SHR-S360

Strapdown Heading Reference

With Gyro Stabilized Heading

Owner's Manual

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Watson Industries prides itself on solving customer problems and serving their needs in a timely fashion. This manual is intended to facilitate this goal and to provide written information about your product. We ask that you carefully read this manual. Becoming familiar with the manual will help you understand the product's capabilities and limitations, as well as provide you with a basic understanding of its operation. If, after reading the manual, you require further assistance, do not hesitate to call Watson Industries with your questions and comments.

CAUTION!

Watson Sensors are rugged devices that have been used successfully in a number of harsh environments. The components have been qualified to withstand a mechanical shock of 200g 's or greater, and most enclosures provide an added level of protection. However, dropping a sensor from waist height onto a hard floor can cause a shock level of 600g's. At this level, damage is likely to occur.

Introduction

The Strapdown Heading Reference provides a slaved compass function. It uses a 3-axis fluxgate magnetometer, a solid-state rate gyro, and a microprocessor. The unit measures the Earth's Magnetic Field with a precision 3-axis fluxgate magnetometer and uses tilt information (bank and elevation) from three accelerometers for coordinate transformations. The heading information is susceptible to disturbance by acceleration since the angle sensors are sensitive to dynamic accelerations. The gyro stabilization reduces this sensitivity and still maintains a high accuracy by slaving to the heading output.

Product Description

Watson Industries SHR-S360 uses solid-state fluxgate magnetometer, gyro and silicon accelerometers. Interface to the microprocessor is done through a 16-bit A/D converter. The solid state vibrating structure angular rate gyro used in this system provides extremely high reliability, low power consumption, shock resistance and exceptional stability. There are no physical adjustments required by the user. All of the primary transducers are locked into position during manufacture. Adjustments are made with the aid of PC-based maintenance software, which communicates with the SHR-S360 via the RS-232 serial connection. Calibration is achieved by using the maintenance software to store data in non-volatile memory within the SHR-S360.

Installation

Orientation:

The base plate of the unit is to be mounted on top of a horizontal surface with the connector toward the forward direction of the vehicle. The SHR drawing, with wire call outs, is located in Figure 2. The SHR is a rugged device and will withstand harsh environments. However, due attention needs to be paid to the nature of the sensor and its prime function, which is to measure attitude and motion. The SHR responds to the motion under investigation.

Mounting:

A mounting plate is provided for a flat surface mount. Use non-magnetic hardware. Ideally, the unit should be installed at least 12 inches away from all significant magnetic materials. Some highly magnetic materials require even greater separation from the SHR sensor. The unit may be adhesively mounted at any of its surfaces. If high shock loads are expected (greater than 10G or repeated shocks greater than 5G), the appropriate shock mounting should be used to prevent damage. Vibration isolation should be used for use in 2.5G or greater vibration environments.

Environment:

Avoid mounting sites that are subject to significant temperature variation over the duration of the test. Temperature variation will induce significant rate sensor bias drift, which will reflect in poor attitude accuracy.

This is a magnetic device. Use non-magnetic hardware. Watson Industries provides brass connectors with the device. If the unit is being installed in a vehicle, ship, etc., some calibration will still be required. Calibration software is available on our website at http://www.watson-gyro.com

For shipboard applications, install the sensor near the center of gravity. For all applications, it is preferable to install the device where linear dynamic effects are minimized.

This is a magnetic sensitive device. Use non-magnetic hardware.

Power:

This unit has an internal regulator to allow operation over a wide voltage input range. Best operation is obtained at either 12 or 24 VDC level, although operation is fully satisfactory down to 10 VDC and up to 30 VDC. Power consumption of the unit is less than 3 Watts. The SHR power system is isolated from the SHR signal system. Internal capacitors are provided to remove a reasonable level of power line noise, however, capacitors should be added for long power line wiring or if noise is induced from other loads on the circuit.

Theory of Operation

The Earth's Magnetic Field can be described as a Vector T located in the horizontal geographic coordinate system $O_{\zeta\xi\eta}$ (See Figure 1)

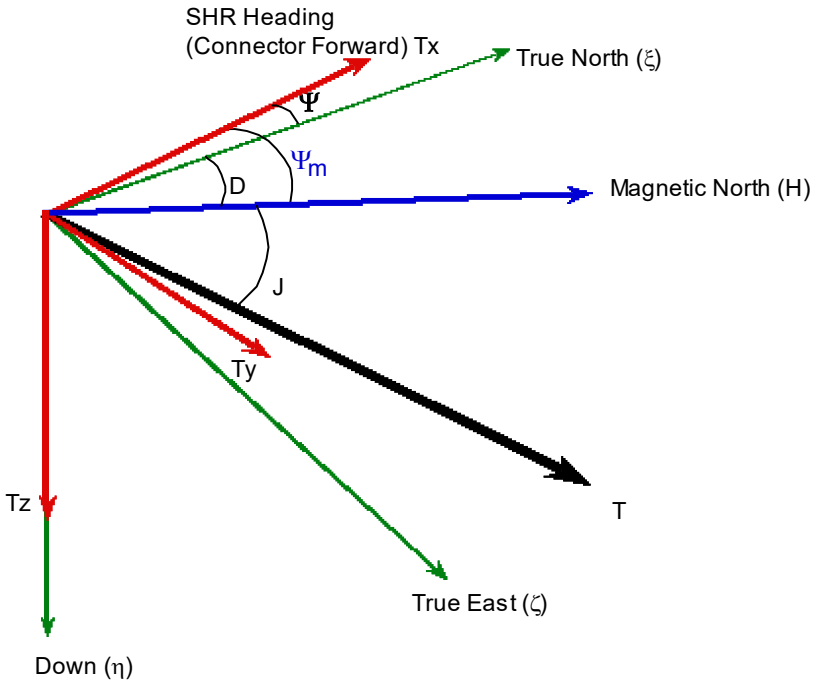


Figure 1

Where:

T - Earth's Magnetic Field Vector
H - Magnetic North
Tx & Ty - Vector of Horizontal Components of Earth's Magnetic Field
T_Z - Vector of Vertical Component of Earth's Magnetic Field
J - Magnetic Dip Angle
D - Magnetic Declination (also known as Magnetic Variation)
Ψ_m - Magnetic Heading
Ψ - True North Heading
ξ - True North Axis (geographic)
η - Down Axis (geographic)
ζ - True East Axis (geographic).

The microprocessor transforms the x, y, and z measurements to a horizontal geographical coordinate system and calculates the magnetic heading Ψ_m as:

$$\Psi_m = \text{Atan}\ (-Y_T/X_T)$$

Where X_T, and Y_T are coordinate transformed to the horizontal system for Fluxgate Magnetometer measurement. To calculate D, the SHR must be turned to true North or its true direction needs to be known.

$$D = \Psi - \Psi_m$$

If you are only interested in the variation of declination, you do not need to know True Heading. However, when the measurements are taken, the SHR has to be oriented in the same Azimuth position. For more details about declination measurement, please contact Watson Industries. Watson Industries provides software for heading calibration in your installation package because each unit will likely have significant magnetic deviations. Your location on the globe will also cause error in the magnetic heading (Ψ_m) by Magnetic Dip Angle (J) and Leveling Error (ΔL). The following is a general relationship:

$$\Delta\Psi_m = tgJ * \Delta L$$

Table 1 lists a general relationship between Magnetic Dip Angle and latitudes on the Earth's surface.

Latitude	30	45	56	70	80
Dip Angle	45	60	68	80	85

Table 1. Magnetic Dip Angle versus Latitude

Specifications

Attitude			
	Range: Bank	±180°	
	Range: Elevation	±90°	
	Resolution:	0.02°	Binary mode (14 bit)
	Analog Scale Factor:	18°/V	±10V Bank
			±5V Elevation
	Accuracy: Static	±0.5°	
Magnetic Heading			
	Range:	0° - 360°	
	Resolution:	0.02°	Binary mode (14 bit)
	Analog Scale Factor:	18°/V	±10V Output
†	Accuracy: Static	±1.5°	
*	Accuracy: Dynamic	2%	
Angular Rate			
	Range: Yaw	±100°/sec	
	Resolution:	0.025°/sec	Binary mode (14 bit)
	Scale Factor Accuracy:	2%	
	Bias: Yaw	< 0.3°/sec	
	Non-Linearity:	< 0.05%	Full scale range
	Bandwidth:	20 Hz	
Acceleration			
	Range: X, Y, Z	±10g	
	Resolution:	4mg	
	Scale Factor Accuracy:	1%	
	Bias:	< 10mg	
	Non-Linearity:	0.1%	Full scale range
	Bandwidth:	3 Hz	
Magnetic			
	Range: X, Y, Z	±1000 mGauss	
	Resolution:	0.1 mGauss	Binary mode (14 bit)
	Scale Factor Accuracy:	1%	
	Bias:	< 5 mGauss	
	Non-Linearity:	< 0.01%	Full scale range
	Bandwidth:	10 Hz	
Environmental			
	Temperature: Operating	-40°C to +85°C	
	Temperature: Storage	-55°C to +85°C	
	Vibration: Operating	2.5g rms	20 Hz to 2 KHz
	Vibration: Survival	10g rms	20 Hz to 2 KHz
	Shock: Survival	500g	10mS ½ sine wave
Electrical			
	Frame Rate:	284.44 Hz	Maximum
	Startup Time: Data	5 sec	
	Startup Time: Fully operational	10 sec	
	Input Power:	10 to 35VDC	2.3W
	Input Current:	150mA @ 12VDC	85mA @ 24VDC
	Digital Output:	RS-232	
	Analog Output:	±10VDC	
	Analog Output Impedance:	300 Ohm	Per line
Physical			
	Axis Alignment:	< 0.25°	
	Size: Including Mounting Flanges	3.24"W x 5.78"L x 2.38"H	8.2 x 14.7 x 6.0 (cm)
	Weight:	19.4 oz (1.2lb)	550 grams (0.6Kg)
	Connection: RS-232	9 pin female "D" subminiature	
	Connection: Power / Analog Outputs	9 pin male "D" subminiature	

* Actual accuracy can be calculated as the listed percentage multiplied by the change in value over the entire dynamic maneuver.

† Static heading accuracy is dependent on the magnetic environment.
This sensor will meet or exceed this spec within the 48 contiguous United States.

- Specifications are subject to change without notice.
- This product may be subject to export restrictions. Export Classification ECCN 7A994.

RS-232 Output Format

The nominal RS-232 output consists of a string of decimal ASCII characters sent asynchronously at regular intervals. By default, the string is sent at 9600 baud with eight data bits, one stop bit and no parity. The mating connector for the RS-232 is a 9 Pin Female D-Sub. The RS-232 signal is referenced to signal ground. The number of strings sent per second depends on the baud rate and the output format. The maximum rate is 250 strings per second. See Appendix B for information on how to change the data string. The contents of a typical string are formed as follows:

1. A single letter and a space used to indicate the start of the data string. The letter "I" indicates the start of an inertial data string. The letter "R" indicates the start of a Reference data string. If the letter is in lower case ("i" or "r"), an error over-range condition is indicated (see below).

2. A seven character string representing the bank angle starting with a "+" or a "-", followed by three digits, a decimal point, one digit and a space for up to ±180.0 degrees.

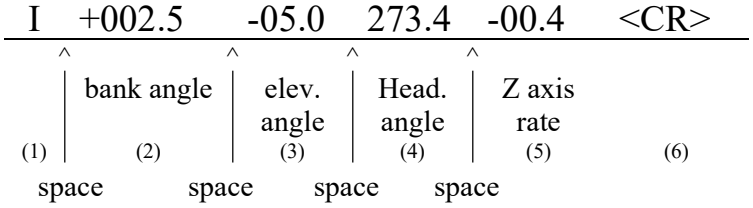
3. A six character string representing the elevation angle starting with a "+" or a "-", followed by two digits, a decimal point, one digit and a space for up to ±90.0 degrees.

4. A six character string representing the relative heading angle by three digits, a decimal point, one digit and a space for zero to 359.9 degrees.

5. A six character string representing the Z axis angular rate starting with a "+" or a "-", followed by two digits, a decimal point, one digit and a space for up to ±99.9 degrees/second.

6. The string is terminated by a carriage return. There will then be a short interval with no data transmission before the next string begins.

Example:



The string transmission rate can be improved by reducing the amount of information (data items) transmitted. The data items transmitted can be changed by using special commands to modify the EEPROM of the unit (see Appendix B). In addition, more channels are available for output (see Appendix A).

The system is protected from inadvertent write-over of the EEPROM by requiring two spacebar commands during the initialization interval to access the EEPROM or related functions.

The baud rate may be changed from the nominal value of 9600 baud by modifying the default value in the EEPROM of the unit to 38.4K, 19.2K, or 4800 baud.

A text header that is sent by the SHR during initializations identifies the unit by part number and by serial number and gives the date of last calibration. Additionally, a line of text characters that identifies the data channel columns is sent if the serial output is set to ASCII decimal. This whole message can be temporarily (or as a default) suppressed or restored by a "*" command from the interfacing computer.

Data transmission sent by the SHR can also be suppressed or restored by a "+" command from the interfacing computer.

The error over range condition is indicated by the use of a lower case "i" or "r" when the calculated attitude or heading error exceeds the ranges listed above. Internal functions that require these error values are disabled while the condition exists. The system will continue to operate in an extended time constant mode with a low level of error accumulation until the condition is cleared. Occasional blips of this condition are expected with no detectable affect on the resulting data.

The other output format available is a binary format. The binary format provides generally the same information as the decimal ASCII format, but in a compact binary file format. In this format, there are nominally 13 words sent that represent 6 fourteen bit output channels followed by a carriage return. Again, the channels may be reduced to improve the update rate by using special commands to modify the EEPROM of the unit. This format is for highly experienced users only. See Appendix D for more information. Consult the factory for further details.

RS-232 Input Commands

The RS-232 input commands are provided for the purpose of unit test and installation set-up. Use the same parameters that are used as for the RS-232 output (9600 baud ASCII nominal, or as reset in the units EEPROM).
Note: Many commands require command or "Double spacebar mode" in order to access them. For more information on how to activate Command Mode, see the instructions in Appendix B.
These commands are available to the user (others are used at the factory for alignment and calibration).

1. An "R" or "r" will set the outputs (analog and serial) to their Reference Command modes. This will also disable the logic input Reference Command, Coast Mode Command and Invalid Velocity Command until the next time the unit is powered up. This mode is used in installation to physically align the unit. Double spacebar at initialization is required for access to this command.

2. An "I" or "i" will clear the Reference Command mode if it had been set by the serial input. This is the default mode at power up and is the normal operating mode. This will also disable the logic input Reference Command, Coast Mode Command and Invalid Velocity Command until the next time the unit is powered up. Double spacebar at initialization is required for access to this command.

3. An “F” will disconnect the references from the attitude system and is the Coast Mode Command. This coast mode is used to make the system ignore the references during high maneuvers and brief disturbances. This mode is not intended for use except in brief intervals, since errors will grow geometrically. This will also disable the logic input Reference Command, Coast Mode Command and Invalid Velocity Command until the next time the unit is powered up.

4. A “K” will clear the Free Mode Command.

5. An “!” will reinitialize the unit. Further, the access to initialization is inhibited such that a spacebar command must be sent within 2.5 seconds of the “!” command for initialization to be engaged.

6. An “L” sent when the sensor is in the decimal mode will return a line of characters that will identify the data columns. Command mode is required for access to this command.

7. An “_” command will change the output format to decimal ASCII. This change is made non-volatile in the unit on EEPROM by keying in the quote (“) character. Double spacebar at initialization. Command mode is required for access to this command.

8. A “^” command will change the output format to binary. This change is made non-volatile in the unit on EEPROM by keying in the quote (“) character. Double spacebar at initialization. Command mode is required for access to this command.

9. A “:” command will toggle the output to send a frame of data upon receiving any non-command character (On to Off; Off to On). This change is made non-volatile in the unit on EEPROM by keying in the quote (“) character. Double spacebar at initialization Command mode is required for access to this command.

Note: To test if this command is active when the unit is not flowing data, send a carriage return (or any other non-command character to the sensor, and observe if there is any output.

10. A “+” command will suppress or restore the transmission of data. This command will toggle the data transmission (On to Off; Off to On). Double spacebar at initialization. Command mode is required for access to this command.

Note: It is possible for both the “:” and the “+” commands to be active at the same time. The “+” command determines whether the sensor is allowed to transmit data. So in this case, the “:” command must also be turned off to allow the free flow of data.

11. An “*” command will suppress or restore the initialization message in the Decimal ASCII mode. This command will toggle the transmitting of the text header during initialization (On to Off; Off to On). This change is made non-volatile in the unit on EEPROM by keying in the quote (“) character. Double spacebar at initialization. Command mode is required for access to this command.

12. An “&” command brings up a menu to select baud rates. This change is made non-volatile in the unit on EEPROM by keying in the quote (“) character. Double spacebar at initialization. Command mode is required for access to this command.

13. The “N” command is used to offset the heading output from any given angle to North. This can be used as a calibration means, but is only recommended for small adjustments. To use this command, first send an “R” command on the keyboard to place the sensor into reference mode (see above). Second, aim the vehicle platform to the North reference required. Third, send an upper case “N” to the unit to enter the adjustments. This is a nonvolatile correction. It can be used with any North reference and will help to correct for local magnetic distortions. Command mode is required for access to this command.

The commands “~”, “@”, “#”, “$”, ‘(“, “)”, “{“, “}”, “|”, “<”, “>” and “?” are used by the Watson factory to calibrate the unit and should be used only with the assistance of the factory. If an undesired function is called, a “Q”, and sometimes Escape or a Delete will interrupt the command and return to operation with the least disturbance to the system. All other unspecified characters such as carriage return, line feed and space are ignored by the system.

If there are problems with the system “hanging up” during the binary output mode, check for crosstalk between the serial transmit and receive line in your installation. In addition, check to see that the communications program used is not sending an echo. This will not happen in the decimal or hexadecimal modes because command characters recognized by the system are not produced in those modes.

Analog Outputs

Analog signals are output from a 14 bit digital to analog converter through an operational amplifier. Each analog output has a 300 ohm resistor in series to eliminate oscillations from high capacitance loads. The output range for all of the analog output channels is ±10 Volts with respect to the common signal ground. The outputs include:

Signal	Pin	Range	Output Range	0 VDC	Scale Factor
Bank	6	±180°	±10V	0°	18°/s/V
Elevation	7	±90°	±5V	0°	18°/s/V
Heading	8	0-360°	±10V	0° (South)	18°/V

Note that the analog switches are disabled after certain serial commands are sent to the unit. This prevents software/hardware switch conflicts.

Connections / Dimensions

9 –Pin Male Power/ Analog Output Connector

Pin	Description
1	Power Ground
2	+ 12 or + 24 VDC
3	Factory use (Do not Connect)
4 - 5	No Connection
6	Bank Analog Output
7	Elevation Analog Output
8	Heading Analog Output
9	Signal Ground

9 –Pin Female RS-232 Connector

Pin	Description
1	No Connection
2	TXD*
3	RXD
4	Shorted to pin 6
5	Signal Ground
6	Shorted to pin 4
7	Shorted to pin 8
8	Shorted to pin 7
9	+5V Power **

*User Receives data on this line

** Power for optional wireless (Bluetooth) adapter

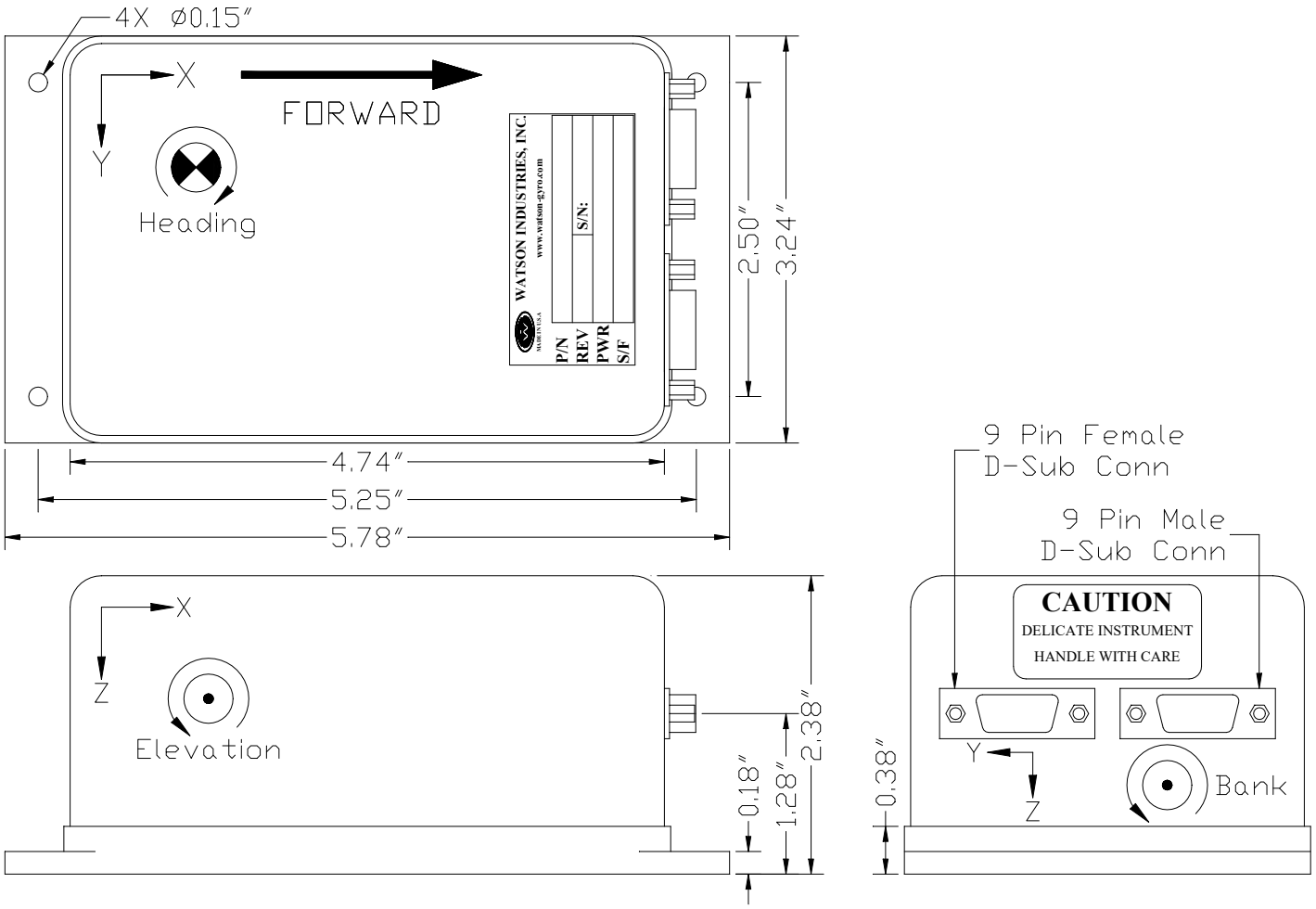


Figure 2 SHR-S360

Warning

Rough handling or dropping of this unit is likely to cause damage. Over-voltage and/or miswiring of this unit will cause damage. This unit should be protected against prolonged exposure to high humidity and/or salt air environments.

DISCLAIMER

The information contained in this manual is believed to be accurate and reliable; however, it is the user's responsibility to test and to determine whether a Watson Industries' product is suitable for a particular use.

Suggestion of uses should not be taken as inducements to infringe upon any patents.

WARRANTY

Watson Industries, Inc. warrants, to the original purchaser, this product to be free from defective material or workmanship for a period of one full year from the date of purchase. Watson Industries' liability under this warranty is limited to repairing or replacing, at Watson Industries' sole discretion, the defective product when returned to the factory, shipping charges prepaid, within one full year from the date of purchase. The warranty described in this paragraph shall be in lieu of any other warranty, express or implied, including but not limited to any implied warranty of merchantability or fitness for a particular purpose.

Excluded from any warranty given by Watson Industries are products that have been subject to abuse, misuse, damage or accident; that have been connected, installed or adjusted contrary to the instructions furnished by seller; or that have been repaired by persons not authorized by Watson Industries.

Watson Industries reserves the right to discontinue models, to change specifications, price or design of this product at any time without notice and without incurring any obligation whatsoever.

The purchaser agrees to assume all liabilities for any damages and/or bodily injury that may result from the use, or misuse, of this product by the purchaser, his employees or agents. The purchaser further agrees that seller shall not be liable in any way for consequential damages resulting from the use of this product.

No agent or representative of Watson Industries is authorized to assume, and Watson Industries will not be bound by any other obligation or representation made in connection with the sale and/or purchase of this product.

PRODUCT LIFE

The maximum expected life of this product is 20 years from the date of purchase. Watson Industries, Inc. recommends the replacement of any product that has exceeded the product life expectation.

Customer Service

All repairs, calibrations and upgrades are performed at the factory. Before returning any product, please contact Watson Industries to obtain a Returned Material Authorization number (RMA).

Return Address & Contact Information

Watson Industries, Inc.
3035 Melby Street
Eau Claire, WI 54703
ATTN: Service Department
Telephone: (715) 839-0628 Fax: (715) 839-8248 email: support@watson-gyro.com

Returning the Product

Product shall be packaged making sure there is adequate packing around all sides. Correspondence shall include:

- Customer's Name and Address
- Contact Information
- Equipment Model Number
- Equipment Serial Number
- Description of Fault

It is the customer's responsibility to pay all shipping charges from customer to Watson Industries, including import and transportation charges.

Appendix A

The following outputs are available via the RS-232 serial link. Their full-scale ranges are listed for both decimal and binary format.

Inertial Output	Label	Full Scale Decimal	Full Scale Binary
Time Since Reset	TM	65535 seconds	16383 seconds
Bank	BK	±75.0º	±180º
Elevation	EL	±75.0º	±180º
Relative Heading	HG	359.9º	±180º
X Acceleration	XA	±9.99 g	±10 g
Y Acceleration	YA	±9.99 g	±10 g
Z Acceleration	ZA	±9.99 g	±10 g
Z Angular Rate	ZR	±99.9 º/s	±200 º/s
Heading Rate	HR	±99.9 º/s	±200 º/s
X Magnetometer	XM	±999.9 mGauss	±1000 mGauss
Y Magnetometer	YM	±999.9 mGauss	±1000 mGauss
Z Magnetometer	ZM	±999.9 mGauss	±1000 mGauss
X inclinometer (simulated)	XI	±179.9º	±180º
Y Inclinometer (simulated)	YI	±89.9º	±180º
Temperature	TP	-40º to 88ºC	-40º to 88ºC (7 bit)
Status Bits	ST	1 byte	1 byte
Flag Bits	FL	1 byte	1 byte

The Status Bits contain the following information:

Bit	Description (If Set)
0	Bank Error Flag
1	Elevation Error Flag
2	Heading Error Flag
3	Not Set
4	Not Set
5	South Heading Flag
6	Checksum Error Flag
7	Not Set

Example: The status channel output in ASCII Decimal is “040”

Octal Digit	0		4			0		
Binary Equivalent	0	0	1	0	0	0	0	0
Status Bit #	7	6	5	4	3	2	1	0

Bit 7	Reset	
Bit 6	Reset	No Checksum Error
Bit 5	Set	South Heading Flag
Bit 4	Reset	
Bit 3	Reset	
Bit 2	Reset	No Heading Error
Bit 1	Reset	No Elevation Error
Bit 0	Reset	No Bank Error

The Flag Bits contains the following information:

Bit	Description (If Set)
0-2	Show the current system time constant, using the following equation: $TC=2^{(\text{Flag Value} + 1)}$
3	Reference Command
4	Command Mode
5	Free Mode
6	Not Set
7	Not Set

Example: The flag channel output in ASCII Decimal is 022”

Octal Digit	0		2			2		
Binary Equivalent	0	0	0	1	0	0	1	0
Status Bit #	7	6	5	4	3	2	1	0

Bit 7	Reset	
Bit 6	Reset	
Bit 5	Reset	Unit is not in Coast Mode
Bit 4	Set	Unit is in Command Mode
Bit 3	Reset	Unit is not in Reference Mode
Bit 2	Reset	Flag value =010 (binary) = 2
Bit 1	Ser	The Current System Time Constant
Bit 0	Reset	$= 2^{(\text{Flag Value} + 1)} = 2^{(2 + 1)} = 2^{(3)} = 8$ seconds

Appendix B

Activating Command Mode (Double Spacebar Mode)

1) Connect the unit to a DC power source that is off.
2) The viewing computer needs a valid bi-directional RS-232 serial port. Connect the serial port of the Watson sensor to the computer's serial port.
3) Open a terminal program (such as HyperTerminal) to interface with the unit. The default baud rate of the unit is 9600 baud. Make sure the computer's serial port is open.
4) Power-on the unit. A startup message will be transmitted by the unit and will appear in the terminal window unless it has been suppressed (See RS-232 Input Commands above).
5) During initialization, hit the space bar twice within close succession.

   Note: The sensor initialization time begins after the startup message is transmitted. Typically, this time period lasts 5 seconds, but could be as long as 127 seconds depending on your sensor.

6) Wait until after initialization is finished. At this point, command mode will be activated and the unit will accept keyboard commands.

   Note: Most Watson sensors have initialization times that are shorter than 30 seconds. Any extra keystrokes (other than two spacebars) sent during initialization will deactivate command mode.

**It can often take a few attempts to get the hang of step 5. Repeat steps 4-6 until successful.

Determining Output Channels

1) Activate Command Mode (See above).
2) To determine which channel present, first type '&'.

This will bring up the main menu:

```
TYPE IN THE NUMBER OF YOUR SELECTION (OR 'Q' TO QUIT):
  1 = ADJUST TIME CONSTANTS
  2 = SET OUTPUT CHANNELS
  3 = LIST CURRENT OUTPUT CHANNEL SELECTION
  4 = SET NEW BAUD RATE
```

3) Typing in '3' will show which channels are currently active.

Setting Output Channels

1) Activate Command Mode (See above).
2) To change which channels are output type '&' (this will bring up the main menu again)
3) Now type '2' to set up channels.
   The following message will appear:

```
TO SET FOR OUTPUT FOR ANY OF THE FOLLOWING DATA ITEMS, PRESS Y
TO AVOID ANY OF THE FOLLOWING DATA ITEMS, PRESS N
TO QUIT AND DISREGARD ANY OTHER DATA, PRESS Q

*** DO YOU WANT TO PROCEED?  (Y/N/Q)
```

4) To proceed type 'Y'. Stop this process by typing either 'N' or 'Q'. If 'Y' is pressed, each channel will come up one at a time.

For example:

```
DO YOU WANT OUTPUT OF BANK ANGLE?
```

5) Type 'Y' to output the channel, type 'N' to remove the channel
   After the last data channel is listed, this message will appear:

```
Y = GOBACK, N = INSTALL DATA & QUIT, Q = QUIT
  DO YOU WANT TO TRY TO SET DATA AGAIN?
```

6) To accept the new channels type 'N'. Typing a 'Y' will start the command menu sequence over.
   Typing a 'Q' at any time in the sequence will quit without updating the channels.
   Changes made will not change the non-volatile settings. To make these new settings the default value, send a Quotation Mark (").

7) Press the space bar after quitting or updating the new channels to restart the data flow.

Adjust Time Constants

We recommend consulting the factory before altering sensor time constants.

Setting Baud Rate

1) Activate Command Mode (See above).
2) Type '&'(this will bring up the main menu again).
3) Typing in '4' will allow the user to change the baud rate.
4) Change the baud rate to a new setting.

To change to 38,400 Baud, type ‘1’.
To change to 19,200 Baud, type ‘2’.
To change to 9,600 Baud, type ‘3’.
To change to 4,800 Baud, type ‘4’.

The baud rate change will take effect immediately. To make the new baud rate the default setting, send a quote symbol (“) using the new baud rate. Otherwise the old baud rate will return the next time the unit is powered up.

Note: The baud rate of the software that is communicating to the sensor will need to be changed to match the new setting.

5) Press the space bar to resume data transmission.

The factory settings for serial communications are 9.6K baud with 8 bits and one stop bit, no parity.

Appendix C

Sensor Test Instructions

B Sensor Test Instructions - Tests within this section have been designed to provide assurance of the correct operation of the sensor without the use of elaborate test equipment other than a means of accurately observing the outputs. The “HyperTerminal” program provides a suitable means of observing the outputs.

B.1 Parameter Exercise Test
After successful initialization, move the sensor in all three axes using both linear and angular motion, making certain each of the measurement parameters responds to the motion.

B.2 Angular Displacement Scale Factor Tests
After successful initialization, place the sensor on a level surface and observe the pitch and roll displacement signals. Place the sensor on a pivot and incline the sensor by a small angle of 6 to 10 degrees in the pitch. A suitable pivot is a 10mm square bar attached to the sensor base plate with adhesive tape. Give the "Reference" command. The signals from the simulated pendulums will be outputted instead of the normal angular displacement signals. Careful note should be taken of the angles indicated in the reference mode. The sensor should then be tipped on the pivot into the other stable position and the angle again noted.

The procedure of tipping the sensor should be repeated with the "Reference" command removed. The angles obtained should agree with those noted with the reference.

The procedure should be repeated in the Roll axis. The same pivot may be used, but some care will be needed to avoid exceeding the 100 degree/second limit. A more appropriate size of bar would be 5mm square.

B.3 Accelerometer Scale Test
After successful initialization, place the sensor on a level surface and monitor the acceleration outputs. Observe the X and Y outputs will read near zero while the Z axis will read minus 1G within the accuracy of the sensor.

Set the sensor at a 45 degree angle to the horizontal in Pitch only. The value of X and Z acceleration should read 0.71G, within the accuracy of the sensor, while the Y acceleration should remain at the level value. The values of Forward, Lateral and Vertical Acceleration should remain at the values when level.

Repeat the test for the roll axis of the sensor. Under this test, Y and Z acceleration will read 0.71G and the X acceleration will retain its value at level.

B.4 Earth Axes Test
After successful initialization, place the sensor on a level surface, and observe the pitch and roll displacement signals as well as acceleration outputs.

The Forward, Lateral and Vertical outputs should correspond to the X, Y and Z outputs to within the accuracy of the sensor.

Set the sensor at a 45 degree angle to the horizontal in pitch only, taking care not to move the sensor at an angular rate of more than 100 deg/sec.
The Forward, Lateral and Vertical output should not change from the values, when level, by more than the accuracy of the sensor.

Move the sensor through a further 45 degrees in pitch such that the base plate is now vertical, again taking care not to exceed the 100 deg/sec limit. The sensor should then be rotated about the vertical and the Yaw output will respond accordingly.

The test should then be repeated for the Roll axis.

Appendix D

Binary Data Format

There is one binary word per output parameter.

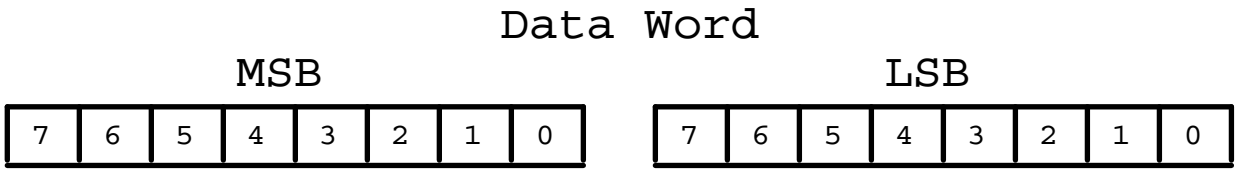
Example 1: The Unit is seeing these conditions:

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
15.0˚	-5.0˚	315.0˚	-002 mGauss	+314 mGauss	+567 mGauss

Binary output Format:

Word1	Word2	Word3	Word4	Word5	Word6	<CR> byte
0x85AA	0xFE9C	0xF080	0xFFF2	0x998F	0xA4A4	0x0D

Word 1 is the 2 byte Bank Angle
Word 2 is the 2 byte Elevation Angle
Word 3 is the 2 byte Magnetic Heading Angle
Word 4 is the 2 byte X Magnetometer
Word 5 is the 2 byte Y Magnetometer
Word 6 is the 2 byte Z Magnetometer



Bit 7 of the MSB is set to 1. Bits 6 to 0 of the MSB are the upper 7 bits of the data. (sign plus 6 bits of data)
Bit 7 of the LSB is set to 1. Bits 6 to 0 of the LSB are the lower 7 bits of the data.

As the data words are received, the LSB is shifted left to shift out the 7th bit (always set to 1). The MSB is then connected to the LSB as a 16 bit word. This word is then shifted left to shift out the 7th bit (always set to 1). What remains is a signed fractional word with a resolution of 13 bits plus a sign bit.

To convert binary data:

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x85AA	0xFE9C	0xF080	0xFFF2	0x998F	0xA4A4

Need split each word into two bytes:

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x85 0xAA	0xFE 0x9C	0xF0 0x80	0xFF 0xF2	0x99 0x8F	0xA4 0xA4

Remove the most significant bit from each byte:

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x05 0x2A	0x7E 0x1C	0x70 0x00	0x7F 0x72	0x14 0x0F	0x24 0x24

Shift lower byte left once (to remove 1 bit space between bytes):

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x05 0x54	0x7E 0x38	0x70 0x00	0x7F 0xE4	0x14 0x1E	0x24 0x48

Shift lower & upper bytes left once (to remove 1 bit space a top of high byte):

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x0A 0xA8	0xFC 0x70	0xE0 0x00	0xFF 0xC8	0x28 0x3C	0x48 0x90

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
0x0AA8	0xFC70	0xE000	0xFFC8	0x283C	0x4890

Convert from hexadecimal to decimal counts:

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
2728	64624	57344	65480	10300	18576

Correct bank, elevation, and magnetometer for the sign
If >32767 then subtract 65536 (2^{16}) from the data

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
2728	-912	57344	-56	10300	18576

Convert to units: counts x scale factor
For bank & elevation: Scale factor is: 180 ˚ / 32768 counts
For Heading: Scale factor is: 360 ˚ / 65536 counts
For Accelerations: Scale factor is 1.000g / 32768 counts
For Magnetometer: Scale factor is 1000mg / 32768 counts

Multiply the data (in counts) by the scale factor
Convert to units: counts * scale factor
For Bank Scale factor is 180˚/ (2^{15}) or 32768 counts = 2728 counts * (180˚/2^{15} counts) = 14.985 ˚
For Elevation Scale factor is 180˚/ (2^{15}) or 32768 counts = -912 counts * (180˚/2^{15} counts) = -5.010 ˚
For Heading Scale factor is 360˚/ (2^{16}) or 65536 counts = 57344 counts * (360˚/2^{16} counts) = 315.000 ˚
For X Mag: Scale factor is 1000 mG/ (2^{15}) or 32768 counts = -56 counts * (1000 mG /2^{15} counts) = -1.71 mG
For Y Mag: Scale factor is 1000 mG/ (2^{15}) or 32768 counts = 10300 counts * (1000 mG /2^{15} counts) = 314.33 mG
For Z Mag: Scale factor is 1000 mG/ (2^{15}) or 32768 counts = 18576 counts * (1000 mG /2^{15} counts) = 566.89 mG

Bank	Elevation	Heading	X Mag	Y Mag	Z Mag
14.985 ˚	-5.010 ˚	315.000 ˚	-1.71 mGauss	314.33 mGauss	566.89 mGauss