

MicroStrain Sensing Product Datasheet

3DM-CV5-AHRS

Attitude and Heading Reference System

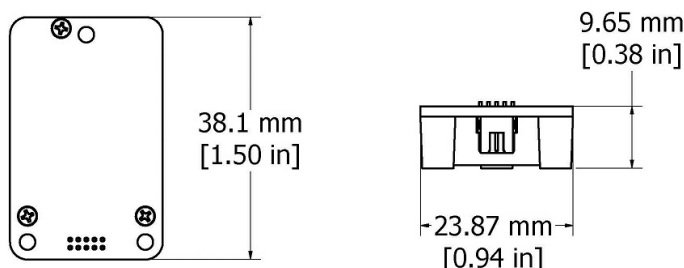


The LORD Sensing 3DM-CV5 family of industrial-grade, board-level inertial sensors provides a wide range of triaxial inertial measurements, computed attitude, and navigation solutions.

The Inertial Measurement Unit (IMU) includes direct measurement of acceleration, angular rate, Delta-theta, and Delta-velocity. Compensation options include automatic compensation for magnetic anomalies, gyro and accelerometer noise, and noise effects. In models that include computed outputs, sensor measurements are processed through an auto-adaptive estimation filter algorithm to produce high accuracy computed outputs under dynamic conditions. The computed outputs vary between models and can include roll, pitch, and yaw. All sensors are fully temperature-compensated and calibrated over the operating temperature. Micro-Electro-Mechanical System (MEMS) technology allows for highly accurate, small, light-weight devices.

SensorConnect software is a user friendly program for device configuration. MIP Monitor (MicroStrain Internet Protocol) can also be used. Both packages provide for device configuration, live data monitoring, and recording. Alternatively, the MIP Data Communications Protocol is available for development of custom interfaces and easy OEM integration.

The sensor operates independent of computer platform, operating system, or coding language.



PRODUCT HIGHLIGHTS

- Triaxial accelerometer, gyroscope, magnetometer, and temperature sensors achieve the optimal combination of measurement qualities
- Dual on-board processors run a new Auto-Adaptive Extended Kalman Filter (EKF) for outstanding dynamic attitude estimates

FEATURES AND BENEFITS

BEST IN CLASS PERFORMANCE

- Bias tracking, error estimation, threshold flags, and adaptive noise modeling allow for fine tuning to conditions in each application
- Smallest and lightest industrial AHRS with Adaptive Kalman Filter available
- High-performance, low-cost solution
- Direct PCB mount or chassis mount with ribbon cable
- Precision mounting alignment features

EASE OF USE

- SensorConnect enables simple device configuration, live data monitoring, and recording
- Hardware development kit available
- The MSCL API allows easy integration with C++, Python, .NET, C#, Visual Basic, LabVIEW and MATLAB environments
- MIP open byte level communication protocol

COST EFFECTIVE

- Out-of-the box solution reduces development time
- Volume discounts

APPLICATIONS

- Unmanned vehicle navigation
- Robotics
- Platform stabilization, artificial horizon
- Health and usage monitoring of vehicles



ENGINEERING YOUR SUCCESS.

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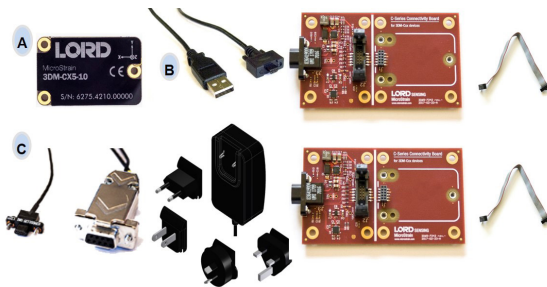
Attitude and Heading Reference System (AHRS)

Specifications

General			
Integrated sensors	Triaxial accelerometer, triaxial gyroscope, triaxial magnetometer, pressure altimeter, temperature sensors		
Data outputs	Inertial Measurement Unit (IMU) outputs: acceleration, angular rate, magnetic field, ambient pressure, Delta-theta, Delta-velocity Computed outputs Extended Kalman Filter (EKF): filter status, timestamp, attitude estimates (in Euler angles, quaternion, orientation matrix), linear and compensated acceleration, bias compensated angular rate, pressure altitude, gravity-free linear acceleration, gyroscope and accelerometer bias, scale factors and uncertainties, gravity and magnetic models, and more. Complementary Filter (CF): attitude estimates (in Euler angles, quaternion, orientation matrix) stabilized, north and up vectors, GNSS correlation timestamp		
Inertial Measurement Unit (IMU) Sensor Outputs			
	Accelerometer	Gyroscope	Magnetometer
Measurement range	±8 g (standard) ±2 g, ±4 g, ±20 g, ±40 g (optional)	±500°/sec (standard) ±250°, ±1000°/sec (optional)	±8 Gauss
Non-linearity	±0.04% fs	±0.06% fs	±0.3% fs
Resolution	0.05 mg (+/- 8 g)	<0.003°/sec (500 dps)	--
Bias instability	±0.08 mg	8°/hr	--
Initial bias error	±0.004 g	±0.01°/sec	±0.003 Gauss
Scale factor stability	±0.05%	±0.05%	±0.1%
Noise density	100 µg/√Hz	0.0075°/sec/√Hz (500°/sec)	400 µGauss/√Hz
Alignment error	±0.05°	±0.08°	±0.05°
Adjustable bandwidth	225 Hz (max)	500 Hz (max)	--
Offset error over temperature	0.02% (typ)	0.01% (typ)	--
Gain error over temperature	0.05% (typ) ±0.2% (max)	0.1% (typ) ±0.4% (max)	--
IMU filtering	First stage sigma delta Analog to Digital Converter sampled at 1 kHz. Second stage user adjustable digital low pass filter.		
Sampling rate	1 kHz	4 kHz	100 Hz
IMU data output rate	1 Hz to 1 kHz (sensor direct mode)		
Pressure Altimeter			
Range	-1800 m to 10,000 m		
Resolution	< 0.1 m		
Noise density	0.01 hPa RMS		
Sampling rate	25 Hz		

Computed Outputs	
Attitude accuracy	EKF outputs: ±0.5° RMS roll and pitch, ±0.1° RMS heading (typ) CF outputs: ±0.8° RMS roll and pitch, ±2° RMS heading (typ)
Attitude heading range	360° about all axes
Attitude resolution	0.05°
Attitude repeatability	0.5°
Calculation update rate	500 Hz
Computed data output rate	EKF outputs: 1 Hz to 500 Hz CF outputs: 1 Hz to 1000 Hz
Operating Parameters	
Communication	USB 2.0 (full speed) TTL serial (3.0 V dc, 9,600 bps to 921,600 bps, default 115,200)
Power source	+3.2 to + 5.2 V dc
Power consumption	360 mW (typ), 500 mW (max)
Operating temperature	-40°C to +85°C
Mechanical shock limit	500g/1ms absolute maximum survivability*
Physical Specifications	
Dimensions	38 mm x 24 mm x 9.7 mm
Weight	11 grams
Enclosure material	Aluminum
MTBF	1,035,471 hours (Telcordia method GM/35C)
Regulatory compliance	ROHS, CE
Integration	
Connectors	Data/power output: Micro-D9 Samtec FTSH Series
Software	SensorConnect and MIP Monitor software included; Windows XP/Vista/7/8/10 compatible
Data Communications Protocol (DCP)	Protocol compatibility across GX3, GX4, RQ1, GQ4, GX5 CX5 and CV5 product families
Software development kit	MicroStrain Communication Library (MSCL) open source license includes full documentation and sample code
Hardware development kit	Option purchased separately

*Prolonged exposure to >2x full scale range can result in permanent damage. See manual for details



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