

## FEATURES

- Triaxial digital gyroscope with digital range scaling**  
 $\pm 250^\circ/\text{sec}$ ,  $\pm 500^\circ/\text{sec}$ ,  $\pm 1000^\circ/\text{sec}$  settings  
 Axis-to-axis alignment,  $<0.05^\circ$
- Triaxial digital accelerometer,  $\pm 18 g$  minimum**
- Triaxial digital magnetometer,  $\pm 1.9$  gauss minimum**
- Digital barometer, 10 mbar to 1200 mbar**  
 Calibrated pressure range: 300 mbar to 1100 mbar
- Autonomous operation and data collection**  
 No external configuration commands required  
 192 ms start-up time
- Factory calibrated sensitivity, bias, and axial alignment**  
 Calibration temperature range:  $-40^\circ\text{C}$  to  $+70^\circ\text{C}$
- SPI-compatible serial interface**
- Embedded temperature sensor**
- Programmable operation and control**  
 Automatic and manual bias correction controls  
 Bartlett window FIR length, number of taps  
 Digital I/O: data ready, alarm indicator, general-purpose  
 Alarms for condition monitoring  
 Enable external sample clock input up to 1.1 kHz  
 Single command self test
- Single-supply operation: 3.15 V to 3.45 V**
- 2000 g shock survivability**
- Operating temperature range:  $-40^\circ\text{C}$  to  $+85^\circ\text{C}$**

## APPLICATIONS

- Platform stabilization and control
- Navigation
- Robotics

## GENERAL DESCRIPTION

The **ADIS16448** *iSensor*® device is a complete inertial system that includes a triaxial gyroscope, a triaxial accelerometer, a triaxial magnetometer, and pressure sensors. Each sensor in the **ADIS16448** combines industry-leading *iMEMS*® technology with signal conditioning that optimizes dynamic performance. The factory calibration characterizes each sensor for sensitivity, bias, alignment, and linear acceleration (gyroscope bias). As a result, each sensor has its own dynamic compensation formulas that provide accurate sensor measurements.

The **ADIS16448** provides a simple, cost-effective method for integrating accurate, multi-axis inertial sensing into industrial systems, especially when compared with the complexity and investment associated with discrete designs. All necessary motion testing and calibration are part of the production process at the factory, greatly reducing system integration time. Tight orthogonal alignment simplifies inertial frame alignment in navigation systems. The SPI and register structures provide a simple interface for data collection and configuration control.

The **ADIS16448** has a compatible pinout for systems that currently use other Analog Devices, Inc., IMU products (**ADIS163xx/ADIS164xx**). The **ADIS16448** is packaged in a module that is approximately 24.1 mm  $\times$  37.7 mm  $\times$  10.8 mm and has a standard connector interface.

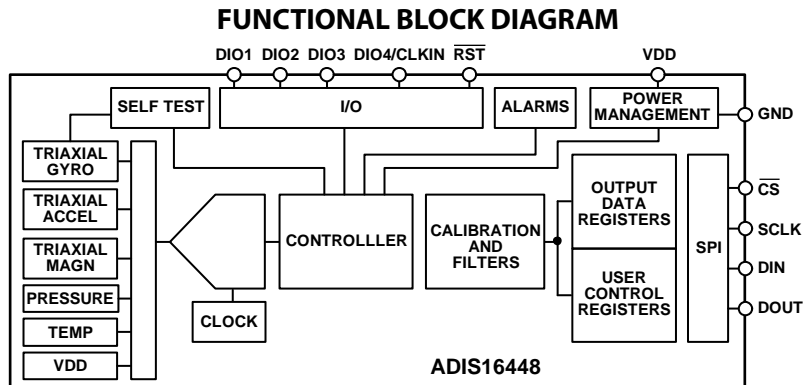


Figure 1.

### Rev. 0

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## REVISION HISTORY

8/12—Revision 0: Initial Version

## SPECIFICATIONS

$T_A = 25^\circ\text{C}$ ,  $V_{DD} = 3.3\text{ V}$ , angular rate =  $0^\circ/\text{sec}$ , dynamic range =  $\pm 1000^\circ/\text{sec} \pm 1\text{ g}$ , unless otherwise noted.

Table 1.

Parameter	Test Conditions/Comments	Min	Typ	Max	Unit
<b>GYROSCOPES</b>					
Dynamic Range		$\pm 1000$	$\pm 1200$		$^\circ/\text{sec}$
Initial Sensitivity	$\pm 1000^\circ/\text{sec}$ , see Table 12	0.0396	0.04	0.0404	$^\circ/\text{sec}/\text{LSB}$
	$\pm 500^\circ/\text{sec}$ , see Table 12	0.0198	0.02	0.0202	$^\circ/\text{sec}/\text{LSB}$
	$\pm 250^\circ/\text{sec}$ , see Table 12	0.0099	0.01	0.0101	$^\circ/\text{sec}/\text{LSB}$
Sensitivity Temperature Coefficient	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		$\pm 40$		$\text{ppm}/^\circ\text{C}$
Misalignment	Axis to axis		$\pm 0.05$		Degrees
	Axis to frame (package)		$\pm 0.5$		Degrees
Nonlinearity	Best fit straight line		$\pm 0.1$		% of FS
Initial Bias Error			0.5		$^\circ/\text{sec}$
In-Run Bias Stability	$1\sigma$ , $\text{SMPL\_PRD} = 0x0001$		14.5		$^\circ/\text{hr}$
Angular Random Walk	$1\sigma$ , $\text{SMPL\_PRD} = 0x0001$		0.66		$^\circ/\sqrt{\text{hr}}$
Bias Temperature Coefficient	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		0.005		$^\circ/\text{sec}/^\circ\text{C}$
Linear Acceleration Effect on Bias	Any axis, $1\sigma$ ( $\text{MSC\_CTRL}[6] = 1$ )		0.015		$^\circ/\text{sec}/\text{g}$
Bias Supply Sensitivity	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		0.2		$^\circ/\text{sec}/\text{V}$
Output Noise	$\pm 1000^\circ/\text{sec}$ range, no filtering		0.27		$^\circ/\text{sec rms}$
Rate Noise Density	$f = 25\text{ Hz}$ , $\pm 1000^\circ/\text{sec}$ range, no filtering		0.0135		$^\circ/\text{sec}/\sqrt{\text{Hz rms}}$
-3 dB Bandwidth			330		Hz
Sensor Resonant Frequency			17.5		kHz
<b>ACCELEROMETERS</b>					
Dynamic Range	Each axis	$\pm 18$			$g$
Initial Sensitivity	See Table 16 for data format	0.825	0.833	0.842	$\text{mg}/\text{LSB}$
Sensitivity Temperature Coefficient	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		$\pm 40$		$\text{ppm}/^\circ\text{C}$
Misalignment	Axis to axis		0.2		Degrees
	Axis to frame (package)		$\pm 0.5$		Degrees
Nonlinearity	Best fit straight line		0.2		% of FS
Initial Bias Error			20		$\text{mg}$
In-Run Bias Stability	$1\sigma$ , $\text{SMPL\_PRD} = 0x0001$		0.25		$\text{mg}$
Velocity Random Walk	$1\sigma$ , $\text{SMPL\_PRD} = 0x0001$		0.11		$\text{m}/\text{sec}/\sqrt{\text{hr}}$
Bias Temperature Coefficient	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		$\pm 0.15$		$\text{mg}/^\circ\text{C}$
Bias Supply Sensitivity	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		5		$\text{mg}/\text{V}$
Output Noise	No filtering		5.1		$\text{mg rms}$
Noise Density	No filtering		0.23		$\text{mg}/\sqrt{\text{Hz rms}}$
-3 dB Bandwidth			330		Hz
Sensor Resonant Frequency			5.5		kHz
<b>MAGNETOMETERS</b>					
Dynamic Range		$\pm 1.9$			gauss
Initial Sensitivity	$25^\circ\text{C}$ , see Table 20 for data format	140.04	142.9	145.76	$\mu\text{gauss}/\text{LSB}$
Sensitivity Temperature Coefficient	Relative to $25^\circ\text{C}$ , $1\sigma$		800		$\text{ppm}/^\circ\text{C}$
Misalignment	Axis to axis		0.25		Degrees
	Axis to frame (package)		0.5		Degrees
Nonlinearity	Best fit straight line		0.1		% of FS
Initial Bias Error	$25^\circ\text{C}$ , 0 gauss stimulus		$\pm 4$		$\text{mgauss}$
Bias Temperature Coefficient	$-40^\circ\text{C} \leq T_A \leq +70^\circ\text{C}$		0.11		$\text{mgauss}/^\circ\text{C}$
Output Noise	$25^\circ\text{C}$ , no filtering, rms		2.4		$\text{mgauss}$
Noise Density	$25^\circ\text{C}$ , no filtering, rms		0.4		$\text{mgauss}/\sqrt{\text{Hz}}$
Bandwidth	-3 dB		25		Hz

Parameter	Test Conditions/Comments	Min	Typ	Max	Unit
TEMPERATURE					
Sensitivity	See Table 23		0.07386		°C/LSB
BAROMETERS					
Pressure Range, Operating		300		1100	mbar
Pressure Range Extended <sup>1</sup>		10		1200	mbar
Sensitivity			0.02		mbar/LSB
Voltage Dependence			0.18		%/V
Bias Supply Voltage Sensitivity			3.24		mbar/V
Total Error	25°C, 300 mbar to 1100 mbar		1.5		mbar
Relative Error <sup>2</sup>	-40°C to +85°C, 300 mbar to 1100 mbar		2.5		mbar
Linearity <sup>3</sup>	25°C, 300 mbar to 1100 mbar		0.1		% of FS
	-40°C to +85°C, 300 mbar to 1100 mbar		0.2		% of FS
Noise			0.08		mbar rms
LOGIC INPUTS <sup>4</sup>					
Input High Voltage, V <sub>IH</sub>		2.0			V
Input Low Voltage, V <sub>IL</sub>				0.8	V
Logic 1 Input Current, I <sub>IH</sub>	V <sub>IH</sub> = 3.3 V		±0.2	±10	µA
Logic 0 Input Current, I <sub>IL</sub>	V <sub>IL</sub> = 0 V				µA
All Pins Except $\overline{\text{RST}}$			40	60	µA
$\overline{\text{RST}}$ Pin			1		mA
Input Capacitance, C <sub>IN</sub>			10		pF
DIGITAL OUTPUTS <sup>4</sup>					
Output High Voltage, V <sub>OH</sub>	I <sub>SOURCE</sub> = 1.6 mA	2.4			V
Output Low Voltage, V <sub>OL</sub>	I <sub>SINK</sub> = 1.6 mA			0.4	V
FLASH MEMORY					
Data Retention <sup>6</sup>	Endurance <sup>5</sup> T <sub>J</sub> = 85°C	10,000 20			Cycles Years
FUNCTIONAL TIMES <sup>7</sup>	Time until new data is available				
Power-On Start-Up Time			192		ms
Reset Recovery Time			77		ms
Flash Memory Back-Up Time			75		ms
Flash Memory Test Time			20		ms
Automatic Self-Test Time	SMPL_PRD = 0x0001		30		ms
CONVERSION RATE					
xGYRO_OUT, xACCL_OUT	SMPL_PRD = 0x0001		819.2		SPS
xMAGN_OUT, BARO_OUT <sup>8</sup>	SMPL_PRD = 0x0001		51.2		SPS
Clock Accuracy				±3	%
Sync Input Clock <sup>9</sup>		0.8		1.1	kHz
POWER SUPPLY					
Power Supply Current	Operating voltage range, VDD	3.15	3.3	3.45	V
			76	104	mA

<sup>1</sup> The extended pressure range is guaranteed by design.

<sup>2</sup> The relative error assumes that the initial error, at 25°C, is corrected in the end application.

<sup>3</sup> Linearity errors assume a full scale (FS) of 1000 mbar.

<sup>4</sup> The digital I/O signals are driven by an internal 3.3 V supply, and the inputs are 5 V tolerant.

<sup>5</sup> Endurance is qualified as per JEDEC Standard 22, Method A117, and measured at -40°C, +25°C, +85°C, and +125°C.

<sup>6</sup> The data retention lifetime equivalent is at a junction temperature (T<sub>J</sub>) of 85°C as per JEDEC Standard 22, Method A117. Data retention lifetime decreases with junction temperature.

<sup>7</sup> These times do not include thermal settling and internal filter response times (330 Hz bandwidth), which may affect overall accuracy.

<sup>8</sup> The xMAGN\_OUT and BARO\_OUT registers update at a rate that is 1/16<sup>th</sup> that of the other output registers.

<sup>9</sup> The sync input clock functions below the specified minimum value but at reduced performance levels.

**TIMING SPECIFICATIONS**

T<sub>A</sub> = 25°C, VDD = 5 V, unless otherwise noted.

Table 2.

Parameter	Description	Normal Mode			Burst Read			Unit
		Min <sup>1</sup>	Typ	Max	Min <sup>1</sup>	Typ	Max	
f <sub>SCLK</sub>	Serial clock	0.01		2.0	0.01		1.0	MHz
t <sub>STALL</sub>	Stall period between data	9			1/f <sub>SCLK</sub>			μs
t <sub>READRATE</sub>	Read rate	40						μs
t <sub>CS</sub>	Chip select to SCLK edge	48.8			48.8			ns
t <sub>DAV</sub>	DOUT valid after SCLK edge			100			100	ns
t <sub>DSU</sub>	DIN setup time before SCLK rising edge	24.4			24.4			ns
t <sub>DHD</sub>	DIN hold time after SCLK rising edge	48.8			48.8			ns
t <sub>SCLKR</sub> , t <sub>SCLKF</sub>	SCLK rise/fall times, not shown in Timing Diagrams		5	12.5		5	12.5	ns
t <sub>DR</sub> , t <sub>DF</sub>	DOUT rise/fall times, not shown in Timing Diagrams		5	12.5		5	12.5	ns
t <sub>SFS</sub>	$\overline{CS}$ high after SCLK edge	5			5			ns
t <sub>1</sub>	Input sync positive pulse width	5			5			μs
t <sub>STDR</sub>	Input sync to data ready valid transition		685			685		μs
t <sub>NV</sub>	Data invalid time		210			210		μs
t <sub>3</sub>	Input sync period	910			910			μs

<sup>1</sup> Guaranteed by design and characterization, but not tested in production.

**Timing Diagrams**

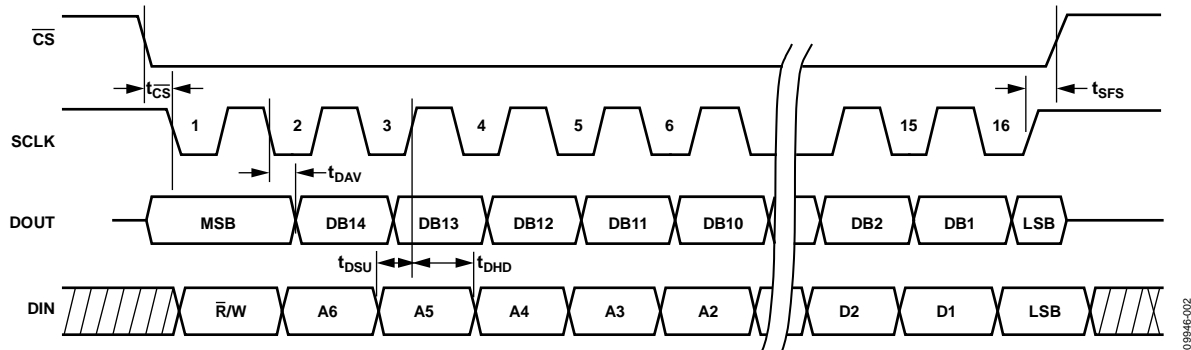


Figure 2. SPI Timing and Sequence

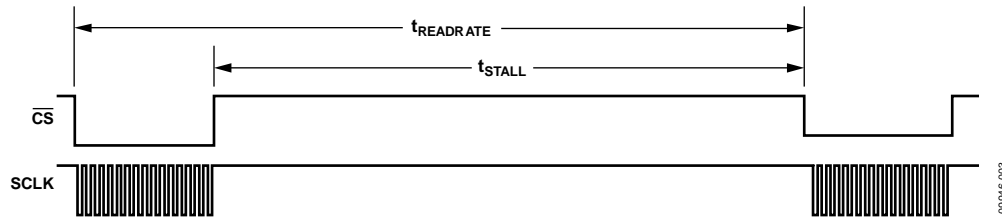


Figure 3. Stall Time and Data Rate

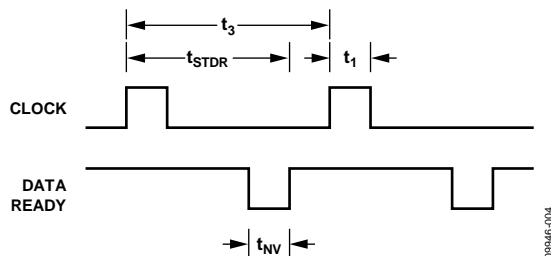


Figure 4. Input Clock Timing Diagram

## ABSOLUTE MAXIMUM RATINGS

Table 3.

Parameter	Rating
Acceleration	
Any Axis, Unpowered	2000 <i>g</i>
Any Axis, Powered	2000 <i>g</i>
VDD to GND	−0.3 V to +3.45 V
Digital Input Voltage to GND	−0.3 V to +VDD + 0.3 V
Digital Output Voltage to GND	−0.3 V to +VDD + 0.3 V
Temperature	
Operating Range	−40°C to +85°C
Storage Range	−65°C to +125°C <sup>1,2</sup>
Pressure	2 bar

<sup>1</sup> Extended exposure to temperatures outside the specified temperature range of −40°C to +105°C can adversely affect the accuracy of the factory calibration. For best accuracy, store the parts within the specified operating range of −40°C to +105°C.

<sup>2</sup> Although the device is capable of withstanding short-term exposure to 150°C, long-term exposure threatens internal mechanical integrity.

Stresses above those listed under Absolute Maximum Ratings may cause permanent damage to the device. This is a stress rating only; functional operation of the device at these or any other conditions above those indicated in the operational section of this specification is not implied. Exposure to absolute maximum rating conditions for extended periods may affect device reliability.

Table 4. Package Characteristics

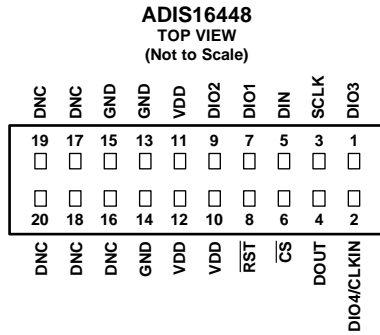
Package Type	$\theta_{JA}$ (°C/W)	$\theta_{JC}$ (°C/W)	Mass (grams)
20-Lead Module (ML-20-2)	36.5	16.9	15

### ESD CAUTION



**ESD (electrostatic discharge) sensitive device.** Charged devices and circuit boards can discharge without detection. Although this product features patented or proprietary protection circuitry, damage may occur on devices subjected to high energy ESD. Therefore, proper ESD precautions should be taken to avoid performance degradation or loss of functionality.

# PIN CONFIGURATION AND FUNCTION DESCRIPTIONS



- NOTES**
1. THIS REPRESENTATION DISPLAYS THE TOP VIEW WHEN THE CONNECTOR IS VISIBLE AND FACING UP.
  2. MATING CONNECTOR: SAMTEC CLM-110-02 OR EQUIVALENT.
  3. DNC = DO NOT CONNECT.

Figure 5. Pin Configuration

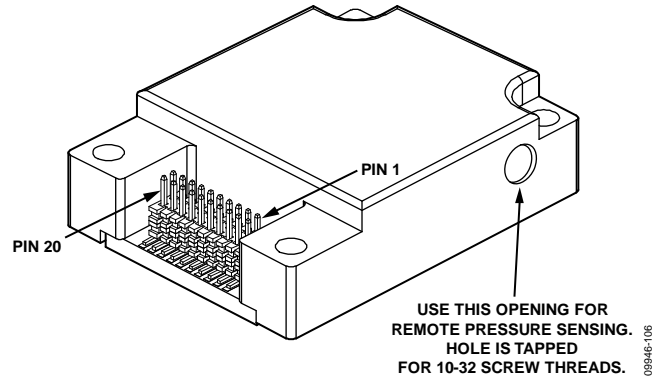


Figure 6. Pin Locations

Table 5. Pin Function Descriptions

Pin No.	Mnemonic	Type <sup>1</sup>	Description
1	DIO3	I/O	Configurable Digital Input/Output.
2	DIO4/CLKIN	I/O	Configurable Digital Input/Output or Sync Clock Input.
3	SCLK	I	SPI Serial Clock.
4	DOUT	O	SPI Data Output. Clocks the output on the SCLK falling edge.
5	DIN	I	SPI Data Input. Clocks the input on the SCLK rising edge.
6	$\overline{CS}$	I	SPI Chip Select.
7	DIO1	I/O	Configurable Digital Input/Output.
8	$\overline{RST}$	I	Reset.
9	DIO2	I/O	Configurable Digital Input/Output.
10, 11, 12	VDD	S	Power Supply.
13, 14, 15	GND	S	Power Ground.
16, 17, 18, 19, 20	DNC	N/A	Do Not Connect. Do not connect to these pins.

<sup>1</sup>S is supply, O is output, I is input, N/A is not applicable.

TYPICAL PERFORMANCE CHARACTERISTICS

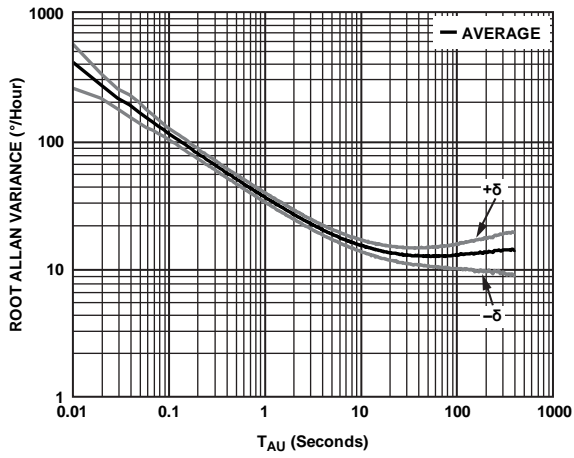


Figure 7. Gyroscope Root Allan Variance

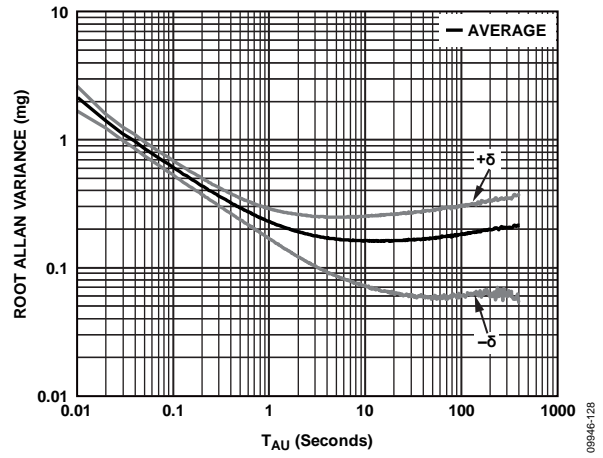


Figure 8. Accelerometer Root Allan Variance



## USER REGISTERS

Table 6. User Register Memory Map<sup>1</sup>

Name	R/W	Flash Backup	Address <sup>2</sup>	Default	Function	Bit Assignments
FLASH_CNT	R	Yes	0x00	N/A	Flash memory write count	See Table 32
Reserved	N/A	N/A	0x02	N/A	N/A	
XGYRO_OUT	R	No	0x04	N/A	X-axis gyroscope output	See Table 9
YGYRO_OUT	R	No	0x06	N/A	Y-axis gyroscope output	See Table 10
ZGYRO_OUT	R	No	0x08	N/A	Z-axis gyroscope output	See Table 11
XACCL_OUT	R	No	0x0A	N/A	X-axis accelerometer output	See Table 13
YACCL_OUT	R	No	0x0C	N/A	Y-axis accelerometer output	See Table 14
ZACCL_OUT	R	No	0x0E	N/A	Z-axis accelerometer output	See Table 15
XMAGN_OUT	R	No	0x10	N/A	X-axis magnetometer measurement	See Table 17
YMAGN_OUT	R	No	0x12	N/A	Y-axis magnetometer measurement	See Table 18
ZMAGN_OUT	R	No	0x14	N/A	Z-axis magnetometer measurement	See Table 19
BARO_OUT	R	No	0x16	N/A	Barometer pressure measurement, high word	See Table 21
TEMP_OUT	R	No	0x18	N/A	Temperature output	See Table 23
XGYRO_OFF	R/W	Yes	0x1A	0x0000	X-axis gyroscope bias offset factor	See Table 37
YGYRO_OFF	R/W	Yes	0x1C	0x0000	Y-axis gyroscope bias offset factor	See Table 38
ZGYRO_OFF	R/W	Yes	0x1E	0x0000	Z-axis gyroscope bias offset factor	See Table 39
XACCL_OFF	R/W	Yes	0x20	0x0000	X-axis acceleration bias offset factor	See Table 40
YACCL_OFF	R/W	Yes	0x22	0x0000	Y-axis acceleration bias offset factor	See Table 41
ZACCL_OFF	R/W	Yes	0x24	0x0000	Z-axis acceleration bias offset factor	See Table 42
XMAGN_HIC	R/W	Yes	0x26	0x0000	X-axis magnetometer, hard iron factor	See Table 43
YMAGN_HIC	R/W	Yes	0x28	0x0000	Y-axis magnetometer, hard iron factor	See Table 44
ZMAGN_HIC	R/W	Yes	0x2A	0x0000	Z-axis magnetometer, hard iron factor	See Table 45
XMAGN_SIC	R/W	Yes	0x2C	0x0000	X-axis magnetometer, soft iron factor	See Table 46
YMAGN_SIC	R/W	Yes	0x2E	0x0000	Y-axis magnetometer, soft iron factor	See Table 47
ZMAGN_SIC	R/W	Yes	0x30	0x0000	Z-axis magnetometer, soft iron factor	See Table 48
GPIO_CTRL	R/W	No	0x32	0x0000	Auxiliary digital input/output control	See Table 33
MSC_CTRL	R/W	Yes	0x34	0x0006	Miscellaneous control	See Table 30
SMPL_PRD	R/W	Yes	0x36	0x0001	Internal sample period (rate) control	See Table 34
SENS_AVG	R/W	Yes	0x38	0x0402	Dynamic range and digital filter control	See Table 35
SEQ_CNT	R	N/A	0x3A	N/A	xMAGN_OUT and BARO_OUT counter	See Table 36
DIAG_STAT	R	No	0x3C	0x0000	System status	See Table 31
GLOB_CMD	W	N/A	0x3E	0x0000	System command	See Table 25
ALM_MAG1	R/W	Yes	0x40	0x0000	Alarm 1 amplitude threshold	See Table 49
ALM_MAG2	R/W	Yes	0x42	0x0000	Alarm 2 amplitude threshold	See Table 50
ALM_SMPL1	R/W	Yes	0x44	0x0000	Alarm 1 sample size	See Table 51
ALM_SMPL2	R/W	Yes	0x46	0x0000	Alarm 2 sample size	See Table 52
ALM_CTRL	R/W	Yes	0x48	0x0000	Alarm control	See Table 53
Reserved	N/A	N/A	0x4A to 0x51	N/A	Reserved	
LOT_ID1	R	Yes	0x52	N/A	Lot identification number	See Table 26
LOT_ID2	R	Yes	0x54	N/A	Lot identification number	See Table 27
PROD_ID	R	Yes	0x56	0x4040	Product identifier	See Table 28
SERIAL_NUM	R	Yes	0x58	N/A	Lot-specific serial number	See Table 29

<sup>1</sup> N/A means not applicable.

<sup>2</sup> Each register contains two bytes. The address of the lower byte is displayed. The address of the upper byte is equal to the address of the lower byte plus 1.

## USER INTERFACE

The ADIS16448 is an autonomous system that requires no user initialization. When it has a valid power supply, it initializes itself and starts sampling, processing, and loading sensor data into the output registers at a sample rate of 819.2 SPS. DIO1 pulses high after each sample cycle concludes. The SPI interface enables simple integration with many embedded processor platforms, as shown in Figure 9 (electrical connection) and Table 7 (pin functions).

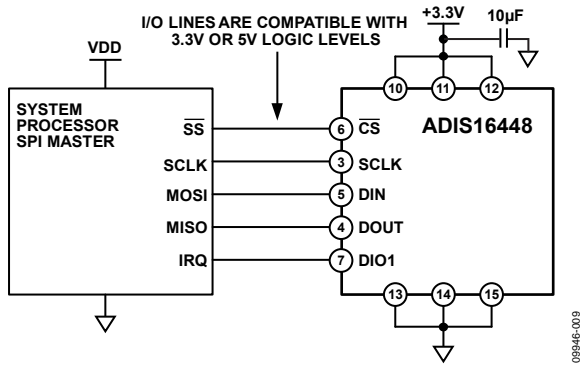


Figure 9. Electrical Connection Diagram

Table 7. Generic Master Processor Pin Names and Functions

Pin Name	Function
SS	Slave select
SCLK	Serial clock
MOSI	Master output, slave input
MISO	Master input, slave output
IRQ	Interrupt request

The ADIS16448 SPI interface supports full duplex serial communication (simultaneous transmit and receive) and uses the bit sequence shown in Figure 12. Table 8 provides a list of the most common settings that require attention to initialize the serial port of a processor for the ADIS16448 SPI interface.

Table 8. Generic Master Processor SPI Settings

Processor Setting	Description
Master	The ADIS16448 operates as a slave
SCLK Rate $\leq 2$ MHz <sup>1</sup>	Maximum serial clock rate
SPI Mode 3	CPOL = 1 (polarity), CPHA = 1 (phase)
MSB-First Mode	Bit sequence
16-Bit Mode	Shift register/data length

<sup>1</sup> For burst read, SCLK rate  $\leq 1$  MHz.

## READING SENSOR DATA

The ADIS16448 provides two different options for acquiring sensor data: single register and burst register. A single register read requires two 16-bit SPI cycles. The first cycle requests the contents of a register using the bit assignments in Figure 12. Bit DC7 to Bit DC0 are don't cares for a read, and then the output register contents follow on DOUT during the second sequence. Figure 10 includes three single register reads in succession. In this example, the process starts with DIN = 0x0400 to request the contents of XGYRO\_OUT, then follows with 0x0600 to request YGYRO\_OUT and 0x0800 to request ZGYRO\_OUT. Full duplex operation enables processors to use the same 16-bit SPI cycle to read data from DOUT while requesting the next set of data on DIN. Figure 11 provides an example of the four SPI signals when reading XGYRO\_OUT in a repeating pattern.

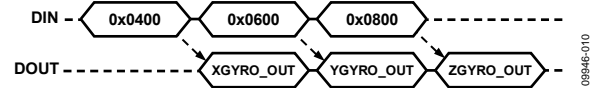


Figure 10. SPI Read Example

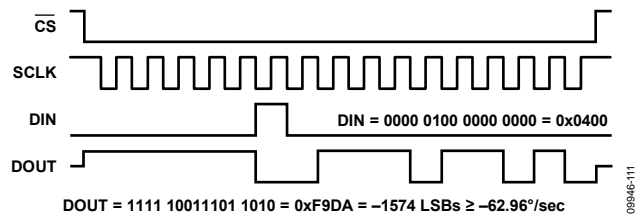
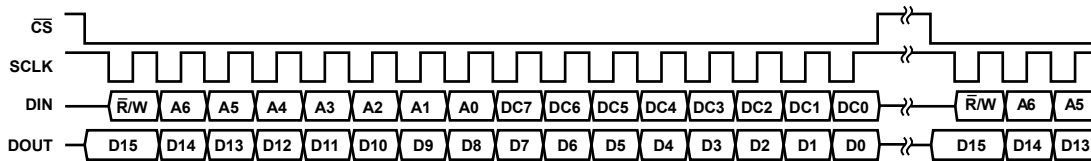


Figure 11. Example SPI Read, Second 16-Bit Sequence



NOTES

- THE DOUT BIT PATTERN REFLECTS THE ENTIRE CONTENTS OF THE REGISTER IDENTIFIED BY [A6:A0] IN THE PREVIOUS 16-BIT DIN SEQUENCE WHEN R/W = 0.
- IF R/W = 1 DURING THE PREVIOUS SEQUENCE, DOUT IS NOT DEFINED.

Figure 12. SPI Communication Bit Sequence

**Burst Read Function**

The burst read function enables the user to read all output registers using one command on the DIN line, 0x3E00. It also shortens the stall time between each 16-bit segment (see Table 2). Figure 13 provides the burst read sequence of data on each SPI signal. The sequence starts with writing 0x3E00 to DIN, followed by each output register clocking out on DOUT, in the order in which they appear in Figure 12.

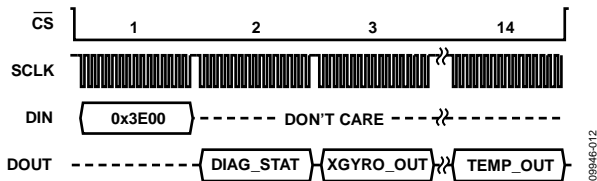


Figure 13. Burst Read Sequence

**SPI Read Test Sequence**

Figure 14 provides a test pattern for testing the SPI communication. In this pattern, write 0x5600 to the DIN line in a repeating pattern and raise chip select for at least 9 μs between each 16-bit sequence. Starting with the second 16-bit sequence, DOUT produces the contents of the PROD\_ID (see Table 28) register, 0x4040.

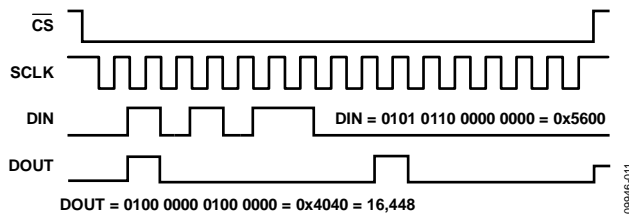
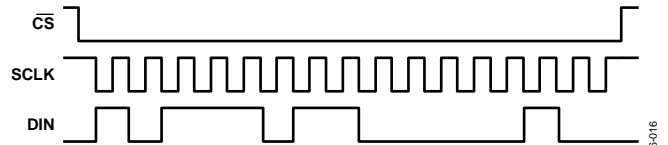


Figure 14. SPI Test Read Pattern DIN = 0x5600, DOUT = 0x4040

**DEVICE CONFIGURATION**

The control registers in Table 6 provide users with a variety of configuration options. The SPI provides access to these registers, one byte at a time, using the bit assignments in Figure 12. Each register has 16 bits, where Bits[7:0] represent the lower address, and Bits[15:8] represent the upper address. Figure 15 provides an example of writing 0x04 to Address 0x36 (SMPL\_PRD[15:8], using DIN = 0xB704. This example reduces the sample rate by a factor of eight (see Table 34).



DIN = 1011 0111 0000 0100 = 0xB704, WRITES 0x04 TO ADDRESS 0x37.

Figure 15. Example SPI Write Sequence

**Dual Memory Structure**

Writing configuration data to a control register updates its SRAM contents, which are volatile. After optimizing each relevant control register setting in a system, set GLOB\_CMD[3] = 1 (DIN = 0xBE08) to backup these settings in nonvolatile flash memory. The flash backup process requires a valid power supply level for the entire process time, 75 ms. Table 6 provides a user register memory map that includes a flash backup column. A yes in this column indicates that a register has a mirror location in flash and, when backed up properly, it automatically restores itself during startup or after a reset. Figure 16 provides a diagram of the dual memory structure used to manage operation and store critical user settings.

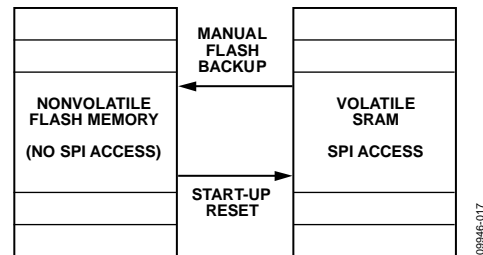


Figure 16. SRAM and Flash Memory Diagram

## OUTPUT DATA REGISTERS

Each sensor in the ADIS16448 has a dedicated output register in the user register map (see Table 6). Figure 17 provides arrows, which describe the direction or rotation ( $g_x, g_y, g_z$ ), acceleration ( $a_x, a_y, a_z$ ), and magnetic field ( $m_x, m_y, m_z$ ) that will produce a positive response in its output data.

### GYROSCOPES

XGYRO\_OUT (see Table 9) contains x-axis gyroscope data ( $g_x$  in Figure 17), YGYRO\_OUT (see Table 10) contains y-axis gyroscope data ( $g_y$  in Figure 17), and ZGYRO\_OUT (see Table 11) contains z-axis gyroscope data ( $g_z$  in Figure 17). Table 12 illustrates the gyroscope data format with numerical examples.

Table 9. XGYRO\_OUT (Base Address = 0x04), Read Only

Bits	Description
[15:0]	X-axis gyroscope data, twos complement format, 25 LSB/°/sec (SENS_AVG[15:8] = 0x04), 0°/sec = 0x0000

Table 10. YGYRO\_OUT (Base Address = 0x06), Read Only

Bits	Description
[15:0]	Y-axis gyroscope data, twos complement format, 25 LSB/°/sec (SENS_AVG[15:8] = 0x04), 0°/sec = 0x0000

Table 11. ZGYRO\_OUT (Base Address = 0x08), Read Only

Bits	Description
[15:0]	Z-axis gyroscope data, twos complement format, 25 LSB/°/sec (SENS_AVG[15:8] = 0x04), 0°/sec = 0x0000

Table 12. Rotation Rate, Twos Complement Format<sup>1</sup>

Rotation Rate (°/sec)	Decimal	Hex	Binary
+1000	+25,000	0x61A8	0110 0001 1010 1000
+2 ÷ 25	+2	0x0002	0000 0000 0000 0010
+1 ÷ 25	+1	0x0001	0000 0000 0000 0001
0	0	0x0000	0000 0000 0000 0000
-1 ÷ 25	-1	0xFFFF	1111 1111 1111 1111
-2 ÷ 25	-2	0xFFFE	1111 1111 1111 1110
-1000	-25,000	0x9E58	1001 1110 0101 1000

<sup>1</sup> SENS\_AVG[15:8] = 0x04, see Table 35.

### ACCELEROMETERS

XACCL\_OUT (see Table 13) contains x-axis accelerometer data ( $a_x$  in Figure 17), YACCL\_OUT (see Table 14) contains y-axis accelerometer data ( $a_y$  in Figure 17), and ZACCL\_OUT (see Table 15) contains z-axis accelerometer data ( $a_z$  in Figure 17). Table 16 illustrates the accelerometer data format with numerical examples.

Table 13. XACCL\_OUT (Base Address = 0x0A), Read Only

Bits	Description
[15:0]	X-axis acceleration data, twos complement format, 1200 LSB/g, 0 g = 0x0000

Table 14. YACCL\_OUT (Base Address = 0x0C), Read Only

Bits	Description
[15:0]	Y-axis acceleration data, twos complement format, 1200 LSB/g, 0 g = 0x0000

Table 15. ZACCL\_OUT (Base Address = 0x0E), Read Only

Bits	Description
[15:0]	Z-axis acceleration data, twos complement format, 1200 LSB/g, 0 g = 0x0000

Table 16. Acceleration, Twos Complement Format

Acceleration (g)	Decimal	Hex	Binary
+18	+21,600	0x5460	0101 0100 0101 0000
+2 ÷ 1200	+2	0x0002	0000 0000 0000 0010
+1 ÷ 1200	+1	0x0001	0000 0000 0000 0001
0	0	0x0000	0000 0000 0000 0000
-1 ÷ 1200	-1	0xFFFF	1111 1111 1111 1111
-2 ÷ 1200	-2	0xFFFE	1111 1111 1111 1110
-18	-21,600	0xABAO	1010 1011 1010 0000

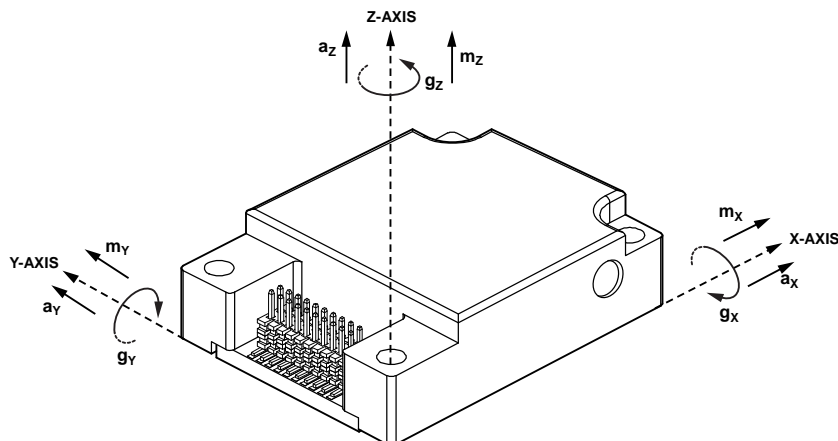


Figure 17. Inertial Sensor Direction Reference

019446-206

**MAGNETOMETERS**

XMAGN\_OUT (see Table 17) contains x-axis magnetometer data ( $m_x$  in Figure 17), YMAGN\_OUT (see Table 18) contains y-axis magnetometer data ( $m_y$  in Figure 17), and ZMAGN\_OUT (see Table 19) contains z-axis magnetometer data ( $m_z$  in Figure 17). Table 20 illustrates the magnetometer data format with numerical examples. The lower four bits of each magnetometer output data register (xMAGN\_OUT[3:0]) are not active at the maximum update rate of 51.2 SPS. They become active when using SMPL\_PRD[12:8] to average and decimate the data. The number of bits that become active is equal to the decimation setting number in SMPL\_PRD[12:8]. For example, if SMPL\_PRD[15:8] = 0x02, xMAGN\_OUT[15:2] are active and xMAGN\_OUT[1:0] are inactive.

Table 17. XMAGN\_OUT (Base Address = 0x10), Read Only

Bits	Description
[15:0]	X-axis magnetic field intensity data, $\pm 1.9$ gauss twos complement, 7 LSB/mgauss, 0x0000 = 0 mgauss

Table 18. YMAGN\_OUT (Base Address = 0x12), Read Only

Bits	Description
[15:0]	Y-axis magnetic field intensity data, $\pm 1.9$ gauss twos complement, 7 LSB/mgauss, 0x0000 = 0 mgauss

Table 19. ZMAGN\_OUT (Base Address = 0x14), Read Only

Bits	Description
[15:0]	Z-axis magnetic field intensity data, $\pm 1.9$ gauss twos complement, 7 LSB/mgauss, 0x0000 = 0 mgauss

Table 20. Magnetometer, Twos Complement Format

Magnetic Field (mgauss)	Decimal	Hex	Binary
+1900	+13,300	0x33F4	0011 0011 1111 0100
+2 $\div$ 7	+2	0x0002	0000 0000 0000 0010
+1 $\div$ 7	+1	0x0001	0000 0000 0000 0001
0	0	0x0000	0000 0000 0000 0000
+1 $\div$ 7	-1	0xFFFF	1111 1111 1111 1111
+2 $\div$ 7	-2	0xFFFE	1111 1111 1111 1110
-1900	-13,300	0xCC0C	1100 1100 0000 1100

**BAROMETRIC PRESSURE**

BARO\_OUT (see Table 21) contains the barometric pressure data. Table 22 provides several numerical format examples for BARO\_OUT.

Table 21. BARO\_OUT (Base Address = 0x16), Read Only

Bits	Description
[15:0]	Barometric pressure data, binary data format, 20 $\mu$ bar per LSB, 0x0000 = 0 mbar

Table 22. Pressure, Binary, BARO\_OUT

Pressure	Decimal	Hex	Binary
1200 mbar	60,000	0xEA60	1110 1010 0110 0000
1100 mbar	55,000	0xD6D8	1101 0110 1101 1000
1000 mbar	50,000	0xC350	1100 0011 0101 0000
0.04 mbar	2	0x0002	0000 0000 0000 0010
0.02 mbar	1	0x0001	0000 0000 0000 0001
0 mbar	0	0x0000	0000 0000 0000 0000

**REMOTE PRESSURE SENSING**

The ADIS16448 package offers a threaded hole (10-32) to support remote pressure sensing. Figure 18 provides an example of a fitting, which mates this hole to a barbed interface that enables a tight connection with rubber tubing (1/8”).

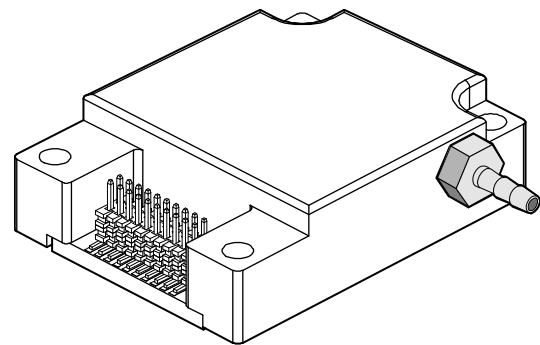


Figure 18. Barb Fitting for Remote Pressure Sensing

**INTERNAL TEMPERATURE**

The internal temperature measurement data loads into the TEMP\_OUT (see Table 23) register. Table 24 illustrates the temperature data format. Note that this temperature represents an internal temperature reading, which will not precisely represent external conditions. The intended use of TEMP\_OUT is to monitor relative changes in temperature.

Table 23. TEMP\_OUT (Base Address = 0x18), Read Only

Bits	Description
15	New data (ND) indicator, 1 = new data in register
14	Error/alarm, 1 = active, see DIAG_STAT for error flags
[13:12]	Not used
[11:0]	Twos complement, 0.07386°C/LSB, 31°C = 0x000

Table 24. Temperature, Twos Complement Format

Temperature (°C)	Decimal	Hex	Binary
+105	+1002	3EA	0011 1110 1010
+85	+731	2DB	0010 1101 1011
+31.14772	+2	2	0000 0000 0010
+31.07386	+1	0	0000 0000 0001
+31	0	0	0000 0000 0000
+30.92614	-1	FFF	1111 1111 1111
+30.85228	-2	FFE	1111 1111 1110
-40	-962	C3E	1100 0011 1110

## SYSTEM FUNCTIONS

### GLOBAL COMMANDS

The GLOB\_CMD register in Table 25 provides trigger bits for software reset, flash memory management, and calibration control. Start each of these functions by writing a 1 to the assigned bit in GLOB\_CMD. After completing the task, the bit automatically returns to 0. For example, set GLOB\_CMD[7] = 1 (DIN = 0xBE80) to initiate a software reset. Set GLOB\_CMD[3] = 1 (DIN = 0xBE08) to back up the user register contents in nonvolatile flash. This sequence includes loading the control registers with the data in their respective flash memory locations prior to producing new data.

**Table 25. GLOB\_CMD (Base Address = 0x3E), Write Only**

Bits	Description (Default = 0x0000)
[15:8]	Not used
7	Software reset
[6:4]	Not used
3	Flash update
2	Not used
1	Factory calibration restore
0	Gyroscope bias correction

### PRODUCT IDENTIFICATION

The PROD\_ID register in Table 28 contains the binary equivalent of 16,448. It provides a product specific variable for systems that need to track this in their system software. The LOT\_ID1 and LOT\_ID2 registers in Table 26 and Table 27 combine to provide a unique, 32-bit lot identification code. The SERIAL\_NUM register in Table 29 contains a binary number that represents the serial number on the device label. The assigned serial numbers in SERIAL\_NUM are lot specific.

**Table 26. LOT\_ID1 (Base Address = 0x52), Read Only**

Bits	Description
[15:0]	Lot identification, binary code

**Table 27. LOT\_ID2 (Base Address = 0x54), Read Only**

Bits	Description
[15:0]	Lot identification, binary code

**Table 28. PROD\_ID (Base Address = 0x56), Read Only**

Bits	Description (Default = 0x4040)
[15:0]	Product identification = 0x4040

**Table 29. SERIAL\_NUM (Base Address = 0x58), Read Only**

Bits	Description
[15:12]	Reserved
[11:0]	Serial number, 1 to 4094 (0xFFE)

### SELF-TEST FUNCTION

The MSC\_CTRL register in Table 30 provides a self-test function for the gyroscopes, accelerometers, magnetometers, and barometers. Note that the magnetometer results assume that the non-earth magnetic fields are low, in comparison to the earth's magnetic field. This function allows the user to verify the mechanical integrity of each MEMS sensor. When enabled, the self test applies an electrostatic force to each internal sensor element, which causes them to move. The movement in each element simulates its response to actual rotation/acceleration and generates a predictable electrical response in the sensor outputs. Set MSC\_CTRL[10] = 1 (DIN = 0xB504) to activate the internal self test routine, which compares the response to an expected range of responses and reports a pass/fail response to DIAG\_STAT[5]. If this is high, review DIAG\_STAT[15:10] to identify the failing sensor.

**Table 30. MSC\_CTRL (Base Address = 0x34), Read/Write**

Bits	Description (Default = 0x0006)
[15:12]	Not used
11	Checksum memory test (cleared upon completion) <sup>1</sup> 1 = enabled, 0 = disabled
10	Internal self test (cleared upon completion) <sup>1</sup> 1 = enabled, 0 = disabled
[9:8]	Do not use, always set to 00
7	Not used
6	Point of percussion, see Figure 22 1 = enabled, 0 = disabled
[5:3]	Not used
2	Data ready enable 1 = enabled, 0 = disabled
1	Data ready polarity 1 = active high when data is valid 0 = active low when data is valid
0	Data ready line select 1 = DIO2, 0 = DIO1

<sup>1</sup> The bit is automatically reset to 0 after finishing the test.

## STATUS/ERROR FLAGS

The DIAG\_STAT register in Table 31 provides error flags for a number of functions. Each flag uses 1 to indicate an error condition and 0 to indicate a normal condition. Reading this register provides access to the status of each flag and resets all of the bits to 0 for monitoring future operation. If the error condition remains, the error flag returns to 1 at the conclusion of the next sample cycle. DIAG\_STAT[0] does not require a read of this register to return to 0. If the power supply voltage goes back into range, this flag clears automatically. The SPI communication error flag in DIAG\_STAT[3] indicates that the number of SCLKs in a SPI sequence did not equal a multiple of 16 SCLKs.

**Table 31. DIAG\_STAT (Base Address = 0x3C), Read Only**

Bits	Description (Default = 0x0000)
15	Z-axis accelerometer self-test failure 1 = fail, 0 = pass
14	Y-axis accelerometer self-test failure 1 = fail, 0 = pass
13	X-axis accelerometer self-test failure 1 = fail, 0 = pass
12	Z-axis gyroscope self-test failure 0 = pass
11	Y-axis gyroscope self-test failure 1 = fail, 0 = pass
10	X-axis gyroscope self-test failure 1 = fail, 0 = pass
9	Alarm 2 status 1 = active, 0 = inactive
8	Alarm 1 status 1 = active, 0 = inactive
7	New data, xMAGN_OUT/BARO_OUT
6	Flash test, checksum flag 1 = fail, 0 = pass
5	Self-test diagnostic error flag 1 = fail, 0 = pass
4	Sensor overrange 1 = overrange, 0 = normal
3	SPI communication failure 1 = fail, 0 = pass
2	Flash update failure 1 = fail, 0 = pass
1	Barometer functional test 1 = fail, 0 = pass
0	Magnetometer functional test 1 = fail, 0 = pass

## Magnetometer/Barometer New Data Indicator

DIAG\_STAT[7] indicates that all four registers have new, unread data in them. This bit rises to 1 after the xMAGN\_OUT and BARO\_OUT registers have new data updates. It lowers to zero after one of the registers are accessed using a SPI-driven read command. This bit does not return to zero after reading DIAG\_STAT.

## MEMORY MANAGEMENT

The FLASH\_CNT register in Table 32 provides a 16-bit counter that helps track the number of write cycles to the nonvolatile flash memory. The flash updates every time a manual flash update occurs. A manual flash update is initiated by the GLOB\_CMD[3] bit and is performed at the completion of the GLOB\_CMD[1:0] functions (see Table 25).

**Table 32. FLASH\_CNT (Base Address = 0x00), Read Only**

Bits	Description
[15:0]	Binary counter

## Checksum Test

Set MSC\_CTRL[11] = 1 (DIN = 0xB508) to perform a checksum test of the internal program memory. This function takes a summation of the internal program memory and compares it with the original summation value for the same locations (from factory configuration). If the sum matches the correct value, DIAG\_STAT[6] is equal to 0. If it does not match, DIAG\_STAT[6] is equal to 1. Make sure that the power supply is within specification for the entire 20 ms that this function takes to complete.

## INPUT/OUTPUT CONFIGURATION

### DATA READY INDICATOR

The data ready indicator provides a signal that indicates when the registers are updating, so that system processors can avoid data collision, a condition when internal register updates happen at the same time that an external processor requests it. The data ready signal has valid and invalid states. Using the transition from invalid to valid to trigger an interrupt service routine provides the most time for data acquisition (before the next register update). See Figure 4 and Table 2 for specific timing information. `MSC_CTRL[2:0]` (see Table 30) provide control bits for enabling this function, selecting the polarity of the valid state and I/O line assignment (DIO1, DIO2). The factory default setting of `MSC_CTRL[2:0] = 110` (DIN = 0xB406) establishes DIO1 as a data ready output line and assigns the valid state with a logic high (1). Set `MSC_CTRL[2:0] = 100` (DIN = 0xB404) to change the polarity of the data ready signal on DIO1 for interrupt inputs that require negative logic inputs for activation.

### GENERAL-PURPOSE INPUT/OUTPUT

DIO1, DIO2, DIO3, and DIO4 are configurable, general-purpose input/output lines that serve multiple purposes. The data ready controls in `MSC_CTRL[2:0]` have the highest priority for configuring DIO1 and DIO2. The alarm indicator controls in `ALM_CTRL[2:0]` have the second highest priority for configuring DIO1 and DIO2. The external clock control associated with `SMPL_PRD[0]` has the highest priority for DIO4 configuration (see Table 34). `GPIO_CTRL` in Table 33 has the lowest priority for configuring DIO1, DIO2, and DIO4, and has absolute control over DIO3.

**Table 33. GPIO\_CTRL (Base Address = 0x32), Read/Write**

Bits	Description (Default = 0x0000)
[15:12]	Not used
11	General-Purpose I/O Line 4 (DIO4) data level
10	General-Purpose I/O Line 3 (DIO3) data level
9	General-Purpose I/O Line 2 (DIO2) data level
8	General-Purpose I/O Line 1 (DIO1) data level
[7:4]	Not used
3	General-Purpose I/O Line 4 (DIO4) direction control 1 = output, 0 = input
2	General-Purpose I/O Line 3 (DIO3) direction control 1 = output, 0 = input
1	General-Purpose I/O Line 2 (DIO2) direction control 1 = output, 0 = input
0	General-Purpose I/O Line 1 (DIO1) direction control 1 = output, 0 = input

#### **Example Input/Output Configuration**

For example, set `GPIO_CTRL[3:0] = 0100` (DIN = 0xB204) to set DIO3 as an output signal pin and DIO1, DIO2, and DIO4 as input signal pins. Set the output on DIO3 to 1 by setting `GPIO_CTRL[10] = 1` (DIN = 0xB304). Then, read `GPIO_CTRL[7:0]` (DIN = 0x3200) and mask off `GPIO_CTRL[9:8]` and `GPIO_CTRL[11]` to monitor the digital signal levels on DIO4, DIO2, and DIO1.



## DIGITAL PROCESSING CONFIGURATION GYROSCOPES/ACCELEROMETERS

Figure 20 provides a diagram that describes all signal-processing components for the gyroscopes and accelerometers. The internal sampling system produces new data in the xGYRO\_OUT and xACCL\_OUT output data registers at a rate of 819.2 SPS. The SMPL\_PRD register in Table 34 provides two functional controls that affect sampling and register update rates. SMPL\_PRD[12:8] provides a control for reducing the update rate, using an averaging filter with a decimated output. These bits provide a binomial control that divides the data rate by a factor of 2 every time this number increases by 1. For example, set SMPL\_PRD[15:8] = 0x04 (DIN = 0xB704) to set the decimation factor to 16. This reduces the update rate to 51.2 SPS and the bandwidth to ~25 Hz. The SMPL\_PRD[12:8] setting affects the update rate for the TEMP\_OUT register (see Table 23) as well.

**Table 34. SMPL\_PRD (Base Address = 0x36), Read/Write**

Bits	Description (Default = 0x0001)
[15:13]	Not used
[12:8]	D, decimation rate setting, binomial, see Figure 20
[7:1]	Not used
0	Clock 1 = internal sampling clock, 819.2 SPS 0 = external sampling clock

### INPUT CLOCK CONFIGURATION

SMPL\_PRD[0] (see Table 34) provides a control for synchronizing the internal sampling to an external clock source. Set SMPL\_PRD[0] = 0 (DIN = 0xB600) and GPIO\_CTRL[3] = 0 (DIN = 0xB200) to enable the external clock. See Table 2 and Figure 4 for timing information.

### Digital Filtering

The SENS\_AVG register in Table 35 provides user controls for the low-pass filter. This filter contains two cascaded averaging filters that provide a Bartlett window, FIR filter response (see Figure 20). For example, set SENS\_AVG[2:0] = 100 (DIN = 0xB804) to set each stage to 16 taps. When used with the default sample rate of 819.2 SPS and zero decimation (SMPL\_PRD[15:8] = 0x00), this value reduces the sensor bandwidth to approximately 16 Hz.

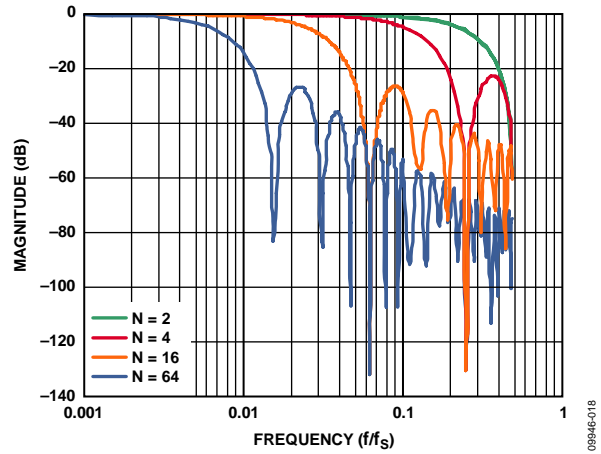


Figure 19. Bartlett Window, FIR Filter Frequency Response (Phase Delay = N Samples)

### Dynamic Range

The SENS\_AVG[10:8] bits provide three dynamic range settings for the gyroscopes. The lower dynamic range settings ( $\pm 250^\circ/\text{sec}$  and  $\pm 500^\circ/\text{sec}$ ) limit the minimum filter tap sizes to maintain resolution. For example, set SENS\_AVG[10:8] = 010 (DIN = 0xB902) for a measurement range of  $\pm 500^\circ/\text{sec}$ . Because this setting can influence the filter settings, program SENS\_AVG[10:8] before programming SENS\_AVG[2:0] if more filtering is required.

**Table 35. SENS\_AVG (Base Address = 0x38), Read/Write**

Bits	Description (Default = 0x0402)
[15:11]	Not used
[10:8]	Measurement range (sensitivity) selection 100 = $\pm 1000^\circ/\text{sec}$ (default condition) 010 = $\pm 500^\circ/\text{sec}$ , filter taps $\geq 4$ (Bits[2:0] $\geq 0x02$ ) 001 = $\pm 250^\circ/\text{sec}$ , filter taps $\geq 16$ (Bits[2:0] $\geq 0x04$ )
[7:3]	Not used
[2:0]	Filter Size Variable B Number of taps in each stage; $N_B = 2^B$ See Figure 19 for filter response

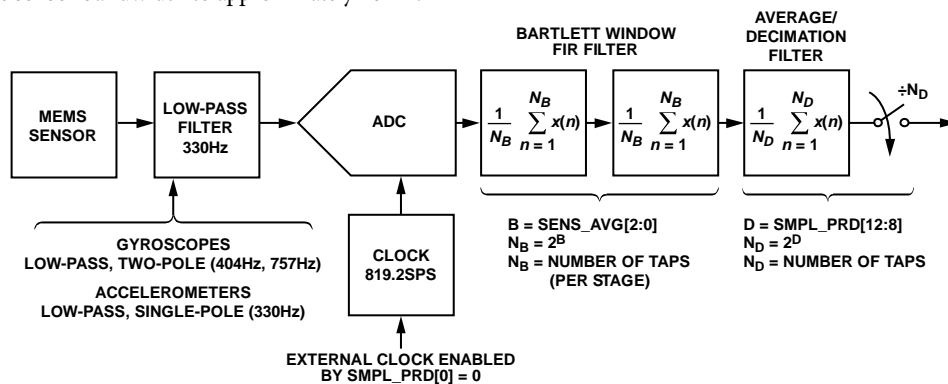


Figure 20. Sampling and Frequency Response Block Diagram

## MAGNETOMETER/BAROMETER

The magnetometer (xMAGN\_OUT) and barometer output registers (BARO\_OUT) update at a rate of 51.2 SPS. When using the external clock, these registers update at a rate of  $1/16^{\text{th}}$  of the input clock frequency. The update rates for the magnetometer and barometers do not change with the SMPL\_PRD [15:8] register settings, unless SMPL\_PRD[15:8] > 0x04.

### New-Data Indicators

DIAG\_STAT[7] (see Table 31) offers a new data bit for the magnetometer (xMAGN\_OUT) and barometer output registers (BARO\_OUT) registers. This bit rises to a 1, right after the xMAGN\_OUT and BARO\_OUT registers receive fresh data. It returns to 0 after one of the four registers experiences a read request.

The SEQ\_CNT register (see Table 36) provides a counter function to help determine when there is new data in the magnetometer and barometer registers. When using the full sample rate (SMPL\_PRD[15:8] = 0x00), SEQ\_CNT will start

at a value of 16 and decrement every time the gyroscope data updates. When it reaches a value of 1, it will return to a value 16 after the next gyroscope update cycle. When SEQ\_CNT equals 16, the magnetometer (xMAGN\_OUT) and barometer (BARO\_OUT) registers contain new data. The SEQ\_CNT register can be useful during initialization to help synchronize read loops for new data in both magnetometer and barometer outputs. When beginning a continuous read loop, read SEQ\_CNT to determine the number of sample cycles that must pass, before the magnetometer and barometer registers update.

**Table 36. SEQ\_CNT (Base Address = 0x3A), Read Only**

Bits	Description
[15:11]	Don't care
[6:0]	Binary counter: 16 to 1, when D = 0 Counter range = $16/2^D - 1$ , when $1 \leq D \leq 4$ See Table 34 for more information on D

## CALIBRATION

The mechanical structure and assembly process of the ADIS16448 provide excellent position and alignment stability for each sensor, even after subjected to temperature cycles, shock, vibration, and other environmental conditions. The factory calibration includes a dynamic characterization of each gyroscope and accelerometer over temperature and generates sensor specific correction formulas.

### GYROSCOPES

The XGYRO\_OFF (see Table 37), YGYRO\_OFF (see Table 38), and ZGYRO\_OFF (see Table 39) registers provide user-programmable bias adjustment function for the X-, Y-, and Z-axis gyroscopes, respectively. Figure 21 illustrates that they contain bias correction factors that adjust to the sensor data immediately before it loads into the output register.

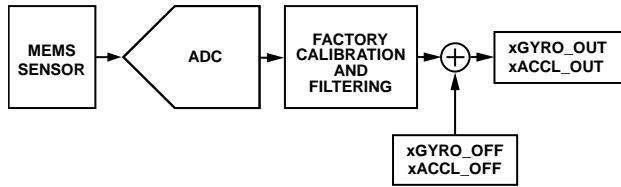


Figure 21. User Calibration, Gyroscopes, and Accelerometers

### Gyroscope Bias Error Estimation

Any system level calibration function must start with an estimate of the bias errors, which typically comes from a sample of gyroscope output data, when the device is not in motion. The sample size of data depends on the accuracy goals. Figure 7 provides a trade-off relationship between averaging time and the expected accuracy of a bias measurement. Vibration, thermal gradients, and power supply instability can influence the accuracy of this process.

Table 37. XGYRO\_OFF (Base Address = 0x1A), Read/Write

Bits	Description (Default = 0x0000)
[15:0]	X-axis, gyroscope offset correction factor, twos complement, 0.01°/sec/LSB, 0°/sec = 0x0000

Table 38. YGYRO\_OFF (Base Address = 0x1C), Read/Write

Bits	Description (Default = 0x0000)
[15:0]	Y-axis, gyroscope offset correction factor, twos complement, 0.01°/sec/LSB, 0°/sec = 0x0000

Table 39. ZGYRO\_OFF (Base Address = 0x1E), Read/Write

Bits	Description (Default = 0x0000)
[15:0]	Z-axis, gyroscope offset correction factor, twos complement, 0.01°/sec/LSB, 0°/sec = 0x0000

### Gyroscope Bias Correction Factors

When the bias estimate is complete, multiply the estimate by -1 to change its polarity, convert it into digital format for the offset correction registers (see Table 37, Table 38, and Table 39), and write the correction factors to the correction registers. For example, lower the X-axis bias by 10 LSB (0.1°/sec) by setting XGYRO\_OFF = 0xFFFF6 (DIN = 0x9BFF, 0x9AF6).

### Single Command Bias Correction

GLOB\_CMD[0] (see Table 25) loads the xGYRO\_OFF registers with the values that are the opposite of the values that are in xGYRO\_OUT, at the time of initiation. Use this command, together with the decimation filter (SMPL\_PRD[12:8], see Table 34), to automatically average the gyroscope data and improve the accuracy of this function, as follows:

1. Set SENS\_AVG[10:8] = 001 (DIN = 0xB901) to optimize the xGYRO\_OUT sensitivity to 0.01°/sec/LSB.
2. Set SMPL\_PRD[12:8] = 0x10 (DIN = 0xB710) to set the decimation rate to 65,536 (2<sup>16</sup>), which provides an averaging time of 80 seconds (65,536 ÷ 819.2 SPS).
3. Wait for 80 seconds while keeping the device motionless.
4. Set GLOB\_CMD[0] = 1 (DIN = 0x3E01) and wait for the time it takes to perform the flash memory backup.

### ACCELEROMETERS

The XACCL\_OFF (see Table 40), YACCL\_OFF (see Table 41), and ZACCL\_OFF (see Table 42) registers provide user-programmable bias adjustment function for the X-, Y-, and Z-axis accelerometers, respectively. These registers adjust the accelerometer data in the same manner as XGYRO\_OFF in Figure 21.

Table 40. XACCL\_OFF (Base Address = 0x20), Read/Write

Bits	Description (Default = 0x0000)
[15:0]	X-axis, accelerometer offset correction factor, twos complement, 1/1200 g/LSB, 0 g = 0x0000

Table 41. YACCL\_OFF (Base Address = 0x22), Read/Write

Bits	Description (Default = 0x0000)
[15:14]	Not used
[13:0]	Y-axis, accelerometer offset correction factor, twos complement, 1/1200 g/LSB, 0 g = 0x0000

Table 42. ZACCL\_OFF (Base Address = 0x24), Read/Write

Bits	Description (Default = 0x0000)
[15:14]	Not used
[13:0]	Z-axis, accelerometer offset correction factor, twos complement, 1/1200 g/LSB, 0 g = 0x0000

### Accelerometer Bias Error Estimation

Under static conditions, orient each accelerometer in positions where the response to gravity is predictable. A common approach to this is to measure the response of each accelerometer when they are oriented in peak response positions, that is, where ±1 g is the ideal measurement position. Next, average the +1 g and -1 g accelerometer measurements together to estimate the residual bias error. Using more points in the rotation can improve the accuracy of the response.

**Accelerometer Bias Correction Factors**

When the bias estimate is complete, multiply the estimate by -1 to change its polarity, convert it to the digital format for the offset correction registers (see Table 40, Table 41 or Table 42) and write the correction factors to the correction registers. For example, lower the x-axis bias by 12 LSB (10 mg) by setting XACCL\_OFF = 0xFFFF4 (DIN = 0xA1FF, 0xA0F4).

**Point of Percussion Alignment**

Set MSC\_CTRL[6] = 1 (DIN = 0xB446) to enable this feature and maintain the factory default settings for DIO1. This feature performs a point of percussion translation to the point identified in Figure 22. See Table 30 for more information on MSC\_CTRL.

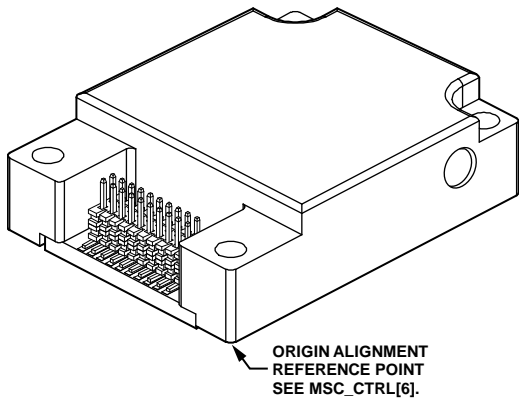


Figure 22. Point of Percussion Physical Reference

**MAGNETOMETER CALIBRATION**

The ADIS16448 provides registers that contribute to both hard iron and soft iron correction factors, as shown in Figure 23.

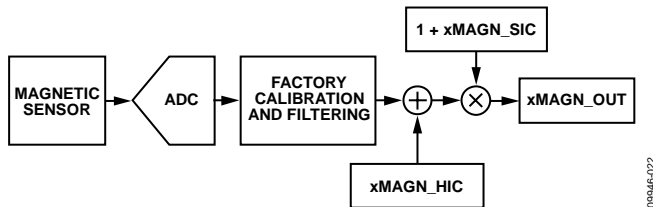


Figure 23. Hard Iron and Soft Iron Factor Correction

**Hard Iron Correction**

The XMAGN\_HIC (see Table 43), YMAGN\_HIC (see Table 44), and ZMAGN\_HIC (see Table 45) registers provide the user programmable bias adjustment function for the X-, Y-, and Z-axis magnetometers, respectively. Hard iron effects result in an offset of the magnetometer response.

**Table 43. XMAGN\_HIC (Base Address = 0x26), Read/Write**

Bits	Description (Default = 0x0000)
[15:0]	X-axis hard iron correction factor, twos complement, 7 LSB/mgauss, 0x0000 = 0

**Table 44. YMAGN\_HIC (Base Address = 0x28), Read/Write**

Bits	Description (Default = 0x0000)
[15:0]	Y-axis hard iron correction factor, twos complement, 7 LSB/mgauss, 0x0000 = 0

**Table 45. ZMAGN\_HIC (Base Address = 0x2A), Read/Write**

Bits	Description (Default = 0x0000)
[15:0]	Z-axis hard iron correction factor, twos complement, 7 LSB/mgauss, 0x0000 = 0 mgauss

**Hard Iron Factors**

When the hard iron error estimation is complete, take the following steps:

1. Multiply the estimate by -1 to change its polarity.
2. Convert it into digital format for the hard iron correction registers (see Table 43).
3. Write the correction factors to the registers. For example, lower the x-axis bias by 10 LSB (~1.429 mgauss) by setting XMAGN\_HIC = 0xFFFF6 (DIN = 0xA7FF, 0xA6F6)

**Soft Iron Effects**

The XMAGN\_SIC (see Table 46), YMAGN\_SIC (see Table 47), and ZMAGN\_SIC (see Table 48) registers provide an adjustment variable for the magnetometer sensitivity adjustment in each magnetometer response to simplify the process of performing a system level soft iron correction.

**Table 46. XMAGN\_SIC (Base Address = 0x2C), Read/Write**

Bits	Description (Default = 0x8000)
[15:0]	X-axis soft iron correction factor, twos complement format, 1 LSB = 100%/32,767 0x7FFF = 100% increase (2x) 0x8000 = 100% decrease (0x)

**Table 47. YMAGN\_SIC (Base Address = 0x2E), Read/Write**

Bits	Description (Default = 0x8000)
[15:0]	Y-axis soft iron correction factor, twos complement format, 1 LSB = 100%/32,767 0x7FFF = 100% increase (2x) 0x8000 = 100% decrease (0x)

**Table 48. ZMAGN\_SIC (Base Address = 0x30), Read/Write**

Bits	Description (Default = 0x8000)
[15:0]	Z-axis soft iron correction factor, twos complement format, 1 LSB = 100%/32,767 0x7FFF = 100% increase (2x) 0x8000 = 100% decrease (0x)

**FLASH UPDATES**

When using the user calibration registers to optimize system level accuracy, set GLOB\_CMD[3] = 1 (DIN = 0xBE04) to save these settings in nonvolatile flash memory. Be sure to consider the endurance rating of the flash memory when determining how often to update the user correction factors in the flash memory.

**RESTORING FACTORY CALIBRATION**

Set GLOB\_CMD[1] = 1 (DIN = 0xBE02) to execute the factory calibration restore function, which resets the gyroscope and accelerometer offset registers to 0x0000 and all sensor data to 0. Then, it automatically updates the flash memory and restarts sampling and processing data. See Table 25 for information on GLOB\_CMD.

## ALARMS

Alarm 1 and Alarm 2 provide two independent alarms with programmable levels, polarity, and data sources.

### STATIC ALARM USE

The static alarms setting compares the data source selection (ALM\_CTRL[15:8]) with the values in the ALM\_MAGx registers listed in Table 49 and Table 50, using ALM\_MAGx[15] to determine the trigger polarity. The data format in these registers matches the format of the data selection in ALM\_CTRL[15:8]. See Table 54, Alarm 1, for a static alarm configuration example.

**Table 49. ALM\_MAG1 (Base Address = 0x40), Read/Write**

Bits	Description (Default = 0x0000)
[15:0]	Threshold setting; matches for format of ALM_CTRL[11:8] output register selection

**Table 50. ALM\_MAG2 (Base Address = 0x42), Read/Write**

Bits	Description (Default = 0x0000)
[15:0]	Threshold setting; matches for format of ALM_CTRL[15:12] output register selection

### DYNAMIC ALARM USE

The dynamic alarm setting monitors the data selection for a rate-of-change comparison. The rate-of-change comparison is represented by the magnitude in the ALM\_MAGx registers over the time represented by the number-of-samples setting in the ALM\_SMPLx registers, located in Table 51. See Table 54, Alarm 2, for a dynamic alarm configuration example.

**Table 51. ALM\_SMPL1 (Base Address = 0x44), Read/Write**

Bits	Description (Default = 0x0000)
[15:8]	Not used
[7:0]	Binary, number of samples (both 0x00 and 0x01 = 1)

**Table 52. ALM\_SMPL2 (Base Address = 0x46), Read/Write**

Bits	Description (Default = 0x0000)
[15:8]	Not used
[7:0]	Binary, number of samples (both 0x00 and 0x01 = 1)

### ALARM REPORTING

The DIAG\_STAT[9:8] bits provide error flags that indicate an alarm condition. The ALM\_CTRL[2:0] bits provide controls for a hardware indicator using DIO1 or DIO2.

**Table 53. ALM\_CTRL (Base Address = 0x48), Read/Write**

Bits	Description (Default = 0x0000)
[15:12]	Alarm 2 data source selection 0000 = disable 0001 = XGYRO_OUT 0010 = YGYRO_OUT 0011 = ZGYRO_OUT 0100 = XACCL_OUT 0101 = YACCL_OUT 0110 = ZACCL_OUT 0111 = XMAGN_OUT 1001 = YMAGN_OUT 1010 = ZMAGN_OUT 1011 = BARO_OUT 1100 = TEMP_OUT
[11:8]	Alarm 1 data source selection (same as Alarm 2)
7	Alarm 2, dynamic/static (1 = dynamic, 0 = static)
6	Alarm 1, dynamic/static (1 = dynamic, 0 = static)
5	Alarm 2, polarity (1 = greater than ALM_MAG2)
4	Alarm 1, polarity (1 = greater than ALM_MAG1)
3	Data source filtering (1 = filtered, 0 = unfiltered)
2	Alarm indicator (1 = enabled, 0 = disabled)
1	Alarm indicator active polarity (1 = high, 0 = low)
0	Alarm output line select (1 = DIO2, 0 = DIO1)

### Alarm Example

Table 54 offers an example that configures Alarm 1 to trigger when filtered ZACCL\_OUT data drops below 0.7 g and Alarm 2 to trigger when filtered ZGYRO\_OUT data changes by more than 50°/sec over a 100 ms period, or 500°/sec<sup>2</sup>. The filter setting helps reduce false triggers from noise and refines the accuracy of the trigger points. The ALM\_SMPL2 setting of 82 samples provides a comparison period that is approximately equal to 100 ms for an internal sample rate of 819.2 SPS.

**Table 54. Alarm Configuration Example**

DIN	Description
0xCD36, 0xCCAF	ALM_CTRL = 0x36AF Alarm 2: dynamic, Δ-ZGYRO_OUT (Δ-time, ALM_SMPL2) > ALM_MAG2 Alarm 1: static, ZACCL_OUT < ALM_MAG1, filtered data DIO2 output indicator, positive polarity
0xC704, 0xC6E2	ALM_MAG2 = 0x04E2 = 1,250 LSB = 50°/sec
0xC503, 0xC448	ALM_MAG1 = 0x0348 = 840 LSB = +0.7 g
0xC866	ALM_SMPL2[7:0] = 0x52 = 82 samples 82 samples ÷ 819.2 SPS = ~100 ms

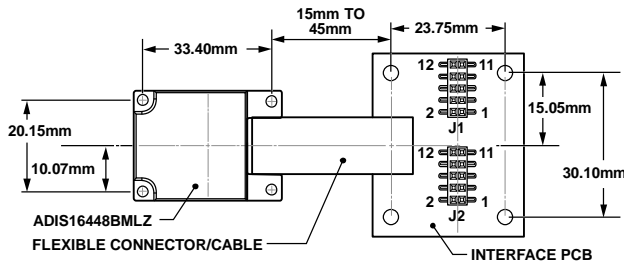
## APPLICATIONS INFORMATION

### POWER SUPPLY CONSIDERATIONS

The power supply must be within 3.15 V and 3.45 V for normal operation and optimal performance. During start up, the internal power conversion system starts drawing current when VDD reaches 1.6 V. The internal processor begins initializing when VDD is equal to 2.35 V. After the processor starts, VDD must reach 2.7 V within 128 ms. Also, make sure that the power supply drops below 1.6 V to shut the device down. Figure 9 shows a 10  $\mu$ F capacitor on the power supply. Using this capacitor supports optimal noise performance in the sensors.

### ADIS16448/PCBZ

The ADIS16448/PCBZ includes one ADIS16448AMLZ, one interface PCB, and one interface flex. This combination of components enables quicker installation for prototype evaluation and algorithm development. Figure 24 provides a mechanical design example for using these three components in a system.



- NOTES  
 1. USE FOUR M2 MACHINE SCREWS TO ATTACH THE ADIS16448.  
 2. USE FOUR M3 MACHINE SCREWS TO ATTACH THE INTERFACE PCB.

Figure 24. Physical Diagram for Mounting the ADIS16448/PCBZ

Figure 25 provides the pin assignments for the interface board.

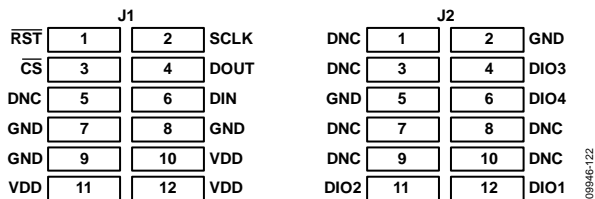


Figure 25. J1/J2 Pin Assignments for Interface PCB

### Installation

The following steps provide an example installation process for using these three components:

- Drill and tap M2 and M3 holes in the system frame, according to the locations in Figure 24.
- Install the ADIS16448 using M2 machine screws. Use a mounting torque of 25 inch-ounces.
- Install the interface PCB using M3 machine screws.
- Connect J1 on the interface flex to the ADIS16448AMLZ connector.

- Connect J2 on the interface flex to J3 on the interface PCB. Note that J2 (interface flex) has 20 pins and J3 (interface PCB) has 24 pins. Make sure that Pin 1 on J2 (interface flex) connects to Pin 20 on J3 (interface PCB). J3 has a Pin 1 indicator to help guide this connection.
- Use J1 and J2 on the interface PCB to make the electrical connection with the system supply and embedded processor, using 12-pin, 1 mm ribbon cables. The following parts may be useful in building this type of cable: 3M Part Number 152212-0100-GB (ribbon crimp connector) and 3M Part Number 3625/12 (ribbon cable).

The C1/C2 pads on the interface PCB do not have capacitors on them, but these pads can support the suggested power supply capacitor of 10  $\mu$ F (see Figure 9).

### PC-BASED EVALUATION TOOLS

The EVAL-ADIS supports PC-based evaluation of the ADIS16448. Go to [www.analog.com/EVAL-ADIS](http://www.analog.com/EVAL-ADIS), to download the user guide (UG-287) and software (IMU evaluation).

### MOUNTING APPROACHES

The ADIS16448 supports both connector-up and connector-down mounting approaches. Figure 26 offers an example of a connector-up mounting approach, which uses a flexible interface cable for the electrical connection. The connector-up approach provides a simple mechanical design but requires the use of a flexible connector. When connecting to legacy systems that use other Analog Devices IMU products (ADIS163xx/ADIS164xx), the connector-up method may be the simplest approach for migrating to the ADIS16448. Figure 24 provide an example for the mechanical design that uses a connector-up mounting approach.

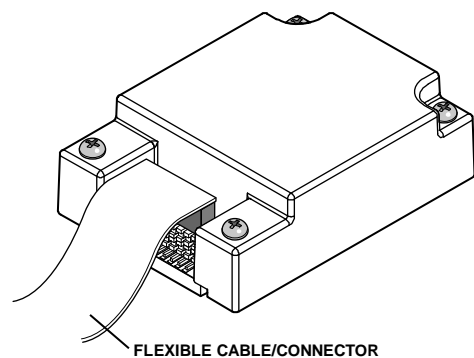


Figure 26. Connector-Up Mounting Example

Figure 27 provides an example of a connector-down mounting approach. The connector-down approach is more complex, from a PCB design perspective, but it eliminates the need for the flexible connector and only requires four machine screws to secure the package body to the PCB or bulkhead. This example uses countersunk, M2 × 0.4 mm × 12 mm machine screws, to secure the ADIS16448AMLZ to the PCB. The machine screws have a head diameter of 3.5 mm and a countersink angle of 45°. Figure 28 provides mechanical design details for a printed circuit board that supports a connector-down mounting approach. For more information and design tools, visit [www.analog.com/ADIS16448](http://www.analog.com/ADIS16448) and click Package and PCB Resources.

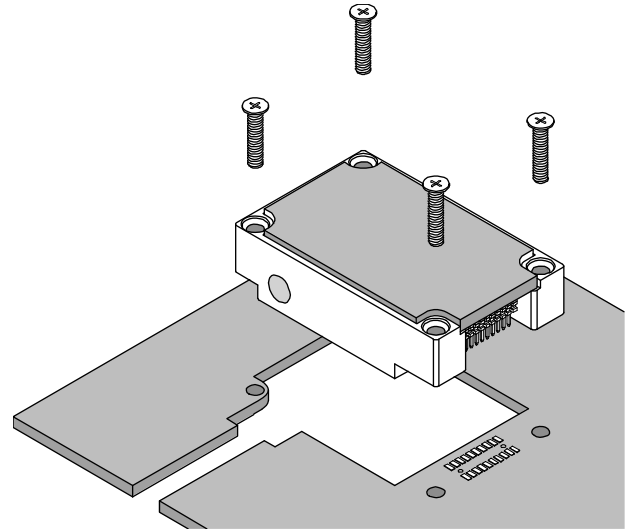


Figure 27. Connector-Down Mounting Example

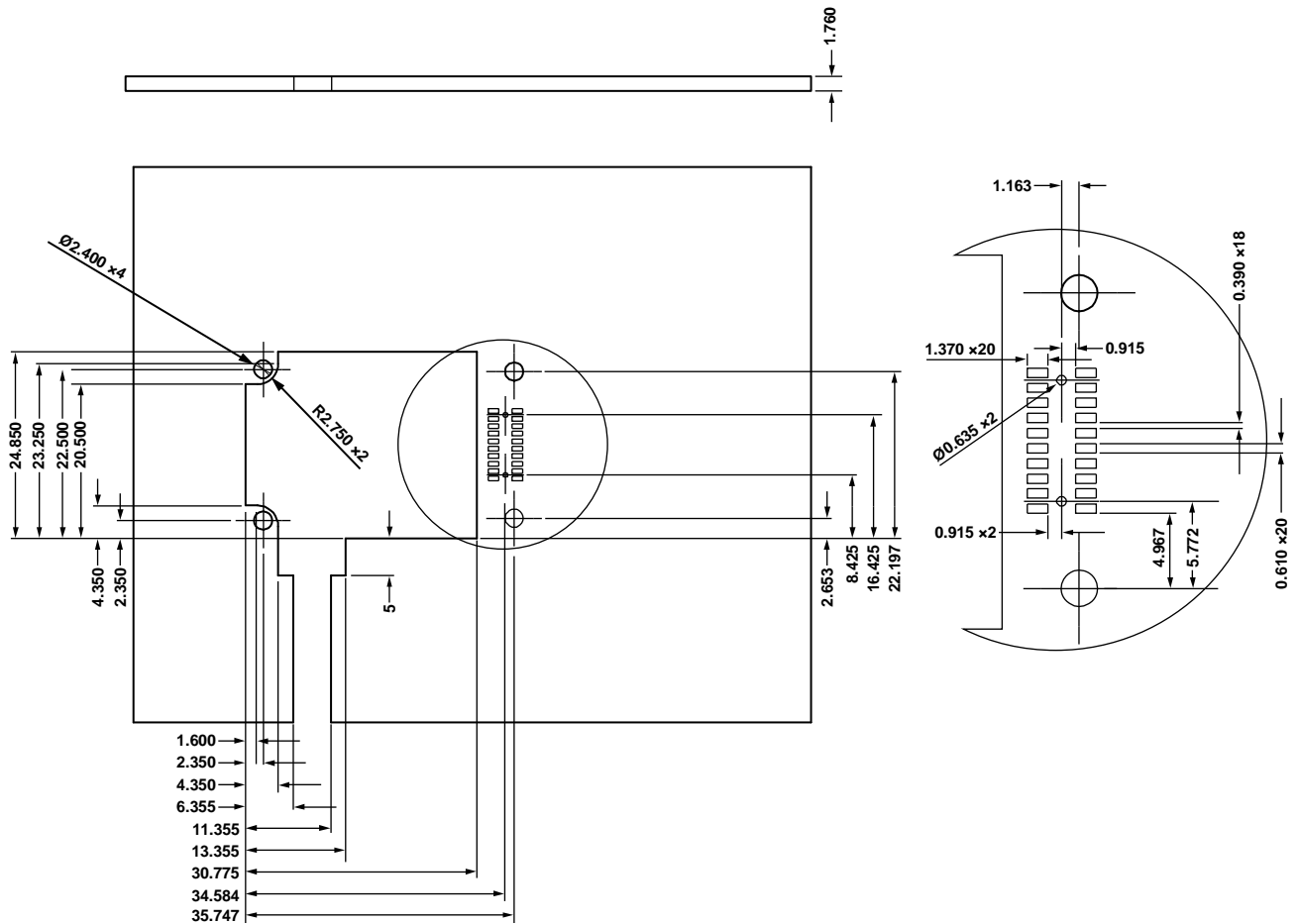


Figure 28. Connector-Down PCB Design Example

OUTLINE DIMENSIONS

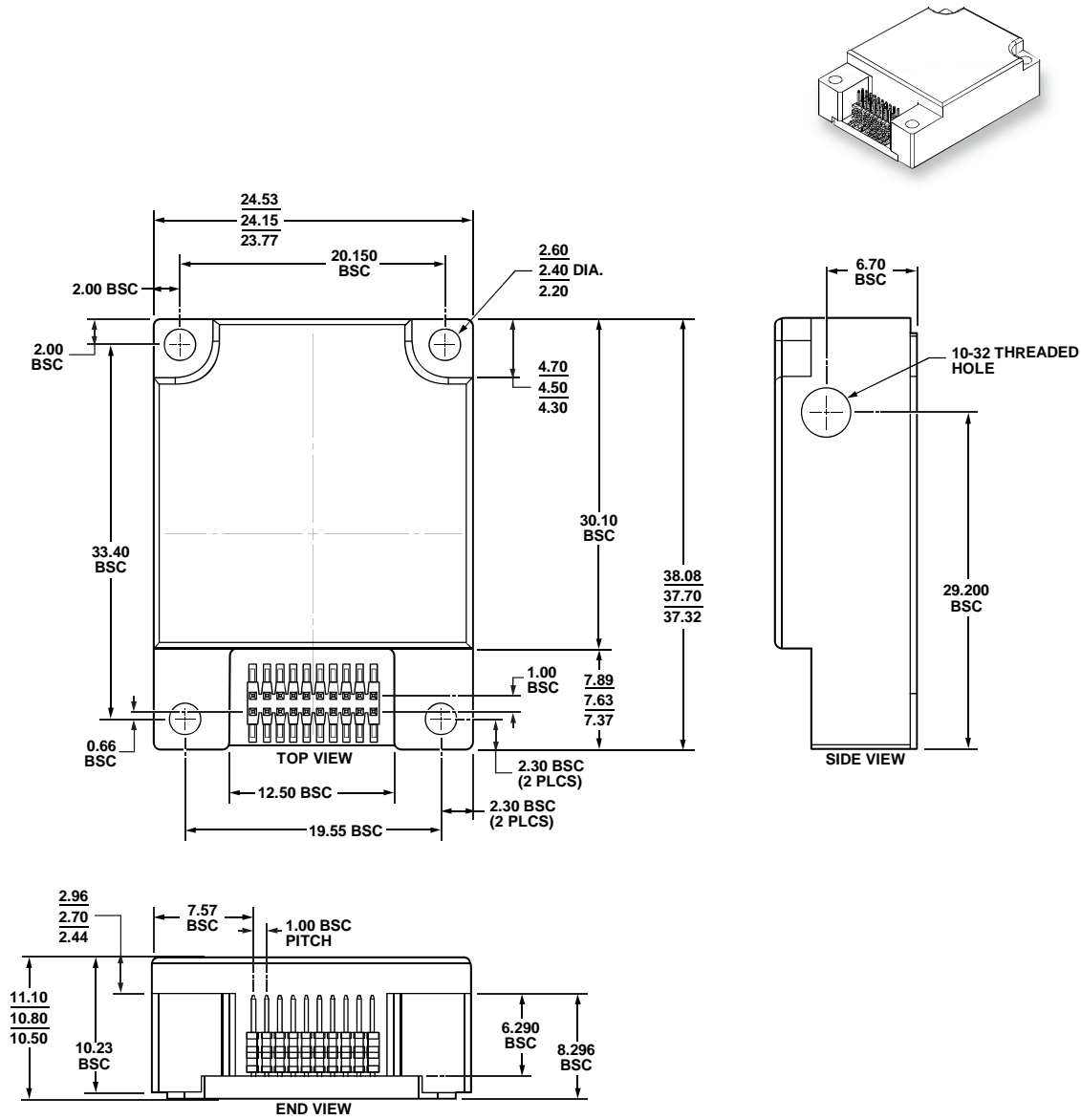


Figure 29. 20-Lead Module with Connector Interface (ML-20-2)  
Dimensions shown in millimeters

05-14207-2-C

ORDERING GUIDE

Model <sup>1</sup>	Temperature Range	Package Description	Package Option
ADIS16448AMLZ	-40°C to +85°C	20-Lead Module with Connector Interface	ML-20-2
ADIS16448/PCBZ		Interface PCB	

<sup>1</sup> Z = RoHS Compliant Part.