

## FEATURES

**Triaxial, digital gyroscope,  $\pm 100^\circ/\text{sec}$  dynamic range**  
 $\pm 0.05^\circ$  axis to axis misalignment error  
 $\pm 0.25^\circ$  axis to package misalignment error  
 $1.8^\circ/\text{hr}$  in run bias stability  
 $0.09^\circ/\sqrt{\text{hr}}$  angular random walk  
**Triaxial, digital accelerometer,  $\pm 8 g$**   
 $3.6 \mu g$  in run bias stability  
**Triaxial, delta angle and delta velocity outputs**  
**Factory calibrated sensitivity, bias, and axial alignment**  
 Calibration temperature range:  $-40^\circ\text{C}$  to  $+85^\circ\text{C}$   
**Serial peripheral interface (SPI) compatible**  
**Programmable operation and control**  
 Automatic and manual bias correction controls  
 4 finite impulse response (FIR) filter banks,  
 120 configurable taps  
 Digital input/output (I/O): data ready, external clock  
 Sample clock options: internal, external, or scaled  
 On demand self test of inertial sensors  
**Single-supply operation: 3.0 V to 3.6 V**  
**2000 g shock survivability**  
**Operating temperature range:  $-40^\circ\text{C}$  to  $+105^\circ\text{C}$**

## APPLICATIONS

Precision instrumentation, stabilization  
 Guidance, navigation, control  
 Avionics, unmanned vehicles  
 Precision autonomous machines, robotics

## GENERAL DESCRIPTION

The [ADIS16490](#) is a complete inertial system that includes a triaxis gyroscope and a triaxis accelerometer. Each inertial sensor in the [ADIS16490](#) 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 [ADIS16490](#) provides a simple, cost effective method for integrating accurate, multiaxis 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 structure provide a simple interface for data collection and configuration control.

The [ADIS16490](#) uses the same footprint and connector system as the [ADIS16375](#), [ADIS16480](#), [ADIS16485](#), and [ADIS16488A](#), which greatly simplifies the upgrade process. The [ADIS16490](#) is packaged in a module that is approximately  $47 \text{ mm} \times 44 \text{ mm} \times 14 \text{ mm}$  and includes a standard connector interface.

## FUNCTIONAL BLOCK DIAGRAM

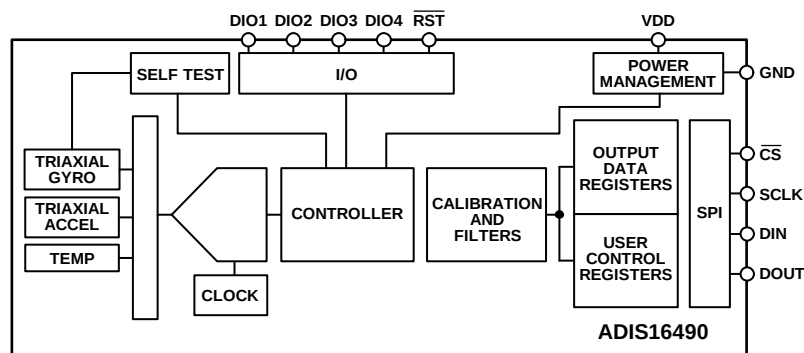


Figure 1.

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## REVISION HISTORY

### 9/2020—Rev. C to Rev. D

|                                                                                                                   |    |
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### 5/2019—Rev. B to Rev. C

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### 4/2017—Rev. 0 to Rev. A

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### 10/2016—Revision 0: Initial Version

## SPECIFICATIONS

$T_C = 25^\circ\text{C}$ ,  $V_{DD} = 3.3\text{ V}$ , angular rate =  $0^\circ/\text{sec}$ , dynamic range =  $\pm 100^\circ/\text{sec} \pm 1\text{ g}$ , unless otherwise noted.

Table 1.

| Parameter                           | Test Conditions/Comments                                          | Min       | Typ                     | Max | Unit                                     |
|-------------------------------------|-------------------------------------------------------------------|-----------|-------------------------|-----|------------------------------------------|
| <b>GYROSCOPES</b>                   |                                                                   |           |                         |     |                                          |
| Dynamic Range                       |                                                                   | $\pm 100$ |                         |     | $^\circ/\text{sec}$                      |
| Sensitivity                         | $x\_GYRO\_OUT$ and $x\_GYRO\_LOW$ (32-bit)                        |           | $7.6294 \times 10^{-8}$ |     | $^\circ/\text{sec}/\text{LSB}$           |
| Repeatability <sup>1</sup>          | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$               |           |                         | 0.5 | %                                        |
| Sensitivity Temperature Coefficient | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | $\pm 24$                |     | ppm/ $^\circ\text{C}$                    |
| Misalignment                        | Axis to axis <sup>2</sup>                                         |           | $\pm 0.05$              |     | Degrees                                  |
|                                     | Axis to frame (package)                                           |           | $\pm 0.25$              |     | Degrees                                  |
| Nonlinearity                        | Best fit straight line, full scale (FS) = $100^\circ/\text{sec}$  |           | 0.3                     |     | % FS                                     |
| <b>Bias</b>                         |                                                                   |           |                         |     |                                          |
| Repeatability <sup>1,3</sup>        | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | 0.05                    |     | $^\circ/\text{sec}$                      |
| In Run Bias Stability               | $1\sigma$                                                         |           | 1.8                     |     | $^\circ/\text{hr}$                       |
| Angular Random Walk                 | $1\sigma$                                                         |           | 0.09                    |     | $^\circ/\sqrt{\text{hr}}$                |
| Temperature Coefficient             | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | 0.0005                  |     | $^\circ/\text{sec}/^\circ\text{C}$       |
| Linear Acceleration Effect          | Any axis, $1\sigma$ (CONFIG[7] = 1)                               |           | 0.005                   |     | $^\circ/\text{sec}/\text{g}$             |
|                                     | Any axis, $1\sigma$ (CONFIG[7] = 0)                               |           | 0.015                   |     | $^\circ/\text{sec}/\text{g}$             |
| Vibration Rectification Error       |                                                                   |           | 0.0003                  |     | $^\circ/\text{sec}/\text{g}^2$           |
| <b>Noise</b>                        |                                                                   |           |                         |     |                                          |
| Output Noise                        | No filtering                                                      |           | 0.05                    |     | $^\circ/\text{sec rms}$                  |
| Rate Noise Density                  | $f = 10\text{ Hz to }40\text{ Hz}$ , no filtering                 |           | 0.002                   |     | $^\circ/\text{sec}/\sqrt{\text{Hz rms}}$ |
| -3 dB Bandwidth                     |                                                                   |           | 480                     |     | Hz                                       |
| Sensor Resonant Frequency           |                                                                   |           | 65                      |     | kHz                                      |
| <b>ACCELEROMETERS<sup>4</sup></b>   |                                                                   |           |                         |     |                                          |
| Dynamic Range                       | Each axis                                                         | $\pm 8$   |                         |     | $g$                                      |
| Sensitivity                         | $x\_ACCL\_OUT$ and $x\_ACCL\_LOW$ (32-bit)                        |           | $7.6294 \times 10^{-9}$ |     | $g/\text{LSB}$                           |
| Repeatability <sup>1</sup>          | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$               |           | 0.05                    | 0.2 | %                                        |
| Sensitivity Temperature Coefficient | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | $\pm 16$                |     | ppm/ $^\circ\text{C}$                    |
| Misalignment                        | Axis to axis                                                      |           | $\pm 0.035$             |     | Degrees                                  |
|                                     | Axis to frame (package)                                           |           | $\pm 0.25$              |     | Degrees                                  |
| Nonlinearity                        | Best fit straight line, $\pm 2\text{ g}$                          |           | 0.1                     |     | % FS                                     |
|                                     | Best fit straight line, $\pm 4\text{ g}$                          |           | 0.15                    |     | % FS                                     |
|                                     | Best fit straight line, $\pm 8\text{ g}$                          |           | 1.6                     |     | % FS                                     |
| <b>Bias</b>                         |                                                                   |           |                         |     |                                          |
| Repeatability <sup>1,3</sup>        | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | $\pm 3.5$               |     | mg                                       |
| In Run Stability                    | $1\sigma$                                                         |           | 3.6                     |     | $\mu\text{g}$                            |
| Velocity Random Walk                | $1\sigma$                                                         |           | 0.008                   |     | $\text{m}/\text{sec}/\sqrt{\text{hr}}$   |
| Temperature Coefficient             | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | $\pm 0.008$             |     | mg/ $^\circ\text{C}$                     |
| Repeatability                       | $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ , $1\sigma$   |           | 1                       |     | mg                                       |
| <b>Noise</b>                        |                                                                   |           |                         |     |                                          |
| Output Noise                        | No filtering                                                      |           | 0.5                     |     | mg rms                                   |
| Noise Density                       | $f = 10\text{ Hz to }40\text{ Hz}$ , no filtering                 |           | 16                      |     | $\mu\text{g}/\sqrt{\text{Hz rms}}$       |
| -3 dB Bandwidth                     |                                                                   |           | 750                     |     | Hz                                       |
| Sensor Resonant Frequency           |                                                                   |           | 2.5                     |     | kHz                                      |
| <b>TEMPERATURE SENSOR</b>           |                                                                   |           |                         |     |                                          |
| Scale Factor                        | Output = $0x0000$ at $25^\circ\text{C}$ ( $\pm 5^\circ\text{C}$ ) |           | 0.01429                 |     | $^\circ\text{C}/\text{LSB}$              |

| Parameter                          | Test Conditions/Comments                                                                                           | Min           | Typ        | Max | Unit            |
|------------------------------------|--------------------------------------------------------------------------------------------------------------------|---------------|------------|-----|-----------------|
| LOGIC INPUTS <sup>5</sup>          |                                                                                                                    |               |            |     |                 |
| Input Voltage                      |                                                                                                                    |               |            |     |                 |
| High, $V_{IH}$                     |                                                                                                                    | 2.0           |            |     | V               |
| Low, $V_{IL}$                      |                                                                                                                    |               |            | 0.8 | V               |
| $\overline{RST}$ Pulse Width       |                                                                                                                    | 1             |            |     | $\mu s$         |
| Input Current                      |                                                                                                                    |               |            |     |                 |
| Logic 1, $I_{IH}$                  | $V_{IH} = 3.3\text{ V}$                                                                                            |               |            | 10  | $\mu A$         |
| Logic 0, $I_{IL}$                  | $V_{IL} = 0\text{ V}$                                                                                              |               |            | 10  | $\mu A$         |
| All Pins Except $\overline{RST}$   |                                                                                                                    |               | 0.33       |     | $\mu A$         |
| $\overline{RST}$ Pin               |                                                                                                                    |               | 10         |     | mA              |
| Input Capacitance, $C_{IN}$        |                                                                                                                    |               | 10         |     | pF              |
| DIGITAL OUTPUTS <sup>5</sup>       |                                                                                                                    |               |            |     |                 |
| Output Voltage                     |                                                                                                                    |               |            |     |                 |
| High, $V_{OH}$                     | $I_{SOURCE} = 0.5\text{ mA}$                                                                                       | 2.4           |            |     | V               |
| Low, $V_{OL}$                      | $I_{SINK} = 2.0\text{ mA}$                                                                                         |               |            | 0.4 | V               |
| FLASH MEMORY                       |                                                                                                                    |               |            |     |                 |
| Data Retention <sup>7</sup>        | Endurance <sup>6</sup><br>$T_J = 85^\circ C$                                                                       | 100,000<br>20 |            |     | Cycles<br>Years |
| FUNCTIONAL TIMES <sup>8</sup>      |                                                                                                                    |               |            |     |                 |
| Power-On Start-Up Time             | Time until data is available                                                                                       |               | 230        |     | ms              |
| Reset Recovery Time                | GLOBAL_CMD register, Bit 7 = 1 (see Table 142)<br>$\overline{RST}$ pulled low <sup>9</sup> , then restored to high |               | 190<br>230 |     | ms<br>ms        |
| Flash Memory Update Time           |                                                                                                                    |               | 1237       |     | ms              |
| Self Test Time                     | GLOBAL_CMD[1] = 1 (see Table 129)                                                                                  |               | 40         |     | ms              |
| CONVERSION RATE                    |                                                                                                                    |               | 4.25       |     | kSPS            |
| Initial Clock Accuracy             |                                                                                                                    |               | 0.02       |     | %               |
| Temperature Coefficient            |                                                                                                                    |               | 40         |     | ppm/ $^\circ C$ |
| Sync Input Clock                   |                                                                                                                    | 3.0           |            | 4.5 | kHz             |
| POWER SUPPLY, VDD                  |                                                                                                                    |               |            |     |                 |
| Power Supply Current <sup>10</sup> | Operating voltage range<br>Normal mode, $V_{DD} = 3.3\text{ V}$ , $\mu + \sigma$                                   | 3.0           | 89         | 3.6 | V<br>mA         |

<sup>1</sup> The repeatability specifications represent a projection for long-term aging, which is derived from the drift behaviors that a sample of units exhibited throughout their 1000-hour, 110 $^\circ C$  high temperature operating life (HTOL).

<sup>2</sup> Cross axis sensitivity is the sine of this number.

<sup>3</sup> Bias repeatability describes a long-term behavior over a variety of conditions. Short-term repeatability relates to the in run bias stability and noise density specifications.

<sup>4</sup> All specifications associated with the accelerometers relate to the full-scale range of  $\pm 8\text{ g}$ .

<sup>5</sup> The digital I/O signals use a 3.3 V system.

<sup>6</sup> Endurance is qualified as per JEDEC Standard 22, Method A117, measured at  $-40^\circ C$ ,  $+25^\circ C$ ,  $+85^\circ C$ , and  $+125^\circ C$ .

<sup>7</sup> The data retention specification assumes a junction temperature ( $T_J$ ) of  $85^\circ C$  per JEDEC Standard 22, Method A117. Data retention lifetime decreases with  $T_J$ .

<sup>8</sup> These times do not include thermal settling and internal filter response times, which may affect overall accuracy.

<sup>9</sup> The  $\overline{RST}$  line must be in a low state for at least 10  $\mu s$  to ensure a proper reset initiation and recovery.

<sup>10</sup> Supply current transients can reach 250 mA during initial startup or reset recovery.

**TIMING SPECIFICATIONS**

T<sub>C</sub> = 25°C, VDD = 3.3 V, unless otherwise noted.

**Table 2.**

| Parameter                         | Description                                                   | Min <sup>1</sup> | Typ | Max <sup>1</sup> | Unit |
|-----------------------------------|---------------------------------------------------------------|------------------|-----|------------------|------|
| f <sub>SCLK</sub>                 | Serial clock                                                  | 0.01             |     | 15               | MHz  |
| t <sub>STALL</sub> <sup>2</sup>   | Stall period between data                                     | 5                |     |                  | μs   |
| t <sub>CLS</sub>                  | Serial clock low period                                       | 31               |     |                  | ns   |
| t <sub>CHS</sub>                  | Serial clock high period                                      | 31               |     |                  | ns   |
| t <sub>CS</sub>                   | Chip select to clock edge                                     | 32               |     |                  | ns   |
| t <sub>DAV</sub>                  | DOUT valid after SCLK edge                                    |                  |     | 10               | ns   |
| t <sub>DSU</sub>                  | DIN setup time before SCLK rising edge                        | 2                |     |                  | ns   |
| t <sub>DHD</sub>                  | DIN hold time after SCLK rising edge                          | 2                |     |                  | ns   |
| t <sub>DR</sub> , t <sub>DF</sub> | DOUT rise/fall times, ≤100 pF loading                         |                  | 3   | 8                | ns   |
| t <sub>DSOE</sub>                 | $\overline{\text{CS}}$ assertion to data out active           | 0                |     | 11               | ns   |
| t <sub>HD</sub>                   | SCLK edge to data out invalid                                 | 0                |     |                  | ns   |
| t <sub>SFS</sub>                  | Last SCLK edge to $\overline{\text{CS}}$ deassertion          | 32               |     |                  | ns   |
| t <sub>DSHI</sub>                 | $\overline{\text{CS}}$ deassertion to data out high impedance | 0                |     | 9                | ns   |
| t <sub>INV</sub>                  | Data invalid time                                             |                  | 11  | 15               | μs   |
| t <sub>1</sub>                    | Input sync pulse width                                        | 5                |     |                  | μs   |
| t <sub>2</sub>                    | Input sync to data invalid                                    |                  | 233 |                  | μs   |
| t <sub>3</sub>                    | Input sync period <sup>3</sup>                                | 222.2            |     |                  | μs   |

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

<sup>2</sup> See Table 3 for exceptions to the stall time rating. Note that an insufficient stall time results in reading all 0s for the register attempting to be read.

<sup>3</sup> This measurement represents the inverse of the maximum frequency for the input sample clock: 4500 Hz.

**Register Specific Stall Times****Table 3.**

| Parameter   | Description                         | Min <sup>1</sup> | Typ | Max | Unit |
|-------------|-------------------------------------|------------------|-----|-----|------|
| STALL TIME  |                                     |                  |     |     |      |
| FNCTIO_CTRL | Configure DIOx functions            | 340              |     |     | μs   |
| FILTR_BNK_0 | Enable/select FIR filter banks      | 65               |     |     | μs   |
| FILTR_BNK_1 | Enable/select FIR filter banks      | 65               |     |     | μs   |
| NULL_CNFG   | Configure autonull bias function    | 71               |     |     | μs   |
| SYNC_SCALE  | Configure input clock scale factor  | 340              |     |     | μs   |
| DEC_RATE    | Configure decimation rate           | 340              |     |     | μs   |
| GPIO_CTRL   | Configure general-purpose I/O lines | 45               |     |     | μs   |
| CONFIG      | Configure miscellaneous functions   | 45               |     |     | μs   |
| GLOB_CMD[1] | On demand self test                 | 40               |     |     | ms   |
| GLOB_CMD[3] | Flash memory update                 | 1.24             |     |     | sec  |
| GLOB_CMD[6] | Factory calibration restore         | 350              |     |     | μs   |
| GLOB_CMD[7] | Software reset                      | 130              |     |     | ms   |

<sup>1</sup> Monitoring the data ready signal (see Table 131 for FNCTIO\_CTRL configuration) for the return of regular pulsing can help minimize system wait times.

Timing Diagrams

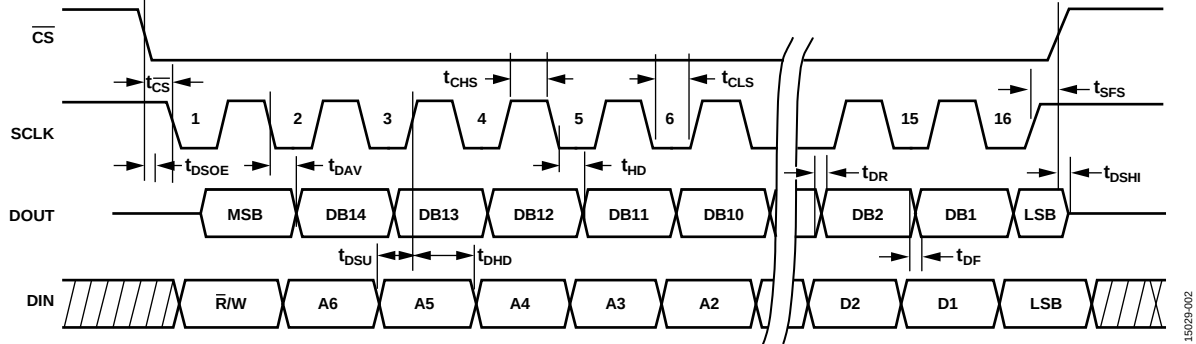


Figure 2. SPI Timing and Sequence

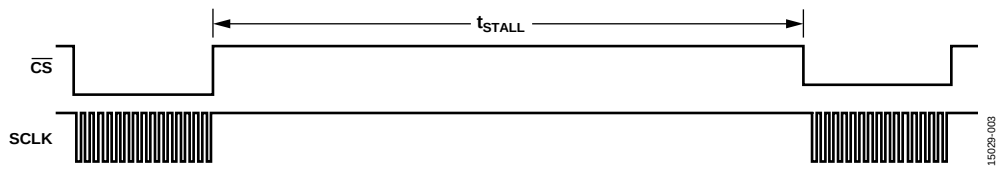


Figure 3. Stall Time and Data Rate

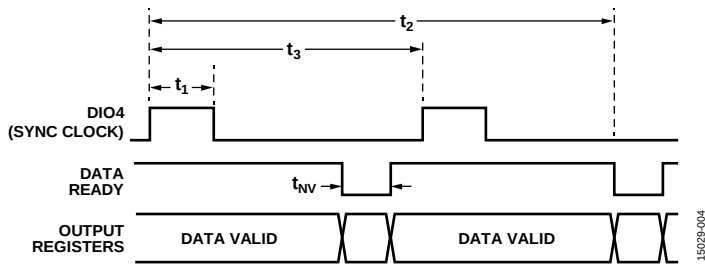


Figure 4. Input Clock Timing Diagram, FNCTIO\_CTRL[7:4] = 0xFD

## ABSOLUTE MAXIMUM RATINGS

Table 4.

| Parameter                              | Rating                |
|----------------------------------------|-----------------------|
| Acceleration                           |                       |
| Any Axis, Unpowered                    | 1500 <i>g</i>         |
| Any Axis, Powered                      | 1500 <i>g</i>         |
| VDD to GND                             | –0.3 V to +3.6 V      |
| Digital Input Voltage to GND           | –0.3 V to VDD + 0.2 V |
| Digital Output Voltage to GND          | –0.3 V to VDD + 0.2 V |
| Operating Temperature Range            | –40°C to +105°C       |
| Storage Temperature Range <sup>1</sup> | –55°C to +150°C       |
| Barometric Pressure                    | 2 bar                 |

<sup>1</sup> Extended exposure to temperatures that are lower than –40°C or higher than +105°C can adversely affect the accuracy of the factory calibration.

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

## THERMAL RESISTANCE

Thermal performance is directly linked to printed circuit board (PCB) design and operating environment. Careful attention to PCB thermal design is required.

$\theta_{JA}$  is the natural convection junction to ambient thermal resistance measured in a one cubic foot sealed enclosure.

$\theta_{JC}$  is the junction to case thermal resistance.

The ADIS16490 is a multichip module, which includes many active components. The values in Table 5 identify the thermal response of the hottest component inside of the ADIS16490, with respect to the overall power dissipation of the module.

This approach enables a simple method for predicting the temperature of the hottest junction, based on either ambient or case temperature.

For example, when the ambient temperature is 70°C, the hottest junction inside of the ADIS16490 is 76.7°C.

$$T_J = \theta_{JA} \times V_{DD} \times I_{DD} + 70^\circ\text{C}$$

$$T_J = 22.8^\circ\text{C/W} \times 3.3 \text{ V} \times 0.089 \text{ A} + 70^\circ\text{C}$$

$$T_J = 76.7^\circ\text{C}$$

Table 5. Package Characteristics

| Package Type         | $\theta_{JA}$ | $\theta_{JC}$ | Device Weight |
|----------------------|---------------|---------------|---------------|
| ML-24-9 <sup>1</sup> | 30.7°C/W      | 20.9°C/W      | 42 g          |

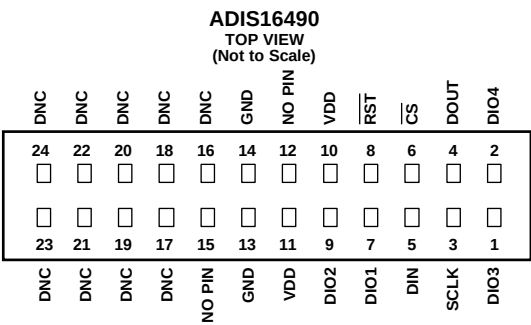
<sup>1</sup> Thermal impedance simulated values come from a case when 4 M2 × 0.4 mm machine screws (torque = 20 inch-ounces) secure the ADIS16490 to the printed circuit board.

## 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 PINOUT FOR THE MATING SOCKET CONNECTOR.
  - 2. THE ACTUAL CONNECTOR PINS ARE NOT VISIBLE FROM THE TOP VIEW.
  - 3. MATING CONNECTOR: SAMTEC CLM-112-02 OR EQUIVALENT.
  - 4. DNC = DO NOT CONNECT.
  - 5. PIN 12 AND PIN 15 ARE NOT PHYSICALLY PRESENT.

Figure 5. Pin Configuration

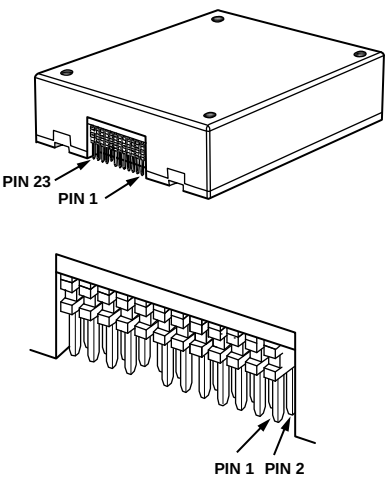


Figure 6. Axial Orientation (Top Side Facing Up)

Table 6. Pin Function Descriptions

| Pin No.      | Mnemonic | Type           | Description                                                                            |
|--------------|----------|----------------|----------------------------------------------------------------------------------------|
| 1            | DIO3     | Input/output   | Configurable Digital Input/Output 3.                                                   |
| 2            | DIO4     | Input/output   | Configurable Digital Input/Output 4.                                                   |
| 3            | SCLK     | Input          | SPI Serial Clock.                                                                      |
| 4            | DOUT     | Output         | SPI Data Output. Clocks output on the SCLK falling edge.                               |
| 5            | DIN      | Input          | SPI Data Input. Clocks input on the SCLK rising edge.                                  |
| 6            | CS       | Input          | SPI Chip Select.                                                                       |
| 7            | DIO1     | Input/output   | Configurable Digital Input/Output 1.                                                   |
| 8            | RST      | Input          | Reset.                                                                                 |
| 9            | DIO2     | Input/output   | Configurable Digital Input/Output 2.                                                   |
| 10, 11       | VDD      | Supply         | Power Supply.                                                                          |
| 12, 15       | NO PIN   | Not applicable | These pins are not physically present.                                                 |
| 13, 14       | GND      | Supply         | Power Ground.                                                                          |
| 16 to 22, 24 | DNC      | Not applicable | Do Not Connect. Do not connect to these pins.                                          |
| 23           | DNC      | Not applicable | Do Not Connect. Do not connect to this pin. This pin can tolerate connection to 3.3 V. |



## TYPICAL PERFORMANCE CHARACTERISTICS

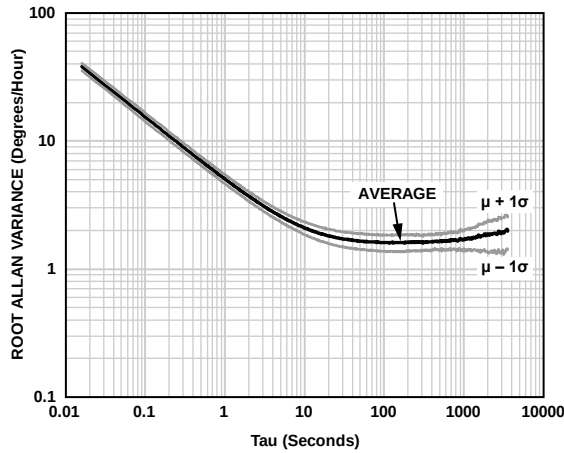


Figure 7. Gyroscope Root Allan Variance

15029-307

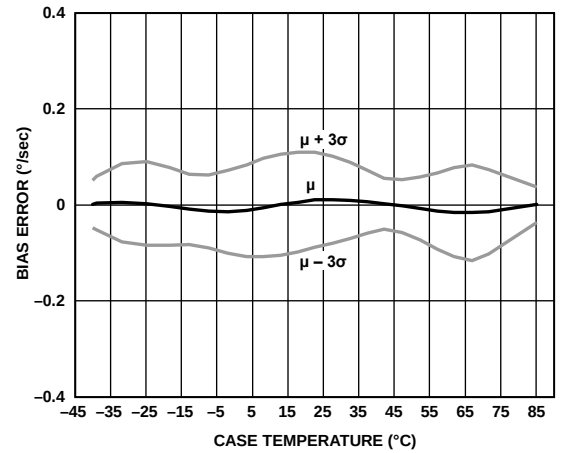


Figure 10. Gyroscope Bias Error, -40°C to +85°C, 1°C/min

15029-310

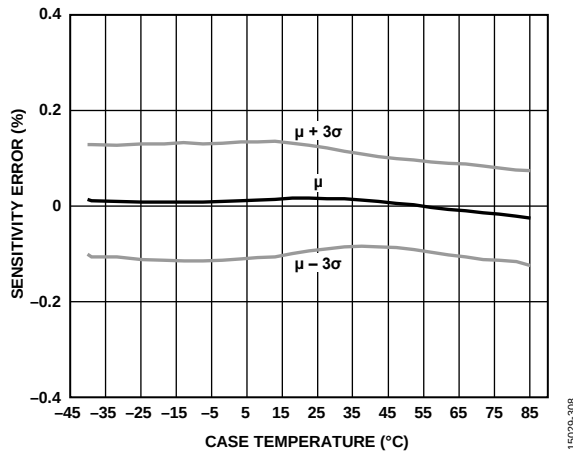


Figure 8. Gyroscope Sensitivity Error, -40°C to +85°C, 1°C/min

15029-308

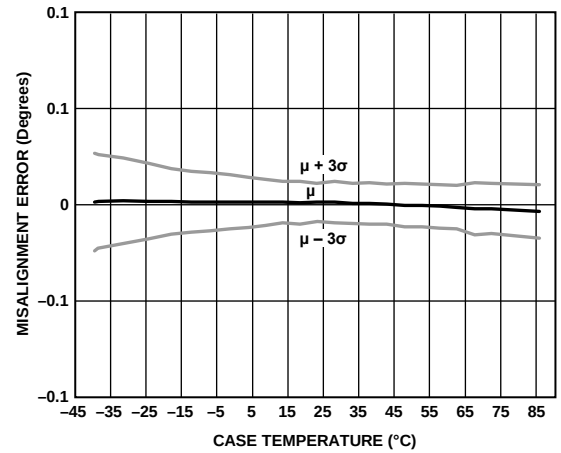


Figure 11. Gyroscope Axis to Axis Misalignment Error, -40°C to +85°C

15029-313

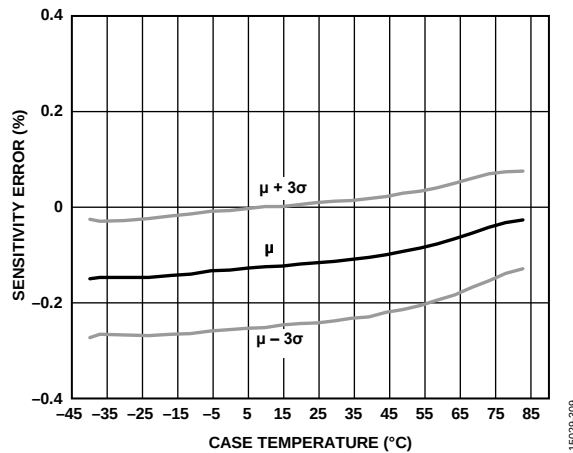
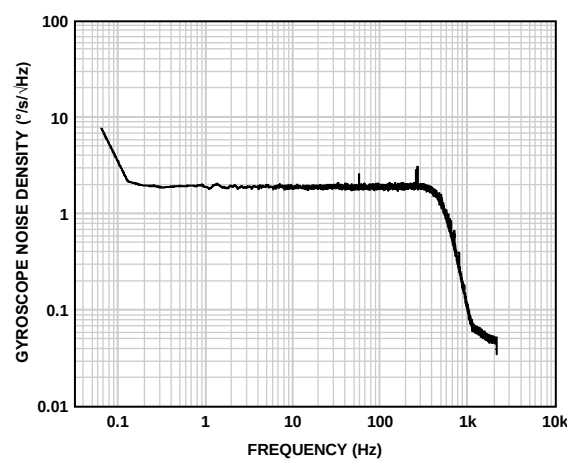


Figure 9. Gyroscope Sensitivity Error, +85°C to -40°C, 1°C/min

15029-309

Figure 12. Gyroscope Noise Density,  $T_c = 25^\circ\text{C}$ 

15029-314

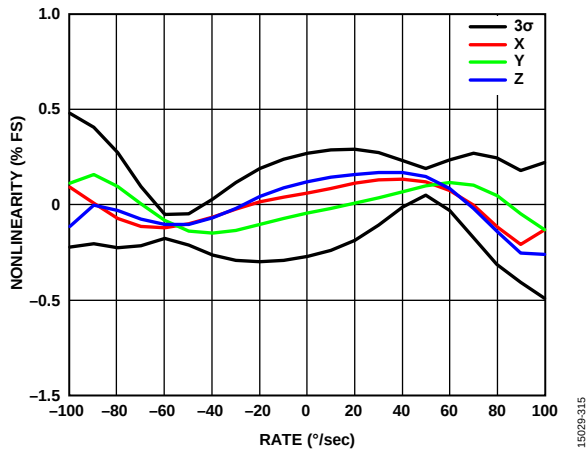


Figure 13. Gyroscope Nonlinearity

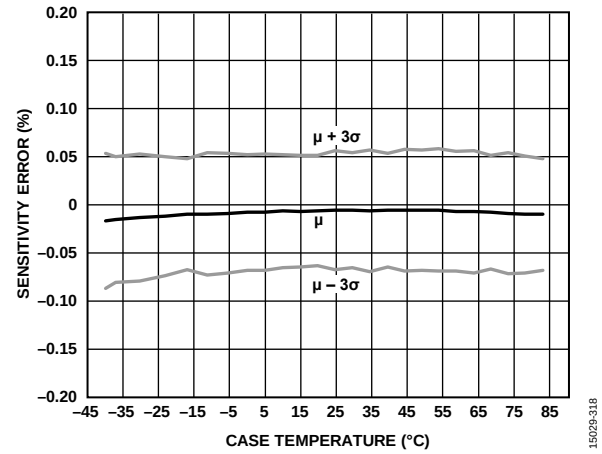


Figure 16. Accelerometer Sensitivity Error, +85°C to -40°C, 1°C/min

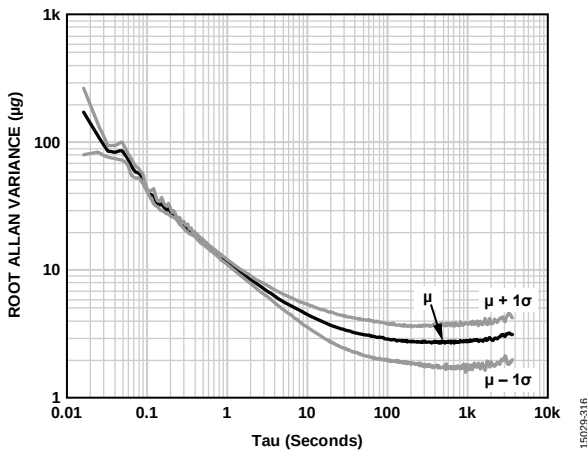


Figure 14. Accelerometer Root Allan Variance, 25°C

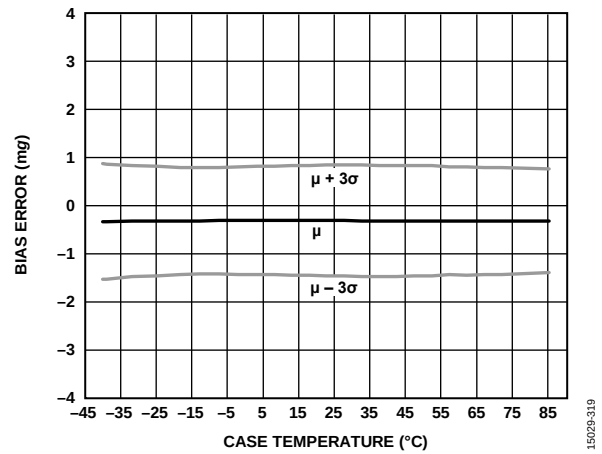


Figure 17. Accelerometer Bias Error, -40°C to +85°C, 1°C/min

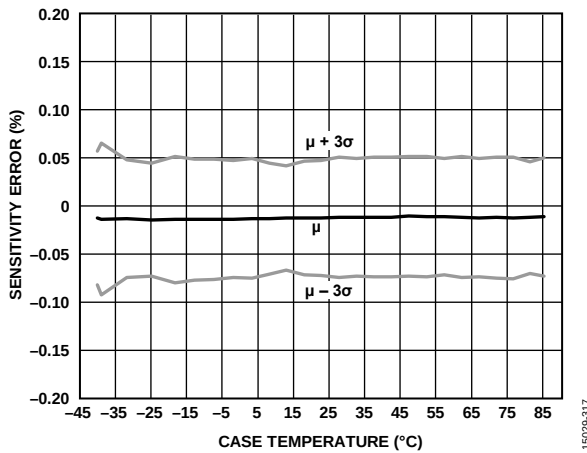


Figure 15. Accelerometer Sensitivity Error, -40°C to +85°C, 1°C/min

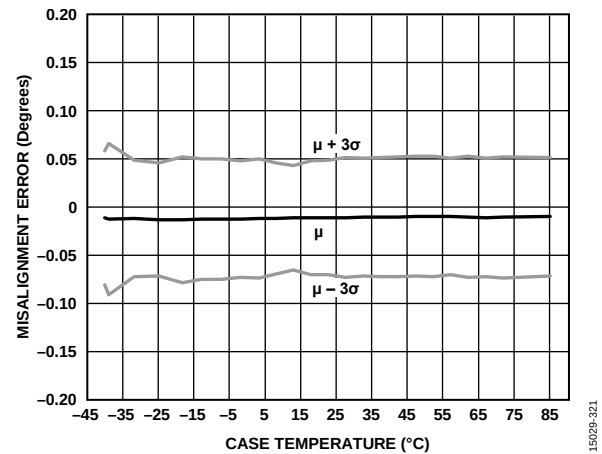


Figure 18. Accelerometer Axis to Axis Misalignment Error, -40°C to +85°C

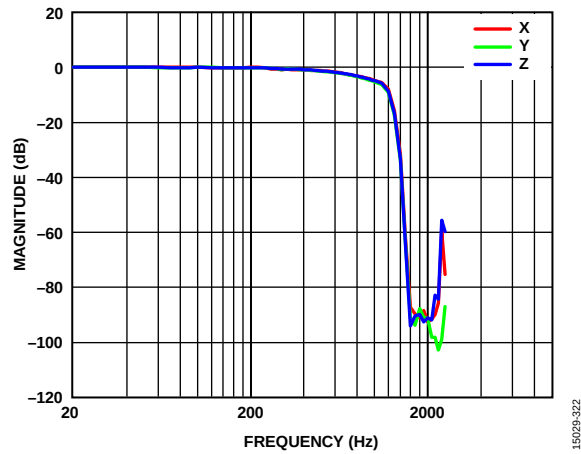


Figure 19. Accelerometer Vibration Response (Swept Sine, 2 g peak)

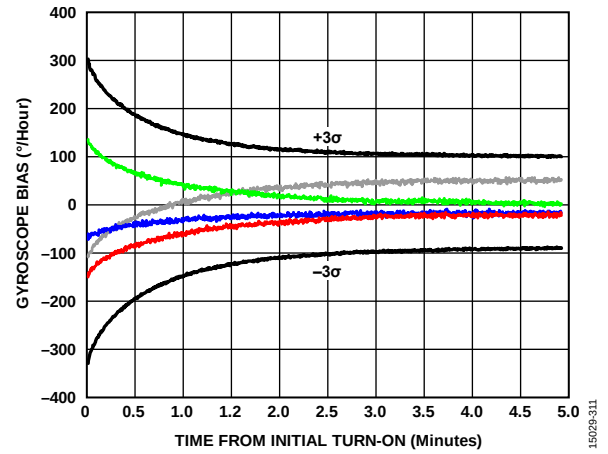


Figure 21. Gyroscope Bias vs. Time from Initial Turn-On

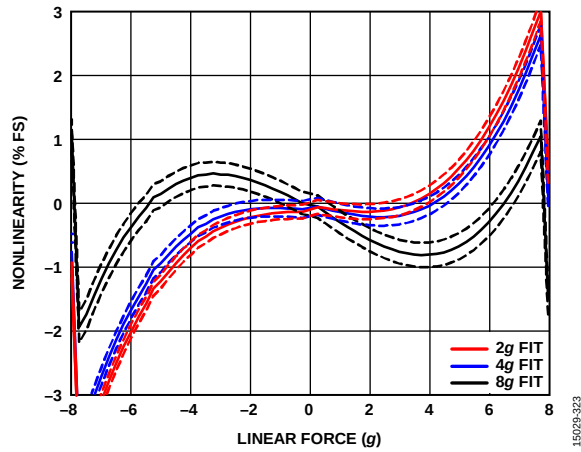


Figure 20. Accelerometer Nonlinearity (FIT Is Curve Fit)

## THEORY OF OPERATION

The ADIS16490 is an autonomous sensor system. A power-on self test begins automatically after the voltage on the power supply pins reaches a minimum safe level as defined by Table 1. After the automatic power-on self test, the ADIS16490 begins sampling, processing, and loading calibrated sensor data into the output registers, which are accessible using the SPI port.

### INERTIAL SENSOR SIGNAL CHAIN

Figure 22 provides the basic signal chain for the inertial sensors in the ADIS16490, which processes data at a rate of 4250 SPS when using the internal sample clock. Using one of the external clock options in FNCTIO\_CTRL[7:4] (see Table 131) can provide flexibility in selecting this rate.

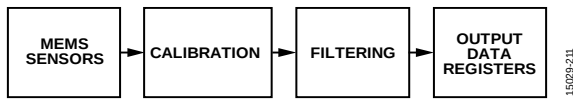


Figure 22. Signal Processing Diagram, Inertial Sensors

### Gyroscope Data Sampling

The ADIS16490 produces angular rate measurements around three orthogonal axes (x, y, and z). Figure 23 shows the basic signal flow for the production of x-axis gyroscope data (same as y-axis and z-axis). This signal chain contains two digital MEMS gyroscopes (X<sub>G1</sub> and X<sub>G2</sub>), which have their own ADC and sample clocks (f<sub>SGX1</sub> and f<sub>SGX2</sub> = 4100 Hz that produce data independently from each other. The sensor to sensor tolerance on this sample rate is ±200 SPS. Processing these data starts with combining (summation and rescale) the most recent sample from each gyroscope together by using an independent sample master frequency (f<sub>SM</sub>) clock (f<sub>SM</sub> = 4250 Hz, see Figure 23), which drives the rest of the digital signal processing (calibration, alignment, and filtering) for the gyroscopes and accelerometers.

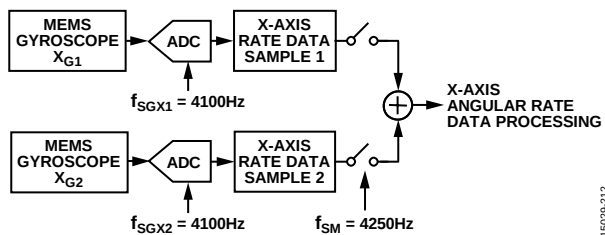


Figure 23. Gyroscope Data Sampling

### Accelerometer Data Sampling

The ADIS16490 produces linear acceleration measurements along the same orthogonal axes (x, y, and z) as the gyroscopes, using the same clock (f<sub>SM</sub>, see Figure 23 and Figure 24) that triggers data acquisition and subsequent processing of the gyroscope data.

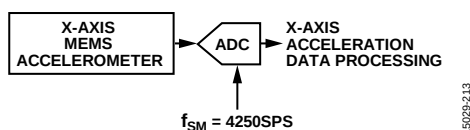


Figure 24. Accelerometer Data Sampling

### External Clock Options

The ADIS16490 offers two modes of operation to control data production with an external clock: sync mode and pulse per second (PPS) mode. In sync mode, the external clock directly controls the data sampling and production clock (f<sub>SM</sub> in Figure 23 and Figure 24). In PPS mode, users can provide a lower input clock rate (1 Hz to 128 Hz) and use a scale factor (SYNC\_SCALE register, see Table 141) to establish a data collection and processing rate that is between 3000 Hz and 4250 Hz for best performance.

### Inertial Sensor Calibration

The calibration function for the gyroscopes and the accelerometers has two components: factory calibration and user calibration (see Figure 25).

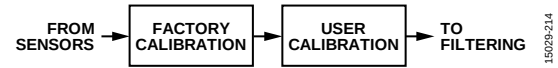


Figure 25. Gyroscope Calibration Processing

### Gyroscope Factory Calibration

Gyroscope factory calibration applies the following correction formula to the data of each gyroscope:

$$\begin{bmatrix} \omega_{XC} \\ \omega_{YC} \\ \omega_{ZC} \end{bmatrix} = \begin{bmatrix} m_{11} & m_{12} & m_{13} \\ m_{21} & m_{22} & m_{23} \\ m_{31} & m_{32} & m_{33} \end{bmatrix} \times \begin{bmatrix} \omega_X \\ \omega_Y \\ \omega_Z \end{bmatrix} + \begin{bmatrix} b_X \\ b_Y \\ b_Z \end{bmatrix} + \begin{bmatrix} g_{11} & g_{12} & g_{13} \\ g_{21} & g_{22} & g_{23} \\ g_{31} & g_{32} & g_{33} \end{bmatrix} \times \begin{bmatrix} a'_X \\ a'_Y \\ a'_Z \end{bmatrix} \quad (1)$$

where:

$\omega_{XC}$ ,  $\omega_{YC}$ , and  $\omega_{ZC}$  are the postcalibration gyroscope data.

$m_{11}$ ,  $m_{12}$ ,  $m_{13}$ ,  $m_{21}$ ,  $m_{22}$ ,  $m_{23}$ ,  $m_{31}$ ,  $m_{32}$ , and  $m_{33}$  are the scale and alignment correction factors.

$\omega_X$ ,  $\omega_Y$ , and  $\omega_Z$  are the precalibration gyroscope data.

$b_X$ ,  $b_Y$ , and  $b_Z$  are the bias correction factors.

$g_{11}$ ,  $g_{12}$ ,  $g_{13}$ ,  $g_{21}$ ,  $g_{22}$ ,  $g_{23}$ ,  $g_{31}$ ,  $g_{32}$ , and  $g_{33}$  are the linear g correction factors.

$a'_X$ ,  $a'_Y$ , and  $a'_Z$  are the postcalibration accelerometer data.

All the correction factors in each matrix/array are derived from direct observation of the response of each gyroscope to a variety of rotation rates at multiple temperatures across the calibration temperature range ( $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ ). These correction factors are stored in the flash memory bank, but they are not available for observation. CONFIG[7] provides an on/off control for the linear g compensation (see Table 135). See Figure 46 for more details on the user calibration options that are available for the gyroscopes.

### Accelerometer Factory Calibration

The accelerometer factory calibration applies the following correction formulas to the data of each accelerometer:

$$\begin{bmatrix} a'_X \\ a'_Y \\ a'_Z \end{bmatrix} = \begin{bmatrix} m_{11} & m_{12} & m_{13} \\ m_{21} & m_{22} & m_{23} \\ m_{31} & m_{32} & m_{33} \end{bmatrix} \times \begin{bmatrix} a_X \\ a_Y \\ a_Z \end{bmatrix} + \begin{bmatrix} b_X \\ b_Y \\ b_Z \end{bmatrix} + \begin{bmatrix} 0 & p_{12} & p_{13} \\ p_{21} & 0 & p_{23} \\ p_{31} & p_{32} & 0 \end{bmatrix} \times \begin{bmatrix} \omega_{XC}^2 \\ \omega_{YC}^2 \\ \omega_{ZC}^2 \end{bmatrix} \quad (2)$$

where:

$a_X$ ,  $a_Y$ , and  $a_Z$  are the precalibration accelerometer data.

$a'_X$ ,  $a'_Y$ , and  $a'_Z$  are the postcalibration accelerometer data.

$m_{11}$ ,  $m_{12}$ ,  $m_{13}$ ,  $m_{21}$ ,  $m_{22}$ ,  $m_{23}$ ,  $m_{31}$ ,  $m_{32}$ , and  $m_{33}$  are the scale and alignment correction factors.

$b_X$ ,  $b_Y$ , and  $b_Z$  are the bias correction factors.

$0$ ,  $p_{12}$ ,  $p_{13}$ ,  $p_{21}$ ,  $0$ ,  $p_{23}$ ,  $p_{31}$ ,  $p_{32}$ , and  $0$  are the point of percussion correction factors

$\omega_{XC}^2$ ,  $\omega_{YC}^2$ , and  $\omega_{ZC}^2$  are the postcalibration gyroscope data (squared).

All the correction factors in each matrix/array are derived from direct observation of the response of each accelerometer to a variety of inertial test conditions at multiple temperatures across the calibration temperature range ( $-40^\circ\text{C} \leq T_C \leq +85^\circ\text{C}$ ). These correction factors are stored in the flash memory bank, but they are not available for observation. CONFIG[6] provides an on/off control for the point of percussion alignment (see Table 135). See Figure 47 for more details on the user calibration options that are available for the accelerometers.

### Filtering

After calibration, the data of each inertial sensor passes through two digital filters, both of which have user configurable attributes: FIR and decimation (see Figure 26).



Figure 26. Inertial Sensor Filtering

The FIR filter includes four banks of coefficients that have 120 taps each. FILTR\_BNK\_0 (see Table 143) and FILTR\_BNK\_1 (see Table 145) provide the configuration options for the use of the FIR filters of each inertial sensor. Each FIR filter bank includes a preconfigured filter, but users can design their own filters and write over these values using the register of each coefficient. For example, Table 174 provides the details for FIR\_COEF\_A071, which contains Coefficient 71 in FIR Bank A. Refer to Figure 50 for the frequency response of the factory default filters. These filters do not represent any specific application environment; they are only examples.

The decimation filter averages multiple samples together to produce each register update. In this type of filter structure, the number of samples in the average is equal to the reduction in the update rate for the output data registers. See the DEC\_RATE register for the user controls for this filter (see Table 137).

### REGISTER STRUCTURE

All communication with the ADIS16490 involves accessing its user registers. The register structure contains both output data and control registers. The output data registers include the latest sensor data, error flags, and identification data. The control registers include sample rate, filtering, input/output, calibration, and diagnostic configuration options. All communication between the ADIS16490 and an external processor involves either reading or writing to one of the user registers.

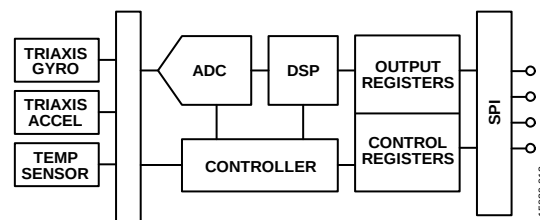
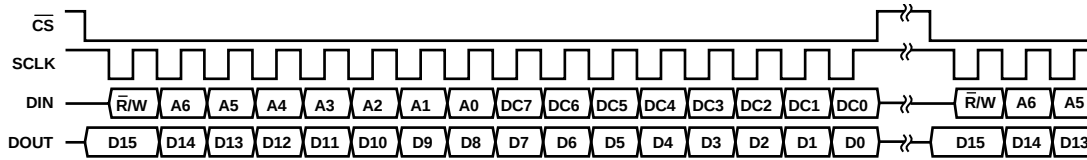


Figure 27. Basic Operation

The register structure uses a paged addressing scheme that contains 13 pages, with each page containing 64 register locations. Each register is 16 bits wide, with each byte having its own unique address within the memory map of that page. The SPI port has access to one page at a time, using the bit sequence in Figure 28. Select the page to activate for SPI access by writing its code to the PAGE\_ID register. Read the PAGE\_ID register to determine which page is currently active. Table 7 displays the PAGE\_ID contents for each page and their basic functions. The PAGE\_ID register is located at Address 0x00 on every page.

Table 7. User Register Page Assignments

| Page | PAGE_ID | Function                                             |
|------|---------|------------------------------------------------------|
| 0    | 0x00    | Output data, clock, identification                   |
| 1    | 0x01    | Reserved                                             |
| 2    | 0x02    | Calibration                                          |
| 3    | 0x03    | Control: sample rate, filtering, I/O                 |
| 4    | 0x04    | Serial number, CRC values                            |
| 5    | 0x05    | FIR Filter Bank A, Coefficient 0 to Coefficient 59   |
| 6    | 0x06    | FIR Filter Bank A, Coefficient 60 to Coefficient 119 |
| 7    | 0x07    | FIR Filter Bank B, Coefficient 0 to Coefficient 59   |
| 8    | 0x08    | FIR Filter Bank B, Coefficient 60 to Coefficient 119 |
| 9    | 0x09    | FIR Filter Bank C, Coefficient 0 to Coefficient 59   |
| 10   | 0x0A    | FIR Filter Bank C, Coefficient 60 to Coefficient 119 |
| 11   | 0x0B    | FIR Filter Bank D, Coefficient 0 to Coefficient 59   |
| 12   | 0x0C    | FIR Filter Bank D, Coefficient 60 to Coefficient 119 |



## NOTES

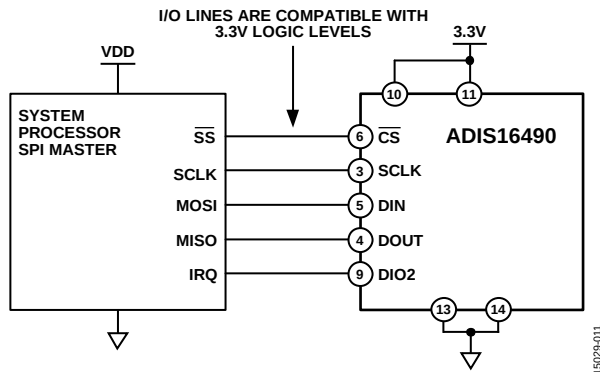
1. DOUT BITS ARE PRODUCED ONLY WHEN THE PREVIOUS 16-BIT DIN SEQUENCE STARTS WITH  $\bar{R}/W = 0$ .
2. WHEN CS IS HIGH, DOUT IS IN A THREE-STATE, HIGH IMPEDANCE MODE, WHICH ALLOWS MULTIFUNCTIONAL USE OF THE LINE FOR OTHER DEVICES.

15029-013

Figure 28. SPI Communication Bit Sequence

## SERIAL PERIPHERAL INTERFACE

The serial peripheral interface (SPI) provides access to the user register structures and typically connects to a compatible port on an embedded processor, using the connection diagram shown in Figure 29. The four SPI signals facilitate synchronous, serial data communication.



15029-011

Figure 29. Electrical Connection Diagram

Table 8. Generic Master Processor Pin Names and Functions

| Mnemonic   | Function                   |
|------------|----------------------------|
| $\bar{SS}$ | Slave select               |
| IRQ        | Interrupt request          |
| MOSI       | Master output, slave input |
| MISO       | Master input, slave output |
| SCLK       | Serial clock               |

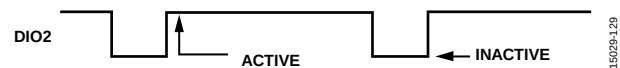
Embedded processors typically use control registers to configure their serial ports for communicating with SPI slave devices such as the ADIS16490. Table 9 provides a list of settings that describe the SPI protocol of the ADIS16490. The initialization routine of the master processor typically establishes these settings using firmware commands to write them into its serial control registers.

Table 9. Generic Master Processor SPI Settings

| Processor Setting  | Description                            |
|--------------------|----------------------------------------|
| Master             | ADIS16490 operates as slave            |
| $SCLK \leq 15$ MHz | Maximum serial clock rate              |
| SPI Mode 3         | CPOL = 1 (polarity), CPHA = 1 (phase)  |
| MSB First Mode     | Bit sequence, see Figure 28 for coding |
| 16-Bit Mode        | Shift register/data length             |

## DATA READY

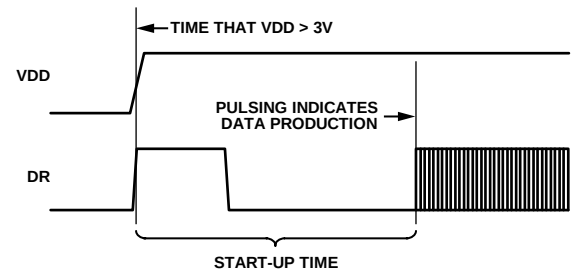
The factory default configuration provides users with a data ready (DR) signal on the DIO2 pin, which pulses low when the output data registers are updating (see Figure 30). In this configuration, connect DIO2 to a pin on the embedded processor, which triggers data collection, when this signal pulses high. Register FNCTIO\_CTRL[3:0] (see Table 131) provides user configuration options for this function.



15029-129

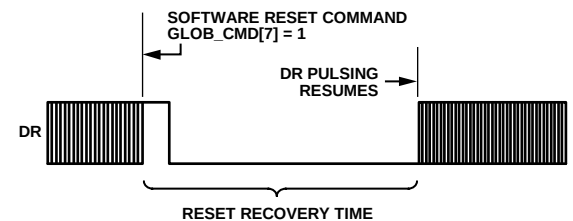
Figure 30. Data Ready, When FNCTIO\_CTRL[3:0] = 1101 (default)

During the start-up and reset recovery processes, the DR signal can exhibit transient behavior before data production begins. Figure 31 provides an example of the DR behavior during startup, and Figure 32 and Figure 33 provide examples of the DR behavior during recovery from reset commands.



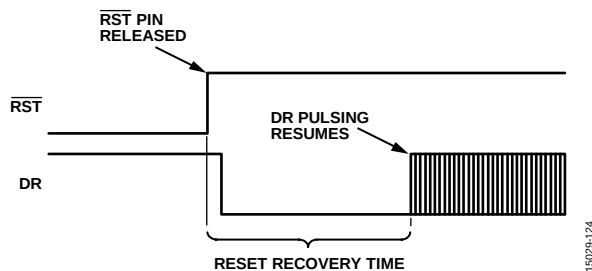
15029-122

Figure 31. Data Ready Response During Startup



15029-123

Figure 32. Data Ready Response During Reset (Register GLOB\_CMD, Bit 7 = 1) Recovery

Figure 33. Data Ready Response During Reset ( $\overline{RST} = 0$ ) Recovery

## READING SENSOR DATA

Reading a single register requires two 16-bit cycles on the SPI: one to request the contents of a register and another to receive those contents. The 16-bit command code (see Figure 28) for a read request on the SPI has three parts: the read bit ( $\overline{R}/W = 0$ ), either address of the register, [A6:A0], and eight don't care bits, [DC7:DC0]. Figure 34 provides an example that includes two register reads in succession. This example starts with DIN = 0x1A00, to request the contents of the Z\_GYRO\_OUT register, and follows with 0x1800, to request the contents of the Z\_GYRO\_LOW register (assuming PAGE\_ID already equals 0x0000). The sequence in Figure 34 also illustrates full duplex mode of operation, which means that the ADIS16490 can receive requests on DIN while also transmitting data out on DOUT within the same 16-bit SPI cycle.



Figure 34. SPI Read Example

Figure 35 provides an example of the four SPI signals when reading the PROD\_ID register (see Table 79) in a repeating pattern. This pattern can be helpful when troubleshooting the SPI interface setup and communications.

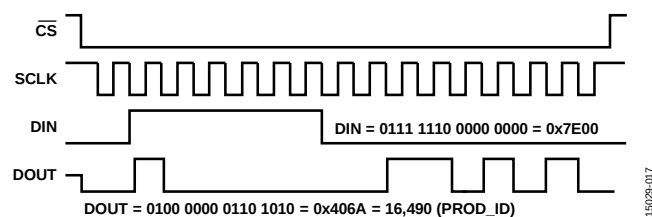


Figure 35. SPI Read Example, Second 16-Bit Sequence

## DEVICE CONFIGURATION

Each register contains 16 bits (two bytes). Bits[7:0] contain the low byte and Bits[15:8] contain the high byte of each register.

Each byte has its own unique address in the user register map (see Table 10). Updating the contents of a register requires writing to its low byte first and its high byte second. There are three parts to coding a SPI command (see Figure 28), which writes a new byte of data to a register: the write bit ( $\overline{R}/W = 1$ ), the address of the byte, [A6:A0], and the new data for that location, [DC7:DC0]. Figure 36 provides a coding example for writing 0xFEDC to the XG\_BIAS\_LOW register (see Table 93), assuming that PAGE\_ID already equals 0x0002.

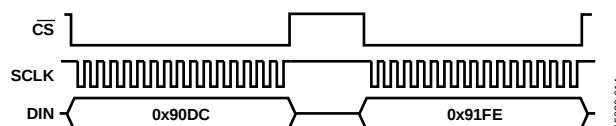


Figure 36. SPI Sequence for Writing 0xFEDC to XG\_BIAS\_LOW

## Dual Memory Structure

The ADIS16490 uses a dual memory structure (see Figure 37), with SRAM supporting real-time operation and flash memory storing operational code, calibration coefficients, and user configurable register settings. The manual flash update command (GLOB\_CMD[3], see Table 129) provides a single-command method for storing user configuration settings into flash memory, for automatic recall during the next power-on or reset recovery process. This portion of the flash memory bank has two independent banks that operate in a ping pong manner, alternating with every flash update. During power-on or reset recovery, the ADIS16490 performs a cyclic redundancy check (CRC) on the SRAM and compares it to a CRC computation from the same memory locations in flash memory. If this fails, the ADIS16490 resets and boots up from the other flash memory location. SYS\_E\_FLAG[2] (see Table 16) provides an error flag for detecting when the back-up flash memory supported the last power-on or reset recovery. Table 10 provides a memory map for the user registers in the ADIS16490, which includes flash backup support (indicated by yes or no in the flash column).

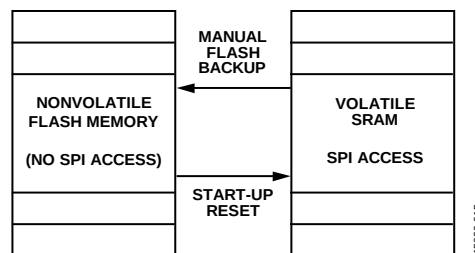


Figure 37. SRAM and Flash Memory Diagram



## USER REGISTER MEMORY MAP

Table 10. User Register Memory Map (N/A Means Not Applicable)

| Name          | R/W | Flash Backup | PAGE_ID | Address      | Default | Register Description                                |
|---------------|-----|--------------|---------|--------------|---------|-----------------------------------------------------|
| PAGE_ID       | R/W | No           | 0x00    | 0x00, 0x01   | 0x0000  | Page identifier                                     |
| Reserved      | N/A | N/A          | 0x00    | 0x02, 0x03   | N/A     | Reserved                                            |
| DATA_CNT      | R   | No           | 0x00    | 0x04, 0x05   | N/A     | Data counter                                        |
| Reserved      | N/A | N/A          | 0x00    | 0x06, 0x07   | N/A     | Reserved                                            |
| SYS_E_FLAG    | R   | No           | 0x00    | 0x08, 0x09   | N/A     | Output, system error flags (0x0000 if no errors)    |
| DIAG_STS      | R   | No           | 0x00    | 0x0A, 0x0B   | N/A     | Output, self test error flags (0x0000 if no errors) |
| Reserved      | N/A | N/A          | 0x00    | 0x0C, 0x0D   | N/A     | Reserved                                            |
| TEMP_OUT      | R   | No           | 0x00    | 0x0E, 0x0F   | N/A     | Output, temperature                                 |
| X_GYRO_LOW    | R   | No           | 0x00    | 0x10, 0x11   | N/A     | Output, x-axis gyroscope, low word                  |
| X_GYRO_OUT    | R   | No           | 0x00    | 0x12, 0x13   | N/A     | Output, x-axis gyroscope, high word                 |
| Y_GYRO_LOW    | R   | No           | 0x00    | 0x14, 0x15   | N/A     | Output, y-axis gyroscope, low word                  |
| Y_GYRO_OUT    | R   | No           | 0x00    | 0x16, 0x17   | N/A     | Output, y-axis gyroscope, high word                 |
| Z_GYRO_LOW    | R   | No           | 0x00    | 0x18, 0x19   | N/A     | Output, z-axis gyroscope, low word                  |
| Z_GYRO_OUT    | R   | No           | 0x00    | 0x1A, 0x1B   | N/A     | Output, z-axis gyroscope, high word                 |
| X_ACCL_LOW    | R   | No           | 0x00    | 0x1C, 0x1D   | N/A     | Output, x-axis accelerometer, low word              |
| X_ACCL_OUT    | R   | No           | 0x00    | 0x1E, 0x1F   | N/A     | Output, x-axis accelerometer, high word             |
| Y_ACCL_LOW    | R   | No           | 0x00    | 0x20, 0x21   | N/A     | Output, y-axis accelerometer, low word              |
| Y_ACCL_OUT    | R   | No           | 0x00    | 0x22, 0x23   | N/A     | Output, y-axis accelerometer, high word             |
| Z_ACCL_LOW    | R   | No           | 0x00    | 0x24, 0x25   | N/A     | Output, z-axis accelerometer, low word              |
| Z_ACCL_OUT    | R   | No           | 0x00    | 0x26, 0x27   | N/A     | Output, z-axis accelerometer, high word             |
| TIME_STAMP    | R   | No           | 0x00    | 0x28, 0x29   | N/A     | Output, time stamp                                  |
| Reserved      | N/A | N/A          | 0x00    | 0x2A to 0x3F | N/A     | Reserved                                            |
| X_DELTANG_LOW | R   | No           | 0x00    | 0x40, 0x41   | N/A     | Output, x-axis delta angle, low word                |
| X_DELTANG_OUT | R   | No           | 0x00    | 0x42, 0x43   | N/A     | Output, x-axis delta angle, high word               |
| Y_DELTANG_LOW | R   | No           | 0x00    | 0x44, 0x45   | N/A     | Output, y-axis delta angle, low word                |
| Y_DELTANG_OUT | R   | No           | 0x00    | 0x46, 0x47   | N/A     | Output, y-axis delta angle, high word               |
| Z_DELTANG_LOW | R   | No           | 0x00    | 0x48, 0x49   | N/A     | Output, z-axis delta angle, low word                |
| Z_DELTANG_OUT | R   | No           | 0x00    | 0x4A, 0x4B   | N/A     | Output, z-axis delta angle, high word               |
| X_DELTVEL_LOW | R   | No           | 0x00    | 0x4C, 0x4D   | N/A     | Output, x-axis delta velocity, low word             |
| X_DELTVEL_OUT | R   | No           | 0x00    | 0x4E, 0x4F   | N/A     | Output, x-axis delta velocity, high word            |
| Y_DELTVEL_LOW | R   | No           | 0x00    | 0x50, 0x51   | N/A     | Output, y-axis delta velocity, low word             |
| Y_DELTVEL_OUT | R   | No           | 0x00    | 0x52, 0x53   | N/A     | Output, y-axis delta velocity, high word            |
| Z_DELTVEL_LOW | R   | No           | 0x00    | 0x54, 0x55   | N/A     | Output, z-axis delta velocity, low word             |
| Z_DELTVEL_OUT | R   | No           | 0x00    | 0x56, 0x57   | N/A     | Output, z-axis delta velocity, high word            |
| Reserved      | N/A | N/A          | 0x00    | 0x58 to 0x7D | N/A     | Reserved                                            |
| PROD_ID       | R   | Yes          | 0x00    | 0x7E, 0x7F   | 0x406A  | Output, product identification (16490d)             |
| Reserved      | N/A | N/A          | 0x01    | 0x00 to 0x7F | N/A     | Reserved                                            |
| PAGE_ID       | R/W | No           | 0x02    | 0x00, 0x01   | 0x0000  | Page identifier                                     |
| Reserved      | N/A | N/A          | 0x02    | 0x02, 0x03   | N/A     | Reserved                                            |
| X_GYRO_SCALE  | R/W | Yes          | 0x02    | 0x04, 0x05   | 0x0000  | Calibration, scale, x-axis gyroscope                |
| Y_GYRO_SCALE  | R/W | Yes          | 0x02    | 0x06, 0x07   | 0x0000  | Calibration, scale, y-axis gyroscope                |
| Z_GYRO_SCALE  | R/W | Yes          | 0x02    | 0x08, 0x09   | 0x0000  | Calibration, scale, z-axis gyroscope                |
| X_ACCL_SCALE  | R/W | Yes          | 0x02    | 0x0A, 0x0B   | 0x0000  | Calibration, scale, x-axis accelerometer            |
| Y_ACCL_SCALE  | R/W | Yes          | 0x02    | 0x0C, 0x0D   | 0x0000  | Calibration, scale, y-axis accelerometer            |
| Z_ACCL_SCALE  | R/W | Yes          | 0x02    | 0x0E, 0x0F   | 0x0000  | Calibration, scale, z-axis accelerometer            |
| XG_BIAS_LOW   | R/W | Yes          | 0x02    | 0x10, 0x11   | 0x0000  | Calibration, bias, gyroscope, x-axis, low word      |
| XG_BIAS_HIGH  | R/W | Yes          | 0x02    | 0x12, 0x13   | 0x0000  | Calibration, bias, gyroscope, x-axis, high word     |
| YG_BIAS_LOW   | R/W | Yes          | 0x02    | 0x14, 0x15   | 0x0000  | Calibration, bias, gyroscope, y-axis, low word      |
| YG_BIAS_HIGH  | R/W | Yes          | 0x02    | 0x16, 0x17   | 0x0000  | Calibration, bias, gyroscope, y-axis, high word     |
| ZG_BIAS_LOW   | R/W | Yes          | 0x02    | 0x18, 0x19   | 0x0000  | Calibration, bias, gyroscope, z-axis, low word      |



| Name                       | R/W | Flash Backup | PAGE_ID | Address      | Default             | Register Description                                      |
|----------------------------|-----|--------------|---------|--------------|---------------------|-----------------------------------------------------------|
| ZG_BIAS_HIGH               | R/W | Yes          | 0x02    | 0x1A, 0x1B   | 0x0000              | Calibration, bias, gyroscope, z-axis, high word           |
| XA_BIAS_LOW                | R/W | Yes          | 0x02    | 0x1C, 0x1D   | 0x0000              | Calibration, bias, accelerometer, x-axis, low word        |
| XA_BIAS_HIGH               | R/W | Yes          | 0x02    | 0x1E, 0x1F   | 0x0000              | Calibration, bias, accelerometer, x-axis, high word       |
| YA_BIAS_LOW                | R/W | Yes          | 0x02    | 0x20, 0x21   | 0x0000              | Calibration, bias, accelerometer, y-axis, low word        |
| YA_BIAS_HIGH               | R/W | Yes          | 0x02    | 0x22, 0x23   | 0x0000              | Calibration, bias, accelerometer, y-axis, high word       |
| ZA_BIAS_LOW                | R/W | Yes          | 0x02    | 0x24, 0x25   | 0x0000              | Calibration, bias, accelerometer, z-axis, low word        |
| ZA_BIAS_HIGH               | R/W | Yes          | 0x02    | 0x26, 0x27   | 0x0000              | Calibration, bias, accelerometer, z-axis, high word       |
| Reserved                   | N/A | N/A          | 0x02    | 0x28 to 0x73 | 0x0000              | Reserved                                                  |
| USER_SCR_1                 | R/W | Yes          | 0x02    | 0x74, 0x75   | 0x0000              | User Scratch Register 1                                   |
| USER_SCR_2                 | R/W | Yes          | 0x02    | 0x76, 0x77   | 0x0000              | User Scratch Register 2                                   |
| USER_SCR_3                 | R/W | Yes          | 0x02    | 0x78, 0x79   | 0x0000              | User Scratch Register 3                                   |
| USER_SCR_4                 | R/W | Yes          | 0x02    | 0x7A, 0x7B   | 0x0000              | User Scratch Register 4                                   |
| FLSHCNT_LOW                | R   | Yes          | 0x02    | 0x7C, 0x7D   | N/A                 | Diagnostic, flash memory count, low word                  |
| FLSHCNT_HIGH               | R   | Yes          | 0x02    | 0x7E, 0x7F   | N/A                 | Diagnostic, flash memory count, high word                 |
| PAGE_ID                    | R/W | No           | 0x03    | 0x00, 0x01   | 0x0000              | Page identifier                                           |
| GLOB_CMD                   | W   | No           | 0x03    | 0x02, 0x03   | N/A                 | Control, global commands                                  |
| Reserved                   | N/A | N/A          | 0x03    | 0x04, 0x05   | N/A                 | Reserved                                                  |
| FNCTIO_CTRL                | R/W | Yes          | 0x03    | 0x06, 0x07   | 0x000D              | Control, I/O pins, functional definitions                 |
| GPIO_CTRL                  | R/W | Yes          | 0x03    | 0x08, 0x09   | 0x00X0 <sup>1</sup> | Control, I/O pins, general purpose                        |
| CONFIG                     | R/W | Yes          | 0x03    | 0x0A, 0x0B   | 0x00C0              | Control, clock, and miscellaneous correction              |
| DEC_RATE                   | R/W | Yes          | 0x03    | 0x0C, 0x0D   | 0x0000              | Control, output sample rate decimation                    |
| NULL_CNFG                  | R/W | Yes          | 0x03    | 0x0E, 0x0F   | 0x070A              | Control, automatic bias correction configuration          |
| SYNC_SCALE                 | R/W | Yes          | 0x03    | 0x10, 0x11   | 0x109A              | Input clock scaling (PPS mode)                            |
| Reserved                   | N/A | N/A          | 0x03    | 0x12 to 0x15 | N/A                 | Reserved                                                  |
| FILTR_BNK_0                | R/W | Yes          | 0x03    | 0x16, 0x17   | 0x0000              | Filter selection                                          |
| FILTR_BNK_1                | R/W | Yes          | 0x03    | 0x18, 0x19   | 0x0000              | Filter selection                                          |
| Reserved                   | N/A | N/A          | 0x03    | 0x1A to 0x77 | N/A                 | Reserved                                                  |
| FIRM_REV                   | R   | Yes          | 0x03    | 0x78, 0x79   | N/A                 | Firmware revision                                         |
| FIRM_DM                    | R   | Yes          | 0x03    | 0x7A, 0x7B   | N/A                 | Firmware programming date: day/month                      |
| FIRM_Y                     | R   | Yes          | 0x03    | 0x7C, 0x7D   | N/A                 | Firmware programming date: year                           |
| BOOT_REV                   | R   | Yes          | 0x03    | 0x7E, 0x7F   | N/A                 | Boot loader revision                                      |
| PAGE_ID                    | R/W | No           | 0x04    | 0x00, 0x01   | 0x0000              | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x04    | 0x02, 0x03   | N/A                 | Reserved                                                  |
| CAL_SIGTR_LWR              | R   | Yes          | 0x04    | 0x04, 0x05   | N/A                 | Signature CRC, calibration coefficients, low word         |
| CAL_SIGTR_UPR              | R   | Yes          | 0x04    | 0x06, 0x07   | N/A                 | Signature CRC, calibration coefficients, high word        |
| CAL_DRVTN_LWR              | R   | No           | 0x04    | 0x08, 0x09   | N/A                 | Real-time CRC, calibration coefficients, low word         |
| CAL_DRVTN_UPR              | R   | No           | 0x04    | 0x0A, 0x0B   | N/A                 | Real-time CRC, calibration coefficients, high word        |
| CODE_SIGTR_LWR             | R   | Yes          | 0x04    | 0x0C, 0x0D   | N/A                 | Signature CRC, program code, low word                     |
| CODE_SIGTR_UPR             | R   | Yes          | 0x04    | 0x0E, 0x0F   | N/A                 | Signature CRC, program code, high word                    |
| CODE_DRVTN_LWR             | R   | No           | 0x04    | 0x10, 0x11   | N/A                 | Real-time CRC, program code, low word                     |
| CODE_DRVTN_UPR             | R   | No           | 0x04    | 0x12, 0x13   | N/A                 | Real-time CRC, program code, high word                    |
| Reserved                   | N/A | N/A          | 0x04    | 0x1C to 0x1F | N/A                 | Reserved                                                  |
| SERIAL_NUM                 | R   | Yes          | 0x04    | 0x20, 0x21   | N/A                 | Serial number                                             |
| Reserved                   | N/A | N/A          | 0x04    | 0x22 to 0x7F | N/A                 | Reserved                                                  |
| PAGE_ID                    | R/W | No           | 0x05    | 0x00, 0x01   | 0x0000              | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x05    | 0x02 to 0x07 | N/A                 | Reserved                                                  |
| FIR_COEF_Axxx <sup>2</sup> | R/W | Yes          | 0x05    | 0x08 to 0x7F | N/A                 | FIR Filter Bank A: Coefficient 0 through Coefficient 59   |
| PAGE_ID                    | R/W | No           | 0x06    | 0x00         | 0x0000              | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x06    | 0x02 to 0x07 | N/A                 | Reserved                                                  |
| FIR_COEF_Axxx <sup>2</sup> | R/W | Yes          | 0x06    | 0x08 to 0x7F | N/A                 | FIR Filter Bank A: Coefficient 60 through Coefficient 119 |
| PAGE_ID                    | R/W | No           | 0x07    | 0x00, 0x01   | 0x0000              | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x07    | 0x02 to 0x07 | N/A                 | Reserved                                                  |
| FIR_COEF_Bxxx <sup>3</sup> | R/W | Yes          | 0x07    | 0x08 to 0x7F | N/A                 | FIR Filter Bank B: Coefficient 0 through Coefficient 59   |

| Name                       | R/W | Flash Backup | PAGE_ID | Address      | Default | Register Description                                      |
|----------------------------|-----|--------------|---------|--------------|---------|-----------------------------------------------------------|
| PAGE_ID                    | R/W | No           | 0x08    | 0x00, 0x01   | 0x0000  | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x08    | 0x02 to 0x07 | N/A     | Reserved                                                  |
| FIR_COEF_Bxxx <sup>3</sup> | R/W | Yes          | 0x08    | 0x08 to 0x7F | N/A     | FIR Filter Bank B: Coefficient 60 through Coefficient 119 |
| PAGE_ID                    | R/W | No           | 0x09    | 0x00, 0x01   | 0x0000  | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x09    | 0x02 to 0x07 | N/A     | Reserved                                                  |
| FIR_COEF_Cxxx <sup>4</sup> | R/W | Yes          | 0x09    | 0x08 to 0x7F | N/A     | FIR Filter Bank C: Coefficient 0 through Coefficient 59   |
| PAGE_ID                    | R/W | No           | 0x0A    | 0x00, 0x01   | 0x0000  | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x0A    | 0x02 to 0x07 | N/A     | Reserved                                                  |
| FIR_COEF_Cxxx <sup>4</sup> | R/W | Yes          | 0x0A    | 0x08 to 0x7F | N/A     | FIR Filter Bank C: Coefficient 60 through Coefficient 119 |
| PAGE_ID                    | R/W | No           | 0x0B    | 0x00, 0x01   | 0x0000  | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x0B    | 0x02 to 0x07 | N/A     | Reserved                                                  |
| FIR_COEF_Dxxx <sup>5</sup> | R/W | Yes          | 0x0B    | 0x08 to 0x7F | N/A     | FIR Filter Bank D: Coefficient 0 through Coefficient 59   |
| PAGE_ID                    | R/W | No           | 0x0C    | 0x00, 0x01   | 0x0000  | Page identifier                                           |
| Reserved                   | N/A | N/A          | 0x0C    | 0x02 to 0x07 | N/A     | Reserved                                                  |
| FIR_COEF_Dxxx <sup>5</sup> | R/W | Yes          | 0x0C    | 0x08 to 0x7F | N/A     | FIR Filter Bank D: Coefficient 60 through Coefficient 119 |

<sup>1</sup> The GPIO\_CTRL[7:4] bits reflect the logic levels on the DIOx lines and do not have a default setting.

<sup>2</sup> See the FIR Filter Bank A, FIR\_COEF\_A000 to FIR\_COEF\_A119 section for additional information.

<sup>3</sup> See the FIR Filter Bank B, FIR\_COEF\_B000 to FIR\_COEF\_B119 section for additional information.

<sup>4</sup> See the FIR Filter Bank C, FIR\_COEF\_C000 to FIR\_COEF\_C119 section for additional information.

<sup>5</sup> See the FIR Filter Bank D, FIR\_COEF\_D000 to FIR\_COEF\_D119 section for additional information.

## USER REGISTER DEFINITIONS

### Page Number (PAGE\_ID)

Table 11. PAGE\_ID Register Definition

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x00 | 0x00, 0x01 | 0x0000  | R/W    | No           |

Table 12. PAGE\_ID Bit Assignments

| Bits   | Description                          |
|--------|--------------------------------------|
| [15:0] | Page number, binary numerical format |

The contents in the PAGE\_ID register (see Table 11 and Table 12) contain the current page setting, and provide a control for selecting another page for SPI access. For example, set DIN = 0x8002 to select Page 2 for SPI-based user access. See Table 10 for the page assignments associated with each user accessible register.

### Data/Sample Counter (DATA\_CNT)

Table 13. DATA\_CNT Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x04, 0x05 | Not applicable | R      | No           |

Table 14. DATA\_CNT Bit Assignments

| Bits   | Description                  |
|--------|------------------------------|
| [15:0] | Data counter, binary format. |

The DATA\_CNT register (see Table 13 and Table 14) is a continuous, real-time, sample counter. It starts at 0x0000, increments every time that the output data registers update, and wraps around from 0xFFFF (65,535 decimal) to 0x0000 (0 decimal).

### Status/Error Flag Indicators (SYS\_E\_FLAG)

Table 15. SYS\_E\_FLAG Register Definition

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x00 | 0x08, 0x09 | 0x0000  | R      | No           |

Table 16. SYS\_E\_FLAG Bit Assignments

| Bits   | Description                                                                                                                                                                                                                                                                   |
|--------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| 15     | Watch dog timer flag. A 1 indicates that the <a href="#">ADIS16490</a> automatically resets itself to clear an issue.                                                                                                                                                         |
| [14:9] | Not used.                                                                                                                                                                                                                                                                     |
| 8      | Sync error. A 1 indicates that the sample timing is not scaling correctly, when operating in PPS mode (FNCTIO_CTRL[8] = 1, see Table 131). When this error occurs, verify that the input sync frequency is correct and that SYNC_SCALE (see Table 141) has the correct value. |
| 7      | Processing overrun. A 1 indicates occurrence of a processing overrun. Initiate a reset to recover. Replace the <a href="#">ADIS16490</a> if this error persists.                                                                                                              |
| 6      | Flash memory update failure. A 1 indicates that the most recent flash memory update failed (GLOB_CMD[3], see Table 129). Repeat the test and replace the <a href="#">ADIS16490</a> if this error persists.                                                                    |
| 5      | Sensor failure. A 1 indicates failure of the self test processes (GLOB_CMD[1], see Table 129), when the device is not in motion. Replace the <a href="#">ADIS16490</a> if the error persists.                                                                                 |
| 4      | Not used.                                                                                                                                                                                                                                                                     |
| 3      | SPI communication error. A 1 indicates that the total number of SCLK cycles is not equal to an integer multiple of 16. Repeat the previous communication sequence to recover. Persistence in this error may indicate a weakness in the SPI service from the master processor. |
| 2      | SRAM error condition. A 1 indicates a failure in the CRC (period = 20 ms) between the SRAM and flash memory. Initiate a reset to recover and replace the <a href="#">ADIS16490</a> if this error persists.                                                                    |
| 1      | Boot memory failure. A 1 indicates that the CRC on the primary flash memory bank did not match the reference CRC value and that the device automatically rebooted using the backup memory bank in flash. Replace the <a href="#">ADIS16490</a> if this error persists.        |
| 0      | Not used.                                                                                                                                                                                                                                                                     |

The SYS\_E\_FLAG register (see Table 15 and Table 16) provides various error flags. Reading this register causes all of its bits to return to 0, with the exception of Bit 7. If an error condition persists, its flag (bit) automatically returns to an alarm value of 1.

**Self Test Error Flags (DIAG\_STS)****Table 17. DIAG\_STS Register Definition**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x00 | 0x0A, 0x0B | 0x0000  | R      | No           |

**Table 18. DIAG\_STS Bit Definitions**

| Bits   | Description (Default = 0x0000)                        |
|--------|-------------------------------------------------------|
| [15:6] | Not used                                              |
| 5      | Self test failure, z-axis accelerometer (1 = failure) |
| 4      | Self test failure, y-axis accelerometer (1 = failure) |
| 3      | Self test failure, x-axis accelerometer (1 = failure) |
| 2      | Self test failure, z-axis gyroscope (1 = failure)     |
| 1      | Self test failure, y-axis gyroscope (1 = failure)     |
| 0      | Self test failure, x-axis gyroscope (1 = failure)     |

SYS\_E\_FLAG[5] (see Table 16) contains the pass/fail result (0 = pass) for the on demand self test (ODST) operations, whereas the DIAG\_STS register (see Table 17 and Table 18) contains pass/fail flags (0 = pass) for each inertial sensor. Reading the DIAG\_STS register causes all of its bits to restore to 0. The bits in DIAG\_STS return to 1 if the error conditions persists.

**Internal Temperature (TEMP\_OUT)****Table 19. TEMP\_OUT Register Definition**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x0E, 0x0F | Not applicable | R      | No           |

**Table 20. TEMP\_OUT Bit Definitions**

| Bits   | Description                                                      |
|--------|------------------------------------------------------------------|
| [15:0] | Temperature data; twos complement, 1°C per 70 LSB, 25°C = 0x0000 |

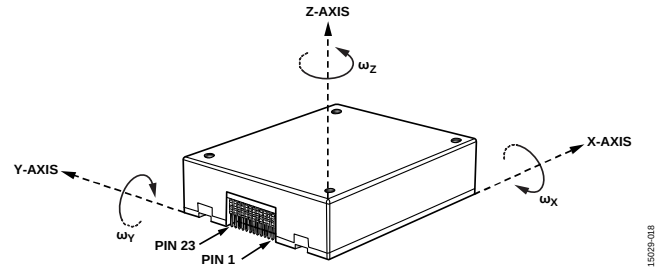
The TEMP\_OUT register (see Table 19 and Table 20) provides a coarse measurement of the temperature inside of the ADIS16490 and is useful for monitoring relative changes in the thermal environment.

**Table 21. TEMP\_OUT Data Format Examples**

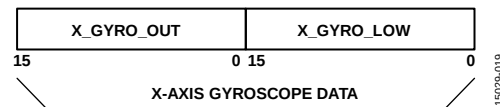
| Temperature (°C) | Decimal | Hex    | Binary              |
|------------------|---------|--------|---------------------|
| +85              | +4200   | 0x1068 | 0001 0000 0110 1000 |
| +25 + 2/70       | +2      | 0x0002 | 0000 0000 0000 0010 |
| +25 + 1/70       | +1      | 0x0001 | 0000 0000 0000 0001 |
| +25              | 0       | 0x0000 | 0000 0000 0000 0000 |
| +25 – 1/70       | –1      | 0xFFFF | 1111 1111 1111 1111 |
| +25 – 2/70       | –2      | 0xFFFE | 1111 1111 1111 1110 |
| –40              | –4550   | 0xEE3A | 1110 1110 0011 1010 |

**GYROSCOPE DATA**

The gyroscopes in the ADIS16490 measure the angular rate of rotation around three orthogonal axes (x, y, and z). Figure 38 illustrates the orientation of each gyroscope axis, along with the direction of rotation that produces a positive response in each of their measurements.

**Figure 38. Gyroscope Axis and Polarity Assignments**

Each gyroscope has two output data registers. Figure 39 illustrates how these two registers combine to support a 32-bit, twos complement data format for the x-axis gyroscope measurements. This format also applies to the y-axis and z-axis as well.

**Figure 39. Gyroscope Output Data Structure****X-Axis Gyroscope (X\_GYRO\_LOW, X\_GYRO\_OUT)****Table 22. X\_GYRO\_LOW Register Definition**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x10, 0x11 | Not applicable | R      | No           |

**Table 23. X\_GYRO\_LOW Bit Definitions**

| Bits   | Description                     |
|--------|---------------------------------|
| [15:0] | X-axis gyroscope data; low word |

**Table 24. X\_GYRO\_OUT Register Definition**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x12, 0x13 | Not applicable | R      | No           |

**Table 25. X\_GYRO\_OUT Bit Definitions**

| Bits   | Description                                                                                             |
|--------|---------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis gyroscope data; high word; twos complement, ±100°/sec range; 0°/sec = 0x0000, 1 LSB = 0.005°/sec |

The X\_GYRO\_LOW (see Table 22 and Table 23) and X\_GYRO\_OUT (see Table 24 and Table 25) registers contain the gyroscope data for the x-axis.

**Y-Axis Gyroscope (Y\_GYRO\_LOW, Y\_GYRO\_OUT)****Table 26. Y\_GYRO\_LOW Register Definition**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x14, 0x15 | Not applicable | R      | No           |

**Table 27. Y\_GYRO\_LOW Bit Definitions**

| Bits   | Description                     |
|--------|---------------------------------|
| [15:0] | Y-axis gyroscope data; low word |

**Table 28. Y\_GYRO\_OUT Register Definition**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x16, 0x17 | Not applicable | R      | No           |

Table 29. Y\_GYRO\_OUT Bit Definitions

| Bits   | Description                                                                                                                                           |
|--------|-------------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis gyroscope data; high word; twos complement, $\pm 100^\circ/\text{sec}$ range; $0^\circ/\text{sec} = 0x0000$ , 1 LSB = $0.005^\circ/\text{sec}$ |

The Y\_GYRO\_LOW (see Table 26 and Table 27) and Y\_GYRO\_OUT (see Table 28 and Table 29) registers contain the gyroscope data for the y-axis.

### Z-Axis Gyroscope (Z\_GYRO\_LOW, Z\_GYRO\_OUT)

Table 30. Z\_GYRO\_LOW Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x18, 0x19 | Not applicable | R      | No           |

Table 31. Z\_GYRO\_LOW Bit Definitions

| Bits   | Description                                       |
|--------|---------------------------------------------------|
| [15:0] | Z-axis gyroscope data; additional resolution bits |

Table 32. Z\_GYRO\_OUT Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x1A, 0x1B | Not applicable | R      | No           |

Table 33. Z\_GYRO\_OUT Bit Definitions

| Bits   | Description                                                                                                                                           |
|--------|-------------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis gyroscope data; high word; twos complement, $\pm 100^\circ/\text{sec}$ range; $0^\circ/\text{sec} = 0x0000$ , 1 LSB = $0.005^\circ/\text{sec}$ |

The Z\_GYRO\_LOW (see Table 30 and Table 31) and Z\_GYRO\_OUT (see Table 32 and Table 33) registers contain the gyroscope data for the z-axis.

### Gyroscope Resolution

Table 34 and Table 35 offer various numerical examples that demonstrate the format of the angular rate (gyroscopes) data in both 16-bit and 32-bit formats.

Table 34. 16-Bit Gyroscope Data Format Examples

| Rotation Rate ( $^\circ/\text{sec}$ ) | Decimal | Hex    | Binary              |
|---------------------------------------|---------|--------|---------------------|
| +100                                  | +20,000 | 0x4E20 | 0100 1110 0010 0000 |
| +0.01                                 | +2      | 0x0002 | 0000 0000 0000 0010 |
| +0.005                                | +1      | 0x0001 | 0000 0000 0000 0001 |
| 0                                     | 0       | 0x0000 | 0000 0000 0000 0000 |
| -0.005                                | -1      | 0xFFFF | 1111 1111 1111 1111 |
| -0.01                                 | -2      | 0xFFFE | 1111 1111 1111 1110 |
| -100                                  | -20,000 | 0xB1E0 | 1011 0001 1110 0000 |

Table 35. 32-Bit Gyroscope Data Format Examples

| Rotation Rate ( $^\circ/\text{sec}$ ) | Decimal        | Hex        |
|---------------------------------------|----------------|------------|
| +100                                  | +1,310,720,000 | 0x4E200000 |
| +0.005/2 <sup>15</sup>                | +2             | 0x00000002 |
| +0.005/2 <sup>16</sup>                | +1             | 0x00000001 |
| 0                                     | 0              | 0x00000000 |
| -0.005/2 <sup>16</sup>                | -1             | 0xFFFFFFF  |
| -0.005/2 <sup>15</sup>                | -2             | 0xFFFFFFF  |
| -100                                  | -1,310,720,000 | 0xB1E00000 |

## ACCELERATION DATA

The accelerometers in the ADIS16490 measure both dynamic and static (response to gravity) acceleration along three orthogonal axes (x, y, and z). Figure 40 illustrates the orientation of each accelerometer axis, along with the direction of acceleration that produces a positive response in each of their measurements.

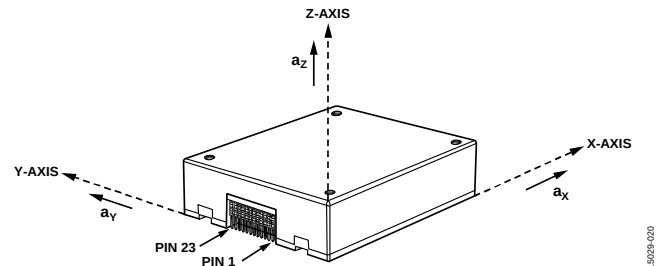


Figure 40. Accelerometer Axis and Polarity Assignments

Each accelerometer has two output data registers. Figure 41 illustrates how these two registers combine to support a 32-bit, twos complement data format for the x-axis accelerometer measurements. This format also applies to the y- and z-axes.

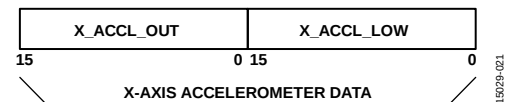


Figure 41. Accelerometer Output Data Structure

### X-Axis Accelerometer (X\_ACCL\_LOW, X\_ACCL\_OUT)

Table 36. X\_ACCL\_LOW Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x1C, 0x1D | Not applicable | R      | No           |

Table 37. X\_ACCL\_LOW Bit Definitions

| Bits   | Description                         |
|--------|-------------------------------------|
| [15:0] | X-axis accelerometer data; low word |

Table 38. X\_ACCL\_OUT Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x1E, 0x1F | Not applicable | R      | No           |

Table 39. X\_ACCL\_OUT Definitions

| Bits   | Description                                                                                               |
|--------|-----------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis accelerometer data, high word; twos complement, $\pm 8 g$ range; $0 g = 0x0000$ , 1 LSB = $0.5 mg$ |

The X\_ACCL\_LOW (see Table 36 and Table 37) and X\_ACCL\_OUT (see Table 38 and Table 39) registers contain the accelerometer data for the x-axis.

### Y-Axis Accelerometer (Y\_ACCL\_LOW, Y\_ACCL\_OUT)

Table 40. Y\_ACCL\_LOW Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x20, 0x21 | Not applicable | R      | No           |

Table 41. Y\_ACCL\_LOW Bit Definitions

| Bits   | Description                         |
|--------|-------------------------------------|
| [15:0] | Y-axis accelerometer data; low word |

Table 42. Y\_ACCL\_OUT Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x22, 0x23 | Not applicable | R      | No           |

Table 43. Y\_ACCL\_OUT Bit Definitions

| Bits   | Description                                                                                             |
|--------|---------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis accelerometer data, high word; twos complement, $\pm 8 g$ range, $0 g = 0x0000$ , 1 LSB = 0.5 mg |

The Y\_ACCL\_LOW (see Table 40 and Table 41) and Y\_ACCL\_OUT (see Table 42 and Table 43) registers contain the accelerometer data for the y-axis.

### Z-Axis Accelerometer (Z\_ACCL\_LOW, Z\_ACCL\_OUT)

Table 44. Z\_ACCL\_LOW Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x24, 0x25 | Not applicable | R      | No           |

Table 45. Z\_ACCL\_LOW Bit Definitions

| Bits   | Description                         |
|--------|-------------------------------------|
| [15:0] | Z-axis accelerometer data; low word |

Table 46. Z\_ACCL\_OUT Register Definition

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x26, 0x27 | Not applicable | R      | No           |

Table 47. Z\_ACCL\_OUT Bit Definitions

| Bits   | Description                                                                                             |
|--------|---------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis accelerometer data, high word; twos complement, $\pm 8 g$ range; $0 g = 0x0000$ , 1 LSB = 0.5 mg |

The Z\_ACCL\_LOW (see Table 44 and Table 45) and Z\_ACCL\_OUT (see Table 46 and Table 47) registers contain the accelerometer data for the z-axis.

### Accelerometer Resolution

Table 48 and Table 49 offer various numerical examples that demonstrate the format of the linear acceleration data in both 16-bit and 32-bit formats.

Table 48. 16-Bit Accelerometer Data Format Examples

| Acceleration | Decimal | Hex    | Binary              |
|--------------|---------|--------|---------------------|
| +8 g         | +16,000 | 0x3E80 | 0011 1110 1000 0000 |
| +1.0 mg      | +2      | 0x0002 | 0000 0000 0000 0010 |
| +0.5 mg      | +1      | 0x0001 | 0000 0000 0000 0001 |
| 0 mg         | 0       | 0x0000 | 0000 0000 0000 0000 |
| -0.5 mg      | -1      | 0xFFFF | 1111 1111 1111 1111 |
| -1.0 mg      | -2      | 0xFFFE | 1111 1111 1111 1110 |
| -8 g         | -16,000 | 0xC180 | 1100 0001 1000 0000 |

Table 49. 32-Bit Accelerometer Data Format Examples

| Acceleration            | Decimal        | Hex        |
|-------------------------|----------------|------------|
| +8 g                    | +1,048,576,000 | 0x3E800000 |
| +0.1/2 <sup>15</sup> mg | +2             | 0x00000002 |
| +0.5/2 <sup>16</sup> mg | +1             | 0x00000001 |
| 0 mg                    | 0              | 0x00000000 |
| -0.5/2 <sup>16</sup> mg | -1             | 0xFFFFFFFF |
| -0.1/2 <sup>15</sup> mg | -2             | 0xFFFFFFFF |
| -8 g                    | -1,048,576,000 | 0xC1800000 |

### DELTA ANGLES

In addition to the angular rate of rotation (gyroscope) measurements around each axis (x, y, and z), the ADIS16490 also provides delta angle measurements that represent a computation of angular displacement between each sample update.

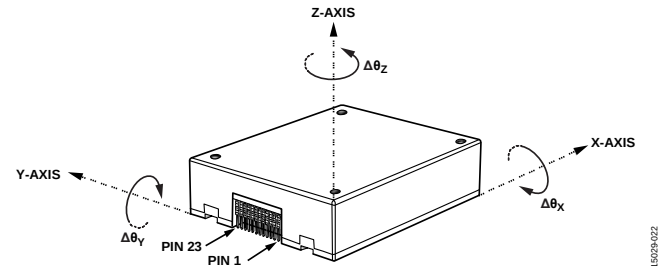


Figure 42. Delta Angle Axis and Polarity Assignments

The delta angle outputs represent an integration of the gyroscope measurements and use the following formula for all three axes (x-axis displayed):

$$\Delta\theta_{x,nD} = \frac{1}{2f_s} \times \sum_{d=0}^{D-1} (\omega_{x,nD+d} + \omega_{x,nD+d-1})$$

where:

$D$  is the decimation rate = DEC\_RATE + 1 (see Table 137).

$f_s$  is the sample rate.

$d$  is the incremental variable in the summation formula.

$\omega_x$  is the x-axis rate of rotation (gyroscope).

$n$  is the sample time, prior to the decimation filter.

When using the internal sample clock,  $f_s$  is equal to 4250 SPS. When using the external clock option,  $f_s$  is equal to the frequency of the external clock. The range in the delta angle registers accommodates the maximum rate of rotation (100°/sec), the nominal sample rate (4250 SPS) and an update rate of 1 Hz (DEC\_RATE = 0x1099; divide by 4249 plus 1, see Table 137), all at the same time. When using an external clock that is higher than 4250 SPS, reduce the DEC\_RATE setting to avoid over-ranging the delta angle registers.

Each axis of the delta angle measurements has two output data registers. Figure 43 illustrates how these two registers combine to support a 32-bit, twos complement data format for the x-axis delta angle measurements. This format also applies to the y- and z-axes.



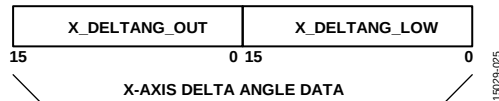


Figure 43. Delta Angle Output Data Structure

**X-Axis Delta Angle (X\_DELTANG\_LOW, X\_DELTANG\_OUT)**

The X\_DELTANG\_LOW (see Table 50 and Table 51) and X\_DELTANG\_OUT (see Table 52 and Table 53) registers contain the delta angle data for the x-axis.

**Table 50. X\_DELTANG\_LOW Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x40, 0x41 | Not applicable | R      | No           |

**Table 51. X\_DELTANG\_LOW Bit Definitions**

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | X-axis delta angle data; low word |

**Table 52. X\_DELTANG\_OUT Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x42, 0x43 | Not applicable | R      | No           |

**Table 53. X\_DELTANG\_OUT Bit Definitions**

| Bits   | Description                                                                                                                                    |
|--------|------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis delta angle data, high word; twos complement, $\pm 720^\circ$ range, $0^\circ = 0x0000$ , 1 LSB = $720^\circ/2^{15} = \sim 0.022^\circ$ |

**Y-Axis Delta Angle (Y\_DELTANG\_LOW, Y\_DELTANG\_OUT)**

The Y\_DELTANG\_LOW (see Table 54 and Table 55) and Y\_DELTANG\_OUT (see Table 56 and Table 57) registers contain the delta angle data for the y-axis.

**Table 54. Y\_DELTANG\_LOW Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x44, 0x45 | Not applicable | R      | No           |

**Table 55. Y\_DELTANG\_LOW Bit Definitions**

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | Y-axis delta angle data; low word |

**Table 56. Y\_DELTANG\_OUT Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x46, 0x47 | Not applicable | R      | No           |

**Table 57. Y\_DELTANG\_OUT Bit Definitions**

| Bits   | Description                                                                                                                                    |
|--------|------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis delta angle data, high word; twos complement, $\pm 720^\circ$ range, $0^\circ = 0x0000$ , 1 LSB = $720^\circ/2^{15} = \sim 0.022^\circ$ |

**Z-Axis Delta Angle (Z\_DELTANG\_LOW, Z\_DELTANG\_OUT)**

The Z\_DELTANG\_LOW (see Table 58 and Table 59) and Z\_DELTANG\_OUT (see Table 60 and Table 61) registers contain the delta angle data for the z-axis.

**Table 58. Z\_DELTANG\_LOW Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x48, 0x49 | Not applicable | R      | No           |

**Table 59. Z\_DELTANG\_LOW Bit Definitions**

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | Z-axis delta angle data; low word |

**Table 60. Z\_DELTANG\_OUT Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x4A, 0x4B | Not applicable | R      | No           |

**Table 61. Z\_DELTANG\_OUT Bit Definitions**

| Bits   | Description                                                                                                                                    |
|--------|------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis delta angle data, high word; twos complement, $\pm 720^\circ$ range, $0^\circ = 0x0000$ , 1 LSB = $720^\circ/2^{15} = \sim 0.022^\circ$ |

**Delta Angle Resolution**

Table 62 and Table 63 offer various numerical examples that demonstrate the format of the delta angle data in both 16-bit and 32-bit formats.

**Table 62. 16-Bit Delta Angle Data Format Examples**

| Delta Angle ( $^\circ$ )          | Decimal | Hex    | Binary              |
|-----------------------------------|---------|--------|---------------------|
| $+720 \times (2^{15} - 1)/2^{15}$ | +32,767 | 0x7FFF | 0111 1111 1110 1111 |
| $+720/2^{14}$                     | +2      | 0x0002 | 0000 0000 0000 0010 |
| $+720/2^{15}$                     | +1      | 0x0001 | 0000 0000 0000 0001 |
| 0                                 | 0       | 0x0000 | 0000 0000 0000 0000 |
| $-720/2^{15}$                     | -1      | 0xFFFF | 1111 1111 1111 1111 |
| $-720/2^{14}$                     | -2      | 0xFFFE | 1111 1111 1111 1110 |
| -720                              | -32,768 | 0x8000 | 1000 0000 0000 0000 |

**Table 63. 32-Bit Delta Angle Data Format Examples**

| Delta Angle ( $^\circ$ )          | Decimal        | Hex          |
|-----------------------------------|----------------|--------------|
| $+720 \times (2^{31} - 1)/2^{31}$ | +2,147,483,647 | 0x7FFFFFFF   |
| $+720/2^{30}$                     | +2             | 0x00000002   |
| $+720/2^{31}$                     | +1             | 0x00000001   |
| 0                                 | 0              | 0x00000000   |
| $-720/2^{31}$                     | -1             | 0xFFFFFFFF   |
| $-720/2^{30}$                     | -2             | 0xFFFFFFFFFE |
| -720                              | -2,147,483,647 | 0x80000000   |

**DELTA VELOCITY**

In addition to the linear acceleration measurements along each axis (x, y, and z), the ADIS16490 also provides delta velocity measurements that represent a computation of linear velocity change between each sample update.

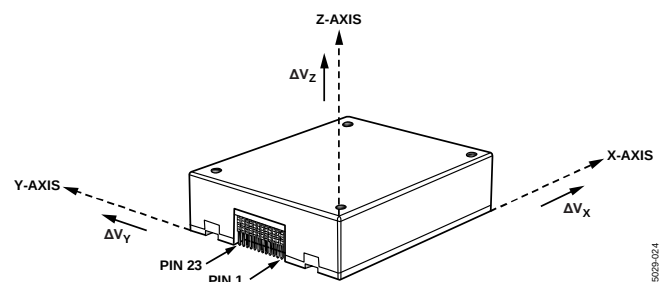


Figure 44. Delta Velocity Axis and Polarity Assignments

The delta velocity outputs represent an integration of the acceleration measurements and use the following formula for all three axes (x-axis displayed):

$$\Delta V_{x,nD} = \frac{1}{2f_s} \times \sum_{d=0}^{D-1} (a_{x,nD+d} + a_{x,nD+d-1})$$

where:

$D$  is the decimation rate = DEC\_RATE + 1 (see Table 137).

$f_s$  is the sample rate.

$d$  is the incremental variable in the summation formula.

$a_x$  is the x-axis rate of acceleration (accelerometer).

$n$  is the sample time, prior to the decimation filter.

When using the internal sample clock,  $f_s$  is equal to 4250 SPS. When using the external clock option,  $f_s$  is equal to the frequency of the external clock. The range in the delta velocity registers accommodates the maximum linear acceleration (8 g), the nominal sample rate (4250 SPS) and an update rate of 1 Hz (DEC\_RATE = 0x1099; divide by 4249 plus 1, see Table 137), all at the same time. When using an external clock that is higher than 4250 SPS, reduce the DEC\_RATE setting to avoid overranging the delta velocity registers.

Each axis of the delta velocity measurements has two output data registers. Figure 45 illustrates how these two registers combine to support 32-bit, twos complement data format for the delta velocity measurements along the x-axis. This format also applies to the y- and z-axes.

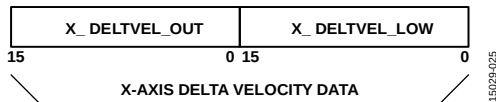


Figure 45. Delta Angle Output Data Structure

### X-Axis Delta Velocity (X\_DELTVEL\_LOW, X\_DELTVEL\_OUT)

Table 64. X\_DELTVEL\_LOW Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x4C, 0x4D | Not applicable | R      | No           |

Table 65. X\_DELTVEL\_LOW Bit Definitions

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | X-axis delta angle data; low word |

Table 66. X\_DELTVEL\_OUT Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x4E, 0x4F | Not applicable | R      | No           |

Table 67. X\_DELTVEL\_OUT Bit Definitions

| Bits   | Description                                                                                                                                               |
|--------|-----------------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis delta velocity data; twos complement, $\pm 200$ m/sec range, 0 m/sec = 0x0000; 1 LSB = $200 \text{ m/sec} \div 2^{15} = \sim 6.104 \text{ mm/sec}$ |

The X\_DELTVEL\_LOW (see Table 64 and Table 65) and X\_DELTVEL\_OUT (see Table 66 and Table 67) registers contain the delta velocity data for the x-axis.

### Y-Axis Delta Velocity (Y\_DELTVEL\_LOW, Y\_DELTVEL\_OUT)

Table 68. Y\_DELTVEL\_LOW Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x50, 0x51 | Not applicable | R      | No           |

Table 69. Y\_DELTVEL\_LOW Bit Definitions

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | Y-axis delta angle data; low word |

Table 70. Y\_DELTVEL\_OUT Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x52, 0x53 | Not applicable | R      | No           |

Table 71. Y\_DELTVEL\_OUT Bit Definitions

| Bits   | Description                                                                                                                                                          |
|--------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis delta velocity data, high word; twos complement, $\pm 200$ m/sec range, 0 m/sec = 0x0000; 1 LSB = $200 \text{ m/sec} \div 2^{15} = \sim 6.104 \text{ mm/sec}$ |

The Y\_DELTVEL\_LOW (see Table 68 and Table 69) and Y\_DELTVEL\_OUT (see Table 70 and Table 71) registers contain the delta velocity data for the y-axis.

### Z-Axis Delta Velocity (Z\_DELTVEL\_LOW, Z\_DELTVEL\_OUT)

Table 72. Z\_DELTVEL\_LOW Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x54, 0x55 | Not applicable | R      | No           |

Table 73. Z\_DELTVEL\_LOW Bit Definitions

| Bits   | Description                       |
|--------|-----------------------------------|
| [15:0] | Z-axis delta angle data; low word |

Table 74. Z\_DELTVEL\_OUT Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x00 | 0x56, 0x57 | Not applicable | R      | No           |

Table 75. Z\_DELTVEL\_OUT Bit Definitions

| Bits   | Description                                                                                                                                                          |
|--------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis delta velocity data, high word; twos complement, $\pm 200$ m/sec range, 0 m/sec = 0x0000; 1 LSB = $200 \text{ m/sec} \div 2^{15} = \sim 6.104 \text{ mm/sec}$ |

The Z\_DELTVEL\_LOW (see Table 72 and Table 73) and Z\_DELTVEL\_OUT (see Table 74 and Table 75) registers contain the delta velocity data for the z-axis.

### Delta Velocity Resolution

Table 76 and Table 77 offer various numerical examples that demonstrate the format of the delta angle data in both 16-bit and 32-bit formats.

Table 76. 16-Bit Delta Velocity Data Format Examples

| Velocity (m/sec)                    | Decimal | Hex    | Binary              |
|-------------------------------------|---------|--------|---------------------|
| $+200 \times (2^{15} - 1) / 2^{15}$ | +32,767 | 0x7FFF | 0111 1111 1110 1111 |
| $+200 / 2^{14}$                     | +2      | 0x0002 | 0000 0000 0000 0010 |
| $+200 / 2^{15}$                     | +1      | 0x0001 | 0000 0000 0000 0001 |
| 0                                   | 0       | 0x0000 | 0000 0000 0000 0000 |



| Velocity (m/sec) | Decimal | Hex    | Binary              |
|------------------|---------|--------|---------------------|
| $-200/2^{15}$    | -1      | 0xFFFF | 1111 1111 1111 1111 |
| $-200/2^{14}$    | -2      | 0xFFFE | 1111 1111 1111 1110 |
| -200             | -32,768 | 0x8000 | 1000 0000 0000 0000 |

Table 77. 32-Bit Delta Angle Data Format Examples

| Velocity (m/sec)                  | Decimal        | Hex        |
|-----------------------------------|----------------|------------|
| $+200 \times (2^{31} - 1)/2^{31}$ | +2,147,483,647 | 0x7FFFFFFF |
| $+200/2^{30}$                     | +2             | 0x00000002 |
| $+200/2^{31}$                     | +1             | 0x00000001 |
| 0                                 | 0              | 0x00000000 |
| $-200/2^{31}$                     | -1             | 0xFFFFFFF  |
| $-200/2^{30}$                     | -2             | 0xFFFFFFF  |
| -200                              | -2,147,483,648 | 0x80000000 |

**Product Identification, PROD\_ID**

Table 78. PROD\_ID Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x00 | 0x7E, 0x7F | 0x406A  | R      | Yes          |

Table 79. PROD\_ID Bit Definitions

| Bits   | Description                     |
|--------|---------------------------------|
| [15:0] | Product identification = 0x406A |

The PROD\_ID register (see Table 78 and Table 79) contains the numerical portion of the part number (16490). See Figure 35 for an example of how to use a looping read of this register to validate the integrity of the communication.

**CALIBRATION**

The signal chain of each inertial sensor (accelerometers, gyroscopes) includes application of unique correction formulas that come from extensive characterization of bias, sensitivity, alignment, and response to linear acceleration (gyroscopes) over a temperature range of  $-40^{\circ}\text{C}$  to  $+85^{\circ}\text{C}$  for the ADIS16490. These correction formulas are not accessible, but users do have the opportunity to adjust the bias and the scale factor, for each sensor individually, through user accessible registers. These correction factors follow immediately after the factory derived correction formulas in the signal chain, which processes at a rate of 4250 Hz when using the internal sample clock (see  $f_{\text{SM}}$  in Figure 23 and Figure 24).

**Calibration, Gyroscope Scale, X\_GYRO\_SCALE**

Table 80. X\_GYRO\_SCALE Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x04, 0x05 | 0x0000  | R/W    | Yes          |

Table 81. X\_GYRO\_SCALE Bit Definitions

| Bits   | Description                                                                                                        |
|--------|--------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis gyroscope scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The X\_GYRO\_SCALE register (see Table 80 and Table 81) provides users with the opportunity to adjust the scale factor for the x-axis gyroscopes. See Figure 46 for an illustration of how this scale factor influences the x-axis gyroscope data.

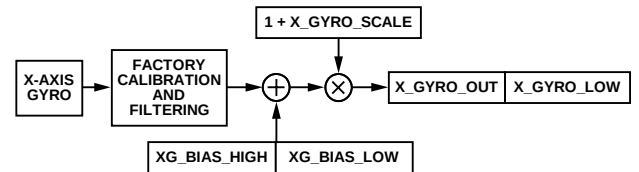


Figure 46. User Calibration Signal Path, Gyroscopes

**Calibration, Gyroscope Scale, Y\_GYRO\_SCALE**

Table 82. Y\_GYRO\_SCALE Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x06, 0x07 | 0x0000  | R/W    | Yes          |

Table 83. Y\_GYRO\_SCALE Bit Definitions

| Bits   | Description                                                                                                        |
|--------|--------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis gyroscope scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The Y\_GYRO\_SCALE register (see Table 82 and Table 83) allows users to adjust the scale factor for the y-axis gyroscopes. This register influences the y-axis gyroscope measurements in the same manner that X\_GYRO\_SCALE influences the x-axis gyroscope measurements (see Figure 46).

**Calibration, Gyroscope Scale, Z\_GYRO\_SCALE**

Table 84. Z\_GYRO\_SCALE Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x08, 0x09 | 0x0000  | R/W    | Yes          |

Table 85. Z\_GYRO\_SCALE Bit Definitions

| Bits   | Description                                                                                                        |
|--------|--------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis gyroscope scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The Z\_GYRO\_SCALE register (see Table 84 and Table 85) allows users to adjust the scale factor for the z-axis gyroscopes. This register influences the z-axis gyroscope measurements in the same manner that X\_GYRO\_SCALE influences the x-axis gyroscope measurements (see Figure 46).

**Calibration, Accelerometer Scale, X\_ACCL\_SCALE**

Table 86. X\_ACCL\_SCALE Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x0A, 0x0B | 0x0000  | R/W    | Yes          |

Table 87. X\_ACCL\_SCALE Bit Definitions

| Bits   | Description                                                                                                            |
|--------|------------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis accelerometer scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The X\_ACCL\_SCALE register (see Table 86 and Table 87) allows users to adjust the scale factor for the x-axis accelerometers. See Figure 47 for an illustration of how this scale factor influences the x-axis accelerometer data.

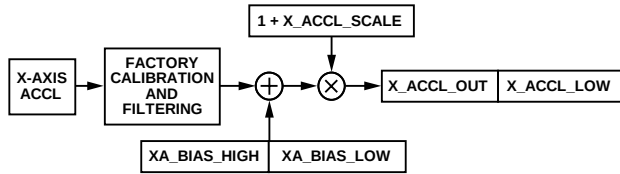


Figure 47. User Calibration Signal Path, Accelerometers

**Calibration, Accelerometer Scale, Y\_ACCL\_SCALE****Table 88. Y\_ACCL\_SCALE Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x0C, 0x0D | 0x0000  | R/W    | Yes          |

**Table 89. Y\_ACCL\_SCALE Bit Definitions**

| Bits   | Description                                                                                                            |
|--------|------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis accelerometer scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The Y\_ACCL\_SCALE register (see Table 88 and Table 89) allows users to adjust the scale factor for the y-axis accelerometers. This register influences the y-axis accelerometer measurements in the same manner that X\_ACCL\_SCALE influences the x-axis accelerometer measurements (see Figure 47).

**Calibration, Accelerometer Scale, Z\_ACCL\_SCALE****Table 90. Z\_ACCL\_SCALE Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x0E, 0x0F | 0x0000  | R/W    | Yes          |

**Table 91. Z\_ACCL\_SCALE Bit Definitions**

| Bits   | Description                                                                                                            |
|--------|------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis accelerometer scale correction; twos complement, 0x0000 = unity gain, 1 LSB = $1 \div 2^{15} = \sim 0.003052\%$ |

The Z\_ACCL\_SCALE register (see Table 90 and Table 91) allows users to adjust the scale factor for the z-axis accelerometers. This register influences the z-axis accelerometer measurements in the same manner that X\_ACCL\_SCALE influences the x-axis accelerometer measurements (see Figure 47).

**Calibration, Gyroscope Bias, XG\_BIAS\_LOW, XG\_BIAS\_HIGH****Table 92. XG\_BIAS\_LOW Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x10, 0x11 | 0x0000  | R/W    | Yes          |

**Table 93. XG\_BIAS\_LOW Bit Definitions**

| Bits   | Description                                                                                                                  |
|--------|------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis gyroscope offset correction, low word; twos complement, 0°/sec = 0x0000, 1 LSB = $0.005^\circ/\text{sec} \div 2^{16}$ |

**Table 94. XG\_BIAS\_HIGH Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x12, 0x13 | 0x0000  | R/W    | Yes          |

**Table 95. XG\_BIAS\_HIGH Bit Definitions**

| Bits   | Description                                                                                                       |
|--------|-------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis gyroscope offset correction, high word; twos complement, 0°/sec = 0x0000, 1 LSB = $0.005^\circ/\text{sec}$ |

The XG\_BIAS\_LOW (see Table 92 and Table 93) and XG\_BIAS\_HIGH (see Table 94 and Table 95) registers combine to allow users to adjust the bias of the x-axis gyroscopes. The digital format examples in Table 34 also apply to the XG\_BIAS\_HIGH register, and the digital format examples in Table 35 apply to the number that comes from combining the XG\_BIAS\_LOW and XG\_BIAS\_HIGH registers. See Figure 46 for an illustration of how these two registers combine and influence the x-axis gyroscope measurements.

**Calibration, Gyroscope Bias, YG\_BIAS\_LOW, YG\_BIAS\_HIGH****Table 96. YG\_BIAS\_LOW Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x14, 0x15 | 0x0000  | R/W    | Yes          |

**Table 97. YG\_BIAS\_LOW Bit Definitions**

| Bits   | Description                                                                                                                  |
|--------|------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis gyroscope offset correction, low word; twos complement, 0°/sec = 0x0000, 1 LSB = $0.005^\circ/\text{sec} \div 2^{16}$ |

**Table 98. YG\_BIAS\_HIGH Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x16, 0x17 | 0x0000  | R/W    | Yes          |

**Table 99. YG\_BIAS\_HIGH Bit Definitions**

| Bits   | Description                                                                                                       |
|--------|-------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis gyroscope offset correction, high word; twos complement, 0°/sec = 0x0000, 1 LSB = $0.005^\circ/\text{sec}$ |

The YG\_BIAS\_LOW (see Table 96 and Table 97) and YG\_BIAS\_HIGH (see Table 98 and Table 99) registers combine to allow users to adjust the bias of the y-axis gyroscopes. The digital format examples in Table 34 also apply to the YG\_BIAS\_HIGH register, and the digital format examples in Table 35 apply to the number that comes from combining the YG\_BIAS\_LOW and YG\_BIAS\_HIGH registers. These registers influence the y-axis gyroscope measurements in the same manner that the XG\_BIAS\_LOW and XG\_BIAS\_HIGH registers influence the x-axis gyroscope measurements (see Figure 46).

**Calibration, Gyroscope Bias, ZG\_BIAS\_LOW, ZG\_BIAS\_HIGH****Table 100. ZG\_BIAS\_LOW Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x18, 0x19 | 0x0000  | R/W    | Yes          |

**Table 101. ZG\_BIAS\_LOW Bit Definitions**

| Bits   | Description                                                                                                                  |
|--------|------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis gyroscope offset correction, low word; twos complement, 0°/sec = 0x0000, 1 LSB = $0.005^\circ/\text{sec} \div 2^{16}$ |

Table 102. ZG\_BIAS\_HIGH Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x1A, 0x1B | 0x0000  | R/W    | Yes          |

Table 103. ZG\_BIAS\_HIGH Bit Definitions

| Bits   | Description                                                                                                                     |
|--------|---------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis gyroscope offset correction, high word twos complement, $0^\circ/\text{sec} = 0x0000$ , 1 LSB = $0.005^\circ/\text{sec}$ |

The ZG\_BIAS\_LOW (see Table 100 and Table 101) and ZG\_BIAS\_HIGH (see Table 102 and Table 103) registers combine to allow users to adjust the bias of the z-axis gyroscopes. The digital format examples in Table 34 also apply to the ZG\_BIAS\_HIGH register, and the digital format examples in Table 35 apply to the number that comes from combining the ZG\_BIAS\_LOW and ZG\_BIAS\_HIGH registers. These registers influence the z-axis gyroscope measurements in the same manner that the XG\_BIAS\_LOW and XG\_BIAS\_HIGH registers influence the x-axis gyroscope measurements (see Figure 46).

#### **Calibration, Accelerometer Bias, XA\_BIAS\_LOW, XA\_BIAS\_HIGH**

Table 104. XA\_BIAS\_LOW Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x1C, 0x1D | 0x0000  | R/W    | Yes          |

Table 105. XA\_BIAS\_LOW Bit Definitions

| Bits   | Description                                                                                                                    |
|--------|--------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis accelerometer offset correction, low word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg} \div 2^{16}$ |

Table 106. XA\_BIAS\_HIGH Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x1E, 0x1F | 0x0000  | R/W    | Yes          |

Table 107. XA\_BIAS\_HIGH Bit Definitions

| Bits   | Description                                                                                                         |
|--------|---------------------------------------------------------------------------------------------------------------------|
| [15:0] | X-axis accelerometer offset correction, high word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg}$ |

The XA\_BIAS\_LOW (see Table 104 and Table 105) and XA\_BIAS\_HIGH (see Table 106 and Table 107) registers combine to allow users to adjust the bias of the x-axis accelerometers. The digital format examples in Table 48 also apply to the XA\_BIAS\_HIGH register and the digital format examples in Table 49 apply to the number that comes from combining the XA\_BIAS\_LOW and XA\_BIAS\_HIGH registers. See Figure 47 for an illustration of how these two registers combine and influence the x-axis gyroscope measurements.

#### **Calibration, Accelerometer Bias, YA\_BIAS\_LOW, YA\_BIAS\_HIGH**

Table 108. YA\_BIAS\_LOW Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x20, 0x21 | 0x0000  | R/W    | Yes          |

Table 109. YA\_BIAS\_LOW Bit Definitions

| Bits   | Description                                                                                                                    |
|--------|--------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis accelerometer offset correction, low word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg} \div 2^{16}$ |

Table 110. YA\_BIAS\_HIGH Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x22, 0x23 | 0x0000  | R/W    | Yes          |

Table 111. YA\_BIAS\_HIGH Bit Definitions

| Bits   | Description                                                                                                         |
|--------|---------------------------------------------------------------------------------------------------------------------|
| [15:0] | Y-axis accelerometer offset correction, high word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg}$ |

The YA\_BIAS\_LOW (see Table 108 and Table 109) and YA\_BIAS\_HIGH (see Table 110 and Table 111) registers combine to allow users to adjust the bias of the y-axis accelerometers. The digital format examples in Table 48 also apply to the YA\_BIAS\_HIGH register, and the digital format examples in Table 49 apply to the number that comes from combining the YA\_BIAS\_LOW and YA\_BIAS\_HIGH registers. These registers influence the y-axis accelerometer measurements in the same manner that the XA\_BIAS\_LOW and XA\_BIAS\_HIGH registers influence the x-axis accelerometer measurements (see Figure 47).

#### **Calibration, Accelerometer Bias, ZA\_BIAS\_LOW, ZA\_BIAS\_HIGH**

Table 112. ZA\_BIAS\_LOW Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x24, 0x25 | 0x0000  | R/W    | Yes          |

Table 113. ZA\_BIAS\_LOW Bit Definitions

| Bits   | Description                                                                                                                    |
|--------|--------------------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis accelerometer offset correction, low word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg} \div 2^{16}$ |

Table 114. ZA\_BIAS\_HIGH Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x26, 0x27 | 0x0000  | R/W    | Yes          |

Table 115. ZA\_BIAS\_HIGH Bit Definitions

| Bits   | Description                                                                                                         |
|--------|---------------------------------------------------------------------------------------------------------------------|
| [15:0] | Z-axis accelerometer offset correction, high word, twos complement, $0\text{ g} = 0x0000$ , 1 LSB = $0.5\text{ mg}$ |

The ZA\_BIAS\_LOW (see Table 112 and Table 113) and ZA\_BIAS\_HIGH (see Table 114 and Table 115) registers combine to allow users to adjust the bias of the z-axis accelerometers. The digital format examples in Table 48 also apply to the ZA\_BIAS\_HIGH register and the digital format examples in Table 49 apply to the number that comes from combining the ZA\_BIAS\_LOW and ZA\_BIAS\_HIGH registers. These registers influence the z-axis accelerometer measurements in the same manner that the XA\_BIAS\_LOW and XA\_BIAS\_HIGH registers influence the x-axis accelerometer measurements (see Figure 47).

**Scratch Registers, USER\_SCR\_x****Table 116. USER\_SCR\_1 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x74, 0x75 | 0x0000  | R/W    | Yes          |

**Table 117. USER\_SCR\_1 Bit Definitions**

| Bits   | Description  |
|--------|--------------|
| [15:0] | User defined |

**Table 118. USER\_SCR\_2 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x76, 0x77 | 0x0000  | R/W    | Yes          |

**Table 119. USER\_SCR\_2 Bit Definitions**

| Bits   | Description  |
|--------|--------------|
| [15:0] | User defined |

**Table 120. USER\_SCR\_3 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x78, 0x79 | 0x0000  | R/W    | Yes          |

**Table 121. USER\_SCR\_3 Bit Definitions**

| Bits   | Description  |
|--------|--------------|
| [15:0] | User defined |

**Table 122. USER\_SCR\_4 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x02 | 0x7A, 0x7B | 0x0000  | R/W    | Yes          |

**Table 123. USER\_SCR\_4 Bit Definitions**

| Bits   | Description  |
|--------|--------------|
| [15:0] | User defined |

The USER\_SCR\_1 (see Table 116 and Table 117), USER\_SCR\_2 (see Table 118 and Table 119), USER\_SCR\_3 (see Table 120 and Table 121), USER\_SCR\_4 (see Table 122 and Table 123) registers provide four locations for users to store information.

**Flash Memory Endurance Counter, FLSHCNT\_LOW, FLSHCNT\_HIGH****Table 124. FLSHCNT\_LOW Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x02 | 0x7C, 0x7D | Not applicable | R      | Yes          |

**Table 125. FLSHCNT\_LOW Bit Definitions**

| Bits   | Description                          |
|--------|--------------------------------------|
| [15:0] | Flash memory write counter, low word |

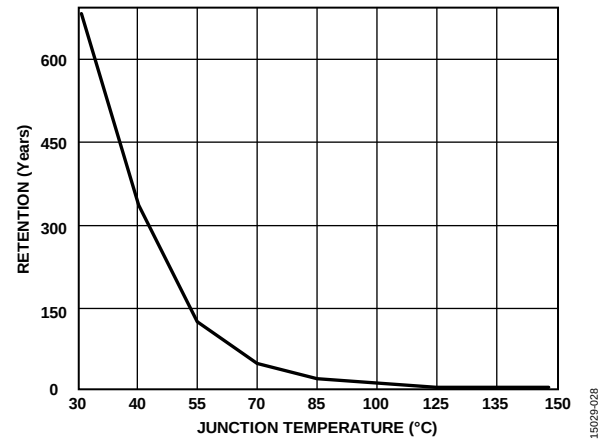
**Table 126. FLSHCNT\_HIGH Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x02 | 0x7E, 0x7F | Not applicable | R      | Yes          |

**Table 127. FLSHCNT\_HIGH Bit Definitions**

| Bits   | Description                           |
|--------|---------------------------------------|
| [15:0] | Flash memory write counter, high word |

The FLSHCNT\_LOW (see Table 124 and Table 125) and FLSHCNT\_HIGH (see Table 126 and Table 127) registers combine to provide a 32-bit, binary counter that tracks the number of flash memory write cycles. In addition to the number of write cycles, the flash memory has a finite service lifetime, which depends on the junction temperature. Figure 48 provides guidance for estimating the retention life for the flash memory at specific junction temperatures. The junction temperature is approximately 7°C above the case temperature.

*Figure 48. Flash Memory Retention***Global Commands, GLOB\_CMD****Table 128. GLOB\_CMD Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x03 | 0x02, 0x03 | Not applicable | W      | No           |

**Table 129. GLOB\_CMD Bit Definitions**

| Bits   | Description                 |
|--------|-----------------------------|
| [15:8] | Not used                    |
| 7      | Software reset              |
| 6      | Factory calibration restore |
| [5:4]  | Not used                    |
| 3      | Flash memory update         |
| 2      | Not used                    |
| 1      | Self test                   |
| 0      | Bias correction update      |

The GLOB\_CMD register (see Table 128 and Table 129) provides trigger bits for several operations. Write a 1 to the appropriate bit in GLOB\_CMD to start a particular function.

**Software Reset**

Select Page 3 (DIN = 0x8003) and then set GLOB\_CMD[7] = 1 (DIN = 0x8280, DIN = 0x8300) to initiate a reset in the operation of the ADIS16490. This reset removes all data, initializes all registers from their flash settings, and restarts data sampling and processing. This function provides a firmware alternative to providing a low pulse on the RST pin (see Table 6, Pin 8).

### Factory Calibration Restore

Select Page 3 (DIN = 0x8003) and then set GLOB\_CMD[6] = 1 (DIN = 0x8240, DIN = 0x8300) to initiate restoration of the factory calibration. This restoration writes 0x0000 to the following registers: X\_GYRO\_SCALE, Y\_GYRO\_SCALE, Z\_GYRO\_SCALE, X\_ACCL\_SCALE, Y\_ACCL\_SCALE, Z\_ACCL\_SCALE, XG\_BIAS\_LOW, XG\_BIAS\_HIGH, YG\_BIAS\_LOW, YG\_BIAS\_HIGH, ZG\_BIAS\_LOW, ZG\_BIAS\_HIGH, XA\_BIAS\_LOW, XA\_BIAS\_HIGH, YA\_BIAS\_LOW, YA\_BIAS\_HIGH, ZA\_BIAS\_LOW, and ZA\_BIAS\_HIGH.

### Flash Memory Update

Select Page 3 (DIN = 0x8003) and then set GLOB\_CMD[3] = 1 (DIN = 0x8208, DIN = 0x8300) to initiate a manual flash update. SYS\_E\_FLAG[6] (see Table 16) identifies success (0) or failure (1) in completing this process.

Note that the user must not poll the status registers while waiting for the update to complete because the serial port is disabled. Rather, the user must either wait the prescribed amount of time found in Table 3 or wait for the data ready indicator pin to begin toggling.

### On Demand Self Test (ODST)

Select Page 3 (DIN = 0x8003) and then set GLOB\_CMD[1] = 1 (DIN = 0x8202, then DIN = 0x8300) to run the ODST routine, which executes the following steps:

1. Measure the output on each sensor.
2. Activate an internal force on the mechanical elements of each sensor, which simulates the force associated with actual inertial motion.
3. Measure the output response on each sensor.
4. Deactivate the internal force on each sensor.
5. Calculate the difference between the force on and normal operating conditions (force off).
6. Compare the difference with internal pass/fail criteria.
7. Report the pass/fail results for each sensor in DIAG\_STS (see Table 18) and the overall pass/fail flag in SYS\_E\_FLAG[5] (see Table 16).

False positive results are possible when executing the ODST while the device is in motion. Note that the user must not poll the status registers while waiting for the test to complete. Rather, the user must either wait the prescribed amount of time found in Table 3 or wait for the data ready indicator pin to begin toggling.

### Bias Correction Update

Select Page 3 (DIN = 0x8003) and set GLOB\_CMD[0] = 1 (DIN = 0x8201, then DIN = 0x8300) to update the user offset registers with the correction factors of the CBE (see Table 139). Ensure that the inertial platform is stable during the entire average time for optimal bias estimates.

### Auxiliary I/O Line Configuration, FNCTIO\_CTRL

Table 130. FNCTIO\_CTRL Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x06, 0x07 | 0x000D  | R/W    | Yes          |

Table 131. FNCTIO\_CTRL Bit Definitions

| Bits   | Description                                                                    |
|--------|--------------------------------------------------------------------------------|
| [15:9] | Not used                                                                       |
| 8      | Sync clock mode: 1 = PPS, 0 = sync                                             |
| 7      | Sync clock input enable: 1 = enabled, 0 = disabled                             |
| 6      | Sync clock input polarity:<br>1 = rising edge, 0 = falling edge                |
| [5:4]  | Sync clock input line selection:<br>00 = DIO1, 01 = DIO2, 10 = DIO3, 11 = DIO4 |
| 3      | Data ready enable: 1 = enabled, 0 = disabled                                   |
| 2      | Data ready polarity: 1 = positive, 0 = negative                                |
| [1:0]  | Data ready line selection:<br>00 = DIO1, 01 = DIO2, 10 = DIO3, 11 = DIO4       |

The FNCTIO\_CTRL register (see Table 130 and Table 131) provides configuration control for each I/O pin (DIO1, DIO2, DIO3, and DIO4). Each DIOx pin supports only one function at a time. When a single pin has two assignments, the enable bit for the lower priority function automatically resets to zero (disabling the lower priority function). The order of priority is as follows, from highest priority to lowest priority: data ready, sync clock input, and general-purpose. The ADIS16490 can take up to 20 ms to execute a write command to the FNCTIO\_CTRL register. During this time, the operational state and the contents of the register remain unchanged, but the SPI interface supports normal communication (for accessing other registers).

### Data Ready Indicator

The FNCTIO\_CTRL[3:0] bits provide three configuration options for the data ready function: on/off, polarity, and DIOx line. The primary purpose this signal is to drive the interrupt control line of an embedded processor, which can help synchronize data collection and minimize latency. The data ready indicator is useful to determine if the controller inside the ADIS16490 is busy with a task (for example, a flash memory update) because data ready stops toggling while these tasks are performed and resumes on completion. The factory default assigns DIO2 as a positive polarity, data ready signal, which means that the data in the output registers is valid when the DIO2 line is high (see Figure 30). This configuration works well when DIO2 drives an interrupt service pin that activates on a low to high pulse. Use the following sequence to change this assignment to DIO3 with negative polarity:

1. Select Page 3 (DIN = 0x8003).
2. Set FNCTIO\_CTRL[3:0] = 1000 (DIN = 0x860A, then DIN = 0x8700).

The timing jitter on the data ready signal is typically within  $\pm 1.4 \mu\text{s}$ . When using DIO1 to support the data ready function, this signal can experience premature data ready pulses during the ADIS16490 start-up. However, these pulses do not indicate



that data production has started. If it is necessary to use DIO1 for this function, use it in conjunction with a delay or other control mechanism to prevent premature data acquisition activity during the start-up process.

### Input Sync/Clock Control

The FNCTIO\_CTRL[8:4] bits provide several configuration options for using one of the DIOx lines as an external clock signal and for controlling inertial sensor data collection and processing. For example, use the following sequence to establish DIO4 as a positive polarity, input clock pin that operates in sync mode and preserves the factory default setting for the data ready function:

1. Select Page 3 (DIN = 0x8003).
2. Set FNCTIO\_CTRL[7:0] = 0xFD (DIN = 0x86FD).
3. Set FNCTIO\_CTRL[15:8] = 0x00 (DIN = 0x8700).

In sync mode, the ADIS16490 disables its internal sample clock, and the frequency of the external clock signal establishes the rate of data collection and processing ( $f_{SM}$  in Figure 23 and Figure 24). When using the PPS mode (FNCTIO\_CTRL[8] = 1) the rate of data collection and production ( $f_{SM}$ ) is equal to the product of the external clock frequency and scale factor ( $K_{ECSE}$ ) in the SYNC\_SCALE register (see Table 141).

### General-Purpose I/O Control, GPIO\_CTRL

Table 132. GPIO\_CTRL Register Definitions<sup>1</sup>

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x08, 0x09 | 0x00X0  | R/W    | Yes          |

<sup>1</sup> The GPIO\_CTRL[7:4] bits reflect the logic levels on the DIOx lines and do not have a default setting.

Table 133. GPIO\_CTRL Bit Definitions<sup>1</sup>

| Bits   | Description                                                                 |
|--------|-----------------------------------------------------------------------------|
| [15:8] | Don't care                                                                  |
| 7      | General-Purpose I/O Line 4 (DIO4) data level                                |
| 6      | General-Purpose I/O Line 3 (DIO3) data level                                |
| 5      | General-Purpose I/O Line 2 (DIO2) data level                                |
| 4      | General-Purpose I/O Line 1 (DIO1) data level                                |
| 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) |

<sup>1</sup> The GPIO\_CTRL[7:4] bits reflect the logic levels on the DIOx lines and do not have a default setting.

When FNCTIO\_CTRL does not configure a DIOx pin, the GPIO\_CTRL register (see Table 132 and Table 133) provides user controls for general-purpose use of the DIOx pins. GPIO\_CTRL[3:0] provide input/output assignment controls for each line. When the DIOx lines are inputs, monitor their level by reading GPIO\_CTRL[7:4]. When the DIOx lines are used as outputs,

set their level by writing to GPIO\_CTRL[7:4]. For example, use the following sequence to set DIO1 and DIO3 as high and low output lines, respectively, and set DIO2 and DIO4 as input lines. Select Page 3 (DIN = 0x8003) and set GPIO\_CTRL[7:0] = 0x15 (DIN = 0x8815, then DIN = 0x8900).

### Miscellaneous Configuration, CONFIG

Table 134. CONFIG Register Definitions

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x0A, 0x0B | 0x00C0  | R/W    | Yes          |

Table 135. CONFIG Bit Definitions

| Bits   | Description                                        |
|--------|----------------------------------------------------|
| [15:8] | Not used                                           |
| 7      | Linear g compensation for gyroscopes (1 = enabled) |
| 6      | Point of percussion alignment (1 = enabled)        |
| [5:0]  | Not used                                           |

The CONFIG register (see Table 134 and Table 135) provides configuration options for the linear g compensation in the gyroscopes (on/off) and the point of percussion alignment for the accelerometers (on/off).

### Point of Percussion

CONFIG[6] offers a point of percussion alignment function that maps the accelerometer sensors to the corner of the package identified in Figure 49. To activate this feature, select Page 3 (DIN = 0x8003), then set CONFIG[6] = 1 (DIN = 0x8A40, DIN = 0x8B00).

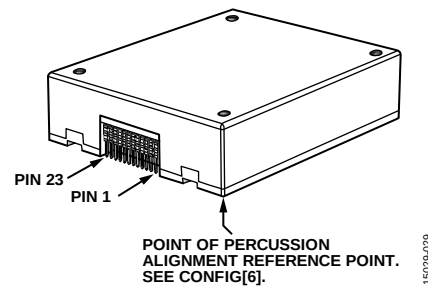


Figure 49. Point of Percussion Reference Point

### Linear Acceleration on Effect on Gyroscope Bias

The ADIS16490 includes first-order compensation for the linear g effect in the gyroscopes, which uses the following model:

$$\begin{bmatrix} \omega_{XC} \\ \omega_{YC} \\ \omega_{ZC} \end{bmatrix} = \begin{bmatrix} LG_{11} & LG_{12} & LG_{13} \\ LG_{21} & LG_{22} & LG_{23} \\ LG_{31} & LG_{32} & LG_{33} \end{bmatrix} \times \begin{bmatrix} A_X \\ A_Y \\ A_Z \end{bmatrix} + \begin{bmatrix} \omega_{XPC} \\ \omega_{YPC} \\ \omega_{ZPC} \end{bmatrix}$$

The linear g correction factors,  $LG_{XY}$ , apply correction for linear acceleration in all three directions to the data path of each gyroscope ( $\omega_{XPC}$ ,  $\omega_{YPC}$ , and  $\omega_{ZPC}$ ) at the rate of the data samples (4250 SPS when using the internal clock). CONFIG[7] provides an on/off control for this compensation. The factory default value for this bit activates this compensation. To turn it off, select Page 3 (DIN = 0x8003) and set CONFIG[7] = 0 (DIN = 0x8A40, DIN =

0x8B00). Note that this command sequence also preserves the default setting for the point of percussion alignment function (on).

### Decimation Filter, DEC\_RATE

**Table 136. DEC\_RATE Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x0C, 0x0D | 0x0000  | R/W    | Yes          |

**Table 137. DEC\_RATE Bit Definitions**

| Bits   | Description                                    |
|--------|------------------------------------------------|
| [15:0] | Decimation rate, binary format, maximum = 4249 |

The DEC\_RATE register (see Table 136 and Table 137) provides user control for the final filter stage (see Figure 26), which averages and decimates the accelerometers and gyroscopes data, while also extending the time that the delta angle and delta velocity track between each update. The output sample rate is equal to  $4250 / (\text{DEC\_RATE} + 1)$ . For example, select Page 3 (DIN = 0x8003), and set DEC\_RATE = 0x2A (DIN = 0x8C2A, then DIN = 0x8D00) to reduce the output sample rate to ~98.8 SPS ( $4250 \div 43$ ).

### Data Update Rate in External Sync Modes

When using the input sync option, in direct mode (FNCTIO\_CTRL[8:7] = 01, see Table 131), replace the 4250 number in this relationship with the input clock frequency. When using the input sync option, in PPS mode (FNCTIO\_CTRL[8:7] = 11, see Table 131), replace the 4250 number in this relationship with the product of the input sync frequency and the scale value in the SYNC\_SCALE register (see Table 141).

### Continuous Bias Estimation (CBE), NULL\_CNFG

**Table 138. NULL\_CNFG Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x0E, 0x0F | 0x070A  | R/W    | Yes          |

**Table 139. NULL\_CNFG Bit Definitions**

| Bits    | Description                                                                                                                             |
|---------|-----------------------------------------------------------------------------------------------------------------------------------------|
| [15:14] | Not used                                                                                                                                |
| 13      | Z-axis acceleration bias correction enable (1 = enabled)                                                                                |
| 12      | Y-axis acceleration bias correction enable (1 = enabled)                                                                                |
| 11      | X-axis acceleration bias correction enable (1 = enabled)                                                                                |
| 10      | Z-axis gyroscope bias correction enable (1 = enabled)                                                                                   |
| 9       | Y-axis gyroscope bias correction enable (1 = enabled)                                                                                   |
| 8       | X-axis gyroscope bias correction enable (1 = enabled)                                                                                   |
| [7:4]   | Not used                                                                                                                                |
| [3:0]   | Time base control (TBC), range: 0 to 13 (default = 10); $t_B = 2^{\text{TBC}} / 4250$ , time base; $t_A = 64 \times t_B$ , average time |

The NULL\_CNFG register (see Table 138 and Table 139) provides the configuration controls for the continuous bias estimator (CBE), which associates with the bias correction update command in GLOB\_CMD[0] (see Table 129). NULL\_CNFG[3:0] establishes the total average time ( $t_A$ ) for the bias estimates and NULL\_CNFG[13:8] provide on/off controls for each sensor. The factory default configuration for

NULL\_CNFG enables the bias null command for the gyroscopes, disables the bias null command for the accelerometers, and sets the average time to ~15.42 seconds.

$$t_B = 2^{\text{TBC}} / 4250 = 2^{10} / 4250 = \sim 0.241 \text{ seconds}$$

$$t_A = 64 \times t_B = 64 \times 0.241 = 15.42 \text{ seconds}$$

where:

$t_B$  is the time base.

$t_A$  is the averaging time.

When a sensor bit in NULL\_CNFG is active (equal to 1), setting GLOB\_CMD[0] = 1 (DIN sequence: 0x8003, 0x8201, 0x8300) causes its bias correction register to automatically update with a value that corrects for its present bias error (from the CBE). For example, setting NULL\_CNFG[8] equal to 1 causes an update in the XG\_BIAS\_LOW (see Table 93) and XG\_BIAS\_HIGH (see Table 95) registers.

### Scaling the Input Clock (PPS Mode), SYNC\_SCALE

**Table 140. SYNC\_SCALE Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x10, 0x11 | 0x109A  | R/W    | Yes          |

**Table 141. SYNC\_SCALE Bit Definitions**

| Bits   | Description                                                     |
|--------|-----------------------------------------------------------------|
| [15:0] | External clock scale factor ( $K_{\text{ECF}}$ ), binary format |

The PPS mode (FNCTIO\_CTRL[8] = 1, see Table 131) supports the use of an input sync frequency that is slower than the data sample rates of the inertial sensors. This mode supports a frequency range of 1 Hz to 128 Hz for the input sync mode. In this mode, the data sample rate is equal to the product of the value in the SYNC\_SCALE register (see Table 140 and Table 141) and the input sync frequency. For example, the following command sequence sets the data collection and processing rate ( $f_{\text{SM}}$  in Figure 23 and Figure 24) to 4000 Hz (SYNC\_SCALE = 0x0FA0) when using a 1 Hz signal on the DIO3 line as the external clock input, while also preserving the factory default configuration for the data ready signal:

1. Select Page 3 (DIN = 0x8003).
2. Set SYNC\_SCALE[7:0] = 0xA0 (DIN = 0x90A0).
3. Set SYNC\_SCALE[15:8] = 0x0F (DIN = 0x910F).
4. Set FNCTIO\_CTRL[7:0] = 0xFD (DIN = 0x86ED).
5. Set FNCTIO\_CTRL[15:8] = 0x00 (DIN = 0x8701).

Note that the data ready indicator pin does not begin to toggle until at least two external clock edges (with valid time period between them) are detected by the ADIS16495.



**FIR Filter Control, FILTR\_BNK\_0, FILTR\_BNK\_1****Table 142. FILTR\_BNK\_0 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x16, 0x17 | 0x0000  | R/W    | Yes          |

**Table 143. FILTR\_BNK\_0 Bit Definitions**

| Bits    | Description (Default = 0x0000)                                                                    |
|---------|---------------------------------------------------------------------------------------------------|
| 15      | Don't care                                                                                        |
| 14      | Y-axis accelerometer filter enable (1 = enabled)                                                  |
| [13:12] | Y-axis accelerometer filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D |
| 11      | X-axis accelerometer filter enable (1 = enabled)                                                  |
| [10:9]  | X-axis accelerometer filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D |
| 8       | Z-axis gyroscope filter enable (1 = enabled)                                                      |
| [7:6]   | Z-axis gyroscope filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D     |
| 5       | Y-axis gyroscope filter enable (1 = enabled)                                                      |
| [4:3]   | Y-axis gyroscope filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D     |
| 2       | X-axis gyroscope filter enable (1 = enabled)                                                      |
| [1:0]   | X-axis gyroscope filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D     |

**Table 144. FILTR\_BNK\_1 Register Definitions**

| Page | Addresses  | Default | Access | Flash Backup |
|------|------------|---------|--------|--------------|
| 0x03 | 0x18, 0x19 | 0x0000  | R/W    | Yes          |

**Table 145. FILTR\_BNK\_1 Bit Definitions**

| Bits   | Description                                                                                       |
|--------|---------------------------------------------------------------------------------------------------|
| [15:3] | Don't care                                                                                        |
| 2      | Z-axis accelerometer filter enable (1 = enabled)                                                  |
| [1:0]  | Z-axis accelerometer filter bank selection:<br>00 = Bank A, 01 = Bank B, 10 = Bank C, 11 = Bank D |

The FILTR\_BNK\_0 (see Table 142 and Table 143) and FILTR\_BNK\_1 (see Table 144 and Table 145) registers provide the configuration controls for the FIR filter bank in the signal chain of each sensor (see Figure 26). These registers provide on/off control for the FIR bank for each inertial sensor, along with the FIR bank (A, B, C, or D) that each sensor uses.

**Firmware Revision, FIRM\_REV****Table 146. FIRM\_REV Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x03 | 0x78, 0x79 | Not applicable | R      | Yes          |

**Table 147. FIRM\_REV Bit Definitions**

| Bits    | Description                                                                                                    |
|---------|----------------------------------------------------------------------------------------------------------------|
| [15:12] | Firmware revision binary coded decimal (BCD) code, tens digit, numerical format = 4-bit binary, range = 0 to 9 |
| [11:8]  | Firmware revision BCD code, ones digit, numerical format = 4-bit binary, range = 0 to 9                        |
| [7:4]   | Firmware revision BCD code, tenths digit, numerical format = 4-bit binary, range = 0 to 9                      |
| [3:0]   | Firmware revision BCD code, hundredths digit, numerical format = 4-bit binary, range = 0 to 9                  |

The FIRM\_REV register (see Table 146 and Table 147) provides the firmware revision for the internal firmware. This register uses a BCD format, where each nibble represents a digit. For example, if FIRM\_REV = 0x1234, the firmware revision is 12.34.

**Firmware Revision Day and Month, FIRM\_DM****Table 148. FIRM\_DM Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x03 | 0x7A, 0x7B | Not applicable | R      | Yes          |

**Table 149. FIRM\_DM Bit Definitions**

| Bits    | Description                                                                                       |
|---------|---------------------------------------------------------------------------------------------------|
| [15:12] | Factory configuration month BCD code, tens digit, numerical format = 4-bit binary, range = 0 to 2 |
| [11:8]  | Factory configuration month BCD code, ones digit, numerical format = 4-bit binary, range = 0 to 9 |
| [7:4]   | Factory configuration day BCD code, tens digit, numerical format = 4-bit binary, range = 0 to 3   |
| [3:0]   | Factory configuration day BCD code, ones digit, numerical format = 4-bit binary, range = 0 to 9   |

The FIRM\_DM register (see Table 148 and Table 149) contains the month and day of the factory configuration date. FIRM\_DM[15:12] and FIRM\_DM[11:8] contain digits that represent the month of the factory configuration in a BCD format. For example, November is the 11<sup>th</sup> month in a year and is represented by FIRM\_DM[15:8] = 0x11. FIRM\_DM[7:4] and FIRM\_DM[3:0] contain digits that represent the day of factory configuration in a BCD format. For example, the 27<sup>th</sup> day of the month is represented by FIRM\_DM[7:0] = 0x27.

**Firmware Revision Year, FIRM\_Y****Table 150. FIRM\_Y Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x03 | 0x7C, 0x7D | Not applicable | R      | Yes          |

**Table 151. FIRM\_Y Bit Definitions**

| Bits    | Description                                                                                           |
|---------|-------------------------------------------------------------------------------------------------------|
| [15:12] | Factory configuration year BCD code, thousands digit, numerical format = 4-bit binary, range = 0 to 9 |
| [11:8]  | Factory configuration year BCD code, hundreds digit, numerical format = 4-bit binary, range = 0 to 9  |
| [7:4]   | Factory configuration year BCD code, tens digit, numerical format = 4-bit binary, range = 0 to 3      |
| [3:0]   | Factory configuration year BCD code, ones digit, numerical format = 4-bit binary, range = 0 to 9      |

The FIRM\_Y register (see Table 150 and Table 151) contains the year of the factory configuration date. For example, the year 2013 is represented by FIRM\_Y = 0x2013.

**Boot Revision Number, BOOT\_REV****Table 152. BOOT\_REV Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x03 | 0x7E, 0x7F | Not applicable | R      | Yes          |

**Table 153. BOOT\_REV Bit Definitions**

| Bits   | Description                   |
|--------|-------------------------------|
| [15:8] | Binary, major revision number |
| [7:0]  | Binary, minor revision number |

**Continuous SRAM Testing**

This device employs a CRC function on the SRAM memory blocks that contain the program code (CODE\_SIGTR\_xxx) and the calibration coefficients (CAL\_DRVTN\_xxx). This process operates in the background and generates real-time, 32-bit CRC values for the program code and calibration coefficients, respectively. At the conclusion of each cycle, the processor writes these calculated values in the CAL\_DRVTN\_xxx and CODE\_DRVTN\_xxx registers (see Table 159, Table 161, Table 167, and Table 169) and compares them with the signature values, which reflect the state of these memory locations at the time of factory configuration. When the calculation results do not match the signature values, SYS\_E\_FLAG[2] increases to a 1. The respective signature values are available for user access through the CAL\_SIGTR\_xxx and CODE\_SIGTR\_xxx registers (see Table 155, Table 157, Table 163, and Table 165). The following conditions must be met for SYS\_E\_FLAG[2] to remain at the zero level:

- CAL\_SIGTR\_LWR = CAL\_DRVTN\_LWR
- CAL\_SIGTR\_UPR = CAL\_DRVTN\_UPR
- CODE\_SIGTR\_LWR = CODE\_DRVTN\_LWR
- CODE\_SIGTR\_UPR = CODE\_DRVTN\_UPR

**Signature CRC, Calibration Values, CAL\_SIGTR\_LWR****Table 154. CAL\_SIGTR\_LWR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x04, 0x05 | Not applicable | R      | Yes          |

**Table 155. CAL\_SIGTR\_LWR Bit Definitions**

| Bits   | Description                                                 |
|--------|-------------------------------------------------------------|
| [15:0] | Factory programmed CRC value for the program code, low word |

**Signature CRC, Calibration Values, CAL\_SIGTR\_UPR****Table 156. CAL\_SIGTR\_UPR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x06, 0x07 | Not applicable | R      | Yes          |

**Table 157. CAL\_SIGTR\_UPR Bit Definitions**

| Bits   | Description                                                  |
|--------|--------------------------------------------------------------|
| [15:0] | Factory programmed CRC value for the program code, high word |

**Derived CRC, Calibration Values, CAL\_DRVTN\_LWR****Table 158. CAL\_DRVTN\_LWR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x08, 0x09 | Not applicable | R      | No           |

**Table 159. CAL\_DRVTN\_LWR Bit Definitions**

| Bits   | Description                                         |
|--------|-----------------------------------------------------|
| [15:0] | Calculated CRC value for the program code, low word |

**Derived CRC, Calibration Values, CAL\_DRVTN\_UPR****Table 160. CAL\_DRVTN\_UPR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x0A, 0x0B | Not applicable | R      | No           |

**Table 161. CAL\_DRVTN\_UPR Bit Definitions**

| Bits   | Description                                          |
|--------|------------------------------------------------------|
| [15:0] | Calculated CRC value for the program code, high word |

**Signature CRC, Program Code, CODE\_SIGTR\_LWR****Table 162. CODE\_SIGTR\_LWR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x0C, 0x0D | Not applicable | R      | Yes          |

**Table 163. CODE\_SIGTR\_LWR Bit Definitions**

| Bits   | Description                                                             |
|--------|-------------------------------------------------------------------------|
| [15:0] | Factory programmed CRC value for the calibration coefficients, low word |

**Signature CRC, Program Code, CODE\_SIGTR\_UPR****Table 164. CODE\_SIGTR\_UPR Register Definitions**

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x0E, 0x0F | Not applicable | R      | Yes          |

Table 165. CODE\_SIGTR\_UPR Bit Definitions

| Bits   | Description                                                              |
|--------|--------------------------------------------------------------------------|
| [15:0] | Factory programmed CRC value for the calibration coefficients, high word |

**Derived CRC, Program Code, CODE\_DRVTN\_LWR**

Table 166. CODE\_DRVTN\_LWR Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x10, 0x11 | Not applicable | R      | No           |

Table 167. CODE\_DRVTN\_LWR Bit Definitions

| Bits   | Description                                                     |
|--------|-----------------------------------------------------------------|
| [15:0] | Calculated CRC value for the calibration coefficients, low word |

**Derived CRC, Program Code, CODE\_DRVTN\_UPR**

Table 168. CODE\_DRVTN\_LWR Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x12, 0x13 | Not applicable | R      | No           |

Table 169. CODE\_DRVTN\_UPR Bit Definitions

| Bits   | Description                                                      |
|--------|------------------------------------------------------------------|
| [15:0] | Calculated CRC value for the calibration coefficients, high word |

**Lot Specific Serial Number, SERIAL\_NUM**

Table 170. SERIAL\_NUM Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x04 | 0x20, 0x21 | Not applicable | R      | Yes          |

Table 171. SERIAL\_NUM Bit Definitions

| Bits   | Description                |
|--------|----------------------------|
| [15:0] | Lot specific serial number |

**FIR FILTERS**

The ADIS16490 provides four FIR filter banks to configure and select for each individual inertial sensor using the FILTR\_BNK\_0 (see Table 143) and FILTR\_BNK\_1 (see Table 145) registers. Each FIR filter bank (A, B, C, and D) has 120 taps that consume two pages of memory. The coefficient associated with each tap, in each filter bank, has its own dedicated register that uses a 16-bit, twos complement format. The FIR filter has unity gain when the sum of all of the coefficients is equal to 32,768. For filter designs that require less than 120 taps, write 0x0000 to all unused registers to eliminate the latency associated with that particular tap.

**FIR Filter Bank A, FIR\_COEF\_A000 to FIR\_COEF\_A119**

Table 172. FIR Filter Bank A Memory Map

| Page | PAGE_ID | Addresses    | Register                       |
|------|---------|--------------|--------------------------------|
| 5    | 0x05    | 0x00, 0x01   | PAGE_ID                        |
| 5    | 0x05    | 0x02 to 0x07 | Not used                       |
| 5    | 0x05    | 0x08, 0x09   | FIR_COEF_A000                  |
| 5    | 0x05    | 0x0A, 0x0B   | FIR_COEF_A001                  |
| 5    | 0x05    | 0x0C to 0x7D | FIR_COEF_A002 to FIR_COEF_A058 |
| 5    | 0x05    | 0x7E, 0x07F  | FIR_COEF_A059                  |
| 6    | 0x06    | 0x00, 0x01   | PAGE_ID                        |
| 6    | 0x06    | 0x02 to 0x07 | Not used                       |
| 6    | 0x06    | 0x08, 0x09   | FIR_COEF_A060                  |
| 6    | 0x06    | 0x0A, 0x0B   | FIR_COEF_A061                  |
| 6    | 0x06    | 0x0C to 0x7D | FIR_COEF_A062 to FIR_COEF_A118 |
| 6    | 0x06    | 0x7E, 0x7F   | FIR_COEF_A119                  |

Table 173 and Table 174 provide detailed register and bit definitions for one of the FIR coefficient registers in Bank A, FIR\_COEF\_A071. Table 175 provides a configuration example, which sets this register to a decimal value of -169 (0xFF57).

Table 173. FIR\_COEF\_A071 Register Definitions

| Page | Addresses  | Default        | Access | Flash Backup |
|------|------------|----------------|--------|--------------|
| 0x06 | 0x1E, 0x1F | Not applicable | R/W    | Yes          |

Table 174. FIR\_COEF\_A071 Bit Definitions

| Bits   | Description                                 |
|--------|---------------------------------------------|
| [15:0] | FIR Bank A, Coefficient 71, twos complement |

Table 175. Configuration Example, FIR Coefficient

| DIN    | Description                |
|--------|----------------------------|
| 0x8006 | Select Page 6              |
| 0x9E57 | FIR_COEF_A071[7:0] = 0x57  |
| 0x9FFF | FIR_COEF_A071[15:8] = 0xFF |

**FIR Filter Bank B, FIR\_COEF\_B000 to FIR\_COEF\_B119**

Table 176. Filter Bank B Memory Map

| Page | PAGE_ID | Addresses    | Register                       |
|------|---------|--------------|--------------------------------|
| 7    | 0x07    | 0x00, 0x01   | PAGE_ID                        |
| 7    | 0x07    | 0x02 to 0x07 | Not used                       |
| 7    | 0x07    | 0x08, 0x09   | FIR_COEF_B000                  |
| 7    | 0x07    | 0x0A, 0x0B   | FIR_COEF_B001                  |
| 7    | 0x07    | 0x0C to 0x7D | FIR_COEF_B002 to FIR_COEF_B058 |
| 7    | 0x07    | 0x7E, 0x07F  | FIR_COEF_B059                  |
| 8    | 0x08    | 0x00, 0x01   | PAGE_ID                        |
| 8    | 0x08    | 0x02 to 0x07 | Not used                       |
| 8    | 0x08    | 0x08, 0x09   | FIR_COEF_B060                  |
| 8    | 0x08    | 0x0A, 0x0B   | FIR_COEF_B061                  |
| 8    | 0x08    | 0x0C to 0x7D | FIR_COEF_B062 to FIR_COEF_B118 |
| 8    | 0x08    | 0x7E, 0x7F   | FIR_COEF_B119                  |

**FIR Filter Bank C, FIR\_COEF\_C000 to FIR\_COEF\_C119****Table 177. Filter Bank C Memory Map**

| Page | PAGE_ID | Addresses    | Register                          |
|------|---------|--------------|-----------------------------------|
| 9    | 0x09    | 0x00, 0x01   | PAGE_ID                           |
| 9    | 0x09    | 0x02 to 0x07 | Not used                          |
| 9    | 0x09    | 0x08, 0x09   | FIR_COEF_C000                     |
| 9    | 0x09    | 0x0A, 0x0B   | FIR_COEF_C001                     |
| 9    | 0x09    | 0x0C to 0x7D | FIR_COEF_C002 to<br>FIR_COEF_C058 |
| 9    | 0x09    | 0x7E, 0x7F   | FIR_COEF_C059                     |
| 10   | 0x0A    | 0x00, 0x01   | PAGE_ID                           |
| 10   | 0x0A    | 0x02 to 0x07 | Not used                          |
| 10   | 0x0A    | 0x08, 0x09   | FIR_COEF_C060                     |
| 10   | 0x0A    | 0x0A, 0x0B   | FIR_COEF_C061                     |
| 10   | 0x0A    | 0x0C to 0x7D | FIR_COEF_C062 to<br>FIR_COEF_C118 |
| 10   | 0x0A    | 0x7E, 0x7F   | FIR_COEF_C119                     |

**FIR Filter Bank D, FIR\_COEF\_D000 to FIR\_COEF\_D119****Table 178. Filter Bank D Memory Map**

| Page | PAGE_ID | Addresses    | Register                          |
|------|---------|--------------|-----------------------------------|
| 11   | 0x0B    | 0x00, 0x01   | PAGE_ID                           |
| 11   | 0x0B    | 0x02 to 0x07 | Not used                          |
| 11   | 0x0B    | 0x08, 0x09   | FIR_COEF_D000                     |
| 11   | 0x0B    | 0x0A, 0x0B   | FIR_COEF_D001                     |
| 11   | 0x0B    | 0x0C to 0x7D | FIR_COEF_D002 to<br>FIR_COEF_D058 |
| 11   | 0x0B    | 0x7E, 0x7F   | FIR_COEF_D059                     |
| 12   | 0x0C    | 0x00, 0x01   | PAGE_ID                           |
| 12   | 0x0C    | 0x02 to 0x07 | Not used                          |
| 12   | 0x0C    | 0x08, 0x09   | FIR_COEF_D060                     |
| 12   | 0x0C    | 0x0A, 0x0B   | FIR_COEF_D061                     |
| 12   | 0x0C    | 0x0C to 0x7D | FIR_COEF_D062 to<br>FIR_COEF_D118 |
| 12   | 0x0C    | 0x7E, 0x7F   | FIR_COEF_D119                     |

**Default Filter Performance**

The FIR filter banks have factory programmed filter designs. They are all low-pass filters that have unity dc gain. Table 179 provides a summary of each filter design, and Figure 50 shows the frequency response characteristics. The phase delay is equal to  $\frac{1}{2}$  of the total number of taps.

**Table 179. FIR Filter Descriptions, Default Configuration**

| FIR Filter Bank | Taps | -3 dB Frequency (Hz) |
|-----------------|------|----------------------|
| A               | 120  | 300                  |
| B               | 120  | 100                  |
| C               | 32   | 300                  |
| D               | 32   | 100                  |

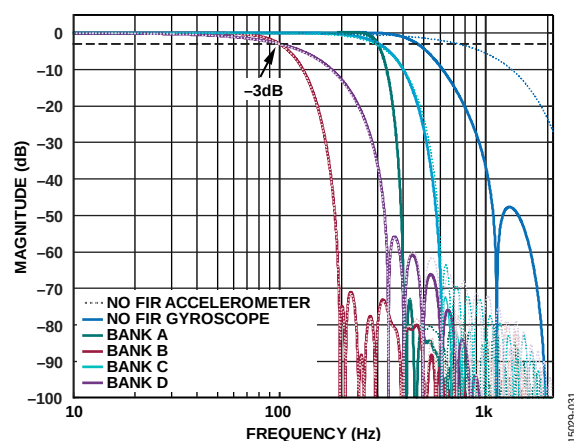


Figure 50. FIR Filter Frequency Response Curves

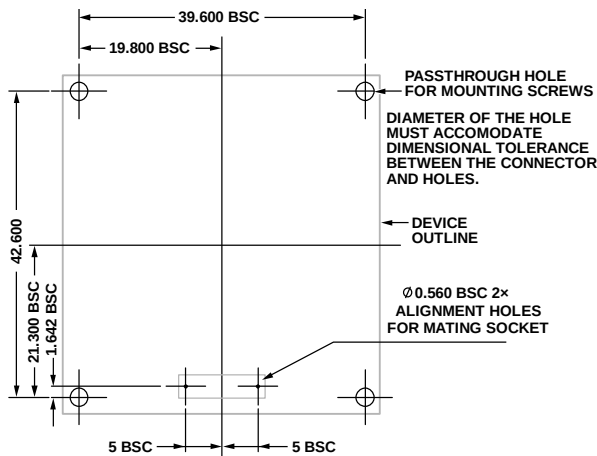
## APPLICATIONS INFORMATION

### MOUNTING BEST PRACTICES

For the best performance, follow these simple rules when installing the ADIS16490 into a system:

- Eliminate opportunity for translational force (x- and y-axis direction, per Figure 40) application on the electrical connector.
- Use uniform mounting forces on all four corners. The suggested torque setting is 40 inch ounces (0.285 Nm).
- When the IMU rests on the PCB, which contains the mating connector (see Figure 51), use a diameter of at least 2.85 mm for the passthrough holes.

These rules help prevent irregular force profiles, which can warp the package and introduce bias errors in the sensors. Figure 51 and Figure 52 provide details for mounting hole and connector alignment pin drill locations.



#### NOTES

1. ALL DIMENSIONS IN mm UNITS.
2. IN THIS CONFIGURATION, THE CONNECTOR IS FACING DOWN AND ITS PINS ARE NOT VISIBLE.

Figure 51. Suggested PCB Layout Pattern, Connector Down

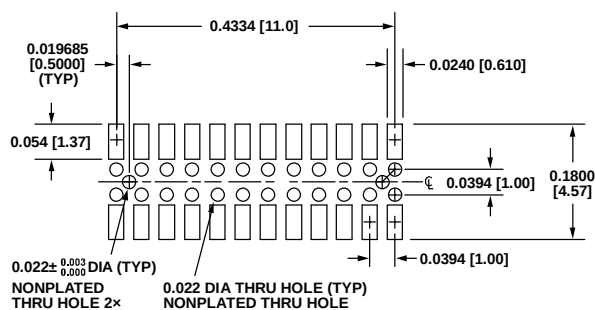


Figure 52. Suggested Layout and Mechanical Design When Using Samtec CLM-112-02-G-D-A for the Mating Connector

### PREVENTING MISINSERTION

The ADIS16490 connector uses the same pattern as the ADIS16485, but with Pin 12 and Pin 15 missing. This pin configuration enables a mating connector to plug these holes, which makes inserting the ADIS16490 incorrectly very difficult. Samtec has a custom part number that provides this type of mating socket: ASP-193371-04.

### EVALUATION TOOLS

#### Breakout Board, ADIS16IMU1/PCBZ

The ADIS16IMU1/PCBZ (sold separately) provides a breakout board function for the ADIS16490, which means that it provides access to the ADIS16490 through larger connectors that support standard 1 mm ribbon cabling. It also provides four mounting holes for attachment of the ADIS16490 to the breakout board.

#### PC-Based Evaluation, EVAL-ADIS2

Use the EVAL-ADIS2 and ADIS16IMU1/PCBZ to evaluate the ADIS16490 on a PC-based platform.

### POWER SUPPLY CONSIDERATIONS

The VDD power supply must charge 46  $\mu$ F of capacitance (inside of the ADIS16490, across the VDD and GND pins) during its initial ramp and settling process. When VDD reaches 2.85 V, the ADIS16490 begins its internal start-up process, which generates additional transient current demand. See Figure 53 for a typical current profile during the start-up process. The first peak in Figure 53 relates to charging the 46  $\mu$ F capacitor bank, whereas the other transient activity relates to numerous functions turning on during the initialization process of the ADIS16490.

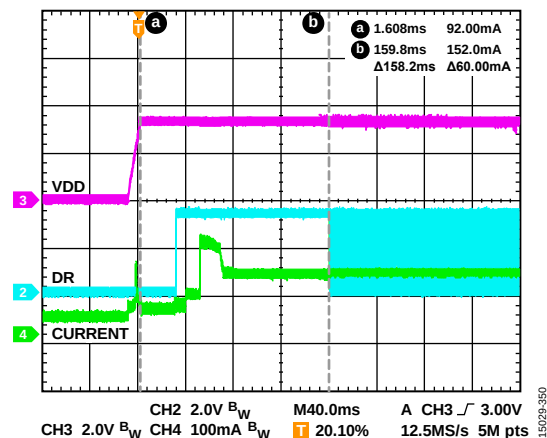


Figure 53. Transient Current Demand, Startup (DR Means Data Ready)

## PACKAGING AND ORDERING INFORMATION

## OUTLINE DIMENSIONS

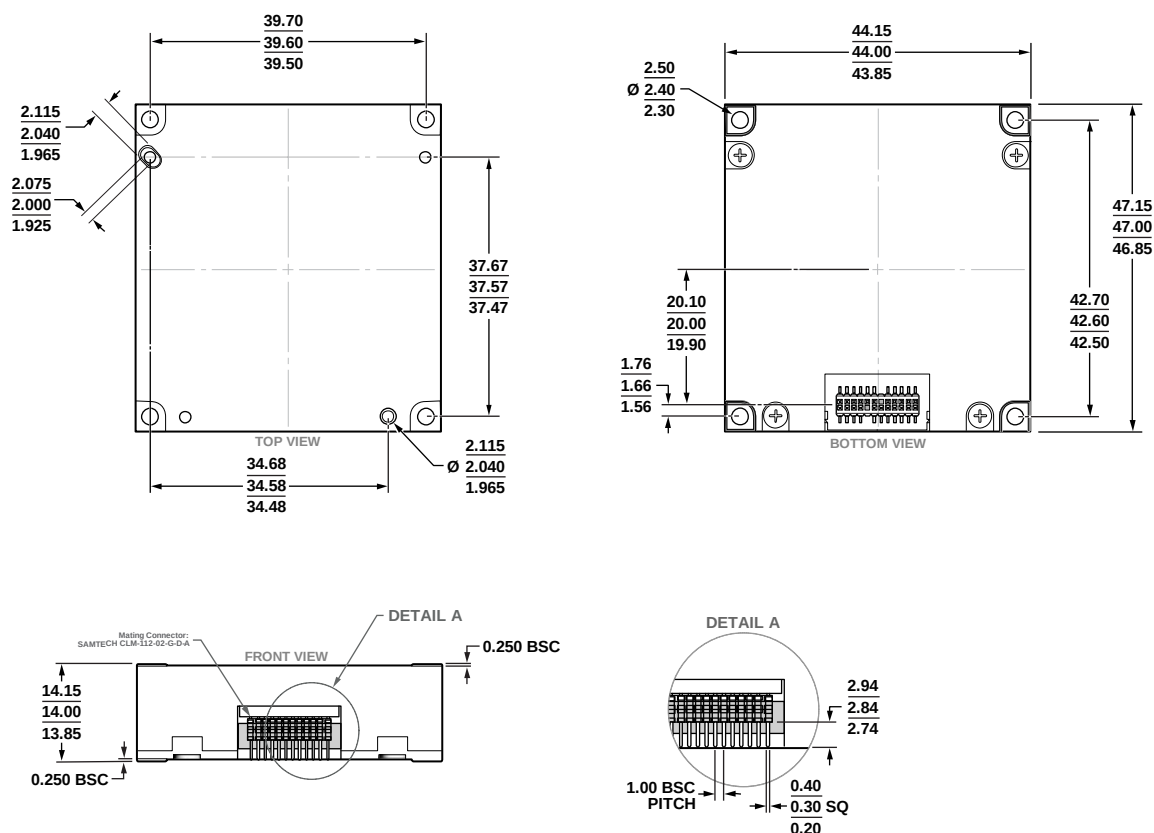


Figure 54. 24-Lead Module with Connector Interface [MODULE]  
(ML-24-9)  
Dimensions shown in millimeters

07-26-2019-B

## ORDERING GUIDE

| Model <sup>1</sup> | Temperature Range | Description                                      | Package Option |
|--------------------|-------------------|--------------------------------------------------|----------------|
| ADIS16490BMLZ      | −40°C to +105°C   | 24-Lead Module with Connector Interface [MODULE] | ML-24-9        |

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



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