

Freescale Sensor Fusion Library for Kinetis MCUs

Updated for Freescale Sensor Fusion Release 5.00

Contents

| | | |
|----------|--|-----------|
| 1 | Introduction | 3 |
| 2 | Functional Overview | 6 |
| 2.1 | Introduction | 6 |
| 2.2 | Accelerometer Only | 6 |
| 2.3 | Accelerometer Plus Magnetometer | 7 |
| 2.4 | Accelerometer Plus Gyroscope | 7 |
| 2.5 | Accelerometer Plus Magnetometer Plus Gyroscope | 7 |
| 3 | Additional Support | 8 |
| 3.1 | Freescale Sensor Fusion Toolbox for Android | 9 |
| 3.2 | Freescale Sensor Fusion Toolbox for Windows | 9 |
| 3.3 | Terms and Acronyms | 11 |
| 3.4 | References | 12 |
| 4 | Mechanical and Electrical Specifications | 12 |
| 4.1 | General Considerations | 12 |
| 4.2 | Hardware Platforms Used to Measure Performance | 13 |
| 4.3 | Simulation Environments | 16 |
| 4.4 | Frame of Reference | 18 |
| 4.5 | Electrical Specifications | 18 |
| 4.6 | Computation Metrics | 19 |
| 4.6.1 | Statistics from Build #5.00 of the Sensor Fusion Library | 19 |
| 4.7 | Magnetic Calibration Metrics | 20 |
| 4.7.1 | Background | 20 |
| 4.7.2 | The Magnetic Buffer | 21 |
| 4.7.3 | Magnetic Calibration Performance Metrics | 22 |
| 4.8 | Fusion Model Performance Metrics | 22 |
| 4.8.1 | Background | 22 |
| 4.8.2 | Gyro Offset Step Response | 23 |
| 4.8.3 | Error in Computed Linear Acceleration | 24 |
| 4.8.4 | Limitations Imposed via Sensor Choice/Configuration | 25 |
| 4.8.5 | 9-Axis Parametrics | 26 |
| 4.8.6 | 6-axis Accelerometer + Magnetometer Parametrics | 27 |

| | | |
|----------|--|-----------|
| 4.8.7 | 6-axis Accelerometer + Gyro Parametrics | 27 |
| 4.8.8 | 3-axis Accelerometer Only Parametrics | 28 |
| 5 | Test Descriptions | 28 |
| 5.1 | MCU Current | 28 |
| 5.1.1 | Intent | 28 |
| 5.1.2 | Procedure | 28 |
| 5.2 | Flash and RAM Required..... | 29 |
| 5.2.1 | Intent | 29 |
| 5.2.2 | Procedure | 29 |
| 5.3 | Fusion Loop Execution Time..... | 29 |
| 5.4 | Compass Heading Linearity and Accuracy..... | 29 |
| 5.4.1 | Intent | 29 |
| 5.4.2 | Procedure | 30 |
| 5.5 | Orientation Static Drift..... | 31 |
| 5.5.1 | Intent | 31 |
| 5.5.2 | Procedure | 31 |
| 5.6 | Orientation Static Noise | 32 |
| 5.6.1 | Intent | 32 |
| 5.6.2 | Procedure | 32 |
| 5.7 | Orientation Dynamic Drift..... | 32 |
| 5.7.1 | Intent | 32 |
| 5.7.2 | Procedure | 32 |
| 5.8 | Maximum Angular Rate | 32 |
| 5.8.1 | Intent | 32 |
| 5.8.2 | Procedure | 32 |
| 5.9 | Orientation Response Delay | 33 |
| 5.9.1 | Waveform Definitions..... | 33 |
| 5.9.2 | Intent | 33 |
| 5.9.3 | Procedure | 33 |
| 5.10 | Orientation Magnetic Immunity (Static Device)..... | 34 |
| 5.10.1 | Intent | 34 |
| 5.10.2 | Procedure | 34 |
| 5.11 | Orientation Magnetic Immunity (Moving Device)..... | 34 |
| 5.11.1 | Intent | 34 |
| 5.11.2 | Procedure | 34 |
| 5.12 | Error in Computed Gyro Bias | 34 |
| 5.12.1 | Intent | 34 |
| 5.12.2 | Procedure | 34 |
| 5.13 | Gyro Offset Step Response | 35 |
| 5.13.1 | Intent | 35 |
| 5.13.2 | Procedure | 35 |
| 5.14 | Error in Computed Linear Acceleration | 35 |
| 5.14.1 | Intent | 35 |
| 5.14.2 | Procedure | 35 |
| 6 | Revision history for XSFLK_DS..... | 36 |

1 Introduction

Sensor Fusion is the process where data from several different sensors are *fused* to complete computations that a single sensor could not handle. An example of sensor fusion is computing the orientation of a device in 3-dimensional space using an accelerometer and magnetometer. That data might then be used to alter the perspective presented by a 3D GUI or game.

The Freescale Sensor Fusion Library for Kinetis MCUs provides advanced functions for computation of device orientation, linear acceleration, gyroscope offset and magnetic interference based upon the outputs of Freescale inertial and magnetic sensors.

Features

- Supports:
 - Accelerometer only (roll, pitch and tilt)
 - Magnetometer only (2D auto)
 - Gyro only
 - Accelerometer plus magnetometer (eCompass)
 - Accelerometer plus gyro (gaming)
 - Accelerometer plus magnetometer plus gyroscope sensors
- Includes Freescale's award-winning magnetic compensation software
 - Provides geomagnetic field strength, hard- and soft-iron corrections, and quality-of-fit indication
- Very low power consumption
 - 3 mA 9-axis fusion I_{DD} on Kinetis ARM[®] Cortex[®] M0+ devices at 25 Hz fusion rate/200 Hz sensor rate
 - 0.6mA 9-axis fusion I_{DD} on Kinetis ARM Cortex M4F devices at 25 Hz fusion rate/200 Hz sensor rate
- Programmable sensor sample and fusion rates
- Supports multiple 3D frames of reference (aerospace NED, Android and Windows 8)
- Library is coded in standard C99 ANSI C
- Compatible with the Freescale Sensor Fusion Toolbox for Android and Windows
- Supported by Freescale CodeWarrior, Kinetis Design Studio and Processor Expert tools
- Out-of-the box support for the following Freedom Development Platforms with FRDM-FXS-MULTx family of sensor boards
 - Cortex M0+: FRDM-KL25Z / FRDM-KL26Z / FRDM-KL46Z
 - Cortex M4: FRDM-K20D50M
 - Cortex M4F: FRDM-K64F / FRDM-K22F (KDS only)
- Library version 5.00 includes bonus bare-metal implementations for tilt and eCompass.

Typical Applications

- Notebook, tablet and smartphone sensor fusion
- Gaming, motion control, head-mounted displays, wearable electronics
- Air mouse, remote control
- Navigation, eCompass, IoT (Internet of Things) sensor data management

Introduction

Table 1. Feature Comparison of the Freescale Sensor Fusion Algorithm Options

| Feature | Accel only | Mag only | Gyro Only | Accel + gyro | Accel + mag | Accel + mag + gyro |
|---|-----------------------------|----------|------------------|------------------|-----------------------|--------------------|
| Filter type | Low pass | Low pass | N/A | Indirect Kalman | Low pass ¹ | Indirect Kalman |
| Roll / Pitch / Tilt in degrees | Yes | No | Yes | Yes | Yes | Yes |
| Yaw in degrees | No | Yes | Yes | No | Yes | Yes |
| Angular rate ² in degrees/second | virtual 2 axis ³ | Yaw only | Yes | Yes | virtual 3 axis | Yes |
| Compass heading (magnetic north) in degrees | No | Yes | No | No | Yes | Yes |
| Quaternion and rotation vector | Yes | Yaw only | Yes ⁵ | Yes | Yes | Yes |
| Rotation matrix | Yes | Yaw only | Yes ⁵ | Yes | Yes | Yes |
| Linear acceleration separate from gravity | No | No | No | Yes | No | Yes |
| NED (North-East-Down) frame of reference | Yes ⁴ | Yes | Yes ⁴ | Yes ⁴ | Yes | Yes |
| ENU (Windows 8 variant) frame of reference | Yes ⁴ | Yes | Yes ⁴ | Yes ⁴ | Yes | Yes |
| ENU (Android variant) frame of reference | Yes ⁴ | Yes | Yes ⁴ | Yes ⁴ | Yes | Yes |
| Magnetic calibration included | N/A | Yes | N/A | N/A | Yes | Yes |
| Gyro offset calibration included | N/A | N/A | No | Yes | N/A | Yes |
| FRDM-KL25Z board support | Yes | Yes | Yes | Yes | Yes | Yes |
| FRDM-KL46Z board support | Yes | Yes | Yes | Yes | Yes | Yes |
| FRDM-K20D50M board support | Yes | Yes | Yes | Yes | Yes | Yes |
| FRDM-KL26Z board support | Yes | Yes | Yes | Yes | Yes | Yes |
| FRDM-K64F board support | Yes | Yes | Yes | Yes | Yes | Yes |
| FRDM-K22F board support | KDS only | | | | | |

1. More precisely: a non-linear modified exponential low pass quaternion SLERP filter.
2. Angular rate for 6 and 9-axis configurations with a gyro include corrections for gyro offset.
3. Subject to well-known limitation of being blind to rotation about axes aligned with gravity.
4. These solutions do not include a magnetometer, therefore there is no sense of compass heading.
5. Rotations for gyro-only solution are relative to sensor position (there is no global frame).

Table 2. Feature Options

| Feature | Options |
|---|--|
| License | BSD 3-Clause |
| CPU selection | MKL25Z128VLK4 MKL26Z128VLH4 MK20DX128VLH5 MKL46Z256VMC4 MK64FN1M0VLL12 MK22FN512VLH12 (KDS only) |
| Board customizable | Yes |
| Sensor sample rate | Programmable |
| Fusion rate | Programmable |
| Frame of Reference | Programmable |
| Algorithms Executing | Programmable |
| Sleep mode enabled between samples/calculations | No It can be added by user, but will interfere with UART operation |
| RTOS | MQX-Lite |
| Code flexibility | Full source code is provided. All files are can be modified. |
| Access to Processor Expert | Yes |
| Product Deliverables | <ul style="list-style-type: none"> • This datasheet • Software user guide • Zip file containing both CodeWarrior and KDS projects |

1. Listed MCUs are those supported by included project templates. The fusion library should be portable to any ARM® processor without change. Ports to other architectures are expected to be very straightforward, as the library is written in standard C.
2. FRDM-KL25Z, FRDM-KL26Z, FRDM-KL46Z, FRDM-K20D50M, FRDM-K64F and FRDM-K22F are supported out-of-the box and may be used as templates for other boards.
3. The sensor fusion library was written assuming the MQX Lite RTOS, but should be easily adaptable to other operating systems. See the "Freescale Sensor Fusion for Kinetis User Guide" for additional details. The sensor fusion library has also been incorporated into Freescale's Intelligent Sensing Framework (ISF). ISF 2.2 offers an RTOS abstraction that allows you to target alternate real time operating systems.

The Freescale Sensor Fusion Toolbox includes bonus projects for 3-axis tilt and 6-axis eCompass running without an RTOS. Sensor shield boards are not needed for these configurations. This results in very low-cost demonstration platforms. The bonus projects are compatible with the Sensor Fusion Toolbox for Windows over USB connection. The FRDM-KL46Z eCompass version can also be used stand-alone since the compass heading is displayed directly on the FRDM-KL46Z LCD display.

The bare-board eCompass projects have sensor sampling, sensor fusion and magnetic algorithms run as a single task at 25Hz. On power up, the green LED flashes slowly to indicate that the software is executing but that there is no magnetic calibration solution. The green LED then flashes rapidly to signal that the compass heading display is accurate and that a valid magnetic calibration has been obtained after rotating the Freedom development board.

2 Functional Overview

2.1 Introduction

Sensor fusion encompasses a variety of techniques that:

- Trade off strengths and weaknesses of the various sensors to compute something more than can be calculated using the individual components
- Improve the quality and noise level of computed results by taking advantage of:
 - Known data redundancies between sensors
 - Knowledge of system transfer functions, dynamics and kinematics

The Freescale Sensor Fusion Library for Kinetis (Fusion Library) supports several combinations of sensors. In general, performance improves as more sensors are added to the system. The primary function of the library is to compute orientation of a sensor subsystem relative to a global frame of reference.

Orientation can be expressed in a number of different ways:

- Tilt from vertical (may also be expressed as roll + pitch)
- Compass heading (geomagnetic north)
- Full 3D rotation from a global frame in any of the following forms:
 - Rotation matrix
 - Rotation vector (3D axis of rotation and rotation about that axis)
 - Quaternion
 - Euler angles (roll, pitch and yaw)

For additional portability details and guidelines refer to the *Freescale Sensor Fusion for Kinetis MCUs User Guide* which is part of the *Sensor Fusion Library* installation. The Fusion Library is available in source code form and is designed to sit on top of board abstractions provided by Processor Expert and MQXLite. The C source and header files in the Sources directory of the project templates are board and MCU independent. Board dependencies are included as compile time options. If a particular board does not bring out the GPIO, I2C or UART needed, the board will not be compatible with the software and therefore will not be supported by Processor Expert.

2.2 Accelerometer Only

An accelerometer measures linear acceleration minus gravity. If linear acceleration is zero, this sensor can be used to measure tilt from vertical, roll and pitch. Computation of yaw is not supported by this configuration.

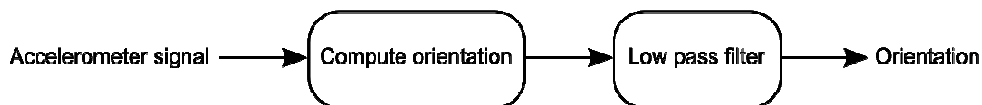


Figure 1. Accelerometer only block diagram

2.3 Accelerometer Plus Magnetometer

The accelerometer plus magnetometer configuration is often used as an electronic compass. The electronic compass is subject to the linear acceleration equals zero, assumption. Accuracy is dependent upon negligible magnetic interference from the environment in which the sensors travel.

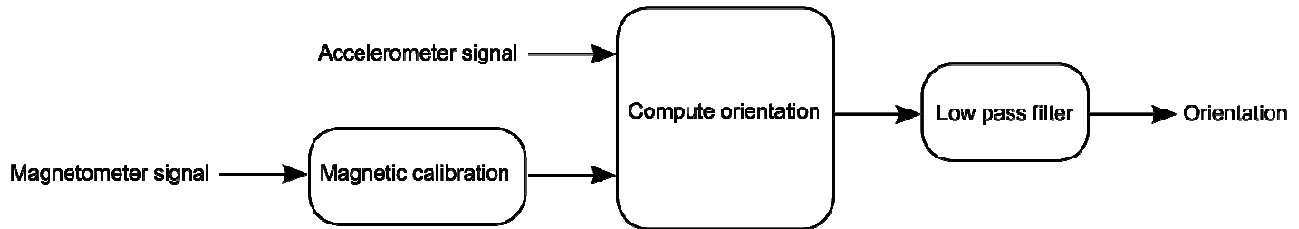


Figure 2. Accelerometer plus magnetometer block diagram

2.4 Accelerometer Plus Gyroscope

Using a gyroscope in addition to an accelerometer yields the ability to smoothly measure rotation in 3D space, although the system can only yield orientation to some random horizontal global frame of reference. That is, the system has no sense of magnetic north. Computation of yaw is not supported by this configuration.

This configuration is commonly known as an Inertial Measurement Unit (IMU).

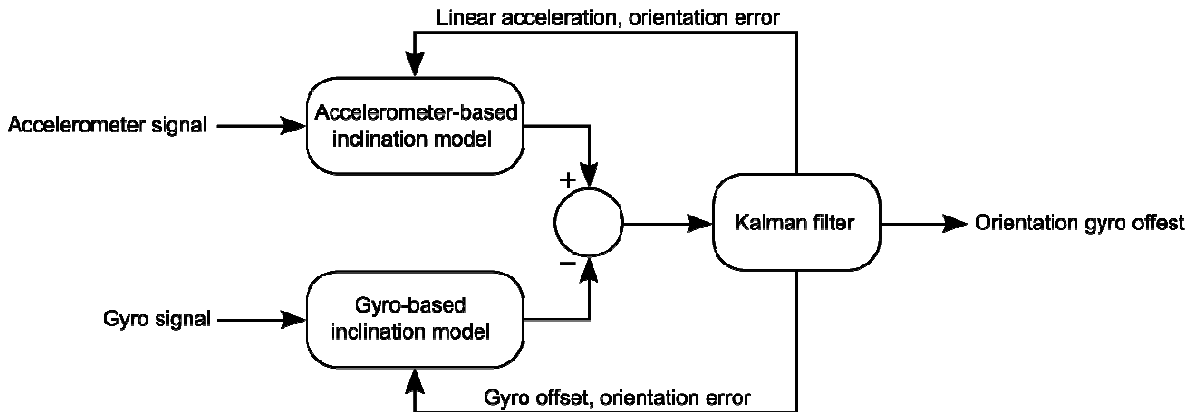


Figure 3. Accelerometer Plus Gyroscope Block Diagram

2.5 Accelerometer Plus Magnetometer Plus Gyroscope

Sometimes referred to as Magnetic, Angular Rate and Gravity (MARG), this subsystem offers an optimal combination of sensors for smooth tracking of orientation and separation of gravity and linear acceleration. This system is capable of yielding absolute orientation data with respect to magnetic north.

Additional Support

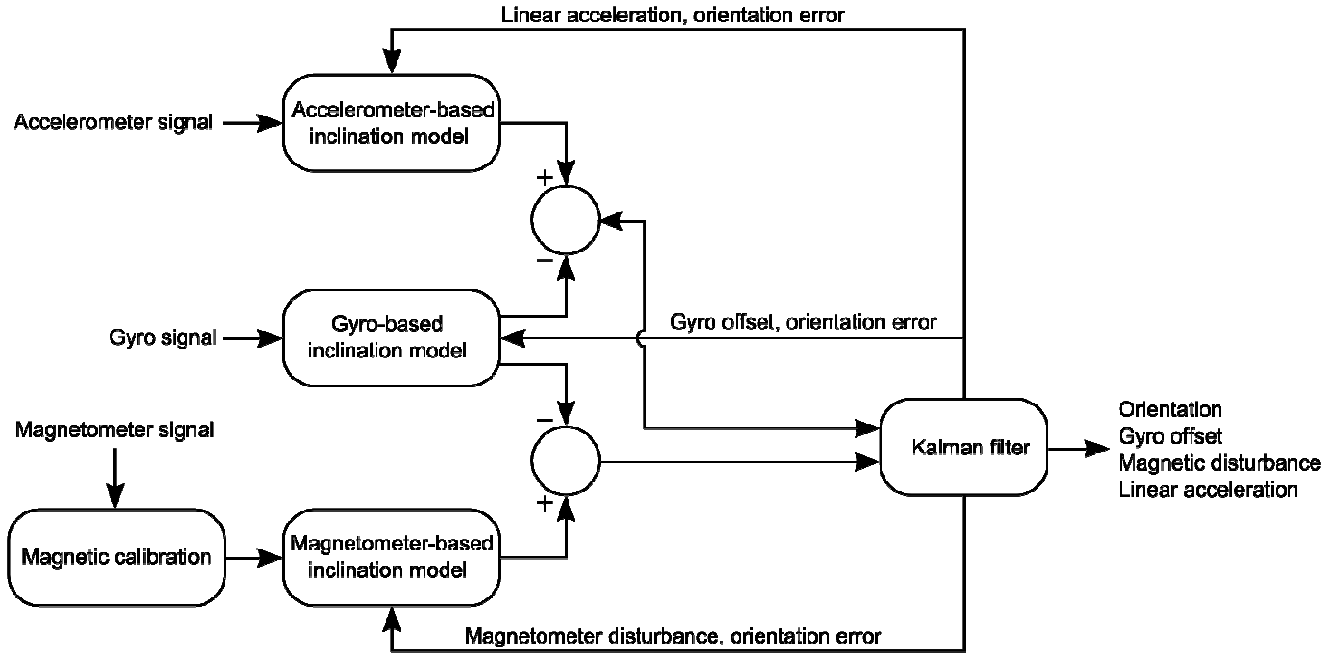


Figure 4. Accelerometer Plus Magnetometer Plus Gyroscope Block Diagram

3 Additional Support

Freescale Sensor Fusion Toolbox provides support for both Android and Windows operating systems. See [Table](#) for the differences between the two implementations.

Table 3. Freescale Sensor Fusion Toolbox Features by Platform

| Feature | Android | PC |
|----------------------------|--------------------|--|
| Bluetooth wireless link | ✓ | Requires BT on PC (built-in or dongle) |
| Ethernet wireless link | On WiGo board only | — |
| UART over USB | — | ✓ |
| OS requirements | >=Android 4.0.3 | >=Windows 7.0 |
| Support for native sensors | ✓ | — |
| Device View | ✓ | ✓ |
| Panorama View | ✓ | — |
| Statistics View | ✓ | — |
| Canvas View | ✓ | — |
| Orientation XY Plots | — | ✓ |
| Inertial XY Plots | — | ✓ |
| Magnetics | — | ✓ |
| Kalman | — | ✓ |
| Altimeter XY Plots | — | ✓ |
| Data Logging | ✓ | ✓ |
| Integrated documentation | ✓ | ✓ |

| Feature | Android | PC |
|--------------|-------------|-------------------|
| Availability | Google Play | Freescale website |
| Price | Free | Free |

3.1 Freescale Sensor Fusion Toolbox for Android

The Fusion Library is supplied in the form of CodeWarrior projects for specific Freescale development boards. The basic function of the Sensor Fusion Android implementation are shown in Figure 5. These projects are compatible with the Freescale Sensor Fusion Toolbox for Android, which can be freely downloaded from Google Play. For download and training links, visit freescale.com/sensorfusion.

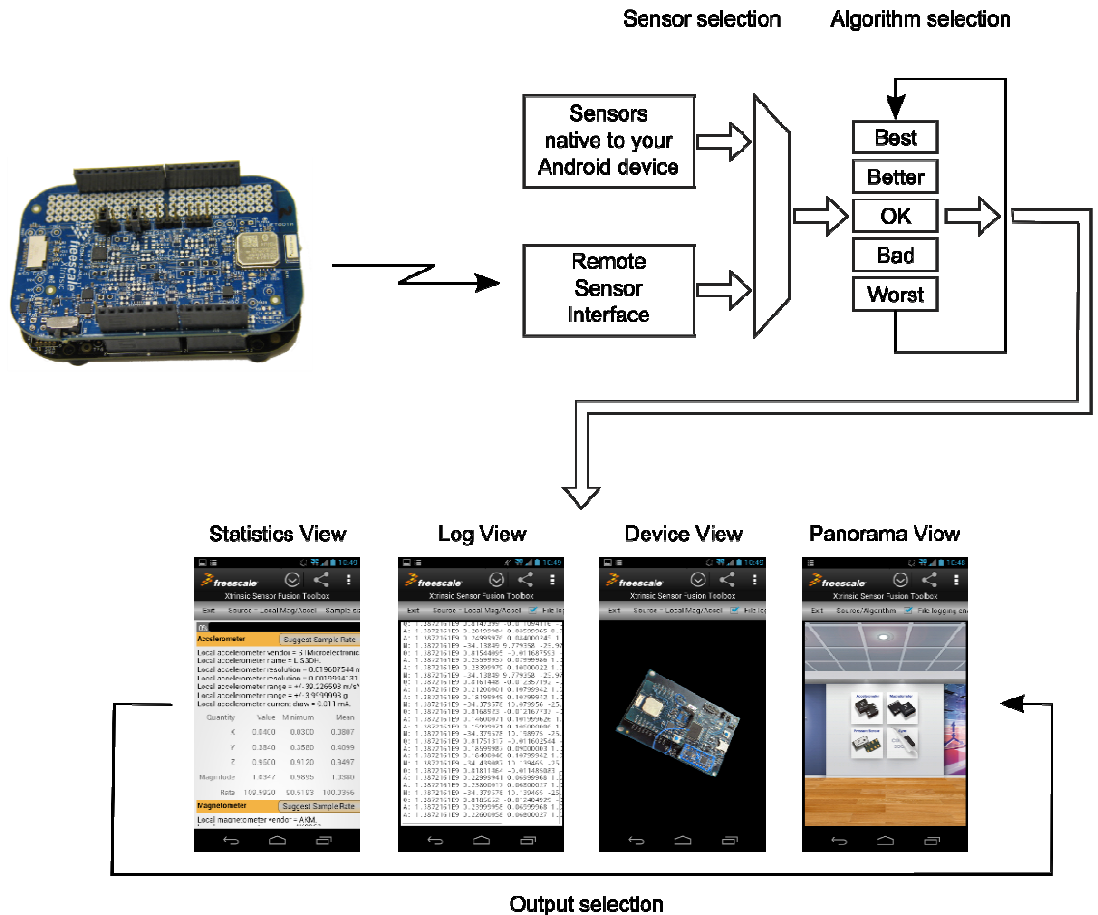


Figure 5. Freescale Sensor Fusion Toolbox for Android Basic Functions

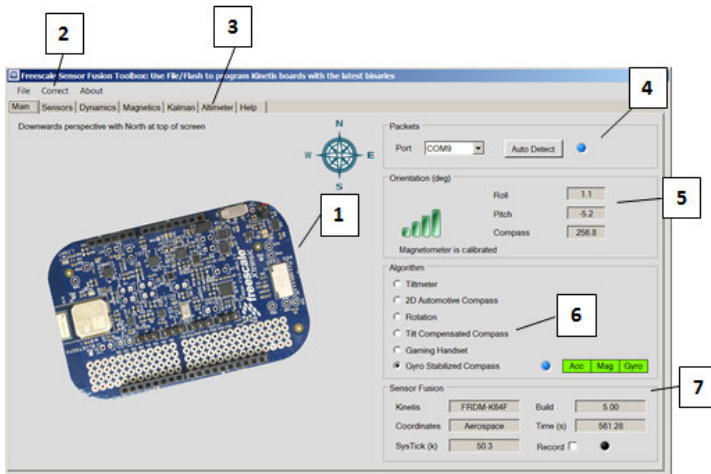
3.2 Freescale Sensor Fusion Toolbox for Windows

The Sensor Fusion Toolbox includes an equivalent version of the software for Windows. For download and training links, visit freescale.com/sensorfusion.

Important Note: Version 5.0 of the Sensor Fusion Library has a modified Kalman packet structure as compared to that used in prior releases. Be sure you have downloaded the Windows toolbox built 3 Sept 2015 or later.

Additional Support

Figure 6 and Figure 7 are Sensor Fusion Toolbox screenshots of the Windows version.



Figures are from 3 September 2015 build of the application. Appearance may vary for other versions.

This is the most intuitive way to confirm that your sensor fusion is working properly.

1. Rotating 3D PCB display
2. Image align function
3. Navigation Tabs for:
 - Main (board view)
 - Sensors
 - Dynamics
 - Magnetics
 - Kalman
 - Altimeter
 - Help
4. Packet information
 - choice of PC communications port
 - packet activity indicator
5. Roll/Pitch/Yaw & MagCal status
6. Choice of sensor set & algorithm
7. Sensor board run time and build parameters, Data logging on/off

Figure 6. PC Version - Main Tab

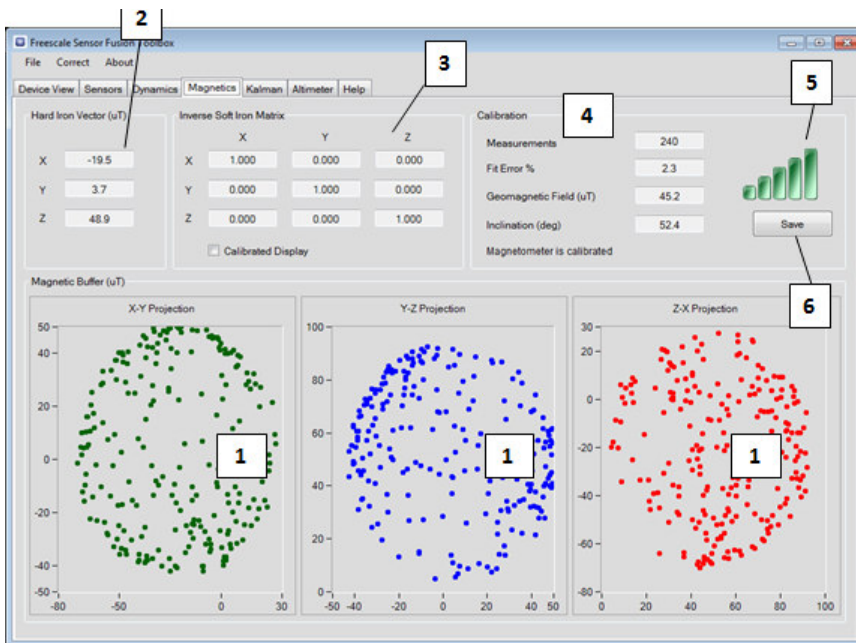


Figure 7. PC Version - Magnetics Tab

1. 2D representation of the data point "cloud" used for hard/soft iron compensation
2. Computed hard iron vector
3. Soft iron matrix
4. Statistics
5. Calibration status light
6. Save to text file

3.3 Terms and Acronyms

| Term | Definition |
|------------|---|
| DUT | Device Under Test |
| ENU | A global frame of reference described by X = E ast, Y = N orth, Z = U p |
| g | abbreviation for gravities. 1 standard gravity = 9.80665 m/s ² . Accelerometers are commonly trimmed using the local gravimetric field, which can vary by 1/2 percent depending upon altitude and latitude. |
| gauss | CGS system unit for measuring magnetic field strength. 100 μ T = 1 gauss. |
| IMU | Inertial Measurement Unit = accelerometer + gyro |
| Kinetis | Freescale family of ARM [®] -based MCUs |
| MagCal | Magnetic Calibration |
| MARG | Magnetic Angular Rate Gravity = IMU + magnetometer |
| MCU | Micro-Controller Unit |
| microTesla | The Tesla is the SI unit for measuring magnetic field strength. 1E-4 Tesla = 100 μ T = 1 gauss |
| NED | A global frame of reference described by X = N orth, Y = E ast, Z = D own |
| pitch | In the Aerospace/NED frame of reference, defined as a rotation about the Y-axis |
| RHR | Right Hand Rule—a standard convention for describing the positive/negative sense of rotations about an axis of rotation. See http://en.wikipedia.org/wiki/Right_hand_rule . |
| roll | In the Aerospace/NED frame of reference, defined as a rotation about the X-axis |
| RPY | Roll, Pitch, and Yaw. In the Aerospace/NED frame of reference these are defined as rotations about the X axis, Y axis, and Z axis |
| | <p>The diagram illustrates the Roll, Pitch, and Yaw (RPY) angles for an airplane. The airplane is shown in a red outline. A coordinate system is defined with the X-axis pointing forward along the fuselage, the Y-axis pointing downward, and the Z-axis pointing to the right. Three rotation angles are shown: Roll (ϕ) is a rotation around the X-axis; Pitch (θ) is a rotation around the Y-axis; and Yaw (ψ) is a rotation around the Z-axis. A red oval labeled "RPY angles" is positioned in the upper left. The text "Body frame" is located at the bottom left of the diagram.</p> |
| SI | International System of Units (meter, kilogram, second, ...) |
| SLERP | S pherical L inear int ER Polation - See http://en.wikipedia.org/wiki/SLERP |
| SysTick | A feature of the ARM [®] processor; a clock timer which for the purposes of this discussion, 1 sysTick = 1 CPU clock cycle. |
| tilt | Angle from vertical |
| UART | Universal Asynchronous Receiver / Transmitter, also known as SCI (Serial Communications Interface) |
| yaw | In the Aerospace/NED frame of reference, defined as a rotation about the Z-axis |

Mechanical and Electrical Specifications

3.4 References

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13. [Matlab computer software by MathWorks—http://www.mathworks.com/products/ matlab/](http://www.mathworks.com/products/matlab/)
14. www.freescale.com/opensda

4 Mechanical and Electrical Specifications

4.1 General Considerations

Fusion algorithms can be *tuned* to trade off one performance parameter versus another. Examples include:

- Speedy handling of magnetic interference versus slower convergence to magnetic north
- Smoothness versus responsiveness
- Accuracy versus bandwidth

NOTE

All of the above means that there is no *one correct* configuration. Accordingly, this datasheet presents typical performance as observed on the sample projects supplied by Freescale on specific Freescale development platforms. No attempt has been made to measure a statistically significant number of boards. Measured values are typically those observed on as few as one board.

4.2 Hardware Platforms Used to Measure Performance

In the following subsections, some parametrics are measured, some represent simulated results. There are multiple methods used to determine parametrics. These make use of hardware platforms for benchmarking purposes, in addition to Matlab.

Kinetis Cortex M0+

This configuration is composed of a Freescale KL25Z, KL46Z or KL26Z Freedom development platform paired with a FXS-MULT2-B Bluetooth-enabled sensor board¹. Use of Bluetooth allows the board to be rotated freely, untethered by cords or power cables.

Table 4. Cortex M0+ Test Configuration

| Component / Parameter | Value |
|---------------------------|---|
| Baseboard | FRDM-KL25Z / FRDM-KL26Z / FRDM-KL-46Z |
| Sensor Board | FRDM-FXS-MULT2-B |
| MCU | Kinetis MKL25Z128VLK4 / MKL26Z128VLH4 / MKL46Z256VMC4 |
| CPU | ARM® Cortex M0+ |
| CPU Clock | 48 MHz |
| Bus Clock | 24 MHz |
| Accelerometer | FXOS8700CQ |
| Magnetometer | |
| Gyroscope | FXAS21000 |
| Sensor Sampling Rate | 200 Hz |
| Fusion Rate | 25 Hz |
| Magnetic Calibration Rate | Twice per minute once full calibration is reached |

This board combination is battery powered and nominally regulated to 3.3 V for use by the sensors in question.

¹ The primary difference between the FRDM-FXS-MULTI-B and FRDM-FXS-MULT2-B is that the latter includes a production FXAS21002 gyroscope, whereas the former used FXAS21000 pre-production units. The FRDM-FXS-MULTI-B board is no longer in production, but continues to be supported by the kit. The two boards are similar in appearance.

Mechanical and Electrical Specifications

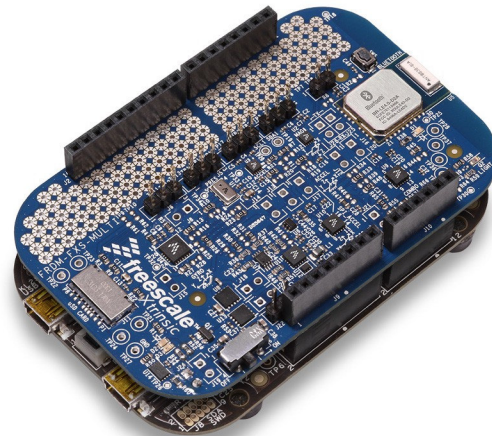


Figure 8. FRDM-KL25Z / FRDM-FXS-MULTI-B sensor fusion prototype platform

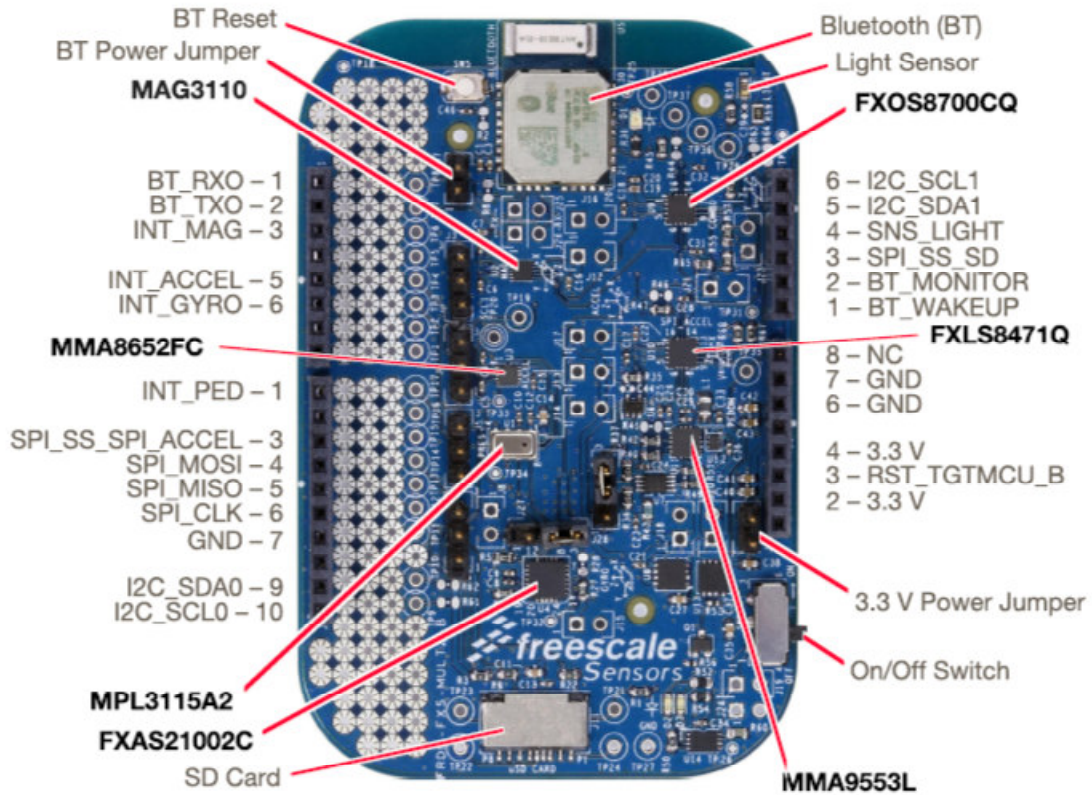


Figure 9. Expanded Diagram of FRDM-FXS-MULT2-B Sensor Board

Kinetis Cortex M4

Table 5. Kinetis Cortex M4

| Component / Parameter | Value |
|---------------------------|---|
| Baseboard | FRDM-K20D50M |
| Sensor Board | FRDM-FXS-MULT2-B |
| MCU | Kinetis MK20DX128VLH5 |
| CPU | ARM® Cortex M4 |
| CPU Clock | 48 MHz |
| Bus Clock | 24 MHz |
| Accelerometer | FXOS8700CQ |
| Magnetometer | |
| Gyroscope | FXAS21000 |
| Sensor Sampling Rate | 200 Hz |
| Fusion Rate | 25 Hz |
| Magnetic Calibration Rate | Twice per minute once full calibration is reached |

This board combination is battery powered and nominally regulated to 3.3 V for use by the sensors in question. Physically, the FRDM-K20D50M / FRDM-FXS-MULT2- B board combination is similar to the KL25Z variant shown in [Figure 8](#), with the exception that the bottom board is red.

Kinetis Cortex M4 with FPU

Table 6. Kinetis Cortex M4 with FPU

| Component / Parameter | Value |
|---------------------------|---|
| Baseboard | FRDM-K64F / FRDM-K22F |
| Sensor Board | FRDM-FXS-MULT2-B |
| MCU | Kinetis MK64FN1M0VLL12 / MK22FN512VLH12 |
| CPU | ARM® Cortex M4 with FPU |
| CPU Clock | 120 MHz |
| Bus Clock | 60 MHz |
| Accelerometer | FXOS8700CQ |
| Magnetometer | |
| Gyroscope | FXAS21000 |
| Sensor Sampling Rate | 200 Hz |
| Fusion Rate | 25 Hz |
| Magnetic Calibration Rate | Twice per minute once full calibration is reached |

The FRDM-K64F /FRDM-K22F / FRDM-FXS-MULTI-B board combinations are similar to the KL25Z variant shown in [Figure 8](#), except that the bottom base board is different.

Mechanical and Electrical Specifications

4.3 Simulation Environments

Many parameters are difficult, if not impossible, to reliably measure in a lab or production environment. Ambient magnetic fields vary tremendously in indoor environments. Determining filter sensitivities to various input parameters can only be done in a simulated environment.

Accordingly, the subsequent sub-sections discuss environments that may be used to explore these areas.

Pure Matlab

Matlab is commonly used in the early development of sensor fusion algorithms. It can be used to model physical stimulus, expected responses and filter operation. See the next section for details concerning sensor and environmental models used to construct stimulus.

Matlab Stimulus/Expected Response + Hardware-based Fusion

Once algorithms are functional, they are translated into C, optimized and then optimized again. The result often makes use of fixed point arithmetic running on an MCU to compute results. To ensure bit-accurate results, a mixture of Matlab (used to generate test stimulus and expected response) and hardware (used to run the filter) are used to determine many parameters.

Simulated values were computed with version 4.17 of the sensor fusion library. Version 4.22 should have almost identical results. Version 5.00 is expected to have better dynamic tracking than indicated in this datasheet, but simulations are still outstanding.

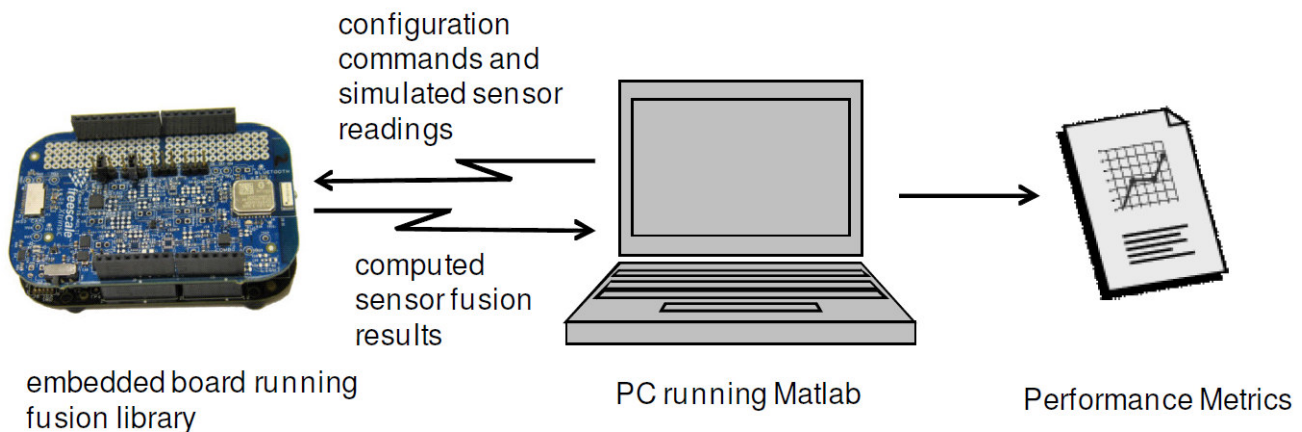


Figure 10. Mixed Simulation/Hardware Characterization

Unless stated otherwise elsewhere, parameters used to create the simulated sensors and environment are:

- Earth magnetic field corresponding to U.S. zip code 85284 (Tempe, Arizona) on 7 November 2013 as determined using the NOAA calculator at ngdc.noaa.gov/geomag-web
 - Declination: 10 degrees 39' 36"
 - Inclination: 59 degrees 32' 53"
 - Horizontal Intensity: 24.2976 μT
 - North Component (+N | -S): 23.8782 μT
 - East Component (+E | -W): 4.4945 μT
 - Vertical Component (+D | -U): 41.3285 μT

- Total field: 47.9418 μT
- Ideal accelerometer model + simple noise
 - Sample rate = 200 Hz
 - milli-*g* noise on X,Y,Z
 - 1 *g* = 9.80665 m/s^2 assumed
- Ideal magnetometer model + simple nose
 - Sample rate = 200 Hz
 - X, Y noise 0.85 μT ; Z noise 1.3 μT
- No hard/soft iron distortion
- Ideal gyroscope model and simple noise
 - Sample rate 200 Hz
 - X, Y, Z noise 0.3 dps

For all tests, the Freescale Matlab-based Trajectory & Sensor Simulation Toolkit (TSim) is used to create DUT trajectories and simulated sensors readings.

Some of the tests require that magnetic calibration procedure is run before the test to initialize the sensor fusion software magnetic buffer. Magnetic calibration is implemented as a trajectory made up of a sequence of random rotations lasting 30seconds.

Benchtop Rotary Table

A variant on the Matlab-based system is shown in Figure 11. In this case, Matlab is used to control a desktop rotary table and to post-process the fusion results into reports. Physical sensor readings are used to drive the fusion routines. Because indoor environments vary magnetically, results may vary from day to day as the setup is moved or electronics in the area cycle on and off.

Results will also change simply because the state of the magnetic buffer is continuously updated.

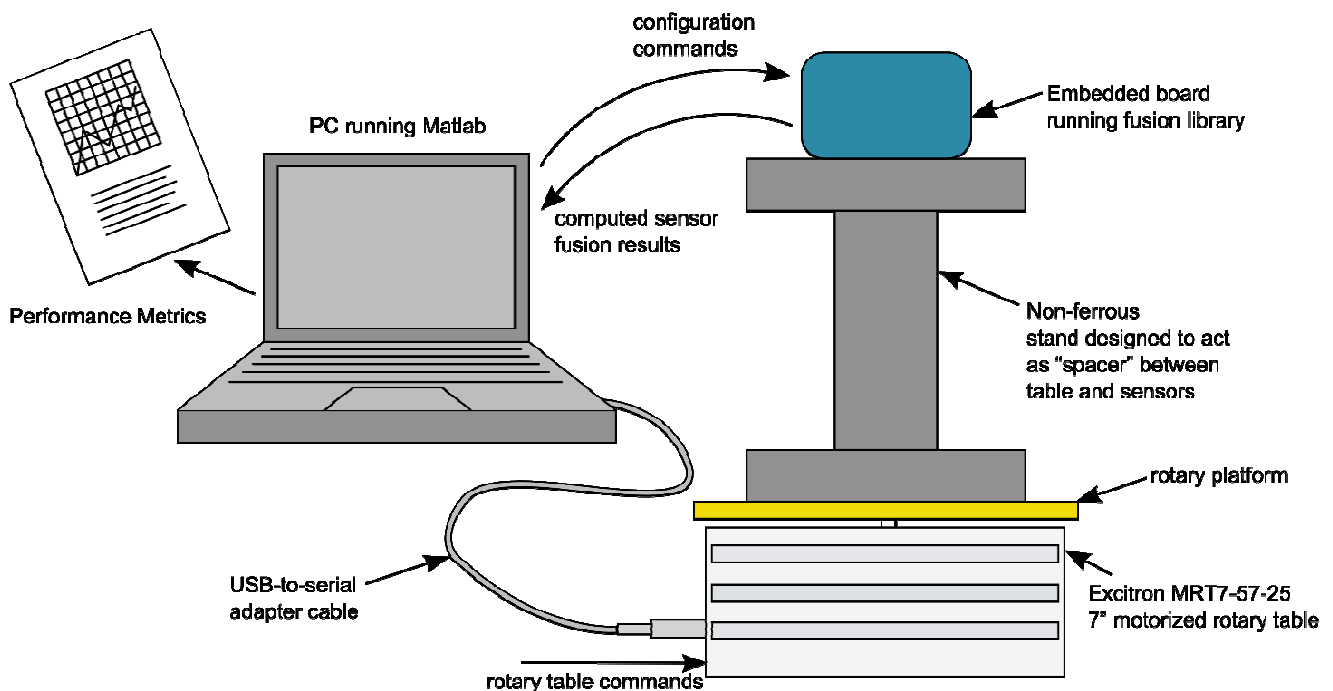


Figure 11. Benchtop Rotary Table Setup

Mechanical and Electrical Specifications

4.4 Frame of Reference

Table summarizes differences between the standard frames of reference supported by the fusion library.

Table 7. Frame of Reference Variations

| | NED | Android | Windows 8 |
|-----------------------------|---|---|---|
| Axes alignment | NED | ENU | ENU |
| Angle rotation order | Yaw then pitch then roll | Yaw then roll then pitch | Yaw then pitch then roll |
| Gimbal lock | Roll instability (x axis) at ± 90 deg pitch (y axis) | Pitch instability (x axis) at ± 90 deg roll (y axis) | Roll instability (y axis) at ± 90 deg pitch (x axis) |
| Roll range | Clockwise -180 to 180 deg | Anti-clockwise -90 to 90 deg | Clockwise -90 to 90 deg |
| Pitch range | -90 to 90 deg | -180 to 180 deg | -180 to 180 deg |
| Yaw range | 0 to 360 | 0 to 360 | 0 to 360 |
| Compass heading | Yaw | Yaw | -Yaw |

1. A clockwise rotation is defined as one that is positive in the Right-Hand-Rule (RHR) sense.

4.5 Electrical Specifications

The parameters in each table are measured using the configurations defined in [Hardware Platforms Used to Measure Performance](#). The MCU currents are estimated using the process defined in [MCU Current](#).

Tables 8 and 9 were developed using the build #5.00 of the Sensor Fusion Library.

Table 8. Typical I_{DD} for FRDM-KL26Z only

| Function | Fusion I_{dd} @ 25Hz rate (mA) | Fusion I_{dd} / Hz (mA) |
|-----------------------|----------------------------------|---------------------------|
| Accel only | 0.25 | 0.01 |
| 2D Mag | 0.19 | 0.01 |
| Gyro only | 0.74 | 0.03 |
| Accel + Mag, eCompass | 0.31 | 0.01 |
| Accel + Gyro | 0.92 | 0.04 |
| 9-axis | 3.20 | 0.13 |
| subtotal | 5.61 | 0.22 |
| estimated RTOS/other | 2.79 | 0.44 |

Table 9. 9-Axis I_{DD} as a Function of Board and Development Tool

| Function | Fusion I_{dd} @ 25Hz rate (mA) Compiled with CodeWarrior | Fusion I_{dd} / Hz (mA) Compiled with KDS |
|--------------|---|--|
| FRDM-K64F | 0.40 | 0.51 |
| FRDM-K22F | N/A | 0.41 |
| FRDM-K20D50M | 3.53 | 4.11 |
| FRDM-KL46Z | 3.70 | 4.16 |
| FRDM-KL26Z | 3.20 | 3.76 |
| FRDM-KL25 | 2.47 | 2.93 |

4.6 Computation Metrics

The Sensor Fusion Library computations are measured directly using the Sensor Fusion Toolbox and the ARM[®] sysTick clock.

4.6.1 Statistics from Build #5.00 of the Sensor Fusion Library

For the current build (5.00), Freescale used the built in sysTick counter to measure each iteration of the algorithm in units of CPU clock cycles. The customer can repeat the exact same measurement, because both PC and Android Sensor Fusion Toolboxes display this information in a real-time basis. The test results will vary depending device movement are presented as “typical” numbers.

Table 10. SysTick Values for Freedom Development Platforms and Sensor Combinations

| Freedom Platform | Accel | 2D Mag | Gyro | eCompass | Accel +Gyro | 9-axis |
|---|-------|--------|------|----------|-------------|--------|
| SysTick Values for CodeWarrior Build 5.00 in kTicks | | | | | | |
| KL25Z | 58 | 46 | 172 | 72 | 208 | 740 |
| KL26Z | 58 | 45 | 171 | 71 | 210 | 740 |
| KL46Z | 59 | 45 | 171 | 72 | 207 | 740 |
| K20D50M | 34 | 26 | 63 | 42 | 157 | 509 |
| K64F | 3.1 | 2.86 | 4.5 | 3.6 | 10.6 | 50.5 |
| KL25Z | 58 | 46 | 172 | 72 | 208 | 740 |
| SysTick Values for KDS Build 5.00 in kTicks | | | | | | |
| KL25Z | 59 | 47 | 174 | 74 | 211 | 840 |
| KL26Z | 61 | 48 | 173 | 75 | 211 | 860 |
| KL46Z | 60 | 49 | 174 | 74 | 210 | 840 |
| K20D50M | 35 | 27 | 66 | 44 | 160 | 580 |
| K64F | 3.3 | 3.1 | 4.9 | 3.9 | 11.4 | 54.6 |
| K22F | 3.9 | 3.7 | 5.8 | 4.4 | 13.4 | 59.1 |

Mechanical and Electrical Specifications

Table 11. Memory Requirements for “All Algorithms” Builds

| Freedom Platform | Text | Data | BSS | Flash | RAM |
|------------------|-------|------|-------|-------|-------|
| CodeWarrior | | | | | |
| FRDM-KL25Z | 96028 | 72 | 14776 | 96100 | 14848 |
| FRDM-KL26Z | 96020 | 72 | 14780 | 96092 | 14852 |
| FRDM-KL46Z | 95956 | 72 | 14780 | 96028 | 14852 |
| FRDM-K20D50M | 88116 | 72 | 14972 | 88188 | 15044 |
| FRDM-K64F | 79724 | 84 | 16484 | 79808 | 16568 |
| KDS | | | | | |
| FRDM-KL25Z | 77812 | 172 | 14816 | 77984 | 14988 |
| FRDM-KL26Z | 77828 | 172 | 14816 | 78000 | 14988 |
| FRDM-KL46Z | 77772 | 172 | 14816 | 77944 | 14988 |
| FRDM-K20D50M | 67356 | 172 | 15008 | 67528 | 15180 |
| FRDM-K64F | 65024 | 184 | 16652 | 65208 | 16836 |
| FRDM-K22F | 62268 | 184 | 16492 | 62452 | 16676 |

Table 12. CodeWarrior Memory Requirements for FRDM-KL25Z and Single Algorithm

| Freedom Platform | Text | Data | BSS | Flash | RAM |
|------------------|-------|------|-------|-------|-------|
| Accel (Tilt) | 34280 | 64 | 12580 | 34344 | 12644 |
| 2D Mag | 53904 | 64 | 12580 | 53968 | 12644 |
| Gyro Only | 33944 | 64 | 12528 | 34008 | 12592 |
| Accel/Mag | 55172 | 64 | 12588 | 55236 | 12652 |
| Accel/Gyro | 54716 | 72 | 12892 | 54788 | 12964 |
| 9-axis | 75552 | 64 | 13664 | 75616 | 13728 |

4.7 Magnetic Calibration Metrics

4.7.1 Background

Hard-iron effects are due to magnetic materials in the vicinity of the sensor. These materials result in an apparent offset to sensor readings when the source of interference is fixed spatially, relative to the sensor.

For a given point in space, plotting magnetometer measurements at various sensor rotations results in the sphere shown on the right hand side of [Figure 12](#). This makes sense, as the magnitude of the 3D magnetic field should not change just because the sensor is rotated.

Soft-iron effects result from the interaction of ferrous materials near the sensor interacting with the ambient magnetic field. If the source of soft iron interference is again fixed spatially with respect to the sensor and does not demonstrate magnetic hysteresis, then the *sphere of plotted measurements* is distorted into an ellipsoid. This is shown (along with a hard-iron offset) on the left side of [Figure 12](#).

[Reference 2: Orientation Representations](#) provides background on the topic of hard- and soft-iron magnetic compensation. For the case where the sensor and sources of interference are spatially fixed with respect to one another, the distortions are linear, and can be reversed mathematically. This is the function of the Freescale magnetic calibration library.

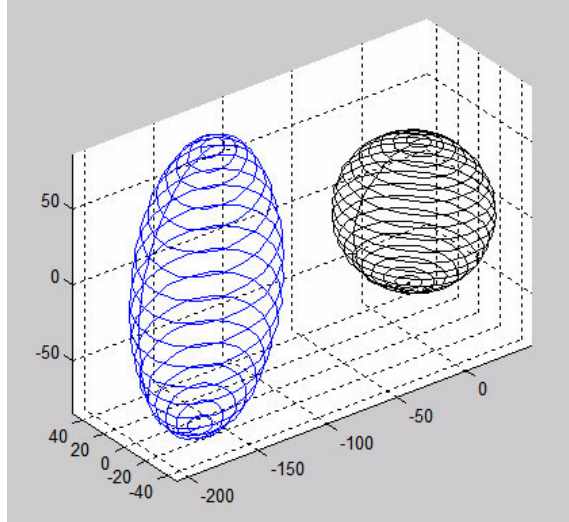


Figure 12. Distorted (left) and Corrected (right) Magnetic Field Data (simulated)

Both hard- and soft-iron interferences are a function of the sensor environment, and not the sensor itself. Each product design will inevitably result in different distortions.

Engineers assigned the task of physically designing PCBs and housings should pay careful attention to sources of magnetic interference early in the design phase.

Inductive charging films found in some portable devices exhibit a significant amount of magnetic hysteresis. This is a nonlinear phenomena and cannot be fully corrected by the Freescale magnetic calibration library.

4.7.2 The Magnetic Buffer

Freescale's magnetic calibration library performs a total least squares fit of a number of data points to map the measured ellipsoid of measurements back into the ideal sphere. Quality of that fit improves as number and spacing of samples across the ellipsoid surface increases. There is a tradeoff in terms of data set size used for calibration versus CPU resources versus quality of fit.

Figure 13 shows improvement in standard deviation of computed results (for a uniform field) versus constellation size.

Mechanical and Electrical Specifications

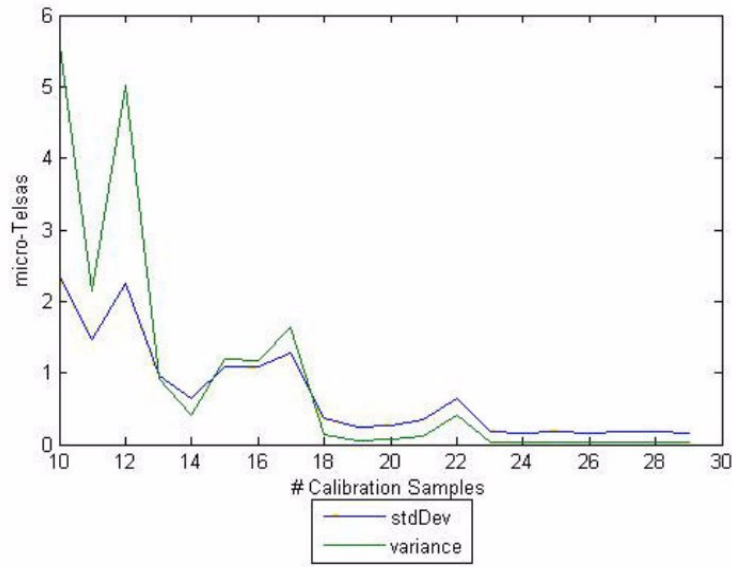


Figure 13. Simulated Standard Deviation and Variance as f(constellation size)

4.7.3 Magnetic Calibration Performance Metrics

Table 13 provides some basic guidance with regard to performance of the magnetic calibration library in a stand-alone configuration.

Table 13. Magnetic Calibration Performance Metrics

| Characteristic | Symbol | Conditions | Min | Typ | Max | Unit |
|--|--------|------------|-----|-----|---------|---------|
| Compass heading linearity; see Compass Heading Linearity and Accuracy | TBD | — | — | < 5 | — | degrees |
| Compass heading accuracy; see Compass Heading Linearity and Accuracy | TBD | — | < 5 | — | degrees | |
| NOTE: The results shown in this table are more conservative than simulated numbers, and are more likely to be representative of actual results. | | | | | | |

4.8 Fusion Model Performance Metrics

4.8.1 Background

The six and nine-axis Kalman filters are optimized for calculation of device orientation. Unmodelled sources of error will affect the other sensor outputs. Tradeoffs are a function of the Kalman filter configuration and are subject to change.

Separate tables are presented for each of the sensor combination options provided by the Fusion Library. Common test conditions and setups are used for all options.

NOTE: Results that follow are simulated build 4.17 using basic sensor models which include noise effects, but ignore nonlinearity and other factors. See Simulation Environments for details. Build 5.00 dynamic performance is expected to be improved from the 4.17 plots shown here.

4.8.2 Gyro Offset Step Response

Gyro Offset Step Response plots are shown in Figure 14 and Figure 15 for 9-axis and 6-axis Accelerometer+Gyro algorithms, respectively and provide an indication of the responsiveness of the system to changes in gyro offsets. The simulation artificially introduces a step in the modeled gyro offset. However, under normal circumstances, gyro offsets change very slowly. The only times that a change such as this would likely occur are:

- at powerup
- if the gyro has an autonomous offset cancellation circuit (which Freescale recommends be turned OFF).

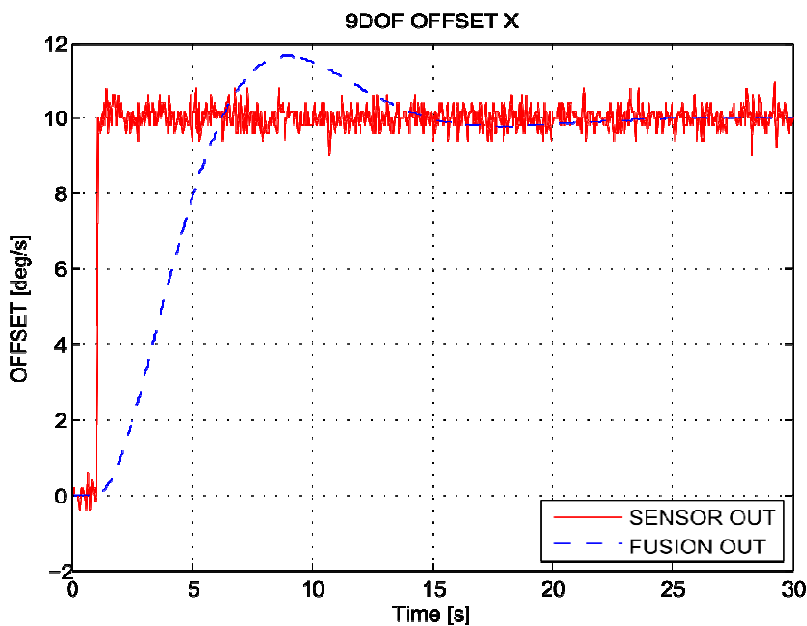


Figure 14. Gyro Offset Step Response for 9-Axis algorithm

Mechanical and Electrical Specifications

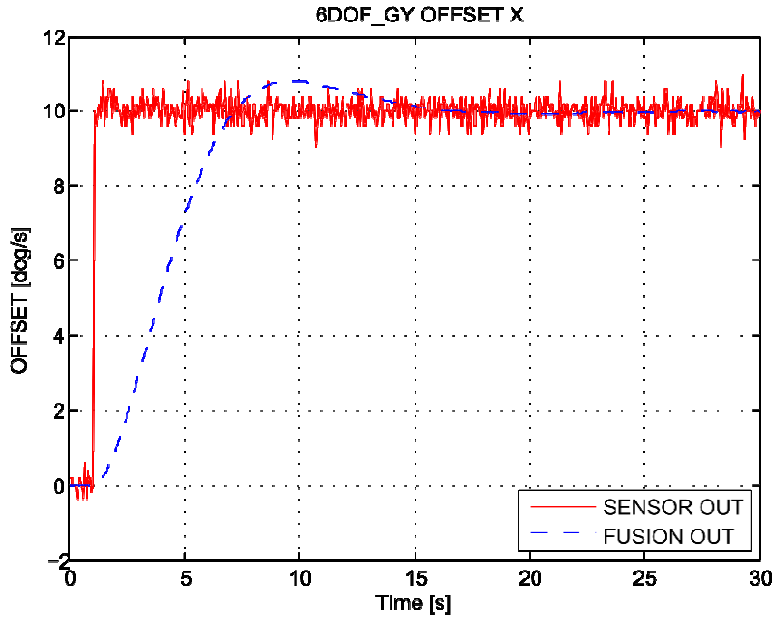


Figure 15. Gyro Offset Step Response for 6-Axis Accelerometer+Gyro algorithm

4.8.3 Error in Computed Linear Acceleration

Estimation of linear acceleration in the 9-axis algorithm is optimized for short duration accelerations lasting less than 1 second. Continuous accelerations are inconsistent with modeled dynamics, and the acceleration estimation error increases. The acceleration error starts leaking into the estimates of orientation resulting in errors in gyro offset and magnetic disturbance estimates. Figure 16, Figure 17 and Figure 18 present the true and 9-axis algorithm calculated linear acceleration for accelerations lasting 0.5 s, 1 s and 5 s respectively.

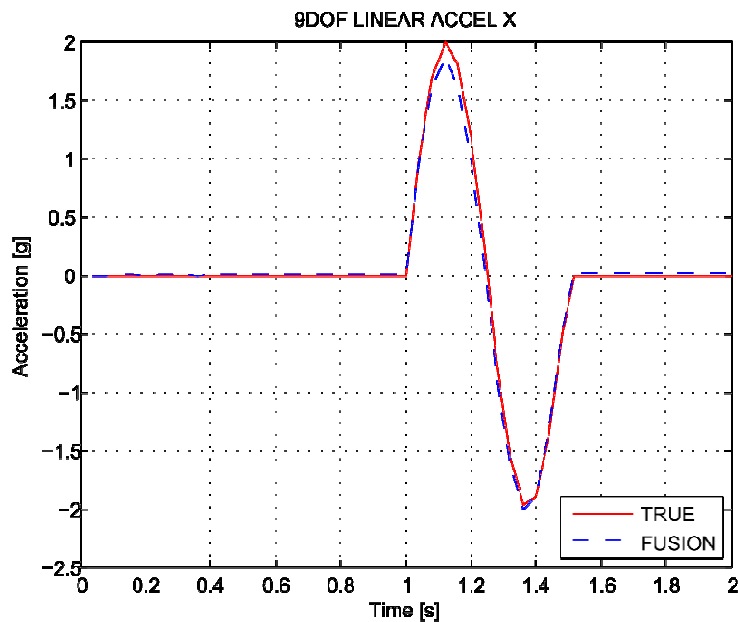


Figure 16. True and calculated linear acceleration, acceleration time 0.5 s

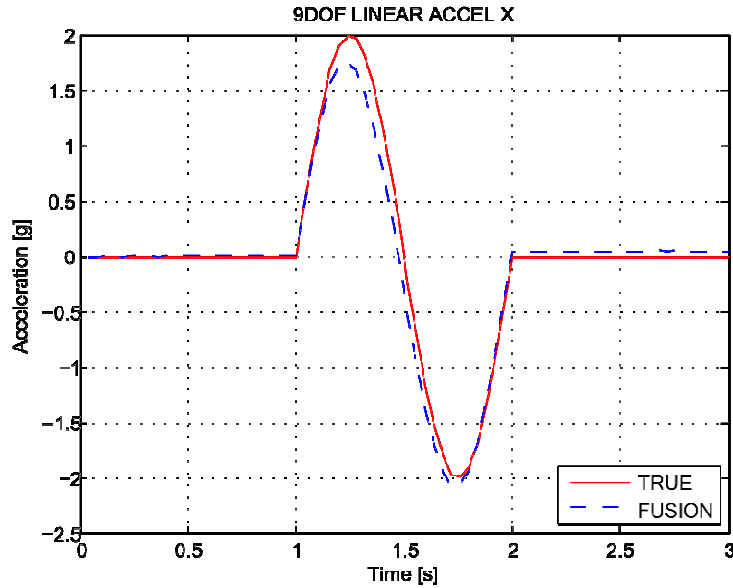


Figure 17. True and calculated linear acceleration, acceleration time 1 s

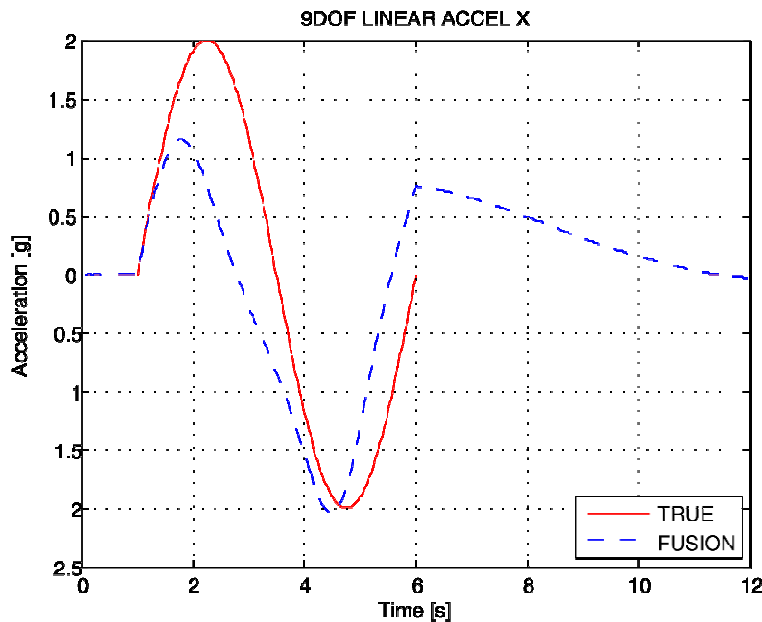


Figure 18. True and calculated linear acceleration, acceleration time 5 s

Similar dependence on the magnetic pulse duration time was noticed in the Orientation Magnetic Immunity tests. A slow-moving magnet introduces a longer lasting magnetic field disturbance pulse than a fast-moving magnet. The longer the magnetic disturbance pulse lasts, the greater the orientation error it causes on the output of the fusion algorithm.

4.8.4 Limitations Imposed via Sensor Choice/Configuration

Table 14 represents the sensor configuration used to determine parameters specified in this datasheet.

Mechanical and Electrical Specifications

Table 14. Sensor/Configuration Imposed Limitations

| Characteristic | Symbol | Min | Max | Unit |
|----------------------|-------------------|-------|-------|----------|
| Maximum Angular Rate | AR _{max} | -2000 | +2000 | dps |
| Linear Acceleration | LA _{max} | -4 | +4 | <i>g</i> |
| Magnetic Field | B _{max} | -1200 | +1200 | μT |

It is believed that the fusion algorithms themselves have no upper limits on any of the parameters above. These are strictly limits associated with the specific physical sensors used to characterize the library.

4.8.5 9-Axis Parametrics

Table 15 provides guidance for the 9-axis (accelerometer/magnetometer/gyro) indirect Kalman filter implementation.

NOTE: All parametrics provided in the following table are based on build 4.17 simulations. Build 5.00 simulations are still pending.

Table 15. 9-axis Sensor Fusion Performance Metrics

| Characteristic | Symbol | Conditions(s) | Min | Typ | Max | Unit |
|---|-------------------|---|-----|--|-----|---|
| Orientation static drift | O _{SD} | See Orientation Static Drift | — | 0.05 | — | degrees |
| Orientation static noise | O _{SN} | See Orientation Static Noise | — | 1.21 | — | degrees RMS |
| Orientation dynamic drift | O _{DD} | See Orientation Dynamic Drift | — | 0.17 | — | degrees |
| Max angular Rate | AR _{MAX} | See Maximum Angular Rate | — | 1600 <small>Error! Reference source not found.</small> | — | dps |
| Orientation response delay | O _{RD} | See Orientation Response Delay | — | <1 | — | ² fusion time interval |
| Gyro offset step response | T _{GOSR} | See Gyro Offset Step Response | — | 3.76 | — | seconds |
| Error in computed linear acceleration | LAE | See Error in Computed Linear Acceleration | — | 0.243 | — | <i>g</i> |
| Compass heading linearity ³ | CH _l | See Compass Heading Linearity and Accuracy | — | 1.02 | — | degrees |
| Compass heading accuracy | CH _{acc} | | — | 1.37 | — | degrees |
| Orientation magnetic immunity - static device | O _{mis} | See Orientation Magnetic Immunity (Static Device) | — | 9.36 | — | degrees |
| Orientation magnetic immunity - moving device | O _{mim} | See Orientation Magnetic Immunity (Moving Device) | — | 8.98 | — | degrees |

1. The Sensor Fusion algorithm has no intrinsic limitation; this was the maximum value supported by the gyro in Freescale testing.
2. Number of output sampling periods where one period = 40 ms
3. Linear sensors, which yields very good compass heading values were assumed. However experience shows that +/-5 degrees are more realistic values.

4.8.6 6-axis Accelerometer + Magnetometer Parametrics

NOTE: All parametrics provided in the following table are based on build 4.17 simulations. Build 5.00 is believed to have similar performance.

Table 16. 6-axis Sensor Fusion Accel + Mag Performance Metrics

| Characteristic | Symbol | Conditions(s) | Min | Typ | Max | Unit |
|--|-------------------|--|-----|--------|-----|---|
| Orientation static drift | O _{SD} | See Orientation Static Drift | — | 0.0018 | — | degrees |
| Orientation static noise | O _{SN} | See Orientation Static Noise | — | 1.06 | — | degrees RMS |
| Orientation dynamic drift | O _{DD} | See Orientation Dynamic Drift | — | 1.16 | — | degrees |
| Orientation response delay | O _{RD} | See Orientation Response Delay | — | <10 | — | sample periods ^{Er} ror! Reference source not found. |
| ² Compass heading linearity | CH _l | See Compass Heading Linearity and Accuracy | — | 1.20 | — | degrees |
| Compass heading accuracy ² | CH _{acc} | | — | 1.58 | — | degrees |

1. Number of output sampling periods where one period = 40 ms
2. Linear sensors, which yields very good compass heading values were assumed. However, experience shows that ±5 degrees are more realistic values.

4.8.7 6-axis Accelerometer + Gyro Parametrics

NOTE: All parametrics provided in the following table are based on build 4.17 simulations. Build 5.00 is believed to have similar static and improved dynamic performance.

Table 17. 6-axis Sensor Fusion Gyro + Accel Performance Metrics

| Characteristic | Symbol | Conditions(s) | Min | Typ | Max | Unit |
|----------------------------|-------------------|---|-----|-------|-----|-----------------------------|
| Orientation static drift | O _{SD} | See Orientation Static Drift | — | 19.07 | — | degrees |
| Orientation static noise | O _{SN} | See Orientation Static Noise | — | 0.068 | — | degrees RMS |
| Orientation dynamic drift | O _{DD} | See Orientation Dynamic Drift | — | 2.04 | — | degrees |
| Max angular Rate | AR _{MAX} | See Maximum Angular Rate | — | 1440 | — | dps |
| Orientation response delay | O _{RD} | See Orientation Response Delay <small>Error! Reference source not found.</small> | — | <1 | — | sample periods ² |
| Gyro offset step response | TBD | See Gyro Offset Step Response | — | 3.76 | — | seconds |

Test Descriptions

1. Output sampling period = 40 ms
2. Number of output sampling periods where one period = 40 ms

4.8.8 3-axis Accelerometer Only Parametrics

NOTE: All parametrics provided in the following table are based on build 4.17 simulations. Build 5.00 should be similar.

Table 18. 3-axis Accelerometer Performance Metrics

| Characteristics | Symbol | Conditions | Min | Typ | Max | Units |
|----------------------------|-----------------|---|-----|-------|-----|----------------------|
| Tilt Error RMS | TAE | Note 1 | — | 0.082 | — | degrees |
| Orientation response delay | O _{RD} | See Orientation Response Delay ² | — | < 5 | — | output sample period |

1. RMS of accelerometer tilt angle error is calculated using the simulated sensor noise RMS values along each of the three axes and the following formula (given for tilt error from the z-axis)

$$\text{TAE} = \arctan \left(\frac{\sqrt{\text{NRMS}_x^2 + \text{NRMS}_y^2}}{1g - \text{NRMS}_z} \right),$$

where NRMS_x, NRMS_y, NRMS_z - RMS values of accelerometer noise for X, Y, Z axes in g units.

2. Number of output sampling periods where one period = 40 ms

5 Test Descriptions

Each of the following sub-sections defines the specification intent and the sample procedure for the specifications listed in [Mechanical and Electrical Specifications](#). Procedures may evolve in future drafts of this document in order to better service the specification intents.

5.1 MCU Current

5.1.1 Intent

This is the average current consumption of the MCU executing the core Fusion routines. This is obviously specific to the particular MCUs listed. This metric must be associated with a specific hardware configuration similar to those defined earlier in this document. The Freedom Development Platform was powered via the OpenSDA USB port for the results specified.

5.1.2 Procedure

1. This procedure uses modified versions of the standard demo build:
 - a. Measure (using the Sensor Fusion Toolbox) sysTick_{fusion} which only includes time spent in the *core fusion routines*. It does *not* include:
 - 1) calls to magnetic calibration
 - 2) reading sensor data
 - 3) applying hardware abstraction layer
 - 4) RTOS
 - 5) Communications overhead

2. Percentage of time spent in the core fusion routines = $100 * \text{sysTick}_{\text{fusion}} / \text{total_sysTicks}^2$
3. I_{dd} Current into the MCU is measured via power jumper on the board using a simple DVM³
4. Fusion $I_{\text{dd}} = \text{MCU } I_{\text{dd}} \times \text{percentage}$
5. All currents shown are in mA
6. Sample size = 1 board

For devices with floating point units, this may yield a somewhat optimistic number, as the computation makes the assumption that all MCU instructions consume the same amount of power. In fact, we can expect floating point instructions to consume a bit more.

5.2 Flash and RAM Required

5.2.1 Intent

These parameters are total RAM and flash memory required to implement and execute the Fusion Library plus MQX-Lite RTOS. The projects for the binaries were created using both CodeWarrior and Kinetis Design Studio. Values for Text, Data and BSS were read directly from the console window after builds completed.

This includes space for code storage, static and dynamic (stack) variables. This metric must be associated with a specific hardware configuration similar to those defined in earlier in this document.

5.2.2 Procedure

The text, data and bss sizes for each build were extracted using the technique outlined at [MCU on Eclipse; text, data and bss: Code and Data Size Explained](#).

1. **text**; includes the user code, the vector table plus constants.
2. **data**; is for initialized variables, and it counts for RAM and FLASH. The linker allocates the data in FLASH which then is copied from ROM to RAM in the startup code.
3. **bss**; is for the uninitialized data in RAM which is initialized with zero in the startup code.

Refer to [Computation Metrics](#) for statistics gathered using the 5.00 build.

5.3 Fusion Loop Execution Time

This is simply CPU cycle time X $\text{sysTick}_{\text{fusion}}$ as measured in Section 5.1.

5.4 Compass Heading Linearity and Accuracy

5.4.1 Intent

Linearity is defined as the deviation of measured data from a least squares straight line approximation of that data.

Absolute accuracy is defined as the maximum difference between measured and ideal values.

² Which is simply the clock rate of the MCU divided by the sensor fusion rate (nominally 25)

³ Consult the user guide / schematic for your Freedom board to determine the specific jumper number applicable to that board.

Test Descriptions

These two concepts are illustrated in [Figure 19](#).

This metric must be stated specifically for a hardware configuration similar to those defined earlier in this document.

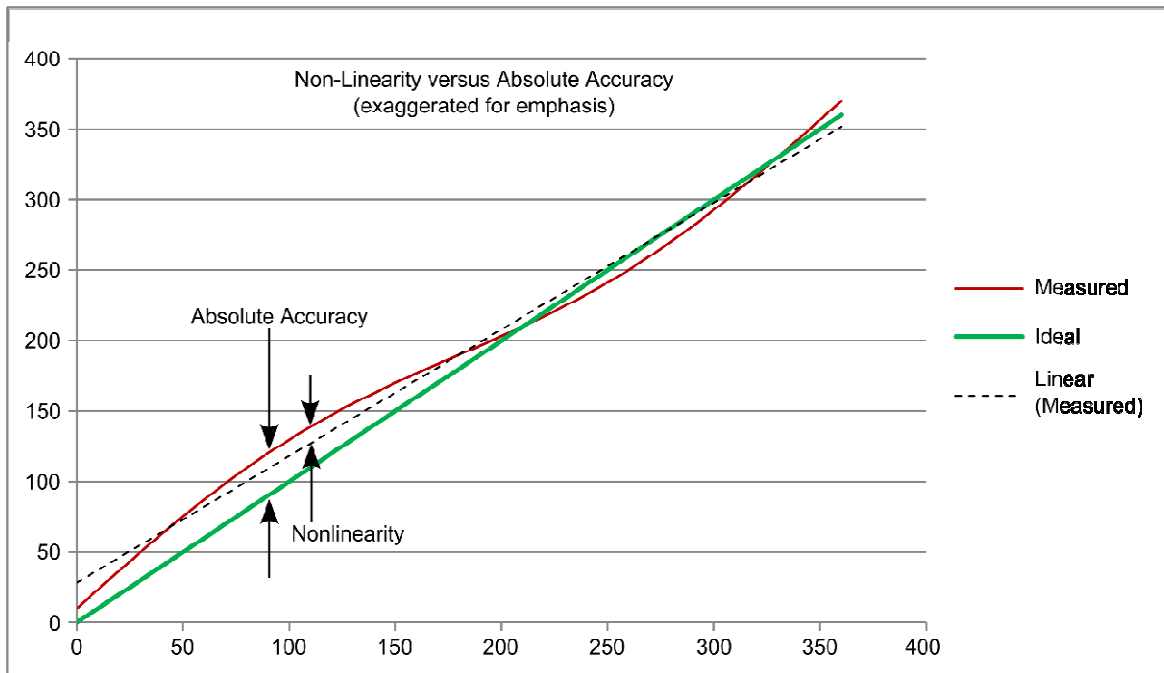


Figure 19. Nonlinearity vs. Absolute Accuracy

5.4.2 Procedure

Heading Linearity

Setup as defined in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Matlab is used to post-process data.

1. Precondition the DUT by executing magnetic calibration trajectory leaving DUT in AZ = + 1 orientation (See [Matlab Stimulus/Expected Response + Hardware-based Fusion](#))
2. Rotate DUT around the z-axis from 0 to 360 degrees with an increment step of 10 degrees as follows
3. Program rate table with desired steps and maximum velocity
 - a. Rotate tabletop by 10 degrees over 0.5 second period
 - b. Pause 0.5 seconds
 - c. Read orientation
 - d. Repeat steps a-c above until 360 degrees is reached.

Absolute Heading Accuracy

These numbers are based on simulations that are idealized models. The real-world values will tend to be approximately 5 degrees.

5.5 Orientation Static Drift

5.5.1 Intent

The maximum change in orientation observed for a DUT remaining motionless for 100 seconds.

5.5.2 Procedure

Setup as defined in *Matlab Stimulus/Expected Response + Hardware-based Fusion*. Matlab is used to post-process data.

This metric must be associated with a specific hardware configuration similar to those defined in earlier in this document. Matlab is used to record and post-process data.

1. Precondition the DUT by executing magnetic calibration trajectory leaving DUT in a given orientation.
2. While the DUT remains in given orientation collect orientation samples for 120 seconds.
3. Plot and process the last 100 s of the test. Orientation static drift is the maximum angle change in the measured rotation vectors.
4. Repeat steps 1-3 for all 6 major orientations of the development board as shown in [Figure 20](#).

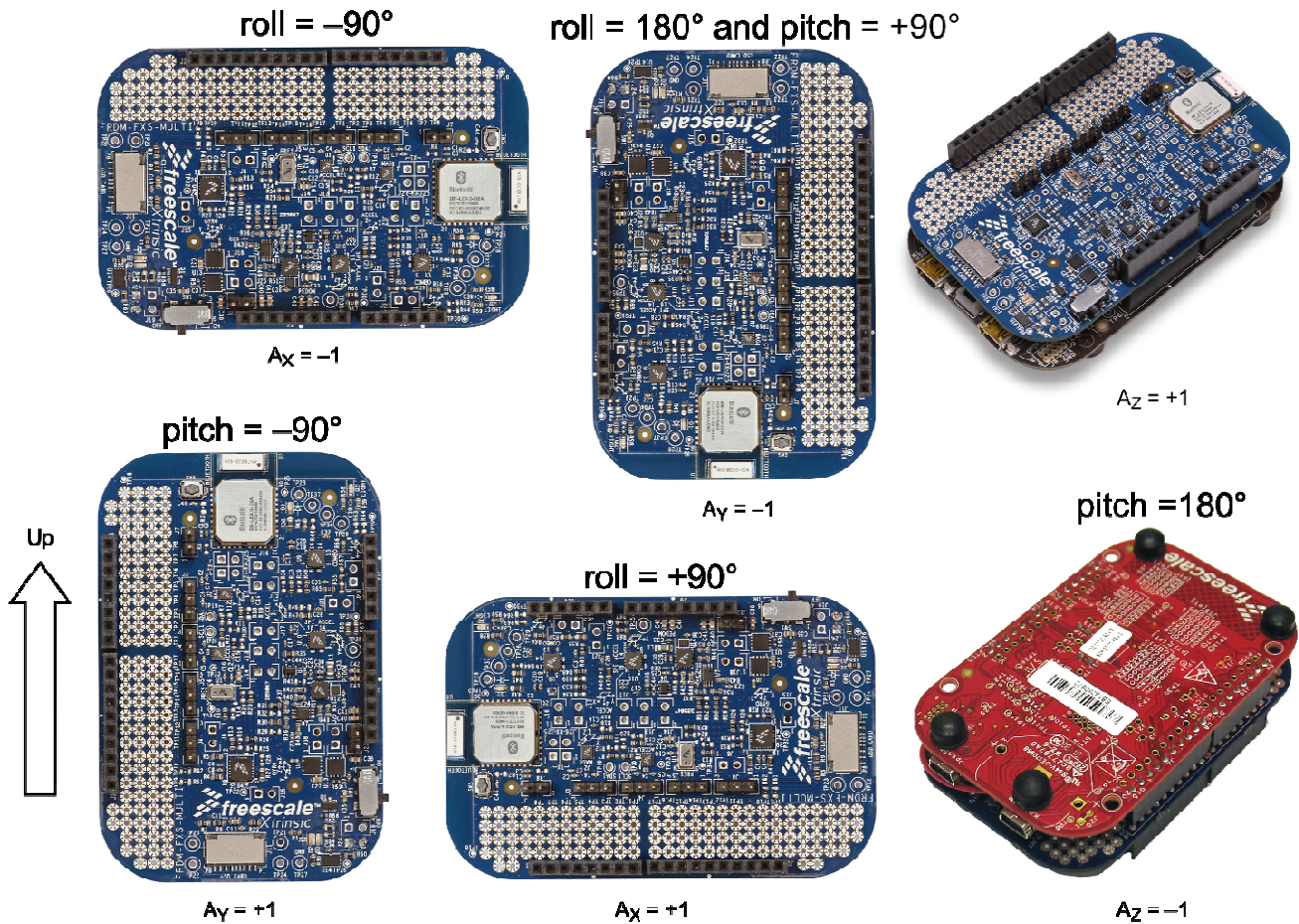


Figure 20. Major orientations relative to gravity

Test Descriptions

5.6 Orientation Static Noise

5.6.1 Intent

RMS noise as a function of orientation for a motionless DUT.

5.6.2 Procedure

This can be based upon data gathered for the orientation static drift test. The classic standard deviation equation is used to compute the metric/value.

5.7 Orientation Dynamic Drift

5.7.1 Intent

Measure of the ability of fusion code to return to a known orientation after movement.

5.7.2 Procedure

Setup as defined in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#) and in [Figure 9](#). Matlab is used to post-process data.

1. Precondition the DUT by executing magnetic calibration trajectory leaving DUT in a given orientation.
2. Keep DUT in a given orientation motionless for 2 seconds.
3. Rotate DUT at 0.5 revolution/sec for 10 seconds around vertical axis.
4. Keep DUT in its last orientation motionless for 2 seconds.
5. Determine the initial orientation by averaging orientation samples from the initial motionless period and the final orientation by averaging the samples from the final motionless period. The difference between the two orientations is the orientation dynamic drift.
6. Repeat steps 1-5 for all six major orientations of the development board.

5.8 Maximum Angular Rate

5.8.1 Intent

This test determines the maximum rotation rate for which the filter is able to correctly track orientation.

5.8.2 Procedure

Setup as defined in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Matlab is used to post-process data.

1. Rotate DUT around X axis five times starting at rotation rate 360 dps.
2. Plot the ideal simulated orientation together with the orientation samples calculated by Kalman filter fusion algorithms: 9DOF and 6DOF Accelerometer + Gyro and notice if fusion data tracks the ideal orientation.
3. Increase the rotation rate by 360 dps and repeat steps 1 and 2.
4. The highest angular rate at which the fusion algorithm orientation still tracks the ideal simulated orientation is the maximum angular rate.

5.9 Orientation Response Delay

5.9.1 Waveform Definitions

90° Input Change in Orientation

The 90° input orientation change waveform is defined as:

- From any starting orientation
- Through the center of mass of the accelerometer
- A change in one of roll, pitch or yaw (global frame)
- Orientation change = $\pm 90^\circ$
- Orientation change is linear in time
- Transition period = 1.0 seconds
- Propagation delays are measured from the 1/2 point ($\pm 45^\circ$)

Output Orientation Changes

When measuring changes in orientation, there are many ways to get from orientation A to orientation B. It is assumed that output orientation changes should track input orientation changes. The Fusion Library will inherently output those values. However, to avoid any ambiguity when measuring propagation delays, the 50% point in computed orientations changes is defined as shown in [Figure 21](#).

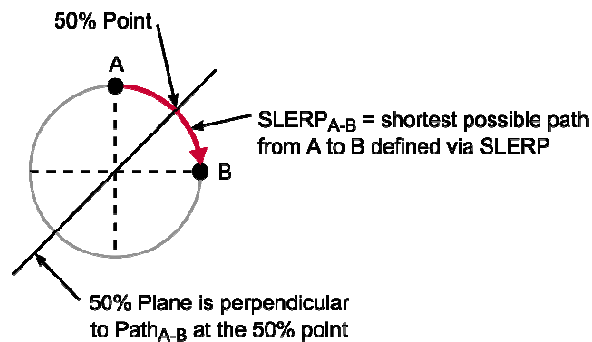


Figure 21. Propagation delays are measured at the plane that bisects and is perpendicular to SLERP_{A-B}

5.9.2 Intent

Orientation response delay is measured from change in physical orientation to the related change in fusion orientation output.

5.9.3 Procedure

Using 90° input orientation change as defined in [90° Input Change in Orientation](#), the response delay is measured from the 50% point on the input waveform to the 50% point of the output waveform as defined in [Output Orientation Changes](#).

Test Descriptions

5.10 Orientation Magnetic Immunity (Static Device)

5.10.1 Intent

The test response of the stationary DUT to momentary changes in the local magnetic field is used to measure the orientation magnetic immunity. Because the device is stationary, the accelerometer and gyroscope readings remain relatively constant, changing only due to sensor noise.

5.10.2 Procedure

Setup as defined in *Matlab Stimulus/Expected Response + Hardware-based Fusion*. Matlab is used to post-process data.

1. Starting point = device stationary, fusion outputs stable
2. 100 μ T magnet moving at 0.25 m/s
3. Closest approach to magnetic sensor = 5 cm
4. Test to be simulated using environment specified in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Magnetic interference may be modeled as a time varying field which is consistent with the description above.

5.11 Orientation Magnetic Immunity (Moving Device)

5.11.1 Intent

This test measures the immunity of a linearly, with no rotation, moving DUT to a 100 μ T magnet change in the magnetic field. The outputs of all acceleration and magnetic sensors change during this test. Gyro outputs should be constant throughout, with any changes attributed to noise only.

5.11.2 Procedure

1. Starting point = device stationary, fusion outputs stable.
2. Use a 100 μ T magnet.
3. The DUT moves by magnet at 0.25 m/s with the closest approach to magnet=5cm.
4. Test to be simulated using environment specified in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Magnetic interference may be modeled as a location varying field which is consistent with the description above.

5.12 Error in Computed Gyro Bias

5.12.1 Intent

Measure how well the fusion library tracks slowly varying gyro bias.

5.12.2 Procedure

Test to be simulated using environment specified in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#).

1. Starting point = device stationary, fusion outputs stable
2. Add 10 dps gyro offset as step function
3. Run test until computed gyro offset stabilizes

4. Note computed/actual for final value
5. Note response time

5.13 Gyro Offset Step Response

5.13.1 Intent

Measure how well the fusion library tracks varying gyro offset.

5.13.2 Procedure

Setup as defined in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Matlab is used to post-process data.

1. Starting point = DUT is stationary and fusion outputs are stable.
2. Add offset of 10 dps to gyro X read data.
3. Run test until computed gyro offset stabilizes.
4. Plot the gyro read data step function and the response fusion algorithm estimated offset. Record response time as time between 50% step change in gyro X read data and 50% change in fusion algorithm estimated gyro X offset.

5.14 Error in Computed Linear Acceleration

5.14.1 Intent

Measure how well the fusion library tracks linear acceleration.

5.14.2 Procedure

Setup as defined in [Matlab Stimulus/Expected Response + Hardware-based Fusion](#). Matlab is used to post-process data.

1. Starting point = DUT is stationary and fusion outputs are stable.
2. Subject DUT to acceleration $A \cdot \sin(2 \cdot \pi \cdot f \cdot t)$, where: $A = 2 \text{ g}$, $f = 1 \text{ Hz}$, $t = \text{zero to one second}$ (1 period), $\pi = 3.141592654$
3. Plot the ideal DUT acceleration and fusion algorithm computed acceleration. Determine the maximum error between the two accelerations.

6 Revision history for FSFLK_DS

| Rev. No. | Date | Description |
|----------|-------------|---|
| 0 | 12 Nov 2013 | <ul style="list-style-type: none"> ROUGH DRAFT ONLY - PRE-REVIEW |
| 0.1 | 22 Nov 2013 | <ul style="list-style-type: none"> Preliminary draft includes updates from 1st review. |
| 0.2 | Feb 2014 | <ul style="list-style-type: none"> Initial public release. |
| 0.3 | Apr 2014 | <ul style="list-style-type: none"> Updated for licensing, software updates and board support changes. |
| 0.4 | May 2014 | <ul style="list-style-type: none"> Updated for software updates, additional (FRDM-K64F) board support changes and electrical specs and computation metrics. |
| 0.5 | Sept 2014 | <ul style="list-style-type: none"> Updated Fusion Performance Metrics section by adding four new figures and tables. adjusted selected parametric values altered several Test Description procedures. |
| 0.6 | Sept 2014 | <ul style="list-style-type: none"> Separated out Computational Metrics section and various minor markups Changed Feature - License, option text. Feature Comparison Based on License Option, Added KDS to Product Deliverables row Moved sections 4.1, 4.1.1 & 4.1.2 and merged in 4.11 Added xrefs from Electrical Specs tables to appropriate Test Description sections Adjusted Performance Metric tables, symbols and units in some cases |
| 0.7 | Sept 2015 | <ul style="list-style-type: none"> Updated for build 5.00 of the sensor fusion library. This version has completely redesigned 6 and 9-axis Kalman filters. Updated all computation metrics. Removed outdated fusion time measurements. Added K22F for KDS. Added additional fusion options. Changed document name from XSFLK_DS to FSFLK_DS. Noted that MULTI-B boards have been replaced with MULT2-B boards. |

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