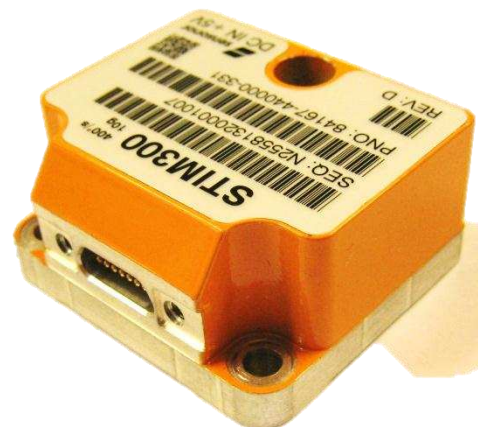


1 FEATURES

- Miniature package
- Low noise
- Low bias instability
- Excellent performance in vibration and shock environments
- 6 axes offered in same package
 - Electronically calibrated axis alignment
- Gyros based on Sensoror ButterflyGyro™
 - Single-crystal silicon technology
 - No intrinsic wear-out effects
- High stability accelerometers and inclinometers
- Separate "AUX" input for 24 bit ADC
- Insensitive to magnetic fields
- Full EMI compliance
- Digital interface, RS422
- Fully configurable
- Continuous self-diagnostics



(38.6mm x 44.8mm x 21.5mm)

2 GENERAL DESCRIPTION

STIM300 is an IMU consisting of 3 high accuracy MEMS-based gyros, 3 high stability accelerometers and 3 high stability inclinometers in a miniature package. Each axis is factory-calibrated for bias, sensitivity and compensated for temperature effects to provide high-accuracy measurements in the temperature range -40°C to +85°C. The unit runs off a single +5V supply.

STIM300 communicates via a standard high-level RS422 interface. The use of a 32-bit RISC ARM microcontroller provides flexibility in the configuration, like choice of output unit, sample rate, low pass filter -3dB frequency and RS422 bit-rate and protocol parameters. All configurable parameters can be defined when ordering or set by customer.

When STIM300 is powered up, it will perform an internal system check and synchronise the sensor channels. As an acknowledgement of the complete power-up sequence, it will provide special datagrams containing part number, serial number and configuration data. STIM300 will then automatically proceed to provide measurement data. Connect power and STIM300 will provide accurate measurements over the RS422 interface.

The measurement data is transmitted as packages of data on a fixed format (datagram) at intervals given by the sample rate together with a synchronization signal (TOV). The datagram is in binary coded format in order to have an efficient transfer of data. In addition to the measurement data itself, the datagram contains an identifier, status bytes and a 32 bit CRC (Cyclic Redundancy Check) to provide high degree of fault detection in the transmissions. The status bytes will flag any detected errors in the system. STIM300 can also be configured to transmit data only when triggered by a separate digital input signal (ExtTrig).

For more advanced users, the gyro may be put in Service Mode. In this mode all the configuration parameters can be intermediately or permanently changed by overwriting the current settings in the flash memory. In Service Mode the commands and responses are in a human readable format (ASCII); to enable the use of terminal-type software during typical product integration. Service Mode also provides the ability to perform single measurements, perform diagnostics and obtain a higher detail level of detected errors reported in the status bytes.

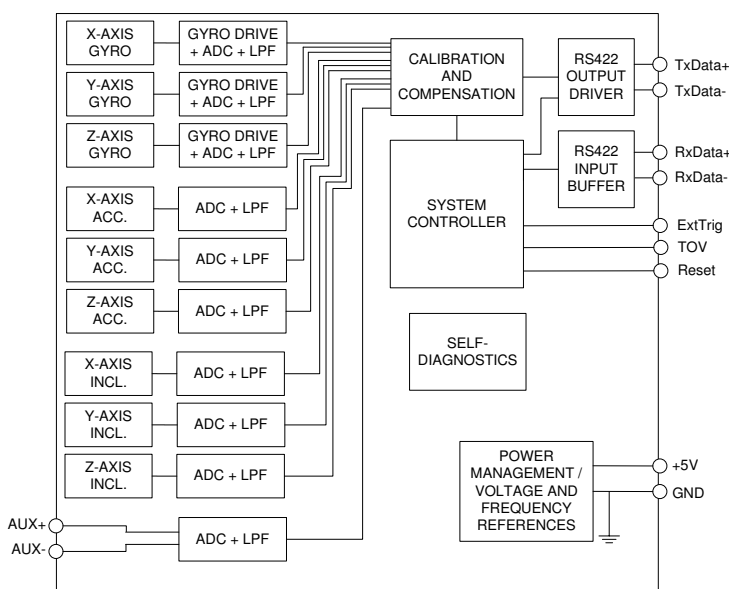


Figure 2-1: STIM300 FUNCTION BLOCK DIAGRAM

Sensoror AS

Phone: +47 3303 5000 - Fax: +47 3303 5005
sales@sensoror.com www.sensoror.com

3 TABLE OF CONTENTS

| | |
|---|----|
| DOCUMENT HISTORY | 1 |
| 1 FEATURES..... | 1 |
| 2 GENERAL DESCRIPTION | 1 |
| 3 TABLE OF CONTENTS..... | 2 |
| 4 DEFINITIONS AND ABBREVIATIONS USED IN DOCUMENT..... | 3 |
| 4.1 Definitions..... | 3 |
| 4.2 Abbreviations | 3 |
| 5 ABSOLUTE MAXIMUM RATINGS | 3 |
| 6 SPECIFICATIONS | 4 |
| 6.1 TYPICAL PERFORMANCE CHARACTERISTICS | 9 |
| 6.1.1 GYRO CHARACTERISTICS..... | 9 |
| 6.1.2 ACCELEROMETER CHARACTERISTICS..... | 13 |
| 6.1.3 INCLINOMETER CHARACTERISTICS | 16 |
| 6.1.4 AUX CHARACTERISTICS..... | 19 |
| 6.2 Configurable parameters | 21 |
| 6.3 Datagram specifications..... | 22 |
| 6.3.1 Part Number datagram | 22 |
| 6.3.2 Serial Number datagram..... | 23 |
| 6.3.3 Configuration datagram | 24 |
| 6.3.4 Normal Mode datagram | 27 |
| 6.3.5 Cyclic Redundancy Check (CRC) | 28 |
| 6.4 Status byte..... | 29 |
| 7 MECHANICAL | 30 |
| 7.1 Mechanical dimensions..... | 30 |
| 7.2 Pin configuration | 31 |
| 7.3 Definition of axes | 31 |
| 8 BASIC OPERATION..... | 32 |
| 8.1 Reset | 32 |
| 8.2 External Trigger | 32 |
| 8.3 Time of Validity (TOV)..... | 33 |
| 8.4 Auxiliary input..... | 34 |
| 8.5 Operating modes | 34 |
| 8.5.1 Init Mode | 35 |
| 8.5.2 Normal Mode | 35 |
| 8.5.3 Service Mode..... | 42 |
| 8.6 Self diagnostics..... | 42 |
| 9 COMMANDS IN NORMAL MODE..... | 43 |
| 9.1 N (PART NUMBER DATAGRAM) command..... | 43 |
| 9.2 I (SERIAL NUMBER DATAGRAM) command | 43 |
| 9.3 C (CONFIGURATION DATAGRAM) command | 43 |
| 9.4 R (RESET) command | 44 |
| 9.5 SERVICEMODE command..... | 44 |
| 10 COMMANDS IN SERVICE MODE..... | 46 |
| 10.1 i (INFORMATION) command..... | 47 |
| 10.2 a (SINGLE-SHOT MEASUREMENT) command..... | 52 |
| 10.3 c (DIAGNOSTIC) command..... | 54 |
| 10.4 d (DATAGRAM FORMAT) command | 56 |
| 10.5 t (TRANSMISSION PARAMETERS) command..... | 58 |
| 10.5.1 User-defined bit-rate | 58 |
| 10.6 r (LINE TERMINATION) command..... | 60 |
| 10.7 u (OUTPUT UNIT) command..... | 61 |
| 10.8 f (LP FILTER -3dB FREQUENCY) command | 62 |
| 10.9 m (SAMPLE RATE) command..... | 64 |
| 10.10 k (AUX COMP) command..... | 65 |
| 10.11 g (GYRO G-COMP) command..... | 66 |
| 10.12 s (SAVE) command | 69 |
| 10.13 x (EXIT) command..... | 70 |
| 10.14 z (RESTORE TO FACTORY SETTINGS) command..... | 72 |
| 10.15 ? (HELP) command | 73 |
| 11 MARKING..... | 78 |
| 12 CONFIGURATION / ORDERING INFORMATION..... | 79 |

4 DEFINITIONS AND ABBREVIATIONS USED IN DOCUMENT

4.1 Definitions

$g_0 = 9.80665 \text{ m/s}^2$ (standard gravity)

4.2 Abbreviations

Table 4-1: Abbreviations

| ABBREVIATION | FULL NAME |
|--------------|---------------------------------|
| BCD | Binary Coded Decimal |
| BSL | Best Straight Line |
| CIC-filter | Cascaded Integrator-Comb filter |
| CR | Carriage Return |
| FS | Full-Scale |
| LF | Line Feed |
| LP filter | Low-Pass filter |
| tbd | to be defined |
| LSB | Least Significant Byte |
| MSB | Most Significant Byte |
| lsb | Least significant bit |
| TOV | Time of Validity |

5 ABSOLUTE MAXIMUM RATINGS

Stresses beyond those listed in Table 5-1 may cause permanent damage to the device.

Exposure to any Absolute Maximum Rating condition for extended periods may affect device reliability and lifetime.

Table 5-1: Absolute maximum ratings

| Parameter | Rating | Comment |
|----------------------|------------------------|---|
| Mechanical shock | 1 500g/0.5ms half-sine | Any direction. Ref: MIL STD-883G |
| ESD human body model | ±2kV | Ref: JEDEC/ESDA JS-001 |
| Storage temperature | -55°C to +90°C | Up to 1000 hours |
| VSUP to GND | -0.5 to +7V | |
| RxD+ or RxD- to GND | -0.3V to +7V | |
| RxD+ to RxD- | ±6V | with 120Ω Line Termination = ON |
| TxD+ or TxD- to GND | -8V to +8V | |
| ExtTrig to GND | -0.3V to +7V | |
| TOV to GND | -0.3V to +7V | |
| NRST to GND | -0.3V to +7V | |
| AUX+ to AUX- | ±6.5V | |
| AUX+ or AUX- to GND | ±6.5V | |
| Chassis to GND | 500V | |
| Helium sensitivity | | Not to be exposed to helium concentrations higher than those normally found in the atmosphere |

6 SPECIFICATIONS

Table 6-1: Operating conditions

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|----------------------------------|------------|-----|------|-----|------|------|
| INPUT RANGE, ANGULAR RATE | | | ±400 | | °/s | |
| INPUT RANGE, ACCELERATION | | | ±10 | | g | 1 |
| INPUT RANGE, INCLINATION | | | ±1.7 | | g | |
| POWER SUPPLY | | 4.5 | 5.0 | 5.5 | V | 2,3 |
| OPERATING TEMPERATURE | | -40 | | +85 | °C | |

Note 1: Other ranges available, ref. note 1 in Table 6-4

Note 2: At supply voltages above 5.85V (nominal value) an internal voltage protection circuit will cut power and the unit will go into reset until the voltage is back within operating conditions.

Note 3: At supply voltages below 4.05V (nominal value) the unit will go into reset until the voltage is back within operating conditions. Due to power consumption being much lower in reset compared to normal operation, the series resistance between power source and STIM300 could give rise for an oscillating behaviour of the input voltage to the unit.

Table 6-2: Functional specifications, general

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|---|------------------------|-----|----------------|---------------------|------|------|
| POWER CONSUMPTION | | | | | | |
| Power consumption | | | 1.5 | 2 | W | |
| TIMING | | | | | | |
| Start-Up time after Power-On | | | | 1 | s | 1 |
| Time to transmit after Reset | | | | 1 | s | 2 |
| Time to valid data | | | | 5 | s | 3 |
| RS422 Bit-Rate | | | ref. Table 6-8 | | | |
| RS422 Bit-Rate Accuracy | | | | ±1 | % | 4 |
| RS422 PROTOCOL | | | | | | |
| Start Bit | | | 1 | | bit | |
| Data Length | | | 8 | | bits | |
| Parity | | | None | | | 5 |
| Stop Bits | | | 1 | | bit | 5 |
| RS422 LINE TERMINATION | | | | | | |
| Input resistance | Line termination = ON | | 120 | | Ω | |
| Input resistance | Line termination = OFF | 48 | 125 | | kΩ | |
| RESET (NRST PIN) | | | | | | |
| Logic levels | “high” | 2.3 | | | V | |
| | “low” | | | 0.6 | V | |
| Minimum hold time for reset | | 1 | | | μs | |
| Pull-Up Resistor | | 80 | 100 | | kΩ | |
| EXTERNAL TRIGGER (ExtTrig PIN) | | | | | | |
| Logic levels | “high” | 2.3 | | | V | |
| | “low” | | | 0.6 | V | |
| Trigger | | | | Negative transition | | |
| Time between triggers | Measurement.unit: | | | | | |
| | angular rate | 0.5 | | 65 | ms | 6 |
| | incremental angle | 0.5 | | 65 | ms | 6 |
| | average rate | 0.5 | | 65 | ms | 6,7 |
| | integrated angle | 0.5 | | 8 | ms | 6,8 |
| Minimum “high” time before trigger, t_{ext_hi} | | 50 | | | ns | 9 |
| Minimum “low” time after trigger, t_{ext_lo} | | 50 | | | ns | 9 |
| Delay from external trigger to start of transmission, t_{ext_dl} | | | | 86 | μs | 9 |
| Pull-Up Resistor | | 40 | 50 | | kΩ | |
| Latency | | | | 1000 | μs | |

STIM300 Inertia Measurement Unit

| | | | | | |
|--|------|------------------|----|----|----|
| TIME OF VALIDITY (TOV PIN) Output configuration Internal Pull-Up Resistor to Vsup Sink capability TOV active level Minimum time of TOV, t_{tov_min} Delay from internal time-tick to TOV active, t_{tov_dl} Delay from TOV active (to start of transmission), t_{tx_dl} | | Open drain 10 | | kΩ | |
| | | | 50 | mA | |
| | | Active "low" | | | |
| | 50 | | | μs | 10 |
| | | 0.5 | 6 | μs | 10 |
| | | | 80 | μs | 10 |
| CHASSIS Isolation resistance chassis to GND (pin 15) | 500V | 100 | | MΩ | |

Note 1: Time from Power-On to start of datagram transmissions (starting with part-number datagram)

Note 2: Time from Reset release to start of datagram transmissions (starting with part-number datagram)

Note 3: Time from Power-On or Reset to the reset of the Start-Up bit (Bit 6 in the STATUS byte ref. Table 6-16).

During this period the output data should be regarded as non-valid.

Note 4: If a user-defined bit-rate larger than 1.5Mbit/s is used, the deviation may exceed the specification due to the resolution of the bit-rate generator, ref. section 10.5.1

Note 5: Other values can be configured, ref. Table 6-8

Note 6: If time between triggers is longer, the latency will over-run. The sample counter will over-run after 127ms.

Note 7: If time between triggers is longer, the accuracy of average rate may also be reduced. Similar for accelerometer and inclinometer outputs

Note 8: If time between triggers is longer, the integrated angle may have wrapped several times and hence the change in angle from last sample will not be possible to calculate. Similar for accelerometer and inclinometer outputs

Note 9: For definition, ref. Figure 8-3

Note 10: For definition, ref. Figure 8-4 and Figure 8-5

Table 6-3: Functional specifications, gyros

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|---------------------------------------|--|------|-----------------|------|------------------------------------|------|
| GYRO | | | | | | |
| Full Scale (FS) | | | ±400 | | °/s | 1 |
| Resolution | | | 24 | | bits | |
| | | | 0.22 | | °/h | |
| Scale Factor Accuracy | | | ±500 | | ppm | |
| Non-Linearity | ±200°/s | | 25 | | ppm | 2 |
| | ±400°/s | | 50 | | ppm | 2 |
| Bandwidth (-3dB) | | | 262 | | Hz | 3 |
| Sample Rate | | | | 2000 | samples/s | 4 |
| Group Delay | LP-filter -3dB = 262Hz | | 1.5 | | ms | 5 |
| | LP-filter -3dB = 131Hz | | 3.0 | | ms | 5 |
| | LP-filter -3dB = 66Hz | | 6.0 | | ms | 5 |
| | LP-filter -3dB = 33Hz | | 12 | | ms | 5 |
| | LP-filter -3dB = 16Hz | | 24 | | ms | 5 |
| Bias Range | | -250 | 0 | +250 | °/h | |
| Bias error over temperature | Static temperatures | | 5 | | °/h | 6 |
| Bias error over temperature gradients | $\Delta T \leq \pm 1^\circ\text{C}/\text{min}$ | | 10 | | °/h | 7 |
| Bias Instability | Allan Variance @25°C | | 0.5 | | °/h | |
| Angular Random Walk | Allan Variance @25°C | | 0.15 | | °/√hr | |
| Linear Acceleration Effect | | | | | | |
| Bias | With g-compensation | | 1 | | °/h /g | 8 |
| | No g-compensation | | | 15 | °/h /g | 8 |
| Scale Factor | With g-compensation | | 30 | | ppm/g | 8 |
| | No g-compensation | | 400 | | ppm/g | 8 |
| Vibration Rectification Coefficient | | | Ref. Figure 6-1 | | °/h /g ² _{rms} | |
| Misalignment | | | 1 | | mrad | 9 |

Note 1: Output is monotonous and will saturate at ±480°/s

Note 2: Largest deviation from BSL (Best Straight Line) over the range specified

Note 3: Low-pass filter -3dB frequency can be configured, ref. Table 6-8 and section 6.1.1.4

Note 4: Other values can be configured, ref. Table 6-8. Sample rate will be same for gyros, accelerometers, inclinometers, AUX and temperature

Note 5: Total delay to start of datagram transmission = group delay + 0.5ms + $t_{\text{tov_dl}}$ + $t_{\text{tx_dl}}$. For output units with delayed output, the group delay will be 5ms longer, ref. section 8.5.2.2.1.

Note 6: rms-value calculated on the residuals at static temperatures over the temperature range

Note 7: rms-value calculated on the residual over two temperature-cycles, ref. Figure 6-7

Note 8: Minimized when linear acceleration is applied in X-direction, ref. Figure 7-3

Note 9: Ref. Figure 6-2 for definition of reference points used in axes alignment

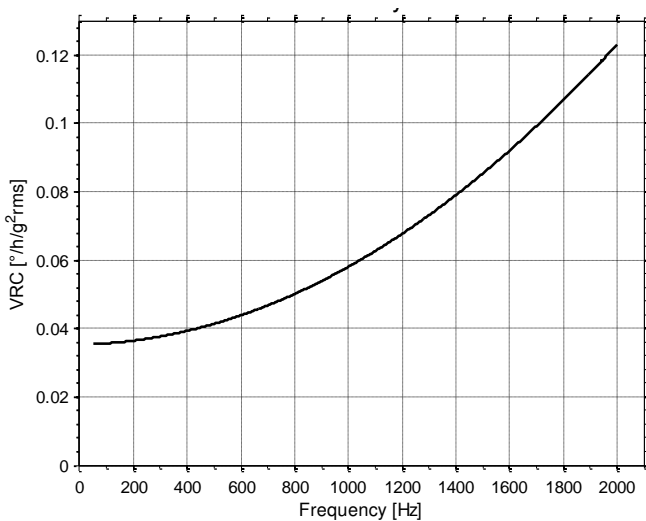


Figure 6-1: Nominal VRC at 5g rms for gyros

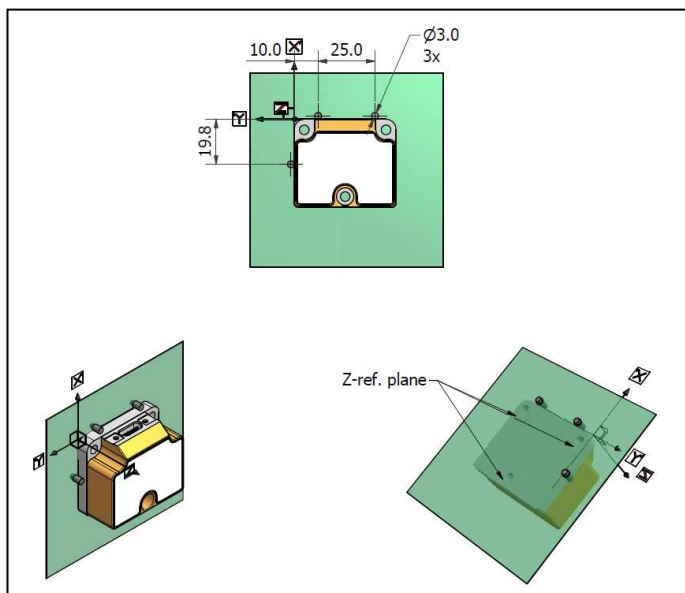


Figure 6-2: Reference points for alignment of axes

Table 6-4: Functional specifications, accelerometers

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|-------------------------------------|---|-------|-----------------|-------|----------------------------------|------|
| ACCELEROMETER | | | | | | |
| Full Scale (FS) | | | ±10 | | g | 1 |
| Resolution | | | 24 | | bits | |
| | | | 1.9 | | µg | |
| Scale Factor Accuracy | | | ±300 | | ppm | |
| Non-Linearity | ±10g | | 100 | | ppm | 2 |
| Bandwidth (-3dB) | LP-filter -3dB = 262Hz | 90 | 214 | | Hz | 3 |
| Sample Rate | | | | 2000 | samples/s | 4 |
| Group Delay | LP-filter -3dB = 262Hz | | 6.5 | | ms | 5 |
| | LP-filter -3dB = 131Hz | | 8.0 | | ms | 5 |
| | LP-filter -3dB = 66Hz | | 11 | | ms | 5 |
| | LP-filter -3dB = 33Hz | | 17 | | ms | 5 |
| | LP-filter -3dB = 16Hz | | 29 | | ms | 5 |
| Bias switch on/off repeatability | | -0.75 | 0 | +0.75 | mg | 6 |
| Bias error over temperature | $\Delta T \leq \pm 1 \text{ }^\circ\text{C}/\text{min}$ | | ±2 | | mg rms | 6 |
| Bias Instability | Allan Variance @25°C | | 0.05 | | mg | 6 |
| Velocity Random Walk | Allan Variance @25°C | | 0.06 | | m/s/√hr | 6 |
| Vibration Rectification Coefficient | | | Ref. Figure 6-3 | | mg/g ² _{rms} | |
| Misalignment | | | 1 | | mrad | 7 |

Note 1: Other ranges possible (±2g, ±5g, ±30g, ±100g)

Note 2: Largest deviation from BSL (Best Straight Line) over the range specified

Note 3: Other values can be configured, ref. Table 6-8 and section 6.1.2.3

Note 4: Other values can be configured, ref. Table 6-8. Sample rate will be same for gyros, accelerometers, inclinometers, AUX and temperature

Note 5: Total delay to start of datagram transmission = group delay + 0.5ms + $t_{\text{tov_dl}}$ + $t_{\text{tx_dl}}$

Note 6: Valid for ±10g range. Specification scale with range for other ranges

Note 7: Ref. Figure 6-2 for definition of reference points used in axes alignment

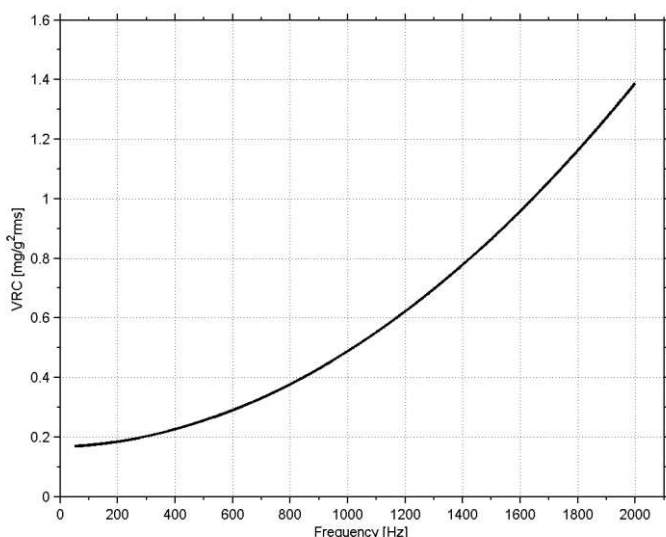

Figure 6-3: Nominal VRC at 10g rms for 10g accelerometers

Table 6-5: Functional specifications, inclinometers

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|----------------------------------|---|-------|------|-------|-----------|------|
| INCLINOMETER | | | | | | |
| Full Scale (FS) | | | ±1.7 | | g | |
| Resolution | | | 24 | | bits | |
| Scale Factor Accuracy | ±1g | | 0.2 | | µg | |
| Non-Linearity | ±1g | | ±500 | | ppm | 1 |
| Bandwidth (-3dB) | | | 500 | | ppm | |
| Sample Rate | | | 17 | | Hz | 2 |
| Group Delay | | | | 2000 | samples/s | 3 |
| | LP-filter -3dB = 262Hz | | 15 | | ms | 4 |
| | LP-filter -3dB = 131Hz | | 17 | | ms | 4 |
| | LP-filter -3dB = 66Hz | | 20 | | ms | 4 |
| | LP-filter -3dB = 33Hz | | 26 | | ms | 4 |
| | LP-filter -3dB = 16Hz | | 38 | | ms | 4 |
| Bias switch on/off repeatability | | -0.75 | 0 | +0.75 | mg | |
| Bias error over temperature | $\Delta T \leq \pm 1 \text{ }^\circ\text{C}/\text{min}$ | | ±2 | | mg rms | |
| Bias Instability | Allan Variance @25 °C | | 0.06 | | mg | |
| Velocity Random Walk | Allan Variance @25 °C | | 0.08 | | m/s/√hr | 5 |
| Misalignment | | | 1 | | mrad | 6 |

Note 1: Largest deviation from BSL (Best Straight Line) over the range specified

Note 2: Other values can be configured, ref. Table 6-8 and section 6.1.3.3

Note 3: Other values can be configured, ref. Table 6-8. Sample rate will be same for gyros, accelerometers, inclinometers, AUX and temperature

Note 4: Total delay to start of datagram transmission = group delay + 0.5ms + $t_{\text{tov_dl}}$ + $t_{\text{tx_dl}}$

Note 5: At 0g. Velocity Random Walk increases by typically 15% at ±1g given by the chosen technology for the inclinometers

Note 6: Ref. Figure 6-2 for definition of reference points used in axes alignment

Table 6-6: Functional specifications, AUXiliary input

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|------------------|------------------------|-----------------|-------|------|-----------|------|
| Full Scale (FS) | | | ±2.5 | | V | 1 |
| Resolution | | | 24 | | bits | |
| Gain error | @25 °C | | 0.30 | | µV | |
| Gain drift | | | ±0.1 | | % | 2 |
| Non-Linearity | | | 1.3 | | ppm/°C | |
| Bandwidth (-3dB) | | | 300 | | ppm | 3 |
| Sample Rate | | | 262 | | Hz | 4 |
| Group Delay | | | | 2000 | samples/s | 5 |
| | LP-filter -3dB = 262Hz | | 6.1 | | ms | 6 |
| | LP-filter -3dB = 131Hz | | 7.6 | | ms | 6 |
| | LP-filter -3dB = 66Hz | | 11 | | ms | 6 |
| | LP-filter -3dB = 33Hz | | 17 | | ms | 6 |
| | LP-filter -3dB = 16Hz | | 29 | | ms | 6 |
| Offset error | @25 °C | | ±0.75 | | mV | 2 |
| Offset drift | | | ±2.8 | | µV/°C | |
| Noise | | | 8 | | µV rms | |
| Input impedance | | Ref. Figure 6-4 | | | | |

Note 1: Full-scale input voltage (FS): $V_{\text{IN}} = (\text{AUX}+) - (\text{AUX}-)$

Note 2: Gain and offset error can be calibrated by changing the calibration coefficients, ref. 8.4 and 10.10

Note 3: Largest deviation from BSL (Best Straight Line) over the range specified

Note 4: Other values can be configured, ref. Table 6-8 and section 6.1.4.1

Note 5: Other values can be configured, ref. Table 6-8. Sample rate will be same for gyros, accelerometers, inclinometers, AUX and temperature

Note 6: Total delay to start of datagram transmission = group delay + 0.5ms + $t_{\text{tov_dl}}$ + $t_{\text{tx_dl}}$

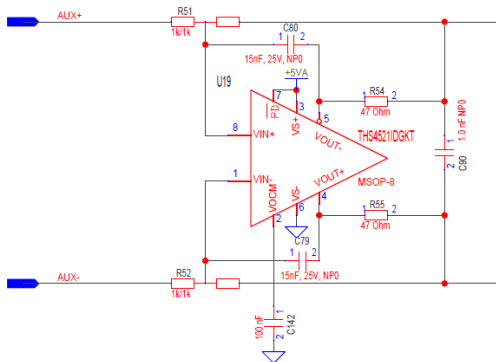


Figure 6-4: AUX input circuitry

Table 6-7: Functional specifications, temperature

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|-----------------------|------------|-----|--------|------|-----------|------|
| Resolution | @25 °C | | 0.0039 | | °C | 1 |
| Bias Accuracy | | | ±5 | | °C | |
| Scale factor accuracy | | | | ±5 | | % |
| Sample Rate | | | | 2000 | samples/s | 2 |

Note 1: Temperature measured at gyros. Temperature calibrated at static condition and referred to ambient temperature.

Note 2: Other values can be configured, ref. Table 6-8. Sample rate will be same for gyros, accelerometers, inclinometers, AUX and temperature

6.1 TYPICAL PERFORMANCE CHARACTERISTICS

6.1.1 GYRO CHARACTERISTICS

6.1.1.1 Root Allan Variance of gyro

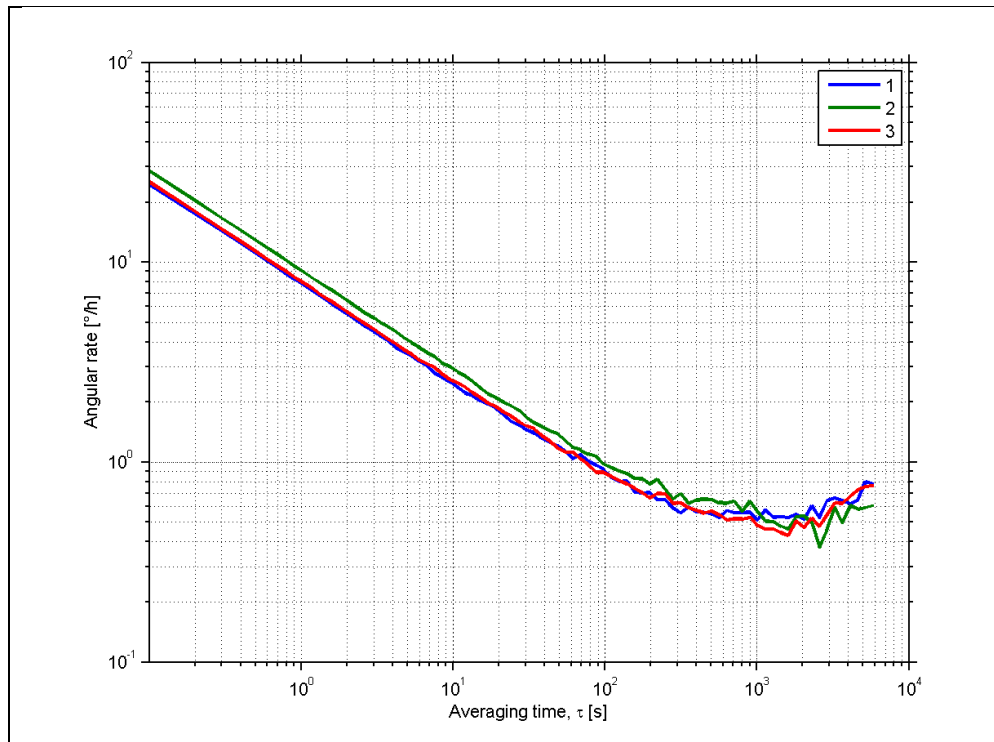
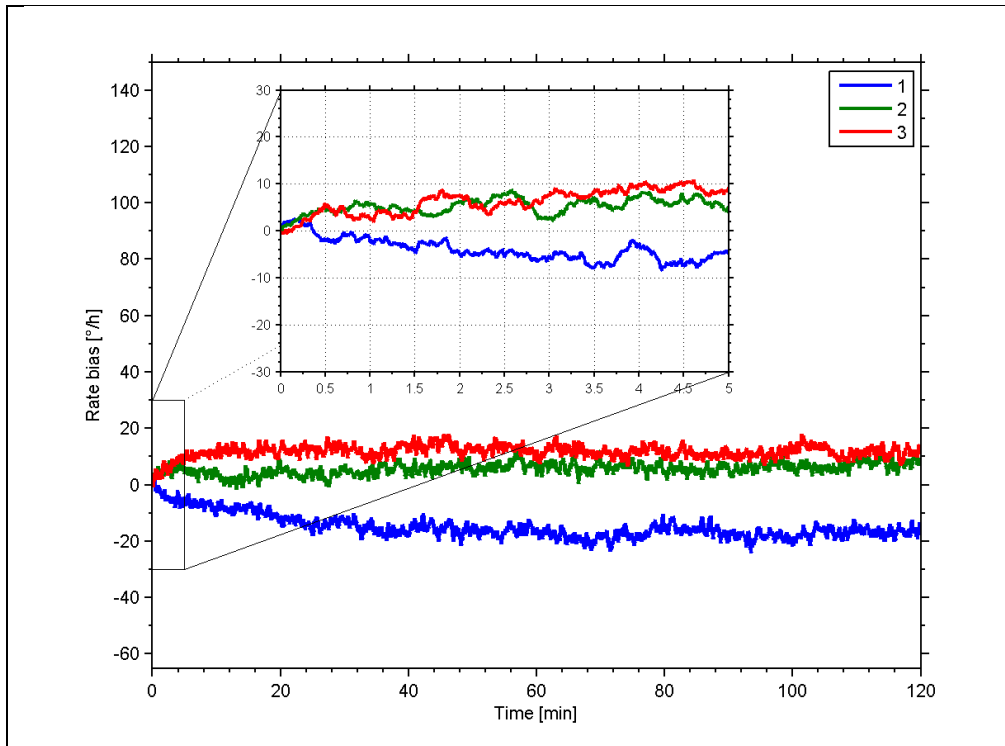
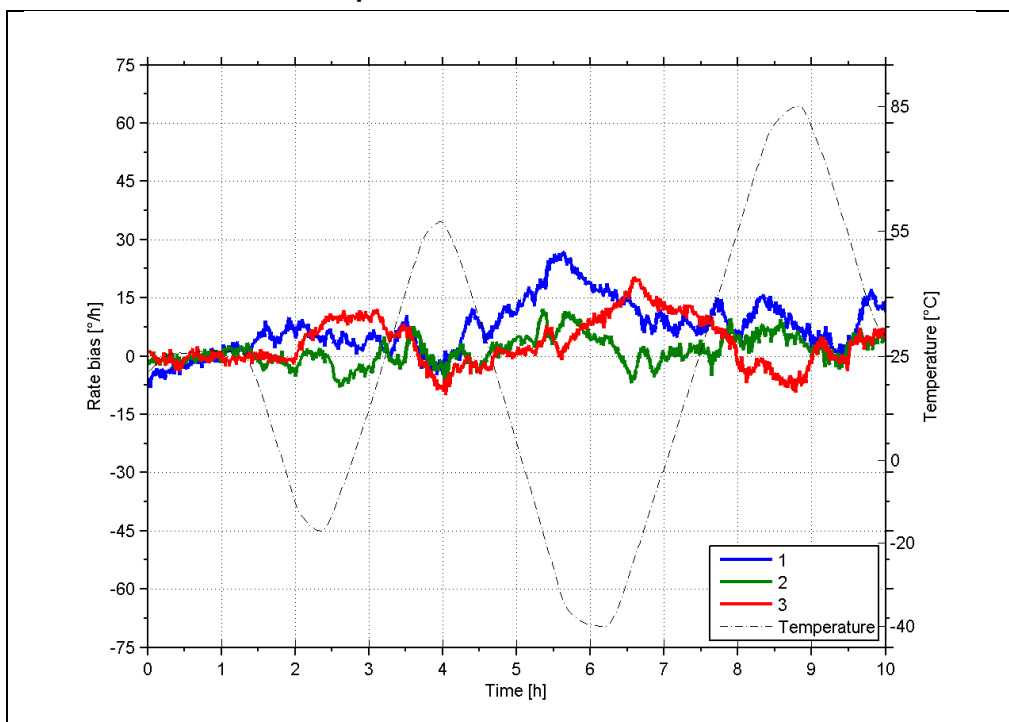


Figure 6-5: Typical Allan-Variance of gyro (400 %s gyro)

6.1.1.2 Initial bias drift of gyro

Figure 6-6: Typical normalized initial bias drift of gyro (400°/s gyro)
6.1.1.3 Bias drift over temperature

Figure 6-7: Typical Bias drift over temperature (400°/s gyro)

6.1.1.4 Frequency characteristics of gyros

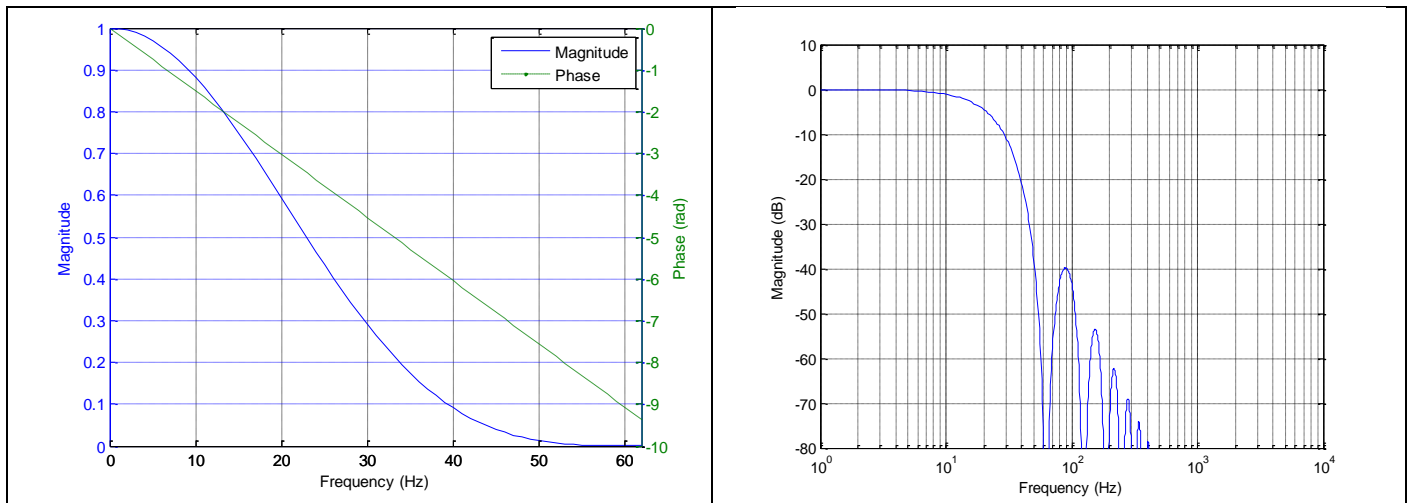


Figure 6-8: Frequency characteristics of gyros with low-pass filter -3dB frequency set to 16Hz

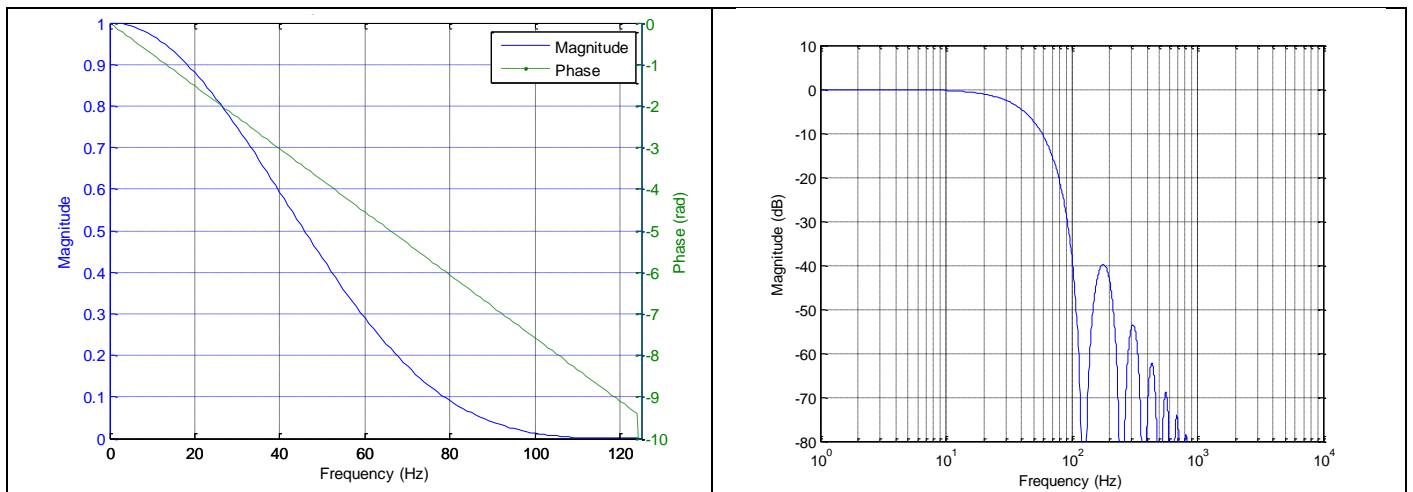


Figure 6-9: Frequency characteristics of gyros with low-pass filter -3dB frequency set to 33Hz

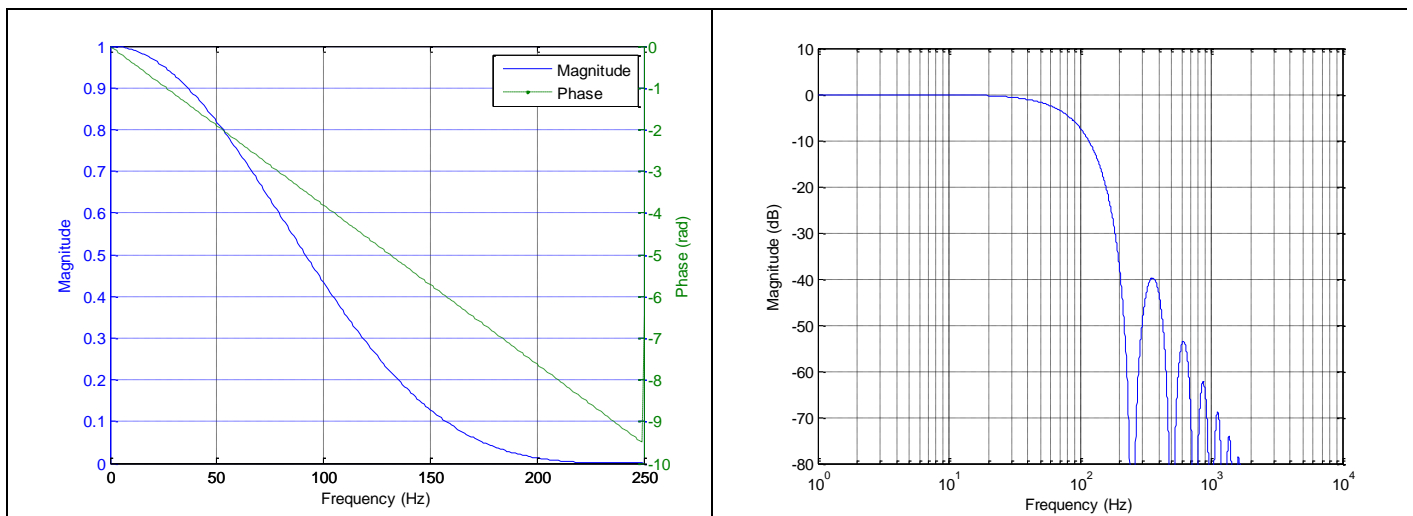


Figure 6-10: Frequency characteristics of gyros with low-pass filter -3dB frequency set to 66Hz

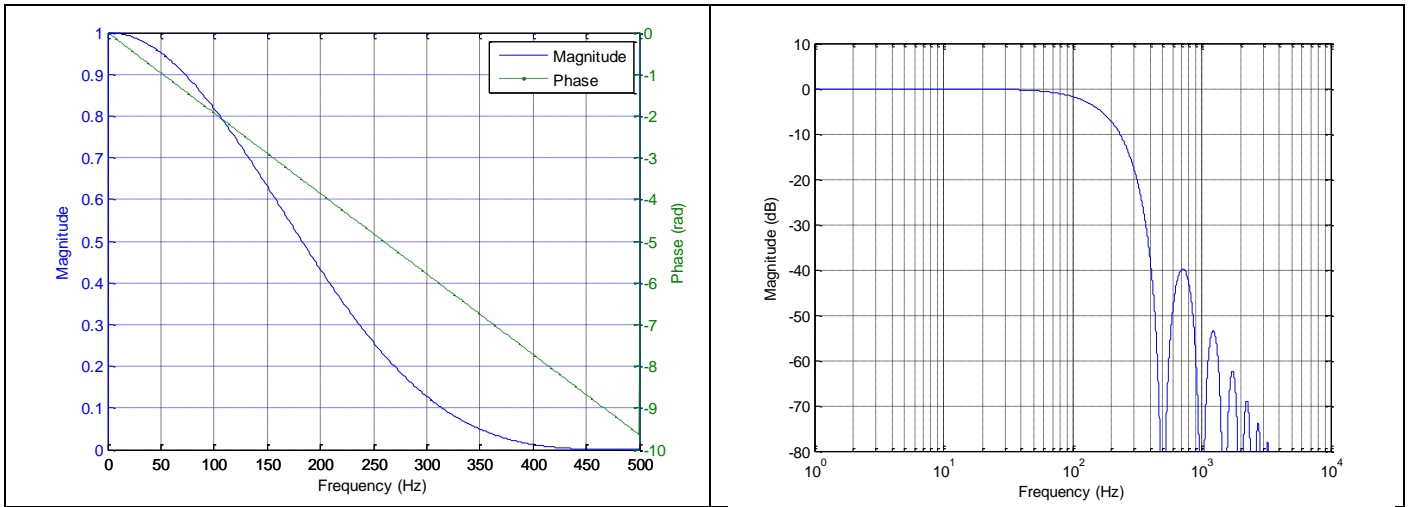


Figure 6-11: Frequency characteristics of gyros with low-pass filter -3dB frequency set to 131Hz

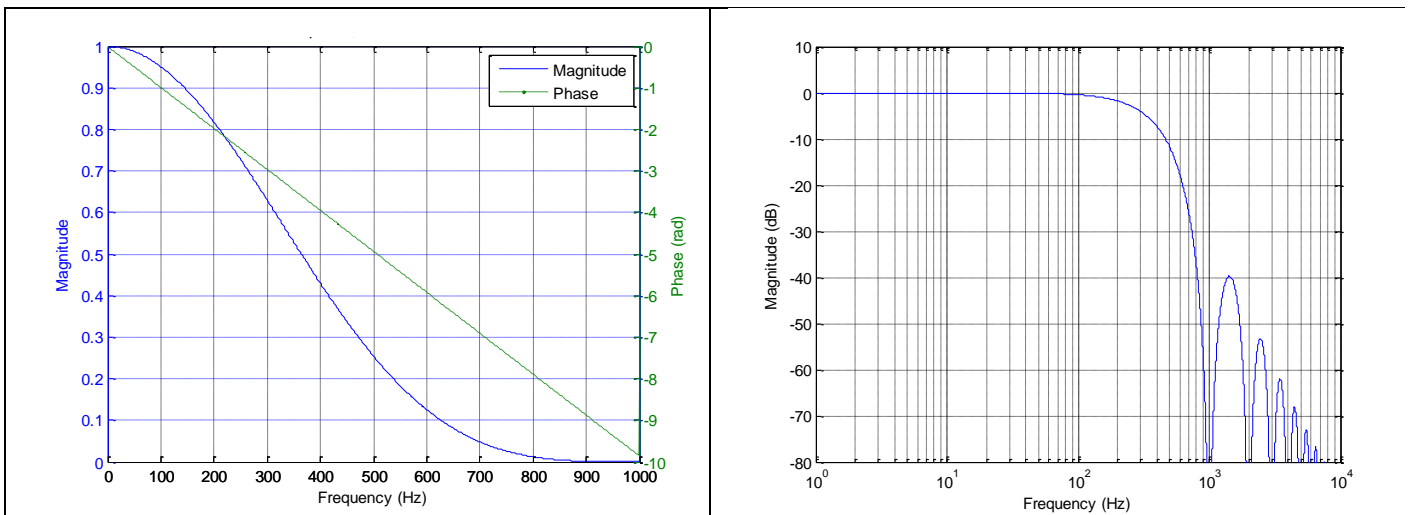


Figure 6-12: Frequency characteristics of gyros with low-pass filter -3dB frequency set to 262Hz

6.1.2 ACCELEROMETER CHARACTERISTICS

6.1.2.1 Root Allan Variance of accelerometer

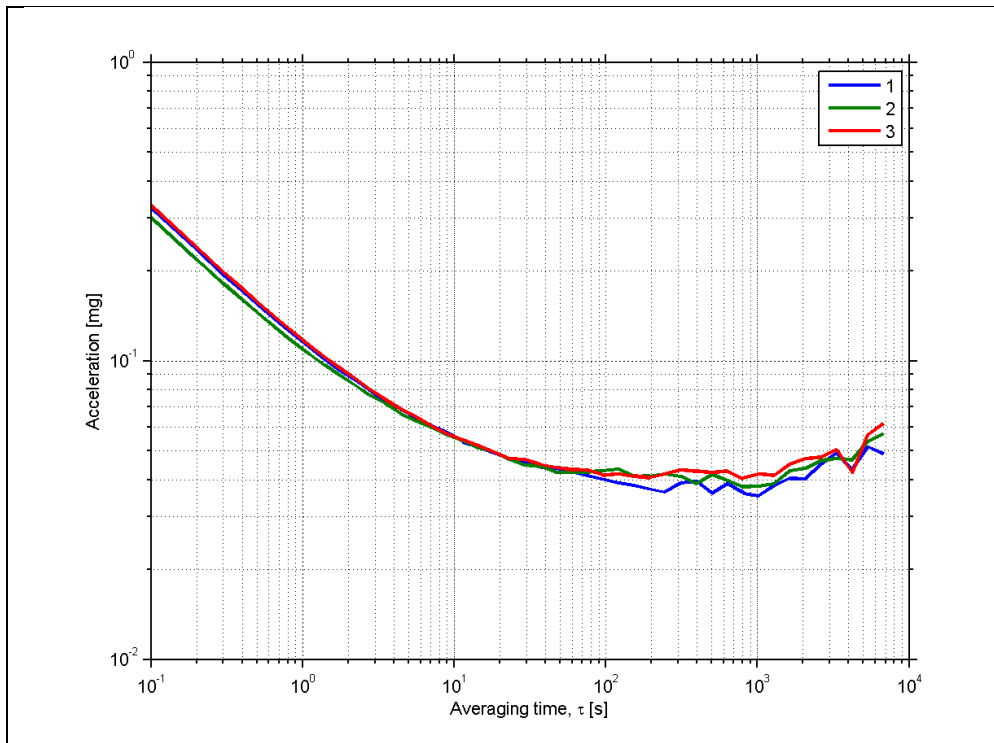


Figure 6-13: Typical Allan-Variance of accelerometer (10g accelerometer)

6.1.2.2 Initial bias drift of accelerometer

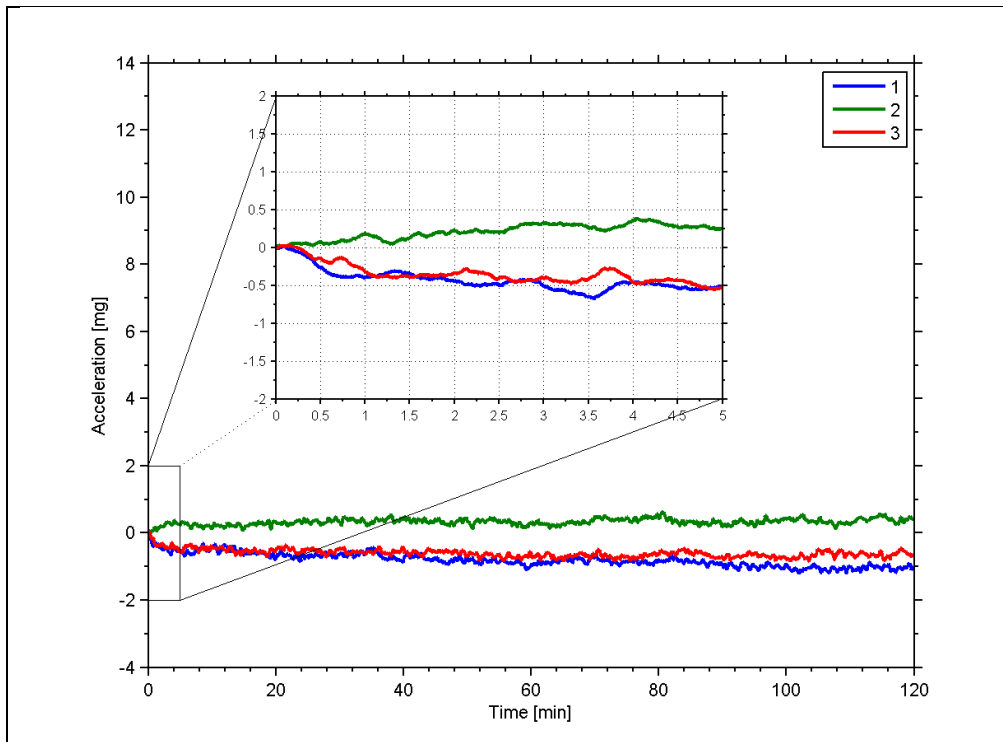


Figure 6-14: Typical normalized initial bias drift of accelerometer (10g accelerometer)

6.1.2.3 Frequency characteristics of accelerometers

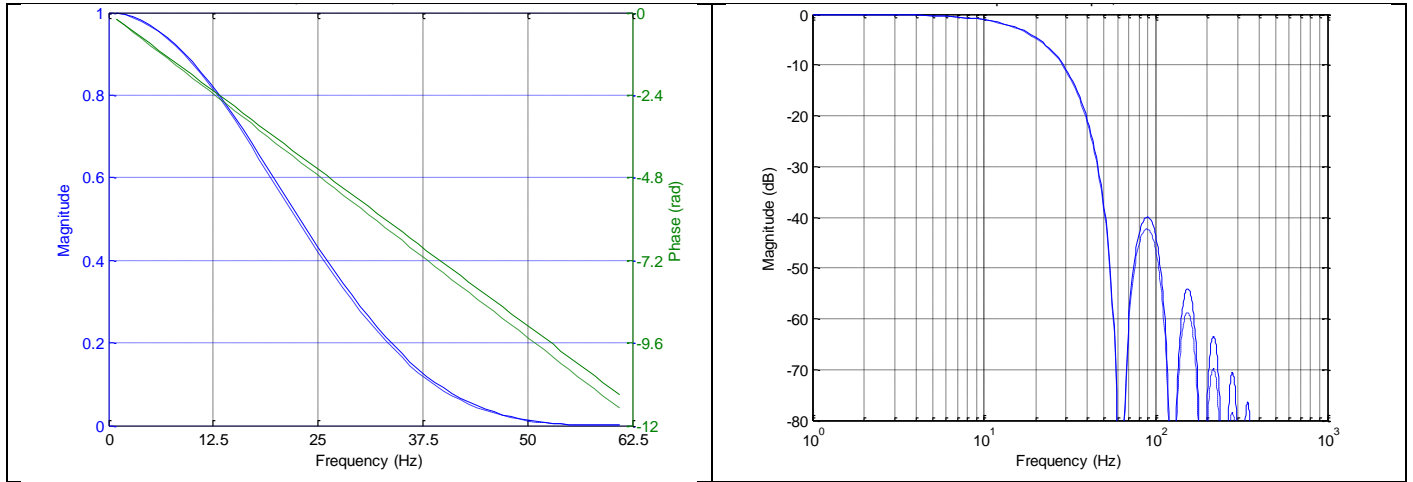


Figure 6-15: Frequency characteristics of accelerometers with low-pass filter -3dB frequency set to 16Hz (solid line: nominal, dashed line: minimum bandwidth, limited by accelerometer)

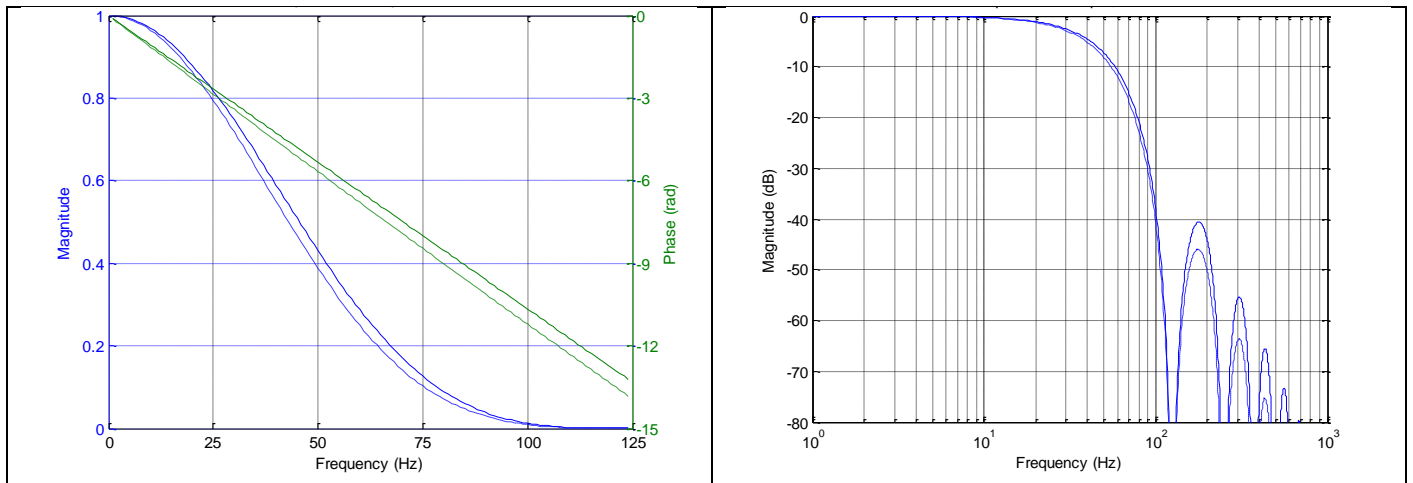


Figure 6-16: Frequency characteristics of accelerometers with low-pass filter -3dB frequency set to 33Hz (solid line: nominal, dashed line: minimum bandwidth, limited by accelerometer)

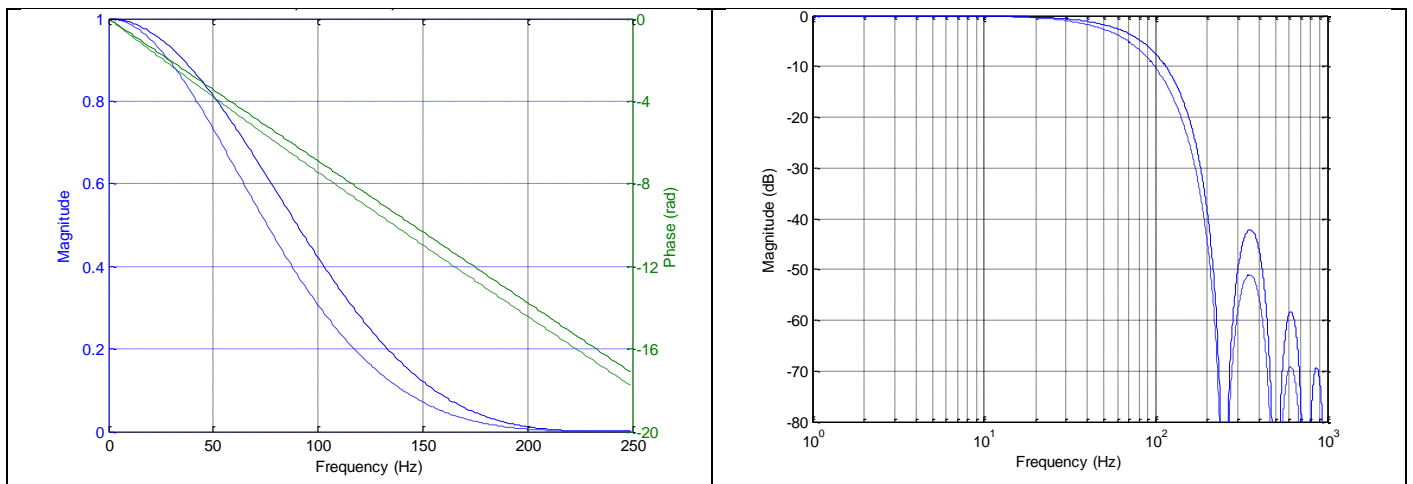


Figure 6-17: Frequency characteristics of accelerometers with low-pass filter -3dB frequency set to 66Hz (solid line: nominal, dashed line: minimum bandwidth, limited by accelerometer)

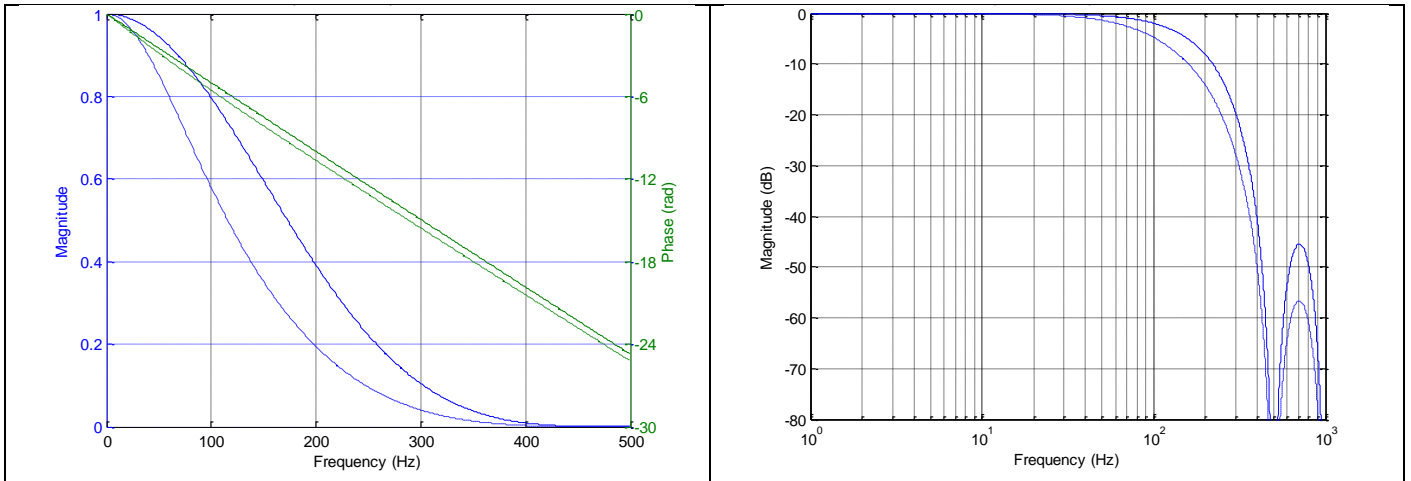


Figure 6-18: Frequency characteristics of accelerometers with low-pass filter -3dB frequency set to 131Hz (solid line: nominal, dashed line: minimum bandwidth, limited by accelerometer)

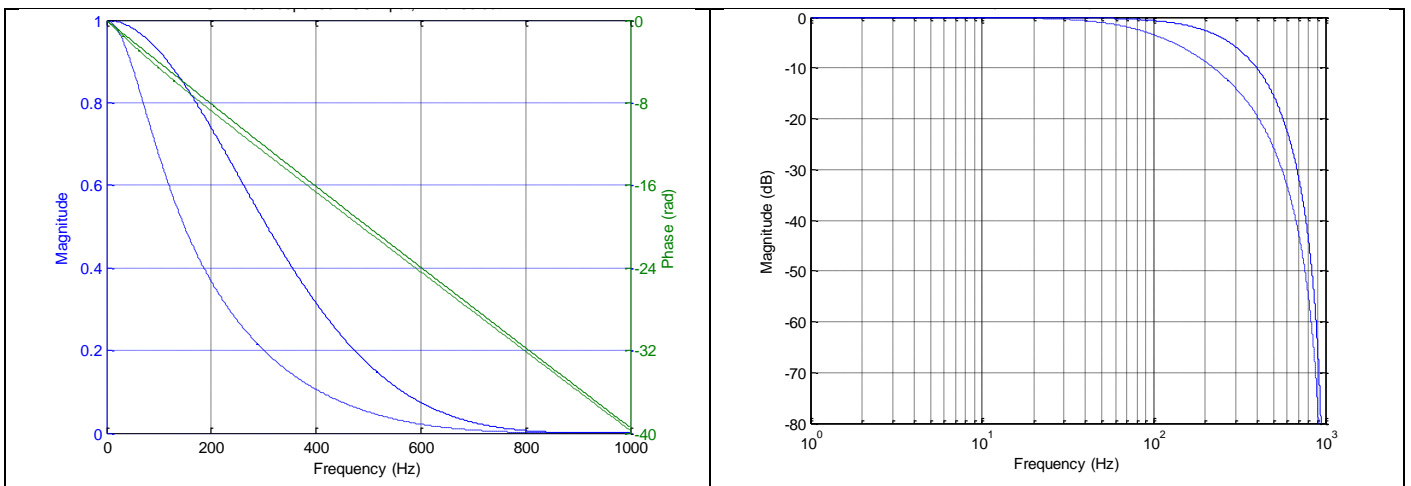


Figure 6-19: Frequency characteristics of accelerometers with low-pass filter -3dB frequency set to 262Hz (solid line: nominal, dashed line: minimum bandwidth, limited by accelerometer)

6.1.3 INCLINOMETER CHARACTERISTICS

6.1.3.1 Root Allan Variance of inclinometer

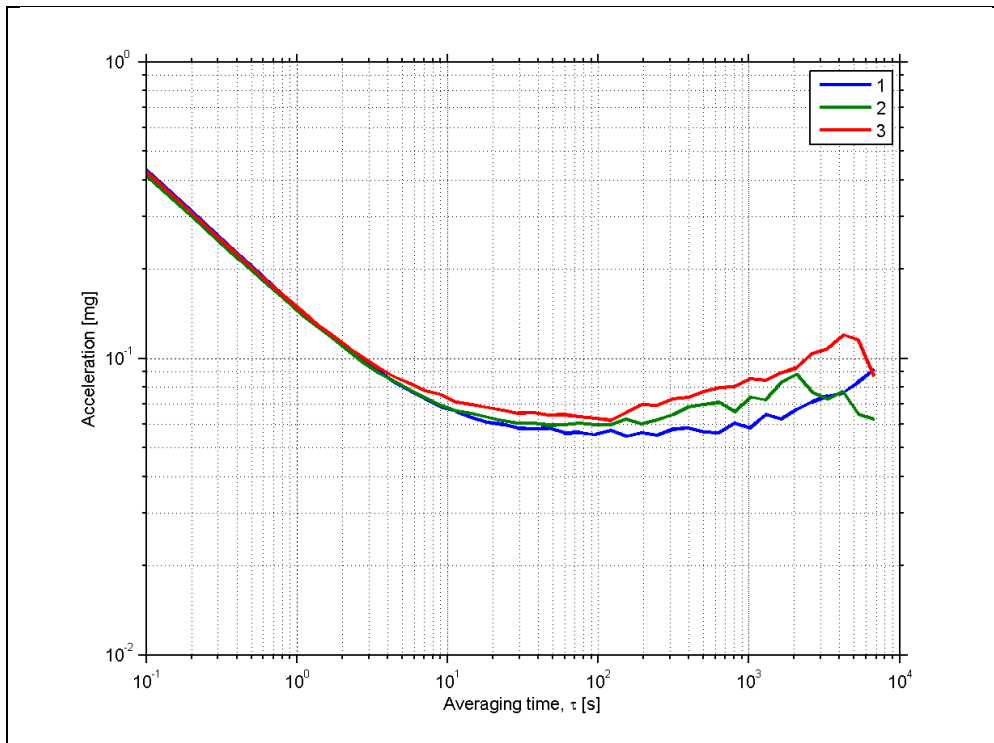


Figure 6-20: Typical Allan-Variance of inclinometer

6.1.3.2 Initial bias drift of inclinometer

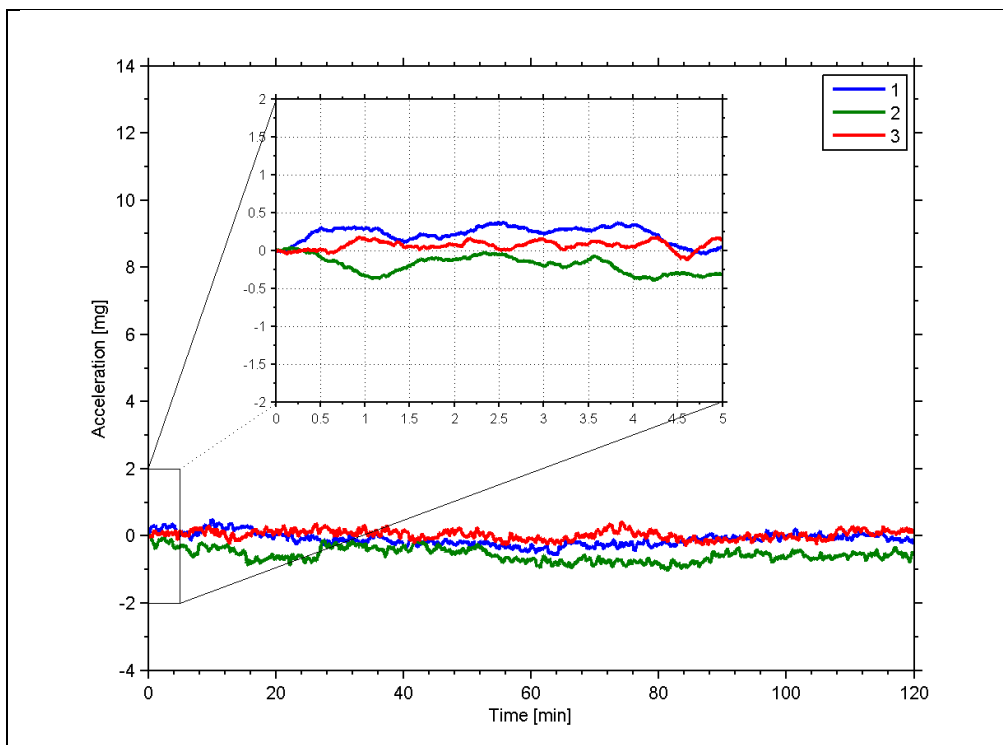


Figure 6-21: Typical normalized initial bias drift of inclinometer

6.1.3.3 Frequency characteristics of inclinometers

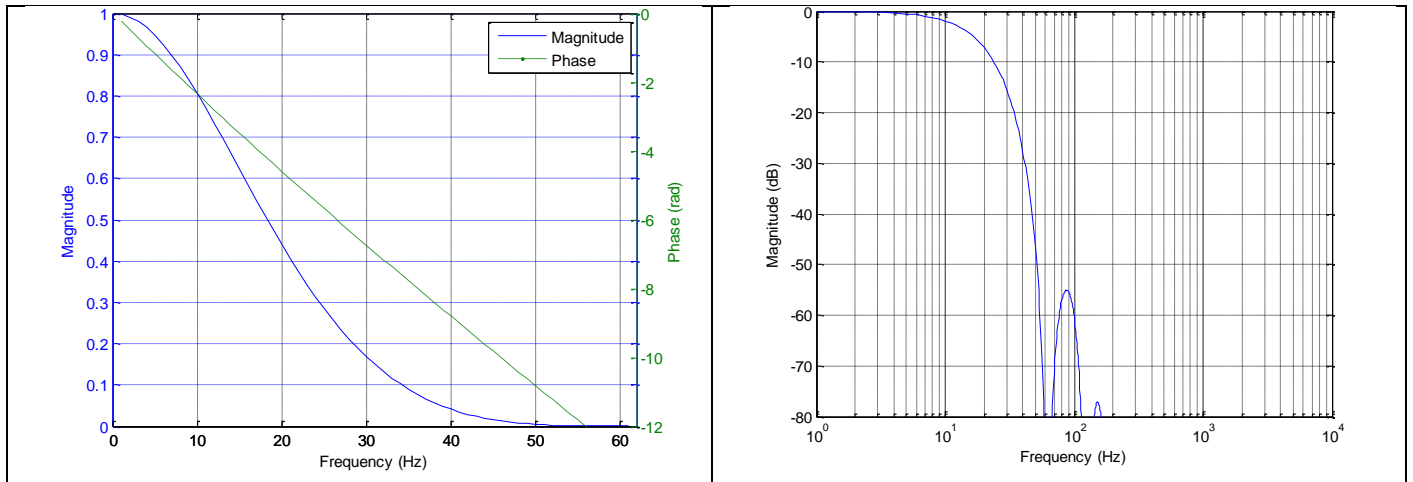


Figure 6-22: Frequency characteristics of inclinometers with low-pass filter -3dB frequency set to 16Hz

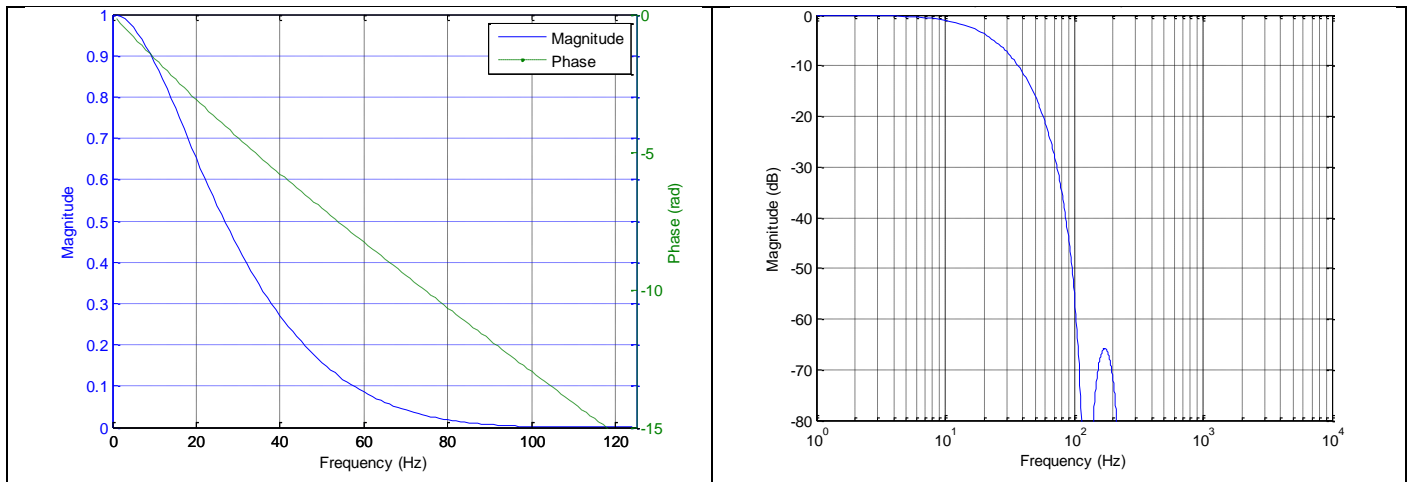


Figure 6-23: Frequency characteristics of inclinometers with low-pass filter -3dB frequency set to 33Hz

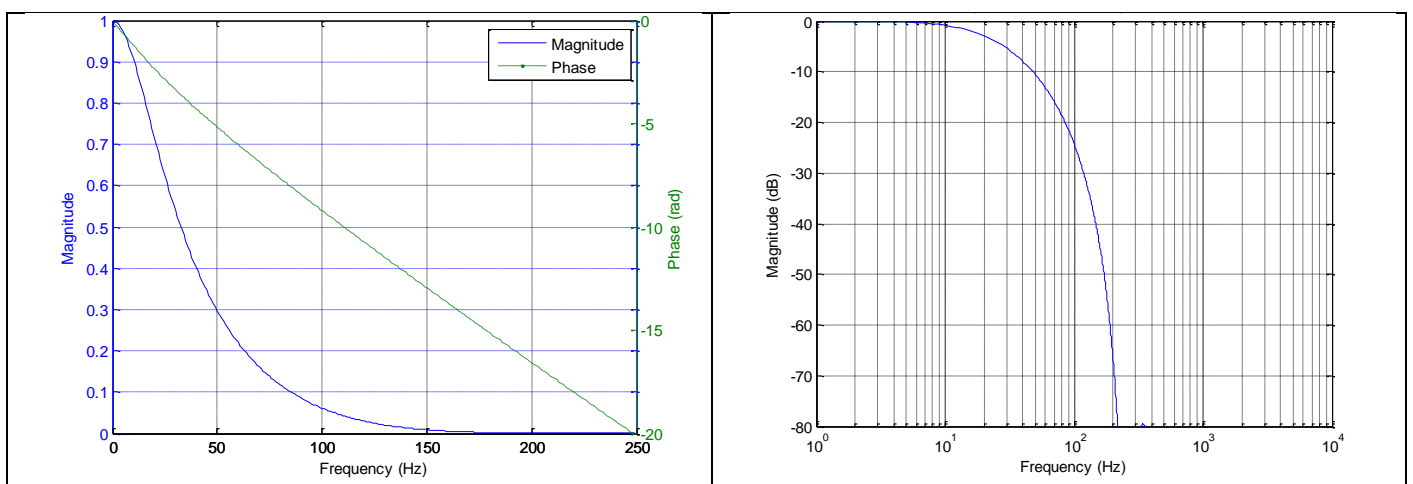


Figure 6-24: Frequency characteristics of inclinometers with low-pass filter -3dB frequency set to 66Hz

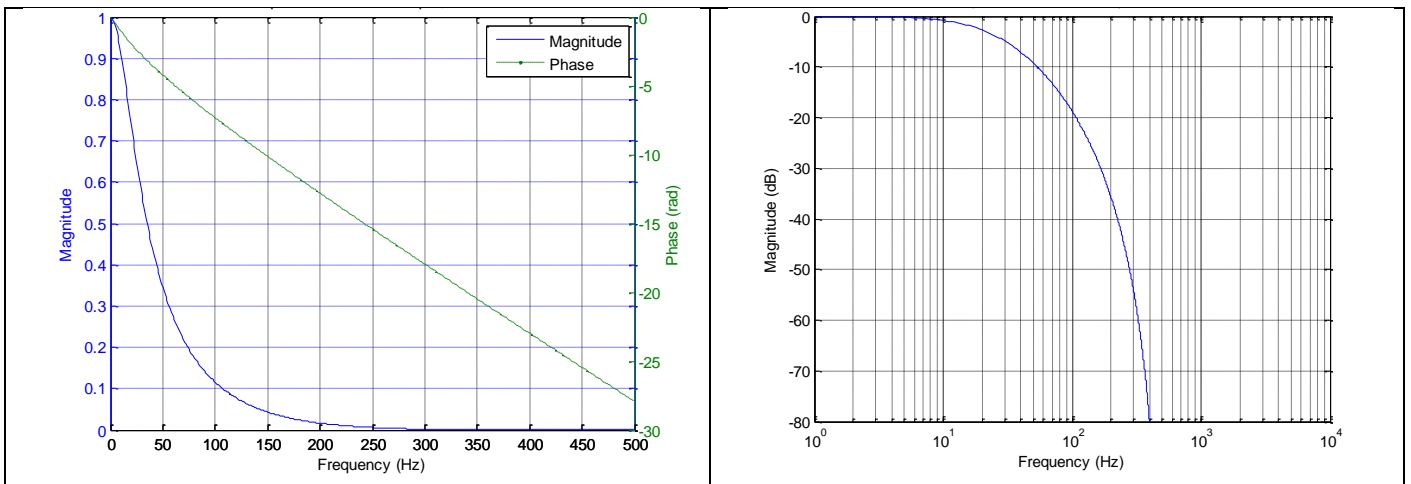


Figure 6-25: Frequency characteristics of inclinometers with low-pass filter -3dB frequency set to 131Hz

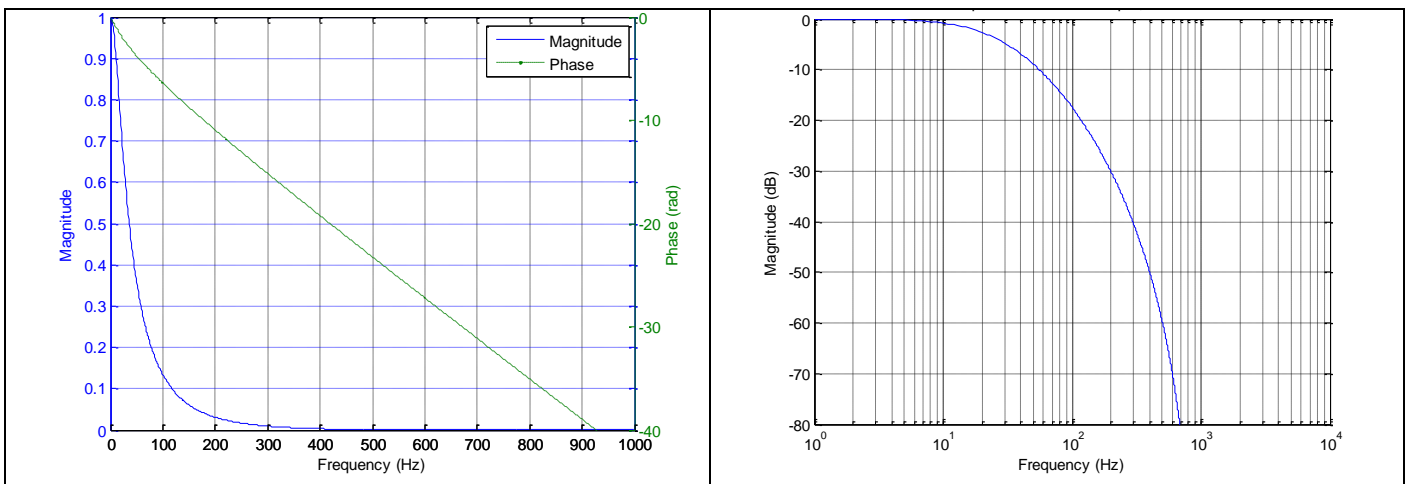


Figure 6-26: Frequency characteristics of inclinometers with low-pass filter -3dB frequency set to 262Hz

6.1.4 AUX CHARACTERISTICS

6.1.4.1 Frequency characteristics of AUX

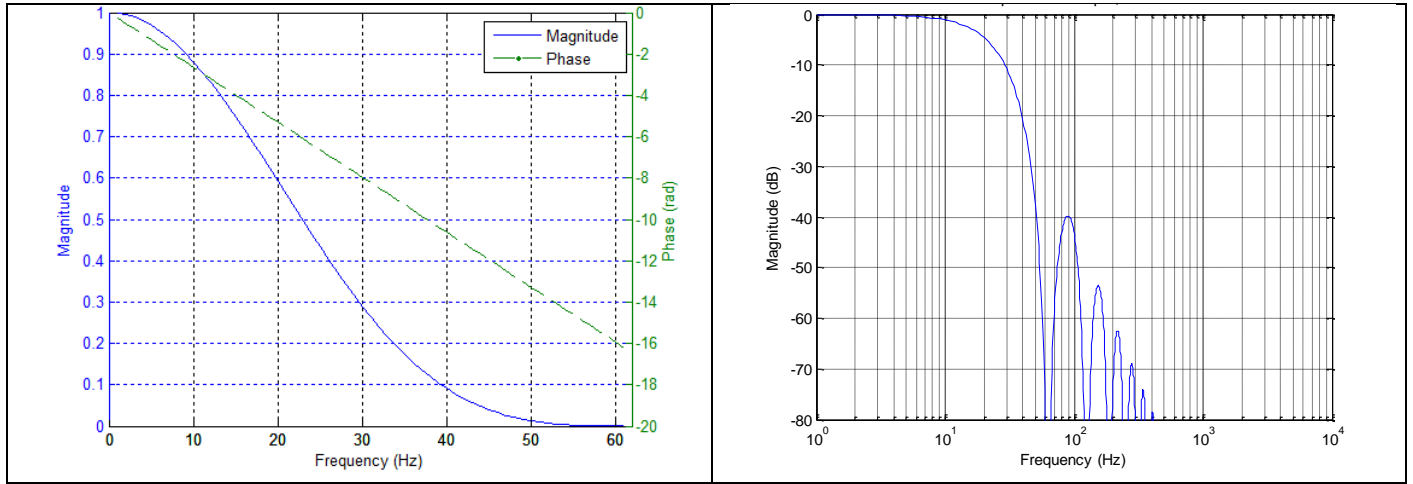


Figure 6-27: Frequency characteristics of AUX with low-pass filter -3dB frequency set to 16Hz

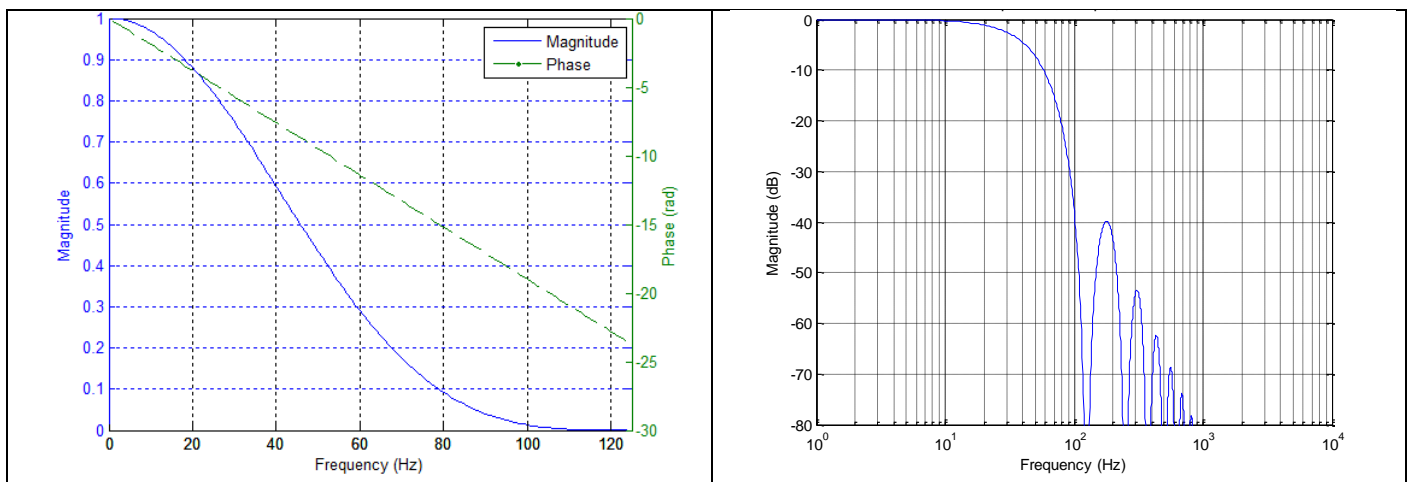


Figure 6-28: Frequency characteristics of AUX with low-pass filter -3dB frequency set to 33Hz

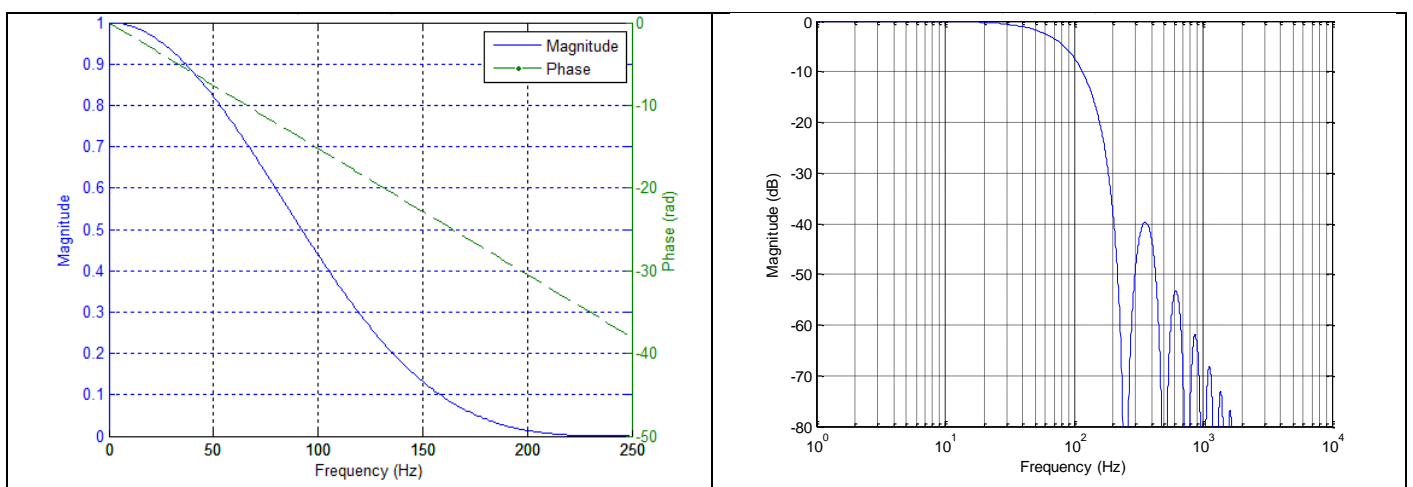


Figure 6-29: Frequency characteristics of AUX with low-pass filter -3dB frequency set to 66Hz

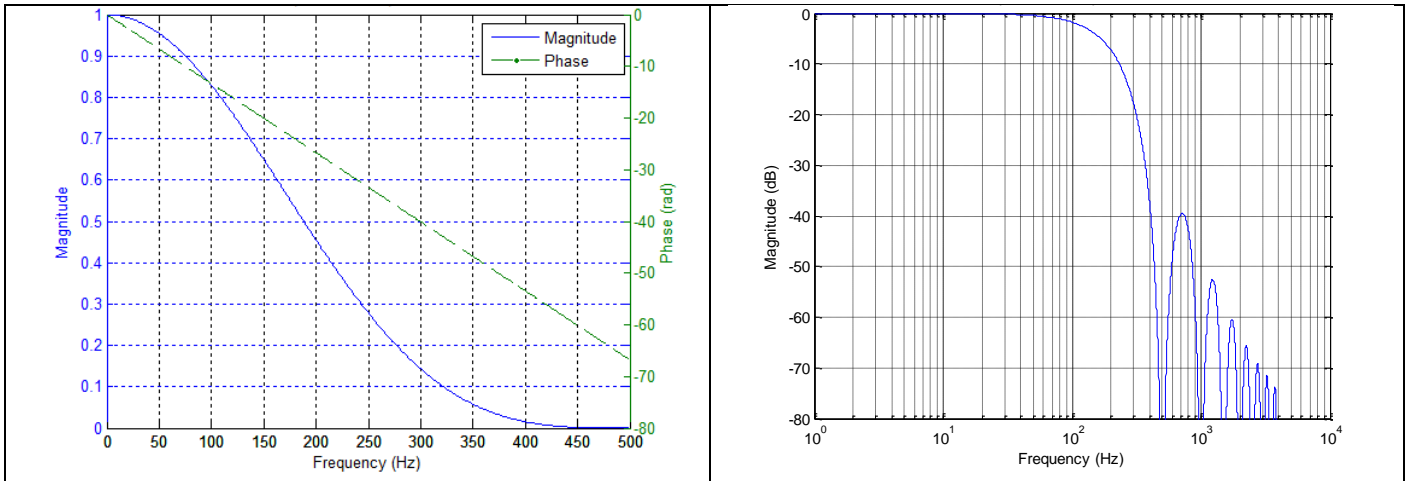


Figure 6-30: Frequency characteristics of AUX with low-pass filter -3dB frequency set to 131Hz

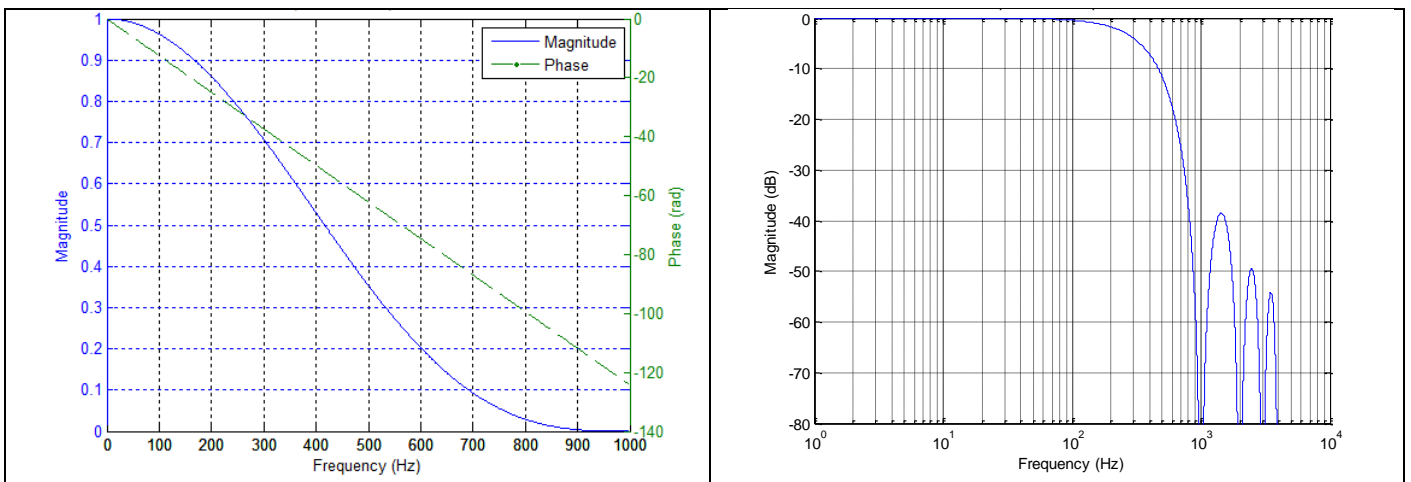


Figure 6-31: Frequency characteristics of AUX with low-pass filter -3dB frequency set to 262Hz

6.2 Configurable parameters

Table 6-8: Configurable parameters

| Parameter | Configurations | Comments |
|---------------------------------------|--|--|
| SAMPLE RATE | 125 samples/s 250 samples/s 500 samples/s 1000 samples/s 2000 samples/s External trigger | Some limitations apply to the use of higher sample rates (>500 samples/s), dependent on selected bit-rate and datagram content, ref. Table 6-9 |
| LOW-PASS FILTER -3dB FREQUENCY | 16Hz 33Hz 66Hz 131Hz 262Hz | Filter settings are independent of sample rate. Low-pass filters are CIC type filters with linear phase response. Filter settings can be set individually for each axis. |
| MEASUREMENT UNIT GYRO | Angular rate [°/s] Incremental angle [°/sample] Average angular rate [°/s] Integrated angle [°] | |
| MEASUREMENT UNIT ACCELEROMETER | Acceleration [g] Incremental velocity [m/s/sample] Average acceleration [g] | |
| MEASUREMENT UNIT INCLINOMETER | Acceleration [g] Incremental velocity [m/s/sample] Average acceleration [g] | |
| DATAGRAM | Rate together with any combination of acceleration, inclination, temperature and AUX | |
| DATAGRAM TERMINATION | NONE <CR><LF> | |
| RS422 BIT-RATE | 374400 bits/s 460800 bits/s 921600 bits/s 1843200 bits/s User-defined | Some limitations apply to the use of lower bit-rates (< 1843200 bits/s) dependent on sample rate and datagram content, ref. Table 6-9. For user-defined bit-rates, see section 10.5 |
| RS422 PARITY | None Odd Even | |
| RS422 STOP BITS | 1 stop bit 2 stop bits | |
| RS422 120Ω LINE TERMINATION | OFF ON | |

Refer to section 12 for information on how to configure STIM300 when ordering and to section 10 for information on how to reconfigure the unit in Service Mode.

Some datagrams are longer than the time between each sample at the lower bit-rate. Table 6-9 show the maximum bit-rates.

Table 6-9: Maximum sample rate

| Datagram content | Number of transmitted bytes ^{Note 1} | 374400 bits/s ^{Note 2} | 460800 bits/s ^{Note 2} | 921600 bits/s ^{Note 2} | 1843200 bits/s ^{Note 2} |
|--|---|---------------------------------|---------------------------------|---------------------------------|----------------------------------|
| Rate | 20 | 1000 | 1000 | 2000 | 2000 |
| Rate and acceleration | 30 | 500 | 1000 | 2000 | 2000 |
| Rate and inclination | 30 | 500 | 1000 | 2000 | 2000 |
| Rate, acceleration and inclination | 40 | 500 | 500 | 1000 | 2000 |
| Rate and temperature | 27 | 1000 | 1000 | 2000 | 2000 |
| Rate, acceleration and temperature | 44 | 500 | 500 | 1000 | 2000 |
| Rate, inclination and temperature | 44 | 500 | 500 | 1000 | 2000 |
| Rate, acceleration, inclination and temperature | 61 | 250 | 500 | 1000 | 2000 |
| Rate and AUX | 24 | 1000 | 1000 | 2000 | 2000 |
| Rate, acceleration and AUX | 34 | 500 | 1000 | 2000 | 2000 |
| Rate, inclination and AUX | 34 | 500 | 1000 | 2000 | 2000 |
| Rate, acceleration, inclination and AUX | 44 | 500 | 500 | 1000 | 2000 |
| Rate, temperature and AUX | 31 | 500 | 1000 | 2000 | 2000 |
| Rate, acceleration, temperature and AUX | 48 | 500 | 500 | 1000 | 2000 |
| Rate, inclination, temperature and AUX | 48 | 500 | 500 | 1000 | 2000 |
| Rate, acceleration, inclination, temperature and AUX | 65 | 250 | 500 | 1000 | 2000 |

Note 1: including <CR><LF> termination

Note 2: 12 bits/byte (=1 start bit, 8 data bits, 1 parity bit, 2 stop bits)

6.3 Datagram specifications

6.3.1 Part Number datagram

Table 6-10: Specification of the Part Number datagram

| Byte# | Bit# | | | | | | | | Specification |
|-------|------------------|------------------|------------------|------------------|------------------|------------------|------------------|------------------|---|
| | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 | |
| 0 | 1 | 0 | 1 | 1 | 0 | 0 | 0 | 1 | Part Number datagram identifier: 0xB1 for datagrams without CR+LF termination 0xB3 for datagrams with CR+LF termination |
| 1 | 0 | 0 | 0 | 0 | P1 ₃ | P1 ₂ | P1 ₁ | P1 ₀ | Low nibble: 1.digit (BCD) of part number |
| 2 | P2 ₃ | P2 ₂ | P2 ₁ | P2 ₀ | P3 ₃ | P3 ₂ | P3 ₁ | P3 ₀ | High nibble: 2.digit (BCD) of part number Low nibble: 3.digit (BCD) of part number |
| 3 | P4 ₃ | P4 ₂ | P4 ₁ | P4 ₀ | P5 ₃ | P5 ₂ | P5 ₁ | P5 ₀ | High nibble: 4.digit (BCD) of part number Low nibble: 5.digit (BCD) of part number |
| 4 | 0 | 0 | 1 | 0 | 1 | 1 | 0 | 1 | ASCII character "-" (0x2D) |
| 5 | P6 ₃ | P6 ₂ | P6 ₁ | P6 ₀ | P7 ₃ | P7 ₂ | P7 ₁ | P7 ₀ | High nibble: 6.digit (BCD) of part number Low nibble: 7.digit (BCD) of part number |
| 6 | P8 ₃ | P8 ₂ | P8 ₁ | P8 ₀ | P9 ₃ | P9 ₂ | P9 ₁ | P9 ₀ | High nibble: 8.digit (BCD) of part number Low nibble: 9.digit (BCD) of part number |
| 7 | P10 ₃ | P10 ₂ | P10 ₁ | P10 ₀ | P11 ₃ | P11 ₂ | P11 ₁ | P11 ₀ | High nibble: 10.digit (BCD) of part number Low nibble: 11.digit (BCD) of part number |
| 8 | 0 | 0 | 1 | 0 | 1 | 1 | 0 | 1 | ASCII character "-" (0x2D) |
| 9 | P12 ₃ | P12 ₂ | P12 ₁ | P12 ₀ | P13 ₃ | P13 ₂ | P13 ₁ | P13 ₀ | High nibble: 12.digit (BCD) of part number Low nibble: 13.digit (BCD) of part number |
| 10 | P14 ₃ | P14 ₂ | P14 ₁ | P14 ₀ | x | x | x | x | High nibble: 14.digit (BCD) of part number |
| 11 | x | x | x | x | x | x | x | x | For future use |
| 12 | x | x | x | x | x | x | x | x | For future use |
| 13 | x | x | x | x | x | x | x | x | For future use |
| 14 | x | x | x | x | x | x | x | x | For future use |
| 15 | r ₇ | r ₆ | r ₅ | r ₄ | r ₃ | r ₂ | r ₁ | r ₀ | Part number revision. Content of byte represents the ASCII-character of the revision. Numbering sequence: "-", "A", "B", ..., "Z" |
| 16 | C ₃₁ | C ₃₀ | C ₂₉ | C ₂₈ | C ₂₇ | C ₂₆ | C ₂₅ | C ₂₄ | Cyclic Redundancy Check is performed on all preceding bytes, ref: 6.3.5 |
| 17 | C ₂₃ | C ₂₂ | C ₂₁ | C ₂₀ | C ₁₉ | C ₁₈ | C ₁₇ | C ₁₆ | |
| 18 | C ₁₅ | C ₁₄ | C ₁₃ | C ₁₂ | C ₁₁ | C ₁₀ | C ₉ | C ₈ | |
| 19 | C ₇ | C ₆ | C ₅ | C ₄ | C ₃ | C ₂ | C ₁ | C ₀ | |
| (20) | 0 | 0 | 0 | 0 | 1 | 1 | 0 | 1 | <CR> If datagram termination has been selected |
| (21) | 0 | 0 | 0 | 0 | 1 | 0 | 1 | 0 | <LF> If datagram termination has been selected |

6.3.2 Serial Number datagram

Table 6-11: Specification of the Serial Number datagram

| Byte# | Bit# | | | | | | | | Specification |
|-------|------------------|------------------|------------------|------------------|------------------|------------------|------------------|------------------|--|
| | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 | |
| 0 | 1 | 0 | 1 | 1 | 0 | 1 | 0 | 1 | Serial Number datagram identifier: 0xB5 for datagrams without CR+LF termination 0xB7 for datagrams with CR+LF termination |
| 1 | 0 | 1 | 0 | 0 | 1 | 1 | 1 | 0 | ASCII-character for letter "N" |
| 2 | S ₁₃ | S ₁₂ | S ₁₁ | S ₁₀ | S ₉ | S ₈ | S ₇ | S ₆ | High nibble: 1.digit (BCD) of serial number Low nibble: 2.digit (BCD) of serial number |
| 3 | S ₃₃ | S ₃₂ | S ₃₁ | S ₃₀ | S ₂₉ | S ₂₈ | S ₂₇ | S ₂₆ | High nibble: 3.digit (BCD) of serial number Low nibble: 4.digit (BCD) of serial number |
| 4 | S ₅₃ | S ₅₂ | S ₅₁ | S ₅₀ | S ₄₉ | S ₄₈ | S ₄₇ | S ₄₆ | High nibble: 5.digit (BCD) of serial number Low nibble: 6.digit (BCD) of serial number |
| 5 | S ₇₃ | S ₇₂ | S ₇₁ | S ₇₀ | S ₆₉ | S ₆₈ | S ₆₇ | S ₆₆ | High nibble: 7.digit (BCD) of serial number Low nibble: 8.digit (BCD) of serial number |
| 6 | S ₉₃ | S ₉₂ | S ₉₁ | S ₉₀ | S ₈₉ | S ₈₈ | S ₈₇ | S ₈₆ | High nibble: 9.digit (BCD) of serial number Low nibble: 10.digit (BCD) of serial number |
| 7 | S ₁₁₃ | S ₁₁₂ | S ₁₁₁ | S ₁₁₀ | S ₁₀₉ | S ₁₀₈ | S ₁₀₇ | S ₁₀₆ | High nibble: 11.digit (BCD) of serial number Low nibble: 12.digit (BCD) of serial number |
| 8 | S ₁₃₃ | S ₁₃₂ | S ₁₃₁ | S ₁₃₀ | S ₁₂₉ | S ₁₂₈ | S ₁₂₇ | S ₁₂₆ | High nibble: 13.digit (BCD) of serial number Low nibble: 14.digit (BCD) of serial number |
| 9 | x | x | x | x | x | x | x | x | For future use |
| 10 | x | x | x | x | x | x | x | x | For future use |
| 11 | x | x | x | x | x | x | x | x | For future use |
| 12 | x | x | x | x | x | x | x | x | For future use |
| 13 | x | x | x | x | x | x | x | x | For future use |
| 14 | x | x | x | x | x | x | x | x | For future use |
| 15 | x | x | x | x | x | x | x | x | For future use |
| 16 | C ₃₁ | C ₃₀ | C ₂₉ | C ₂₈ | C ₂₇ | C ₂₆ | C ₂₅ | C ₂₄ | Cyclic Redundancy Check is performed on all preceding bytes, ref: 6.3.5 |
| 17 | C ₂₃ | C ₂₂ | C ₂₁ | C ₂₀ | C ₁₉ | C ₁₈ | C ₁₇ | C ₁₆ | |
| 18 | C ₁₅ | C ₁₄ | C ₁₃ | C ₁₂ | C ₁₁ | C ₁₀ | C ₉ | C ₈ | |
| 19 | C ₇ | C ₆ | C ₅ | C ₄ | C ₃ | C ₂ | C ₁ | C ₀ | |
| (20) | 0 | 0 | 0 | 0 | 1 | 1 | 0 | 1 | <CR> If datagram termination has been selected |
| (21) | 0 | 0 | 0 | 0 | 1 | 0 | 1 | 0 | <LF> If datagram termination has been selected |

6.3.3 Configuration datagram

Table 6-12: Specification of the Configuration datagram

| Byte# | Bit# | | | | | | | | Specification |
|-------|----------------|----------------|----------------|----------------|----------------|----------------|----------------|---|--|
| | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 | |
| 0 | 1 | 0 | 1 | 1 | 1 | 0 | 0 | 1 | Configuration datagram identifier: 0xBC for datagrams without CR+LF termination 0xBD for datagrams with CR+LF termination |
| 1 | r ₇ | r ₆ | r ₅ | r ₄ | r ₃ | r ₂ | r ₁ | r ₀ | Part number revision. Content of byte represents the ASCII-character of the revision. Numbering sequence: "-", "A", "B", ..., "Z" |
| 2 | f ₇ | f ₆ | f ₅ | f ₄ | f ₃ | f ₂ | f ₁ | f ₀ | Firmware revision. Numbering sequence: 0, 1, ..., 255 |
| 3 | 0 | 0 | 0 | x | x | x | x | x | System configuration, Byte 1: Sample frequency = 125 samples/s |
| | 0 | 0 | 1 | x | x | x | x | x | Sample frequency = 250 samples/s |
| | 0 | 1 | 0 | x | x | x | x | x | Sample frequency = 500 samples/s |
| | 0 | 1 | 1 | x | x | x | x | x | Sample frequency = 1000 samples/s |
| | 1 | 0 | 0 | x | x | x | x | x | Sample frequency = 2000 samples/s |
| | 1 | 0 | 1 | x | x | x | x | x | Sample frequency = External trigger |
| | x | x | x | 0 | x | x | x | x | AUX not included in Datagram |
| | x | x | x | 1 | x | x | x | x | AUX included in Datagram |
| | x | x | x | x | 0 | x | x | x | Temperature not included in Normal Mode datagram |
| | x | x | x | x | 1 | x | x | x | Temperature included in Normal Mode datagram |
| | x | x | x | x | x | 0 | x | x | Inclination not included in Normal Mode datagram |
| | x | x | x | x | x | 1 | x | x | Inclination included in Normal Mode datagram |
| | x | x | x | x | x | x | 0 | x | Acceleration not included in Normal Mode datagram |
| | x | x | x | x | x | x | 1 | x | Acceleration included in Normal Mode datagram |
| x | x | x | x | x | x | x | 0 | No <CR><LF> termination of Normal Mode datagram | |
| x | x | x | x | x | x | x | 1 | <CR><LF> termination of Normal Mode datagram | |
| 4 | 0 | 0 | 0 | 0 | x | x | x | x | System configuration, Byte 2: Bit-rate = 374400 bits/s |
| | 0 | 0 | 0 | 1 | x | x | x | x | Bit-rate = 460800 bits/s |
| | 0 | 0 | 1 | 0 | x | x | x | x | Bit-rate = 921600 bits/s |
| | 0 | 0 | 1 | 1 | x | x | x | x | Bit-rate = 1843200 bits/s |
| | 1 | 1 | 1 | 1 | x | x | x | x | Bit-rate = User-defined, ref.section 10.5 |
| | x | x | x | x | 0 | x | x | x | Stop bit = 1 |
| | x | x | x | x | 1 | x | x | x | Stop bits = 2 |
| | x | x | x | x | x | 0 | 0 | x | Parity = none |
| | x | x | x | x | x | 0 | 1 | x | Parity = even |
| | x | x | x | x | x | 1 | 0 | x | Parity = odd |
| | x | x | x | x | x | x | x | 0 | Line termination = OFF |
| x | x | x | x | x | x | x | 1 | Line termination = ON | |
| 5 | x | 0 | x | x | x | x | x | x | System configuration, Byte 3: Gyro X-axis is inactive |
| | x | 1 | x | x | x | x | x | x | Gyro X-axis is active |
| | x | x | 0 | x | x | x | x | x | Gyro Y-axis is inactive |
| | x | x | 1 | x | x | x | x | x | Gyro Y-axis is active |
| | x | x | x | 0 | x | x | x | x | Gyro Z-axis is inactive |
| | x | x | x | 1 | x | x | x | x | Gyro Z-axis is active |
| | x | x | x | x | 0 | 0 | 0 | 0 | Gyro output unit = ANGULAR RATE |
| | x | x | x | x | 0 | 0 | 0 | 1 | Gyro output unit = INCREMENTAL ANGLE |
| | x | x | x | x | 0 | 0 | 1 | 0 | Gyro output unit = AVERAGE ANGULAR RATE |
| | x | x | x | x | 0 | 0 | 1 | 1 | Gyro output unit = INTEGRATED ANGLE |
| | x | x | x | x | 1 | 0 | 0 | 0 | Gyro output unit = ANGULAR RATE - DELAYED |
| | x | x | x | x | 1 | 0 | 0 | 1 | Gyro output unit = INCREMENTAL ANGLE - DELAYED |
| | x | x | x | x | 1 | 0 | 1 | 0 | Gyro output unit = AVERAGE ANGULAR RATE - DELAYED |
| x | x | x | x | 1 | 0 | 1 | 1 | Gyro output unit = INTEGRATED ANGLE - DELAYED | |
| 6 | x | 0 | 0 | 0 | x | x | x | x | System configuration, Byte 4: Gyro LP filter -3dB frequency for X-axis = 16Hz |
| | x | 0 | 0 | 1 | x | x | x | x | Gyro LP filter -3dB frequency for X-axis = 33Hz |
| | x | 0 | 1 | 0 | x | x | x | x | Gyro LP filter -3dB frequency for X-axis = 66Hz |
| | x | 0 | 1 | 1 | x | x | x | x | Gyro LP filter -3dB frequency for X-axis = 121Hz |
| | x | 1 | 0 | 0 | x | x | x | x | Gyro LP filter -3dB frequency for X-axis = 262Hz |
| | x | x | x | x | x | 0 | 0 | 0 | Gyro LP filter -3dB frequency for Y-axis = 16Hz |
| | x | x | x | x | x | 0 | 0 | 1 | Gyro LP filter -3dB frequency for Y-axis = 33Hz |
| | x | x | x | x | x | 0 | 1 | 0 | Gyro LP filter -3dB frequency for Y-axis = 66Hz |
| | x | x | x | x | x | 0 | 1 | 1 | Gyro LP filter -3dB frequency for Y-axis = 121Hz |
| | x | x | x | x | x | 1 | 0 | 0 | Gyro LP filter -3dB frequency for Y-axis = 262Hz |

| | | | | | | | | | |
|----|---|---|---|---|---|---|---|--|---|
| 7 | x | 0 | 0 | 0 | x | x | x | x | System configuration, Byte 5: |
| | x | 0 | 0 | 1 | x | x | x | x | Gyro LP filter -3dB frequency for Z-axis = 16Hz |
| | x | 0 | 1 | 0 | x | x | x | x | Gyro LP filter -3dB frequency for Z-axis = 33Hz |
| | x | 0 | 1 | 1 | x | x | x | x | Gyro LP filter -3dB frequency for Z-axis = 66Hz |
| | x | 1 | 0 | 0 | x | x | x | x | Gyro LP filter -3dB frequency for Z-axis = 121Hz |
| | x | x | x | x | 0 | 0 | 0 | 0 | Gyro LP filter -3dB frequency for Z-axis = 262Hz |
| | x | x | x | x | 0 | 0 | 0 | 1 | Gyro g-comp: OFF |
| | x | x | x | x | 0 | 0 | 1 | 0 | Gyro g-comp: bias = OFF , scale = ACC |
| | x | x | x | x | 0 | 0 | 1 | 1 | Gyro g-comp: bias = OFF , scale = ACC+0.01Hz-filter |
| | x | x | x | x | 0 | 0 | 1 | 1 | Gyro g-comp: bias = ACC , scale = OFF |
| | x | x | x | x | 0 | 1 | 0 | 0 | Gyro g-comp: bias = ACC+0.01Hz-filter , scale = OFF |
| | x | x | x | x | 0 | 1 | 0 | 1 | Gyro g-comp: bias = INC , scale = OFF, |
| | x | x | x | x | 0 | 1 | 1 | 0 | Gyro g-comp: bias = INC+0.01Hz-filter, scale = OFF |
| | x | x | x | x | 0 | 1 | 1 | 1 | Gyro g-comp: bias = ACC, scale = ACC |
| | x | x | x | x | 1 | 0 | 0 | 0 | Gyro g-comp: bias = ACC+0.01Hz-filter , scale = ACC |
| | x | x | x | x | 1 | 0 | 0 | 1 | Gyro g-comp: bias = INC, scale = ACC |
| x | x | x | x | 1 | 0 | 1 | 0 | Gyro g-comp: bias = INC+DC-filter, scale = ACC | |
| x | x | x | x | 1 | 0 | 1 | 1 | Gyro g-comp: bias = ACC+0.01Hz-filter, scale = ACC+0.01Hz-filter | |
| x | x | x | x | 1 | 1 | 0 | 0 | Gyro g-comp: bias = INC+0.01Hz-filter, scale = INC+0.01Hz-filter | |
| x | x | x | x | 1 | 1 | 1 | 1 | Gyro g-comp: user-defined | |
| 8 | x | 0 | x | x | x | x | x | System configuration, Byte 6: | |
| | x | 1 | x | x | x | x | x | Accelerometer X-axis is inactive | |
| | x | x | 0 | x | x | x | x | Accelerometer X-axis is active | |
| | x | x | 1 | x | x | x | x | Accelerometer Y-axis is inactive | |
| | x | x | x | 0 | x | x | x | Accelerometer Y-axis is active | |
| | x | x | x | 1 | x | x | x | Accelerometer Z-axis is inactive | |
| | x | x | x | x | 0 | 0 | 0 | Accelerometer Z-axis is active | |
| | x | x | x | x | 0 | 0 | 0 | Accelerometer output unit = ACCELERATION | |
| x | x | x | x | 0 | 0 | 0 | 1 | Accelerometer output unit = INCREMENTAL VELOCITY | |
| x | x | x | x | 0 | 0 | 1 | 0 | Accelerometer output unit = AVERAGE ACCELERATION | |
| 9 | x | 0 | 0 | 0 | x | x | x | System configuration, Byte 7: | |
| | x | 0 | 0 | 1 | x | x | x | Accelerometer LP filter -3dB frequency for X-axis = 16Hz | |
| | x | 0 | 1 | 0 | x | x | x | Accelerometer LP filter -3dB frequency for X-axis = 33Hz | |
| | x | 0 | 1 | 1 | x | x | x | Accelerometer LP filter -3dB frequency for X-axis = 66Hz | |
| | x | 1 | 0 | 0 | x | x | x | Accelerometer LP filter -3dB frequency for X-axis = 131Hz | |
| | x | x | x | x | x | 0 | 0 | 0 | Accelerometer LP filter -3dB frequency for X-axis = 262Hz |
| | x | x | x | x | x | 0 | 0 | 1 | Accelerometer LP filter -3dB frequency for Y-axis = 16Hz |
| | x | x | x | x | x | 0 | 1 | 0 | Accelerometer LP filter -3dB frequency for Y-axis = 33Hz |
| | x | x | x | x | x | 0 | 1 | 1 | Accelerometer LP filter -3dB frequency for Y-axis = 66Hz |
| x | x | x | x | x | 1 | 0 | 0 | Accelerometer LP filter -3dB frequency for Y-axis = 131Hz | |
| x | x | x | x | x | 1 | 0 | 0 | Accelerometer LP filter -3dB frequency for Y-axis = 262Hz | |
| 10 | x | 0 | 0 | 0 | x | x | x | System configuration, Byte 8: | |
| | x | 0 | 0 | 1 | x | x | x | Accelerometer LP filter -3dB frequency for Z-axis = 16Hz | |
| | x | 0 | 1 | 0 | x | x | x | Accelerometer LP filter -3dB frequency for Z-axis = 33Hz | |
| | x | 0 | 1 | 1 | x | x | x | Accelerometer LP filter -3dB frequency for Z-axis = 66Hz | |
| | x | 1 | 0 | 0 | x | x | x | Accelerometer LP filter -3dB frequency for Z-axis = 131Hz | |
| x | 1 | 0 | 0 | x | x | x | Accelerometer LP filter -3dB frequency for Z-axis = 262Hz | | |
| 11 | x | 0 | x | x | x | x | x | System configuration, Byte 9: | |
| | x | 1 | x | x | x | x | x | Inclinometer X-axis is inactive | |
| | x | x | 0 | x | x | x | x | Inclinometer X-axis is active | |
| | x | x | 1 | x | x | x | x | Inclinometer Y-axis is inactive | |
| | x | x | x | 0 | x | x | x | Inclinometer Y-axis is active | |
| | x | x | x | 1 | x | x | x | Inclinometer Z-axis is inactive | |
| | x | x | x | x | 0 | 0 | 0 | Inclinometer Z-axis is active | |
| | x | x | x | x | 0 | 0 | 0 | Inclinometer output unit = ACCELERATION | |
| x | x | x | x | 0 | 0 | 0 | 1 | Inclinometer output unit = INCREMENTAL VELOCITY | |
| x | x | x | x | 0 | 0 | 1 | 0 | Inclinometer output unit = AVERAGE ACCELERATION | |
| 12 | x | 0 | 0 | 0 | x | x | x | System configuration, Byte 10: | |
| | x | 0 | 0 | 1 | x | x | x | Inclinometer LP filter -3dB frequency for X-axis = 16Hz | |
| | x | 0 | 1 | 0 | x | x | x | Inclinometer LP filter -3dB frequency for X-axis = 33Hz | |
| | x | 0 | 1 | 1 | x | x | x | Inclinometer LP filter -3dB frequency for X-axis = 66Hz | |
| | x | 1 | 0 | 0 | x | x | x | Inclinometer LP filter -3dB frequency for X-axis = 121Hz | |
| | x | x | x | x | x | 0 | 0 | 0 | Inclinometer LP filter -3dB frequency for X-axis = 262Hz |
| | x | x | x | x | x | 0 | 0 | 1 | Inclinometer LP filter -3dB frequency for Y-axis = 16Hz |
| | x | x | x | x | x | 0 | 1 | 0 | Inclinometer LP filter -3dB frequency for Y-axis = 33Hz |
| | x | x | x | x | x | 0 | 1 | 1 | Inclinometer LP filter -3dB frequency for Y-axis = 66Hz |
| | x | x | x | x | x | 0 | 1 | 1 | Inclinometer LP filter -3dB frequency for Y-axis = 121Hz |
| x | x | x | x | x | 1 | 0 | 0 | Inclinometer LP filter -3dB frequency for Y-axis = 262Hz | |
| 13 | x | 0 | 0 | 0 | x | x | x | System configuration, Byte 11: | |
| | x | 0 | 0 | 1 | x | x | x | Inclinometer LP filter -3dB frequency for Z-axis = 16Hz | |
| | x | 0 | 1 | 0 | x | x | x | Inclinometer LP filter -3dB frequency for Z-axis = 33Hz | |
| | x | 0 | 1 | 1 | x | x | x | Inclinometer LP filter -3dB frequency for Z-axis = 66Hz | |
| | x | 1 | 0 | 0 | x | x | x | Inclinometer LP filter -3dB frequency for Z-axis = 121Hz | |
| x | 1 | 0 | 0 | x | x | x | Inclinometer LP filter -3dB frequency for Z-axis = 262Hz | | |

| | | | | | | | | | |
|------|-----------------|-----------------|-----------------|-----------------|-----------------|-----------------|-----------------|-----------------|--|
| 14 | x | 0 | 0 | 0 | x | x | x | x | System configuration, Byte 12: AUX LP filter -3dB frequency = 16Hz AUX LP filter -3dB frequency = 33Hz AUX LP filter -3dB frequency = 66Hz AUX LP filter -3dB frequency = 121Hz AUX LP filter -3dB frequency = 262Hz |
| 15 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Gyro range, x-axis - 400°/s Low nibble: Gyro range, y-axis - 400°/s |
| 16 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Gyro range, z-axis - 400°/s |
| 17 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Accelerometer range, x-axis - 10g - 2g - 5g - 30g - 100g Low nibble: Accelerometer range, y-axis - 10g - 2g - 5g - 30g - 100g |
| 18 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Accelerometer range, z-axis - 10g - 2g - 5g - 30g - 100g |
| 19 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Inclinator range, x-axis - 1.7g Low nibble: Inclinator range, y-axis - 1.7g |
| 20 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: Inclinator range, z-axis - 1.7g |
| 21 | 0 | 0 | 0 | 0 | x | x | x | x | High nibble: AUX range - ±2.5V |
| 22 | C ₃₁ | C ₃₀ | C ₂₉ | C ₂₈ | C ₂₇ | C ₂₆ | C ₂₅ | C ₂₄ | Cyclic Redundancy Check is performed on all preceding bytes, ref: 6.3.5 |
| 23 | C ₂₃ | C ₂₂ | C ₂₁ | C ₂₀ | C ₁₉ | C ₁₈ | C ₁₇ | C ₁₆ | |
| 24 | C ₁₅ | C ₁₄ | C ₁₃ | C ₁₂ | C ₁₁ | C ₁₀ | C ₉ | C ₈ | |
| 25 | C ₇ | C ₆ | C ₅ | C ₄ | C ₃ | C ₂ | C ₁ | C ₀ | |
| (26) | 0 | 0 | 0 | 0 | 1 | 1 | 0 | 1 | <CR> If datagram termination has been selected |
| (27) | 0 | 0 | 0 | 0 | 1 | 0 | 1 | 0 | <LF> If datagram termination has been selected |

6.3.4 Normal Mode datagram

Table 6-13: Specification of the Normal Mode datagram (full data content in datagram)

| Byte# | Bit# | | | | | | | | Specification | |
|-------|-------------------|-------------------|-------------------|-------------------|-------------------|-------------------|------------------|------------------|---|---|
| | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 | | |
| 0 | 0 | 0 | 0 | 1 | 1 | 1 | 1 | 1 | Normal Mode datagram identifier for Normal Mode datagram with full content. Identifier for reduced content datagrams can be found in Table 6-14 | |
| 1 | Gx ₂₃ | Gx ₂₂ | Gx ₂₁ | Gx ₂₀ | Gx ₁₉ | Gx ₁₈ | Gx ₁₇ | Gx ₁₆ | X-axis gyro output, ref. section 8.5.2.2.1 to 8.5.2.2.5 for conversion to units | |
| 2 | Gx ₁₅ | Gx ₁₄ | Gx ₁₃ | Gx ₁₂ | G ₁₁ | Gx ₁₀ | Gx ₉ | Gx ₈ | | |
| 3 | Gx ₇ | Gx ₆ | Gx ₅ | Gx ₄ | Gx ₃ | Gx ₂ | Gx ₁ | Gx ₀ | | |
| 4 | Gy ₂₃ | Gy ₂₂ | Gy ₂₁ | Gy ₂₀ | Gy ₁₉ | Gy ₁₈ | Gy ₁₇ | Gy ₁₆ | | |
| 5 | Gy ₁₅ | Gy ₁₄ | Gy ₁₃ | Gy ₁₂ | Gy ₁₁ | Gy ₁₀ | Gy ₉ | Gy ₈ | Y-axis gyro output, ref. section 8.5.2.2.1 to 8.5.2.2.5 for conversion to units | |
| 6 | Gy ₇ | Gy ₆ | Gy ₅ | Gy ₄ | Gy ₃ | Gy ₂ | Gy ₁ | Gy ₀ | | |
| 7 | Gz ₂₃ | Gz ₂₂ | Gz ₂₁ | Gz ₂₀ | Gz ₁₉ | Gz ₁₈ | Gz ₁₇ | Gz ₁₆ | | |
| 8 | Gz ₁₅ | Gz ₁₄ | Gz ₁₃ | Gz ₁₂ | Gz ₁₁ | Gz ₁₀ | Gz ₉ | Gz ₈ | | |
| 9 | Gz ₇ | Gz ₆ | Gz ₅ | Gz ₄ | Gz ₃ | Gz ₂ | Gz ₁ | Gz ₀ | Z-axis gyro output, ref. section 8.5.2.2.1 to 8.5.2.2.5 for conversion to units | |
| 10 | Gs ₇ | Gs ₆ | Gs ₅ | Gs ₄ | Gs ₃ | Gs ₂ | Gs ₁ | Gs ₀ | | |
| 11 | Ax ₂₃ | Ax ₂₂ | Ax ₂₁ | Ax ₂₀ | Ax ₁₉ | Ax ₁₈ | Ax ₁₇ | Ax ₁₆ | | X-axis accelerometer output, ref. section 8.5.2.2.7 to 8.5.2.2.9 for conversion to units |
| 12 | Ax ₁₅ | Ax ₁₄ | Ax ₁₃ | Ax ₁₂ | Ax ₁₁ | Ax ₁₀ | Ax ₉ | Ax ₈ | | |
| 13 | Ax ₇ | Ax ₆ | Ax ₅ | Ax ₄ | Ax ₃ | Ax ₂ | Ax ₁ | Ax ₀ | | |
| 14 | Ay ₂₃ | Ay ₂₂ | Ay ₂₁ | Ay ₂₀ | Ay ₁₉ | Ay ₁₈ | Ay ₁₇ | Ay ₁₆ | | |
| 15 | Ay ₁₅ | Ay ₁₄ | Ay ₁₃ | Ay ₁₂ | Ay ₁₁ | Ay ₁₀ | Ay ₉ | Ay ₈ | Y-axis accelerometer output, ref. section 8.5.2.2.7 to 8.5.2.2.9 for conversion to units | |
| 16 | Ay ₇ | Ay ₆ | Ay ₅ | Ay ₄ | Ay ₃ | Ay ₂ | Ay ₁ | Ay ₀ | | |
| 17 | Az ₂₃ | Az ₂₂ | Az ₂₁ | Az ₂₀ | Az ₁₉ | Az ₁₈ | Az ₁₇ | Az ₁₆ | | |
| 18 | Az ₁₅ | Az ₁₄ | Az ₁₃ | Az ₁₂ | Az ₁₁ | Az ₁₀ | Az ₉ | Az ₈ | | |
| 19 | Az ₇ | Az ₆ | Az ₅ | Az ₄ | Az ₃ | Az ₂ | Az ₁ | Az ₀ | Z-axis accelerometer output, ref. section 8.5.2.2.7 to 8.5.2.2.9 for conversion to units | |
| 20 | As ₇ | As ₆ | As ₅ | As ₄ | As ₃ | As ₂ | As ₁ | As ₀ | | |
| 21 | Ix ₂₃ | Ix ₂₂ | Ix ₂₁ | Ix ₂₀ | Ix ₁₉ | Ix ₁₈ | Ix ₁₇ | Ix ₁₆ | | X-axis Inclinomometer output, ref. section 8.5.2.2.10 to 8.5.2.2.12 for conversion to units |
| 22 | Ix ₁₅ | Ix ₁₄ | Ix ₁₃ | Ix ₁₂ | Ix ₁₁ | Ix ₁₀ | Ix ₉ | Ix ₈ | | |
| 23 | Ix ₇ | Ix ₆ | Ix ₅ | Ix ₄ | Ix ₃ | Ix ₂ | Ix ₁ | Ix ₀ | | |
| 24 | Iy ₂₃ | Iy ₂₂ | Iy ₂₁ | Iy ₂₀ | Iy ₁₉ | Iy ₁₈ | Iy ₁₇ | Iy ₁₆ | | |
| 25 | Iy ₁₅ | Iy ₁₄ | Iy ₁₃ | Iy ₁₂ | Iy ₁₁ | Iy ₁₀ | Iy ₉ | Iy ₈ | Y-axis Inclinomometer output, ref. section 8.5.2.2.10 to 8.5.2.2.12 for conversion to units | |
| 26 | Iy ₇ | Iy ₆ | Iy ₅ | Iy ₄ | Iy ₃ | Iy ₂ | Iy ₁ | Iy ₀ | | |
| 27 | Iz ₂₃ | Iz ₂₂ | Iz ₂₁ | Iz ₂₀ | Iz ₁₉ | Iz ₁₈ | Iz ₁₇ | Iz ₁₆ | | |
| 28 | Iz ₁₅ | Iz ₁₄ | Iz ₁₃ | Iz ₁₂ | Iz ₁₁ | Iz ₁₀ | Iz ₉ | Iz ₈ | | |
| 29 | Iz ₇ | Iz ₆ | Iz ₅ | Iz ₄ | Iz ₃ | Iz ₂ | Iz ₁ | Iz ₀ | Z-axis Inclinomometer output, ref. section 8.5.2.2.10 to 8.5.2.2.12 for conversion to units | |
| 30 | Is ₇ | Is ₆ | Is ₅ | Is ₄ | Is ₃ | Is ₂ | Is ₁ | Is ₀ | | |
| 31 | GTX ₁₅ | GTX ₁₄ | GTX ₁₃ | GTX ₁₂ | GTX ₁₁ | GTX ₁₀ | GTX ₉ | GTX ₈ | | X-axis gyro temperature data, ref. chapter 0 for conversion to units |
| 32 | GTX ₇ | GTX ₆ | GTX ₅ | GTX ₄ | GTX ₃ | GTX ₂ | GTX ₁ | GTX ₀ | | |
| 33 | GTy ₁₅ | GTy ₁₄ | GTy ₁₃ | GTy ₁₂ | GTy ₁₁ | GTy ₁₀ | GTy ₉ | GTy ₈ | | |
| 34 | GTy ₇ | GTy ₆ | GTy ₅ | GTy ₄ | GTy ₃ | GTy ₂ | GTy ₁ | GTy ₀ | | |
| 35 | GTz ₁₅ | GTz ₁₄ | GTz ₁₃ | GTz ₁₂ | GTz ₁₁ | GTz ₁₀ | GTz ₉ | GTz ₈ | Z-axis gyro temperature data, ref. chapter 0 for conversion to units | |
| 36 | GTz ₇ | GTz ₆ | GTz ₅ | GTz ₄ | GTz ₃ | GTz ₂ | GTz ₁ | GTz ₀ | | |
| 37 | GTS ₇ | GTS ₆ | GTS ₅ | GTS ₄ | GTS ₃ | GTS ₂ | GTS ₁ | GTS ₀ | | |
| 38 | ATX ₁₅ | ATX ₁₄ | ATX ₁₃ | ATX ₁₂ | ATX ₁₁ | ATX ₁₀ | ATX ₉ | ATX ₈ | | |
| 39 | ATX ₇ | ATX ₆ | ATX ₅ | ATX ₄ | ATX ₃ | ATX ₂ | ATX ₁ | ATX ₀ | X-axis accelerometer temperature data, ref. chapter 0 for conversion to units | |
| 40 | ATy ₁₅ | ATy ₁₄ | ATy ₁₃ | ATy ₁₂ | ATy ₁₁ | ATy ₁₀ | ATy ₉ | ATy ₈ | | |
| 41 | ATy ₇ | ATy ₆ | ATy ₅ | ATy ₄ | ATy ₃ | ATy ₂ | ATy ₁ | ATy ₀ | | |
| 42 | ATz ₁₅ | ATz ₁₄ | ATz ₁₃ | ATz ₁₂ | ATz ₁₁ | ATz ₁₀ | ATz ₉ | ATz ₈ | | |
| 43 | ATz ₇ | ATz ₆ | ATz ₅ | ATz ₄ | ATz ₃ | ATz ₂ | ATz ₁ | ATz ₀ | Z-axis accelerometer temperature data, ref. chapter 0 for conversion to units | |
| 44 | ATS ₇ | ATS ₆ | ATS ₅ | ATS ₄ | ATS ₃ | ATS ₂ | ATS ₁ | ATS ₀ | | |
| 45 | ITX ₁₅ | ITX ₁₄ | ITX ₁₃ | ITX ₁₂ | ITX ₁₁ | ITX ₁₀ | ITX ₉ | ITX ₈ | | |
| 46 | ITX ₇ | ITX ₆ | ITX ₅ | ITX ₄ | ITX ₃ | ITX ₂ | ITX ₁ | ITX ₀ | | |
| 47 | ITy ₁₅ | ITy ₁₄ | ITy ₁₃ | ITy ₁₂ | ITy ₁₁ | ITy ₁₀ | ITy ₉ | ITy ₈ | Y-axis inclinometer temperature data, ref. chapter 0 for conversion to units | |
| 48 | ITy ₇ | ITy ₆ | ITy ₅ | ITy ₄ | ITy ₃ | ITy ₂ | ITy ₁ | ITy ₀ | | |
| 49 | ITz ₁₅ | ITz ₁₄ | ITz ₁₃ | ITz ₁₂ | ITz ₁₁ | ITz ₁₀ | ITz ₉ | ITz ₈ | | |
| 50 | ITz ₇ | ITz ₆ | ITz ₅ | ITz ₄ | ITz ₃ | ITz ₂ | ITz ₁ | ITz ₀ | | |
| 51 | ITS ₇ | ITS ₆ | ITS ₅ | ITS ₄ | ITS ₃ | ITS ₂ | ITS ₁ | ITS ₀ | Z-axis inclinometer temperature data, ref. chapter 0 for conversion to units | |
| 52 | Au ₂₃ | Au ₂₂ | Au ₂₁ | Au ₂₀ | Au ₁₉ | Au ₁₈ | Au ₁₇ | Au ₁₆ | | |
| 53 | Au ₁₅ | Au ₁₄ | Au ₁₃ | Au ₁₂ | Au ₁₁ | Au ₁₀ | Au ₉ | Au ₈ | | |
| 54 | Au ₇ | Au ₆ | Au ₅ | Au ₄ | Au ₃ | Au ₂ | Au ₁ | Au ₀ | | |
| 55 | Aus ₇ | Aus ₆ | Aus ₅ | Aus ₄ | Aus ₃ | Aus ₂ | Aus ₁ | Aus ₀ | STATUS byte for AUX measurement, ref. Table 6-16 | |
| 56 | n ₇ | n ₆ | n ₅ | n ₄ | n ₃ | n ₂ | n ₁ | n ₀ | | |
| 57 | t ₁₅ | t ₁₄ | t ₁₃ | t ₁₂ | t ₁₁ | t ₁₀ | t ₉ | t ₈ | | |
| 58 | t ₇ | t ₆ | t ₅ | t ₄ | t ₃ | t ₂ | t ₁ | t ₀ | | |
| 59 | C ₃₁ | C ₃₀ | C ₂₉ | C ₂₈ | C ₂₇ | C ₂₆ | C ₂₅ | C ₂₄ | Cyclic Redundancy Check is performed on all preceding bytes, ref:section 6.3.5 | |
| 60 | C ₂₃ | C ₂₂ | C ₂₁ | C ₂₀ | C ₁₉ | C ₁₈ | C ₁₇ | C ₁₆ | | |
| 61 | C ₁₅ | C ₁₄ | C ₁₃ | C ₁₂ | C ₁₁ | C ₁₀ | C ₉ | C ₈ | | |
| 62 | C ₇ | C ₆ | C ₅ | C ₄ | C ₃ | C ₂ | C ₁ | C ₀ | | |
| (63) | 0 | 0 | 0 | 0 | 1 | 1 | 0 | 1 | <CR> If datagram termination has been selected | |
| (64) | 0 | 0 | 0 | 0 | 1 | 0 | 1 | 0 | <LF> If datagram termination has been selected | |

Normal Mode datagrams with reduced content can be chosen at order or configured in Service Mode. Overview of available datagrams can be found in Table 6-14 and in section 12. When choosing a Normal mode datagram with reduced content, the Normal Mode datagram will be shorter. However the order of requested data will be transmitted as shown in Table 6-13. When selecting temperature in the datagram, only temperatures for the selected measurement-clusters will be transmitted, e.g. if gyro and inclinometer data have been chosen together with temperature, only temperatures for the gyros and inclinometers will be transmitted.

Table 6-14: Normal Mode datagram identifiers

| Datagram content | Identifier |
|--|------------|
| Rate | 0x90 |
| Rate and acceleration | 0x91 |
| Rate and inclination | 0x92 |
| Rate, acceleration and inclination | 0x93 |
| Rate and temperature | 0x94 |
| Rate, acceleration and temperature | 0xA5 |
| Rate, inclination and temperature | 0xA6 |
| Rate, acceleration, inclination and temperature | 0xA7 |
| Rate and AUX | 0x98 |
| Rate, acceleration and AUX | 0x99 |
| Rate, inclination and AUX | 0x9A |
| Rate, acceleration, inclination and AUX | 0x9B |
| Rate, temperature and AUX | 0x9C |
| Rate, acceleration, temperature and AUX | 0xAD |
| Rate, inclination, temperature and AUX | 0xAE |
| Rate, acceleration, inclination, temperature and AUX | 0xAF |

6.3.5 Cyclic Redundancy Check (CRC)

At the end of all datagrams is a 32-bit Cyclic Redundancy Checksum. The CRC checksum enables the user to detect errors in the transfer of data from STIM300. The CRC is calculated using the following equation:

$$x^{32} + x^{26} + x^{23} + x^{22} + x^{16} + x^{12} + x^{11} + x^{10} + x^8 + x^7 + x^5 + x^4 + x^2 + x + 1$$

seed = 0xFFFFFFFF

All preceding data, including the datagram identifier, is included in the CRC.

The CRC-algorithm requires full sets of 32-bits (4 bytes). Several of the defined datagrams from STIM300 have a length which is not an integer of 4 bytes. In order to have an efficient transmission of data and thereby avoid transmitting bytes with no meaningful content, dummy-byte(s) with content = 0x00 are added when the CRC of the last byte(s) is calculated.

Example: Datagram with ID=0xA7 (rate, acceleration, inclination and temperature) has been chosen. This datagram consists of 55 bytes prior to the CRC checksum. Hence this datagram consists of 13 sets of 32 bits + 3 bytes. In order to include the last 3 bytes in the CRC checksum, 1 byte = 0x00 is added, making the last data byte the most significant byte.

Table 6-15 lists the number of dummy-bytes needed to calculate the final CRC-checksum for the different datagrams in Normal Mode.

Table 6-15: Number of dummy-bytes to be added for CRC-calculation

| Datagram content | Identifier | # dummy-bytes |
|--|------------|---------------|
| Part Number datagram | 0xB1, 0xB3 | 1 |
| Serial Number datagram | 0xB5, 0xB7 | 1 |
| Configuration datagram | 0xB9, 0xBB | 1 |
| Rate | 0x90 | 2 |
| Rate and acceleration | 0x91 | 0 |
| Rate and inclination | 0x92 | 0 |
| Rate, acceleration and inclination | 0x93 | 2 |
| Rate and temperature | 0x94 | 3 |
| Rate, acceleration and temperature | 0xA5 | 2 |
| Rate, inclination and temperature | 0xA6 | 2 |
| Rate, acceleration, inclination and temperature | 0xA7 | 1 |
| Rate and AUX | 0x98 | 2 |
| Rate, acceleration and AUX | 0x99 | 0 |
| Rate, inclination and AUX | 0x9A | 0 |
| Rate, acceleration, inclination and AUX | 0x9B | 2 |
| Rate, temperature and AUX | 0x9C | 3 |
| Rate, acceleration, temperature and AUX | 0xAD | 2 |
| Rate, inclination, temperature and AUX | 0xAE | 2 |
| Rate, acceleration, inclination, temperature and AUX | 0xAF | 1 |

6.4 Status byte

Table 6-16: Interpretation of bits in STATUS byte

| Bit | STATUS bit information | Comment |
|-----|--------------------------------------|---|
| 7 | 0=OK, 1=System integrity error | Bits 0-2 will flag the overload channel(s) Bits 0-2 will flag the error channel(s) |
| 6 | 0=OK, 1=Start-Up | |
| 5 | 0=OK, 1=Outside operating conditions | |
| 4 | 0=OK, 1=Overload | |
| 3 | 0=OK, 1=Error in measurement-channel | |
| 2 | 0=OK, 1=Z-channel | |
| 1 | 0=OK, 1=Y-channel | |
| 0 | 0=OK, 1=X-channel (or AUX) | |

7 MECHANICAL

Table 7-1: Mechanical specifications

| Parameter | Conditions | Min | Nom | Max | Unit | Note |
|---|------------------------------|--|-----|-----|--------------|------|
| HOUSING MATERIAL | | Aluminium, Alloy 6082-T6, DIN EN 754-2 | | | | |
| SURFACE TREATMENT Passivation | | Surtec 650 | | | | 1 |
| WEIGHT | | 55 | | | grams | |
| VOLUME | | 32.6 1.99 | | | ccm cu in | |
| DUST AND HUMIDITY CLASSIFICATION | | IP67 | | | | |
| CONNECTOR Type Number of pins Contact type | | Micro-D 15 female | | | | |
| PLUG Proposed plug to fit connector Proposed cover to fit plug | For best EMI performance | Axon MDA 2 15 P Axon micro-D EMI back shell | | | | |
| FIXATION BOLTS Recommended torque | Steel base Aluminium base | M4 ISO 4762 / DIN 912 3.5 3.0 | | | Nm Nm | |

Note 1: Hexavalent chromium free

7.1 Mechanical dimensions

All dimensions are in mm.

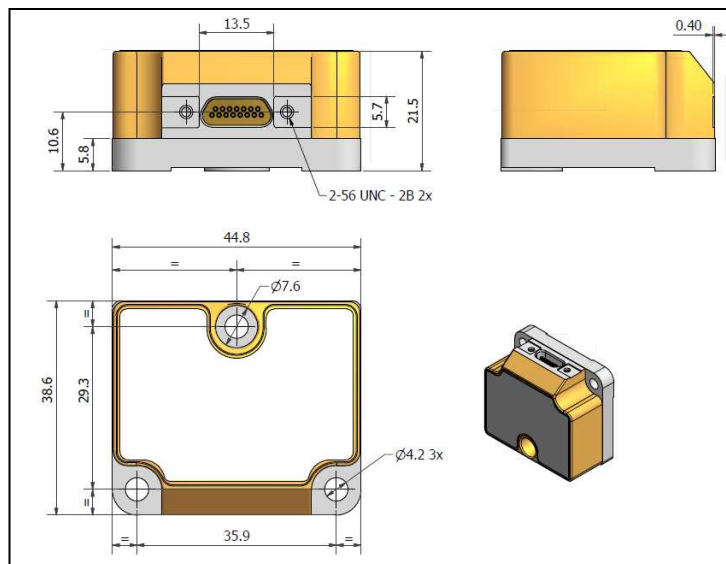
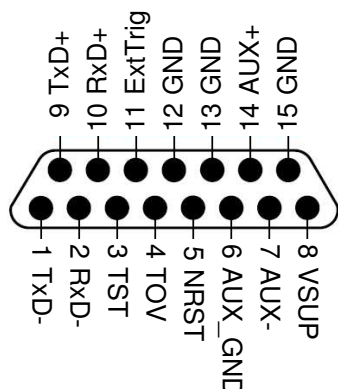


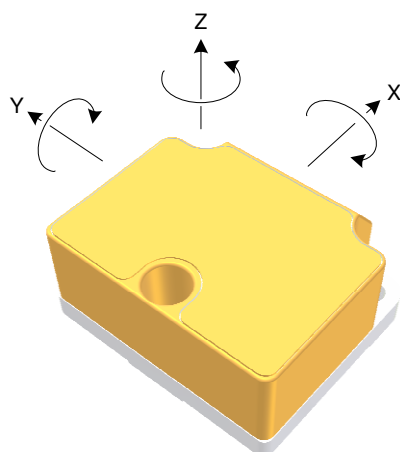
Figure 7-1: Mechanical dimensions

Table 7-2: Nominal position of accelerometer mass-centres (ref. Figure 6-2 for reference definition)

| Axis | X-offset | Y-offset | Z-offset |
|------|----------|----------|----------|
| X | -33.47mm | -8.67mm | 12.92mm |
| Y | -24.90mm | -5.14mm | 16.03mm |
| Z | -27.50mm | -11.78mm | 6.81mm |

7.2 Pin configuration

Figure 7-2: Pin configuration as seen from front of STIM300
Table 7-3: Pin descriptions

| Pin# | Label | Type | Description |
|------|---------|--------|---|
| 1 | TxD- | OUTPUT | RS422 negative output |
| 2 | RxD- | INPUT | RS422 negative input |
| 3 | TST | OUTPUT | Test pin: Do not connect |
| 4 | TOV | OUTPUT | Time of Validity (if not in use, leave floating) |
| 5 | NRST | INPUT | Reset (if not in use, connect to VSUP or leave floating) |
| 6 | AUX_GND | INPUT | AUX signal ground (internally connected to Power ground) |
| 7 | AUX- | INPUT | AUX negative signal input |
| 8 | VSUP | SUPPLY | Power supply (+5V) |
| 9 | TxD+ | OUTPUT | RS422 positive output |
| 10 | RxD+ | INPUT | RS422 positive input |
| 11 | ExtTrig | INPUT | External trigger (if not in use, connect to VSUP or leave floating) |
| 12 | GND | INPUT | Test pin: Connect to ground (0V) |
| 13 | GND | INPUT | Test pin: Connect to ground (0V) |
| 14 | AUX+ | INPUT | AUX positive signal input |
| 15 | GND | SUPPLY | Power ground (0V) |

7.3 Definition of axes

Figure 7-3: Definition of axes

8 BASIC OPERATION

STIM300 is very simple to use. Unless having been configured with external trigger, the unit will start performing measurements and transmit the results over the RS422 interface without any need for additional signalling or set-up after power-on. Figure 8-1 shows the simplest connection set-up for STIM300.

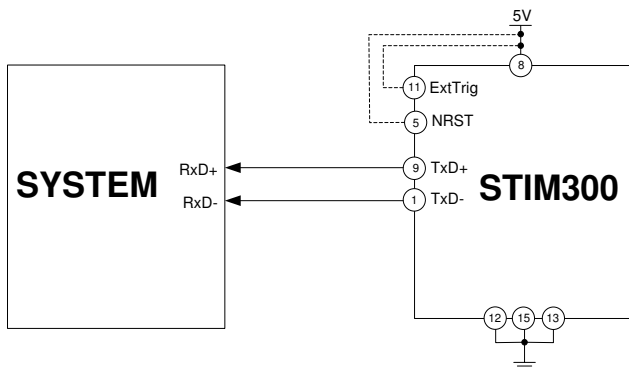


Figure 8-1: Transmit-Only Electrical Connection Diagram

In order to take full advantage of all features of STIM300, the unit needs to be connected as shown in Figure 8-2. In this set-up the system can reset the unit without having to toggle power, the external trigger function can be utilized, configuration parameters can be changed and extended information like diagnostic information can be read from the device.

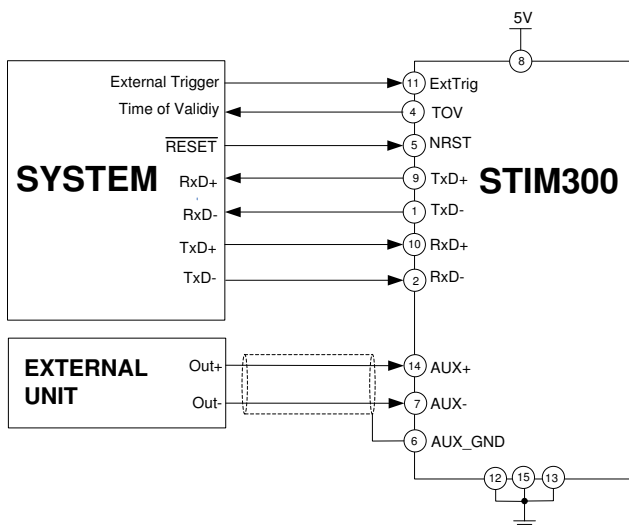


Figure 8-2: Full Function Electrical Connection Diagram

8.1 Reset

STIM300 has a separate reset pin (NRST) in order for the application to reset the unit without having to toggle power. The reset is active low and has an internal pull-up. Hence the input could be left floating if not in use.

The reset signal is routed to the reset of the microcontroller and effectively forces STIM300 into Init Mode (ref. Figure 8-6 and section 8.5.1).

8.2 External Trigger

STIM300 has a separate digital input pin to be used when the unit has been configured to transmit only upon external trigger. The measurements themselves will be continuously running at the highest sample rate (2000 samples/s) in order to ensure shortest possible latency when a transmission is requested. The input is set to trigger on the falling edge of the input signal and will then transmit one datagram containing the result of the latest measurement.

The input has an internal pull-up. Hence the input could be left floating if not in use.

Please note that the commands in Normal Mode are active even if the datagram transmission has been configured to transmit only upon external trigger. This means that e.g. if the Normal Mode command "C" is issued over the RS-422

interface, the STIM300 will transmit a Configuration Datagram independent on the external trigger input. Also when STIM300 is in Init Mode (after Power on or Reset), it will transmit the 3 datagrams as described in section 8.5.1.

The timing diagram is shown in Figure 8-3. Latency is the time between the moment at which the sample has been digitized + low pass-filtered and the external trigger.

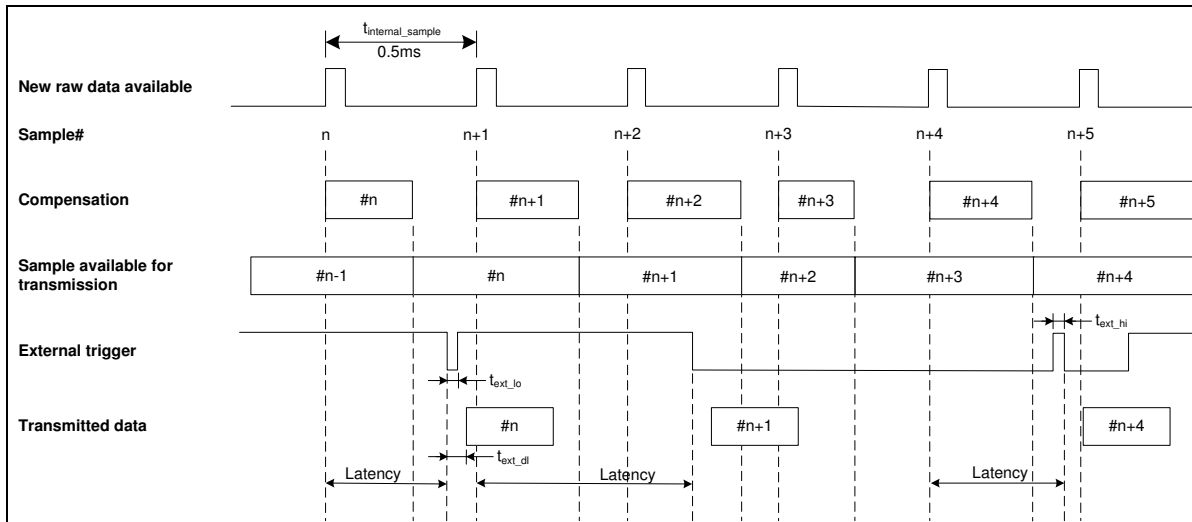


Figure 8-3: Timing of external trigger

8.3 Time of Validity (TOV)

The TOV-output serves 2 purposes:

- Provide a synchronisation-signal derived from the internal clock of STIM300
- Provide means to signal when a datagram is being transmitted (NB: not when configured to external trigger)

The TOV raising edge occurs synchronous to the sample rate. The falling edge occurs after the last bit of the datagram has been transmitted.

Figure 8-4 and Figure 8-5 show the timing diagram of the TOV-output.

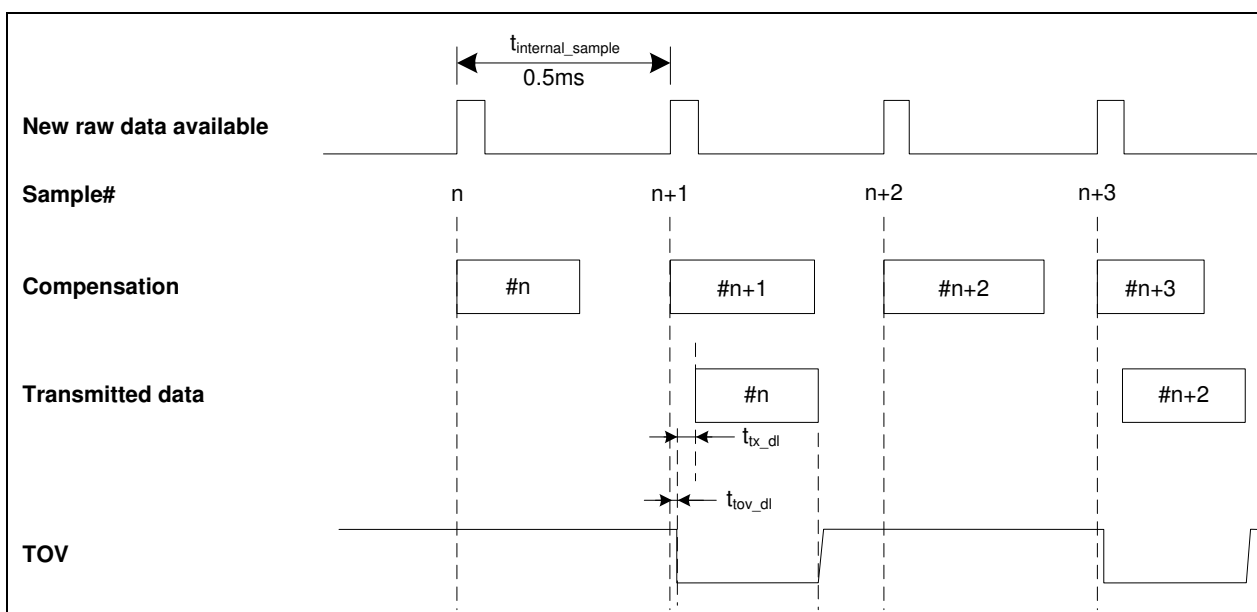


Figure 8-4: Timing of TOV (example: sample rate = 1000samples/s)

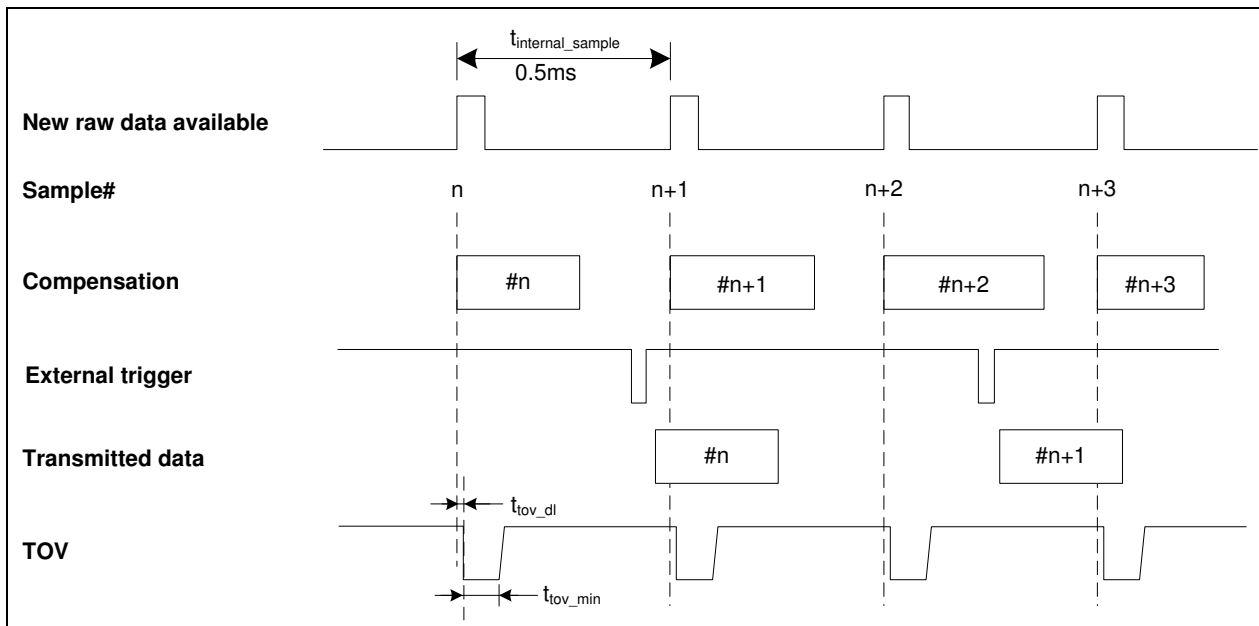


Figure 8-5: Timing of TOV with external trigger

8.4 Auxiliary input

STIM300 provides input in order to digitize an external signal. The digitizer is a 24 bit sigma-delta ADC. The AUX data (24 bits + status byte) can be included in the datagrams, ref. sections 12 and 10.4. A simple compensation of the AUX data is performed as shown in Equation 1. The AUX data will be low-pass filtered. The bandwidth can be changed in Service Mode, ref. section 10.8.

Equation 1: AUX compensation algorithm:

$$AUX_Output = A * AUX_Input + B$$

where A and B are coefficients that can be programmed by the user in SERVICEMODE (k (AUX COMP)-command)

8.5 Operating modes

The operating modes of STIM300 are shown in Figure 8-6:

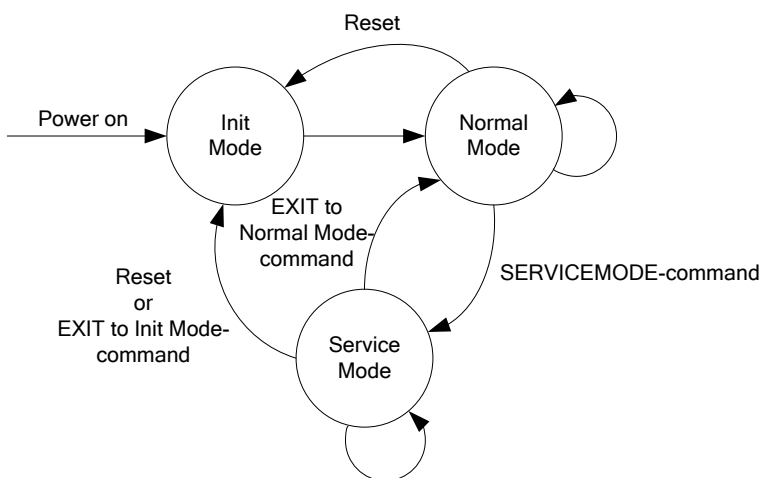


Figure 8-6: Operating modes**8.5.1 Init Mode**

Init Mode is entered after the following conditions:

- power on
- after an external reset
- when receiving a reset-command in Normal Mode
- when exiting to Init Mode from Service Mode.

In Init Mode the system waits for internal references to settle, resets and synchronizes the sensor channels and transmits three special datagrams containing part number, serial number and configuration data. Please note that length and format of the special datagrams are different to the datagrams in Normal Mode.

The content and format of the Part Number datagram is specified in Table 6-10.

The content and format of the Serial Number datagram is specified in Table 6-11.

The content and format of the Configuration datagram is specified in Table 6-12.

After having transmitted the special Part Number, Serial Number and Configuration datagrams, STIM300 enters Normal Mode.

All these special datagrams can also be requested by commands in Normal Mode, ref. Section: 9.

8.5.2 Normal Mode

In Normal Mode STIM300 will constantly measure the available sensor channels at the configured sample rate. Note that if external trigger has been chosen, the internal sample rate will be set to maximum in order to minimize latency.

STIM300 will continue to transmit data regardless of any errors reported in the STATUS-bytes (ref. Table 6-16). Hence the content of the STATUS-byte should continuously be examined.

The content of the part number datagram is specified in Table 6-13.

8.5.2.1 Start-Up

When STIM300 enters Normal Mode from Init Mode, there will be a start-up period where STIM300 is stabilizing the gyros. During this period bit 6 is set in the STATUS-byte (ref. Table 6-16) to communicate its condition. Once stabilized, bit 6 will be cleared. During this period the output data should be regarded as non-valid.

There will not be any start-up period when STIM300 is exiting from Service Mode directly to Normal Mode.

8.5.2.2 Data output options and interpretation

8.5.2.2.1 Delayed gyro output

The inherent group delay of the gyro-, accelerometer-, inclinometer- and AUX-signals are different, ref. Table 6-3, Table 6-4, Table 6-5 and Table 6-6 respectively. An option is available to delay the gyro signals by 5ms in order for the group delay of gyros, accelerometers and AUX to be similar. To enable this feature, select the gyro output-unit ≥ 8 , ref. section 10.7 and 12.

8.5.2.2.2 Gyro output unit = Angular Rate

In the case of STIM300 being configured to output angular rate, Equation 2 and Figure 8-7 show how to convert to [°/s]. Please note that the output data is represented as two's complement.

Equation 2: Converting output to [°/s]:

$$\text{Output}[\text{°/s}] = \frac{(\text{AR}_1) \cdot 2^{16} + (\text{AR}_2) \cdot 2^8 + (\text{AR}_3)}{2^{14}}$$

where AR_1 is the most significant byte of the 24bit output
 AR_2 is the middle byte of the 24bit output
 AR_3 is the least significant byte of the 24bit output

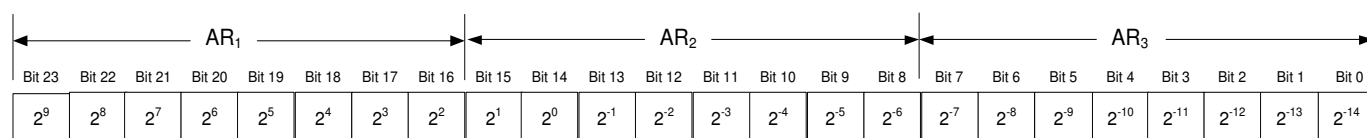


Figure 8-7: Converting output bytes to [°/s]

8.5.2.2.3 Gyro output unit = Incremental Angle

In the case of STIM300 being configured to output incremental angle per sample, the equations for conversion to [°/sample] can be found in Equation 3 and Figure 8-8. Please note that the output data is represented as two's complement.

Equation 3: Converting output to [°/sample]

$$\text{Output}[\text{°/sample}] = \frac{(\text{IA}_1) \cdot 2^{16} + (\text{IA}_2) \cdot 2^8 + (\text{IA}_3)}{2^{21}}$$

where IA_1 is the most significant byte of the 24bit output
 IA_2 is the middle byte of the 24bit output
 IA_3 is the least significant byte of the 24bit output

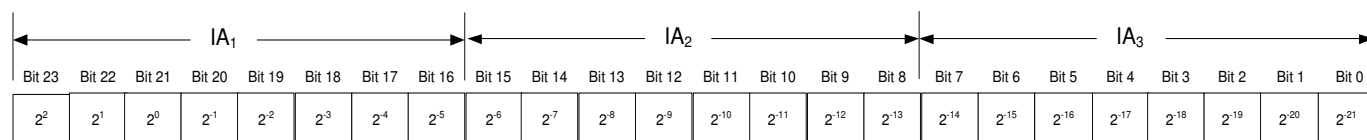


Figure 8-8: Converting output bytes to [°/sample]

8.5.2.2.4 Gyro output unit = Average Angular Rate

In the case of STIM300 being configured to output average angular rate, the transmitted data will be the average of the samples since last transmission. E.g. in the case of continuous transmission of datagrams and a sample rate of 500Hz, each transmission will contain the average of the four previous internal samples.

Please note that the configured low-pass filtering is performed prior to calculating the average.

The average is calculated on the samples using the conventional equation for average calculation:

Equation 4: Calculating average:

$$\text{Average_Angular_Rate} [^\circ/\text{s}] = \frac{\sum_{m=1..n} \text{Angular_Rate}_m}{n}$$

where Angular_Rate_m is one angular rate data sampled at 2000 samples/s
n is number of samples since last transmission

Conversion to [%/s] is the same as for angular rate and is described in Equation 2.

8.5.2.2.5 Gyro output unit = Integrated Angle

In the case of STIM300 being configured to output integrated angle, the transmitted data will be the continuously integrated angle since power-on or reset. The integrated angle takes values in the interval [-4°, 4°] and will naturally wrap-around with no error-message indication in the Status-byte.

Conversion to [°] is the same as for incremental angle and is described in Equation 3.

8.5.2.2.6 Gyro g-compensation

The gyros are sensitive to acceleration-forces in certain directions:

- X- and Y-gyros are sensitive to acceleration-forces in Z-direction
- Z-gyro is sensitive to acceleration-forces in Y-direction
- The gyros are insensitive to acceleration-forces in X-direction

As the STIM300 also contains accelerometers and inclinometers, functionality has been implemented to provide means to compensate for the g-sensitivity for gyro scale-factor and/or bias.

In addition, a simple 1-pole low-pass filter can be switched in to apply additional filtering of the accelerometer-/inclinometer-signal prior to use in the compensation, ref: Figure 8-10. A simplified compensation-scheme can be found in Figure 8-9.

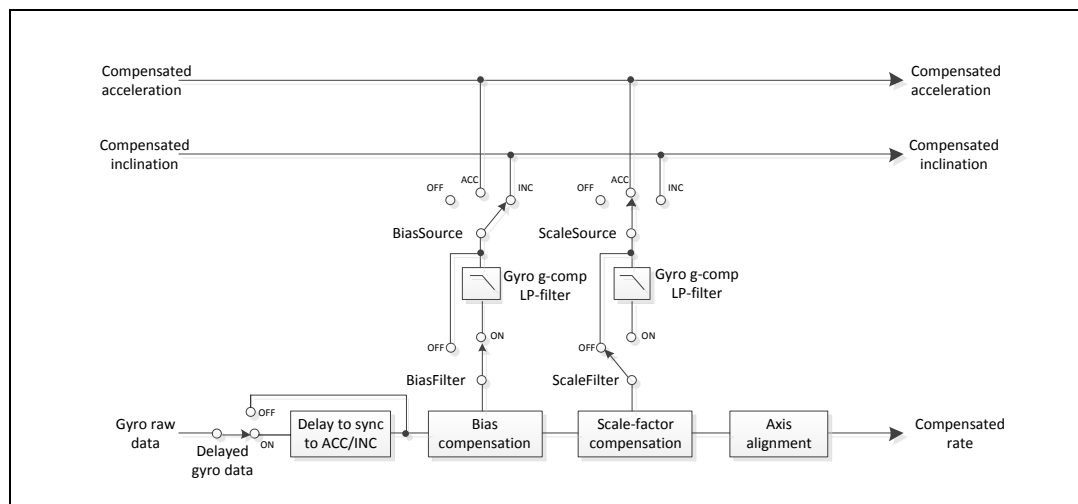


Figure 8-9: Simplified compensation-scheme for gyro g-compensation

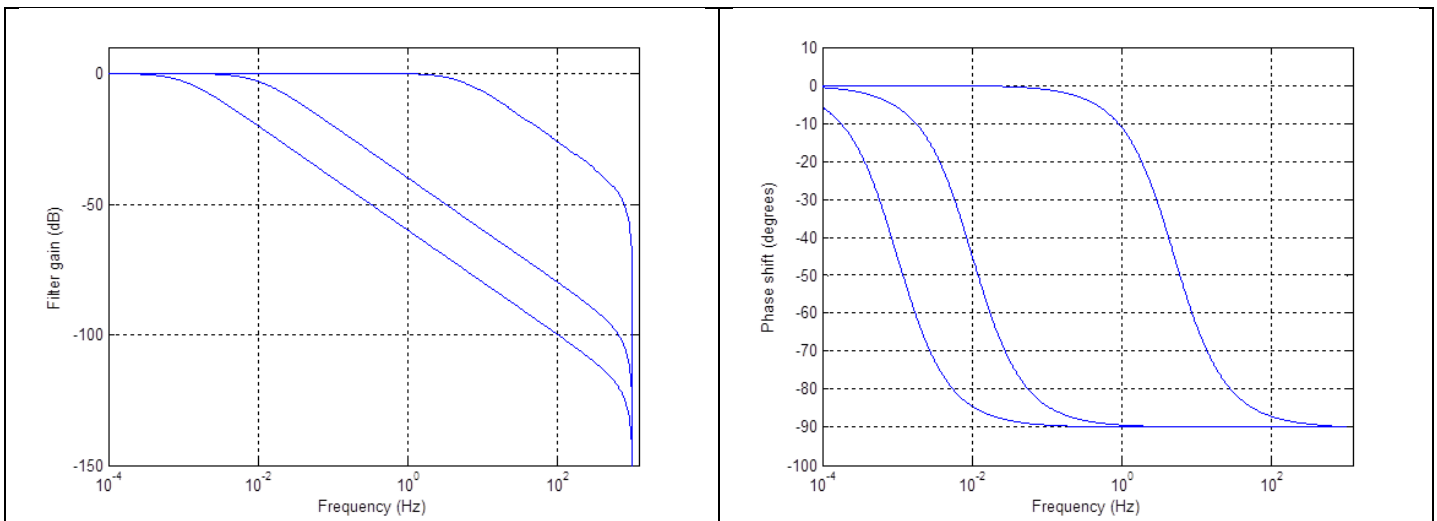


Figure 8-10: Frequency characteristics of g-compensation low-pass filter for 0.001Hz, 0.01Hz and 5Hz settings

8.5.2.2.7 Accelerometer output unit = Acceleration

In the case of STIM300 being configured to output acceleration, Equation 5 and Figure 8-11 show how to do this. Please note that the output data is represented as two's complement.

Equation 5: Converting output to [g]:

| Range | Conversion: |
|-------|--|
| 2g | $\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{21}}$ |
| 5g | $\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{20}}$ |
| 10g | $\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{19}}$ |
| 30g | $\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{18}}$ |
| 100g | $\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{16}}$ |

where ACC_1 is the most significant byte of the 24bit output

ACC_2 is the middle byte of the 24bit output

ACC_3 is the least significant byte of the 24bit output

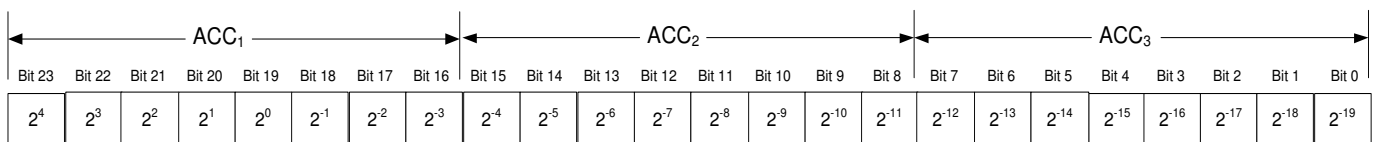


Figure 8-11: Converting output bytes to [g] (example is valid for 10g range)

8.5.2.2.8 Accelerometer output unit = Incremental Velocity

In the case of STIM300 being configured to output incremental velocity per sample, the equations for conversion to [m/s/sample] can be found in Equation 6 and Figure 8-12. Please note that the output data is represented as two's complement.

Equation 6: Converting output to [m/s/sample]

| Range | Conversion: |
|-------|--|
| 2g | $\text{Output}[\text{m/s/sample}] = \frac{(\text{IV}_1) \cdot 2^{16} + (\text{IV}_2) \cdot 2^8 + (\text{IV}_3)}{2^{24}}$ |
| 5g | $\text{Output}[\text{m/s/sample}] = \frac{(\text{IV}_1) \cdot 2^{16} + (\text{IV}_2) \cdot 2^8 + (\text{IV}_3)}{2^{23}}$ |
| 10g | $\text{Output}[\text{m/s/sample}] = \frac{(\text{IV}_1) \cdot 2^{16} + (\text{IV}_2) \cdot 2^8 + (\text{IV}_3)}{2^{22}}$ |
| 30g | $\text{Output}[\text{m/s/sample}] = \frac{(\text{IV}_1) \cdot 2^{16} + (\text{IV}_2) \cdot 2^8 + (\text{IV}_3)}{2^{21}}$ |
| 100g | $\text{Output}[\text{m/s/sample}] = \frac{(\text{IV}_1) \cdot 2^{16} + (\text{IV}_2) \cdot 2^8 + (\text{IV}_3)}{2^{19}}$ |

where IV_1 is the most significant byte of the 24bit output
 IV_2 is the middle byte of the 24bit output
 IV_3 is the least significant byte of the 24bit output

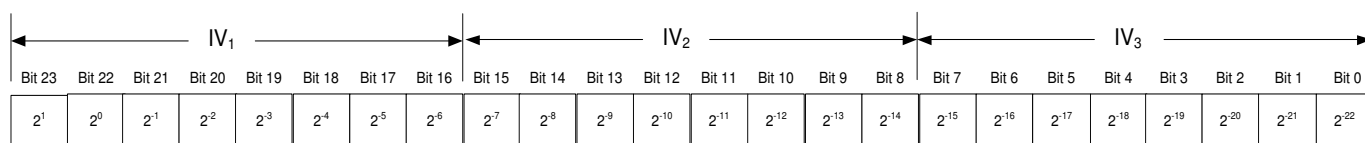


Figure 8-12: Converting output bytes to [m/s/sample] (example is valid for 10g range)

8.5.2.2.9 Accelerometer output unit = Average Acceleration

In the case of STIM300 being configured to output average acceleration, the transmitted data will be the average of the samples since last transmission. E.g. in the case of continuous transmission of datagrams and a sample rate of 500Hz, each transmission will contain the average of the four internal samples.

The average is calculated on the samples using the conventional equation for average calculation:

Equation 7: Calculating average:

$$\text{Output}[\text{g}] = \frac{\sum_{m=1..n} \text{Acceleration}_m}{n}$$

where Acceleration_m is one acceleration data sampled at 2000 samples/s
 n is number of samples since last transmission

Conversion to g] is the same as for angular rate and is described in Equation 5.

8.5.2.2.10 Inclinometer output unit = Acceleration

In the case of STIM300 being configured to output acceleration, Equation 8 and Figure 8-13 show how to do this. Please note that the output data is represented as two's complement.

Equation 8: Converting output to [g]:

$$\text{Output}[g] = \frac{(ACC_1) \cdot 2^{16} + (ACC_2) \cdot 2^8 + (ACC_3)}{2^{22}}$$

where ACC_1 is the most significant byte of the 24bit output
 ACC_2 is the middle byte of the 24bit output
 ACC_3 is the least significant byte of the 24bit output

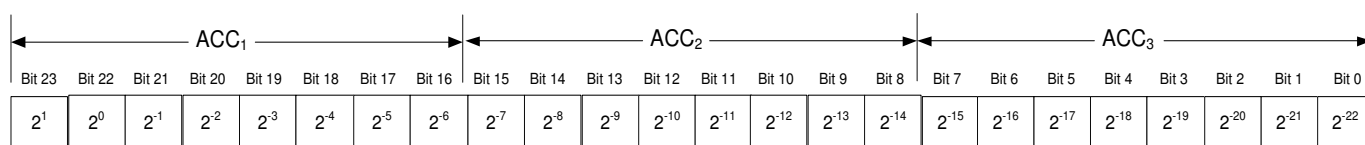


Figure 8-13: Converting output bytes to [g]

8.5.2.2.11 Inclinometer output unit = Incremental Velocity

In the case of STIM300 being configured to output incremental velocity per sample, the equations for conversion to [m/s/sample] can be found in Equation 9 and Figure 8-14. Please note that the output data is represented as two's complement.

Equation 9: Converting output to [m/s/sample]

$$\text{Output}[m/s/sample] = \frac{(IV_1) \cdot 2^{16} + (IV_2) \cdot 2^8 + (IV_3)}{2^{25}}$$

where IV_1 is the most significant byte of the 24bit output
 IV_2 is the middle byte of the 24bit output
 IV_3 is the least significant byte of the 24bit output

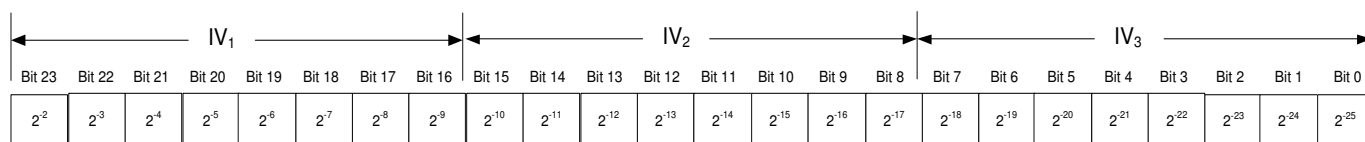


Figure 8-14: Converting output bytes to [m/s/sample]

8.5.2.2.12 Inclinometer output unit = Average Acceleration

In the case of STIM300 being configured to output average acceleration, the transmitted data will be the average of the samples since last transmission. E.g. in the case of continuous transmission of datagrams and a sample rate of 500Hz, each transmission will contain the average of the four internal samples.

The average is calculated on the samples using the conventional equation for average calculation:

Equation 10: Calculating average:

$$\text{Output}[g] = \frac{\sum_{m=1..n} \text{Inclination}_m}{n}$$

where Inclination_m is one inclination data sampled at 2000 samples/s

Conversion to [g] is the same as for angular rate and is described in Equation 8.

8.5.2.2.13 Temperature

Temperature data for each axis is available in certain datagrams (ref. section 12).

Equation 11 and Figure 8-15 show how to convert to [°C]. Please note that the output data is represented as two's complement.

Equation 11: Converting temperature data to [°C]

$$\text{Output}[^{\circ}\text{C}] = \frac{(T_1) \cdot 2^8 + (T_2)}{2^8}$$

where T_1 is the most significant byte of the 16bit output

T_2 is the least significant byte of the 16bit output

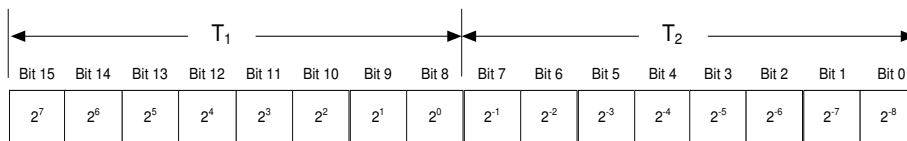


Figure 8-15: Converting temperature data to [°C]

8.5.2.2.14 AUX

In the case of STIM300 being configured to AUX-data, Equation 12 and Figure 8-11 show how to do this. Please note that the output data is represented as two's complement.

Equation 12: Converting output to [V]:

$$\text{Output}[V] = \frac{(AUX_1) \cdot 2^{16} + (AUX_2) \cdot 2^8 + (AUX_3)}{2^{24}} \cdot 5V$$

where AUX_1 is the most significant byte of the 24bit output

AUX_2 is the middle byte of the 24bit output

AUX_3 is the least significant byte of the 24bit output

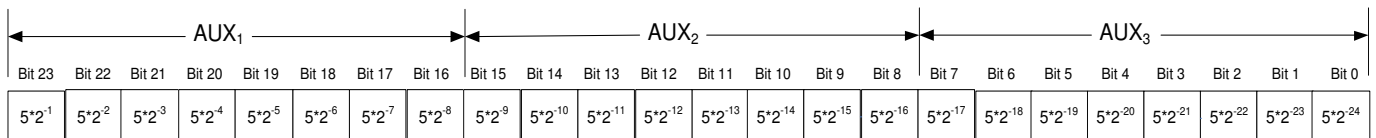


Figure 8-16: Converting output bytes to [V]

8.5.2.2.15 Counter

Counter is continuously counting the internal samples (2000 samples/s). Counter is an un-signed single byte taking values in the interval [0 , 255]. The counter will naturally wrap-around with no error-message indication in the Status-byte.

8.5.2.2.16 Latency

To calculate the latency in [μs], refer to Equation 13 and Figure 8-17. Please note that latency is an unsigned word.

Equation 13: Converting output to [μs]:

$$\text{Output}[\mu\text{s}] = (\text{LT}_1) \cdot 2^8 + (\text{LT}_2)$$

where LT_1 is the most significant byte of the 16bit output

LT_2 is the least significant byte of the 16bit output

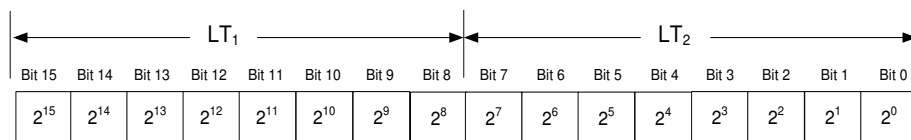


Figure 8-17: Converting output bytes to [μs]

8.5.3 Service Mode

In Service Mode the communication interface is human readable and hence the communication format (ASCII) supports the use of terminal-based software during the development phase, when the configuration of a device needs to be changed or during investigations into an observed problem.

When Service Mode is entered, STIM300 will respond with its configuration information (same as the response to the `i` (INFORMATION) command, ref: Figure 10-1).

A set of commands are available, ref. Section 10, enabling the user to change intermediately or permanently the configuration parameters, display latest measurement results, display higher details on error information and perform a full diagnostic of the unit.

In Service Mode the gyro measurements will still be running in the background, enabling to switch directly back to Normal Mode without the need for any stabilisation time of filters, etc. However the measurement data itself, when STIM300 is in Service Mode are not transmitted and therefore lost. By using the `a` (SINGLE-SHOT MEASUREMENT) command (ref. Section 10.2) it is possible to display single measurement results.

Exiting Service Mode can be done in several ways:

1. Using the external reset. This will force STIM300 into Init Mode. Please be advised that during Init Mode, all the configuration parameters are loaded from flash. If any of the configuration parameters have been changed during the Service Mode session but not saved to flash, these changes will be overwritten by the content already stored in flash.
2. Using the `x` (EXIT) command. When using this command a parameter is required to decide whether the device should go to Init Mode or to Normal Mode. When exiting to Normal Mode, any of the changes made to the configuration parameters will still be valid. However, if not saved, the configuration parameters will be overwritten by the content already stored in flash at the next power-up or reset.

8.6 Self diagnostics

STIM300 is constantly checking its internal status. The checks include:

- Check of internal references
- Check of sensors (error and overload)
- Check of internal temperatures
- Check of RAM and flash
- Check of supply voltage

When an error situation is detected, the corresponding bit in the STATUS byte (ref. Table 6-16) will be set.

The bits in the STATUS are valid for the data in a single transmission. Hence any error condition is not latched.

In Service Mode it is possible to see the last detected error by using the `ie` (INFORMATION on LAST ERROR IN NORMAL MODE) command, ref. Section 10.1 or run a full diagnostic and see the result of the individual checks by using the `c` (DIAGNOSTIC) command, ref. Section 10.3.

9 COMMANDS IN NORMAL MODE

Several commands are available in Normal Mode, as listed in Table 9-1. Please note that all commands in Normal Mode must be transmitted in upper case letters.

Table 9-1 Available commands in Normal Mode

| Command | Short description |
|-------------|--------------------------------------|
| N | Transmits one Part Number datagram |
| I | Transmits one Serial Number datagram |
| C | Transmits one Configuration datagram |
| R | Resets the unit |
| SERVICEMODE | Enters Service Mode |

Table 9-2 List of special ASCII characters used in Normal Mode

| Char | Hex | Dec | Short description |
|------|------|-----|---|
| <CR> | 0x0D | 13 | “Carriage Return”: used as execution character for commands |

No echo of received command characters nor error messages will appear for these commands. Only at the receipt of the complete correct command, STIM300 executes accordingly.

NB: if OUTPUT-UNIT of the gyros is set to INCREMENTAL ANGLE (ref. Section 10.7), the transmitted incremented angle in the datagram following any of the requested special datagrams will NOT contain the incremental angle since the last transmitted measurement. Hence the incremented angle occurring during the transmission of a special requested datagram will be lost.

9.1 N (PART NUMBER DATAGRAM) command

General description: Requests transmission of a Part Number datagram (ref. Table 6-10).

Table 9-3 : Available I (PART NUMBER DATAGRAM) command

| Syntax | Response |
|--------|------------------------------------|
| N<CR> | Transmits one Part Number datagram |

The Part Number datagram will replace the next transmitted Normal Mode datagram. If datagram transmission is set to trigger on external trigger, the Part Number datagram will be transmitted without waiting for an external trigger signal.

9.2 I (SERIAL NUMBER DATAGRAM) command

General description: Requests transmission of a Serial number datagram (ref. Table 6-11).

Table 9-4 : Available I (SERIAL NUMBER DATAGRAM) command

| Syntax | Response |
|--------|--------------------------------------|
| I<CR> | Transmits one Serial Number datagram |

The Serial Number datagram will replace the next transmitted Normal Mode datagram. If datagram transmission is set to trigger on external trigger, the Serial Number datagram will be transmitted without waiting for an external trigger signal.

9.3 C (CONFIGURATION DATAGRAM) command

General description: Requests transmission of a Configuration datagram (ref. Table 6-12).

Table 9-5: Available C (CONFIGURATION DATAGRAM) command

| Syntax | Response |
|--------|--------------------------------------|
| C<CR> | Transmits one Configuration datagram |

The Configuration datagram will replace the next transmitted Normal Mode datagram. If datagram transmission is set to trigger on external trigger, the Configuration datagram will be transmitted without waiting for an external trigger signal.

9.4 R (RESET) command

General description: Force a Reset

Table 9-6: Available R (RESET) command

| Syntax | Response |
|--------|-----------------|
| R<CR> | Resets the unit |

9.5 SERVICEMODE command

General description : Enters Service Mode (ref. section 8.5.3).

Table 9-7: Available SERVICEMODE command

| Syntax | Response |
|-----------------|---------------------|
| SERVICEMODE<CR> | Enters Service Mode |

If the command is received during the transmission of a datagram, it will complete the transmission before entering Service Mode.

When entering Service Mode, the configuration and identification data of the device will be listed, as shown in Figure 9-1:

```

SERIAL NUMBER = N25580846002002
PRODUCT = STIM300
PART NUMBER = 84167-44000-331 REV C
FW CONFIG = SWD12046 REV 2
GYRO OUTPUT UNIT = [%s] – ANGULAR RATE DELAYED
ACCELEROMETER OUTPUT UNIT = [g] – ACCELERATION
INCLINOMETER OUTPUT UNIT = [g] - ACCELERATION
SAMPLE RATE [samples/s] = 2000
GYRO CONFIG = XYZ
ACCELEROMETER CONFIG = XYZ
INCLINOMETER CONFIG = XYZ
GYRO RANGE:
  X-AXIS: ± 400°s
  Y-AXIS: ± 400°s
  Z-AXIS: ± 400°s
ACCELEROMETER RANGE:
  X-AXIS: ± 10g
  Y-AXIS: ± 10g
  Z-AXIS: ± 10g
INCLINOMETER RANGE:
  X-AXIS: ± 1.7g
  Y-AXIS: ± 1.7g
  Z-AXIS: ± 1.7g
AUX RANGE: ± 2.5V
GYRO LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
AUX LP FILTER -3dB FREQUENCY [Hz] = 262
AUX COMP COEFF: A = 1.0000000e+00, B = 0.0000000e+00
GYRO G-COMPENSATION:
  BIAS SOURCE, X-AXIS = OFF
  BIAS G-COMP LP-FILTER, X-AXIS = NA
  SCALE SOURCE, X-AXIS = ACC
  SCALE G-COMP LP-FILTER, X-AXIS = OFF
  BIAS SOURCE, Y-AXIS = OFF
  BIAS G-COMP LP-FILTER, Y-AXIS = NA
  SCALE SOURCE, Y-AXIS = ACC
  SCALE G-COMP LP-FILTER, Y-AXIS = OFF
  BIAS SOURCE, Z-AXIS = OFF
  BIAS G-COMP LP-FILTER, Z-AXIS = NA
  SCALE SOURCE, Z-AXIS = ACC
  SCALE G-COMP LP-FILTER, Z-AXIS = OFF
  G-COMP LP-FILTER CUTOFF = 0.010 HZ
DATAGRAM = RATE, ACCELERATION, INCLINATION
DATAGRAM TERMINATION = NONE
BIT-RATE [bits/s] = 1843200
DATA LENGTH = 8
STOP BITS = 1
PARITY = NONE
LINE TERMINATION = ON
>

```

Figure 9-1: Example of response from SERVICEMODE command

10 COMMANDS IN SERVICE MODE

Several commands are available in Service Mode, as listed in Table 10-1. Please note that all commands in Service Mode are case-sensitive (commands are lower case letters, whilst some parameters may be capital case letters).

Table 10-1 Available commands in Service Mode

| Command | Short description |
|---------|---|
| i | Lists specific information (e.g. serial number, configuration, error information) |
| a | Performs a single-shot measurement |
| c | Performs a diagnostic of the unit |
| d | Changes datagram format |
| t | Changes transmission parameters (e.g. bit-rate, data-length, stop-bits) |
| r | Turns line termination ON or OFF |
| u | Changes measurement output unit |
| f | Changes LP filter -3dB frequency |
| m | Changes sample rate |
| k | Changes coefficients of the AUX compensation algorithm |
| g | Changes the gyro g-compensation configuration for bias and scale factor |
| s | Saves configuration data |
| x | Exits Service Mode and returns to Normal Mode or Init Mode |
| z | Restore to factory settings |
| ? | Help function on the available commands in Service Mode |

Table 10-2 List of special ASCII characters used in Service Mode

| Char | Hex | Dec | Short description |
|------|------|-----|--|
| <BS> | 0x08 | 8 | “Back Space”: deletes last received character (received since last <CR>) |
| <CR> | 0x0D | 13 | “Carriage Return”: typically used as execution character for commands |
| <SP> | 0x20 | 32 | “Space”: used to separate command and first parameter |
| ‘,’ | 0x2C | 44 | “Comma”: used to separate parameters in a command |
| ‘>’ | 0x3E | 62 | Used together with <CR> as: “Ready to receive new command”-prompt |

When STIM300 is in Service Mode and ready to receive a new command, it will issue the special ASCII character <CR> followed by ‘>’. As some commands (e.g. SINGLE-SHOT MEASUREMENT-command) may respond with a varying number of lines, automated set-ups should look for the special prompt-sequence (<CR>+’>’) before issuing a new command.

Received characters will be echoed. A command is decoded and executed when receiving the special ASCII character <CR>. <BS> (“back-space”) is also recognised and will delete the last received character in the input buffer. The size of the input buffer is 80 characters. <BS> is valid for the characters received since last <CR>.

The command-character and first parameter (when applicable) are separated by a space (character 0x20). When there are more than one parameter to a command (e.g. TRANSMISSION PARAMETER-command), these must be separated by a comma (character 0x2C).

In the event of an unknown command, inconsistent syntax or incorrect value of parameter(s), STIM300 will respond with an error message. Error messages are on the format:

E<nnn><SP><Error description><CR>

where nnn is an error number

10.1 i (INFORMATION) command

General description: Lists various requested information about the device

Table 10-3 : Available i (INFORMATION) commands

| Syntax | Response |
|----------------|---|
| i<CR> | Lists the product configuration and identification data |
| i<SP><cmd><CR> | Gives information about the specific parameter |

Table 10-4 : Allowed values for <cmd> parameter for i (INFORMATION) commands

| <cmd> | Result |
|-------|---|
| s | Returns the serial number of the device |
| n | Returns the product name of the device |
| x | Returns the part number of the device |
| a | Returns the axis configuration of the device |
| p | Returns the FW configuration and revision of the device |
| m | Returns the sample rate of the device |
| f | Returns the LP filter -3dB frequency for each axis |
| d | Returns the datagram format |
| t | Returns the transmission parameters of the device |
| r | Returns the line termination (ON or OFF) |
| u | Returns the output units of the device |
| g | Returns the configuration of the gyro g-compensation |
| k | Returns the compensation coefficients for AUX input |
| e | Prints the extended error information from the last detected error in Normal Mode |

Table 10-5: Error messages for i (INFORMATION) commands

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command or parameter is not recognised |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```

>i
SERIAL NUMBER = N25580846002002
PRODUCT = STIM300
PART NUMBER = 84167-44000-331 REV C
FW CONFIG = SWD12046 REV 2
GYRO OUTPUT UNIT = [%s] – ANGULAR RATE DELAYED
ACCELEROMETER OUTPUT UNIT = [g] – ACCELERATION
INCLINOMETER OUTPUT UNIT = [g] - ACCELERATION
SAMPLE RATE [samples/s] = 2000
GYRO CONFIG = XYZ
ACCELEROMETER CONFIG = XYZ
INCLINOMETER CONFIG = XYZ
GYRO RANGE:
  X-AXIS: ± 400 %s
  Y-AXIS: ± 400 %s
  Z-AXIS: ± 400 %s
ACCELEROMETER RANGE:
  X-AXIS: ± 10g
  Y-AXIS: ± 10g
  Z-AXIS: ± 10g
INCLINOMETER RANGE:
  X-AXIS: ± 1.7g
  Y-AXIS: ± 1.7g
  Z-AXIS: ± 1.7g
AUX RANGE: ± 2.5V
GYRO LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
AUX LP FILTER -3dB FREQUENCY [Hz] = 262
AUX COMP COEFF: A = 1.0000000e+00, B = 0.0000000e+00
GYRO G-COMPENSATION:
  BIAS SOURCE, X-AXIS = OFF
  BIAS G-COMP LP-FILTER, X-AXIS = NA
  SCALE SOURCE, X-AXIS = ACC
  SCALE G-COMP LP-FILTER, X-AXIS = OFF
  BIAS SOURCE, Y-AXIS = OFF
  BIAS G-COMP LP-FILTER, Y-AXIS = NA
  SCALE SOURCE, Y-AXIS = ACC
  SCALE G-COMP LP-FILTER, Y-AXIS = OFF
  BIAS SOURCE, Z-AXIS = OFF
  BIAS G-COMP LP-FILTER, Z-AXIS = NA
  SCALE SOURCE, Z-AXIS = ACC
  SCALE G-COMP LP-FILTER, Z-AXIS = OFF
  G-COMP LP-FILTER CUTOFF = 0.010 HZ
DATAGRAM = RATE, ACCELERATION, INCLINATION
DATAGRAM TERMINATION = NONE
BIT-RATE [bits/s] = 1843200
DATA LENGTH = 8
STOP BITS = 1
PARITY = NONE
LINE TERMINATION = ON
>

```

Figure 10-1: Example of response from i (INFORMATION) command

```
>i s
SERIAL NUMBER = N25580846002002
>
```

Figure 10-2: Example of response from i s (INFORMATION on SERIAL NUMBER) command

```
>i n
PRODUCT = STIM300
>
```

Figure 10-3: Example of response from i n (INFORMATION on PRODUCT NAME) command

```
>i x
PART NUMBER = 84167-44000-331 REV C
>
```

Figure 10-4: Example of response from i x (INFORMATION on PART NUMBER) command

```
>i a
GYRO CONFIG = XYZ
ACCELEROMETER CONFIG = XYZ
INCLINOMETER CONFIG = XYZ
GYRO RANGE:
X-AXIS: ± 400°/s
Y-AXIS: ± 400°/s
Z-AXIS: ± 400°/s
ACCELEROMETER RANGE:
X-AXIS: ± 10g
Y-AXIS: ± 10g
Z-AXIS: ± 10g
INCLINOMETER RANGE:
X-AXIS: ± 1.7g
Y-AXIS: ± 1.7g
Z-AXIS: ± 1.7g
AUX RANGE: ± 2.5V
>
```

Figure 10-5: Example of response from i a (INFORMATION on AXIS CONFIGURATION) command

```
>i p
FW CONFIG = SWD12046 REV 2
>
```

Figure 10-6: Example of response from i p (INFORMATION on FW CONFIGURATION) command

```
>i m
SAMPLE RATE [samples/s] = 2000
>
```

Figure 10-7: Example of response from i m (INFORMATION on SAMPLE RATE) command

```
>i f
GYRO LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
GYRO LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
ACCELEROMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 262
INCLINOMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 262
AUX LP FILTER -3dB FREQUENCY [Hz] = 262
```

Figure 10-8: Example of response from i f (INFORMATION on LP FILTER -3dB FREQUENCY) command

```
>i d
DATAGRAM = RATE, ACCELERATION, INCLINATION
DATAGRAM TERMINATION = NONE
```

Figure 10-9: Example of response from i d (INFORMATION on DATAGRAM TRANSMISSION MODE AND TERMINATION) command

```
>i t
BIT-RATE [bits/s] = 1843200
DATA LENGTH = 8
STOP BITS = 1
PARITY = NONE
```

Figure 10-10: Example of response from i t (INFORMATION on TRANSMISSION PARAMETERS) command

```
>i r
LINE TERMINATION = ON
```

Figure 10-11: Example of response from i r (INFORMATION on LINE TERMINATION) command

```
>i u
GYRO OUTPUT UNIT = [%s] – ANGULAR RATE DELAYED
ACCELEROMETER OUTPUT UNIT = [g] – ACCELERATION
INCLINOMETER OUTPUT UNIT = [g] – ACCELERATION
```

Figure 10-12: Example of response from i u (INFORMATION on OUTPUT UNIT) command

```
>i g
GYRO G-COMPENSATION:
BIAS SOURCE, X-AXIS = OFF
BIAS G-COMP LP-FILTER, X-AXIS = NA
SCALE SOURCE, X-AXIS = ACC
SCALE G-COMP LP-FILTER, X-AXIS = OFF
BIAS SOURCE, Y-AXIS = OFF
BIAS G-COMP LP-FILTER, Y-AXIS = NA
SCALE SOURCE, Y-AXIS = ACC
SCALE G-COMP LP-FILTER, Y-AXIS = OFF
BIAS SOURCE, Z-AXIS = OFF
BIAS G-COMP LP-FILTER, Z-AXIS = NA
SCALE SOURCE, Z-AXIS = ACC
SCALE G-COMP LP-FILTER, Z-AXIS = OFF
G-COMP LP-FILTER CUTOFF = 0.010 HZ
>
```

Figure 10-13: Example of response from i g (INFORMATION on GYRO G-COMP) command

```
>i k
AUX COMP COEFF: A = 1.0200000e+00, B = 3.4000000e-02
>
```

Figure 10-14: Example of response from i k (INFORMATION on AUX COMP) command

```
>i e
GYRO X-AXIS I-CH OVERFLOW = FAILED
>
```

Figure 10-15: Example of response from i e (INFORMATION on LAST ERROR IN NORMAL MODE) command

10.2 a (SINGLE-SHOT MEASUREMENT) command

General description: Displays the result of latest measurement (measurement process running constantly in the background).

NB: SINGLE-SHOT MEASUREMENT-command is not available if SAMPLE RATE is set to External Trigger.

Table 10-6: Available a (SINGLE-SHOT MEASUREMENT) command

| Syntax | Response |
|--------|--|
| a<CR> | Displays the result of the latest measurement <u>s</u> ample |

Table 10-7: Error messages for a (SINGLE-SHOT MEASUREMENT) command

| Error | Message | Possible reason |
|-------|--------------------------------|---|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Any characters between command and <CR> |

```

>a
GYRO X-AXIS = 1.43253 %s
GYRO Y-AXIS = 2.34525 %s
GYRO Z-AXIS = 243.33628 %s
GYRO STATUS = 00000000 = OK

ACCELEROMETER X-AXIS = 0.042113 g
ACCELEROMETER Y-AXIS = 0.000342 g
ACCELEROMETER Z-AXIS = 0.929376 g
ACCELEROMETER STATUS = 00000000 = OK

INCLINOMETER X-AXIS = 0.0426473 g
INCLINOMETER Y-AXIS = 0.0003832 g
INCLINOMETER Z-AXIS = 0.9246325 g
INCLINOMETER STATUS = 00000000 = OK

TEMPERATURE GYRO X-AXIS = 32.326 °C
TEMPERATURE GYRO Y-AXIS = 32.467 °C
TEMPERATURE GYRO Z-AXIS = 32.265 °C
TEMPERATURE STATUS = 00000000 = OK

TEMPERATURE ACC X-AXIS = 32.846 °C
TEMPERATURE ACC Y-AXIS = 32.477 °C
TEMPERATURE ACC Z-AXIS = 32.965 °C
TEMPERATURE STATUS = 00000000 = OK

TEMPERATURE INC X-AXIS = 32.326 °C
TEMPERATURE INC Y-AXIS = 32.123 °C
TEMPERATURE INC Z-AXIS = 32.326 °C
TEMPERATURE STATUS = 00000000 = OK

AUX = -0.8356746 V
AUX STATUS = 00000000 = OK

COUNTER = 10
LATENCY = 516 us

>

```

Figure 10-16: Example of response from a (SINGLE-SHOT MEASUREMENT) command

```
>a
GYRO X-AXIS = 0.00071 %/s
GYRO Y-AXIS = 0.12324 %/s
GYRO Z-AXIS = 480.00000 %/s
GYRO STATUS = 00010100 = NOT OK
  BIT 4: OVERLOAD
  BIT 2: ERROR IN Z-CHANNEL

ACCELEROMETER X-AXIS = 0.042113 g
ACCELEROMETER Y-AXIS = 0.000342 g
ACCELEROMETER Z-AXIS = 0.929376 g
ACCELEROMETER STATUS = 00000000 = OK

INCLINOMETER X-AXIS = 0.0426473 g
INCLINOMETER Y-AXIS = 0.0003832 g
INCLINOMETER Z-AXIS = 0.9246325 g
INCLINOMETER STATUS = 00000000 = OK

TEMPERATURE GYRO X-AXIS = 32.326 °C
TEMPERATURE GYRO Y-AXIS = 32.467 °C
TEMPERATURE GYRO Z-AXIS = 32.265 °C
TEMPERATURE STATUS = 00000000 = OK

TEMPERATURE ACC X-AXIS = 32.846 °C
TEMPERATURE ACC Y-AXIS = 32.477 °C
TEMPERATURE ACC Z-AXIS = 32.965 °C
TEMPERATURE STATUS = 00000000 = OK

TEMPERATURE INC X-AXIS = 32.326 °C
TEMPERATURE INC Y-AXIS = 32.123 °C
TEMPERATURE INC Z-AXIS = 32.326 °C
TEMPERATURE STATUS = 00000000 = OK

AUX = -0.8356746 V
AUX STATUS = 00000000 = OK

COUNTER = 10
LATENCY = 516 us

>
```

Figure 10-17: Example of response from a (SINGLE-SHOT MEASUREMENT) command with error flagging

10.3 c (DIAGNOSTIC) command

General description: Performs a diagnostic of the unit.

Table 10-8: Available c (DIAGNOSTIC) command

| Syntax | Response |
|--------|-----------------------------|
| c<CR> | Performs a diagnostic check |

Table 10-9: Error messages for c (DIAGNOSTIC) command

| Error | Message | Possible reason |
|-------|--------------------------------|---|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Any characters between command and <CR> |

```

SERIAL NUMBER = N25581142431021
PRODUCT = STIM300
PART NUMBER = 84167-44000-331 REV C
HW CONFIG = M5728 REV 2
FW CONFIG = SWD12008 REV 2
SYSTEM STATUS:
RAM CHECK = OK
FLASH CHECK = OK
STACK STATUS MONITOR = OK
STACK COMMAND HANDLER = OK
STACK SAMPLE = OK
STACK FLASH = OK
MICRO CONTROLLER TEMPERATURE = OK
VOLTAGE SUPPLIES:
REFERENCE VOLTAGE 5.0V = OK
REFERENCE VOLTAGE 2.5V = OK
REFERENCE VOLTAGE 2.048V = OK
REGULATED VOLTAGE 5.0V = OK
REGULATED VOLTAGE 1.8V = OK
INPUT VOLTAGE 5.0V = OK
VOLTAGE BOOST = OK
VOLTAGE DAC = OK
GYRO X-AXIS:
GYRO X-AXIS Data Ready = OK
GYRO X-AXIS EXC.FREQ = OK
GYRO X-AXIS ASIC TEMP = OK
GYRO X-AXIS SENSOR TEMP = OK
GYRO X-AXIS COMPENSATED RATE SIGNAL = OK
GYRO X-AXIS DASIC COMMUNICATION = OK
GYRO X-AXIS Q-CH RANGE = OK
GYRO X-AXIS I-CH RANGE = OK
GYRO X-AXIS DET. DC = OK
GYRO X-AXIS EXC. DC = OK
GYRO X-AXIS SPI = OK
GYRO X-AXIS EXC.AMPL = OK
GYRO X-AXIS OVERRUN = OK
GYRO Y-AXIS:
GYRO Y-AXIS Data Ready = OK
GYRO Y-AXIS EXC.FREQ = OK
GYRO Y-AXIS ASIC TEMP = OK
GYRO Y-AXIS SENSOR TEMP = OK
GYRO Y-AXIS COMPENSATED RATE SIGNAL = OK
GYRO Y-AXIS DASIC COMMUNICATION = OK
GYRO Y-AXIS Q-CH RANGE = OK
GYRO Y-AXIS I-CH RANGE = OK
GYRO Y-AXIS DET. DC = OK
    
```

```
GYRO Y-AXIS EXC. DC = OK
GYRO Y-AXIS SPI = OK
GYRO Y-AXIS EXC.AMPL = OK
GYRO Y-AXIS OVERRUN = OK
GYRO Z-AXIS:
GYRO Z-AXIS Data Ready = OK
GYRO Z-AXIS EXC.FREQ = OK
GYRO Z-AXIS ASIC TEMP = OK
GYRO Z-AXIS SENSOR TEMP = OK
GYRO Z-AXIS COMPENSATED RATE SIGNAL = OK
GYRO Z-AXIS DASIC COMMUNICATION = OK
GYRO Z-AXIS Q-CH RANGE = OK
GYRO Z-AXIS I-CH RANGE = OK
GYRO Z-AXIS DET. DC = OK
GYRO Z-AXIS EXC. DC = OK
GYRO Z-AXIS SPI = OK
GYRO Z-AXIS EXC.AMPL = OK
GYRO Z-AXIS OVERRUN = OK
ACCELEROMETER X-AXIS:
ACCELEROMETER X-AXIS COMPENSATED SIGNAL = OK
ACCELEROMETER X-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
ACCELEROMETER Y-AXIS:
ACCELEROMETER Y-AXIS COMPENSATED SIGNAL = OK
ACCELEROMETER Y-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
ACCELEROMETER Z-AXIS:
ACCELEROMETER Z-AXIS COMPENSATED SIGNAL = OK
ACCELEROMETER Z-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
INCLINOMETER X-AXIS:
INCLINOMETER X-AXIS COMPENSATED SIGNAL = OK
INCLINOMETER X-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
INCLINOMETER Y-AXIS:
INCLINOMETER Y-AXIS COMPENSATED SIGNAL = OK
INCLINOMETER Y-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
INCLINOMETER Z-AXIS:
INCLINOMETER Z-AXIS COMPENSATED SIGNAL = OK
INCLINOMETER Z-AXIS TEMPERATURE = OK
EXTERNAL ADC COMMUNICATION = OK
AUX:
AUX = OK
EXTERNAL ADC COMMUNICATION = OK
```

>

Figure 10-18: Example of response from c (DIAGNOSTIC) command

10.4 d (DATAGRAM FORMAT) command

General description: Sets the datagram transmission mode and termination (ref. Table 6-8 and section 12).

Note that the datagram format could be considered invalid, even if it has been entered correctly. This is because a valid datagram format also depends on the sample rate and chosen datagram content (ref. Table 6-9 and error message E007 in Table 10-13).

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-10 : Available d (DATAGRAM FORMAT) command

| Syntax | Response |
|--------------------------|---|
| d<SP><type>','<term><CR> | Changes the datagram transmission mode and termination in Normal Mode |

Table 10-11 : Allowed values for <trans> parameter of d (DATAGRAM TRANSMISSION MODE AND TERMINATION) command

| <type> | Datagram content |
|--------|--|
| 0 | ID, rate, counter, latency, CRC |
| 1 | ID, rate, acceleration, counter, latency, CRC |
| 2 | ID, rate, inclination, counter, latency, CRC |
| 3 | ID, rate, acceleration, inclination, counter, latency, CRC |
| 4 | ID, rate, temperature, counter, latency, CRC |
| 5 | ID, rate, acceleration, temperature, counter, latency, CRC |
| 6 | ID, rate, inclination, temperature, counter, latency, CRC |
| 7 | ID, rate, acceleration, inclination, temperature, counter, latency, CRC |
| 8 | ID, rate, AUX, counter, latency, CRC |
| 9 | ID, rate, acceleration, AUX, counter, latency, CRC |
| a | ID, rate, inclination, AUX, counter, latency, CRC |
| b | ID, rate, acceleration, inclination, AUX, counter, latency, CRC |
| c | ID, rate, temperature, AUX, counter, latency, CRC |
| d | ID, rate, acceleration, temperature, AUX, counter, latency, CRC |
| e | ID, rate, inclination, temperature, AUX, counter, latency, CRC |
| f | ID, rate, acceleration, inclination, temperature, AUX, counter, latency, CRC |

Table 10-12 : Allowed values for <term> parameter of d (DATAGRAM TRANSMISSION MODE AND TERMINATION) command

| <trans> | Result |
|---------|--|
| 0 | Changes the datagram termination to no termination |
| 1 | Changes the datagram termination to <CR><LF> |

Table 10-13: Error messages for d (DATAGRAM TRANSMISSION MODE AND TERMINATION) command

| Error | Message | Possible reason |
|-------|---------------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |
| E007 | DATAGRAM WILL BE TOO LONG TO TRANSMIT | Combination of bit-rate, sample rate and datagram content results in a datagram that cannot be transmitted |

```
>d 8,0
DATAGRAM = RATE, AUX
DATAGRAM TERMINATION = NONE
>
```

Figure 10-19: Example of response from d (DATAGRAM MODE AND TERMINATION) command

```
>d 3,1  
DATAGRAM = RATE, ACCELERATION, INCLINATION  
DATAGRAM TERMINATION = <CR><LF>  
  
>
```

Figure 10-20: Example of response from d (DATATGRAM MODE AND TERMINATION) command

10.5 t (TRANSMISSION PARAMETERS) command

General description: Changes the transmission parameters for the RS422 interface.

Note that the bit-rate could be considered invalid, even if it has been entered correctly. This is because a valid bit-rate also depends on the sample rate and chosen datagram content (ref. Table 6-9 and error message E007 in Table 10-18).

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-14 : Available t (TRANSMISSION PARAMETERS) commands

| Syntax | Response |
|---|--|
| t<SP><bit-rate code><CR> | Changes the transmission bit-rate and leaves number of stop-bits and parity unchanged |
| t<SP><bit-rate code>,'<stop-bits>','<parity><CR> | Changes the transmission bit-rate, number of stop-bits and parity |
| t<SP>'f','<bit-rate><CR> | Changes the transmission bit-rate to a user-defined bit-rate and leaves number of stop-bits and parity unchanged, ref.section 10.5.1 |
| t<SP>'f','<bit-rate>','<stop-bits>','<parity><CR> | Changes the transmission bit-rate to a user-defined bit-rate, number of stop-bits and parity, ref.section 10.5.1 |

Table 10-15: Allowed values for <bit-rate code> parameter for t (TRANSMISSION PARAMETERS) commands

| <bit-rate code> | Result |
|-----------------|---|
| 0 | Will set the bit-rate to 377400 bits/s |
| 1 | Will set the bit-rate to 460800 bits/s |
| 2 | Will set the bit-rate to 921600 bits/s |
| 3 | Will set the bit-rate to 1843200 bits/s |

Table 10-16: Allowed values for <stop-bits> parameter for t (TRANSMISSION PARAMETERS) commands

| <stop-bits> | Result |
|-------------|-----------------------------------|
| 1 | Will set number of stop bits to 1 |
| 2 | Will set number of stop bits to 2 |

Table 10-17: Allowed values for <parity> parameter for t (TRANSMISSION PARAMETERS) commands

| <parity> | Result |
|----------|----------------------|
| 0 | Will set no parity |
| 1 | Will set odd parity |
| 2 | Will set even parity |

10.5.1 User-defined bit-rate

The STIM300 hardware is capable of setting bit-rates in the range between 1500 and 9 550 000 bits/s. However, the sample rate and the datagram length decide the minimum bit-rate possible, ref. Equation 14:

Equation 14: Minimum bit-rate

$$\text{Bit-rate}_{\text{MIN}} = 1.1 \cdot \text{bits} \cdot \text{bytes} \cdot \text{sample_rate}$$

where bits = start-bit (1) + data-bits (8) + stop-bits (1 or 2) + parity-bit (0 or 1)
 bytes = number of bytes in the chosen datagram, ref. Table 6-13 and Table 6-9 (NB: number of bytes in Table 6-9 includes <CR><LF>)
 sample_rate is the chosen sample rate [samples/s]

If a bit-rate, lower than the allowed bit-rate defined by Equation 14, is entered, the command will respond with error message E007, ref. Table 10-18.

There are a finite number of bit-rates possible to set. This is defined in Equation 15:

Equation 15: Set bit-rate

$$\text{Bit-rate}_{\text{SET}} = \frac{85504000}{n} \text{ bits/s}$$

where n is an integer

The actually set bit-rate will hence be the closest to requested bit-rate. The response of the t (TRANSMISSION PARAMETERS)-command will be the set bit-rate. Be aware that for certain bit-rates above 1.5Mbit/s, the deviation between the requested bit-rate and set bit-rate could be larger than 1% and may be in conflict with the RS422 specification. No warnings are issued related to this issue. As a safety precaution, the new bit-rate can only be permanently by the s (SAVE)-command later using the new bit-rate.

Table 10-18: Error messages for t (TRANSMISSION PARAMETERS) commands

| Error | Message | Possible reason |
|-------|---------------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |
| E007 | DATAGRAM WILL BE TOO LONG TO TRANSMIT | Combination of bit-rate, sample rate and datagram content results in a datagram that cannot be transmitted |

```
>t 2,1,2
BIT-RATE [bits/s] = 921600
DATA LENGTH = 8
STOP BITS = 1
PARITY = EVEN
>
```

Figure 10-21: Example of response from t (TRANSMISSION PARAMETERS) command to set standard bit-rate

```
>t f,500000
BIT-RATE [bits/s] = 500023
DATA LENGTH = 8
STOP BITS = 1
PARITY = EVEN
>
```

Figure 10-22: Example of response from t (TRANSMISSION PARAMETERS) command to set user-defined bit-rate

10.6 r (LINE TERMINATION) command

General description: Turns the line termination ON or OFF. Line termination should be ON when communicating point-point (single master – single slave).

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-19: Available r (LINE TERMINATION) command

| Syntax | Response |
|---------------------|------------------------------|
| r<SP><lineterm><CR> | Changes the line termination |

Table 10-20: Allowed values for r (LINE TERMINATION) command

| <lineterm> | Result |
|------------|----------------------------|
| 0 | Turns line termination OFF |
| 1 | Turns line termination ON |

Table 10-21: Error messages for r (LINE TERMINATION) command

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```
>r 0
LINE TERMINATION = OFF
>
```

Figure 10-23: Example of response from r 0 (LINE TERMINATION) command

```
>r 1
LINE TERMINATION = ON
>
```

Figure 10-24: Example of response from r 1 (LINE TERMINATION) command

10.7 u (OUTPUT UNIT) command

General description: Sets the output unit of the transmission in Normal Mode.

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-22: Available u (OUTPUT UNIT) command

| Syntax | Response |
|-----------------------------------|---|
| u <SP>'<sens>','<unit><CR> | Changes the unit of the transmission in Normal Mode |

Table 10-23: Allowed values for <sens> and <unit> for u (OUTPUT UNIT) command

| <sens> | <unit> | Result |
|--------|--------|--|
| g | 0 | Changes the gyro output unit to angular rate [%s] |
| g | 1 | Changes the gyro output unit to incremental angle [%sample] |
| g | 2 | Changes the gyro output unit to average angular rate [%s] |
| g | 3 | Changes the gyro output unit to integrated angle [°] |
| g | 8 | Changes the gyro output unit to angular rate – delayed [%s] |
| g | 9 | Changes the gyro output unit to incremental angle – delayed [%sample] |
| g | a | Changes the gyro output unit to average angular rate – delayed [%s] |
| g | b | Changes the gyro output unit to integrated angle – delayed [°] |
| a | 0 | Changes the accelerometer output unit to acceleration [g] |
| a | 1 | Changes the accelerometer output unit to incremental velocity [m/s/sample] |
| a | 2 | Changes the accelerometer output unit to average acceleration [g] |
| i | 0 | Changes the inclinometer output unit to acceleration [g] |
| i | 1 | Changes the inclinometer output unit to incremental velocity [m/s/sample] |
| i | 2 | Changes the inclinometer output unit to average acceleration [g] |

Table 10-24: Error messages for u (OUTPUT UNIT) command

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```
>u g,0
GYRO OUTPUT UNIT = [%s] – ANGULAR RATE
>
```

Figure 10-25: Example of response from u (OUTPUT UNIT) command

```
>u a,2
ACCELEROMETER OUTPUT UNIT = [g] – AVERAGE ACCELERATION
>
```

Figure 10-26: Example of response from u (OUTPUT UNIT) command

10.8 f (LP FILTER -3dB FREQUENCY) command

General description: Changes the low-pass filter -3dB frequency for one or all axes.

Note that low pass filter settings should be considered together with sample rate in order to avoid issues with folding due to undersampling. No warnings will be issued by STIM300 if e.g. a high filter bandwidth and a low sample rate have been chosen.

Note that change in filter setting will change the group delay, ref. Table 6-8.

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-25: Available f (LP FILTER -3dB FREQUENCY) commands

| Syntax | Response |
|---------------------------------------|--|
| f<SP><-3dBfreq><CR> | Changes the LP filter -3dB frequency for all sensors and axes |
| f<SP><-3dBfreq>','<sens><CR> | Changes the LP filter -3dB frequency for all axes of a specific sensor |
| f<SP><-3dBfreq>','<sens>','<axis><CR> | Changes the LP filter -3dB frequency for a specified sensor and axis |

Table 10-26: Allowed values for <-3dBfreq> parameter for f (LP FILTER -3dB FREQUENCY) commands

| <-3dBfreq> | Result |
|------------|---|
| 0 | Will change LP filter -3dB frequency to 16Hz |
| 1 | Will change LP filter -3dB frequency to 33Hz |
| 2 | Will change LP filter -3dB frequency to 66Hz |
| 3 | Will change LP filter -3dB frequency to 131Hz |
| 4 | Will change LP filter -3dB frequency to 262Hz |

Table 10-27: Allowed values for <sens> parameter for f (LP FILTER -3dB FREQUENCY) commands

| <sens> | Result |
|--------|---|
| g | Will change LP filter -3dB frequency for the gyro(s) |
| a | Will change LP filter -3dB frequency for the accelerometer(s) |
| i | Will change LP filter -3dB frequency for the inclinometer(s) |
| u | Will change LP filter -3dB frequency for AUX |

Table 10-28: Allowed values for <axis> parameter for f (LP FILTER -3dB FREQUENCY) commands

| <axis> | Result |
|--------|--|
| x | Will change LP filter -3dB frequency for X-axis only |
| y | Will change LP filter -3dB frequency for Y-axis only |
| z | Will change LP filter -3dB frequency for Z-axis only |

Table 10-29: Error messages for f (LP FILTER -3dB FREQUENCY) commands

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```
>f 2,a,x
ACCELEROMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 66
>
```

Figure 10-27: Example of response from f (LP FILTER -3dB FREQUENCY) command

```
>f 3
GYRO LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 131
GYRO LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 131
GYRO LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 131
ACCELEROMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 131
ACCELEROMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 131
ACCELEROMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 131
INCLINOMETER LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 131
INCLINOMETER LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 131
INCLINOMETER LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 131
AUX LP FILTER -3dB FREQUENCY [Hz] = 131
```

```
>
```

Figure 10-28: Example of response from f (LP FILTER -3dB FREQUENCY) command

```
>f 1,g
GYRO LP FILTER -3dB FREQUENCY, X-AXIS [Hz] = 33
GYRO LP FILTER -3dB FREQUENCY, Y-AXIS [Hz] = 33
GYRO LP FILTER -3dB FREQUENCY, Z-AXIS [Hz] = 33
```

```
>
```

Figure 10-29: Example of response from f (LP FILTER -3dB FREQUENCY) command

```
>f 0,u
AUX LP FILTER -3dB FREQUENCY [Hz] = 16
```

```
>
```

Figure 10-30: Example of response from f (LP FILTER -3dB FREQUENCY) command

10.9 m (SAMPLE RATE) command

General description: Changes the sample rate in Normal Mode. The sample rate is the same for all channels.

Note that the sample rate could be considered invalid, even if it has been entered correctly. This is because a valid sample rate also depends on the sample rate and chosen datagram content (ref. Table 6-9 and error message E007 in Table 10-32).

Note that sample rate should be considered together with filter settings in order to avoid issues with folding due to undersampling. No warnings will be issued by STIM300 if e.g. a high filter bandwidth and a low sample rate have been chosen.

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-30: Available m (SAMPLE RATE) command

| Syntax | Response |
|-----------------------|--|
| m<SP><sampl.rate><CR> | Changes the sample rate in Normal Mode |

Table 10-31: Allowed values for <sampl.rate> parameter for m (SAMPLE RATE) command

| <sampl.rate> | Result |
|--------------|--|
| 0 | Will set sample rate to 125 samples /second |
| 1 | Will set sample rate to 250 samples /second |
| 2 | Will set sample rate to 500 samples /second |
| 3 | Will set sample rate to 1000 samples /second |
| 4 | Will set sample rate to 2000 samples /second |
| 5 | Will set sample to External Trigger |

Table 10-32: Error messages for m (SAMPLE RATE) command

| Error | Message | Possible reason |
|-------|---------------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |
| E007 | DATAGRAM WILL BE TOO LONG TO TRANSMIT | Combination of bit-rate, sample rate and datagram content results in a datagram that cannot be transmitted |

```
>m 2
SAMPLE RATE [samples/s] = 500
>
```

Figure 10-31: Example of response from m (SAMPLE RATE) command

```
>m 5
SAMPLE RATE = EXTERNAL TRIGGER
>
```

Figure 10-32: Example of response from m (SAMPLE RATE) command

10.10 k (AUX COMP) command

General description: Changes the compensation coefficients of the AUX input.

Note that this change will only be effective until STIM300 is initialized, reset or powered off, unless the new setting has been stored in flash using the SAVE-command (ref. chapter 10.11). In order to use or test a new setting in Normal Mode without permanently storing it, this can be achieved by using the EXIT n-command (ref. chapter 10.13).

Table 10-33: Available k (AUX COMP) command

| Syntax | Response |
|----------------------------|--|
| k <SP><A>','<CR> | Changes the compensation coefficients, A and B, of the AUX input |

<A> and are numbers. Decimal point = '.'. Format can be integer, scientific or decimal.

Table 10-34: Error messages for k (AUX COMP) command

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |

```

>k 1.02,3.4e-2
AUX COMP COEFF: A = 1.0200000e+00, B = 3.4000000e-02
>
```

Figure 10-33: Example of response from e (AUX COMP) command

10.11 g (GYRO G-COMP) command

General description: Changes the compensation parameters for the gyro g-compensation of bias and/or scale-factor. Refer to section 8.5.2.2.6 for a description of this functionality.

Table 10-35: Available g (GYRO G-COMP) commands

| Syntax | Response |
|---|--|
| g<SP><StdComp><CR> | Changes the gyro g-compensation to one of the defined standard configurations. The cut-off frequency of the g-compensation LP-filter will be set to 0.01Hz. Gyro g-compensation will be applied to all axes. |
| g<SP><StdComp>','<FilterCutoff><CR> | Changes the gyro g-compensation to one of the defined standard configurations, but sets the g-compensation LP-filter to a non-standard cut-off frequency. Gyro g-compensation will be applied to all axes. |
| g<SP><BiasSource>','<BiasFilter>','<ScaleSource>','<ScaleFilter><CR> | Changes the gyro g-compensation to a user-defined gyro g-compensation configuration, but leaves the g-compensation LP-filter unchanged. Gyro g-compensation will be applied to all axes. |
| g<SP><BiasSource>','<BiasFilter>','<ScaleSource>','<ScaleFilter>','<FilterCutoff><CR> | Changes the gyro g-compensation to a user-defined gyro g-compensation configuration, including the g-compensation LP-filter. Gyro g-compensation will be applied to all axes. |
| g<SP><Xonoff>','<Yonoff>','<Zonoff>','<BiasSource>','<BiasFilter>','<ScaleSource>','<ScaleFilter><CR> | Changes the gyro g-compensation to a user-defined gyro g-compensation configuration, but leaves the g-compensation LP-filter unchanged. Gyro g-compensation will be applied to specific axes. |
| g<SP><Xonoff>','<Yonoff>','<Zonoff>','<BiasSource>','<BiasFilter>','<ScaleSource>','<ScaleFilter>','<FilterCutoff><CR> | Changes the gyro g-compensation to a user-defined gyro g-compensation configuration, including the g-compensation LP-filter. Gyro g-compensation will be applied to specific axes. |

Table 10-36 : Allowed values for <StdComp> for g (GYRO G-COMP) command

| <StdComp> | Bias | | | |
|-----------------|------------|------------|-------------|-------------|
| | BiasSource | BiasFilter | ScaleSource | ScaleFilter |
| 0 | OFF | - | OFF | - |
| 1 ¹⁾ | OFF | - | ACC | OFF |
| 2 | OFF | - | ACC | ON |
| 3 ¹⁾ | ACC | OFF | OFF | - |
| 4 | ACC | ON | OFF | - |
| 5 ¹⁾ | INC | OFF | OFF | - |
| 6 | INC | ON | OFF | - |
| 7 ¹⁾ | ACC | OFF | ACC | OFF |
| 8 ¹⁾ | ACC | ON | ACC | OFF |
| 9 ¹⁾ | INC | OFF | ACC | OFF |
| a ¹⁾ | INC | ON | ACC | OFF |
| b | ACC | ON | ACC | ON |
| c | INC | ON | INC | ON |

¹⁾ A warning will be issued if gyro output unit has not been chosen as delayed (ref. section 8.5.2.2.1 and 10.7)

Table 10-37 : Allowed range for <FilterCutoff> for g (GYRO G-COMP) command

| | Unit | Minimum | Standard | Maximum |
|----------------|------|---------|----------|---------|
| <FilterCutoff> | Hz | 0.001 | 0.01 | 5.00 |

Decimal point = '.'. Format can be integer, scientific or decimal.

Table 10-38 : Allowed values for <ScaleSource> and <BiasSource> for g (GYRO G-COMP) command

| <BiasSource> <ScaleSource> | Result |
|-------------------------------|---|
| 0 | Gyro g-compensation turned OFF |
| 1 | Gyro g-compensation uses data from accelerometers |
| 2 | Gyro g-compensation uses data from inclinometers |

Table 10-39 : Allowed values for <ScaleFilter> and <BiasFilter> for g (GYRO G-COMP) command

| <BiasFilter> <ScaleFilter> | Result |
|-------------------------------|---|
| 0 | Gyro g-compensation LP-filter not applied (OFF) |
| 1 | Gyro g-compensation LP-filter applied (ON) |

Table 10-40 : Allowed values for <Xonoff>, <Yonoff> and <Zonoff> for g (GYRO G-COMP) command

| <Xonoff> <Yonoff> <Zonoff> | Result |
|----------------------------------|--|
| 0 | Gyro g-compensation is not applied to specific axis (OFF) |
| 1 | Gyro g-compensation is applied to specific axis (ACC or INC) |

Table 10-41: Error messages for g (GYRO G-COMP) command

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```

>g 1
GYRO G-COMPENSATION:
BIAS SOURCE, X-AXIS = OFF
BIAS G-COMP LP-FILTER, X-AXIS = NA
SCALE SOURCE, X-AXIS = ACC
SCALE G-COMP LP-FILTER, X-AXIS = OFF
BIAS SOURCE, Y-AXIS = OFF
BIAS G-COMP LP-FILTER, Y-AXIS = NA
SCALE SOURCE, Y-AXIS = ACC
SCALE G-COMP LP-FILTER, Y-AXIS = OFF
BIAS SOURCE, Z-AXIS = OFF
BIAS G-COMP LP-FILTER, Z-AXIS = NA
SCALE SOURCE, Z-AXIS = ACC
SCALE G-COMP LP-FILTER, Z-AXIS = OFF
G-COMP LP-FILTER CUTOFF = 0.010 HZ
>

```

Figure 10-34: Example of response from g (GYRO G-COMP) command

```

>g 8,0,3
GYRO G-COMPENSATION: WARNING: DELAYED GYRO OUTPUT UNIT IS RECOMMENDED
BIAS SOURCE, X-AXIS = ACC
BIAS G-COMP LP-FILTER, X-AXIS = ON
SCALE SOURCE, X-AXIS = ACC
SCALE G-COMP LP-FILTER, X-AXIS = OFF
BIAS SOURCE, Y-AXIS = ACC
BIAS G-COMP LP-FILTER, Y-AXIS = ON
SCALE SOURCE, Y-AXIS = ACC
SCALE G-COMP LP-FILTER, Y-AXIS = OFF
BIAS SOURCE, Z-AXIS = ACC
BIAS G-COMP LP-FILTER, Z-AXIS = ON
SCALE SOURCE, Z-AXIS = ACC
SCALE G-COMP LP-FILTER, Z-AXIS = OFF
G-COMP LP-FILTER CUTOFF = 0.300 HZ
>

```

Figure 10-35: Example of response from g (GYRO G-COMP) command with warning

```

>g 2,1,1,0,0.5
GYRO G-COMPENSATION:
BIAS SOURCE, X-AXIS = INC
BIAS G-COMP LP-FILTER, X-AXIS = ON
SCALE SOURCE, X-AXIS = ACC
SCALE G-COMP LP-FILTER, X-AXIS = OFF
BIAS SOURCE, Y-AXIS = INC
BIAS G-COMP LP-FILTER, Y-AXIS = ON
SCALE SOURCE, Y-AXIS = ACC
SCALE G-COMP LP-FILTER, Y-AXIS = OFF
BIAS SOURCE, Z-AXIS = INC
BIAS G-COMP LP-FILTER, Z-AXIS = ON
SCALE SOURCE, Z-AXIS = ACC
SCALE G-COMP LP-FILTER, Z-AXIS = OFF
G-COMP LP-FILTER CUTOFF = 0.500 HZ
>

```

Figure 10-36: Example of response from g (GYRO G-COMP) command

```

>g 0,0,1,2,1,1,0
GYRO G-COMPENSATION:
BIAS SOURCE, X-AXIS = OFF
BIAS G-COMP LP-FILTER, X-AXIS = NA
SCALE SOURCE, X-AXIS = OFF
SCALE G-COMP LP-FILTER, X-AXIS = NA
BIAS SOURCE, Y-AXIS = OFF
BIAS G-COMP LP-FILTER, Y-AXIS = NA
SCALE SOURCE, Y-AXIS = OFF
SCALE G-COMP LP-FILTER, Y-AXIS = NA
BIAS SOURCE, Z-AXIS = INC
BIAS G-COMP LP-FILTER, Z-AXIS = ON
SCALE SOURCE, Z-AXIS = ACC
SCALE G-COMP LP-FILTER, Z-AXIS = OFF
G-COMP LP-FILTER CUTOFF = 0.500 HZ
>

```

Figure 10-37: Example of response from g (GYRO G-COMP) command

10.12 s (SAVE) command

General description: Saves configuration parameters to flash. This will permanently change the configuration parameters and hence be valid after an initialisation or power-off.

The flash used in STIM300 is specified to be capable of minimum 1000 saves. A save-counter has been implemented and when the number of saves exceeds 1000, there will be issued a warning. STIM300 will always attempt to save the configuration when receiving the s (SAVE) command regardless of the content of the save-counter.

Table 10-42: Available s (SAVE) command

| Syntax | Response |
|--------|---|
| s<CR> | Saves system parameters to flash. This command will require an additional confirmation prior to execution. Confirmation ("Y") to be responded in upper case letter. |

Table 10-43: Error messages for s (SAVE) command

| Error | Message | Possible reason |
|-------|----------------------------------|---|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Any characters between command and <CR> |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |
| E004 | EXCEEDED MAXIMUM NUMBER OF SAVES | Warning appears when maximum number of saves has been exceeded (1000 saves). STIM300 will always attempt to save the configuration when receiving the s (SAVE)-command. |
| E005 | ERROR DURING SAVE | System parameters not successfully transferred to flash |

```
>s
SYSTEM PARAMETERS WILL BE PERMANENTLY CHANGED. CONFIRM SAVE(Y/N): Y
SYSTEM PARAMETERS SUCCESSFULLY STORED IN FLASH.
NUMBER OF SAVES = 26
>
```

Figure 10-38: Example of response from s (SAVE) command when confirming save

```
>s
SYSTEM PARAMETERS WILL BE PERMANENTLY CHANGED. CONFIRM SAVE(Y/N): N
SAVE COMMAND ABORTED.
>
```

Figure 10-39: Example of response from s (SAVE) command when not confirming save

```
>s
SYSTEM PARAMETERS WILL BE PERMANENTLY CHANGED. CONFIRM SAVE(Y/N): y
SAVE COMMAND ABORTED.

E003 INVALID PARAMETER
>
```

Figure 10-40: Example of response from s (SAVE) command when not correctly responding to confirmation

10.13 x (EXIT) command

General description: Terminates Service Mode and returns to Normal Mode directly or via Init Mode (ref. Figure 8-6).

Table 10-44 : Available x (EXIT) command

| Syntax | Response |
|--------------------|-------------------------|
| x<SP><exit_to><CR> | Terminates Service Mode |

Table 10-45 : Allowed values for <exit_to> for x (EXIT) command

| <exit_to> | Result |
|-----------|---|
| n | Terminates Service Mode and return to Normal Mode. If system parameters have been changed compared to flash content, a confirmation is requested before exiting to Normal Mode ("Y" in upper case letter). There will be a 3 seconds hold-time between the transmitted command response and execution of the EXIT-command. |
| i | Terminates Service Mode and return to Init Mode. If system parameters have been changed compared to flash content, a confirmation is requested before exiting to Normal Mode ("Y" in upper case letter). There will be a 3 seconds hold-time between the transmitted command response and execution of the EXIT-command. NB: Changes made to system parameters, but not saved, will be overwritten by the data already stored in flash when entering Init Mode. |
| N | Terminates Service Mode and return immediately to Normal Mode (without confirmation if system parameters have been changed compared to flash and without any hold-time) |
| I | Terminates Service Mode and return immediately to Init Mode (without confirmation if system parameters have been changed compared to flash and without any hold-time). NB: Changes made to system parameters, but not saved, will be overwritten by the data already stored in flash when entering Init Mode. |

Table 10-46: Error messages for x (EXIT) command

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```
>x n
SYSTEM RETURNING TO NORMAL MODE.
```

Figure 10-41: Example of response from x n (EXIT) command when system parameters match contents of flash

```
>x i
SYSTEM RETURNING TO INIT MODE.
```

Figure 10-42: Example of response from x i (EXIT) command when system parameters match contents of flash

```
>x n
CURRENT SYSTEM PARAMETERS DO NOT MATCH FLASH CONTENT. CONFIRM EXIT(Y/N): Y
SYSTEM RETURNING TO NORMAL MODE.
```

Figure 10-43: Example of response from x n (EXIT) command after system parameters have been changed but not saved with confirmed EXIT

```
>x i
CURRENT SYSTEM PARAMETERS DO NOT MATCH FLASH CONTENT. CONFIRM EXIT(Y/N): N
>
```

Figure 10-44: Example of response from x i (EXIT) command after system parameters have been changed but not saved with confirmed not to EXIT

```
>x n
CURRENT SYSTEM PARAMETERS DOES NOT MATCH FLASH CONTENT. CONFIRM EXIT(Y/N): n

E003 INVALID PARAMETER

>
```

Figure 10-45: Example of response from x n (EXIT) command after system parameters have been changed but not saved with incorrect response to confirmation.

10.14 z (RESTORE TO FACTORY SETTINGS) command

General description: Restores the configuration of the unit to its factory settings.

Table 10-47: Available z (RESTORE TO FACTORY SETTINGS) commands

| Syntax | Response |
|--------|--|
| z<CR> | Restores the configuration of the unit to its factory settings. NB: The restored configuration will not be permanent unless it is SAVED to flash before EXITing Service Mode, resetting the unit or turning off power. |

Table 10-48: Error messages for z (RESTOR TO FACTORY SETTINGS) command

| Error | Message | Possible reason |
|-------|--------------------------------|---|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Any characters between command and <CR> |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```
>z
RESTORE TO FACTORY SETTINGS.
CONFIRM CHANGE TO FACTORY SETTINGS (Y/N): Y

APPLYING FACTORY SETTINGS
FACTORY SETTINGS APPLIED. TO PERMANENTLY STORE THE SETTINGS, USE THE SAVE COMMAND.

>
```

Figure 10-46: Example of response from z (RESTORE TO FACTORY SETTINGS) command with no change in transmission parameters.

```
>z
RESTORE TO FACTORY SETTINGS.
CONFIRM CHANGE TO FACTORY SETTINGS(Y/N): Y

TRANSMISSION PARAMETERS WILL BE CHANGED. PLEASE CONFIRM (Y/N): Y
THE TRANSMISSION CONFIGURATION WILL BE CHANGED TO:
TRANSMISSION PROTOCOL = 460800 BITS/S, 2 STOP BIT(S), EVEN PARITY

APPLYING FACTORY SETTINGS
FACTORY SETTINGS APPLIED. TO PERMANENTLY STORE THE SETTINGS, USE THE SAVE COMMAND.

>
```

Figure 10-47: Example of response from z (RESTORE TO FACTORY SETTINGS) command with change in transmission parameters.

10.15 ? (HELP) command

General description: Help function on the available commands in Service Mode.

Table 10-49: Available ? (HELP) commands

| Syntax | Response |
|----------------|--|
| ?<CR> | Lists the available parameters for this command |
| ?<SP><hlp><CR> | Responds with information on the specified command |

Table 10-50: Allowed values for <hlp> for ? (HELP) command

| <hlp> | Result |
|-------|--|
| i | Responds with information on the INFORMATION-command |
| a | Responds with information on the SINGLE-SHOT MEASUREMENT-command |
| c | Responds with information on the DIAGNOSTIC-command |
| d | Responds with information on the DATAGRAM FORMAT-command |
| t | Responds with information on the TRANSMISSION PARAMETERS-command |
| r | Responds with information on the LINE TERMINATION-command |
| u | Responds with information on the OUTPUT UNIT-command |
| f | Responds with information on the LP FILTER -3dB FREQUENCY-command |
| m | Responds with information on the SAMPLE RATE-command |
| g | Responds with information on the GYRO G-COMP-command |
| k | Responds with information on the AUX COMP-command |
| s | Responds with information on the SAVE-command |
| x | Responds with information on the EXIT-command |
| z | Responds with information on the RESTORE TO FACTORY SETTINGS-command |

Table 10-51: Error messages for ? (HELP) commands

| Error | Message | Possible reason |
|-------|--------------------------------|--|
| E001 | UNKOWN COMMAND | Command is incorrectly entered |
| E002 | INCORRECT NUMBER OF PARAMETERS | Too many or too few parameters, use of comma between command and first parameter |
| E003 | INVALID PARAMETER | Value of parameter outside valid range |

```

>?
AVAILABLE PARAMETERS:
i: LISTS SPECIFIC INFORMATION
a: PERFORMS A SINGLE-SHOT MEASUREMENT
c: PERFORMS A DIAGNOSTIC OF THE UNIT
d: CHANGES DATAGRAM FORMAT
t : CHANGES TRANSMISSION PARAMETERS
r: CHANGES THE LINE TERMINATION
u : CHANGES OUTPUT UNIT
f: CHANGES LP FILTER -3DB FREQUENCY
m: CHANGES SAMPLE RATE
g: CHANGES CONFIGURATION OF GYRO G-COMPENSATION
k: CHANGES COMPENSATION COEFFICIENTS FOR AUX INPUT
s: SAVES CONFIGURATION DATA
x: EXITS SERVICE MODE
z: RESTORES FACTORY SETTINGS

>

```

Figure 10-48: Example of response from ? (HELP) command

```
>? i
i: LISTS THE PRODUCT CONFIGURATION DATA
i s: RETURNS THE SERIAL NUMBER
i n: RETURNS THE PRODUCT NAME
i x: RETURNS THE PART NUMBER
i a: RETURNS THE AXIS CONFIGURATION
i p: RETURNS THE FW CONFIGURATION AND REVISION
i m: RETURNS THE SAMPLE RATE
i f: RETURNS THE LP FILTER -3DB FREQUENCY
i d: RETURNS THE DATAGRAM FORMAT
i t: RETURNS THE TRANSMISSION PARAMETERS
i r: RETURNS THE LINE TERMINATION SETTING
i u: RETURNS THE OUTPUT UNIT
i g: RETURNS THE CONFIGURATION OF GYRO G-COMPENSATION
i k: RETURNS THE COMPENSATION COEFFICIENTS OF AUX INPUT
i e: PRINTS THE EXTENDED ERROR INFORMATION FROM THE LAST DETECTED ERROR IN NORMAL MODE

>
```

Figure 10-49: Example of response from ? i (HELP on INFORMATION) command

```
>? a
a: PERFORMS A SINGLE-SHOT MEASUREMENT

>
```

Figure 10-50: Example of response from ? a (HELP ON SINGLE-SHOT MEASUREMENT) command

```
>? c
c: PERFORMS A DIAGNOSTIC OF THE UNIT

>
```

Figure 10-51: Example of response from ? c (HELP on DIAGNOSTIC) command

```
>? d
d <type>','<term>: CHANGES THE DATAGRAM FORMAT
  ALLOWED VALUES FOR <type>:
    0 = ID, RATE, COUNTER, LATENCY, CRC
    1 = ID, RATE, ACCELERATION, COUNTER, LATENCY, CRC
    2 = ID, RATE, INCLINATION, COUNTER, LATENCY, CRC
    3 = ID, RATE, ACCELERATION, INCLINATION, COUNTER, LATENCY, CRC
    4 = ID, RATE, TEMPERATURE, COUNTER, LATENCY, CRC
    5 = ID, RATE, ACCELERATION, TEMPERATURE, COUNTER, LATENCY, CRC
    6 = ID, RATE, INCLINATION, TEMPERATURE, COUNTER, LATENCY, CRC
    7 = ID, RATE, ACCELERATION, INCLINATIONS, TEMPERATURE, COUNTER, LATENCY, CRC
    8 = ID, RATE, AUX, COUNTER, LATENCY, CRC
    9 = ID, RATE, ACCELERATION, AUX, COUNTER, LATENCY, CRC
    A = ID, RATE, INCLINATION, AUX, COUNTER, LATENCY, CRC
    B = ID, RATE, ACCELERATION, INCLINATION, AUX, COUNTER, LATENCY, CRC
    C = ID, RATE, TEMPERATURE, COUNTER, AUX, LATENCY, CRC
    D = ID, RATE, ACCELERATION, AUX, TEMPERATURE, COUNTER, LATENCY, CRC
    E = ID, RATE, INCLINATION, AUX, TEMPERATURE, COUNTER, LATENCY, CRC
    F = ID, RATE, ACCELERATION, INCLINATIONS, TEMPERATURE, AUX, COUNTER, LATENCY, CRC
  ALLOWED VALUES FOR <term>:
    0 = NONE
    1 = <CR><LF>

>
```

Figure 10-52: Example of response from ? d (DATAGRAM TRANSMISSION MODE AND TERMINATION) command

```

>? t
t <bit-rate code>[','<bit-rate>]: CHANGES THE BIT-RATE [bits/s]
t <bit-rate code>[','<bit-rate>'],'<stop bits>','<parity>: CHANGES THE BIT-RATE [bits/s], NUMBER OF STOP-BITS AND PARITY
  ALLOWED VALUES FOR <bit-rate code>:
    0 = 377400
    1 = 460800
    2 = 921600
    3 = 1843200
    f = USER-DEFINED
  <bit-rate> MUST ONLY BE INCLUDED WHEN <bit-rate code> = f
  ALLOWED RANGE FOR <bit-rate>:
    1500 – 5023000 (INTEGER VALUE). SEE STIM300 DATASHEET FOR LIMITATIONS
  ALLOWED VALUES FOR <stop bits>:
    1 = 1
    2 = 2
  ALLOWED VALUES FOR <parity>:
    0 = NONE
    1 = ODD
    2 = EVEN
>
  
```

Figure 10-53: Example of response from ? t (HELP on TRANSMISSION PARAMETERS) command

```

>? r
r <on/off>: TURNS LINE TERMINATION ON OR OFF
  ALLOWED VALUES FOR <on/off>:
    0 = OFF
    1 = ON
>
  
```

Figure 10-54: Example of response from ? r (HELP on LINE TERMINATION) command

```

>? u
u <sens>','<unit>: CHANGES OUTPUT UNIT
  ALLOWED VALUES FOR <sens>:
    g = GYRO
    a = ACCELEROMETER
    i = INCLINOMETER
  ALLOWED VALUES FOR u,g,<unit>:
    0 = ANGULAR RATE
    1 = INCREMENTAL ANGLE
    2 = AVERAGE ANGULAR RATE
    3 = INTEGRATED ANGLE
    8 = ANGULAR RATE - DELAYED
    9 = INCREMENTAL ANGLE - DELAYED
    a = AVERAGE ANGULAR RATE - DELAYED
    b = INTEGRATED ANGLE - DELAYED
  ALLOWED VALUES FOR u,a,<unit>:
    0 = ACCELERATION
    1 = INCREMENTAL VELOCITY
    2 = AVERAGE ACCELERATION
  ALLOWED VALUES FOR u,i,<unit>:
    0 = ACCELERATION
    1 = INCREMENTAL VELOCITY
    2 = AVERAGE ACCELERATION
>
  
```

Figure 10-55: Example of response from ? u (HELP on OUTPUT UNIT) command

```
>? f
f <-3dBfreq>: CHANGES THE LP FILTER -3DB FREQUENCY [Hz] FOR ALL SENSORS AND AXES
f <-3dBfreq>',<sens>: CHANGES THE LP FILTER -3DB FREQUENCY [Hz] FOR ALL AXES OF SPECIFIED SENSOR
f <-3dBfreq>',<sens>',<axis>: CHANGES THE LP FILTER -3DB FREQUENCY [Hz] FOR A SPECIFIC SENSOR AND AXIS
  ALLOWED VALUES FOR <-3dBfreq>:
    0 = 16
    1 = 33
    2 = 66
    3 = 131
    4 = 262
  ALLOWED VALUES FOR <sens>:
    g = GYRO(S)
    a = ACCELEROMETER(S)
    i = INCLINOMETER(S)
    u = AUX
  ALLOWED VALUES FOR <axis>:
    x = X-AXIS
    y = Y-AXIS
    z = Z-AXIS
>
```

Figure 10-56: Example of response from ? f (HELP on LP FILTER -3dB FREQUENCY) command

```
>? m
m <sampl.rate>: CHANGES THE SAMPLE RATE [samples/s]
  ALLOWED VALUES FOR <sampl.rate>
    0 = 125
    1 = 250
    2 = 500
    3 = 1000
    4 = 2000
    5 = EXTERNAL TRIGGER
>
```

Figure 10-57: Example of response from ? m (HELP on SAMPLE RATE) command

```

>? g
g <StdComp>: CHANGES GYRO G-COMP TO A PRE-DEFINED CONFIGURATION
g <StdComp>,<FilterCutoff>: CHANGES GYRO G-COMP TO A PRE-DEFINED CONFIG., BUT SPECIAL LP-FILTER CUTOFF
g <BiasSource>, <BiasFilter>,<ScaleSource>,<ScaleFilter>[,<FilterCutoff>]: CHANGES CONFIGURATION OF GYRO-G-COMP
g <Xonoff><Yonoff><Zonoff><BiasSource>, <BiasFilter>,<ScaleSource>,<ScaleFilter>[,<FilterCutoff>]: CHANGES
CONFIGURATION OF GYRO-G-COMP ON SPECIFIED AXES
  ALLOWED VALUES FOR <StdComp>:
    0 = <BiasSource> = 0, <BiasFilter> = 0, <ScaleSource> = 0, <ScaleFilter> = 0 (NO GYRO G-COMP)
    1 = <BiasSource> = 0, <BiasFilter> = 0, <ScaleSource> = 1, <ScaleFilter> = 0
    2 = <BiasSource> = 0, <BiasFilter> = 0, <ScaleSource> = 1, <ScaleFilter> = 1, <FilterCutoff> = 0.01
    3 = <BiasSource> = 1, <BiasFilter> = 0, <ScaleSource> = 0, <ScaleFilter> = 0
    4 = <BiasSource> = 1, <BiasFilter> = 1, <ScaleSource> = 0, <ScaleFilter> = 0, <FilterCutoff> = 0.01
    5 = <BiasSource> = 2, <BiasFilter> = 0, <ScaleSource> = 0, <ScaleFilter> = 0
    6 = <BiasSource> = 2, <BiasFilter> = 1, <ScaleSource> = 0, <ScaleFilter> = 0, <FilterCutoff> = 0.01
    7 = <BiasSource> = 1, <BiasFilter> = 0, <ScaleSource> = 1, <ScaleFilter> = 0
    8 = <BiasSource> = 1, <BiasFilter> = 1, <ScaleSource> = 1, <ScaleFilter> = 0, <FilterCutoff> = 0.01
    9 = <BiasSource> = 2, <BiasFilter> = 0, <ScaleSource> = 1, <ScaleFilter> = 0
    a = <BiasSource> = 2, <BiasFilter> = 1, <ScaleSource> = 1, <ScaleFilter> = 0, <FilterCutoff> = 0.01
    b = <BiasSource> = 1, <BiasFilter> = 1, <ScaleSource> = 1, <ScaleFilter> = 1, <FilterCutoff> = 0.01
    c = <BiasSource> = 2, <BiasFilter> = 1, <ScaleSource> = 2, <ScaleFilter> = 1, <FilterCutoff> = 0.01
  ALLOWED RANGE FOR <FilterCutoff>
    0.010 – 5.000 (ENTERED VALUE IS IN [Hz])
  ALLOWED VALUES FOR <BiasSource> and <ScaleSource>:
    0 = OFF (NO G-COMP)
    1 = ACCELEROMETER
    2 = INCLINOMETER
  ALLOWED VALUES FOR <BiasFilter> and <ScaleFilter>:
    0 = GYRO G-COMP LP-FILTER NOT IN USE (OFF)
    1 = GYRO G-COMP LP-FILTER IN USE (ON)
  ALLOWED VALUES FOR <Xonoff>, <Yonoff> and <Zonoff>:
    0 = NO GYRO G-COMP FOR SPECIFIC AXIS (OFF)
    1 = GYRO G-COMP FOR SPECIFIC AXIS (ON)
>

```

Figure 10-58: Example of response from ? m (HELP on GYRO G-COMP) command

```

? k
k <coeff1>,'<coeff2>: CHANGES THE AUX COMPENSATE COEFFICIENTS
>

```

Figure 10-59: Example of response from ? k (HELP on AUX COMP) command

```

>? s
s: SAVES SYSTEM PARAMETERS TO FLASH
>

```

Figure 10-60: Example of response from ? s (HELP on SAVE) command

```

>? x
x n: EXITS SERVICE MODE AND RETURNS TO NORMAL MODE
x i: EXITS SERVICE MODE AND RETURNS TO INIT MODE
x N: EXITS SERVICE MODE AND RETURNS IMMEDIATELY TO NORMAL MODE
x I: EXITS SERVICE MODE AND RETURNS IMMEDIATELY TO INIT MODE
NB: NON-STORED SYSTEM PARAMETERS WILL BE OVERWRITTEN BY STORED CONTENT IN FLASH
WHEN EXITING TO INIT MODE
>

```

Figure 10-61: Example of response from ? x (HELP on EXIT) command

```
? z
z: RESTORES FACTORY SETTINGS
>
```

Figure 10-62: Example of response from ? z (HELP on RESTORE TO FACTORY SETTINGS) command

11 MARKING

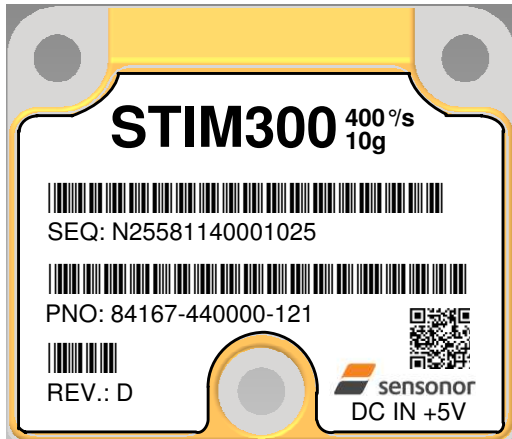


Figure 11-1: Example of marking of STIM300

12 CONFIGURATION / ORDERING INFORMATION

The STIM300 will be delivered according to the configuration code as shown below. All configuration parameters can be changed later in Service Mode, ref. section 8.5.3. A full list of configurable parameters can be found in Table 6-8.

Configuration parameters in **bold** letters show the standard option.

| Range | | Measurement | | | | | | Output/RS422 | | | |
|---------|---|-------------|-------------------|------------------|------------------|-------------------|-------------|--------------|----------|----------|-------------|
| Prod_ID | - | Sample rate | Filter band-width | Gyro output unit | Acc. output unit | Incl. output unit | Gyro g-comp | - | Datagram | Bit-rate | Termination |

| Range | | |
|--------------|---------------|------------|
| Prod_ID | Gyro | Acc |
| 84455 | 400°/s | 2g |
| 84458 | 400°/s | 5g |
| 84167 | 400°/s | 10g |
| 84461 | 400°/s | 30g |
| 84467 | 400°/s | 100g |

| Sample rate: | |
|--------------|-------------------------|
| 0 | = 125 samples/s |
| 1 | = 250 samples/s |
| 2 | = 500 samples/s |
| 3 | = 1000 samples/s |
| 4 | = 2000 samples/s |
| 5 | = External Trigger |

| Filter bandwidth: | |
|-------------------|----------------|
| 0 | = 16Hz |
| 1 | = 33Hz |
| 2 | = 66Hz |
| 3 | = 131Hz |
| 4 | = 262Hz |

| Gyro output unit: | |
|-------------------|--|
| 0 | = Angular Rate [°/s] |
| 1 | = Incremental Angle [°/sample] |
| 2 | = Average Angular Rate [°/s] |
| 3 | = Integrated Angle [°] |
| 8 | = Angular Rate [°/s] – delayed |
| 9 | = Incremental Angle [°/sample] – delayed |
| a | = Average Angular Rate [°/s] – delayed |
| b | = Integrated Angle [°] - delayed |

| Acc. output unit: | |
|-------------------|-------------------------------------|
| 0 | = Acceleration [g] |
| 1 | = Incremental Velocity [m/s/sample] |
| 2 | = Average Acceleration [g] |

| Incl. output unit: | |
|--------------------|-------------------------------------|
| 0 | = Acceleration [g] |
| 1 | = Incremental Velocity [m/s/sample] |
| 2 | = Average Acceleration [g] |

| Gyro g-comp | | | | |
|-----------------|------------|---------------|--------------|---------------|
| | Bias | | Scale-factor | |
| | Source | 0.01Hz-filter | Source | 0.01Hz-filter |
| 0 | OFF | - | OFF | - |
| 1 ¹⁾ | OFF | - | ACC | OFF |
| 2 | OFF | - | ACC | ON |
| 3 ¹⁾ | ACC | OFF | OFF | - |
| 4 | ACC | ON | OFF | - |
| 5 ¹⁾ | INC | OFF | OFF | - |
| 6 | INC | ON | OFF | - |
| 7 ¹⁾ | ACC | OFF | ACC | OFF |
| 8 ¹⁾ | ACC | ON | ACC | OFF |
| 9 ¹⁾ | INC | OFF | ACC | OFF |
| a ¹⁾ | INC | ON | ACC | OFF |
| b | ACC | ON | ACC | ON |
| c | INC | ON | INC | ON |

| Datagram | | | | | |
|----------|---------------|--------------|-------------|-------------|-----------|
| | Included data | | | | |
| | Rate | Acceleration | Inclination | Temperature | AUX |
| 0 | YES | NO | NO | NO | NO |
| 1 | YES | YES | NO | NO | NO |
| 2 | YES | NO | YES | NO | NO |
| 3 | YES | YES | YES | NO | NO |
| 4 | YES | NO | NO | YES | NO |
| 5 | YES | YES | NO | YES | NO |
| 6 | YES | NO | YES | YES | NO |
| 7 | YES | YES | YES | YES | NO |
| 8 | YES | NO | NO | NO | YES |
| 9 | YES | YES | NO | NO | YES |
| a | YES | NO | YES | NO | YES |
| b | YES | YES | YES | NO | YES |
| c | YES | NO | NO | YES | YES |
| d | YES | YES | NO | YES | YES |
| e | YES | NO | YES | YES | YES |
| f | YES | YES | YES | YES | YES |

| Bit-rate: | |
|-----------|------------------------------|
| 0 | = 374400 bits/s |
| 1 | = 460800 bits/s |
| 2 | = 921600 bits/s |
| 3 | = 1843200 bits/s |
| f | = User-defined ²⁾ |

| Termination | | |
|-------------|-----------|-------------|
| | Line | Datagram |
| 0 | OFF | None |
| 1 | ON | None |
| 2 | OFF | <CR><LF> |
| 3 | ON | <CR><LF> |

- 1) Delayed gyro output unit should be selected with this option
 2) Bit-rate must be specified. See section 10.5 for limitations

Example: 84167-413020-330 has the following configuration:

- Gyro range = 400°/s, accelerometer range = 10g
- Sample rate = 2000 samples/s
- Low-pass filter bandwidth = 33Hz
- Gyro output unit = Integrated Angle [°]
- Accelerometer output unit = Acceleration [g]
- Inclinometer output unit = Average Acceleration [g]
- No g-/acc-compensation of bias and scale-factor
- Datagram containing Rate, Acceleration and Inclination
- Bit-rate = 1843200 bits/s
- Datagram Termination = None
- Line termination OFF

NOTES

Information furnished by Sensoror is believed to be accurate and reliable. However, no responsibility is assumed by Sensoror for its use, nor for any infringements of patents or other rights of third parties that may result from its use. Sensoror reserves the right to make changes without further notice to any products herein. Sensoror makes no warranty, representation or guarantee regarding the suitability of its products for any particular purpose, nor does Sensoror assume any liability arising out of the application or use of any product or circuit, and specifically disclaims any and all liability, including without limitation consequential or incidental damages. No license is granted by implication or otherwise under any patent or patent rights of Sensoror. Trademarks and registered trademarks are the property of their respective owners. Sensoror products are not intended for any application in which the failure of the Sensoror product could create a situation where personal injury or death may occur. Should Buyer purchase or use Sensoror products for any such unintended or unauthorized application, Buyer shall indemnify and hold Sensoror and its officers, employees, subsidiaries, affiliates, and distributors harmless against all claims, costs, damages, and expenses, and reasonable legal fees arising out of, directly or indirectly, any claim of personal injury or death associated with such unintended or unauthorized use, even if such claim alleges that Sensoror was negligent regarding the design or manufacture of the part.

Sensoror AS

Phone: +47 3303 5000 - Fax: +47 3303 5005

sales@sensoror.comwww.sensoror.com