LPMS-B

Reference Manual

Version 1.2.7

www.lp-research.com

I. INTRODUCTION

Welcome to the LP-RESEARCH Motion Sensor Bluetooth version (LPMS-B) User’s Manual!

In this manual we will try to explain everything you need to know to set up the LPMS-B hardware, install and use its software, as well as getting started with integrating the sensor within your own software project. We have put a lot of effort into making the LPMS-B a great product, but we are always eager to improve and work on new developments. So, if you have any further question or have any comment regarding this manual please feel free to contact us anytime.

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

II. TABLE OF CONTENTS

III. REVISION HISTORY

Date	Revision	Changes
01-May-2012	1.0	Initial release.
01-Sep-2012	1.0.11	The introduction part of LPMS-CU has been removed, and summarized into another separated document. The whole manual includes only the information of LPMS-B.
17-Sep-2012	1.0.12	- Updates to reflect the latest changes in the firmware command set. - OpenMAT library section contains more details on how to use the binary LpSensor library. - Section on how to compile LpmsControl was removed.
25-Feb-2013	1.1.0	- Correction of some bugs of system sampling timing. - GUI has been optimized by adding more tool bars. - Up to 4 sensor 3 D visualization view modes are added. - Altitude calculation by using pressure sensor is included. - Another two Euler filter modes are added. - Low pass filter setting is added.
13-Jan-2014	1.2.7	- Correction of some bugs on commands list. - Add introduction of advanced gyroscope calibration.

IV. DEVICE OVERVIEW

Measurement Output

The LP-RESEARCH Motion Sensor Bluetooth version (LPMS-B) is a wireless 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 air-planes. 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 the traditional way of describing the orientation of an object, quaternion allow orientation measurement without encountering the so-called Gimbal's lock 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-B will follow later on in this manual.

In addition, a pressure sensor is selectable on the LPMS-B for some specific applications, such as GPS navigation enhancement, indoor and outdoor navigation, vertical velocity indication, and so on.

Technical Background

To measure the orientation of an object, the sensor internally uses three different sensing units. 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-B for orientation determination are a 3-axis gyroscope (detecting angular velocity), a 3-aixs 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 result. Therefore we correct the orientation data from the gyroscope with information from the accelerometer (roll and pitch angles) and magnetometer (yaw angle) 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). 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.). Sampling rates of the sensor can be adjusted to up to 300 Hz internal measurement frequency.

Communication Methods

For the transmission of the data from the sensor to a data logging unit we applied the wireless Bluetooth technology. For communication protocols we rely on commonly used open standard protocols: a modified ModBus protocol (LpBUS)

Calibration

For accurate operation the sensor needs to be calibrated. The calibration procedure includes the determination of the gyroscope data offset 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 location or under varying experiment environments. Later in this manual we will describe in detail the necessary calibration procedures and measures to be taken to guarantee the accuracy of the measurements taken 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 the users.

Magnetic Field Distortion Compensation

Additionally to the established method of compensating a distorted earth magnetic field by re-calibrating the magnetometer, the LPMS-B offers either completely switching off the magnetometer compensation of the gyroscope data or selectively switching the compensation modes between: dynamics; weak; medium; and strong, in places where an earth magnetic field outside the normal limits is being detected. We implemented a special algorithm that allows switching between operation with different modes of magnetometer compensation and without magnetometer compensation without any inconsistencies in the orientation detection. For further adjustment of the calibration parameters to the sensor environment a temperature sensor and pressure sensor have been integrated on the LPMS-B. Data from these indicators can be utilized by the user to correct raw data measurements from the LPMS-B sub-sensors.

Size and Run-times

During the development of the LPMS-B we tried to make the unit as small as possible to allow a large variety of application areas. For size reduction the actual sensing units and microcontroller hardware are integrated into one main-board with 6-layers PCB design. The communication hardware interface is implemented on an extension-board, which is stacked above the main-board.

Each LPMS-B consists of these two boards as a whole unit. The main-board contains the actual sensor devices and manages the sensor data acquisition. The extension-board contains the Bluetooth hardware to communicate with data logging devices. In case of the wireless version additionally to the circuit boards, the LPMS-B case also contains a rechargeable battery. The battery is exchangeable and allows independent run times of up to 10 hours.

Application Areas

The LPMS-B 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 and evaluation 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

Currently we have 2 different packages of LPMS-B sensor. They are respectively named as LPMS-B standard version and OEM version. Please see the below table of the summary of sensor specification.

Parameters	LPMS-B (standard version)	LPMS-B (maker edition)
Size	45x 37 x 20 mm	28 x 20 x 12 mm
Weight	34 g	7 g
Bluetooth	2.1 + EDR, 2.412 - 2.484 GHz	
Communication distance	< 18 m	
Orientation Range	360 ° about all axes	
Resolution	< 0.05 °	
Accuracy	< 2 ° (dynamic),< 0.5 ° (static)	
Accelerometer	3-axis, ±20 / ±40 / ±80 / ±160 m/s^2, 16 bits	
Gyroscope	3-axis, ±250 / ±500 / ±2000 ^{O}/s, 16 bits	
Magnetometer	3-axis, ±130 ～ ±810 uT, 16 bits	
Pressure sensor	300 ～ 1100 hPa *	
Data output format	Raw data / Euler angle / Quaternion	
Sampling rate	0 ～ 300 Hz	
Latency	20ms	
Power consumption	290 mW @ 3.3 V	
Power supply	Lithium battery > 10 h (3.7 V @ 800mAh)	3.6 ～ 18 V DC
Temperature range	- 20 ～ +60 ^{O}C	- 40 ～ +80 ^{O}C
Connector	Micro USB, type B	
Software	C++ library for Windows, Java library for Android, LpmsControl software and Open Motion Analysis Toolkit (OpenMAT) for Windows.	

*The pressure sensor is optional and can be added on LPMS-B, which depends on the requirement from users. Please contact us for more information about this.

VI. CONNECTOR CONFIGURATION

LPMS-B Connector

Pin description:

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

Connector type: Micro-USB type B female

Remark: This connector is used for recharging the LPMS-B battery. Power is internally supplied to the LPMS-B by a rechargeable battery contained inside the LPMS-B case. To recharge the sensor, we supply a specific recharger called LPMS-B recharger. More detail information of the recharger can be found out in the following section.

LPMS-B Recharger Connector

Port #1

Pin description:

Pin	*1*	*2*	*3*	*4*	*5*
Function	*+5V*	*None*	*None*	*None*	*GND*

Connector type: Micro-USB type B female

Port #2

Pin description:

Pin	*1*	*2*	*3*	*4*	*5*
Function	*Vcc*	*None*	*None*	*None*	*GND*

Connector type: USB type A female

Remark: The connector “Port #1” needs to be connected to a USB power source with at least 500mA output current capacity. The connector “Port #2” as the output of the recharger needs to be connected with the LPMS-B for recharging the battery. We supply two cables with USB-A to MicroUSB-B conversion for the connections between USB power source → recharger → LPMS-B. A schematics drawing of the connection configuration among USB power source, LPMS-B and recharger is shown in section “*X. MECHANICAL INFORMATION*”.

Charging Status Indication:

Red LED	Green LED	Status
On	*Off*	The battery is being recharged.
Off	*On*	The battery has been fully charged.
On	*On*	The recharger is not connected to LPMS-B.

Remark: If the recharger is powered on and has not been connected to LPMS-B after about 5 minutes, both LEDs will be on to indicate the connection error. The total recharging time normally takes 5 to 6 hours.

VII. OPERATION

Powering Up and Operation Modes

The LPMS-B sensor is switched on by pressing the power button for duration of ~ 1s. The red and green LEDs visible on the top of the LPMS-B light up when operation power is supplied to the device. And after about 5 seconds, the green color status LED will start blinking with an interval of 1s, which means the sensor is ready for connection. There are 3 different modes for operation:

Mode	Description
Command mode	In command mode the functionality of the sensor is accessed command-by-command. Also 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.
Streaming mode (default 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.
Sleep mode (reserved)	Sleep mode is the power-saving state of the sensor. The sensor can be woken up by switching into streaming mode or command mode. In this mode no data can be read from the sensor.

IMPORTANT: The sensor is set to streaming mode in default after power on and connection established. Command Mode and Sleep Mode can be switched by sending commands over the communication interface. The modification of operation mode can be saved into the sensor memory. We will specify the available commands in detail later on in this manual.

Host Device Communication

To connect to the sensor, a Bluetooth connection request must be sent to the Bluetooth MAC address of LPMS-B. This MAC address as the sensor device ID can be checked by using the LpmsControl Software or OpenMAT library, which will be illustrated in detail at section “*IX. OpenMAT LIBRARY*”.

Users should connect to the Bluetooth module of LPMS-B using a standard class 2 Bluetooth host interface that supports SPP (serial protocol profile). A key-code for pairing is not required. Establishing a connection with the sensor usually takes around 2 to 5 seconds. The Bluetooth device name of the sensor for device discovery is ‘LPMS-B’. The baudrate of the connection is set to 9216000 bit/s by default.

Data Acquisition

For data acquisition, all the communications with the device must be according to the LpBUS protocol, which is introduced in detail in section “*VIII. COMMUNICATION PROTOCOL*”.

Raw Sensor Data

The LPMS-B IMU 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. This 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. Details will be explained later on in this manual at section of “*VIII. COMMUNICATION PROTOCOL*”.

The LPMS-B is calibrated in default, 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.

Orientation Data

The LPMS-B 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 the users to use the quaternion representation for the 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

First, the mode of the filter needs to be selected, which can be set by LpmsControl software or the firmware commands. The following filter modes are available:

Filter mode	Description
Gyroscope only	Only the data from the gyroscope is used to calculate the orientation data output from the sensor. In this mode the orientation data can be calculated very quickly and with little noise. However, a strong drift of the acquired

	values can occur due to the inherent bias problem of gyroscope. This mode should therefore be only used for cases in which a frequent reset of the zero-angle position is allowed.
Gyroscope + accelerometer (default mode)	The orientation data that is calculated from the gyroscope is corrected by the accelerometer data based on quaternion representation. The accelerometer acquires accurate information about the roll and pitch orientation regarded with the earth gravity vector. The result of the correction is therefore orientation information that has very little error on the roll and pitch axis, the yaw axis however is still affected by the drift of the un-corrected gyroscope data. This mode might be significant useful when there is a strong magnetic interference that can hardly be efficiently calibrated exiting around the sensor and only the roll and pitch information is interest to the users.
Gyroscope + accelerometer + magnetometer	Orientation data from the gyroscope that has been corrected by the accelerometer output as previously described is additionally modified by the direction of the earth magnetic field. This results in accurate orientation information for all three axes. This mode delivers good speed and accuracy for roll, pitch and yaw. In this mode, (un-calibrated) distortions of the earth magnetic will affect the accuracy of the orientation measurement.
Accelerometer + magnetometer (Euler only)	Orientation is directly calculated by the combination of the data from accelerometer and magnetometer using Euler representation. Therefore it has the singularity problem at certain orientations. Based on the information of gravity in the vertical frame and the geomagnetic field vector in horizontal frame, the roll, pitch and yaw angle can be achieved based on the readings from accelerometer and magnetometer. This mode is suitable for the application of small motion and limited magnetic distortion.
Gyroscope + accelerometer (Euler only)	The orientation data that is calculated from the gyroscope is corrected by the accelerometer data based on Euler representation. Therefore it has the singularity problem at certain orientations. The accelerometer acquires accurate information about the roll and pitch orientation regarded with the earth gravity vector. The result of the correction is therefore orientation information that has very little error on the roll and pitch axis, the yaw axis however is still affected by the drift of the un-corrected gyroscope data. This mode might be significant useful when there is a strong magnetic interference that can hardly be efficiently calibrated exiting around the sensor and only the roll and pitch information is interest to the users.

Magnetometer Correction Setting

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

Parameter presets	Description
Dynamic (default)	The value "Dynamic" means the magnetic correction inside the filter is performed dynamically together with the acceleration data according to the variance of magnetic interference. This parameter set is suitable for the situation when the magnetic interference keeps changing.
Weak	The value "weak" means the magnetic correction inside the filter has little impact on the orientation output. Sensor orientation is calculated mainly from the acceleration / gyroscope data. This parameter set is suitable for situations when strong magnetic interference that cannot be compensated through calibration appear regularly.
Medium	With the "medium" correction setting the impact of the magnetometer readings is still relatively weak, but stronger than in "weak" mode. This mode should be suitable for environments with occasional irregular field distortions.
Strong	In this mode the magnetometer readings have a strong direct impact on the orientation output. It can be used in environments with a calibrate-able constant field distortion or in "clean" fields (outside buildings with no metal parts or strong power sources in the vicinity of the sensor). Yaw orientation measurement in world coordinates will be most accurate in this mode.

Acceleration Compensation Setting

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

Linear Acceleration Correction Settings

Parameter presets	Description
Off	There is no linear acceleration compensation for the sensor fusion

	in this mode. This parameter set is suitable for situations when there is no linear acceleration appears.
Weak	The value "weak" means the linear acceleration correction inside the filter has little dynamic impact on the orientation output. This parameter set is suitable for situations when linear acceleration appears regularly and slightly.
Strong (default)	The value "Strong" means the linear acceleration correction inside the filter has strong dynamic impact on the orientation output. This parameter set is suitable for situations when linear acceleration appears regularly and strongly.

Rotational Acceleration Correction Settings

Parameter presets	Description
Disable	There is no rotational acceleration compensation for the sensor fusion in this mode.
Enable (default)	There is dynamic rotational acceleration compensation for the sensor fusion in this mode.

Gyroscope Threshold

The input from the gyroscope can be thresholded so that the sensor orientation data is only updated when the sensor is moved. This threshold is automatically determined during gyroscope calibration.

Parameter preset	Description
Enable	Switches gyroscope threshold on.
Disable (default)	Switches gyroscope threshold off.

Gyroscope Auto-calibration Function

The selection of the following parameter values allows the users to enable or disable the gyroscope auto calibration function. In auto calibration mode the filter is automatically detects if the sensor is moving or not. If the sensor stays still for a certain time, the currently sampled gyroscope data will be used to re-calculate the gyroscope offset. This function is significant useful when the user is using the "Gyroscope only" filter mode, and most the time of the system stays still. Using this function will reduce the drift problem of the gyroscope.

Parameter preset	Description
Enable (default)	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 (default)	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	$a = 0.001$

Trade-offs and Limitations

Although we have put (and still do) a lot of effort into the design of the LPMS-B, there are a few limitations of the sensor that need to be taken into account when using the device. The accuracy of the sensor is limited by the electronic noise level of the MEMS sensors used in the LPMS-B. Although the sensor data acquisition speeds for gyroscope, accelerometer and magnetometer are more than 500Hz, but the data output frequency of the whole system is limited to a certain frequency (up to 300Hz). 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 affectability by a deformed earth magnetic field (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-B, battery run-times should be taken into account when considering the sensor for a new application. Furthermore, the wireless Bluetooth connection puts a limit on the maximum range and the maximum data update frequency.

Calibration Methods

Basic Gyroscope Calibration

When the sensor is resting the output data of the gyroscope should be around zero. The raw data from the gyroscope sensor has a constant bias of a certain value. To determine this value please follow the following calibration procedure:

Step	Description
1	If it is not already switched on, power up the LPMS-B device.
2	Put the sensor in a resting (non-moving) position.
3	Connect to the sensor.
4	Trigger the gyroscope calibration procedure either through a firmware command or using the “Calibrate gyroscope” function in LpmsControl software.
5	The gyroscope calibration will take around 30s. After that the gyroscope is calibrated, normal operation can be resumed.

Additionally to the gyroscope bias, the gyroscope threshold value will be adjusted during this calibration procedure. By default the use of the gyroscope threshold is disabled. It can be enabled by sending a firmware command or using the LpmsControl software. The gyro auto calibration function is enabled by default.

Advanced Gyroscope Calibration

The gain and misalignment parameters of gyroscope can be further calibrated under the following instructions by expert users.

Step	Description
1	If it is not already switched on, power up the LPMS-B device.
2	Put the sensor on a turntable which is placed horizontally.
3	Set the rotating rate of the turntable to 45rpm.
4	Trigger the gyroscope misalignment calibration procedure either through a firmware command or using the “Calibrate gyr. misalignment” function in LpmsControl software.
5	Following the guideline of pop out window, to set the x axis upwards, and start the turntable until the x axis calibration is finished
6	To set the y axis upwards, and start the turntable until the y axis calibration is finished
7	To set the z axis upwards, and start the turntable until the z axis calibration is finished
	After finishing the above procedures the gyroscope misalignment matrix and gain values will be re-calculated. This finishes the gyroscope advanced calibration.

Magnetometer Calibration

During the magnetometer calibration procedure several parameters are to be determined: magnetometer bias and gain on the X, Y and Z-axis; length and direction of the 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.

During the magnetometer calibration the amount of de-centering and deformed as well as the average length of the magnetic field vector is calculated. These parameters are tuned automatically using the calibration procedures in the LpmsControl software:

Step	Description
1	If it is not already switched on, power up the LPMS-B device.
2	If it is not already connected, connect to the sensor.
3	Start the magnetometer calibration using the LpmsControl software.
4	Rotate the sensor around its yaw axis for 2~3 rotations.
5	Rotate the sensor around its pitch axis for 2~3 rotations.
6	Rotate the sensor around its roll axis for 2~3 rotations.
7	Rotate the sensor randomly to acquire data as much as possible from different directions.
8	The calibration procedure finished automatically after 30 seconds. After that the magnetometer has been calibrated.

IMPORTANT: Euler angle transmission must be turned on for the magnetometer calibration to succeed.

Accelerometer Calibration

The misalignment of the accelerometer relative to the casing of the LPMS-B device is expressed by the so called misalignment matrix. Using the LpmsControl software this misalignment matrix can be calibrated by the user. In the mean time, the offsets of the accelerometer can be also evaluated. Whereas the usage of the LpmsControl software is explained in more detail in the “*LpmsControl Software Operation*” section, the calibration procedure consists of the following steps:

Step	Description
1	If it is not already switched on, power up the LPMS-B device.
2	If it is not already connected, connect to the sensor.
3	Start the accelerometer misalignment calibration using the LpmsControl software. See “LpmsControl Software Operation” section.
4	Fix the sensor to a horizontal surface with the Z-axis pointing upwards.
5	Fix the sensor to a horizontal surface with the Z-axis pointing downwards.
6	Fix the sensor to a horizontal surface with the X-axis pointing upwards.
7	Fix the sensor to a horizontal surface with the X-axis pointing downwards.
8	Fix the sensor to a horizontal surface with the Y-axis pointing upwards.
9	Fix the sensor to a horizontal surface with the Y-axis pointing downwards.

10	After finishing the above procedures the accelerometer misalignment matrix and offset values will be re-calculated. This finishes the accelerometer calibration.

VIII. COMMUNICATION PROTOCOL

Establishing a Connection

Before starting to communicate with the LPMS-B, users need to establish a connection over Bluetooth according to the introduction at section "*Host Device Communication*".

Basic Protocol Introduction

The 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-B device). Later in this manual we will show a description of all supported commands to the sensor, their type, contained data etc.

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 an ACK command feedback for a successful write, or NACK command feedback for a failure to set the register occurred.

LpBUS Protocol

Packet Format

All communication with the LPMS-B works with a common protocol called LpBUS. The protocol is based on the industry standard MODBUS that we slightly adapted to be most suitable for our purpose. Each packet sent during the communication is based on this protocol, which is described in the following table:

Byte no.	Name	Description
0	Packet start (3Ah)	Mark of the beginning of a data packet.
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-B 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 no. byte 1	Contains the low byte of the command to be performed by the data transmission.
4	Command no. 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(packet 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.

32-bit integer values (LENGTH = 4 bytes)

Transmission order	**0**	**1**	**2**	**3**
Integer word, byte number	0 (LSB)	1	2	3 (MSB)

32-bit integer 3-component vector (LENGTH = 12 bytes)

Transmission order	**0**	**1**	**2**	**3**
Vector component 1, byte number	0 (LSB)	1	2	3 (MSB)
Transmission order	**4**	**5**	**6**	**7**
Vector component 2, byte number	0 (LSB)	1	2	3 (MSB)
Transmission order	**8**	**9**	**10**	**11**
Vector component 3, byte number	0 (LSB)	1	2	3 (MSB)

32-bit float value encoded as integer (LENGTH = 4 bytes)

Transmission order	**0**	**1**	**2**	**3**
Integer-encoded float, byte number	0 (LSB)	1	2	3 (MSB)

32-bit float 3-component vector (LENGTH = 12 byte)

Transmission order	**0**	**1**	**2**	**3**
Vector component 1, byte number	0 (LSB)	1	2	3 (MSB)
Transmission order	**4**	**5**	**6**	**7**
Vector component 2, byte number	0 (LSB)	1	2	3 (MSB)
Transmission order	**8**	**9**	**10**	**11**
Vector component 3, byte number	0 (LSB)	1	2	3 (MSB)

Protocol Commands List

Acknowledged and Not-acknowledged Identifier

Command No. (decimal values)	**Command description**
0	REPLY_ACK (acknowledged). Confirms a successful SET command.
1	REPLY_NACK (not-acknowledged) Reports an error during processing a SET command.

Firmware Update and In-Application-Programmer Upload Command

2	Start the firmware update process. IMPORTANT: By not correctly uploading a firmware file the sensor might become in-operable. In normal cases please use the LpmsControl software to upload new firmware. Also please only use firmware packages that have been authorized by LP-RESEARCH.

<table>
<tr><td></td><td>Packet data: Firmware data
Data format Firmware binary file separated into 256 byte chunks for each update packet.
Macro name: UPDATE_FIRMWARE
Response: ACK (success) or NACK (error) for each transmitted packet.</td></tr>
<tr><td>3</td><td>“RESERVED” This command is reserved by LP-RESEARCH.
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.
Macro name: UPDATE_IAP
Response: ACK (success) or NACK (error) for each transmitted packet.</td></tr>
</table>

Configuration and Status Command

<table>
<tr><td>4</td><td>Get the current value of the configuration register of the sensor. The configuration word can ONLY be read. 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.
Return format: 32-bit integer
<table>
<tr><th>Bit</th><th>Reported State / Parameter</th></tr>
<tr><td>0 - 2</td><td>Stream frequency setting (see SET_STREAM_FREQ)</td></tr>
<tr><td>3 - 8</td><td>Reserved</td></tr>
<tr><td>9</td><td>Pressure data transmission enabled</td></tr>
<tr><td>10</td><td>Magnetometer data transmission enabled</td></tr>
<tr><td>11</td><td>Accelerometer data transmission enabled</td></tr>
<tr><td>12</td><td>Gyroscope data transmission enabled</td></tr>
<tr><td>13</td><td>Temperature output enabled</td></tr>
<tr><td>14</td><td>Heave motion output enabled</td></tr>
<tr><td>15</td><td>Reserved</td></tr>
<tr><td>16</td><td>Angular velocity output enabled</td></tr>
<tr><td>17</td><td>Euler angle data transmission enabled</td></tr>
</table>
</td></tr>
</table>

<table>
<tr>
<td></td>
<td>
<table>
<tr><td>18</td><td>Quaternion orientation output enabled</td></tr>
<tr><td>19</td><td>Output enabled</td></tr>
<tr><td>20</td><td>Dynamic magnetometer correction enabled</td></tr>
<tr><td>21</td><td>Linear acceleration output enabled</td></tr>
<tr><td>22</td><td>Reserved</td></tr>
<tr><td>23</td><td>Gyroscope threshold enabled</td></tr>
<tr><td>24</td><td>Magnetometer compensation enabled</td></tr>
<tr><td>25</td><td>Accelerometer compensation enabled</td></tr>
<tr><td>26</td><td>Reserved</td></tr>
<tr><td>27</td><td>Reserved</td></tr>
<tr><td>28</td><td>Reserved</td></tr>
<tr><td>29</td><td>Reserved</td></tr>
<tr><td>30</td><td>Gyroscope auto-calibration enabled</td></tr>
<tr><td>31</td><td>Reserved</td></tr>
</table>
Macro name: GET_CONFIG
</td>
</tr>
<tr>
<td>5</td>
<td>
Get the current value of the status register of the LPMS-B device. The status word can ONLY be read.
Packet data: Status indicator. Each bit represents the state of one status parameter.
Return format: 32-bit integer
<table>
<tr><th>Bit</th><th>Indicated state</th></tr>
<tr><td>0</td><td>COMMAND mode enabled</td></tr>
<tr><td>1</td><td>STREAM mode enabled</td></tr>
<tr><td>2</td><td>SLEEP mode enabled</td></tr>
<tr><td>3</td><td>Gyroscope calibration on</td></tr>
<tr><td>4</td><td>Reserved</td></tr>
<tr><td>5</td><td>Gyroscope initialization failed</td></tr>
<tr><td>6</td><td>Accelerometer initialization failed</td></tr>
<tr><td>7</td><td>Magnetometer initialization failed</td></tr>
<tr><td>8</td><td>Pressure sensor initialization failed</td></tr>
<tr><td>9</td><td>Gyroscope unresponsive</td></tr>
<tr><td>10</td><td>Accelerometer unresponsive</td></tr>
<tr><td>11</td><td>Magnetometer unresponsive</td></tr>
<tr><td>12</td><td>Flash write failed</td></tr>
<tr><td>13</td><td>Reserved</td></tr>
</table>
</td>
</tr>
</table>

<table>
<tr><td></td><td><table><tr><td>14</td><td>Set broadcast frequency failed</td></tr><tr><td>15-31</td><td>reserved</td></tr></table>Macro name: GET_STATUS</td></tr>
</table>

Mode Switching Command

6	Switch to command mode. In command mode the user can issue commands to the firmware to perform calibration, set parameters etc. **Packet data:** none **Macro name:** GOTO_COMMAND_MODE **Response:** ACK (success) or NACK (error)
7	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. **Packet data:** none **Macro name:** GOTO_STREAM_MODE **Response:** ACK (success) or NACK (error)
8	Switch to sleep mode. The purpose of the sleep mode is to reduce the power consumption of the sensor. Once in sleep mode, no commands can be issued to the sensor until it is woken up by switching back into command mode or streaming mode. **Packet data:** none **Macro name:** GOTO_SLEEP_MODE **Response:** ACK (success) or NACK (error)

Data Transmission Command

9	Get the latest set of sensor data. The format of the sensor data depends on the transmission settings (SET_TRANSMIT_DATA). The currently set format can be retrieved with the sensor configuration word. IMPORTANT: In the current version of the firmware calibrated accelerometer data as well as calibrated magnetometer data will always be transmitted. As these values are necessary for the calibration of the sensor, they can at the moment not be switched off. This format is also used in streaming mode to continuously send data from the sensor to the host. **Packet data:** Sensor data. The data always has the same order. Depending on the enabled transmission data, chunks are inserted or left out.

<table>
<tr>
<td></td>
<td>
Return format: Raw sensor data chunk
<table>
<tr><td>Chunk number</td><td>Data type</td><td>Sensor data</td></tr>
<tr><td>1</td><td>Float</td><td>Timestamp (ms)</td></tr>
<tr><td>2</td><td>Float 3-vector</td><td>Calibrated gyroscope data [deg/s]</td></tr>
<tr><td>3</td><td>Float 3-vector</td><td>Calibrated accelerometer data [m/s^2]</td></tr>
<tr><td>4</td><td>Float 3-vector</td><td>Calibrated magnetometer data [μT]</td></tr>
<tr><td>5</td><td>Float 3-vector</td><td>Angular velocity [deg/s]</td></tr>
<tr><td>6</td><td>Float 4-vector</td><td>Orientation quaternion [normalized]</td></tr>
<tr><td>7</td><td>Float 3-vector</td><td>Euler angle data [deg.]</td></tr>
<tr><td>8</td><td>Float 3-vector</td><td>Linear acceleration data [m/s^2]</td></tr>
<tr><td>9</td><td>Float</td><td>Barometric pressure [mPa]</td></tr>
<tr><td>10</td><td>Float</td><td>Heave motion [m] (if enabled)</td></tr>
</table>
Macro name: GET_SENSOR_DATA
</td>
</tr>
<tr>
<td>10</td>
<td>
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. The flags to switch data chunks on (set the bit to 1) and off (set the bit to 0) are the same as in the configuration word (see SET_CONFIG).
<table>
<tr><th>Bit</th><th>Reported State / Parameter</th></tr>
<tr><td>**9**</td><td>Pressure data transmission enabled</td></tr>
<tr><td>**10**</td><td>Magnetometer data transmission enabled</td></tr>
<tr><td>**11**</td><td>Accelerometer data transmission enabled</td></tr>
<tr><td>**12**</td><td>Gyroscope data transmission enabled</td></tr>
<tr><td>**13**</td><td>Temperature output enabled</td></tr>
<tr><td>**14**</td><td>Heave motion output enabled</td></tr>
<tr><td>**16**</td><td>Angular velocity output enabled</td></tr>
</table>
</td>
</tr>
</table>

<table>
<tr>
<td></td>
<td>
<table>
<tr><td>17</td><td>Euler angle data transmission enabled</td></tr>
<tr><td>18</td><td>Quaternion orientation output enabled</td></tr>
<tr><td>19</td><td>Altitude output enabled</td></tr>
<tr><td>21</td><td>Linear acceleration output enabled</td></tr>
</table>
Macro name: SET_TRANSMIT_DATA
Response: ACK (success) or NACK (error)
Default value: Gyroscope, accelerometer, magnetometer and quaternion data.
</td>
</tr>
<tr>
<td>11</td>
<td>
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
Format: 32-bit integer
<table>
<tr><td>Frequency (Hz)</td><td>Identifier</td></tr>
<tr><td>5</td><td>5</td></tr>
<tr><td>10</td><td>10</td></tr>
<tr><td>30</td><td>30</td></tr>
<tr><td>50</td><td>50</td></tr>
<tr><td>100</td><td>100</td></tr>
<tr><td>200</td><td>200</td></tr>
<tr><td>300</td><td>300</td></tr>
<tr><td>500</td><td>500</td></tr>
</table>
Macro name: SET_STREAM_FREQ
Response: ACK (success) or NACK (error)
Default value: 100 Hz
</td>
</tr>
<tr>
<td>12</td>
<td>
Get the current roll angle in radians.
Packet data: Roll angle
Return format: 32-bit integer coded float value.
Macro name: GET_ROLL
</td>
</tr>
<tr>
<td>13</td>
<td>
Get the current pitch angle in radians.
Packet data: Pitch angle
Return format: 32-bit integer coded float value.
Macro name: GET_PITCH
</td>
</tr>
<tr>
<td>14</td>
<td>Get the current yaw angle in radians.</td>
</tr>
</table>

	Packet data: Yaw angle **Return format:** 32-bit integer coded float value. **Macro name:** GET_YAW

Register Value Save and Reset Command

15	Write the currently set parameters to flash memory. **Packet data:** None **Macro name:** WRITE_REGISTERS **Response:** ACK (success) or NACK (error)
16	Reset the LPMS parameters to factory default values. Please note that upon issuing this command your currently set parameters will be erased. **Packet data:** none **Macro name:** RESTORE_FACTORY_VALUE **Response:** ACK (success) or NACK (error)

Reference Setting and Offset Reset Command

17	Set the accelerometer and magnetometer reference vectors. **Packet data:** None **Macro name:** RESET_REFERENCE **Response:** ACK (success) or NACK (error)
18	Set the orientation offset (the value that is subtracted from the acquired orientation value after a measurement) to the currently measured orientation. This effectively resets the zero orientation of the sensor to the current orientation. **Packet data:** none **Macro name:** SET_OFFSET **Response:** ACK (success) or NACK (error)

Self-Test Command

19	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. **Packet data:** none **Macro name:** SELF_TEST **Response:** ACK (success) or NACK (error)

IMU ID Setting Command

<table>
<tr><td>20</td><td>Set the OpenMAT ID of the LPMS-B.
Packet data: OpenMAT ID
Data format: 32-bit integer
Macro name: SET_IMU_ID
Response: ACK (success) or NACK (error)
Default value: 1</td></tr>
<tr><td>21</td><td>Get the ID (OpenMAT ID) of the device
Packet data: The ID of the IMU device
Return format: 32-bit integer
Macro name: GET_IMU_ID</td></tr>
</table>

Gyroscope Settings Command

<table>
<tr><td>22</td><td>Start the calibration procedure of the gyroscope sensor. Details of the gyroscope calibration procedure are described in the <i>Operation – Calibration Methods</i> section of this manual. The calibration takes about 30s.
Packet data: none
Macro name: START_GYR_CALIBRATION
Response: ACK (success) or NACK (error)</td></tr>
<tr><td>23</td><td>Enable or disable auto-calibration of the gyroscope.
Packet data: Gyroscope auto-calibration enable / disable identifier
Format: 32-bit integer
<table>
<tr><td>State</td><td>Value</td></tr>
<tr><td>Disable</td><td>0x00000000</td></tr>
<tr><td>Enable</td><td>0x00000001</td></tr>
</table>
Macro name: ENABLE_GYR_AUTOCAL
Response: ACK (success) or NACK (error)
Default value: Disable</td></tr>
<tr><td>24</td><td>Enable or disable gyroscope threshold.
Packet data: Gyroscope threshold enable / disable identifier
Format: 32-bit integer
<table>
<tr><td>State</td><td>Value</td></tr>
</table>
</td></tr>
</table>

<table>
<tr><td></td><td><table><tr><td>Disable</td><td>0x00000000</td></tr><tr><td>Enable</td><td>0x00000001</td></tr></table>**Macro name:** ENABLE_GYR_THRES
Response: ACK (success) or NACK (error)
Default value: Disable</td></tr>
<tr><td>25</td><td>Set the current range of the gyroscope.
Packet data: Gyroscope range identifier
Format: 32-bit integer<table><tr><td>Range (deg/s)</td><td>Identifier</td></tr><tr><td>250</td><td>250</td></tr><tr><td>500</td><td>500</td></tr><tr><td>2000</td><td>2000</td></tr></table>**Macro name:** SET_GYR_RANGE
Response: ACK (success) or NACK (error)
Default value: 2000 deg/s</td></tr>
<tr><td>26</td><td>Get current gyroscope range.
Packet data: Gyroscope range indicator
Return format: 32-bit integer
Macro name: GET_GYR_RANGE</td></tr>
</table>

Accelerometer Settings Command

<table>
<tr><td>27</td><td>Set the accelerometer bias.
Packet data: Accelerometer bias (X, Y, Z-axis)
Format: 32-bit integer encoded float 3-component vector
Macro name: SET_ACC_BIAS
Response: ACK (success) or NACK (error)
Default value: (0.0, 0.0, 0.0)</td></tr>
<tr><td>28</td><td>Get the current accelerometer bias vector.
Packet data: Accelerometer bias vector
Return format: 32-bit integer encoded float 3-component vector
Macro name: GET_ACC_BIAS</td></tr>
<tr><td>29</td><td>Set the accelerometer alignment matrix.</td></tr>
</table>

<table>
<tr><td></td><td>Packet data: Alignment matrix
Format: 32-bit integer encoded float 3 x 3 matrix
Macro name: SET_ACC_ALIG
Response: ACK (success) or NACK (error)
Default value: 3x3 Identity matrix</td></tr>
<tr><td>30</td><td>Get the current accelerometer alignment matrix.
Packet data: Accelerometer alignment matrix
Return format: 32-bit integer encoded float 3 x 3 matrix
Macro name: GET_ACC_ALIG</td></tr>
<tr><td>31</td><td>Set the current range of the accelerometer.
Packet data: Accelerometer range identifier
Format: 32-bit integer
<table>
<tr><td>Range (g: 1 gravity)</td><td>Identifier</td></tr>
<tr><td>2g</td><td>2</td></tr>
<tr><td>4g</td><td>4</td></tr>
<tr><td>8g</td><td>8</td></tr>
<tr><td>16g</td><td>16</td></tr>
</table>
Macro name: SET_ACC_RANGE
Response: ACK (success) or NACK (error)
Default value: 2g</td></tr>
<tr><td>32</td><td>Get current accelerometer range.
Packet data: Accelerometer range indicator
Return format: 32-bit integer
Macro name: GET_ACC_RANGE</td></tr>
</table>

Magnetometer Settings Command

<table>
<tr><td>33</td><td>Set the current range of the magnetometer.
Packet data: Magnetometer range identifier
Format: 32-bit integer
<table>
<tr><td>Range</td><td>Identifier</td></tr>
<tr><td>130 uT</td><td>130</td></tr>
<tr><td>190 uT</td><td>190</td></tr>
<tr><td>250 uT</td><td>250</td></tr>
<tr><td>400 uT</td><td>400</td></tr>
</table>
</td></tr>
</table>

<table>
<tr><td></td><td><table><tr><td>470 uT</td><td>470</td></tr><tr><td>560 uT</td><td>560</td></tr><tr><td>810 uT</td><td>810</td></tr></table>**Macro name:** SET_MAG_RANGE
Response: ACK (success) or NACK (error)
Default value: 250 uT</td></tr>
<tr><td>34</td><td>Get current magnetometer range.
Packet data: Magnetometer range indicator (same as above)
Return format: 32-bit integer
Macro name: GET_MAG_RANGE</td></tr>
<tr><td>35</td><td>Set the current hard iron offset vector.
Packet data: Hard iron offset values in uT
Format: 32-bit integer encoded 3-element float vector
Macro name: SET_HARD_IRON_OFFSET
Response: ACK (success) or NACK (error)
Default value: (0.0, 0.0, 0.0)</td></tr>
<tr><td>36</td><td>Get current hard iron offset vector.
Packet data: Hard iron offset values in uT
Return format: 32-bit integer encoded 3-element float vector
Macro name: GET_HARD_IRON_OFFSET</td></tr>
<tr><td>37</td><td>Set the current soft iron matrix.
Packet data: Soft iron matrix values in uT
Format: 32-bit integer encoded 9-element (3x3) float matrix
Macro name: SET_SOFT_IRON_MATRIX
Response: ACK (success) or NACK (error)
Default value: (1, 0, 0)
(0, 1, 0)
(0, 0, 1)</td></tr>
<tr><td>38</td><td>Get the current soft iron matrix.
Packet data: Soft iron matrix values in uT
Return format: 32-bit integer encoded 9-element (3x3) float matrix</td></tr>
</table>

	Macro name: GET_SOFT_IRON_MATRIX
39	Set the current earth magnetic field strength estimate. **Packet data:** Field estimate value in uT **Format:** 32-bit integer encoded float **Macro name:** SET_FIELD_ESTIMATE **Response:** ACK (success) or NACK (error) **Default value:** 50 uT
40	Get the current earth magnetic field strength estimate. **Packet data:** Field estimate value in uT **Return format:** 32-bit integer encoded float **Macro name:** GET_FIELD_ESTIMATE

Filter Settings Command

<table>
<tr><td>41</td><td>Set the sensor filter mode.
Packet data: Mode identifier
Format: 32-bit integer
<table>
<tr><td>Mode</td><td>Value</td></tr>
<tr><td>Gyroscope only</td><td>0x00000000</td></tr>
<tr><td>Accelerometer + gyroscope</td><td>0x00000001</td></tr>
<tr><td>Accelerometer + gyroscope + magnetometer</td><td>0x00000002</td></tr>
<tr><td>Accelerometer + Magnetometer (Euler angle based filtering)</td><td>0x00000003</td></tr>
<tr><td>Accelerometer + Gyroscope (Euler angle-based filtering)</td><td>0x00000004</td></tr>
</table>
Macro name: SET_FILTER_MODE
Response: ACK (success) or NACK (error)
Default value: Accelerometer + gyroscope + magnetometer</td></tr>
<tr><td>42</td><td>Get the currently selected filter mode.
Packet data: Filter mode identifier</td></tr>
</table>

<table>
<tr><td></td><td>Return format: 32-bit integer
<table><tr><td>Mode</td><td>Value</td></tr><tr><td>Gyroscope only</td><td>0x00000000</td></tr><tr><td>Accelerometer + gyroscope</td><td>0x00000001</td></tr><tr><td>Accelerometer + gyroscope + magnetometer</td><td>0x00000002</td></tr></table>Macro name: GET_FILTER_MODE</td></tr>
<tr><td>43</td><td>Set one of the filter parameter presets.
Packet data: Magnetometer correction strength preset identifier
Format: 32-bit integer
<table><tr><td>Preset</td><td>Value</td></tr><tr><td>Dynamic</td><td>0x00000000</td></tr><tr><td>Strong</td><td>0x00000001</td></tr><tr><td>Medium</td><td>0x00000002</td></tr><tr><td>Weak</td><td>0x00000003</td></tr></table>Macro name: SET_FILTER_PRESET
Response: ACK (success) or NACK (error)
Default value: Dynamic</td></tr>
<tr><td>44</td><td>Get the currently magnetometer correction strength preset
Packet data: Magnetometer correction strength preset identifier
Return format: 32-bit integer
<table><tr><td>Correction strength</td><td>Value</td></tr><tr><td>Dynamic</td><td>0x00000000</td></tr><tr><td>Strong</td><td>0x00000001</td></tr><tr><td>Medium</td><td>0x00000002</td></tr><tr><td>Weak</td><td>0x00000003</td></tr></table>Macro name: GET_FILTER_PRESET</td></tr>
</table>

CAN Bus Settings Command (Only for LPMS-CU module)

<table>
<tr><td>45</td><td>Set CAN stream format. This command has been deprecated.</td></tr>
<tr><td>46</td><td>Set the CAN baudrate
Packet data: CAN communication baudrate</td></tr>
</table>

<table>
<tr><td></td><td>Format: 32-bit integer
<table>
<tr><td>Correction strength</td><td>Value</td></tr>
<tr><td>10Kbit/s</td><td>0x00000000</td></tr>
<tr><td>20Kbit/s</td><td>0x00000008</td></tr>
<tr><td>50Kbit/s</td><td>0x00000010</td></tr>
<tr><td>125Kbit/s</td><td>0x00000018</td></tr>
<tr><td>250Kbit/s</td><td>0x00000020</td></tr>
<tr><td>500Kbit/s</td><td>0x00000028</td></tr>
<tr><td>800Kbit/s</td><td>0x00000030</td></tr>
<tr><td>1Mbit/s</td><td>0x00000038</td></tr>
</table>
Macro name: SET_CAN_BAUDRATE
Response: ACK (success) or NACK (error)
Default value: 1Mbit/s</td></tr>
</table>

Additional Settings

47	Get the currently firmware version.
48	Set gyroscope alignment bias **Packet data:** Gyroscope alignment bias **Format:** Float 3-vector **Macro name:** SET_GYR_ALIGN_BIAS **Response:** ACK (success) or NACK (error) **Default value:** 1Mbit/s
49	Get gyroscope alignment bias **Packet data:** Gyroscope alignment bias **Return format:** Float 3-vector **Macro name:** GET_GYR_ALIGN_BIAS
50	Set gyroscope alignment matrix **Packet data:** Gyroscope alignment matrix **Format:** Float 3x3 matrix **Macro name:** SET_GYR_ALIGN_MATRIX **Response:** ACK (success) or NACK (error) **Default value:** (1, 0, 0) (0, 1, 0) (0, 0, 1)
51	Get gyroscope alignment matrix **Packet data:** Gyroscope alignment matrix

<table>
<tr><td></td><td>Return format: Float 3x3 matrix
Macro name: GET_GYR_ALIGN_MATRIX</td></tr>
<tr><td>52</td><td>Reserved</td></tr>
<tr><td>53</td><td>Reserved</td></tr>
<tr><td>54</td><td>Reserved</td></tr>
<tr><td>55</td><td>Reserved</td></tr>
<tr><td>56</td><td>Reserved</td></tr>
<tr><td>57</td><td>Reserved</td></tr>
<tr><td>58</td><td>Reserved</td></tr>
<tr><td>59</td><td>Reserved</td></tr>
<tr><td>60</td><td>Set raw data low-pass
Packet data: Low pass strength (1.0 is weakest / disabled)
Format: Float
Macro name: SET_RAW_DATA_LP
Response: ACK (success) or NACK (error)
Default value: 1.0</td></tr>
<tr><td>61</td><td>Get raw data low-pass
Packet data: Low pass strength (1.0 is weakest / disabled)
Return format: Float
Macro name: GET_RAW_DATA_LP</td></tr>
<tr><td>62</td><td>Set CANOpen mapping (only for LPMS-CU module)
Packet data: CANOpen mapping
Format: The mapping data consists of 8 integer words. Each of these words represents the assignment of half a CANOpen transmission object / message (TPDO) to specific sensor data. In more detail:
<table>
<tr><th>Message name</th><th>Position in configuration mapping message</th></tr>
<tr><td>TPDO 1 (msg. 0x180, bytes 0-3)</td><td>0</td></tr>
<tr><td>TPDO 1 (msg. 0x180, bytes 5-7)</td><td>1</td></tr>
<tr><td>TPDO 2 (msg. 0x280, bytes 0-3)</td><td>2</td></tr>
<tr><td>TPDO 2 (msg. 0x280, bytes 5-7)</td><td>3</td></tr>
<tr><td>TPDO 3 (msg. 0x380, bytes 0-3)</td><td>4</td></tr>
</table>
</td></tr>
</table>

<table>
<tr><td></td><td>
<table>
<tr><td>TPDO 3 (msg. 0x380, bytes 5-7)</td><td>5</td></tr>
<tr><td>TPDO 4 (msg. 0x480, bytes 0-3)</td><td>6</td></tr>
<tr><td>TPDO 4 (msg. 0x480, bytes 5-7)</td><td>7</td></tr>
</table>
<p>Assignments work according to the following table:</p>
<table>
<tr><th>Sensor data</th><th>Assignment index</th></tr>
<tr><td>Angular velocity X</td><td>0</td></tr>
<tr><td>Angular velocity Y</td><td>1</td></tr>
<tr><td>Angular velocity Z</td><td>2</td></tr>
<tr><td>Euler angle X</td><td>3</td></tr>
<tr><td>Euler angle Y</td><td>4</td></tr>
<tr><td>Euler angle Z</td><td>5</td></tr>
<tr><td>Lin. acceleration X</td><td>6</td></tr>
<tr><td>Lin. acceleration Y</td><td>7</td></tr>
<tr><td>Lin. acceleration Z</td><td>8</td></tr>
<tr><td>Magnetometer X</td><td>9</td></tr>
<tr><td>Magnetometer Y</td><td>10</td></tr>
<tr><td>Magnetometer Z</td><td>11</td></tr>
<tr><td>Quaternion W</td><td>12</td></tr>
<tr><td>Quaternion X</td><td>13</td></tr>
<tr><td>Quaternion Y</td><td>14</td></tr>
<tr><td>Quaternion Z</td><td>15</td></tr>
<tr><td>Accelerometer X</td><td>16</td></tr>
<tr><td>Accelerometer Y</td><td>17</td></tr>
<tr><td>Accelerometer Z</td><td>18</td></tr>
</table>
Macro name: SET_CAN_MAPPING
Response: ACK (success) or NACK (error)
Default value: 0x00000007 00000006 00000005 00000004 00000003 00000002 00000001 00000000
</td></tr>
<tr><td>63</td><td>Get CANOpen mapping (only for LPMS-CU module)
Packet data: CANOpen mapping
Return format: See command 62
Macro name: GET_CAN_MAPPING</td></tr>
<tr><td>64</td><td>Set CANOpen heartbeat frequency (only for LPMS-CU module)
Packet data: CANOpen heartbeat frequency</td></tr>
</table>

<table>
<tr><td></td><td>Format: Integer. In detail:
<table>
<tr><td>Heartbeat frequency</td><td>Identifier</td></tr>
<tr><td>5Hz</td><td>0x00000000</td></tr>
<tr><td>1Hz</td><td>0x00000001</td></tr>
<tr><td>0.5Hz</td><td>0x00000002</td></tr>
<tr><td>0.2Hz</td><td>0x00000003</td></tr>
<tr><td>0.1Hz</td><td>0x00000004</td></tr>
</table>
Macro name: SET_CAN_HEARTBEAT
Response: ACK (success) or NACK (error)
Default value: 0x00000000</td></tr>
<tr><td>65</td><td>Get CAN heartbeat (only for LPMS-CU module)
Packet data: CANOpen heartbeat frequency
Return format: See command 64
Macro name: GET_CAN_HEARTBEAT</td></tr>
<tr><td>66</td><td>Reset sensor data timestamp to 0
Packet data: none
Format: none
Macro name: RESET_TIMESTAMP
Response: ACK (success) or NACK (error)
Default value: none</td></tr>
</table>

Example Communication

In this section we will show a practical example of how a communication sequence could be structured. A similar sequence is also used in the LpmsControl software to poll data from the LPMS-B. Our standard LpBUS protocol is used.

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

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

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	Timestamps
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	xxxxxxxxh	Orientation quaternion q0
51-54	xxxxxxxxh	Orientation quaternion q1
55-58	xxxxxxxxh	Orientation quaternion q2
59-62	xxxxxxxxh	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

IX. OpenMAT LIBRARY

Overview

Introduction

OpenMAT is the software package delivered with a 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 also a network interface (OpenMAT network) that allows applications to communicate with each other to exchange sensor information. OpenMAT consists of the following components:

1. **LpSensor library**: OpenMAT applications above are based on the LpSensor library. This library contains classes that allow easy access to the functionality of the LPMS devices. Contained classes and their most important methods as well as usage examples are described further on in this chapter.

2. **LpmsControl application**: This application is used to control the basic LPMS device functionality. It can be used to connect to multiple sensors, adjust parameters and record sample data. Data is graphically represented as line graphs or as a 3D cube that changes orientation according to the data received from a sensor.
   PLEASE NOTE: LpmsControl is also used to do updates of the LPMS firmware. We will explain further details below. IMPORTANT: We recommend the users to use the high performance mode of a PC in order to guarantee the LpmsControl application performance.

3. **OpenMAT server**: The OpenMAT server manages the communication of applications on the OpenMAT network. Please contact LP-Research for examples of how to use the OpenMAT network.

OpenMAT is available as binary release and as source code release. If you would like to use the included applications as is, please use the binary release. This is suggested as the easiest way to start as it allows you to test the functionality of your sensor.

We also offer a source code release that allows you to re-compile or modify the code. In case you would like to include OpenMAT with your own applications it is recommended to take a look at the source code release.

Application Installation

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

1. When you purchase one of our sensors the latest version of the library at the time is also contained on the included CD. Please be aware that development on OpenMAT is ongoing and therefore the version on the CD might become outdated. Therefore please check on our website for updates.
2. Start OpenMAT-x.x.x-Setup.exe (x.x.x being the latest version number).
3. Follow the displayed installation instructions.
4. Switch the LPMS device on.
5. Start LpmsControl from the OpenMAT entry in the start menu.
6. Check if your device is listed in the 'Discovered devices' list.
7. Mark the device you would like to connect to by clicking on it in the list and push the connect button.
8. After a few seconds you should be seeing data being streamed from your sensor.

LpmsControl Software Operation

Overview

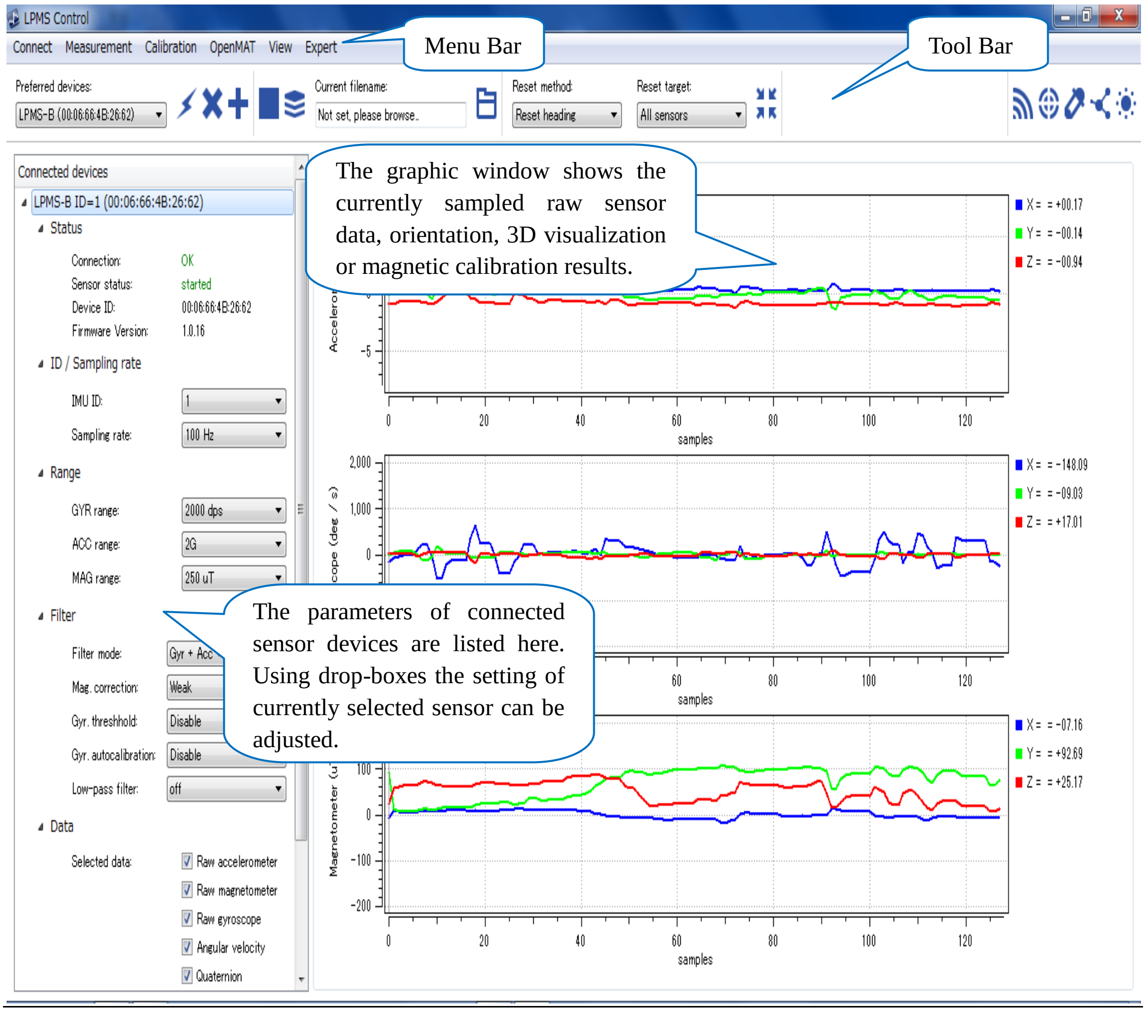
The LpmsControl application allows users to control various aspects of the LPMS-B sensor that can be used to:

- list all LPMS devices that are discovered in the system.
- connect to up to 7 sensors simultaneously by one Bluetooth receiver.
- adjust the sensor parameters (sensor range etc.).
- reset orientation and reference vectors.
- initiate gyroscope and magnetometer calibration.
- display the acquired data in real-time either as line graphs or a 3D cube.
- record data from the sensors to a CSV data file.
- upload new firmware and in-application-programming software to the sensor.

As LpmsControl is part of the open-source OpenMAT library its source code is available and can be modified by the user. Most parts of the code are documented, so that a user can also use parts of LpmsControl to write their own sensor control code.

GUI Elements

Application window



Preferred devices: LPMS-B (00:06:66:4B:26:62)

Current filename: Not set, please browse..

Reset method: Reset heading

Reset target: All sensors

LPMS-B ID=1 (00:06:66:4B:26:62)

- Status
  - Connection: OK
  - Sensor status: started
  - Device ID: 00:06:66:4B:26:62
  - Firmware Version: 1.0.16
- ID / Sampling rate
  - IMU ID: 1
  - Sampling rate: 100 Hz
- Range
  - GYR range: 2000 dps
  - ACC range: 2G
  - MAG range: 250 uT
- Filter
  - Filter mode: Gyr + Acc
  - Mag. correction: Weak
  - Gyr. threshhold: Disable
  - Gyr. autocalibration: Disable
  - Low-pass filter: off
- Data
  - Selected data: ☑ Raw accelerometer ☑ Raw magnetometer ☑ Raw gyroscope ☑ Angular velocity ☑ Quaternion

X = +00.17 Y = -00.14 Z = -00.94

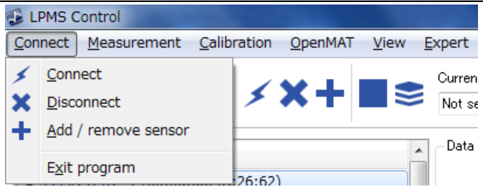
X = -148.09 Y = -09.03 Z = +17.01

X = -07.16 Y = +92.69 Z = +25.17

The graphic window shows the currently sampled raw sensor data, orientation, 3D visualization or magnetic calibration results.

The parameters of connected sensor devices are listed here. Using drop-boxes the setting of currently selected sensor can be adjusted.

Menu Bar



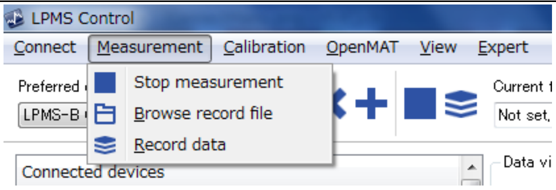
Connect menu

Connect - Connects to sensor selected in ‘Preferred devices’ list.

Disconnect - Disconnects sensor currently selected in the ‘Connected devices’ list.

Add / remove sensor – add new discovered sensor from the “Discovered devices” list to “Preferred devices” list, or remove the currently selected sensor from “Preferred devices” list.

Exit program - Exits the application.

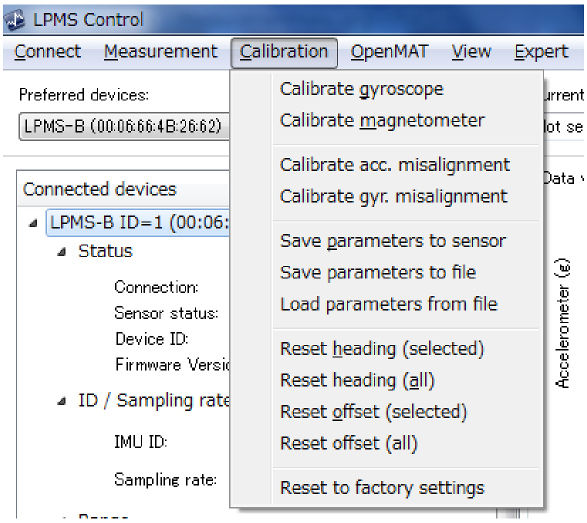


Measurement menu

Stop measurement - Starts or stops a measurement (depending if measurement is already in progress or not).

Browse record file – locates or create a csv format file for saving the recorded data.

Record data - Starts or stops data recording (depending if recording is already in progress or not).



Calibration menu

Calibrate gyroscope – Starts the gyroscope calibration (users should follow the insturctions introdued in section "*Calibration Methods*")

Calibrate magnetometer – Starts the magnetic calibration (users should follow the insturctions introdued in section "*Calibration Methods*"). IMPORTANT: Euler angle transmission must be turned on for the magnetometer calibration to succeed.

Calibrate acc. misalignment – Starts the accelerometer calibration. (users should follow the insturctions introdued in section "*Calibration Methods*").

Calibrate gyr. misalignment – reserved by LP-RESEARCH.

Save parameters to sensor – Saves the current parameter settings and calibration results into the sensor flash.

Save parameters to file – Saves the current parameter settings and calibration results into a .txt file in your local host system.

Load parameters from file – Loads the previously saved calibration results in a local txt file into the sensor flash.

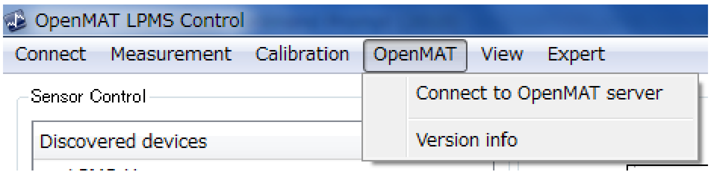
Reset heading (selected) – Sets the magnetometer and accelerometer reference of the LP-Filter of the currenly selected sensor in the "Connected devices" list to the current measured magnetic and acceleration vector. This function should be used after calibrating the magnetometer.

Reset heading (all) – Sets the magnetometer and accelerometer reference of the LP-Filter of all the sensors in the "Connected devices" list to the current measured magnetic and acceleration vector. This function should be used after calibrating the magnetometer.

Reset offset (selected) - Resets the current orientation of the selected sensor in the "Connected devices" list as zero-orientation. Further rotations will be the difference rotation between the zero-orientation and the currently measured orientation.

Reset offset (all) - Resets the current orientation of all the sensors in the "Connected devices" list as zero-orientation. Further rotations will be the difference rotation between the zero-orientation and the currently measured orientation.

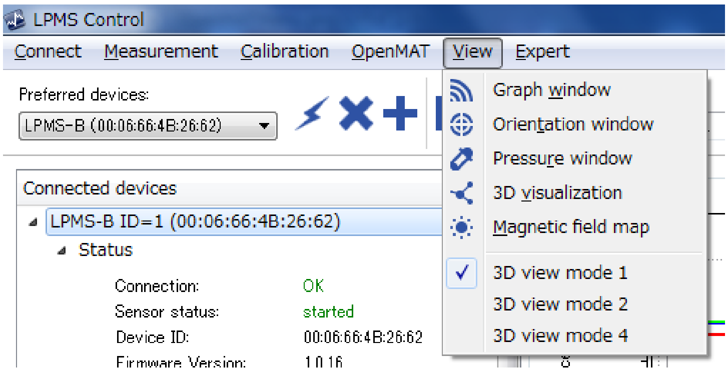
Reset to factory settings – Recovers the settings of all the connected sensors to the factory default values.



OpenMAT menu

Connect to OpenMAT server - This is used for human model simulator. The human model simulator allows the construction of 3D models with links and joints that can be associated with orientation sensors on the OpenMAT network. Momentarily this application is still in an experimental state. PLEASE NOTE: This function is reserved by LP-RESEARCH.

Version info – Version information of the LpmsControl software.



Preferred devices: LPMS-B (00:06:66:4B:26:62)

Connected devices

LPMS-B ID=1 (00:06:66:4B:26:62)

Status

Connection: OK

Sensor status: started

Device ID: 00:06:66:4B:26:62

Firmware Version: 1.0.16

View menu

Graph window- Switches the middle graph window to show the raw sensor data.

Orientation window – Switches the middle graph window to show the orientation data.

Pressure window - Switches the middle graph window to show the pressure data.

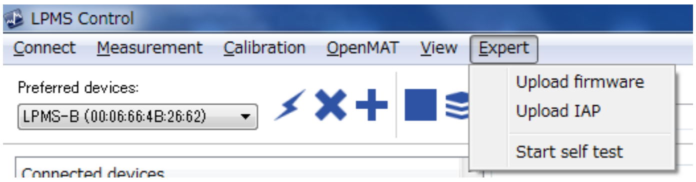
3D visualization - Switches the middle graph window to 3D cube view.

Magnetic field map – Switches the middle graph window to magnetic field map view.

3D view mode 1 - Switches the middle graph window to 1 window for one sensor 3D visualization.

3D view mode 2 - Switches the middle graph window to 2 windows for 2 sensors 3D visualization.

3D view mode 4 - Switches the middle graph window to 4 windows for 4 sensors 3D visualization.



Expert menu

Upload firmware - Starts firmware upload. IMPORTANT: Only upload authorized firmware that you received from LP-RESEARCH. Uploading a wrong firmware file can make the sensor in-operable.

Upload IAP - Uploads a new in-application programmer. PLAESENOTE: This is reserved by LP-RESEARCH and should not be used by user.

Start self test - Starts a self test for checking the basic functionalities of the sensor.

Device Discovery

The discovery of Bluetooth devices usually takes up to 20s, depending on your system, so please be patient, if the LPMS-B device does not show up in the "Discovered devices" list immediately. If the LPMS-B device cannot be discovered by the initial discovering, please try to push the "Scan devices" button and search again. After your devices have been discovered, push the "Add devices" button to add your discovered devices to the "Preferred devices" list, and save the setting by clicking "Save devices" button.

Connecting and Disconnecting a Device

To connect a LPMS-B sensor click on the corresponding item in the 'Preferred devices' list and click the 'Connect' button. The sensor should now become listed in the 'Connected devices' list. While establishing the connection, the 'Connection status' indicator shows 'connecting…'. Once a connection has been successfully established, the connection status will change 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'.

PLEASE NOTE: The LpmsControl software is using the windows Bluetooth stack driver. Please verify your Bluetooth receiver in the host system whether it is using the correct drivers.

Sensor Parameter Adjustment

Sensor parameters can be adjusted using the item in the "Connected devices" list that corresponds to the target device. Using the drop down lists the following parameters can be set:

- **IMU ID**: The device OpenMAT ID.
- **Sampling rate**: System sampling frequency
- **GYR range**: Gyroscope measurement range

- **ACC range**: Accelerometer measurement range
- **MAG range**: Magnetometer measurement range
- **Filter mode**: The filter mode setting (see also the previous section "*Filter Settings*")
- **Mag. correction**: The magnetic correction setting (see also the previous section "*Filter Settings*")
- **Linear acc cor**.: The linear acceleration correction setting (see also the previous section "*Filter Settings*")
- **Rotational acc cor**.: The rotational acceleration correction setting (see also the previous section "*Filter Settings*")
- **Gyr. threshold**: To enable or disable the gyroscope threshold function (see also the previous section "*Filter Settings*")
- **Gyr. autocalibration**: To enable or disable the gyroscope auto calibration function (see also the previous section "*Filter Settings*")
- **Low-pass filter**: To set up the coefficient of the low pass filter (see also the previous section "*Filter Settings*")
- **Selected data**: check the data types you want to acquire.

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.

Reset of Orientation and Reference Vectors

The offset of the orientation measured by the sensor can be set to the currently acquired orientation by clicking on the "Reset offset" functions of LpmsControl. The newly reported orientation data will be the orientation difference between this zero-orientation and the un-adjusted (raw) orientation measurement.

The accelerometer and magnetometer reference vector is reset by clicking on the "Reset heading" function of LpmsControl. Before resetting the heading reference, PLEASSE DO complete the magnetic calibration. While initiating the heading reference reset, point the y axis of the sensor roughly in north direction and hold the x-y plane of the sensor parallel to the ground.

IMPORTANT: The adjustment of the heading reference vectors is very important for accurate orientation measurements. The sensor will be delivered to you in a pre-calibrated state. However, as the direction of the earth magnetic field slightly varies at different place, it might be necessary to reset the reference. To save the new heading reference after a successful reset, select "Save parameters to sensor" function of LpmsControl. Normally the setting of the heading reference vectors when done accurately only needs to be done once.

How to Upload New Firmware

IMPORTANT: Please follow the following steps carefully when you are updating the sensor firmware. Any mistake operation might result in a failure of firmware update and disable sensor functionality.

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 in your local host system.
4. Select “Upload firmware” function in the “Expert” menu.
5. Click OK and select the new firmware file. Be careful that you select the right file which should be named as LpmsBFirmwareX.X.X.bin by LP-RESEARCH.
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.
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 from file” function from the calibration menu of LpmsControl to recover the previous sensor calibration results.
11. Choose the “Save parameters to sensor” function from the calibration menu of LpmsControl to save the previous sensor calibration results into sensor flash.
12. The whole procedure is done. Make sure everything works as expected. If there is anything unexpected, please contact LP-RESEARCH by Email.

The LpSensor Library

Building Your Application

The LpSensor library contains classes that allow a user to integrate LPMS devices into their own applications. The library is a Windows 32-bit C++ library for MS Visual C++ (express) 2010. Should you require a binary for the library for other operating systems 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.
ftd2xx.dll	The FTDI library to communicate with an LPMS over USB.

To compile the application please do the following:

1. Include LpmsSensorManagerI.h before you access any LpSensor classes.
2. Add LpSensor.lib (or LpSensorD.lib if you are compiling in debug mode) to the ist of linked libraries for your application.
3. Make sure that you set a path to LpSensor.dll / LpSensorD.dll, PCANBasic.dll and ftd2xx.dll reside so that the runtime file of your application can access them.

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.

IMPORTANT: 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><code>LpSensor* addSensor(int mode, string deviceId)</code></td></tr>
<tr><td>Parameters</td><td>mode 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>
deviceId 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>Pointer to LpSensor object.</td></tr>
<tr><td>Description</td><td>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.

<table>
<tr><td>Method name</td><td><code>int getSensorStatus(void)</code></td></tr>
<tr><td>Parameters</td><td>None</td></tr>
<tr><td>Returns</td><td>Sensor state identifier:
<table>
<tr><th>Macro</th><th>Sensor state</th></tr>
<tr><td><code>SENSOR_STATUS_PAUSED</code></td><td>Sensor is currently paused.</td></tr>
<tr><td><code>SENSOR_STATUS_RUNNING</code></td><td>Sensor is currently acquiring data.</td></tr>
<tr><td><code>SENSOR_STATUS_CALIBRATING</code></td><td>Sensor is currently calibrating.</td></tr>
<tr><td><code>SENSOR_STATUS_ERROR</code></td><td>Sensor has detected an error.</td></tr>
<tr><td><code>SENSOR_STATUS_UPLOADING</code></td><td>Sensor is currently receiving new firmware data.</td></tr>
</table></td></tr>
<tr><td>Description</td><td>Retrieves the current sensor status.</td></tr>
</table>

<table>
<tr><td>Method name</td><td><code>int getConnectionStatus(void)</code></td></tr>
<tr><td>Parameters</td><td>None</td></tr>
<tr><td>Returns</td><td>Connection status identifier:
<table>
<tr><th>Macro</th><th>Sensor state</th></tr>
<tr><td><code>SENSOR_CONNECTION_CONNECTED</code></td><td>Sensor is connected.</td></tr>
<tr><td><code>SENSOR_CONNECTION_CONNECTING</code></td><td>Connection is currently being established.</td></tr>
<tr><td><code>SENSOR_CONNECTION_FAILED</code></td><td>Attempt to connect has failed.</td></tr>
<tr><td><code>SENSOR_CONNECTION_INTERRUPTED</code></td><td>Connection has been interrupted.</td></tr>
</table></td></tr>
<tr><td>Description</td><td>Retrieves the current connection status.</td></tr>
</table>

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 startCalibrateMag(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

<table>
<tr><td></td><td>
<table>
<tr><td><code>GYR_RANGE_2000DPS</code></td><td>Gyr. Range = 2000 deg./s</td></tr>
</table>
<code>PRM_ACC_RANGE</code>
<table>
<tr><th>Macro</th><th>Description</th></tr>
<tr><td><code>ACC_RANGE_2G</code></td><td>Acc. range = 2g</td></tr>
<tr><td><code>ACC_RANGE_4G</code></td><td>Acc. range = 4g</td></tr>
<tr><td><code>ACC_RANGE_8G</code></td><td>Acc. range = 8g</td></tr>
<tr><td><code>ACC_RANGE_16G</code></td><td>Acc. range = 16g</td></tr>
</table>
<code>PRM_MAG_RANGE</code>
<table>
<tr><th>Macro</th><th>Description</th></tr>
<tr><td><code>MAG_RANGE_130UT</code></td><td>Mag. range = 130uT</td></tr>
<tr><td><code>MAG_RANGE_190UT</code></td><td>Mag. range = 190uT</td></tr>
<tr><td><code>MAG_RANGE_250UT</code></td><td>Mag. range = 250uT</td></tr>
<tr><td><code>MAG_RANGE_400UT</code></td><td>Mag. range = 400uT</td></tr>
<tr><td><code>MAG_RANGE_470UT</code></td><td>Mag. range = 470uT</td></tr>
<tr><td><code>MAG_RANGE_560UT</code></td><td>Mag. range = 560uT</td></tr>
<tr><td><code>MAG_RANGE_810UT</code></td><td>Mag. range = 810uT</td></tr>
</table>
</td></tr>
<tr><td>Returns</td><td>None</td></tr>
<tr><td>Description</td><td>Sets a configuration parameter.</td></tr>
</table>

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

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

Connecting to the an LPMS-B device

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

main()
{
```

```
        // Get a LpmsSensorManager instance
        LpmsSensorManagerI* manager = SensorManagerFactory();

        // Connect 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) {
                float q[4];

                // Read quaternion data
                lpms->getQuaternion(q);

                // Do something with the data
                // ..
        }

        // After doing the work, remove the initialized sensor
        sm->removeSensor(lpms);

        // Delete LpmsSensorManager object
        delete manager;
}
```

Setting and Retrieval of Sensor Parameters

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

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

Sensor and Connection Status Inquiry

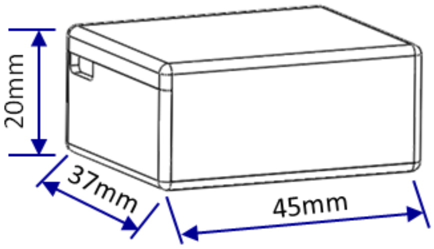
```
/* Retrieves current sensor status */
int status = getSensorStatus();
```

```

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;
}
```

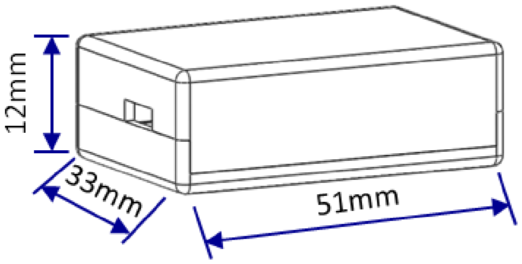
In case you have any further questions regarding the programming interface please contact LP-RESEARCH directly.

X. MECHANICAL INFORMATION

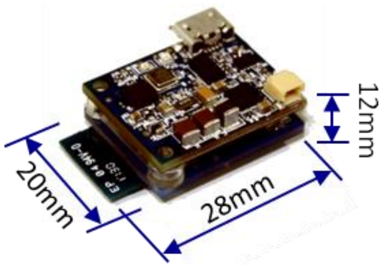
LPMS-B Dimension



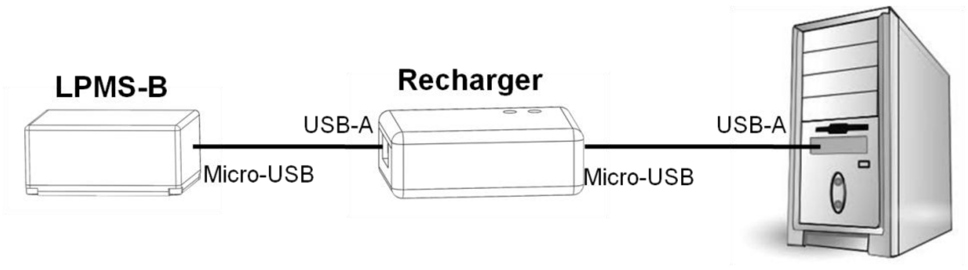
LPMS-B Recharger Dimension



LPMS-B OEM Dimension



LPMS-B and Recharger Connection



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