed to S' as follows:

The S' Z-axis is the vertical (up) at time of reset
The S' X-axis equals the S X-axis, but projected on the new horizontal plane.
The S' Y-axis is chosen as to obtain a right handed coordinate frame.

NOTE: Once this object reset is done, both calibrated data and orientation will be output in the new coordinate frame (S').

The object reset aligns the LPMS coordinate frame to that of the object to which it is attached (see Figure 5). The sensor has to be attached in such a way that the X-axis is in the XZ-plane of the object coordinate frame, i.e. the LPMS can be used to identify the X-axis of the object. To preserve the global vertical, the object must be oriented such that the object Z-axis is vertical. The object reset causes the new S' coordinate frame and the object coordinate frame to be aligned.

NOTE: Since the sensor X-axis is used to describe the direction of the object X-axis, the reset will not work if the sensor X-axis is aligned along the Z-axis of the object.

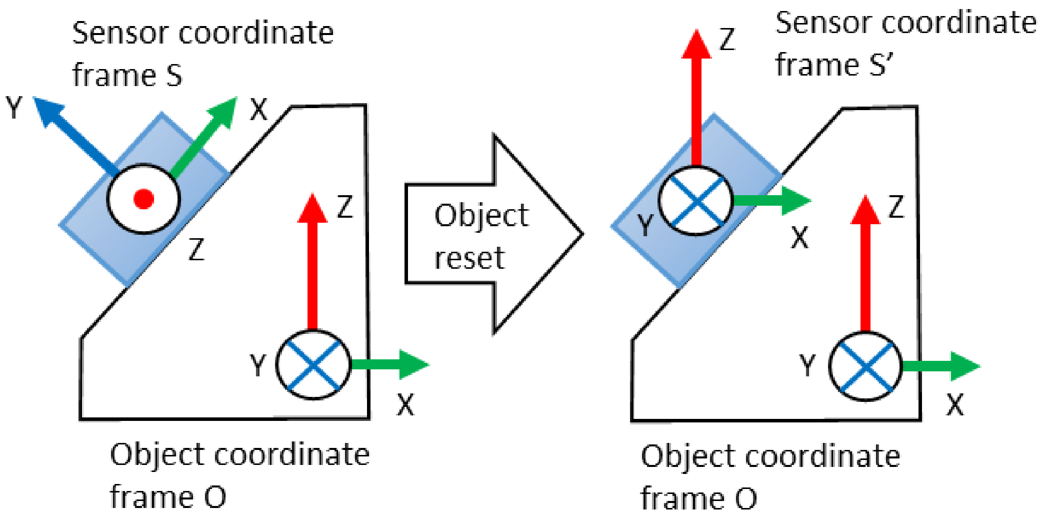

Figure 5 - The object reset aligns the sensor coordinate system with the object coordinate system.

Alignment reset

The alignment reset simply combines the Object reset and the Heading reset at a single instant in time. This has the advantage that all coordinate systems can be aligned with a single action. Keep in mind that the new global reference X-axis (heading) is defined by the object X-axis (to which XZ-plane you have aligned the LPMS).

NOTE: Once this alignment reset is conducted, both calibrated data and orientation will be output with respect to the new S' coordinate frame.

Data Acquisition

Raw Sensor Data

The LPMS contains three MEMS sensors: A gyroscope, an accelerometer and a magnetometer. The raw data from all three of these sensors can be accessed by the host system based on the LPBUS protocol. The raw sensor data can be used to check if the current acquisition range of the sensors is sufficient and if the different sensors generate correct output. Users can also implement their own sensor fusion algorithms using the raw sensor data values. Sensor range and data sampling speed can be set by sending commands to the firmware.

The LPMS is delivered in a factory-calibrated state, but it might be necessary to recalibrate the sensors if the measurement environment changes (different ambient electromagnetic field, strong temperature change). Please refer to the following sections for a detailed introduction of sensor calibration methods.

1. Gyroscope raw data: Data from sensor is calibrated (bias, scaling and misalignment applied)
2. Accelerometer raw data: Data from sensor is calibrated (bias, scaling and misalignment applied)
3. Magnetometer raw data: Data from sensor is scaled, but not hard / soft iron calibrated (scaling and misalignment applied)

Orientation Data

The LPMS has two orientation output formats: quaternion and Euler angle. As the Euler angle representation of orientation is subject to the Gimbal lock, we strongly recommend users to rely on quaternion representation for orientation calculation.

Filter Settings

Data from the three MEMS sensors is combined using an extended complementary Kalman filter (LP-Filter) to calculate the orientation data, like quaternion and Euler angle. To make the filter operate correctly, its parameters need to be set in an appropriate way.

Filter Modes

The selection of the right filter mode is essential for a good performance of the orientation calculation. The following filter modes are available:

Filter mode	Description
Gyroscope only	This mode uses only gyroscope data to calculate sensor orientation. **Pro:** Very responsive, Low noise **Con:** Accumulating offset due to integration of gyroscope bias error
Gyroscope + accelerometer (default mode)	Gyroscope-based orientation values are stabilized by accelerometer measurements in the pitch and roll axis. **Pro:** No drift on the pitch and roll axis **Con:** Drift on yaw axis, slightly longer stabilization times than pure gyroscope calculation
Gyroscope + accelerometer + magnetometer	Gyroscope-based orientation values are stabilizes by accelerometer measurements in the pitch and roll axis and by magnetometer measurements in the yaw axis. **Pro:** No drift on all axes, especially in noise-free environment **Con:** Prone to magnetic noise, slightly longer stabilization times than pure gyroscope calculation, calibration necessary
Accelerometer + magnetometer (Euler only)	Orientation is calculated by Euler-angle based triangulation. **Pro:** No drift (especially in noise-free environment), fast, no misalignment offset **Con:** Singularities due to Euler-angle-based calculation, prone to magnetic noise, prone to linear acceleration noise, calibration necessary
Gyroscope + accelerometer (Euler only)	Gyroscope-based orientation values are stabilized by accelerometer measurements in the pitch and roll axis. **Pro:** No drift on the pitch and roll axis **Con:** Singularities due to Euler-angle-based calculation, drift on yaw axis, slightly longer stabilization times than pure gyroscope calculation

Magnetometer Correction Setting

The amount by which the magnetometer corrects the orientation output of the sensor is controlled by the magnetic correction settings. The following options are selectable through LpmsControl or directly through the firmware commands.

Parameter presets	Description
Dynamic (default)	Magnetic correction is performed dynamically. The stronger the detected magnetic noise the less the sensor will rely on magnetometer data.
Weak	Low reliance on magnetometer correction
Medium	Medium reliance on magnetometer correction
Strong	Strong reliance on magnetometer correction

Acceleration Compensation Setting

The amount by which the accelerometer corrects the orientation output of the sensor is controlled by both linear acceleration and centripetal acceleration settings. The following options are selectable through LpmsControl or directly through firmware commands.

Linear Acceleration Correction Settings

Parameter presets	Description
Off	No linear acceleration correction
Weak	Weak linear acceleration correction
Medium (default)	Medium reliance on magnetometer correction
Strong	Strong reliance on magnetometer correction
Ultra	Very strong reliance on magnetometer correction

Rotational Acceleration Correction Settings

Parameter presets	Description
Disable	No centripetal acceleration correction
Enable (default)	Centripetal acceleration correction is on

Gyroscope Threshold

A threshold can be applied to the gyroscope data so that the sensor orientation data is only updated when the sensor is moved.

Parameter preset	Description

Enable	Switches gyroscope threshold on
Disable (default)	Switches gyroscope threshold off

Gyroscope Auto-calibration Function

As described earlier in this manual the selection of the following parameter values allows the users to enable or disable the gyroscope auto calibration function. In auto calibration mode the sensor fusion filter automatically detects if the sensor is in a stable / motion-less state. If the sensor stays still for 7.5s, the currently sampled gyroscope data will be used to re-calculate the gyroscope offset. Using this function will enhance the accuracy of the gyroscope data in especially in changing temperature environments.

Parameter preset	Description
Enable	Switch gyroscope auto-calibration on
Disable	Switch gyroscope auto-calibration off

Low Pass Filter Setting

The selection of the following parameter values allows the users to further implement a simple low pass filter for smoothing the output data after the sensor fusion algorithm. The low pass filter is based on the following formula: $X_i = (1-a)*X_{i-1} + a*U_i$, where a is the coefficient listed in the following table, U is the input.

Parameter preset	Description
Off	No filter implemented
0.1	a = 0.1
0.05	a = 0.05
0.01	a = 0.01
0.005	a = 0.005
0.001	a = 0.001

Calibration Methods

Gyroscope Bias Calibration and Threshold

When the sensor is resting, the output data of the gyroscope should be close to 0. The raw data from the gyroscope sensor has a constant bias of a certain value. This is related to the mechanical structure of the gyroscope MEMS, which can slightly change its characteristics depending e.g. on the environment temperature. There are two ways to determine the gyroscope bias:

1. **Automatic calibration**: If the sensor is in a motion-less state for more than 7.5s the gyroscope bias will be automatically readjusted.

2. **Manual calibration**: To determine the bias value manually the following calibration procedure needs to be applied. Alternatively to calibration from the LpmsControl application, the calibration can also be triggered through direct communication with the sensor.

Step	Description
1	Put the sensor in a resting (non-moving) position
2	Trigger the gyroscope calibration procedure either through a firmware command or using the “Calibrate gyroscope” function in LpmsControl software
3	The gyroscope calibration will take around 30s. After that the gyroscope is calibrated, normal operation can be resumed

The **gyroscope threshold** will set up an angular speed limit, below which the LPMS will not process any motion data. This setting can be used to suppress noise or vibrations that might impact the sensor measurements. Users should be careful when applying this functionality, though, as motion information below the threshold will be lost and this might significantly reduce the accuracy of the overall orientation measurement.

Magnetometer Calibration

During the magnetometer calibration procedure several parameters about the magnetic environment close to the sensor are to be determined: magnetometer bias / gain on the X, Y and Z-axis and length / direction of the local geomagnetic field vector. In most environments the earth magnetic field is influenced by electromagnetic noise sources such as power lines, metal etc. As a result the magnetic field becomes de-centered and deformed.

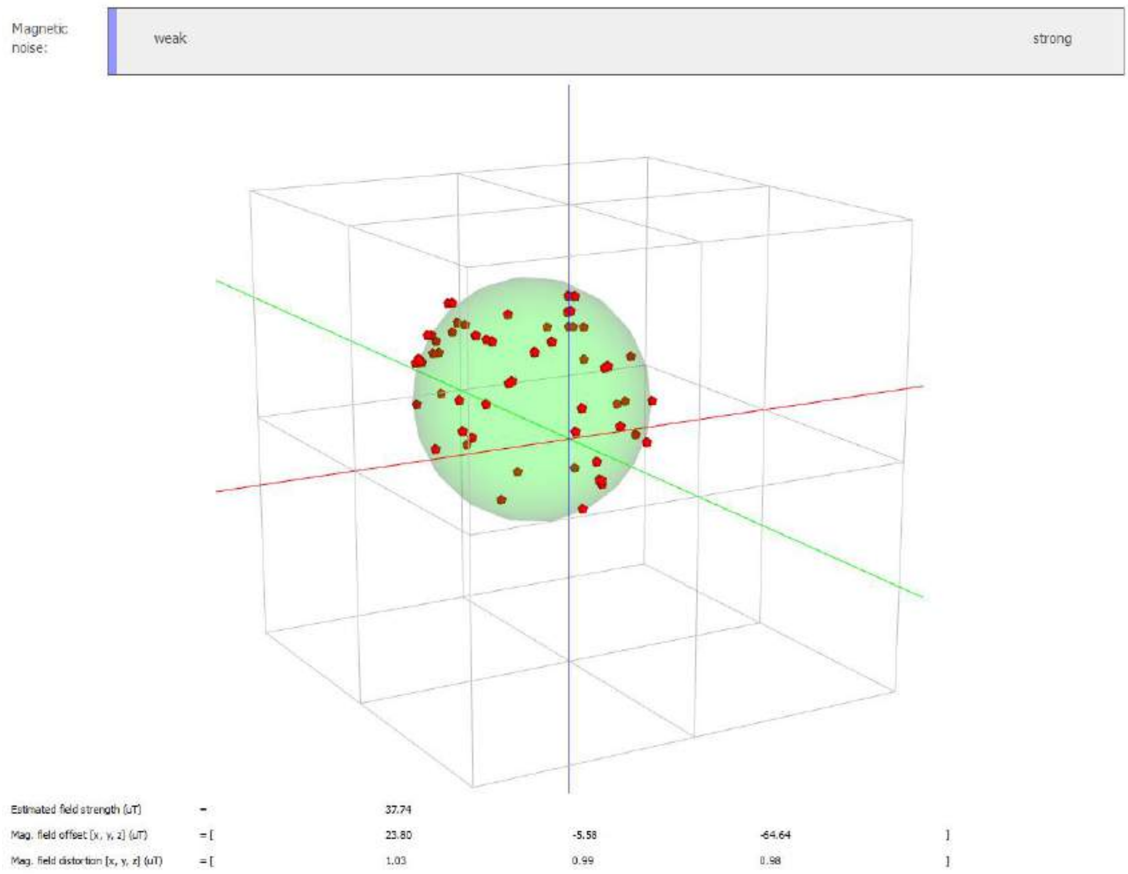

Figure 6 - Result of a successful magnetometer calibration. The green ellipsoid fit should be relatively close to the red points of the magnetic field map. The magnetic noise indicator should be very low in vicinity of the place where the calibration was done.

During the magnetometer calibration the amount of this deformation as well as the average length of the magnetic field vector is calculated. This is usually also referred to as **hard-iron and soft-iron calibration**. These parameters are tuned automatically using the calibration procedures in the LpmsControl software:

Step	Description
1	Start the magnetometer calibration using the LpmsControl software (Calibration -> Calibrate mag.).
2	Follow the instructions of the calibration wizard. Rotate the sensor around its yaw axis for 2-3 rotations.
3	Rotate the sensor around its pitch axis for 2-3 rotations.
4	Rotate the sensor around its roll axis for 2-3 rotations.
5	Rotate the sensor randomly to acquire data as much as possible from different directions.

6	The collection of the field map data is finished after 40 seconds. This is followed by calculation of the geomagnetic field vector (local earth magnetic field inclination). Keep the sensor close to the calibration location and press the Next button in the calibration wizard.
7	After 10 seconds the calibration is complete.

There are two methods for calibrating the hard iron offset and soft iron matrix:

1. Ellipsoid fit: Parameters are calculated by creating a map of the environment field and then fitting an ellipsoid through the point data. The point cloud after rotating the sensor around its axes should look similar to Figure 6.

2. Min / max fit: Parameters are calculated by measuring the minimum and maximum field values for each axis during the sensor rotation process. This method can in principle be used for planar magnetometer calibration. This is important in cases where the magnetometer is fixed to a reference frame that can't be rotated around all axes e.g. a car.

NOTE: The calculations for the magnetometer calibration are currently executed within the LpSensor library running on the host. They can't be triggered directly from communication commands on the sensor.

Multiple-device Synchronization

Often we want to sync multiple LPMS-B2 sensors during data acquisition. A software synchronization functionality is implemented in each sensor. To sync multiple sensors, please follow the steps below:

1. Under Calibration menu > click Software Sync Start to put the sensors into sync mode
2. Sensor LED should light up indefinitely.
3. Wait ~1s and click Software Sync Stop to stop sync mode and resume to normal operation.
4. Each sensor LED wave pattern should light up at the same time indicating the sensors are in sync.
   Note: The sync accuracy is affected by the delay in bluetooth communication. Hard realtime sync cannot be guaranteed

Trade-offs and Limitations

Although we put a lot of effort into the design of the LPMS, there are a few limitations that need to be taken into account when using the sensor. The accuracy of the sensor is limited by the electronic noise level of the MEMS sensors. The system runs at an internal measurement and processing frequency of 400Hz. The parameters of the filter that fuses the data from the gyroscope, magnetometer and accelerometer need to be adjusted well, in order to achieve measurements with maximum accuracy. Furthermore, in case the sensor is used in changing environments, the sensor occasionally might need to be re-calibrated. The greatest drawback of the measurement principle of the sensor certainly is its sensitivity to a noisy earth magnetic field (e.g. in the vicinity of hard / soft iron, electric motors etc.). In such situations the use of the filter mode and parameters of the filter must be well considered. In case of LPMS-B2, battery run-times should be taken into account when planning usage of the sensor for a new application. Furthermore, the wireless Bluetooth connection puts a limit on the maximum range and the maximum data update frequency.

VII. COMMUNICATION PROTOCOL

LPBUS Protocol

LPBUS is a communication protocol based on the industry standard MODBUS protocol. It is the default communication format used by LPMS devices.

An LPBUS communication packet has two basic command types, GET and SET, that are sent from a host (PC, mobile data logging unit etc.) to a client (LPMS device). Later in this manual we will show a description of all supported commands to the sensor, their type and transported data.

GET Commands

Data from the client is read using GET requests. A GET request usually contains no data. The answer from the client to a GET request contains the requested data.

SET Commands

Data registers of the client are written using SET requests. A SET command from the host contains the data to be set. The answer from the client is either ACK(acknowledged) for a successful write, or NACK(not acknowledged) for a failure to set the register occurred.

Packet Format

Each packet sent during the communication is based on the following structure:

Byte #	Name	Description
0	Packet start (3Ah)	Data packet start
1	OpenMAT ID byte 1	Contains the low byte of the OpenMAT ID of the sensor to be communicated with. The default value of this ID is 1. The host sends out a GET / SET request to a specific LPMS sensor by using this ID, and the client answers to request also with the same ID. This ID can be adjusted by sending a SET command to the sensor firmware.
2	OpenMAT ID byte 2	High byte of the OpenMAT ID of the sensor.
3	Command # byte 1	Contains the low byte of the command to be performed by the data transmission.
4	Command # byte 2	High byte of the command number.
5	Packet data length byte 1	Contains the low byte of the packet data length to be transmitted in the packet data field.
6	Packet data length byte 2	High byte of the data length to be transmitted.
x	Packet data(***n*** bytes)	If data length ***n*** not equal to zero, ***x* = 6+1, 6+2…6+*n***. Otherwise ***x*** = none. This data field contains the packet data to be transferred with the transmission if the data length not equals to zero, otherwise the data field is empty.
7+*n*	LRC byte 1	The low byte of LRC check-sum. To ensure the integrity of the transmitted data the LRC check-sum is used. It is calculated in the following way: LRC = sum(OpenMAT ID, Command, Package data length, and packet data byte no. 1 to no. ***x***) The calculated LRC is usually compared with the LRC transmitted from the remote device. If the two LRCs are not equal, and error is reported.
8+n	LRC byte 2	High byte of LRC check-sum.
9+n	Termination byte 1	0Dh
10+n	Termination byte 2	0Ah

Data Format in a Packet Data Field

Generally data is sent in little-endian format, low order byte first, high order byte last. Data in the data fields of a packet can be encoded in several ways, depending on the type of information to be transmitted. In the following we list the most common data types. Other command-specific data types are explained in the command reference.

Identifier	Description
Int32	32-bit signed integer value
Int16	16-bit signed integer value
Float32	32-bit float value
Vector3f	3 element 32-bit float vector
Vector3i16	3 element 16-bit signed integer vector
Vector4f	4 element 32-bit float vector
Vector4i16	4 element 16-bit signed integer vector
Matrix3x3f	3x3 element float value matrix

Sensor Measurement Data in Streaming Mode

In streaming mode, LPBUS transports measurement data in the following form, wrapped into the standard LPBUS protocol. See the following chapter for examples of transmission packets. The order of the sensor data chunks depends on which sensor data is switched on

The following is the data types in **32-bit float transmission mode.**

In 32-bit float transmission mode:

Chunk #	Data type	Sensor data
1	uint32	Timestamp counter. Divide by 400 to get timestamp in ms
2	Vector3f	Calibrated gyroscope data(deg/s)
3	Vector3f	Calibrated accelerometer data(m/s^2)
4	Vector3f	Calibrated magnetometer data(μT)
5	Vector3f	Angular velocity (rad/s)
6	Vector4f	Orientation quaternion(normalized)
7	Vector3f	Euler angle data (rad)
8	Vector3f	Linear acceleration data (m/s^2)
9	Float32	Barometric pressure (kPa)
10	Float32	Altitude (m)
11	Float32	Temperature (℃)
12	Float32	Heave motion (m) (optional)

In **16-bit transmission mode** values are transmitted to the host with a multiplication factor applied to increase precision:

Order #	Data type	Sensor data	Factor
1	uint32	Timestamp counter. Divide by 400 to get timestamp in ms	
2	Vector3i16	Calibrated gyroscope data(deg/s)	1000
3	Vector3i16	Calibrated accelerometer data(m/s^2)	1000
4	Vector3i16	Calibrated magnetometer data(µT)	100
5	Vector3i16	Angular velocity (rad/s)	1000
6	Vector4i16	Orientation quaternion(normalized)	1000
7	Vector3i16	Euler angle data (rad)	1000
8	Vector3i16	Linear acceleration data (m/s^2)	1000
9	Int16	Barometric pressure (kPa)	100
10	Int16	Altitude (m)	10
11	Int16	Temperature (℃)	100
12	Int16	Heave motion (m) (optional)	1000

The following units are used for measured and processed sensor data:

Data type	Units
Angular velocity (gyroscope)	rad/s
Acceleration (accelerometer)	g
Magnetic field strength (magnetometer)	µT
Euler angle	radians
Linear acceleration	g
Quaternion	normalized units
Barometric pressure	kPa
Altitude	m
Temperature	℃

NOTE: Raw accelerometer data is transmitted with misalignment correction and scaling to m/s^2 units applied. Raw gyroscope data is transmitted with misalignment correction, bias correction and scaling to rad/s applied. Raw magnetometer data is transmitted with misalignment correction and scaling to µT applied, **hard and soft iron calibration is not applied to raw magnetometer data transmitted directly from sensor.**

Example Communication

In this section we will show a few practical examples of communication using the LPBUS protocol. For further practical implementation ideas check the open source code of LpmsControl and LpSensor.

Request Sensor Configuration

GET request (HOST -> SENSOR)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	04h	Command no. LSB (4d = GET_CONFIG)
4	00h	Command no. MSB
5	00h	Data length LSB (GET command = no data)
6	00h	Data length MSB
7	05h	Check sum LSB
8	00h	Check sum MSB
9	0Dh	Packet end 1
10	0Ah	Packet end 2

Reply data (SENSOR -> HOST)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT LSB (ID = 1)
2	00h	OpenMAT MSB
3	04h	Command no. LSB (4d = GET_CONFIG)
4	00h	Command no. MSB
5	04h	Data length LSB (32-bit integer = 4 bytes)
6	00h	Data length MSB
7	xxh	Configuration data byte 1 (LSB)
8	xxh	Configuration data byte 2
9	xxh	Configuration data byte 3
10	xxh	Configuration data byte 4 (MSB)
11	xxh	Check sum LSB
12	xxh	Check sum MSB

13	0Dh	Packet end 1
14	0Ah	Packet end 2

xx = Value depends on the current sensor configuration.

Request Gyroscope Range

GET request (HOST -> SENSOR)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	1Ah	Command no. LSB (26d = GET_GYR_RANGE)
4	00h	Command no. MSB
5	00h	Data length LSB (GET command = no data)
6	00h	Data length MSB
7	1Bh	Check sum LSB
8	00h	Check sum MSB
9	0Dh	Packet end 1
10	0Ah	Packet end 2

Reply data (SENSOR -> HOST)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	1Ah	Command no. LSB (26d = GET_GYR_RANGE)
4	00h	Command no. MSB
5	04h	Data length LSB (32-bit integer = 4 bytes)
6	00h	Data length MSB
7	xxh	Range data byte 1 (LSB)
8	xxh	Range data byte 2
9	xxh	Range data byte 3
10	xxh	Range data byte 4 (MSB)
11	xxh	Check sum LSB
12	xxh	Check sum MSB
13	0Dh	Packet end 1

14	0Ah	Packet end 2

xx = Value depends on the current sensor configuration.

Set Accelerometer Range

SET request (HOST -> SENSOR)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	1Fh	Command no. LSB (31d = SET_ACC_RANGE)
4	00h	Command no. MSB
5	04h	Data length LSB (32-bit integer = 4 bytes)
6	00h	Data length MSB
7	08h	Range data byte 1 (Range indicator 8g = 8d)
8	00h	Range data byte 2
9	00h	Range data byte 3
10	00h	Range data byte 4
11	2Bh	Check sum LSB
12	00h	Check sum MSB
13	0Dh	Packet end 1
14	0Ah	Packet end 2

Reply data (SENSOR -> HOST)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	00h	Command no. LSB (0d = REPLY_ACK)
4	00h	Command no. MSB
5	00h	Data length LSB (ACK reply = no data)
6	00h	Data length MSB
11	01h	Check sum LSB
12	00h	Check sum MSB
13	0Dh	Packet end 1
14	0Ah	Packet end 2

Read Sensor Data

Get request (HOST -> SENSOR)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT MSB
3	09h	Command no. LSB (9d = GET_SENSOR_DATA)
4	00h	Command no. MSB
5	00h	Data length LSB (GET command = no data)
6	00h	Data length MSB
7	0Ah	Check sum LSB
8	00h	Check sum MSB
9	0Dh	Packet end 1
10	0Ah	Packet end 2

Reply data (SENSOR -> HOST)

Packet byte no.	Content	Meaning
0	3Ah	Packet start
1	01h	OpenMAT ID LSB (ID = 1)
2	00h	OpenMAT ID MSB
3	09h	Command no. LSB (9d = GET_SENSOR_DATA)
4	00h	Command no. MSB
5	34h	Data length LSB (56 bytes)
6	00h	Data length MSB
7-10	xxxxxxxxh	Timestamp
11-14	xxxxxxxxh	Gyroscope data x-axis
15-18	xxxxxxxxh	Gyroscope data y-axis
19-22	xxxxxxxxh	Gyroscope data z-axis
23-26	xxxxxxxxh	Accelerometer x-axis
27-30	xxxxxxxxh	Accelerometer y-axis
31-34	xxxxxxxxh	Accelerometer z-axis
35-38	xxxxxxxxh	Magnetometer x-axis
39-42	xxxxxxxxh	Magnetometer y-axis
43-46	xxxxxxxxh	Magnetometer z-axis

47-50	xxxxxxxxxh	Orientation quaternion q0
51-54	xxxxxxxxxh	Orientation quaternion q1
55-58	xxxxxxxxxh	Orientation quaternion q2
59-62	xxxxxxxxxh	Orientation quaternion q3
63	xxh	Check sum LSB
64	xxh	Check sum MSB
65	0Dh	Message end byte 1
66	0Ah	Message end byte 2

xx = Value depends on the current configuration and measurement value.

VIII. OpenMAT LIBRARY

Overview

Introduction

The OpenMAT (Open motion analysis toolkit) is the software package delivered with an LPMS device. The package contains the basic hardware device drivers for the sensors, a C++ library to easily access the functionality of the IMUs and various other examples and utility programs. Except for our proprietary algorithms the library is open-source. This includes the firmware of the LPMS devices. OpenMAT consists of the following components:

Core applications

LpSensor: The core library to manage communication with LPMS devices

LpmsControl: An application to control and use LPMS devices

Programming examples

LpmsSimpleExample: A simple example on how to use the LpSensor library

OpenMAT is available as binary release and as source code release. If you would like to use the included applications in their original form, please use the binary release. This is suggested as the easiest way to start because it allows you to easily test the functionality of your sensor. The source code of OpenMAT is available from the LP-RESEARCH Bitbucket repository: `https://bitbucket.org/lpresearch/openmat`

Application Installation under Windows

Please follow the steps below to install an OpenMAT binary release under Windows. The binary release includes the OpenMAT API pre-compiled for Windows 32-bit.

1. Download the latest OpenMAT installer from `http://www.lp-research.com/support/`
2. Start OpenMAT-x.x.x-Setup.exe (x.x.x being the latest version number)
3. Follow the displayed installation instructions

LpmsControl Software Operation

Overview

The LpmsControl application allows users to control various aspects of an LPMS device.In particular the application has the following core functionality:

- List all LPMS devices connected to the system
- Connect to up to 256 sensors simultaneously
- Adjust all sensor parameters (sensor range etc.).
- Set orientation offsets
- Initiate accelerometer, gyroscope and magnetometer calibration.
- Display the acquired data in real-time either as line graphs or a 3D image
- Record data from the sensors to a CSV data file
- Play back data from a previously recorded CSV file
- Upload new firmware and in-application-programming software to the sensor

GUI Elements

Toolbar Items

The key functionality of LpmsControl can be accessed via the toolbar. See an overview of the toolbar in Figure 7, Figure 8, Figure 9 and Figure 10.

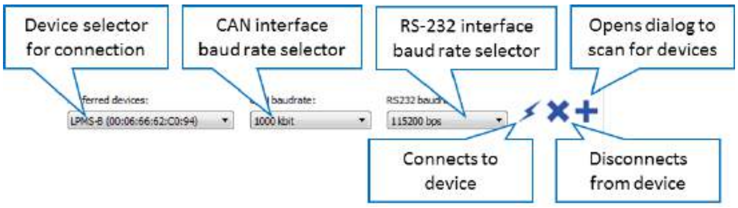

Figure 7 - Connection toolbar

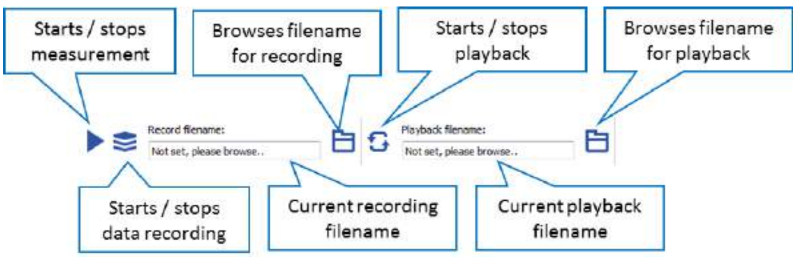

Figure 8 - Recording and playback toolbar

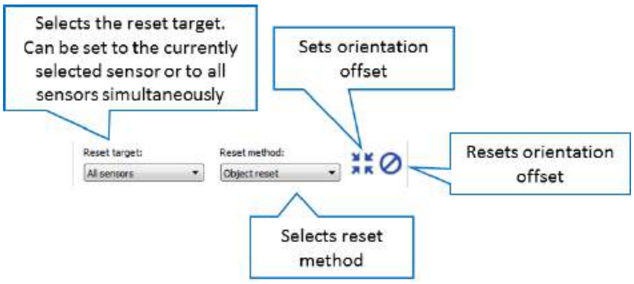

Figure 9 - Orientation offset toolbar

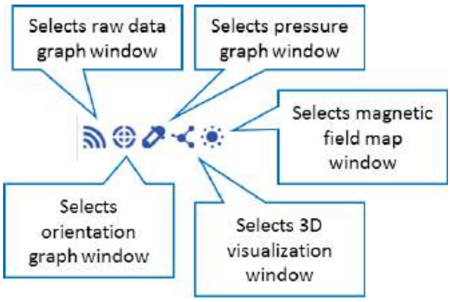

Figure 10 - Window selector

Menu Items

Menu title	Menu item	Operation
Connect menu		
	Connect	Connects to sensor selected in "Preferred devices" list
	Disconnect	Disconnects sensor currently selected in "Connected devices" list
	Add / remove sensor	Opens "Scan devices" dialog
	Exit program	Exits the application
Measurement menu		
	Stop measurement	Toggles measurement
	Browse record file	Opens browser for selectinga file for data recording
	Record data	Togglesdata recording

	Browse replay file	Opens browser for selecting a playback file
	Playback data	Starts data playback
Calibration menu		
	Calibrate gyroscope	Starts manual gyroscope calibration
	Calibrate mag. (ellipsoid fit)	Starts magnetometer calibration wizard for ellipsoid fit calibration
	Calibrate mag. (min/max fit)	Starts magnetometer calibration wizard for min/max fit calibration
	Save parameters to sensor	Saves parameters to sensor flash memory
	Save calibrationfile	Saves file with calibration data
	Load calibrationfile	Loads file with calibration data
	Set offset	Sets sensor orientation offset (depending on "Reset target" and "Reset method")
	Reset offset	Resets sensor orientation offset (depending on "Reset target")
	Arm timestamp reset	Arms hardware timestamp reset
	Software Sync Start	Starts software sync routine
	Software Sync Stop	Stops software sync routine
	Reset to factory settings	Resets sensor settings to factory default
View		
	Graph window	Selects raw data graph window
	Orientation window	Selects orientation graph window

	Pressure window	Selects pressure graph window
	3D visualization	Selects 3D visualization window
	3D view mode 1	Selects view mode 1
	3D view mode 2	Selects view mode 2
	3D view mode 4	Selects view mode 4
	Load object file	Loads 3D OBJ file
Advanced		
	Upload firmware	Uploads firmware file
	Upload IAP	Uploads in-application-programmer file
	Start self test	Starts self-test
	Calibrate acc. misalignment	Starts accelerometer calibration wizard
	Calibrate gyr. misalignment	Starts gyroscope calibration wizard
	Calibrate mag. misalignment (HH-coils)	Starts magnetometer calibration wizard (Helmholtz coils mode)
	Calibrate mag. misalignment (auto)	Starts magnetometer calibration wizard (automatic mode)
	Version info	Displays version information dialog

Connected Devices List

Devices connected to the system are shown in the Connected devices list. Through this list each sensor parameter can be adjusted according to the table below.

Top level item	**Parameter item**	**Description**
Status		
	Connection	Displays the current connection status OK: Connection successful In progress: Currently connecting Failed: Connection failed
	Sensor status	Displays the current sensor status Started: Sensor measurement is running Stopped: Sensor measurement stopped
	Device ID	Current device ID
	Firmware version	Firmware version
ID / sampling rate		
	IMU ID	Selects OpenMAT ID
	Transmission rate	Selects data transmission rate
Range		
	GYR range	Selects gyroscope range
	ACC range	Selects accelerometer range
	MAG range	Selects magnetometer range
Filter		
	Filter mode	Selects filter mode
	MAG correction	Selects magnetometer correction mode
	Lin. ACC correction	Selects linear acceleration correction mode
	Rot. ACC correction	Selects centripetal acceleration correction
	GYR threshold	Selects gyroscope threshold
	GYR auto calibration	Selects auto-calibration setting
	Low-pass filter	Selects low-pass filter setting
Data		
	LPBUS data mode	Switches between 16-bit integer or 32-bit floating point mode
	Enabled data	Selects data to be enabled for transmission from the sensor

NOTE: Parameter adjustments are normally only persistent until the sensor is switched off. You can permanently save the newly adjusted parameters to the LPMS flash memory by selecting Save parameters to sensor in the Calibration menu of LpmsControl.

Scanning, Discovering and Saving Devices

Discovering devices, especially Bluetooth devices, can be quite time-consuming. Therefore LpmsControl allows scanning for devices once and then saves the device identification in a list of preferred devices. Figure 11 shows the device discovery dialog. To add a device to the preferred devices list, please follow the steps below:

1. Click "Scan devices" and wait until the scanning process is finished.
2. Select the target device from the discovered devices list
3. Click "Add device" to add the device to the Preferred devices list
4. Click Save devices to save the list of preferred devices

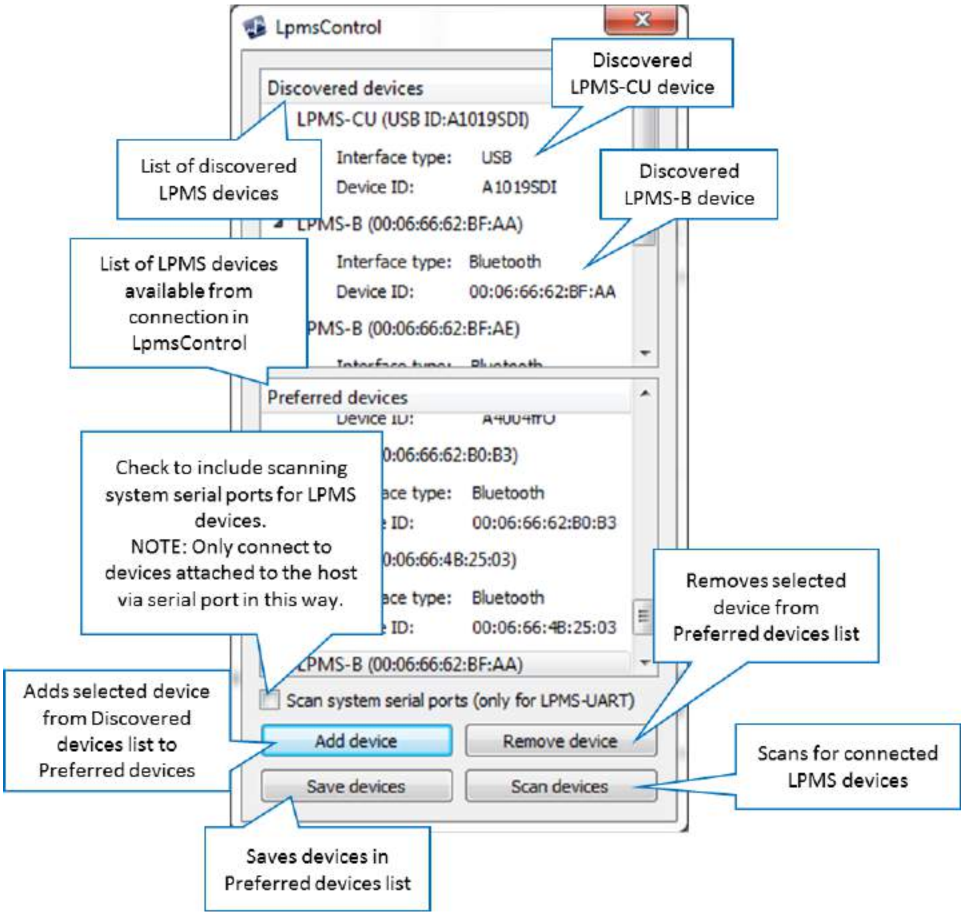

Figure 11 - Discover devices dialog

Connecting and Disconnecting a Device

To connect to an LPMS device, please follow the steps below.

1. Select device to connect to in "Preferred devices" dropdown list.
2. Click "Connect" button.
3. Sensor status should now be "Connecting..".
4. Connection establishment should take between 2 and 5 seconds.

If the connection is successful the sensor status should switch to "Connected". The sensor will start measuring automatically after connecting. Should the connection procedure fail for some reason, Failed will be displayed. If a successful connection is interrupted the connection status will change to "Connection interrupted".

NOTE: Please make sure that you have no 3rd party Bluetooth driver (Toshiba, Bluesoleil etc.) installed on your system. LpmsControl uses the native Windows Bluetooth driver and any other driver will block communication with the native Windows driver. The Windows Bluetooth pairing functionality will be automatically started when connecting to the sensor from LpmsControl. A PIN code should not be required for connecting with the LPMS.

Recording and Playing Back Data

LpmsControl allows recording and playback of sensor data. Recorded data is saved in a CSV format that can be easily processed by Excel, MATLAB etc. Saved files can be loaded into LpmsControl and played back. At the moment only playback of the sensor with the lowest OpenMAT ID in the file is possible. To start data recording please follow the steps below:

1. Select "Measurement" ->"Browse record file" and choose a filename that you would like to record to.
2. Start the recording by selecting "Measurement -> Record" data.
3. Once you have collected enough data stop the recording by selecting "Measurement" ->"Stop recording".

To replay a data file do the following:

1. Select "Measurement" ->"Browse replay" file and select a file that you would like to replay.
2. Start replay by selecting "Measurement" ->"Replay data".
3. Replay will loop automatically. Once you would like to stop replay select "Measurement" ->"Stop replay data".

Switching View Modes

LpmsControl can visualize sensor orientation data either as data graphs or as 3D representation. In 3D view mode the orientation of the sensor is shown as a 3D cube. Up to 4 sensors can be shown simultaneously in one window. In this multi-view mode, which sensors are visualized can be adjusted by assigning an IMU ID to each window (see Figure 12).

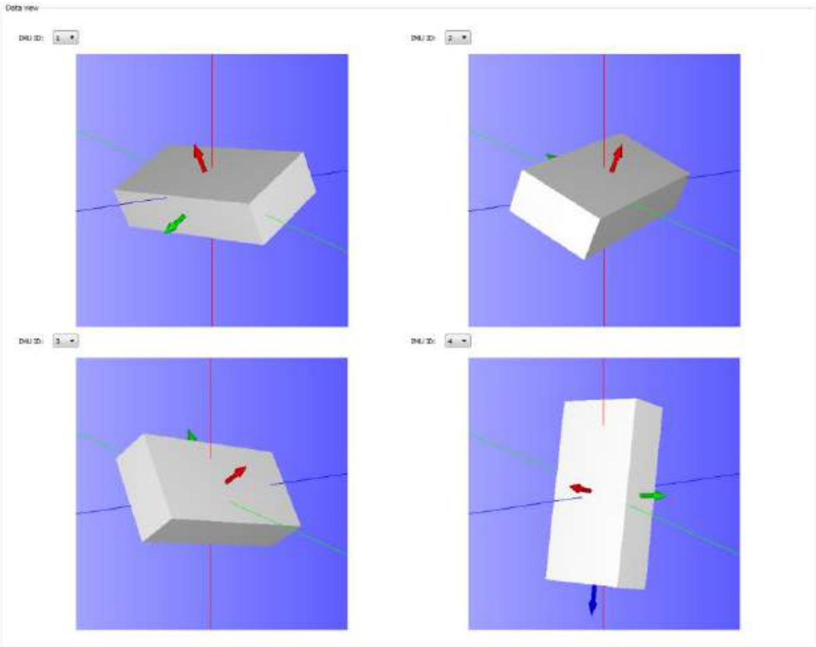

Figure 12 - Viewing the orientation of 4 connected LPMS at the same time

By selecting Load object file from the View menu, custom 3D data can be loaded into LpmsControl as shown in Figure 13.

NOTE: LpmsControl so far only supports the OBJ file format for loading 3D CAD files. We recommend exporting files in this format from the open-source 3D visualizer Meshlab: `http://meshlab.sourceforge.net/`

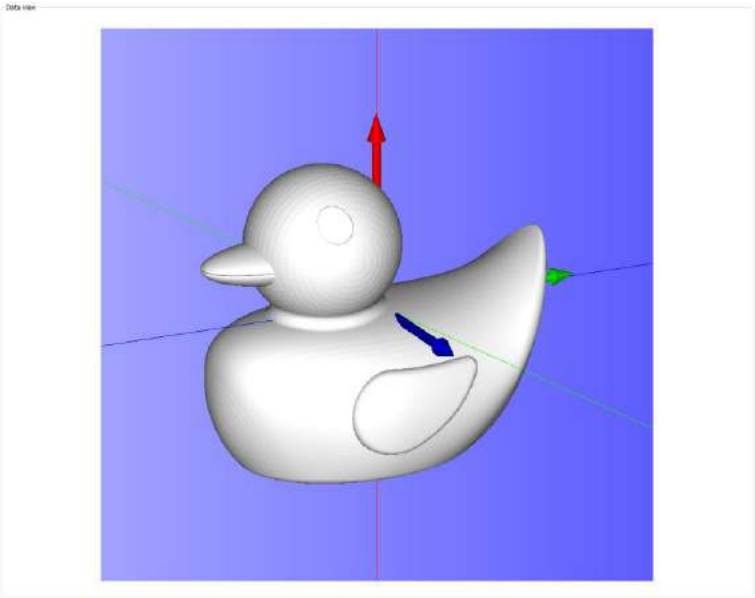

Figure 13 - Custom 3D OBJ data can be loaded into the visualization window

Uploading New Firmware

Please follow the following steps carefully when you are updating the sensor firmware. Invalid operation might result in an incomplete firmware update and brick the sensor.

1. Start your current LpmsControl software.
2. Connect to the sensor you would like to update.
3. Choose the “Save parameters to file” function from the “Calibration” menu of LpmsControl to save the current sensor calibration results into a .txt file on your local host system.
4. Select Upload firmware function in the “Advanced” menu.
5. Click OK and select the new firmware file. Be careful that you select the right file which should be named as LpmsXFirmwareX.X.X.bin (with X being the sensor type identifier and firmware version).
6. Wait for the upload process to finish. It should take around 30 seconds. At around 15s the green LED on the sensor should begin to blink rapidly (~10 Hz).
7. Disconnect from the sensor and exit LpmsControl.
8. Now install the new LpmsControl application. The previous LpmsControl application does not need to be un-installed.
9. Start LpmsControl and connect to your sensor.
10. Choose the “Load parameters fromfile” function from the “Calibration” menu of LpmsControl to recover the previous sensor calibration results.

11. Choose the “Save parameters”tosensor function from the calibration menu of LpmsControl to save the previous sensor calibration results into sensor flash.
12. The update is finished. Make sure everything works as expected.

The LpSensor Library

Building Your Application

The LpSensor library contains classes that allow a user to integrate LPMS devices into their own applications. **The standard library is a Windows 32-bit C++ library for MS Visual C++ (express) 2013.** Should you require a binary of the library to work on another operating system or 64-bit applications, please contact LP-RESEARCH.

Compiling applications that use the LpSensor library requires the following components:

Header files (usually in `C:/OpenMAT/include`):

LpmsSensorManagerI.h	Contains the interface for the LpmsSensorManager class.
LpmsSensorI.h	Contains the interface for the LpmsSensor class
ImuData.h	Structure for containing output data from a LPMS device
LpmsDefinitions.h	Macro definitions for accessing LPMS
DeviceListItem.h	Contains the class definition for an element of a LPMS device list

LIB files (usually in `C:/OpenMAT/lib/x86`):

LpSensorD.lib	LpSensor library (Debug version)
LpSensor.lib	LpSensor library (Release version)

DLL files (usually in `C:/OpenMAT/lib/x86`):

LpSensorD.dll	LpSensor library (Debug version)
LpSensor.dll	LpSensor library (Release version)
PCANBasic.dll	PeakCAN library DLL for CAN interface communication (optional).
ftd2xx.dll	The FTDI library to communicate with an LPMS over USB.

To compile the application please do the following:

1. Include LpmsSensorManagerI.h.
2. Add LpSensor.lib (or LpSensorD.lib if you are compiling in debug mode) to the link libraries file list of your application
3. Make sure that you set a path to LpSensor.dll / LpSensorD.dll, PCANBasic.dll (optional) and

ftd2xx.dll so that the runtime file of your application can access them.

4. Build your application.

Important Classes

SensorManager

The sensor manager class wraps a number of LpmsSensor instances into one class, handles device discovery and device polling. For user applications the following methods are most commonly used. Please refer to the interface file SensorManagerI.h for more information.

NOTE: An instance of LpmsSensor is returned by the static function **LpmsSensorManagerFactory()**. See the example listing in the next section for more information how to initialize an LpmsSensorManager object.

Method name	`SensorManager(void)`
Parameters	none
Returns	SensorManager object
Description	Constructor of a SensorManager object.

<table>
<tr><td>Method name</td><td colspan="2"><code>LpSensor* addSensor(int mode, string deviceId)</code></td></tr>
<tr><td rowspan="2">Parameters</td><td>mode</td><td>The device type to be connected. The following device types are available:
<table>
<tr><th>Macro</th><th>Device type</th></tr>
<tr><td>DEVICE_LPMS_B</td><td>LPMS-B</td></tr>
<tr><td>DEVICE_LPMS_C</td><td>LPMS-CU (CAN mode)</td></tr>
<tr><td>DEVICE_LPMS_U</td><td>LPMS-CU (USB mode)</td></tr>
</table></td></tr>
<tr><td>deviceId</td><td>Device ID of the LPMS device. The ID is equal to the OpenMAT ID (initially set to 1, user definable).</td></tr>
<tr><td>Returns</td><td colspan="2">Pointer to LpSensor object.</td></tr>
<tr><td>Description</td><td colspan="2">Adds a sensor device to the list of devices adminstered by the SensorManager object.</td></tr>
</table>

Method name	`void removeSensor(LpSensor *sensor)`	
Parameters	**sensor**	Pointer to LpSensor object that is to be removed from the list of sensors. The call to removeSensor frees the memory associated with the LpSensor object.

Returns	none
Description	Removes a device from the list of currently administered sensors.

Method name	**void listDevices(std::vector<DeviceListItem> *v)**	
Parameters	***v**	Pointer to a vector containing DeviceListItem objects with information about LPMS devices that have been discovered by the method.
Returns	None	
Description	Lists all connected LPMS devices. The device discovery runs in a seperate thread.For Bluetooth devices should take several seconds to be added to the devicelist. CAN bus and USB devices should be added after around 1s.	

LpmsSensor

This is a class to access the specific functions and parameters of an LPMS. The most commonly used methods are listed below. Please refer to the interface file LpmSensorI.h for more information.

Method name	**void run(void)**
Parameters	None
Returns	None
Description	Starts the data acquisition procedure.

Method name	**void pause(void)**
Parameters	None
Returns	None
Description	Pauses the data acquisition procedure.

Method name	**int getSensorStatus(void)**	
Parameters	None	
Returns	Sensor state identifier:	
	Macro	**Sensor state**
	SENSOR_STATUS_PAUSED	Sensor is currently paused.
	SENSOR_STATUS_RUNNING	Sensor is currently acquiring data.
	SENSOR_STATUS_CALIBRATING	Sensor is currently calibrating.

	SENSOR_STATUS_ERROR	Sensor has detected an error.
	SENSOR_STATUS_UPLOADING	Sensor is currently receiving new firmware data.
Description	Retrieves the current sensor status.	

Method name	**`int getConnectionStatus(void)`**	
Parameters	None	
Returns	Connection status identifier:	
	Macro	**Sensor state**
	SENSOR_CONNECTION_CONNECTED	Sensor is connected.
	SENSOR_CONNECTION_CONNECTING	Connection is currently being established.
	SENSOR_CONNECTION_FAILED	Attempt to connect has failed.
	SENSOR_CONNECTION_INTERRUPTED	Connection has been interrupted.
Description	Retrieves the current connection status.	

Method name	**`void startResetReference(void)`**
Parameters	None
Returns	None
Description	Resets the current accelerometer and magnetometer reference. Please see the ‘Operation’ chapter for details on the reference vector adjustment procedure.

Method name	**`void startCalibrateGyro(void)`**
Parameters	None
Returns	None
Description	Starts the calibration of the sensor gyroscope.

Method name	**`void startMagCalibration(void)`**
Parameters	None
Returns	None
Description	Starts the calibration of the LPMS magnetometer.

Method name	**`CalibrationData* getConfigurationData(void)`**
Parameters	None
Returns	Pointer to CalibrationData object.
Description	Retrieves the CalibrationData structure containing theconfigurationparameters ofthe connected LPMS.

Method name	**`bool setConfigurationPrm(int parameterIndex, int parameter)`**
Parameters	**parameterIndex** The parameter to be adjusted. **parameter** The new parameter value. Supported parameterIndex identifiers: **Macro** — **Description** `PRM_OPENMAT_ID` — Sets the current OpenMAT ID. `PRM_FILTER_MODE` — Sets the current filter mode. `PRM_PARAMETER_SET` — Changes the current filter preset. `PRM_GYR_THRESHOLD_ENABLE` — Enables / diables the gyroscope threshold. `PRM_MAG_RANGE` — Modifies the current magnetometer sensor range. `PRM_ACC_RANGE` — Modifies the current accelerometer sensor range. `PRM_GYR_RANGE` — Modifies the current gyroscope range. Supported parameter identifiers for each parameter index: **`PRM_OPENMAT_ID`** `Integer ID number between 1 and 255.` **`PRM_FILTER_MODE`** **Macro** — **Description** `FM_GYRO_ONLY` — Only gyroscope `FM_GYRO_ACC` — Gyroscope + accelerometer `FM_GYRO_ACC_MAG_NS` — Gyroscope + accelerometer + magnetometer

	PRM_PARAMETER_SET

Macro	Description
LPMS_FILTER_PRM_SET_1	Magnetometer correction “dynamic” setting.
LPMS_FILTER_PRM_SET_2	Strong
LPMS_FILTER_PRM_SET_3	Medium
LPMS_FILTER_PRM_SET_4	Weak

PRM_GYR_THRESHOLD_ENABLE

Macro	Description
IMU_GYR_THRESH_DISABLE	Enable gyr. threshold
IMU_GYR_THRESH_ENABLE	Disable gyr. thershold

PRM_GYR_RANGE

Macro	Description
GYR_RANGE_250DPS	Gyr. Range = 250 deg./s
GYR_RANGE_500DPS	Gyr. Range = 500 deg./s
GYR_RANGE_2000DPS	Gyr. Range = 2000 deg./s

PRM_ACC_RANGE

Macro	Description
ACC_RANGE_2G	Acc. range = 2g
ACC_RANGE_4G	Acc. range = 4g
ACC_RANGE_8G	Acc. range = 8g
ACC_RANGE_16G	Acc. range = 16g

PRM_MAG_RANGE

Macro	Description
MAG_RANGE_4GAUSS	Mag. range = 4 Gauss
MAG_RANGE_8GAUSS	Mag. range = 8 Gauss
MAG_RANGE_12GAUSS	Mag. range = 12 Gauss
MAG_RANGE_16GAUSS	Mag. range = 16 Gauss

Returns	None
Description	Sets a configuration parameter.

Method name	`bool getConfigurationPrm(int parameterIndex, int *parameter)`
Parameters	**parameterIndex** The parameter to be adjusted. **parameter** Pointer to the retrieved parameter value. See setConfigurationPrm method for an explanation of supported paramer indices and parameters.
Returns	None
Description	Retrieves a configuration parameter.

Method name	`void resetOrientation(void)`
Parameters	None
Returns	None
Description	Resets the orientation offset of the sensor.

Method name	`void saveCalibrationData(void)`
Parameters	None
Returns	None
Description	Starts saving the current parameter settings to the sensor flash memory.

Method name	`virtual void getCalibratedSensorData(float g[3], float a[3], float b[3])`
Parameters	**g[0..2]** Calibrated gyroscope data (x, y, z-axis). **a[0..2]** Calibrated accelerometer data (x, y, z-axis). **b[0..2]** Calibrated magnetometer data (x, y, z-axis).
Returns	None
Description	Retrieves calibrated sensor data (gyroscope, accelerometer, magnetometer).

Method name	`virtual void getQuaternion(float q[4])`
Parameters	**q[0..3]** Orientation quaternion (qw, qx, qy, qz)
Returns	None
Description	Retrieves the 3d orientation quaternion.

Method name	`virtual void getEulerAngle(float r[3])`
Parameters	**r[0..2]** Euler angle vector (around x, y, z-axis)

Returns	None
Description	Retrieves the currently measured 3d Euler angles.

Method name	**`virtual void getRotationMatrix(float M[3][3])`**
Parameters	**M[0..2][0..2]** Rotations matrix (row i=0..2, column j=0..2)
Returns	None
Description	Retrievs the current rotation matrix.

Example Code (C++)

Connecting to the an LPMS device

```
#include "stdio.h"

#include "LpmsSensorI.h"
#include "LpmsSensorManagerI.h"

int main(int argc, char *argv[])
{
	ImuData d;

	// Gets a LpmsSensorManager instance
	LpmsSensorManagerI* manager = LpmsSensorManagerFactory();

	// Connects to LPMS-B sensor with address 00:11:22:33:44:55
	LpmsSensorI* lpms = manager->addSensor(DEVICE_LPMS_B, "00:11:22:33:44:55");

	while(1) {
		// Checks, if conncted
		if (lpms->getConnectionStatus() == SENSOR_CONNECTION_CONNECTED) {

			// Reads quaternion data
			d = lpms->getCurrentData();

			// Shows data
			printf("Timestamp=%f, qW=%f, qX=%f, qY=%f, qZ=%f¥n", d.timeStamp,
			d.q[0], d.q[1], d.q[2], d.q[3]);
		}
```

```
        }

        // Removes the initialized sensor
        manager->removeSensor(lpms);

        // Deletes LpmsSensorManager object
        delete manager;

        return 0;
}
```

Setting and Retrieval of Sensor Parameters

```
/* Setting a sensor parameter. */
lpmsDevice->setParameter(PRM_ACC_RANGE, LPMS_ACC_RANGE_8G);

/* Retrieving a sensor parameter. */
lpmsDevice->setParameter(PRM_ACC_RANGE, &p);
```

Sensor and Connection Status Inquiry

```
/* Retrieves current sensor status */
int status = getSensorStatus();

switch (status) {
case SENSOR_STATUS_RUNNING:
        std::cout << "Sensor is running." << std::endl;
break;

case SENSOR_STATUS_PAUSED:
        std::cout << "Sensor is paused." << std::endl;
break;
}

status = lpmsDevice->getConnectionStatus();

switch (status) {
case SENSOR_CONNECTION_CONNECTING:
```

```
        std::cout << "Sensor is currently connecting." << std::endl;
break;

case SENSOR_CONNECTION_CONNECTED:
        std::cout << "Sensor is connected." << std::endl;
break;
}
```

IX. APPENDIX

Appendix A –COMMON CONVERSION ROUTINES

Conversion Quaternion to Matrix

```
typedef struct _LpVector3f {
        float data[3];
} LpVector3f;

typedef struct _LpVector4f {
        float data[4];
} LpVector4f;

typedef struct _LpMatrix3x3f {
        float data[3][3];
} LpMatrix3x3f;

void quaternionToMatrix(LpVector4f *q, LpMatrix3x3f* M)
{
        float tmp1;
        float tmp2;

        float sqw = q->data[0] * q->data[0];
        float sqx = q->data[1] * q->data[1];
        float sqy = q->data[2] * q->data[2];
        float sqz = q->data[3] * q->data[3];

        float invs = 1 / (sqx + sqy + sqz + sqw);

        M->data[0][0] = ( sqx - sqy - sqz + sqw) * invs;
        M->data[1][1] = (-sqx + sqy - sqz + sqw) * invs;
        M->data[2][2] = (-sqx - sqy + sqz + sqw) * invs;

        tmp1 = q->data[1] * q->data[2];
        tmp2 = q->data[3] * q->data[0];

        M->data[1][0] = 2.0f * (tmp1 + tmp2) * invs;
```

```
        M->data[0][1] = 2.0f * (tmp1 - tmp2) * invs;

        tmp1 = q->data[1] * q->data[3];
        tmp2 = q->data[2] * q->data[0];

        M->data[2][0] = 2.0f * (tmp1 - tmp2) * invs;
        M->data[0][2] = 2.0f * (tmp1 + tmp2) * invs;

        tmp1 = q->data[2] * q->data[3];
        tmp2 = q->data[1] * q->data[0];

        M->data[2][1] = 2.0f * (tmp1 + tmp2) * invs;
        M->data[1][2] = 2.0f * (tmp1 - tmp2) * invs;
}
```

Conversion Quaternion to Euler Angles (ZYX rotation sequence)

```
void quaternionToEuler(LpVector4f *q, LpVector3f *r)
{
        // ZYX Rotation sequence
        const float r2d = 57.2958f;
        float w = q->data[0];
        float x = q->data[1];
        float y = q->data[2];
        float z = q->data[3];

        float r11 = 2 * (x*y + w*z);
        float r12 = w*w + x*x - y*y - z*z;
        float r21 = -2 * (x*z - w*y);
        float r31 = 2 * (y*z + w*x);
        float r32 = w*w - x*x - y*y + z*z;

        r->data[2] = (float)atan2(r11, r12) * r2d;
        r->data[1] = (float)asin(r21) * r2d;
        r->data[0] = (float)atan2(r31, r32) * r2d;
}
```

Appendix B – LPBUS Protocol Command List

Acknowledged and Not-acknowledged Identifiers

Identifier: 0

Name: REPLY_ACK

Description: Confirms a successful SET command.

Identifier: 1

Name: REPLY_NACK

Description: Reports an error during processing a SET command.

Firmware Update and In-Application-Programmer Upload Commands

Identifier: 2

Name: UPDATE_FIRMWARE

Description: Start the firmware update process.

NOTE: By not correctly uploading a firmware file the sensor might become in-operable. Please only use authorized firmware packages.

Packet data: Firmware data

Data format: Firmware binary file separated into 256 byte chunks for each update packet.

Response: ACK (success) or NACK (error) for each transmitted packet.

Identifier: 3

Name: UPDATE_IAP

Description: Start the in-application programmer (IAP) update process.

Packet data: IAP data

Data format: IAP binary file separated into 256 byte chunks for each update packet.

Response: ACK (success) or NACK (error) for each transmitted packet.

Configuration and Status Commands

Identifier: 4

Name: GET_CONFIG

Description: Get the current value of the configuration register of the sensor. The configuration word is read-only. The different parameters are set by their respective SET commands. E.g. SET_TRANSMIT_DATA for defining which data is transmitted from the sensor.

Packet data: Configuration word. Each bit represents the state of one configuration parameter.

Data format: 32-bit integer

Bit	Reported State / Parameter
0 - 2	Stream frequency setting (see SET_STREAM_FREQ)
3 - 8	Reserved
9	Pressure data transmission enabled (optional)
10	Magnetometer data transmission enabled
11	Accelerometer data transmission enabled
12	Gyroscope data transmission enabled
13	Temperature output enabled (optional)
14	Heave motion output enabled (optional)
15	Reserved
16	Angular velocity output enabled
17	Euler angle data transmission enabled
18	Quaternion orientation output enabled
19	Altitude output enabled (optional)
20	Dynamic magnetometer correction enabled
21	Linear acceleration output enabled
22	16-bit data output mode enabled
23	Gyroscope threshold enabled
24	Magnetometer compensation enabled
25	Accelerometer compensation enabled
26	Reserved
27	Reserved
28	Reserved
29	Reserved
30	Gyroscope auto-calibration enabled
31	Reserved

Identifier: 5

Name: GET_STATUS

Description: Get the current value of the status register of the LPMS device. The status word is read-only.

Packet data: Status indicator. Each bit represents the state of one status parameter.

Data format: 32-bit integer

Bit	Indicated state
0	COMMAND mode enabled
1	STREAM mode enabled
2	Reserved
3	Gyroscope calibration on
4	Reserved
5	Gyroscope initialization failed
6	Accelerometer initialization failed
7	Magnetometer initialization failed
8	Pressure sensor initialization failed
9	Gyroscope unresponsive
10	Accelerometer unresponsive
11	Magnetometer unresponsive
12	Flash write failed
13	Reserved
14	Set streaming frequency failed
15-31	reserved

Mode Switching Commands

Identifier: 6

Name: GOTO_COMMAND_MODE

Description: Switch to command mode. In command mode the user can issue commands to the firmware to perform calibration, set parameters etc.

Response: ACK (success) or NACK (error)

Identifier: 7

Name: GOTO_STREAM_MODE

Description: Switch to streaming mode. In this mode data is continuously streamed from

	the sensor,and all other commands cannot be performed until the sensor receives the GOTO_COMMAND_MODE command.
Response:	ACK (success) or NACK (error)

Data Transmission Commands

Identifier:	9
Name:	GET_SENSOR_DATA
Description:	Retrieves the latest set of sensor data.A data packet will be composed as defined by SET_TRANSMIT_DATA. The currently set format can be retrieved with the sensor configuration word.
Data format:	See the LPBUS protocol explanation for a description of the measurement data format.

Identifier:	10
Name:	SET_TRANSMIT_DATA
Description:	Set the data that is transmitted from the sensor in streaming mode or when retrieving data through the GET_SENSOR_DATA command.
Packet data:	Data selection indicator
Data format:	32-bit integer.

Bit	Reported State / Parameter
9	Pressure data transmission enabled
10	Magnetometer data transmission enabled
11	Accelerometer data transmission enabled
12	Gyroscope data transmission enabled
13	Temperature output enabled
14	Heave motion output enabled
16	Angular velocity output enabled
17	Euler angle data transmission enabled
18	Quaternion orientation output enabled
19	Altitude output enabled
21	Linear acceleration output enabled

Response:	ACK (success) or NACK (error)

Identifier: 11

Name: SET_STREAM_FREQ

Description: Set the timing in which streaming data is sent to the host. Please note that high frequencies might be not practically applicable due to limitations of the communication interface. Check the current baudrate before setting this parameter.

Packet data: Update frequency identifier

Data format: 32-bit integer

Frequency (Hz)	Identifier
5	5
10	10
25	25
50	50
100	100
200	200
400	400

Response: ACK (success) or NACK (error)

Identifier: 75

Name: SET_LPBUS_DATA_MODE

Description: Sets current data mode for LP-BUS (binary) output.

Packet data: Data mode identifier

Data format: Int32

Data mode	Identifier
32-bit float	0
16-bit integer	1

Response: ACK (success) or NACK (error)

Identifier: 66

Name: RESET_TIMESTAMP

Description: Sets current sensor timestamp

Packet data: Timestamp data (in timestamp counter units, 400 counts == 1s)

Data format: Int32

Response: ACK (success) or NACK (error)

Identifier: 83

Name: SET_ARM_HARDWARE_TIMESTAMP_RESET

Description: Arms hardware timestamp reset

Packet data: None

Response: ACK (success) or NACK (error)

Register Value Save and Reset Command

Identifier: 15

Name: WRITE_REGISTERS

Description: Write the currently set parameters to flash memory.

Response: ACK (success) or NACK (error)

Identifier: 16

Name: RESTORE_FACTORY_VALUE

Description: Reset the LPMS parameters to factory default values. Please note that upon issuing this command your currently set parameters will be erased.

Response: ACK (success) or NACK (error)

Reference Setting and Offset Reset Command

Identifier: 18

Name: SET_OFFSET

Description: Sets the orientation offset using one of the three offset methods.

Orientation offset mode

Mode	Value
Object reset	0
Heading reset	1
Alignment reset	2

Packet data:

Data format:

Response: ACK (success) or NACK (error)

Identifier: 82

Name: RESET_ORIENTATION_OFFSET

Description: Reset the orientation offset to 0 (unity quaternion).

Response: ACK (success) or NACK (error)

Self-Test Command

Identifier: 19

Name: SELF_TEST

Description: Initiate the self-test. During the self test the sensor automatically rotates about the three room axes. To simulate realistic circumstances an artificial offset is applied to the magnetometer and the gyroscope values.

Response: ACK (success) or NACK (error)

IMU ID Setting Command

Identifier: 20

Name: SET_IMU_ID

Description: Set the OpenMAT ID.

Packet data: OpenMAT ID

Data format: 32-bit integer

Response: ACK (success) or NACK (error)

Identifier: 21

Name: GET_IMU_ID

Description: Get the ID (OpenMAT ID) of the device.

Packet data: The ID of the IMU device

Return format: 32-bit integer

Gyroscope Settings Command

Identifier: 22

Name: START_GYR_CALIBRATION

Description: Start the calibration of the gyroscope sensor.

Response: ACK (success) or NACK (error)

Identifier: 23

Name: ENABLE_GYR_AUTOCAL

Description: Enable or disable auto-calibration of the gyroscope.

Packet data: Gyroscope auto-calibration enable / disable identifier

Format: 32-bit integer

State	Value
Disable	0x00000000
Enable	0x00000001

Response: ACK (success) or NACK (error)

Identifier: 24

Name: ENABLE_GYR_THRES

Description: Enable or disable gyroscope threshold.

Packet data: Gyroscope threshold enable / disable identifier

Format: 32-bit integer

State	Value
Disable	0x00000000
Enable	0x00000001

Response: ACK (success) or NACK (error)

Identifier: 25

Name: SET_GYR_RANGE

Description: Set the current range of the gyroscope.

Packet data: Gyroscope range identifier

Format: 32-bit integer

Range (deg/s)	Identifier
250	250
500	500
2000	2000

Response:

ACK (success) or NACK (error)

Identifier: 26
Name: GET_GYR_RANGE
Description: Get current gyroscope range.
Response: Gyroscope range indicator
Return format: 32-bit integer

Identifier: 48
Name: SET_GYR_ALIGN_BIAS
Description: Set gyroscope alignment bias.
Packet data: Gyroscope alignment bias
Format: Float 3-vector
Response: ACK (success) or NACK (error)

Identifier: 49
Name: GET_GYR_ALIGN_BIAS
Description: Get gyroscope alignment bias.
Response: Gyroscope alignment bias
Return format: Float 3-vector

Identifier: 50
Name: GET_GYR_ALIGN_MATRIX
Description: Set gyroscope alignment matrix.
Packet data: Gyroscope alignment matrix
Format: Float 3x3 matrix
Response: ACK (success) or NACK (error)

Identifier: 51
Name: GET_GYR_ALIGN_MATRIX
Description: Get gyroscope alignment matrix.

Response: Gyroscope alignment matrix

Return format: Float 3x3 matrix

Accelerometer Settings Command

Identifier: 27

Name: SET_ACC_BIAS

Description: Set the accelerometer bias.

Packet data: Accelerometer bias (X, Y, Z-axis)

Format: 32-bit integer encoded float 3-component vector

Response: ACK (success) or NACK (error)

Identifier: 28

Name: GET_ACC_BIAS

Description: Get the current accelerometer bias vector.

Response: Accelerometer bias vector

Return format: 32-bit integer encoded float 3-component vector

---

Identifier: 29

Name: SET_ACC_ALIG

Description: Set the accelerometer alignment matrix.

Packet data: Alignment matrix

Format: 32-bit integer encoded float 3 x 3 matrix

Response: ACK (success) or NACK (error)

Identifier: 30

Name: GET_ACC_ALIG

Description: Get the current accelerometer alignment matrix.

Response: Accelerometer alignment matrix

Return format: 32-bit integer encoded float 3 x 3 matrix

Identifier: 31

Name: SET_ACC_RANGE

Description: Set the current range of the accelerometer.

Packet data: Accelerometer range identifier

Format: 32-bit integer

Range	Identifier
2g	2
4g	4
8g	8
16g	16

Response: ACK (success) or NACK (error)

Identifier: 32

Name: GET_ACC_RANGE

Description: Get current accelerometer range.

Response: Accelerometer range indicator

Return format: 32-bit integer

Magnetometer Settings Command

Identifier: 33

Name: SET_MAG_RANGE

Description: Set the current range of the magnetometer.

Packet data: Magnetometer range identifier

Format: 32-bit integer

Response:

Range	Identifier
4 Gauss	4
8 Gauss	8
12 Gauss	12
16 Gauss	16

Identifier: 34

Name:	GET_MAG_RANGE
Description:	Get current magnetometer range.
Response:	Magnetometer range indicator (same as above)
Return format:	32-bit integer

Identifier:	35
Name:	SET_HARD_IRON_OFFSET
Description:	Set the current hard iron offset vector.
Packet data:	Hard iron offset values
Format:	32-bit integer encoded 3-element float vector
Response:	ACK (success) or NACK (error)

Identifier:	36
Name:	GET_HARD_IRON_OFFSET
Description:	Get current hard iron offset vector.
Response:	Hard iron offset values
Return format:	32-bit integer encoded 3-element float vector

Identifier:	37
Name:	SET_SOFT_IRON_MATRIX
Description:	Set the current soft iron matrix.
Packet data:	Soft iron matrix values
Format:	32-bit integer encoded 9-element (3x3) float matrix
Response:	ACK (success) or NACK (error)

Identifier:	38
Name:	GET_SOFT_IRON_MATRIX
Description:	Get the current soft iron matrix.
Response:	Soft iron matrix values
Return format:	32-bit integer encoded 9-element (3x3) float matrix

---

Identifier: 39
Name: SET_FIELD_ESTIMATE
Description: Set the current earth magnetic field strength estimate.
Packet data: Field estimate value in uT
Format: 32-bit integer encoded float
Response: ACK (success) or NACK (error)

Identifier: 40
Name: GET_FIELD_ESTIMATE
Description: Get the current earth magnetic field strength estimate.
Response: Field estimate value in uT
Return format: Int32

Identifier: 76
Name: SET_MAG_ALIGNMENT_MATRIX
Description: Sets the magnetometer misalignment matrix.
Packet data: Misalignment matrix
Format: Matrix3x3f
Response: ACK (success) or NACK (error)

Identifier: 77
Name: SET_MAG_ALIGNMENT_BIAS
Description: Sets the magnetometer misalignment bias.
Packet data: Misalignment bias
Format: Vector3f
Response: ACK (success) or NACK (error)

Identifier: 78
Name: SET_MAG_REFRENCE
Description: Sets the magnetometer reference vector.
Packet data: Misalignment matrix
Format: Vector3f

Response: ACK (success) or NACK (error)

Identifier: 79

Name: GET_MAG_ALIGNMENT_MATRIX

Description: Gets magnetometer misalignment matrix.

Response: Misalignment matrix

Return format: Matrix3x3f

Identifier: 80

Name: GET_MAG_ALIGNMENT_BIAS

Description: Gets magnetometer misalignment bias.

Response: Misalignment bias

Return format: Vector3f

Identifier: 81

Name: GET_MAG_REFERENCE

Description: Gets magnetometer reference.

Response: Magnetometer reference vector

Return format: Vector3f

Filter Settings Command

Identifier: 41

Name: SET_FILTER_MODE

Description: Setthe sensor filter mode.

Packet data: Mode identifier

Format: 32-bit integer

Mode	Value
Gyroscope only	0x00000000
Accelerometer + gyroscope	0x00000001
Accelerometer+ gyroscope+ magnetometer	0x00000002
Accelerometer + Magnetometer (Euler angle based filtering)	0x00000003

Accelerometer + Gyroscope (Euler angle-based filtering)	0x00000004

Response: ACK (success) or NACK (error)

Identifier: 42

Name: GET_FILTER_MODE

Description: Get the currently selected filter mode.

Response: Filter mode identifier

Return format: 32-bit integer

Mode	Value
Gyroscope only	0x00000000
Accelerometer + gyroscope	0x00000001
Accelerometer + gyroscope + magnetometer	0x00000002

Identifier: 43

Name: SET_FILTER_PRESET

Description: Set one of the filter parameter presets.

Packet data: Magnetometer correction strength preset identifier

Format: 32-bit integer

Response:

Preset	Value
Dynamic	0x00000000
Strong	0x00000001
Medium	0x00000002
Weak	0x00000003

Identifier: 44

Name: GET_FILTER_PRESET

Description: Get the currently magnetometer correction strength preset

Response: Magnetometer correction strength preset identifier

Return format: 32-bit integer

Correction strength	Value
Dynamic	0x00000000

Strong	0x00000001
Medium	0x00000002
Weak	0x00000003

Identifier: 60
Name: SET_RAW_DATA_LP
Description: Set raw data low-pass
Packet data: Low pass strength
Format: Float

Cutoff frequency	Value
Off	0x00000000
40 Hz	0x00000001
20 Hz	0x00000002
4 Hz	0x00000003
2 Hz	0x00000004
0.4 Hz	0x00000005

Response: ACK (success) or NACK (error)

Identifier: 61
Name: GET_RAW_DATA_LP
Description: Get raw data low-pass
Response: Low pass strength
Return format: Float

Identifier: 67
Name: SET_LIN_ACC_COMP_MODE
Description: Sets linear acceleration compensation mode.
Packet data: Mode identifier
Format: 32-bit integer
Response: ACK (success) or NACK (error)

Identifier: 68
Name: GET_LIN_ACC_COMP_MODE
Description: Gets linear acceleration compensation mode.
Response: Mode identifier
Return format: 32-bit integer

Identifier: 69
Name: SET_CENTRI_COMP_MODE
Description: Sets centripetal acceleration compensation mode.
Packet data: Mode identifier
Format: 32-bit integer
Response: ACK (success) or NACK (error)

Identifier: 70
Name: GET_CENTRI_COMP_MODE
Description: Gets centripetal acceleration compensation mode.
Response: Mode identifier
Return format: 32-bit integer

Battery status Commands

Identifier: 87
Name: GET_BATTERY_LEVEL
Description: Get current battery remaining capacity in percentage.
Response: Remaining battery capacity
Return format: Float

Identifier: 88
Name: GET_BATTERY_VOLTAGE
Description: Get current battery voltage.

Response: Current battery voltage

Return format: Float

Identifier: 89

Name: GET_CHARGING_STATUS

Description: Get charging status

Response: Charging status: 1: Charging 0: Not charging

Return format: Uint32

Device Info Command

Identifier: 91

Name: GET_DEVICE_NAME

Description: Get sensor name

Response: 16-character sensor name

Return format: Char[16]

Identifier: 92

Name: GET_FIRMWARE_INFO

Description: Get firmware info

Response: 16-character firmware info

Return format: Char[16]

Software Sync Commands

Identifier: 96
Name: START_SYNC
Description: Start software sync routine.
Response: ACK (success) or NACK (error)

Identifier: 97
Name: STOP_SYNC
Description: Start software sync routine.
Response: ACK (success) or NACK (error)

APPENDIX C – SOFTWARE REVISION HISTORY

Version 2.0.1

SW / FW: Improves 400Hz high speed communication stability

Version 2.0.0

SW / FW: First release based on a series of previous in-official releases.

APPENDIX D – MECHANICAL DIMENSIONS

LPMS-B2

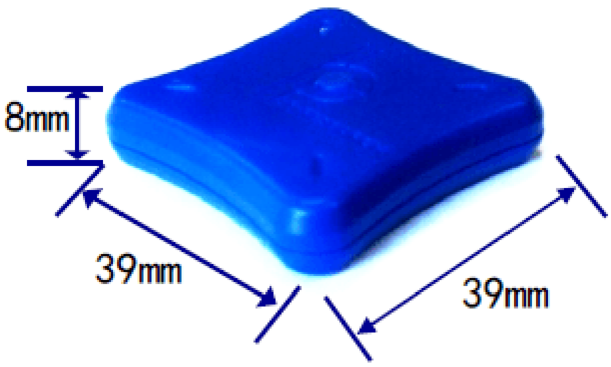

Figure 14 - LPMS-B2 mechanical dimensions

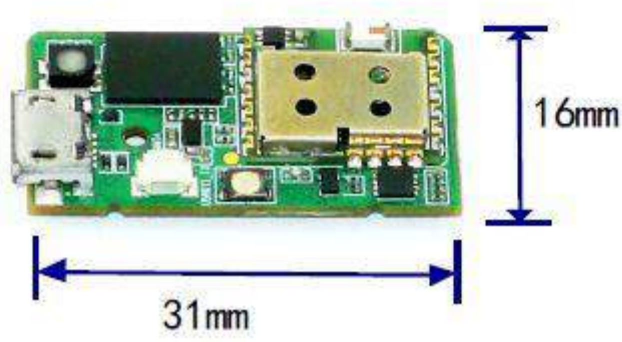

Figure 16 - LPMS-B2 OEM mechanical dimensions

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