DYNAMIC MEASUREMENT SYSTEM

OWNER'S MANUAL

PART NUMBER: DMS-SGP01
GPS Module & Antenna

WATSON INDUSTRIES, INC.
3035 MELBY STREET
EAU CLAIRE, WI 54703

Phone: (715) 839-0628

Fax: (715) 839-8248

Email: support@watson-gyro.com

TABLE OF CONTENTS

1. Introduction 3
2. Product Description 3
3. Installation 4
   - Orientation 4
   - Mounting 4
   - Environment 4
   - Power / Connectors 4
   - Calibration 4
4. Operation 5
   - Initialization 5
   - Normal Operation 5
   - Special Operation Modes 5

   Reference Mode 5
   Free Mode 6
   Hold Mode 6
   Command Mode 6
   - Interface 6

   RS-232 Output Format 6
   RS-232 Input Commands 8
   Analog Outputs 10
   Analog Inputs 10
   Speed Inputs 10
   Input Logic Commands 11
5. Specifications 12
   - Table 1: Connections / Dimensions 13
   - Figure 1 DMS-SGP01 13
   - Figure 2 GPS Antenna Dimensions 14
   - Warning 15
6. Customer Service 16
7. Appendix A 17
8. Appendix B 19
   - Activating Command mode or Double Spacebar Access to commands 19
   - Determining Output Channels 19
   - Setting Output Channels 20
   - Setting Output Format 20
   - Setting Heading Mode 21
   - Setting Velocity Mode 21
   - Setting Altitude Correction: 22
   - Setting Baud Rate 22
9. Appendix C 23
10. Appendix D 25

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 500g '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 Dynamic Measurement System (DMS) is a solid-state sensor that provides the user with dynamic measurements of angular attitude and angular rate, together with linear acceleration, in three (3) mutually perpendicular planes (see Figure 2). A unique feature is the two sets of acceleration measurements. One set gives sensor acceleration with respect to the sensor mounting face while the other set resolves the motion into horizontal and vertical components, irrespective of the sensor attitude. This allows the earth's gravitational field to be isolated from the measurement of sensor motion. This System consists of a DMS unit with an internal GPS module and one GPS antenna.

Product Description

Watson Industries DMS uses solid-state angular rate sensors and silicon accelerometers. Interface to the microprocessor is done through a 16-bit A/D converter. The solid-state angular rate sensors used in this system provide high reliability, excellent performance, and low cost. 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 DMS via the RS-232 serial connection. Calibration is achieved by using the maintenance software to store data in non-volatile memory within the DMS. The DMS-SGP01 differs from a “standard” DMS with the addition of a GPS antenna and receiver. This allows the DMS to output track heading instead of relative heading. The GPS receiver also provides a vehicle velocity that is used to improve accuracy in high dynamic environments. This is most useful with wheeled vehicles. This unit outputs Latitude & Longitude based on the position of the antenna.

This unit will operate in two heading modes. In the first mode, the DMS uses the GPS module. In this mode, the unit outputs track heading, and the vehicle speed is digital. The heading needs to be in the GPS Track mode and velocity input needs to be in the GPS Ground Track mode. (See Appendix A Setting Velocity & Heading Modes)

In the second mode, the unit does not use the GPS module, it outputs relative heading, and the vehicle speed is an analog input. The heading needs to be in the relative mode and velocity input needs to be in the Analog input mode.
(See Appendix A Setting Velocity & Heading Modes).

A vehicle speed input is used to assist in the correction of errors. It is also included in the parameter set that is available for serial output. Although its use is not always required, it is highly recommended that this signal be supplied to the DMS. The unit ordinarily acquires this data from the GPS system but is user configurable to acquire velocity from an analog input. The analog signal is scaled to 40 KPH per volt. Forward motion should produce a positive signal with respect to signal ground. Many other velocity scale factors can be handled through simple changes in the scale factor stored in the EEPROM in the microprocessor. This can be done with a PC and the assistance of the factory.

Installation

Orientation

The connector face of the unit must point in the forward direction. The DMS drawing, with wire call outs, is located in Table 1. The DMS 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.

Mounting

The DMS-SGP01 has four 0.15" diameter mounting holes for 6-32 screws (See Figure 1). If high shock loads are expected (greater than 10G or repeated shocks greater than 5G), appropriate shock mounting should be used to prevent damage. Vibration isolation should be used if operation in 2.5G or greater vibration environments is expected.

The GPS antenna has a magnetic mount with two M2.6 mounting holes (See Figure 2) and needs an unobstructed view of the sky to receive signals from GPS satellites. The antenna needs to be mounted on a minimum 6" x 6" ground plane. Nothing nearby the antenna can be higher than this ground plane.

Environment

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

Power / Connectors

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, although operation is fully satisfactory down to 10 VDC and up to 35 VDC. Power draw of the unit is about 4.4 Watts. 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. The DMS power system is isolated from the DMS signal system. The mating connector for the Power/Analog Output Connector is a 25 Pin female D-Sub.

Note: The signal ground is connected to case.

The SMA GPS antenna connector is on the front of the case. This type of connector should be torqued to a maximum of 5 in-lbs. The GPS Antenna is supplied with +5 VDC, less than 40mA. The minimum gain requirement for these antennas is 20 dB. For more information on the connectors and pinout of the DMS-SGP01, see Table 1.

Calibration

The DMS is calibrated at the factory before it is shipped to the user. It is recommended that the unit be returned to the factory annually for evaluation and recalibration.

Operation

Initialization

Ideally, the DMS should be stationary and level when it is turned on. If not, the sensor readings may not be accurate after initialization. The time required for the initialization process is not the same for every type of DMS, but typically takes 4 to 5 seconds. During this time, a message is sent from the unit via the RS-232 serial link. This message gives information about the DMS such as the full model number, serial number, and software revision. The message can be read by using a terminal program or by using the terminal mode of Watson Industries' communication software.

The DMS can also be "re-initialized" after it has been turned on. This is especially useful if the sensor has been used in severe maneuvers that have over-ranged the angular rate sensors and caused significant errors to accumulate. Sometimes re-initializing the unit will allow for a faster recovery than waiting for the error correction routines to correct the sensor readings. There are several ways to re-initialize the DMS. For more information, see the Interface section of this manual.

Normal Operation

During normal operation, the DMS will output highly accurate inertial data for the user to interpret. This data is transmitted in several different ways. The most common way to acquire data from the DMS is to use the RS-232 serial output. There are two RS-232 output formats: decimal and binary. The exact formatting structure is discussed later in the Interface section of this manual. The DMS generates fourteen different data items for output: X, Y, and Z rates, X, Y, and Z accelerations, Bank, Elevation, and Heading, and Forward, Lateral, and Vertical Accelerations, Velocity, Latitude & Longitude. Any combination of these data items can be selected for transmission via the RS-232 serial link. The DMS also has analog outputs (see Interface section) that can be used to send data to the user.

In normal operation, the DMS takes data from its internal rate sensors and integrates in a closed loop system, with the accelerometers as a long-term reference, to generate Bank, Elevation and Heading data. In most cases, these algorithms provide for very stable and accurate output signals; however, the user should be aware that exceeding the normal ranges of the sensors would affect accuracy. For example, while custom DMS units may have differing ranges, the rate sensors in a typical DMS have a maximum rate of 100°/s. Care should be taken not to exceed this rate because the closed loop system will receive inaccurate data. This will result in errors in the angle output signals.

While this DMS is "all attitude", the accuracy deteriorates rapidly when its forward direction is within about 5 degrees of vertical. Operation for any extended period of time at more than 60 degrees from level is not recommended. If these few operational precautions are observed, the DMS should provide very accurate data for a wide variety of applications.

Special Operation Modes

Reference Mode

This mode is usually used for calibration or diagnostics. When in reference mode, the DMS will output data generated directly from the sensor reference signals rather than as a product of the closed loop integration used for normal operation. This mode provides sensor information similar to normal operation mode with the following differences:

Bank and Elevation are obtained directly from the accelerometers - no gyro stabilization.
Track Heading is directly from the GPS reference.
Angular Rate Sensors bias corrections are not updated.

The reference mode can be selected either through the command mode, or by an analog logic command. Note that reference mode is never a default setting. It must be re-selected when re-powering the unit.

Free Mode

While in Free Mode, the DMS will output data from the sensors without correction by the references. For example, the Bank Angle data output in Free Mode is calculated directly from the X-axis Rate Sensor. In this case, the angle is a direct integration of the roll rate. Free Mode can be used to totally reject effects from dynamic accelerations, but accuracy degrades with time. It is intended for use over periods of up to a minute at a time. This mode provides sensor information similar to normal operation mode with the following differences:

Bank, Elevation and Heading are obtained directly from the rate sensors alone.
Relative Heading from last known heading is used.
Angular Rate Sensors bias corrections are not updated.

Free mode can be accessed either through command mode, or by an analog logic command. Note that free mode is never a default setting. It must be re-selected when re-powering the unit. The user should not enter free mode until after the DMS is initialized and its readings are stable.

Hold Mode

This mode inhibits bias adjustments to the rate sensors. It is intended for short-term use only since leaving biases uncorrected will allow errors to accumulate over time. The accumulating bias error will result in small attitude errors. Hold mode can provide better performance in highly dynamic environments such as continuous circling over several minutes time. The user should not enter hold mode until after the DMS is initialized and its readings are stable.

Command Mode

In this mode, the DMS will output sensor data normally unless it receives a valid command character. Once a command is received, the DMS will send data in response and await the next command. Using this mode, the user can retrieve the EEPROM map, adjust baud rates, adjust output formats, and many other operational settings of this sensor. Having access to this information makes the Command Mode useful in assisting the factory to remotely troubleshoot operational problems that may occur. For more details, see the RS-232 Input Commands section later in this manual.

Interface

The DMS has analog, digital logic, and digital serial interface capabilities.

RS-232 Output Format

The standard RS-232 output consists of a string of decimal ASCII characters sent asynchronously at regular intervals. Nominally, 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 Male 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 71.11 strings per second. See Appendix A 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 “G” indicates the start of an inertial data string with successful GPS data input. The letter “I” indicates the start of an inertial data string with GPS disabled or absence of valid GPS data. The letter “R” indicates the start of a Reference data string. If the letter is in lower case (“g”,“i”, or “r”), an error over-range condition is indicated (see below).

2. A nine character string representing the Universal Time (UTC) starting with six digits, a decimal point, one digit and a space for up to 235959.9 Hours minutes seconds tenth seconds (HHMMSS.S). Note: The field is filled with asterisks when the data is invalid. (“******.*”)

3. 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 ±179.9 degrees.

4. 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 ±89.9 degrees.

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

6. A seven character string representing the Velocity starting with a “+” or a “-“, followed by three digits, a decimal point, one digit and a space for up to ±399.9 Km/Hr. Note: The field is filled with asterisks when the data is invalid. (“****.*”)

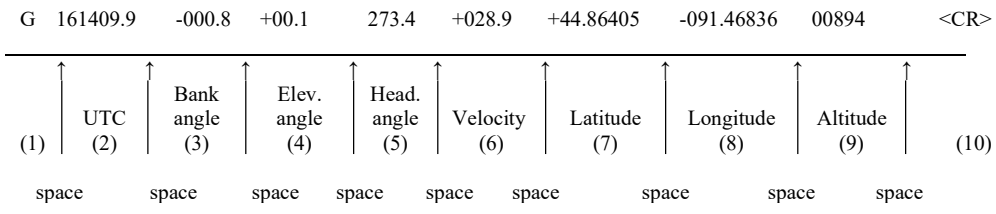
7. A ten character string representing the Latitude starting with a “+” or a “-“, followed by two digits, a decimal point, five digits and a space for up to ±89.99999 degrees. Note: The field is filled with asterisks when the data is invalid. (“+**.*****”)

8. A eleven character string representing the Longitude starting with a “+” or a “-“, followed by three digits, a decimal point, five digits and a space for up to ±179.99999 degrees. The field is filled with asterisks when the data is invalid. (“+***.*****”)

9. A six character string representing the Altitude by five digits and a space for up to 21500 feet. The field is filled with asterisks when the data is invalid. (“*****”).

10. 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 A). 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 is sent by the DMS during initializations that identifies the unit by part number and by serial number and gives the date of last calibration. 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 DMS can also be suppressed or restored by a "+" command from the interfacing computer. This is used when only analog data is used as a noise reduction measure.

The error over-range condition is indicated by the use of a lower case "i", "g" 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. While maneuvering the vehicle, occasional blips of this condition are expected with no detectable effect on the resulting data.
The other output format available is a binary format. In this mode, the unit provides generally the same information as the decimal ASCII format, but in a compact binary message. 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. 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 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, replacing the Inertial mode. This will also disable the logic input Reference Command and Free Mode Command until the next time the unit is powered up. This mode is used in installation to physically align the unit. Command mode is required for access to this command.

2. An "I" or "i" sets the unit to Inertial mode. Switching to this mode clears the Reference Command mode. This will also disable the logic input Reference Command and Free Mode Command until the next time the unit is powered up. Command mode is required for access to this command.

3. An "F" or "f" will disconnect the references from the attitude system and is the Free Mode Command. Free 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 and Free Mode Command until the next time the unit is powered up. This command does not require Command mode to be in effect.

4. An “H” or “h” will remove bias correction from the system and is the Hold Mode Command. This mode is useful is highly dynamic situations that may last for a few minutes. Hold mode should not be used for more than a few minutes, because errors can accumulate. This command does not require Command mode to be in effect.

5. A “K” or “k” will clear the Free Mode Command and the Hold Mode Command. This command does not require command mode to be in effect.

6. 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. This command does not require Command mode to be in effect.

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. 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. 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. 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). 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. The “&” command calls a menu which allows any of several parameters to be set. From this menu, the user can change system time constants, data channels for serial output, heading source, velocity source and baud rate. Command mode is required for access to this command.

The commands “~”, “@”, “#”, “$”, ‘(“, “)”, “{“, “}”, “|”, “<”, “>”,“?” and “S” 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 cross talk 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. Please note that the signal and power ground are isolated from one another.

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	14	±180°	±10V	0°	18°/s/V
Elevation	15	±90°	±5V	0°	18°/s/V
Heading	16	0-360°	±10V	0° (North)	18°/s/V
Roll Rate (X Axis)	23	±100°/s	±10V	0°/s	10°/s/V
Pitch Rate (Y Axis)	24	±100°/s	±10V	0°/s	10°/s/V
Yaw Rate (Z Axis)	25	±100°/s	±10V	0°/s	10°/s/V
X Acceleration	17	±10g	±10V	0g	1g/V
Y Acceleration	18	±10g	±10V	0g	1g/V
Z Acceleration	19	±10g	±10V	0g	1g/V
Forward Acceleration	20	±10g	±10V	0g	1g/V
Lateral Acceleration	21	±10g	±10V	0g	1g/V
Vertical Acceleration	22	±10g	±10V	0g	1g/V

Analog Inputs

In an effort to make this system more versatile, the DMS allows the user to input analog data that can then be added to the serial data output. This allows the system to act as a data acquisition unit for other vehicle information such as engine RPM, engine temperature, fuel remaining, altitude/depth or any other important data. The four analog user inputs as well as the velocity input have one megohm input impedance, 16 bit A/D conversion resolution, ±10 volt input range and have a bandwidth of DC to 25 Hertz.

Speed Inputs

A vehicle speed input is used to assist in the correction of errors. It is also included in the parameter set that is available for serial output. Although its use is not always required, it is highly recommended that this signal be supplied to the DMS. The unit can receive speed information in two formats, an analog or digital signal. The internal GPS receiving unit provides the digital signal.

The optional analog speed input signal is a voltage that is scaled to 40 KPH per volt. Forward motion should produce a positive signal with respect to signal ground. Many other velocity scale factors can be handled through simple changes in the scale factor stored in the EEPROM in the microprocessor. This can be done with a PC and the assistance of the factory.

Input Logic Commands

The DMS also has several digital inputs that are all activated by connecting to signal ground. The user should only apply a ground because all the inputs have an internal pull-up resistor to +5VDC. The pins are as follows:

a) Initialization - Resets all angle integrators. The unit should be in a non-accelerated condition if this command is given. Leave pin open if not in use. Ground to command.

b) Reference - An alternate set of sensor information primarily intended as an instrumentation mode. Leave pin open if not in use. Ground to command.

c) Free Inertial Mode – In this mode, the attitude is computed from gyro data only. Free mode is used when extreme accelerations are expected. Leave pin open if not in use. Ground to command.

NOTE: The digital logic inputs are all disabled if any one equivalent serial command is sent via RS-232. This is to prevent hardware/software conflicts.

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°	
*	Accuracy: Dynamic	2%	

GPS Heading

	Range:	0° - 360°	
	Resolution:	0.02°	Binary mode (14 bit)
	Analog Scale Factor:	18°/V	±10V Output
	Accuracy: Static	±0.5° (±0.05°/sec stationary)	Relative, based on gyro drift
*	Accuracy: Dynamic or Relative	2%	±0.1°/sec (without GPS)

Angular Rate

	Range: Roll, Pitch, Yaw	±100°/sec	
	Resolution:	0.025°/sec	Binary mode (14 bit)
	Analog Scale Factor:	10°/sec/V	±10V Output
	Scale Factor Accuracy:	2%	
	Bias: Roll, Pitch, Yaw	< 0.3°/sec	
	Non-Linearity:	< 0.05%	Full scale range
	Bandwidth:	20 Hz	

Acceleration

	Range: X, Y, Z	±10g	
	Range: Forward, Lateral, Vertical	±10g	
	Resolution:	4mg	
	Analog Scale Factor:	1g/V	±10V Output
	Scale Factor Accuracy:	1%	
	Bias:	< 10mg	
	Non-Linearity:	0.1%	Full scale range
	Bandwidth:	3 Hz	

GPS Positioning

	Range: Latitude	±90°	
	Range: Longitude	±180°	
	Range: Altitude	0ft to 21500ft	
	Resolution: Latitude, Longitude	0.0000013°	Binary mode (28 bit)
	Resolution: Altitude	2 ft	
	Accuracy: Latitude, Longitude	1.5m rms	

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:	71.1 Hz	Maximum
	Startup Time: Data	5 sec	
†	Startup Time: Satellite Acquisition	5 min	Typical
	Input Power:	10 to 35VDC	4.4W
	Input Current:	335mA @ 12VDC	185mA @ 24VDC
	Input Velocity: (Optional)	±10VDC	Full scale (±400kph)
	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 3.50"H	8.2 x 14.7 x 8.9 (cm)
	Weight:	27 oz (1.7lb)	765 grams (0.8Kg)
	Connection: RS-232	9 pin female "D" subminiature	
	Connection: Power / Analog Outputs	25 pin male "D" subminiature	
	Connection: Antenna	SMA	Antenna cable length: 3.0m

* Using velocity data with GPS mode on.
Actual accuracy can be calculated as the listed percentage multiplied by the change in value over the entire dynamic maneuver.

† Acquisition time for GPS units is typical for the contiguous United States. Acquisition time may differ due to interference in your geographic area.

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

Table 1: Connections / Dimensions

25 Pin Male D-Sub Power/Analog Output Connector			
Pin	Description	Pin	Description
1	Power Ground *	15	Elevation Angle Analog Output
2	+12 or +24 VDC	16	Heading Angle Analog Output
3 - 6	User Inputs 1 - 4	17	X Axis Acceleration Analog Output
7	Factory Use – Do not Connect	18	Y Axis Acceleration Analog Output
8	Coast Command	19	Z Axis Acceleration Analog Output
9	No Connection	20	Forward Acceleration Analog Output
10	Initialization Command	21	Lateral Acceleration Analog Output
11	Velocity Input (option)	22	Vertical Acceleration Analog Output
12	Signal Ground	23	X Axis Rate Analog Output
13	Reference Command	24	Y Axis Rate Analog Output
14	Bank Angle Analog Output	25	Z Axis Rate Analog Output
• Power Ground & Signal Ground are electrically isolated • The signal ground is connected to case.			

9 –Pin Female D-Sub RS-232 Serial Communication 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	No Connection
** The user receives on this line.	

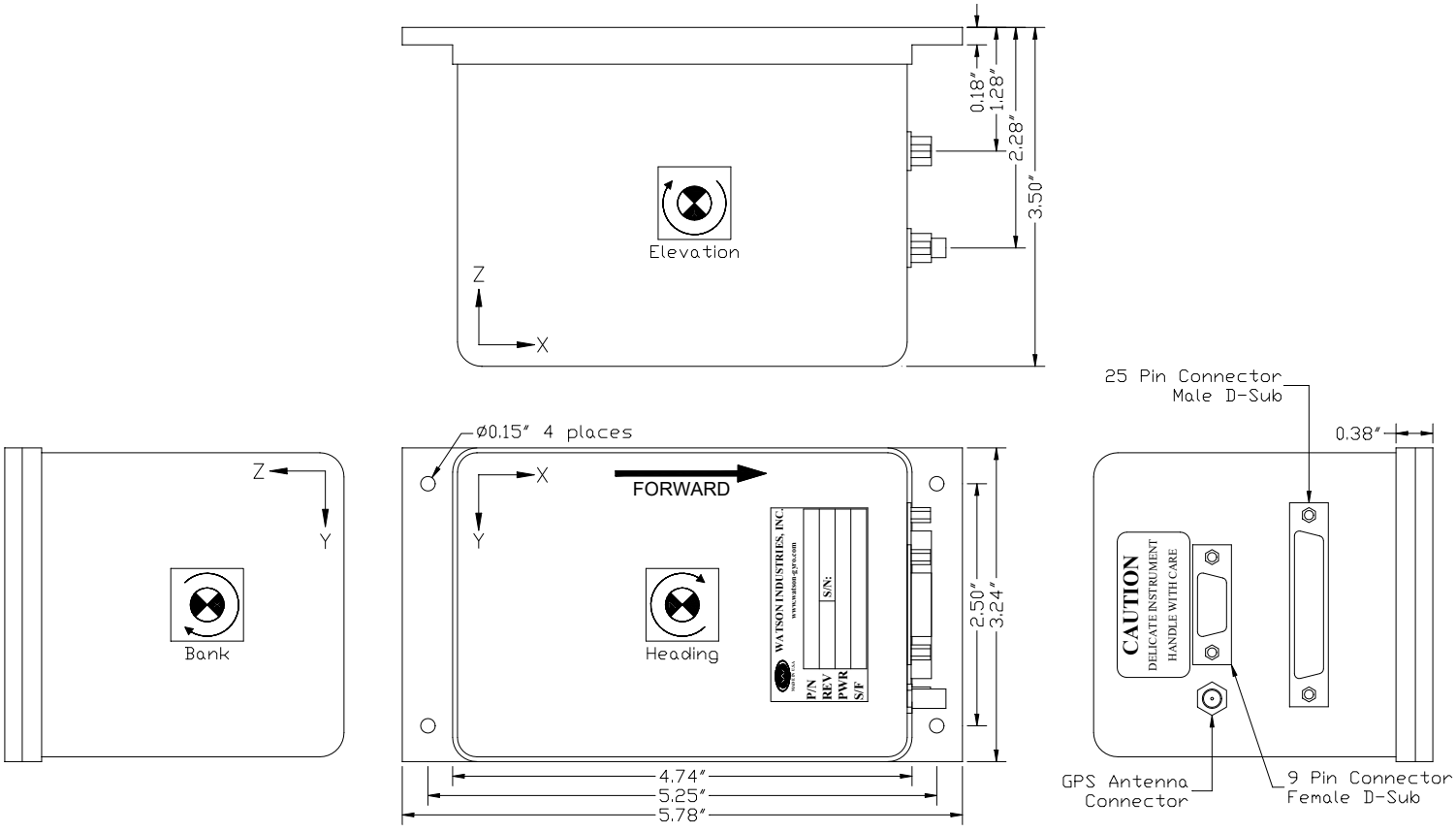


Figure 1 DMS-SGP01

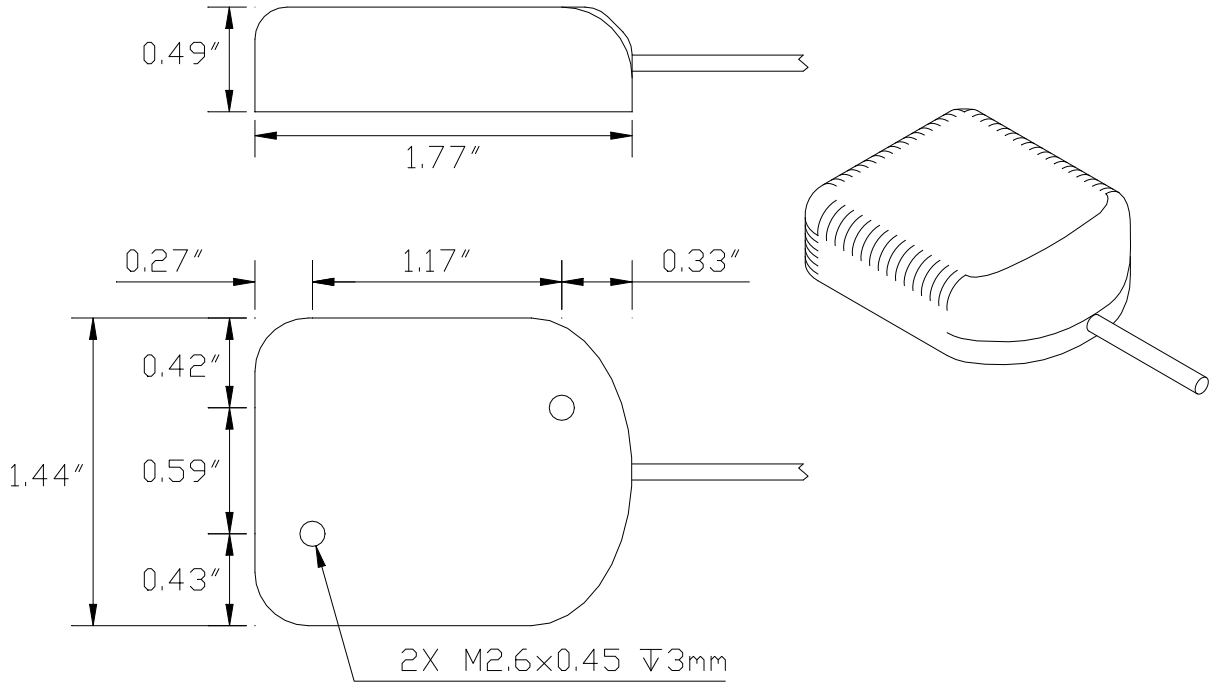


Figure 2 GPS Antenna Dimensions

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	TM	UTC [1] HHMMSS.S	Seconds Since Reset 16,383 seconds
Bank Angle	BK	±179.9º	±180º
Elevation Angle	EL	±89.9º	±180º
Heading Angle	HG	0.0 to 359.9º	±180º
X Accelerometer	XA	±9.99 G	±10 G
Y Accelerometer	YA	±9.99 G	±10 G
Z Accelerometer	ZA	±9.99 G	±10 G
Forward Acceleration	FA	±9.99 G	±10 G
Lateral Acceleration	LA	±9.99 G	±10 G
Vertical Acceleration	VA	±9.99 G	±10 G
X Angular Rate	XR	±99.9 º/s	±200 º/s
Y Angular Rate	YR	±99.9 º/s	±200 º/s
Z Angular Rate	ZR	±99.9 º/s	±200 º/s
Heading Rate	HR	±99.9 º/s	±200 º/s
User Channel 1	U1	±9.99 VDC	±10 VDC
User Channel 2	U2	±9.99 VDC	±10 VDC
User Channel 3	U3	±9.99 VDC	±10 VDC
User Channel 4	U4	±9.99 VDC	±10 VDC
Ground Track [2] / Forward Velocity	VS	±399.9 Km/hr	±400 Km/hr
Latitude [3]	LT	±89.99999	±90° (4 bytes)
Longitude [3]	LN	±179.99999	±180° (4 bytes)
Altitude [4]	AL	21500 Feet	32768 Feet
Temperature	TP	-40º to 88ºC	-40º to 88ºC (7 bit)
Status Bits	ST	3 ASCII chars representing Octal digits	1 byte
Flag Bits	FL	3 ASCII chars representing Octal digits	1 byte

[1] Note: The GPS universal time (UTC) field is filled with asterisks when the data is invalid. ("******")

[2] Note: The Ground Track Velocity field is filled with asterisks when the data is invalid. (****.*)

[3] Note: The Latitude & Longitude fields are filled with asterisks when the data is invalid. ("+**.***** +***.*****")

[4] Note: The Altitude field is filled with asterisks when the data is invalid. (*****)

The Status Bits contain the following information:

Bit	Description (If Set)
0	Bank Error Flag
1	Elevation Error Flag
2	Heading Error Flag
3	System Error Flag
4	Velocity Error Flag
5	Ready Flag
6	Checksum Error Flag
7	Not Used (always zero)

Example: The status channel output in ASCII Decimal is “146”

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

Bit 7	Reset	
Bit 6	Set	Checksum Error
Bit 5	Set	Ready
Bit 4	Reset	No Velocity Error
Bit 3	Reset	No System Error
Bit 2	Set	Heading Error
Bit 1	Set	Elevation Error
Bit 0	Reset	No Bank Error

The Flag Bits contains the following information:

Bit	Description (If Set)
0	GPS Heading fail.
1	GPS Velocity fail.ground track velocity data loss
2	Not used (always zero)
3	Reference Command selected
4	GPS enabled
5	Free Mode selected
6	Analog Switches disabled
7	Not used (always zero)

Example: The flag channel output in ASCII Decimal is “120”

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

Bit 7	Reset	
Bit 6	Set	Analog Switches Disabled
Bit 5	Reset	Not in Free Mode
Bit 4	Set	GPS Enabled
Bit 3	Reset	Not in Reference Mode
Bit 2	Reset	
Bit 1	Reset	Valid GPS velocity data
Bit 0	Reset	Valid GPS heading data

Appendix B

Activating Command mode or Double Spacebar Access to commands

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 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 = SELECT HEADING SOURCE
    5 = SELECT VELOCITY SOURCE
    6 = SELECT ALTITUDE CORRECTION
    7 = 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 TIME?
```

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.

Setting Output Format

There are two output formats:

Decimal output – "_" Command.
Binary output – "^" Command.

To change the output format:

1) Activate Command Mode (See above).

2) Press the key Command corresponding to the format you want to switch into.
   To make this output format the default the next time you power the unit on, send a Quotation Mark (").

3) Press the space bar to resume data transmission.

Setting Heading Mode

1) Activate Command Mode (See above).
2) Type '&'(this will bring up the main menu again).
3) To set new baud rate, type ‘4’.

This will bring up the menu:

```
SELECTION HEADING SOURCE (OR 'Q' TO QUIT):
    1 = GPS TRUE NORTH GROUND TRACK HEADING
    2 = RELATIVE HEADING
```

4) To set the heading mode to GPS True North Heading type ‘1’. To use this mode, the GPS antennas must be connected to the DMS.

5) To set the heading mode to Relative Heading type ‘2’. This is the normal DMS mode (non-GPS). In this mode, the GPS antennas do not need to be connected.

To make any of these modes the default the next time you power the unit on type in " (a quote mark.)

Setting Velocity Mode

1) Activate Command Mode (See above).
2) Type '&'(this will bring up the main menu again).
3) To set new baud rate, type ‘5’.

This will bring up the menu:

```
SELECTION VELOCITY SOURCE (OR 'Q' TO QUIT):
    1 = GPS GROUND TRACK VELOCITY
    2 = ANALOG VELOCITY
```

4) To set to GPS Ground Velocity type ‘1’. This is the mode when using the GPS module.

5) To set to Analog Velocity type ‘2’. This is the normal DMS mode (non-GPS). Make sure that the proper analog velocity signal is applied.

To make this selection the default the next time you power the unit on type in " (a quote mark.)

Setting Altitude Correction:

1) Activate Command Mode (See above).
2) Type '&'(this will bring up the main menu again).
3) To select the altitude correction setting , type ‘6’.

This will bring up the menu:

```
SELECTION ALTITUDE CORRECTION (OR 'Q' TO QUIT):
    1 = GPS GEODETIC CORRECTION
    2 = NO CORRECTION
```

4) To turn on Altitude Correction type ‘1’. This displays the Altitude corrected for “height of geoid above WGS84 ellipsoid” in feet.

5) To shut off Altitude Correction type ‘2’. This displays the Altitude above Mean Sea Level (MSL) in feet. This is the factory default setting.

To make this selection the default the next time you power the unit on type in " (a quote mark.)

Setting Baud Rate

1) Activate Command Mode (See above).
2) Type '&'(this will bring up the main menu again).
3) To set new baud rate, type ‘7’.

   This will bring up the menu:

```
TYPE IN THE NUMBER OF YOUR SELECTION (OR 'Q' TO QUIT):
(EFFECTIVE NEXT POWER-UP)
   1 = 38.4 K BAUD
   2 = 19.2 K BAUD
   3 =  9.6 K BAUD
   4 =  4.8 K BAUD
```

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

Tests within this section have been designed to allow the user to verify 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 output 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 in “Inertial Mode”. The angles obtained should agree with those noted in “Reference Mode”.

Repeat this procedure for the Roll axis. The same pivot may be used, but some care will be needed to avoid exceeding the 100 °/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 that the X and Y outputs read near zero while the Z-axis will read -1G within the accuracy of the sensor.

Set the sensor at a 45° 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 Leveled Accelerometer 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° angle to the horizontal in pitch only, taking care not to move the sensor at an angular rate of more than 100 °/sec.

The Forward, Lateral and Vertical Acceleration outputs should not change from the values at level by more than the accuracy of the sensor.

Move the sensor through a further 45 degrees in pitch such that the baseplate is now vertical, again taking care not to exceed the 100 °/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

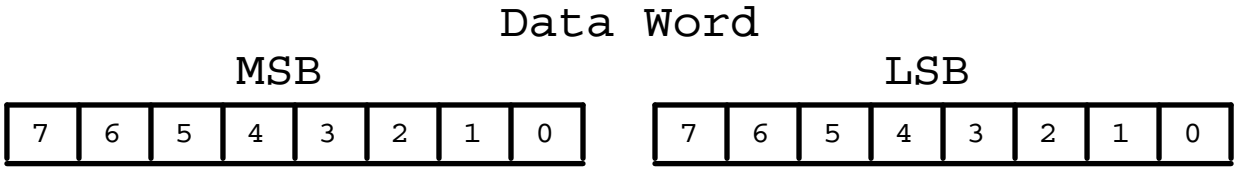
The unit will output up to 6 words at 71.11 frames per second set at 9600 Baud. One word per output parameter.

Example 1: The Unit is seeing these conditions:

Bank	Elevation	Heading	X angular rate	Y angular rate	Z angular rate
15.0˚	-5.0˚	315.0˚	10.0˚/sec	-15.0˚/sec	55.0˚/sec

2) Binary output Format:

Word1	Word2	Word3	Word4	Word5	Word6	<CR> byte
0x85AA	0xFE9C	0xF080	0x8399	0xFB99	0x91CC	0x0D



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 bit 7 (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 bit 7 (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 Rate	Y Rate	Z Rate
0x85AA	0xFE9C	0xF080	0x8399	0xFB99	0x91CC

Need split each word into two bytes:

Bank	Elevation	Heading	X Rate	Y Rate	Z Rate
0x85 0xAA	0xFE 0x9c	0xF0 0x80	0x83 0x99	0xFB 0x99	0x91 0xCC

Remove the most significant bit from each byte:

Bank	Elevation	Heading	X Rate	Y Rate	Z Rate
0x05 0x2A	0x7E 0x1C	0x70 0x00	0x03 0x19	0x7B 0x19	0x11 0x4C

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

Bank	Elevation	Heading	X Rate	Y Rate	Z Rate
0x05 0x54	0x7E 0x38	0x70 0x00	0x03 0x32	0x7B 0x32	0x11 0x98

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

Bank	Elevation	Heading	X Rate	Y Rate	Z Rate
0x0A 0xA8	0xFC 0x70	0xE0 0x00	0x06 0x64	0xF6 0x64	0x23 0x30

Convert from hexadecimal to decimal counts:

Bank	Elevation	Heading	X angular rate	Y angular rate	Z angular rate
2728	64624	57344	1636	63076	9008

Correct bank, elevation, and angular rates for the sign
If >32767 then subtract 65536 from the data

Bank	Elevation	Heading	X angular rate	Y angular rate	Z angular rate
2728	-912	57344	1636	-2460	9008

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 Angular Rates: Scale factor is: (200 ˚/sec) / 32768 counts

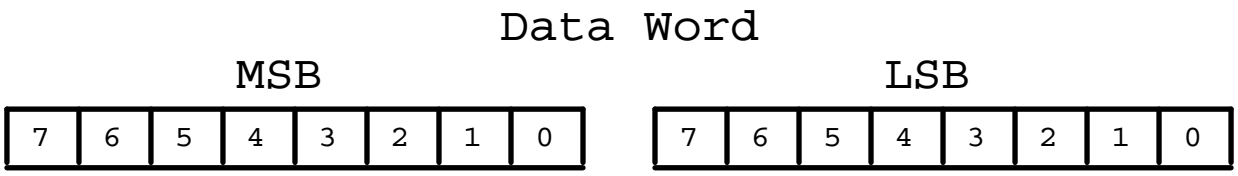
Bank	Elevation	Heading	X angular rate	Y angular rate	Z angular rate
14.991 ˚	-5.010 ˚	315 ˚	9.985 ˚/sec	-15.015 ˚/sec	54.980 ˚/sec

Example 2: The Unit is seeing these conditions:

X Acceleration	Y Acceleration	Z Acceleration	X angular rate	Y angular rate	Z angular rate
0.00 g	-0.28 g	-0.96g	10.0˚/sec	-15.0˚/sec	55.0˚/sec

2) Binary output Format:

Word1	Word2	Word3	Word4	Word5	Word6	<CR> byte
0x8080	0xFE9A	0xF9EE	0x8399	0xFB99	0x91CC	0x0D



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 bit 7 (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 bit 7 (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:

X Accel	Y Accel	Z Accel	X Rate	Y Rate	Z Rate
0x8080	0xFE9A	0xF9EE	0x8399	0xFB99	0x91CC

Need split each word into two bytes:

X Accel	Y Accel	Z Accel	X Rate	Y Rate	Z Rate
0x80 0x80	0xFE 0x9A	0xF9 0xEE	0x83 0x99	0xFB 0x99	0x91 0xCC

Remove the most significant bit from each byte:

X Accel	Y Accel	Z Accel	X Rate	Y Rate	Z Rate
0x00 0x00	0x7E 0x1A	0x79 0x6E	0x03 0x19	0x7B 0x19	0x11 0x4C

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

X Accel	Y Accel	Z Accel	X Rate	Y Rate	Z Rate
0x00 0x00	0x7E 0x34	0x79 0xDC	0x03 0x32	0x7B 0x32	0x11 0x98

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

X Accel	Y Accel	Z Accel	X Rate	Y Rate	Z Rate
0x00 0x00	0xFC 0x68	0xF3 0xB8	0x06 0x64	0xF6 0x64	0x23 0x30

Convert from hexadecimal to decimal counts:

X Accel	Y Accel	Z Accel	X angular rate	Y angular rate	Z angular rate
0	64616	62392	1636	63076	9008

Correct bank, elevation, and angular rates for the sign
If >32767 then subtract 65536 from the data

X Accel	Y Accel	Z Accel	X angular rate	Y angular rate	Z angular rate
0	-920	-3144	1636	-2460	9008

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 10g / 32768 counts
For Angular Rates: Scale factor is: (200 ˚/sec) / 32768 counts

X Accel	Y Accel	Z Accel	X angular rate	Y angular rate	Z angular rate
0.0000g	-0.2808g	-0.9595g	9.985 ˚/sec	-15.015 ˚/sec	54.980 ˚/sec

9600 Baud
8 Bit Data
1 Start Bit
1 Stop Bit
No Parity