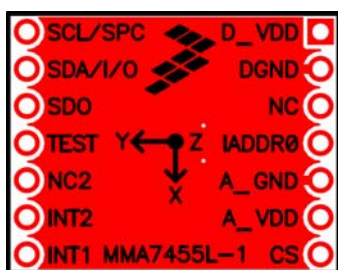


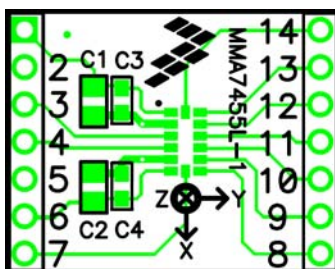
The MMA745xL Digital Accelerometer

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The MMA745xL digital accelerometer is a 3 x 5 x 1 mm product that can communicate using both I²C and SPI. This device has both threshold and pulse detection interrupts. There are 2 sampling rates available at 125 Hz (using the 62.5 Hz digital filter) and 250 Hz (using the 125 Hz digital filter). There is a self test function to verify the integrity of the MEMS sensor and the ASIC signal path. **Figure 1** shows the simple evaluation board for the MMA745xL which is available online. This board contains the accelerometer with all pins mapped out to a 14 pin header. The image on the left shows the ground plane which ties the digital and analog ground pins together. This is necessary to improve the noise performance based on internal trim and is the recommendation for this part. The image in the center is the front view of the board which shows all the other connections. This board can be wired to a Freescale MCU evaluation or demo board and programmed for various application functions which are described in detail below.



Back View



Front View



Actual Image of the Board

Figure 1. MMA745xL Accelerometer Simple Evaluation Board

APPLICATIONS AND SENSING CAPABILITIES OF THE MMA745XL

The MMA745xL is the first family of digital 3-axis consumer accelerometers that Freescale has designed. There are several sensing functions that accelerometers are capable of detecting. These are motion, freefall, shock, vibration, and tilt. The advantage of a digital accelerometer is that the A/D converter is implemented within the sensor and an MCU can be used to accompany the sensor that does not require the A/D converter. The sensor can connect directly to the SPI or I²C into the MCU. The disadvantage is that there are selected digital filters within the sensor which limits the sampling rate for certain applications.

Motion Detection

Typically motion detection is used to identify if an object is in use or not based on change in acceleration output. The purpose of power cycling is to try to minimize the power consumption for the application. By moving into a standby (low power) mode when the device is not in use then switching to measurement mode (active mode) which is a full power mode, the overall power consumption can be decreased. The power consumption is the same regardless of the two sampling rate options in the active modes. The MMA745xL can be put into standby mode for a set period of time consuming only 5 μ A. Then the device must be programmed to switch over to measurement mode to monitor the X, Y, Z outputs to determine if a significant change in acceleration has occurred. This can be done using a timer function in the MCU. The device will not auto wake from standby mode. When in an active mode the device consumes 400-450 μ A of current. The device can be power cycled between standby mode and measurement mode minimizing the overall current consumption for the application. This is useful in a wide variety of applications. It is particularly important in handheld devices which require batteries to operate.

Hints for a Power Cycling Algorithm

During a power cycling routine the device will be set to standby mode until the MCU timer triggers. Then the MCU will switch the sensor into measurement mode and take one reading from X, Y and Z. If the RMS value is a certain threshold greater than 1g or less than 1g then motion is detected and the device will stay in measurement mode. Otherwise the MCU will switch accelerometer back into standby mode. The timing will be somewhat dependant on the circumstances of the application and the tradeoff between the reaction time vs. the consumed current.

Motion Detection using the MMA745xL Logic Interrupts

The Level Detection mode can be used to detect motion with an interrupt. The threshold level can be set and the interrupt will occur when a motion greater than the threshold occurs. There are no timers in the Level Detection mode and false readings are possible. It is recommended to set the threshold level to 2g or greater for motion detection using the Level Detection to minimize false readings. The Pulse Detection mode can detect motion as a single pulse or as a double pulse. The threshold and the time of the pulse must be set. In pulse mode the detection occurs when X or Y or Z is greater than the set threshold within the set time window (less than the time window). It is not able to detect motion for a time period greater than a set time window. Motion detection can also be done in measurement mode sampling the X, Y and Z outputs with a set timer. This method would require programming the algorithm with the MCU. This last method would be necessary to detect a motion for greater than a set time period.

Freefall

Freefall is a sensing function that can be used to identify that a large impact is highly probable. This is useful in notebook computers to park the drive heads before impact and for many types of electronic equipment to shut down before impact. Freefall can also be used for warranty protection along with shock to identify how high an object has fallen to determine the approximate resultant force. For a robust algorithm there are various different freefall conditions that should be considered; linear freefall, projectile fall and rotational fall. Cheaper freefall solutions typically only consider linear freefall.

Linear Freefall using the MMA745xL Logic Interrupts

The MMA745xL has internal logic to detect linear freefall using either the *Level* Detection or the *Pulse* Detection modes. The Level Detection is not as robust because it does not have any timers associated with it. It simply detects any resultant output of $X \& \& Y \& \& Z < \text{Set Threshold}$. The Pulse Detection Freefall condition is more robust because it has a timer. The Pulse Detection freefall algorithm looks at $X \& \& Y \& \& Z < \text{Threshold}$ for $> \text{Latency Timer}$. The timer in the pulse detection helps avoid false readings.

Advanced Freefall Algorithm Hint

Using a microcontroller to store some of the past history and to analyze the outputs linear, projectile and rotational falls can be detected using the MMA745xL to detect if any of these different conditions are occurring.

Shock

Shock is a sensing function of the accelerometer that is useful for warranty protection, shipping and handling and to detect the end of a fall condition. It is also used to detect tapping. Shock is a sensing function that can be difficult to detect with the consumer low-g accelerometers because shocks are typically high accelerations. The MMA745xL is capable of detecting up to 8g of acceleration. In some cases freefall can be used to determine the height of a fall using the standard Newtonian equations of motion and then back calculating for the distance.

Detecting Shock using the MMA745xL Logic Interrupts

The Level Detection interrupt can be used to detect shock in the same manner it is done for motion detection. The single and double pulse interrupts are the most useful for shock.

Vibration

Vibration sensing is limited by the digital filtering in the accelerometer. The MMA745xL has a maximum sampling rate of 250 Hz. Therefore it is capable of detecting from DC to 125 Hz of vibration. The MMA745xL is suitable for these lower frequencies.

Tilt

Tilt is used for many different applications. The cell phone and PMP market has exploded with opportunities for accelerometers to perform tilt functions. The most popular features are portrait/landscape orientation detection, scrolling, and menu selection. The two main challenges of tilt are to determine the required resolution and accuracy for the application. The MMA745xL has a maximum sensitivity of 64 counts/g. The resolution is the smallest detectable change in acceleration which is 16 mg per count. This corresponds to approximately 1.5 degrees of resolution using two axes. The accuracy is how closely the true value is equal to the measured value from the accelerometer. This is dependant on the sum of all errors from the accelerometer. Typically after calibration the accuracy is about ± 4 degrees.

SENSOR PLACEMENT

Sensor placement is very important and is often overlooked. The MEMS sensor inside the package is very sensitive to stresses. Small deflections inside the MEMS sensor on the order of 10 nm correspond to a change in acceleration of 1g. Care must be taken to ensure that the package is not stressed by holes or components on the PCB placed too closely to the accelerometer. Please review the mounting guidelines in AN3484. It is important to not place the sensor near an edge where it may be knocked around or touched by people's hands. Also avoid bending the PCB as the PCB stress is transferred to the accelerometer. Temperature can also be an issue. It is good to avoid placing the sensor far away from components that may have large temperature variations, or that are constantly very hot as this will also affect the offset of the sensor. For optimal motion detection, place the sensor away from the center of the device. This will ensure better acceleration readings and make them more significant to detect smaller motions, from a higher moment of inertia than if placed right on the center of movement.

Connecting the MMA745xL to an MCU using I²C Communication

Connecting this evaluation board to an MCU using I²C communication is simple. Connect power and ground, SDA and the SCL lines appropriately to the MCU. The 10 μ F capacitors are added in case of a dirty input supply.

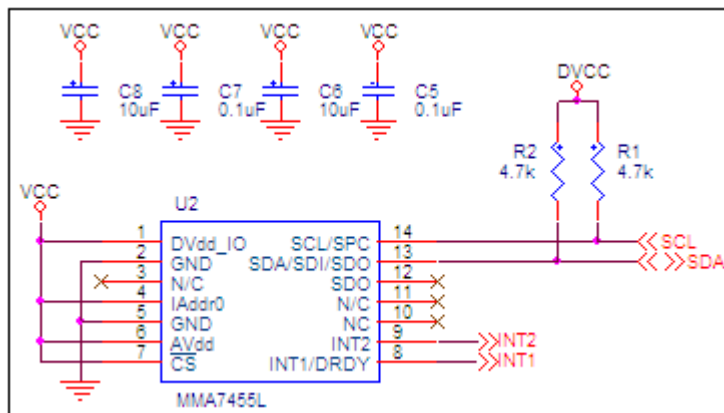


Figure 2. I²C Communication Sensor Connections

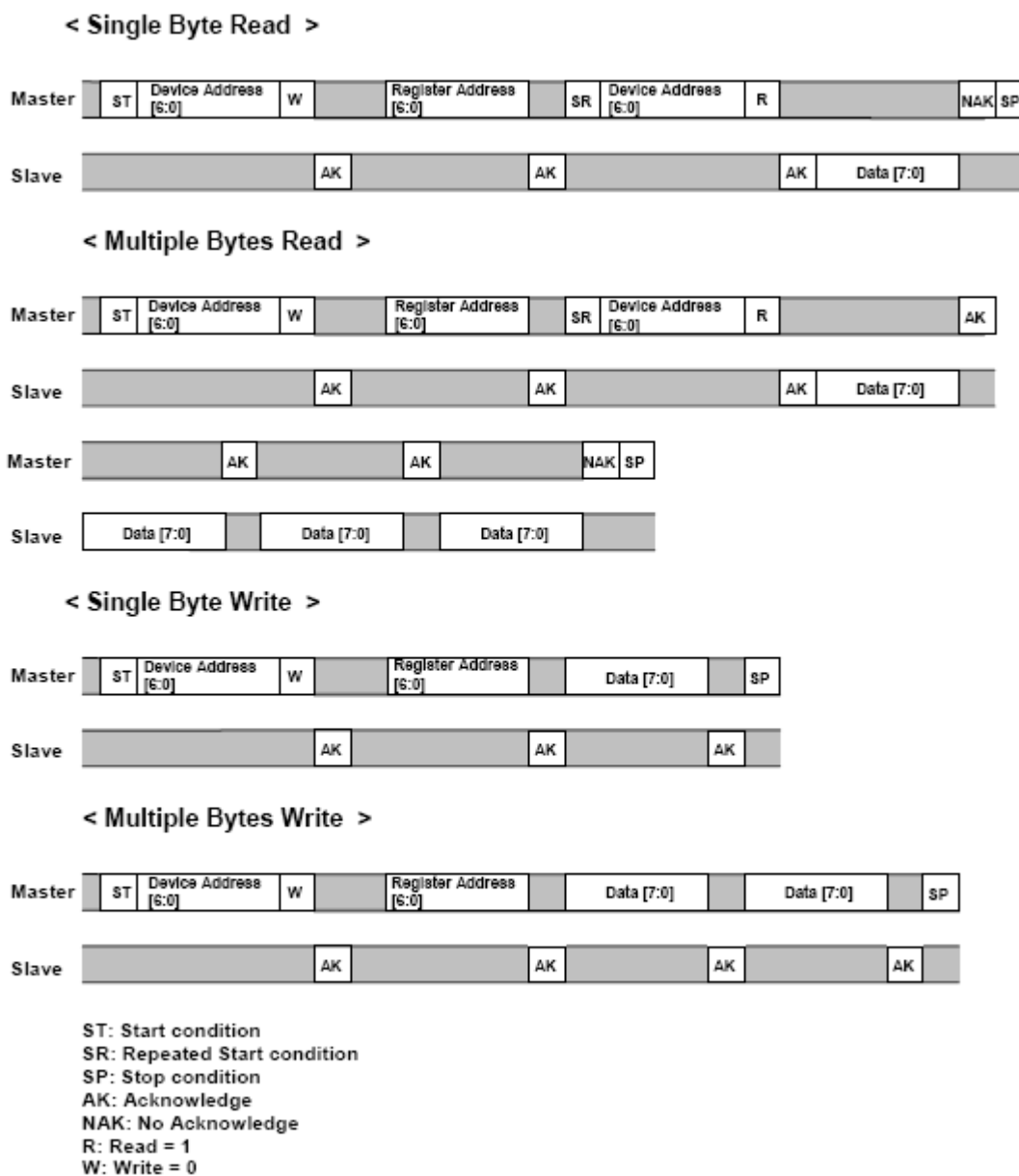


Figure 3. IIC Read and Write Protocol Format

The MMA745xL IIC communication protocol follows the Philips Semiconductors (now NXP Semiconductors) standard. In this interface only two bus lines are required: a serial data line (SDA) and a serial clock line (SCL). Serial, 8-bit oriented bidirectional data transfers can be made at up to 100 kbit/s in the Standard-mode and up to 400 kbit/s in the fast-mode. These modes are adjustable by changing the clock frequency. The maximum allowable bus capacitance is 400 pF. Both SDA and SCL are bidirectional lines, connected to a positive supply voltage via a pull-up resistor. The recommended value is between 2.2 kΩ - 4.7 kΩ. The accelerometer is always considered the slave and the MCU is always considered the master. The accelerometer is not capable of stretching the clock.

The benefits of the I²C Communication interface is that many ICs can be added to this bus. The only limitation is the bus capacitance. The simple 2 wire serial I²C-bus minimizes interconnections so ICs have fewer pins and there are not as many PCB traces, resulting in smaller and less expensive PCBs.

Each device is recognized by a unique address (whether it is a microcontroller, memory or an accelerometer). The MMA7455L has an extra address bit to allow for two different addresses available but the address pin on this sensor has been disabled. This device is addressed by \$1D only. The IADDR0 pin is enabled on the MMA7458L, which will be available in Q4 2008.

The following are four simple rules of the IIC bus to be aware of:

1. The SDA (data) and SCL (clock) cannot actively be driven high by any I²C device. I²C devices must use open-drain drivers. The logic is high by using the recommended external pull-up resistors.
2. The information on the data line is only read on the high phase of the clock.
3. Changing the level of the data is only allowed in the low phase of the clock except during start or stop conditions and this is how these events are signified.
4. When the bus is not busy SDA and SCL lines are pulled back to logic "1".

For more detailed information on the I²C protocol please refer to the NXP Semiconductor IIC bus specification and user manual available online.

BASIC START-UP PROCEDURE

The following are some simple steps to set up the accelerometer using IIC.

1. Set up the microcontroller hardware shown above for IIC communication.
2. Configure the clock speed and all the pins required. The speed is set by adjusting the baud rate.
3. Write simple single byte Read and Write command to communicate to the device. The example below was done using the MC9S08QE hardware controller for the IIC.
4. Write to the MMA745xL Register \$16, sending in a value of 0x05 to set up the device for measurement mode with $\pm 2g$ dynamic range.
5. Read the Control Register \$16 to ensure that the value is correct (0x05).
6. Read the X, Y and Z registers and watch the outputs change.

Example Code for Start-up Using IIC

The following code has been written with a Freescale S08 MCU using the embedded IIC module. This software is for the host side.

```
//-----
// HW I2C driver embedded I2C module using FSL MC9S08QE K. Tuck
#define IIC_WriteAdr 0x1D // $1D shifted in with a 0 had been $3A
#define IIC_ReadAdr 0x1D // $1D shifted in with a 1 had been $3B

//Function Definitions
void MCU_init(void); // From Device initialization
void Delay(byte count);
void IIC_SingleByteWrite(unsigned char reg, unsigned char val);
char IIC_SingleByteRead(unsigned char reg);
// global variables
char Xdata=0;
char Ydata=0;
char Zdata=0;
char ControlRegVal=0;
unsigned char ACK, writel;
//-----
//Main
void main(void) {
    MCU_init();
    IIC2C1_MST = 0;
    Delay(0xFF);
    IIC2C1_MST = 1; // create start
    Delay(0xFF);
    IIC2C1_MST = 0; // create stop
    Delay(0xFF);
    //IIC_SingleByteWrite(0x16,0x05); // Put ION into Measurement Mode
    Delay(0xFF);
    ControlRegVal=0;
    Xdata=0;
    Ydata=0;
```

```

Zdata=0;
ControlRegVal= IIC_SingleByteRead(0x16); //Read back out the value of Register 16, make sure
it is 5

// Read X, Y, and Z forever
for(;;) {
    Delay(0xFF);
    Xdata=IIC_SingleByteRead(0x06); // Read X Register
    Delay(0xFF);
    Ydata=IIC_SingleByteRead(0x07); // Read Y Register
    Delay(0xFF);
    Zdata=IIC_SingleByteRead(0x08); // Read Z Register
}
for(;;) {
    /* __RESET_WATCHDOG(); by default, COP is disabled with device init. When enabling, also
reset the watchdog. */
    } /* loop forever */
    /* please make sure that you never leave main */
}
//-----
//-----
//Simple Delay Function
void Delay(byte count)
{
    byte i;
    for (i=0; i<count; i++)
    {
        }
}
//-----
// This is the I2C byte write function
void IIC_SingleByteWrite(unsigned char reg, unsigned char val)
{
    IIC2C1_IICEN=1;
    IIC2C1_TX=1;
    IIC2C1_MST=1; //Sends Start;
    IIC2D = (IIC_WriteAdr<<1); // send the accelerometer address
    while (IIC2S_IICIF==0);//Waiting for transmission to complete
    Delay(100);
    IIC2S_IICIF=1;
    Delay(100);
    if (IIC2S_RXAK==1){
        IIC2C_MST=0; //send stop
        ACK=0;
        while(1);
    }
    else{
        ACK=1;
    }
    IIC2D = reg; //write in the register address
    while (IIC2S_IICIF==0 );//Waiting for transmission to complete
    IIC2S_IICIF=1;
    if (IIC2S_RXAK==1){
        IIC2C1_MST=0; //send stop
        ACK=0;
        while(1);
    }
    else{
        ACK=1;
    }
    IIC2D = val; // send the data to be written
    while (IIC2S_IICIF==0);//Waiting for transmission to complete
}

```

```

IIC2S_IICIF=1;
if (IIC2S_RXAK==1){
IIC2C_MST=0; //send stop
ACK=0;
while(1);
}
else{
ACK=1;
}
IIC2C1_MST=0;
writel=1;
}
//-----
//-----
// This is the I2C byte read function
char IIC_SingleByteRead(unsigned char reg)
{
char data;
IIC2C1_IICEN=1;
IIC2C1_TX=1;
IIC2C1_MST=1; //Sends Start;
IIC2D = (IIC_WriteAdr<<1); // send the accelerometer address
Delay(0x50);
while (IIC2S_IICIF==0); //Waiting for transmission to complete
IIC2S_IICIF=1;
if (IIC2S_RXAK==1){
IIC2C_MST=0; //send stop
ACK=0;
while(1);
}
else{
ACK=1;
}
IIC2D = reg; //write in the register address
Delay(0x50);
//Check_ACK(); //check ACK
while (IIC2S_IICIF==0); //Waiting for transmission to complete
IIC2S_IICIF=1;
if (IIC2S_RXAK==1){
IIC2C_MST=0; //send stop
ACK=0;
while(1);
}
else{
ACK=1;
}
//Sending a Restart, the device Address with a Read
IIC2C1_TX=1;
IIC2C1_RSTA=1; //Sends Start;
IIC2D =(IIC_ReadAdr<<1)|0x01;
// Send the accelerometer device address with the Read Bit
//Delay(100);
//Check_ACK(); //check ACK
while (IIC2S_IICIF==0); //Waiting for transmission to complete
IIC2S_IICIF=1;
if (IIC2S_RXAK==1)
{
IIC2C_MST=0; //send stop
ACK=0;
while(1);
}
else{

```

```

    ACK=1;
}
IIC2C1_TX=0; // Change over to Receiver Mode
IIC2C_TXAK = 1; // send NACK in the next read
data=IIC2D; //dummy read
while (IIC2S_IICIF==0);
IIC2S_IICIF=1; // wait until the transmission ends
data = IIC2D; //This is the real Read command
while (IIC2S_IICIF==0); // wait until the transmission ends
IIC2S_IICIF=1; //Clear the interrupt flag
IIC2C1_MST = 0; // send a stop, leave master mode
return(data);
}
//-----

```

General Pseudo Code Using IIC

The following is general IIC code based on work by V.Himpe¹.

n, x = general BYTE
 SIZE = max number
 DATA(SIZE) = an array holding up to SIZE number of bytes. This will contain the data transmitted and store received data.
 BUFFER = a byte value holding immediate received or transmit data.

```

/ $$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$ / / **** I2C Driver
General I2C Pseudo Code Released as Public Domain **** / /
$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$$ /
DECLARE N,SIZE,BUFFER,X Byte
DECLARE DATA() Array of SIZE elements
SUBroutine I2C_INIT / call this immediately after power-on /
    SDA=1
    SCK=0
    FOR n = 0 to 3
    CALL STOP
    NEXT n
ENDsub
SUBroutine START
    SCK=1
    SDA=1
    SDA=0
    SCK=0
    SDA=1
ENDsub
SUBroutine STOP
    SDA=0
    SCK=1
    SDA=1
ENDsub
SUBroutine PUTBYTE(BUFFER)
    FOR n = 7 TO 0
        SDA= BIT(n) of BUFFER
        SCK=1
        SCK=0
    NEXT n
    SDA=1
ENDsub
SUBroutine GETBYTE
    FOR n = 7 to 0
        SCK=1
        BIT(n) OF BUFFER = SDA

```

1. <http://www.esacademy.com/faq/i2c/general/i2cpseud.htm>


```

        SCK=0
    NEXT n
    SDA=1
ENDsub
SUBroutine GIVEACK
    SDA=0
    SCK=1
    SCK=0
    SDA=1
ENDsub
SUBroutine GETACK
    SDA=1
    SCK=1
    WAITFOR SDA=0
    SCK=0
ENDSUB
/ this concludes the low-level set of instructions for the I2C driver
The next functions will handle the telegram formatting on a higher level /
SUBroutine READ(Device_address,Number_of_bytes)
    Device_address=Device_address OR (0000.0001)b /This sets the READ FLAG/
    CALL START
    CALL PUTBYTE(Device_adress)
    CALL GETACK
    FOR x = 0 to Number_of_bytes
        CALL GETBYTE DATA(x)=BUFFER /Copy received BYTE to DATA array /
        IF X< Number_of_bytes THEN /Not ack the last byte/
            CALL GIVEACK
        END IF
    NEXT x
    CALL STOP
ENDsub
SUBroutine WRITE(Device_address,Number_of_bytes)
    Device_address=Device_address AND (1111.1110)b / This clears READ flag /
    CALL START
    CALL PUTBYTE(Device_adress)
    CALL GETACK
    FOR x = 0 to Number_of_bytes
        CALL PUTBYTE (DATA(x))
        CALL GETACK
    NEXT x
    CALL STOP
ENDsub
SUBroutine RANDOMREAD(Device_adress,Start_adress,Number_of_bytes)
Device_adress=Device_adress AND (1111.1110)b / This clears READ flag /
    CALL START
    CALL PUTBYTE(Device_adress)
    CALL GETACK
    CALL PUTBYTE(Start_adress)
    CALL GETACK
    CALL START /create a repeated start condition/
    Device_adress=Device_adress OR (0000.0001)b /This sets the READ FLAG/
    CALL PUTBYTE(Device_adress)
    CALL GETACK
    FOR x = 0 to Number_of_bytes
        CALL GETBYTE
        DATA(x)=BUFFER
        CALL GIVEACK
    NEXT x
    CALL STOP
ENDsub

```

For further information and examples using the QE128 Freescale S08 with the MMA745xL there is an example with a SW implementation of the driver available in the following software application notes on-line.

- AN3479SW: shows the programming required to communicate to the device using the IIC bus.
- AN3468SW: has examples of using measurement mode, level mode and pulse detection.
- AN3571SW: shows different settings for using either the level or the pulse detection mode

Connecting the MMA745xL to an MCU using SPI Communication

When connecting the sensor to the MCU using SPI communications there are 6 connections into the MCU. These connections are power, ground, the clock (SPSCK), MOSI (data), MISO (data) and CS which is the slave select line. The 10 μ F caps are added as an extra precaution in case of a dirty supply input.

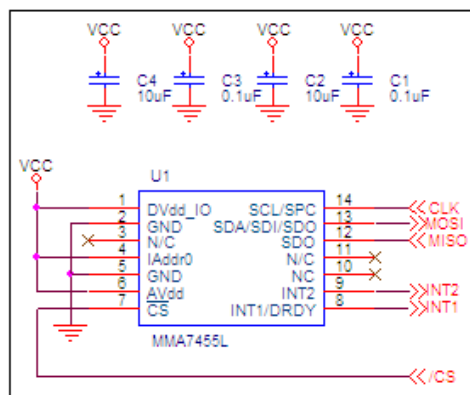
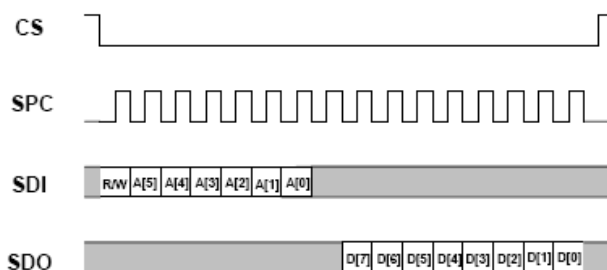


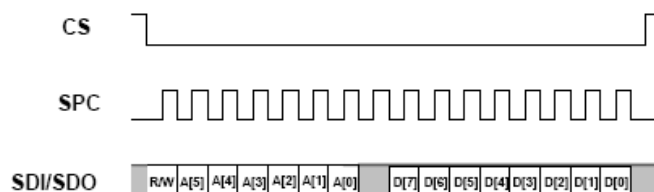
Figure 4. SPI Communication Sensor Connections

< Read Operation >

4 wire mode



3 wire mode



< Write Operation >



Figure 5. SPI Timing Diagrams

SPI communication can be implemented using 4 lines: MOSI (master-output/slave-input), MISO (master-input/slave-output), SS (slave select), and SPSCK (SPI serial clock). The master device initiates all SPI data transfers. During a transfer, the master shifts data out (on the MOSI pin) to the slave while simultaneously shifting data in on the MISO pin from the slave (SDO). The transfer effectively exchanges the data that was in the SPI shift registers of the two SPI systems. The SPSCK signal is a clock output from the master and an input to the slave. The slave device must be selected by a low level on the slave select input (CS pin). The MMA745xL is in SPI 4 wire mode by default. Register \$16 contains a bit labeled SPI3W, which is set to 0 by default for 4 wire mode. SPI communication can also be implemented using 3 lines: MIMO (master-in/master-out), SS (slave select), SPSCK (SPI serial clock). The SDA/I/O line on the MMA745xL changes from being an input into the accelerometer and becomes a bidirectional line. To set up the sensor for 3 wire SPI communication bit SPI3W in Register \$16 (Control Register 1) must be set to 1. For four wire SPI mode SPI3W is set to 0. The following example shows how to set up the register in either mode and into 2g measurement mode.

WriteRegister (0x16, 0x25) to set the accelerometer into SPI 3 wire mode 2g measurement mode.

WriteRegister (0x15, 0x05) to set the accelerometer into SPI 4 wire mode 2g measurement mode.

When using the SPI bus the register value is sent with the first value being a 1 to indicate write or 0 to indicate a read command. Note this is opposite from the IIC R/W bit. The address is 6 bits, followed by a "Don't Care" bit, which has no meaning to the slave. For example to send a read command the 6-bit register data is simply shifted left 1 bit. (SPI2D=((reg &0x3F)<<1);). For a write command the first bit is a 1. SPI2D(((reg &0x3F)<<1)|0x80);

The SPI clock speed of the sensor can go up to 4 MHz which is configured by the baud rate chosen in the MCU. This is the maximum achievable speed when DVdd is less than 2.4 V. When DVdd is greater than 2.4 V up to 8 MHz is achievable.

BASIC START-UP PROCEDURE

The following are some simple steps to set up the accelerometer with an MCU for the SPI communication.

1. Set-up the microcontroller hardware shown in [Figure 4](#) for SPI communication.
2. Configure the clock speed and all the pins required. The speed is set by adjusting the baud rate.
3. Write simple single byte Read and Write command to communicate to the device. The example below was done using the hardware controller for the SPI.
4. Write to the MMA745xL Register \$16, sending in a value of 0x05 to set up the device for measurement mode with $\pm 2g$ dynamic range.
5. Read the Control Register \$16 to ensure that the value is correct (0x05).
6. Read the X, Y and Z registers and watch the outputs change.

Example Code for Start-up Using SPI

The following example code was developed with a Freescale S08 MCU using the embedded SPI module. This software is for the host side. This example shows the code for both 4Wire Mode and 3Wire Mode. The MCU can be initialized for 3 Wire Mode or for 4 Wire Mode and the following code will execute.

```
//-----
// HW SPI driver embedded SPI module using FSL S08QE MCU K. Tuck
//-----
#define CS PTDD_PTDD3
byte Xdata,Ydata,Zdata,CTLReg;
void MCU_init(void); /* Device initialization function declaration */
byte spi_read(byte reg);
void spi_write(byte reg, byte data);

void main(void) {
    MCU_init(); /* call Device Initialization */
    PTDD_PTDD3=1; //CS Pin description
    PTDDD_PTDDD3=1;
    Xdata=0;
    CTLReg=0;
    //Set up sensor for SPI 3 Wire Mode or 4 Wire Mode by writing to SPI3W in Register $16
    spi_write(0x16,0x25); //3 Wire Mode Set up in the Accelerometer
    // spi_write(0x16,0x05); //4 Wire Mode Set up in the Accelerometer
    CTLReg=spi_read(0x16); // Read back the value that has been set for the Mode
    for (;;) {
        Xdata=spi_read(0x06); //Read X,Y,Z outputs from Sensor
        Ydata=spi_read(0x07);
    }
}
```

```

Zdata=spi_read(0x08);
}
for(;;) {
    /* __RESET_WATCHDOG(); by default, COP is disabled with device init. When enabling, also
reset the watchdog. */
    } /* loop forever */
    /* please make sure that you never leave main */
}
//-----
// Function Definitions for Read and Write
// Read function SPI 3 Wire Mode or 4 Wire Mode
byte spi_read(byte reg){
    byte x;
    CS=0;
    x=SPI2S;
    x=SPI2D;
    while (!SPI2S_SPTEF);
    SPI2D= ((reg &0x3F)<<1); // write in the register address with the read command
    while(!SPI2S_SPRF); //wait for transfer
    x=SPI2D;
    SPI2C2_BIDIROE = 0;          // MOSI become input when 3 wire mode
    SPI2D = 0x00;                // send 2nd byte
    while (!SPI2S_SPRF);        // wait transfer done
    x = SPI2D;
    SPI2C2_BIDIROE = 1;          //change direction back to output when in 3 wire mode
    CS=1;
    return (x);
}
//-----
//Write function SPI 3 Wire or SPI 4 Wire Mode
void spi_write(byte reg, byte data){
    byte x;
    CS=0;
    SPI2D=(((reg &0x3F)<<1)|0x80);
    while (!SPI2S_SPRF); //wait for transmission complete
    x=SPI2D; //dummy read
    SPI2D=data;
    while (!SPI2S_SPRF); //wait for transmission complete
    x=SPI2D;
    CS=1;
}
//-----

```

General Pseudo Code using SPI

This is pseudo code for general communication.

1. SS = 0 Slave Select is cleared
2. Assert MOSI most significant bit
3. Toggle the clock
4. Shift the next data bit onto the MOSI pin
5. Repeat 3 and 4 until done
6. SS = 1 Slave Select is set

For further examples using the SPI SW protocol please refer to the following application notes which should be available on the website. These examples use the basic evaluation board shown in [Figure 1](#) with the MC9S08QE128, or with the HCS08GB60 MCU development boards.

- AN3468SW: has examples of using measurement mode, level mode and pulse detection.
- AN3480SW: shows the programming required to communicate to the device using the SPI bus.
- AN3571SW: shows different settings for using either the level or the pulse detection mode

PROGRAMMING THE MMA745XL

This section focuses on explaining all the available features of the device which are all accessible by reading and writing to the 32 registers of the MMA745xL. [Figure 6](#) is a screen shot of an evaluation interface for this device. This GUI uses the MMA745xL with the MC9S08QE8 microcontroller on a small 1" x 1" board which connects through SCI to USB to the computer. This demo board and software is available as part of the Sensors Toolbox (LFSTBEB7456). It displays the 3-axis output on a scope screen to view motion of the different axes. All the different settings and operation modes of the device are displayed on the menu buttons or sliders. On the right hand side all the useful registers of the device are displayed. This allows the user to view how the registers change when different settings are changed.

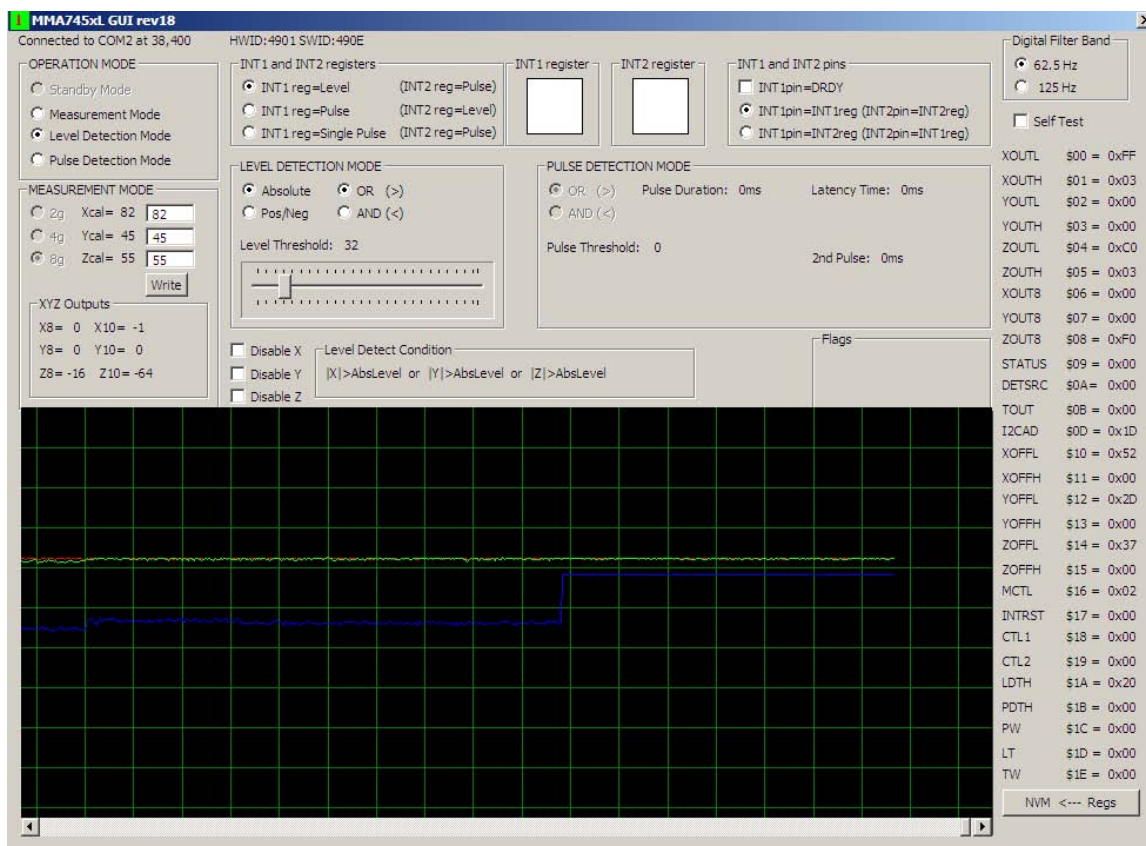


Figure 6. MMA745xL Evaluation Software Interface

OPERATION MODES OF THE MMA745XL ACCELEROMETER

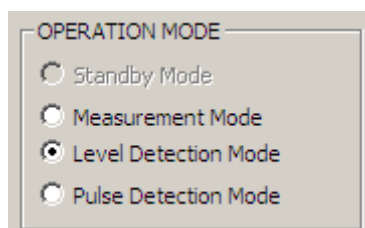


Figure 7. Operation Modes of the MMA745xL

All modes of the device are controlled in the mode control register (MCTL). [Figure 7](#) displays the different modes of the MMA745xL. The following are the bits in the register and the different modes that the device can be set.

\$16	MCTL	LPEN	DRPD	SPI3W	STON	GLVL[1]	GLVL[0]	MOD[1]	MOD[0]
------	------	------	------	-------	------	---------	---------	--------	--------

Standby mode is a low power mode consuming less than 5 μ A. This mode is used when the sensor is not needed to take new data. In standby mode the sensor can read and write to the registers and the other sensor detection modes are easily enabled.

Standby Mode: RegisterWrite (0x16, 0x00)

In measurement mode the device can be set up for 3 different dynamic ranges (2g, 4g and 8g). With the 8g dynamic range 8-bit or 10-bit data is available. The 2g and 4g ranges are only 8-bit data. The 10-bit data is available by reading X: \$00-01, Y\$02-03 and Z\$04-05. In 2g mode and 4g mode the 10-bit data will match the 8-bit data. In 8g mode the 10-bit data is going to be 4 times that of the 8-bit data.

Measurement Mode: RegisterWrite (0x16,0x01)

Dynamic Range Settings: In Measurement Mode

2g: RegisterWrite(0x16, 0x05)

4g RegisterWrite (0x16,0x09)

8g RegisterWrite (0x16,0x01)

Level Detection Mode: RegisterWrite (0x16, 0x02)

Note: Dynamic range setting is automatically 8g.

Pulse Detection Mode: RegisterWrite (0x16, 0x03)

Note: Dynamic range setting is automatically 8g.

CALIBRATION OF THE MMA745XL

The offset can be calibrated by storing the offset values in the designated offset drift registers \$10 to \$15 in the accelerometer. These values will be stored until the part loses power and therefore it is a good idea to store these values in the memory of a microcontroller, used in conjunction with the sensor. This will provide automatic calibration of the sensor each time the sensor is turned back on. In order to calibrate the MMA745xL 0g offset, the predetermined digital offset values should be subtracted from the reading of the actual digital sensing values. The following procedure is a recommendation for how this can be accomplished:

Step 1. After power up, set up the "Mode Control Register"(Register \$16) to be in "measurement mode" by writing \$05 into Register \$16. Then read the X, Y and Z offset values from the Registers \$00-\$08. The first 6 registers of the 9 are 10-bit XYZ output values: LSB, first; MSB, second. Please verify with the data sheet for detailed register information.

Step 2. In this step, the offset compensation is calculated to shift the offset to zero. For example, if the 0g offset is calibrated flat (where X = 0g, Y = 0g and Z = +1g) in 2g mode (64 LSB/g sensitivity), the outputs from Registers \$00-\$08 might be the following: X = +18, Y = -20, Z = +44. In this case,

- X must be shifted by -18 to get X back to zero
- Y must be shifted by +20 to get to zero
- Z must be shifted by $(+64 - 44) = +20$ to get to +64 (since Z is in the +1g orientation)

If the register values in the X = 0g, Y = 0g and Z = +1g orientation are the following:

Step 3. These compensation values can be written in hexadecimal into the "Offset Drift Registers" \$10-\$15. The Offset Drift Registers require each value to be ½ LSB, therefore the calibration values calculated in Step 2. must be multiplied by two. Note that there will still be a bit of offset shift, and you may need to multiply by a bit more than two to exactly subtract the offset.

If the register values in the X = 0 g, Y = 0g and Z = +1g orientation are the following:

X = +18, Y = -20, Z = +44

Write -36 (DC Hex) into the X drift Register \$10

Write +40 (28 Hex) into the Y drift Register \$12

Write +40 (28 Hex) into the Z drift Register, \$14

If the compensation requires negative values, remember that 2's complement is always used in hexadecimal for storing the signed value as was done for the X-axis above. If using 10-bit mode, and the calibrated values are greater than 8 bits, then there is another register for up to 3 more bits:

- Register \$10 and \$11 are for X
- Register \$12 and \$13 are for Y
- Register \$14 and \$15 are for Z

These registers follow signed byte data using 2's complement. Reading or writing low byte (X, Y or Z) OUTL latches high byte data (X, Y, or Z) OUTH to allow coherent 10-bit reads or writes. (X, Y, or Z) OUTH should be read/written directly following (X, Y or Z) OUTL.

Step 4. After this compensation process is complete, you can continue to modify the values by overcompensating until you get the final output to be right at 0 for X and Y and at 64 for Z. Note this is an iterative process.

Step 5. The calibrated values are stored in the "Offset Drift Registers". To avoid the values being erased when the power is turned off, it is recommended to store these values in flash or a nonvolatile memory in the main processor or external to the processor. It is also recommended to include a short start-up sequence to write the compensation values stored in flash or nonvolatile memory to the registers \$10-\$15 in the accelerometer on start-up. If a microcontroller is used, a recursive program is available to auto-calibrate the device.

To set the 0g offset the following recursive program can be written as a routine in the software. Place the part flat in the X = 0g, Y = 0g, Z = 1g orientation. The following is an example of the code to do an auto-calibration routine.

```
signed char Xdata,Ydata,Zdata;
signed short Xcal,Xcalp, Ycal, Ycalp, Zcal, Zcalp;
byte Xcal_L, Xcal_H, Ycal_L,Ycal_H, Zcal_L, Zcal_H;

void main (void){
//Initialization code for the MCU connections and accelerometer
MCU_and_MMA745xL_demo_Init();
//Put the device in 2g Measurement Mode
IIC_ByteWrite(0x16,0x05);
//Assure that the calibration registers are cleared (not necessary)
IIC_ByteWrite(0x10,0);
IIC_ByteWrite(0x11,0);
Xcal=0;
for (;;)
{
Xdata=IIC_ByteRead(0x06);          //Read X, Y,Z
Ydata=IIC_ByteRead(0x07);
Zdata=IIC_ByteRead(0x08);
Xcal+= -2*Xdata;                   //Calculate out the calibration Value based on current Data
Ycal+= -2*Ydata;
if (Zdata>65){Zcal+=(Zdata-64)*2;}
else{Zcal+=(64-Zdata)*2;}
Xcalp=Xcal;                        //If calp is "positive" it is assigned to cal variable
if (Xcalp<0) Xcalp +=2048;         //If Negative value then convert for 2's complement
Ycalp=Ycal;
if(Ycalp<0) Ycalp+=2048;
Zcalp=Zcal;
if(Zcalp<0) Zcalp+=2048;

Xcal_L= (byte)(Xcalp&0x00FF); //shift low byte to lower 8 bits
Xcal_H= (byte)((Xcalp&0xFF00)>>8); //shift high byte to upper 8 bits

Ycal_L= (byte)(Ycalp&0x00FF); //shift low byte to lower 8 bits
Ycal_H= (byte)((Ycalp&0xFF00)>>8); //shift high byte to upper 8 bits

Zcal_L= (byte)(Zcalp&0x00FF); //shift low byte to lower 8 bits
Zcal_H= (byte)((Zcalp&0xFF00)>>8); //shift high byte to upper 8 bits
Xcal += -2*Xdata;
Delay (0xFF);
Xdata=RegisterRead(0x00);
}
IIC_ByteWrite(0x10,Xcal_L); //Write low calibration value to the low calibration register
IIC_ByteWrite(0x11,Xcal_H); //Write high calibration value to the high calibration register
IIC_ByteWrite(0x12,Ycal_L); //Write low calibration value to the low calibration register
IIC_ByteWrite(0x13,Ycal_H); //Write high calibration value to the high calibration register
IIC_ByteWrite(0x14,Zcal_L); //Write low calibration value to the low calibration register
IIC_ByteWrite(0x15,Zcal_H); //Write high calibration value to the high calibration register

MCU_Delay100us(100); //Delay before rereading to ensure that values are written
}
}
```


SETTING UP THE SAMPLING FREQUENCY AND SELF TEST

To set the bandwidth filter to 62.5 Hz the sampling frequency will be 125 Hz. Clear DFBW in Control Register 1.

RegisterWrite (0x18,regs[0x18] & 0xEF)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	1	1	1	1	1	1	1
\$18	result	0	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

To set the bandwidth filter to 125 Hz the sampling frequency will be 62.5 Hz. Set DFBW in Control Register 1.

RegisterWrite (0x18,regs[0x18] | 0x80)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	0	0	0	0	0	0
\$18	result	1	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

To verify the self test. Set STON in Mode Control Register \$16. Clear STON to turn off self test.

RegisterWrite(0x16, regs[0x16] ^ 0x10)

\$16	MCTL	LPEN	DRPD	SPI3W	STON	GLVL[1]	GLVL[0]	MOD[1]	MOD[0]
\$16	mask	0	0	0	1	0	0	0	0
\$16	result	LPEN	DRPD	SPI3W	~STON	GLVL[1]	GLVL[0]	MOD[1]	MOD[0]

SETTING UP INT1 AND INT2 INTERRUPT REGISTERS

This section explains how to set up the interrupt pins in all possible configurations.

The interrupt registers are set up in the Control 1 (CTL1) Register to determine which interrupt is assigned to Level detection and which is assigned to Pulse detection. [Figure 8](#) displays the different options for setting up the interrupt pins.

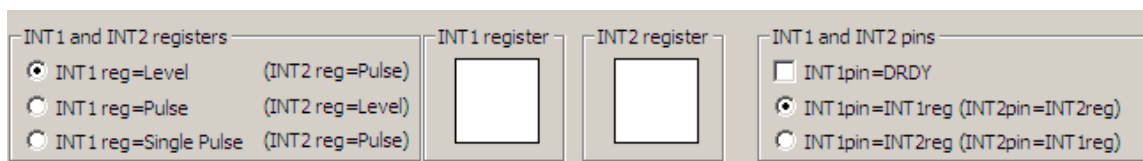


Figure 8. Setting up the Interrupt Registers for Level and Pulse Detection

INT1 reg = Level and INT2 reg = Pulse

RegisterWrite(0x18, regs[0x18]&0xF9)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	1	1	1	1	0	0	1
\$18	result	DFBW	THOPT	ZDA	YDA	XDA	0	0	INTPIN

INT1 reg = Pulse and INT2 reg = Level

RegisterWrite(0x18,(regs[0x18]&0xFB)|0x02)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	1	1	1	1	0	1	1
\$18	result	DFBW	THOPT	ZDA	YDA	XDA	0	1	INTPIN

INT1 reg = Single Pulse and INT2 reg = Pulse

RegisterWrite(0x18,(regs[0x18]&0xFD)|0x04)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	1	1	1	1	1	0	1
\$18	result	DFBW	THOPT	ZDA	YDA	XDA	1	0	INTPIN

INT1pin assigned to DRDY

This pin can be set to allow INT1 to be used to indicate when data is ready from the sensor.

RegisterWrite(0x16, reg[0x16]^0x40)

\$16	MCTL	LPEN	DRPD	SPI3W	STON	GLVL[1]	GLVL[0]	MOD[1]	MOD[0]
\$16	mask	0	1	0	0	0	0	0	0
\$16	Result	LPEN	~DRPD	SPI3W	STON	GLVL[1]	GLVL[0]	MOD[1]	MOD[0]

INT1pin assigned to INT1 Reg (INT2pin = INT2 Reg)

RegisterWrite(0x18, regs[0x18]&FE)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	1	1	1	1	1	1	0
\$18	result	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	0

INT1pin assigned to INT2 Reg (INT2pin = INT1 Reg)

RegisterWrite(0x18, regs[0x18] | 0x01)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	0	0	0	0	0	1
\$18	result	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	1

LEVEL DETECTION MODE

Level detection mode is capable of detecting both motion and freefall. There are no timers associated with the level detection. The OR logic is used for motion detection and the AND logic is used for freefall detection. Then there is signed threshold detection (+ or -) or absolute (+ and -).

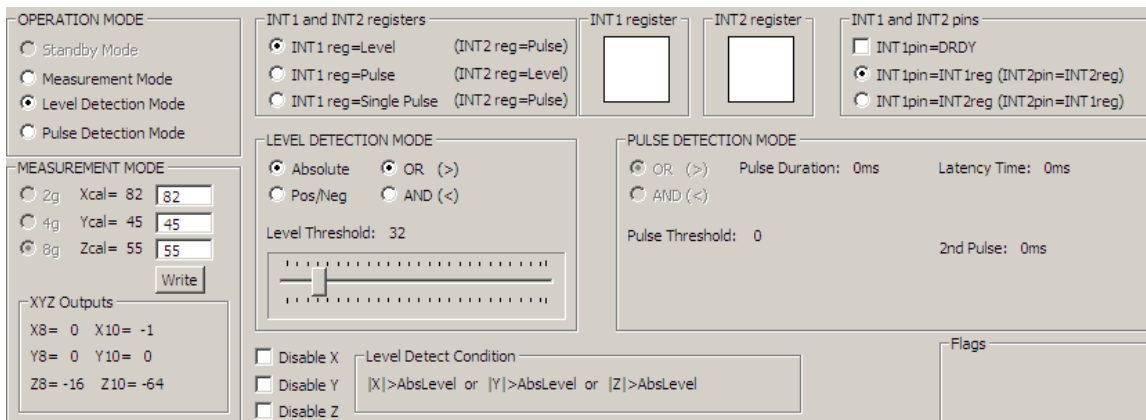


Figure 9. Level Detection Settings

These are the following available options for Level Detection Mode and how they can be enabled.

For motion or for freefall detection there is an **absolute condition** that can be used.

RegisterWrite(0x18,regs[0x18]&0xBF)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	1	1	1	1	1	1
\$18	result	DFBW	0	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

For motion detection there is a **positive/negative detection condition** that can be used.

RegisterWrite(0x18,regs[0x18]|0x40)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	1	0	0	0	0	0	0
\$18	result	DFBW	1	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

For **motion** detection only there is an **or** logic condition that can be used. LDPL = 0

RegisterWrite (0x19,regs[0x19]&0xFE)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	1	1	1	1	1	1	1	0
\$19	Result	—	—	—	—	—	DRVO	PDPL	0

For **freefall** detection only there is an **and** logic condition that can be used. LDPL = 1

RegisterWrite1(0x19,regs[0x19]|0x01)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	0	0	0	0	0	0	0	1
\$19	result	—	—	—	—	—	DRVO	PDPL	1

This is an example of how to toggle the XDA bit to enable or disable the X-axis.

RegisterWrite1(0x18,regs[0x18]^0x08)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	0	0	1	0	0	0
\$18	result	DFBW	THOPT	ZDA	YDA	~XDA	INTRG[1]	INTRG[0]	INTPIN

This is an example of how to toggle the YDA bit to enable or disable the Y-axis.

RegisterWrite1(0x18,regs[0x18]^0x10)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	0	1	0	0	0	0
\$18	result	DFBW	THOPT	ZDA	~YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

This is an example of how to toggle the ZDA bit to enable or disable the Z-axis.

RegisterWrite1(0x18,regs[0x18]^0x20)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	1	0	0	0	0	0
\$18	result	DFBW	THOPT	~ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

This is the register for setting the threshold value. [Table 1](#) shows the hex values with the associated counts and g-values to understand how to program in the level value that corresponds to the acceleration threshold desired.

\$1A	LDTH	LDTH[7]	LDTH[6]	LDTH[5]	LDTH[4]	LDTH[3]	LDTH[2]	LDTH[1]	LDTH[0]
------	------	---------	---------	---------	---------	---------	---------	---------	---------

In Threshold Detection Mode the sensitivity is 16 counts/g. The threshold is set in the LDTH \$1A 8-bit Register.

Table 1. Setting Threshold Values

Binary	Hex	Decimal	Counts	g-value
0000 0000	0x00	0	0	0g
0001 0000	0x10	16	16	1g
0010 0000	0x20	32	32	2g
0011 0000	0x30	48	48	3g
0100 0000	0x40	64	64	4g
0101 0000	0x50	80	80	5g
0110 0000	0x60	96	96	6g
0111 0000	0x70	112	112	7g
0111 1111	0x7F	127	127	8g
1000 0000	0x80	-128	128	-8g
1001 0000	0x90	-112	144	-7g
1010 0000	0xA0	-96	160	-6g
1011 0000	0xB0	-80	176	-5g
1100 0000	0xC0	-64	192	-4g
1101 0000	0xD0	-48	208	-3g
1110 0000	0xE0	-32	224	-2g
1111 0000	0xF0	-16	240	-1g
1111 1111	0xFF	-1	255	0g

Optimal Settings for Freefall using Level Detection

For optimal settings for the freefall using Level Detection choose the following settings:

- Absolute Logic (THOPT)
- X, Y, and Z must be enabled (ZDA, YDA, XDA)
- Negative AND Logic (LDPL = 1)
- LDTH: Level Detection Threshold = 0x03 = 0.19g

1. THOPT = 0 Absolute Condition
2. ZDA = 0 Enable Z, YDA = 0 Enable Y, XDA = 0 Enable X

RegisterWrite(0x18,regs[0x18]&0x87)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	0	0	0	1	1	1
\$18	result	DFBW	0	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

3. Negative AND Logic Set LDPL

RegisterWrite(0x19,regs[0x19]|0x01)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	0	0	0	0	0	0	0	1
\$19	Result	—	—	—	—	—	DRVO	PDPL	1

4. Set Threshold = 0.19 g

RegisterWrite(0x1A,0x03)

\$1A	LDTH	LDTH[7]	LDTH[6]	LDTH[5]	LDTH[4]	LDTH[3]	LDTH[2]	LDTH[1]	LDTH[0]
------	------	---------	---------	---------	---------	---------	---------	---------	---------

Set the threshold to 3 counts (3/16 = 0.1875 g).

Optimal Settings for Motion using Level Detection

For optimal settings for the motion using Level Detection choose the following settings:

- Absolute Logic (THOPT)
- X, Y enabled (YDA, XDA) with Z disabled
- Positive OR Logic (LDPL = 0)
- LDTH: Level Detection Threshold = 0x20 (2g)

1. THOPT=0 Absolute Condition
2. ZDA=1 Disable Z, YDA=0 Enable Y, XDA=0 Enable X

RegisterWrite(0x18,((regs[0x18]&0x87) | 0x20)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	1	0	0	1	1	1
\$18	result	DFBW	0	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

3. Positive OR Logic Clear LDPL

RegisterWrite(0x19,regs[0x19]&0xFE)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	1	1	1	1	1	1	1	0
\$19	result	—	—	—	—	—	DRVO	PDPL	0

4. Set Threshold to 2g

RegisterWrite(0x1A,0x20)

\$1A	LDTH	LDTH[7]	LDTH[6]	LDTH[5]	LDTH[4]	LDTH[3]	LDTH[2]	LDTH[1]	LDTH[0]
\$1A	LDTH	LDTH[7]	LDTH[6]	LDTH[5]	LDTH[4]	LDTH[3]	LDTH[2]	LDTH[1]	LDTH[0]

Set the threshold to 32 counts ($32/16 = 2$ g).

PULSE DETECTION MODE

Pulse detection mode is capable of detecting both motion and freefall. There are timers associated with the pulse detection. The OR logic is used for motion detection where either a single or a double pulse can be detected. For motion detection the logic is set up to detect an event when a programmed “Threshold” has been reached for < Time Window. It is not possible to set up motion detection for Threshold reached for > Time Window. The AND logic is used for freefall detection. In this case when below the set “Threshold” for > Latency Timer the Pulse Detection flag is set.

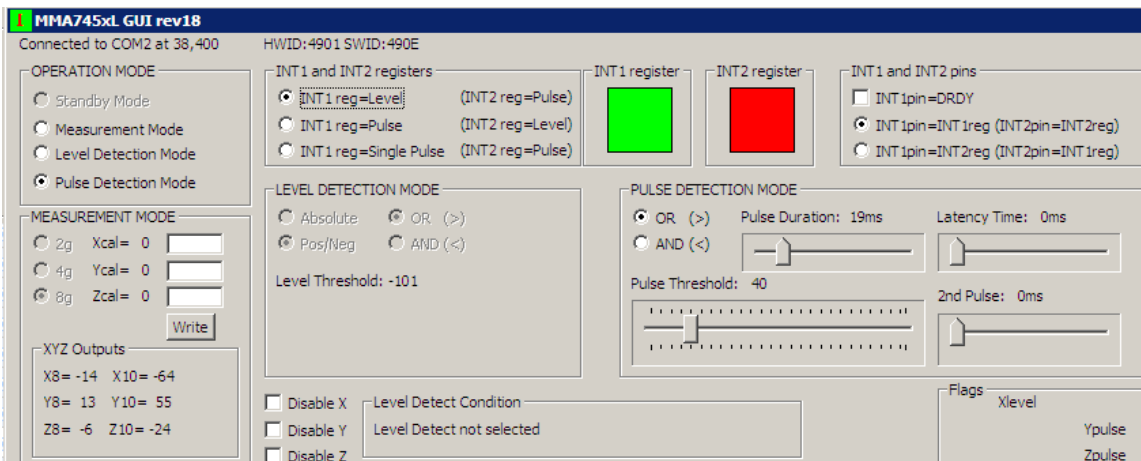


Figure 10. Pulse Mode Settings

The following are all the available settings that can be used in the pulse detection mode.

For the OR logic used for single or double pulse detection, the following register should be set with PDPL = 0.

RegisterWrite(0x19,regs[0x19]&0xFD)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	1	1	1	1	1	1	0	1
\$19	result	—	—	—	—	—	DRVO	0	LDPL

For the AND logic used for pulse freefall detection, the following register should be set with PDPL=1.

RegisterWrite(0x19,regs[0x19]|0x02)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	0	0	0	0	0	0	1	0
\$19	result	—	—	—	—	—	DRVO	1	LDPL

This is an example of how to toggle the XDA bit to enable or disable the X-axis.

RegisterWrite(0x18,regs[0x18]^0x08)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	0	1	0	0	0	0
\$18	result	DFBW	THOPT	ZDA	1	XDA	INTRG[1]	INTRG[0]	INTPIN

This is an example of how to toggle the YDA bit to enable or disable the Y-axis.

RegisterWrite(0x18,regs[0x18]^0x10)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	0	1	0	0	0	0
\$18	result	DFBW	THOPT	ZDA	1	XDA	INTRG[1]	INTRG[0]	INTPIN

This is an example of how to toggle the ZDA bit to enable or disable the Z-axis.

RegisterWrite(0x18,regs[0x18]^0x20)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	0	0	1	0	0	0	0	0
\$18	result	DFBW	THOPT	1	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN

This is the pulse detection threshold value that can be set according to [Table 1](#).

\$1B	PDTH	PDTH[7]	PDTH[6]	PDTH[5]	PDTH[4]	PDTH[3]	PDTH[2]	PDTH[1]	PDTH[0]
------	------	---------	---------	---------	---------	---------	---------	---------	---------

This register defines the pulse width of the first pulse window. The pulse duration increments in ½ ms values, so every count is ½ ms. The total range is from 0 - 127.5 ms.

\$1C	PW	PD[7]	PD [6]	PD [5]	PD [4]	PD [3]	PD [2]	PD [1]	PD [0]
------	----	-------	--------	--------	--------	--------	--------	--------	--------

This register defines the latency time, which is the time in between pulses for double pulse, or the amount of time to trigger a freefall condition. The scale increases from 0 ms - 255 ms 0x00-0xFF. Every count is equal to 1 ms.

\$1D	LT	LT[7]	LT [6]	LT [5]	LT [4]	LT [3]	LT [2]	LT [1]	LT [0]
------	----	-------	--------	--------	--------	--------	--------	--------	--------

This is the timing window for the second pulse when setting up the double pulse condition. The scale is in ms increments from 0 ms - 255 ms 0x00-0xFF.

\$1E	TW	TW[7]	TW [6]	TW [5]	TW [4]	TW [3]	TW [2]	TW [1]	TW [0]
------	----	-------	--------	--------	--------	--------	--------	--------	--------

Optimal Settings for Single Pulse Detection

- Positive OR logic: PDPL = 0
- X, Y, Z enabled
- PDTH = 0x40 (4g)
- PD = 0x10

1. Positive OR Logic PDPL = 0

RegisterWrite(0x19,regs[0x19]&0xFD)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	1	1	1	1	1	1	0	1
\$19	result	—	—	—	—	—	DRVO	0	LDPL

2. X, Y, Z enabled

RegisterWrite1(0x18,regs[0x18]&0x87)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	0	0	0	1	1	1
\$18	result	DFBW	0	0	0	0	INTRG[1]	INTRG[0]	INTPIN

3. PDTH (Pulse Threshold) set to 4g

RegisterWrite(0x1B,0x40)

\$1B	PDTH	PDTH[7]	PDTH[6]	PDTH[5]	PDTH[4]	PDTH[3]	PDTH[2]	PDTH[1]	PDTH[0]
\$1B	result	0	1	0	0	0	0	0	0

4. PD (Pulse Duration) set to 8 ms

RegisterWrite(0x1C,10)

\$1C	PW	PD[7]	PD [6]	PD [5]	PD [4]	PD [3]	PD [2]	PD [1]	PD [0]
\$1C	result	0	0	0	1	0	0	0	0

Optimal Settings for Double Pulse Detection

- Positive OR Logic PDPL = 0
- Z-axis enabled only
- Pulse Threshold set to 4 g
- Pulse Duration = \$3C (60 counts) 30 ms
- Latency Time = 0x5A 90 ms
- 2nd Time Window 0x82 (130 ms)

1. Positive OR Logic Enabled PDPL = 0

RegisterWrite(0x19,regs[0x19]&0xFD)

\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$19	mask	1	1	1	1	1	1	0	1
\$19	result	—	—	—	—	—	DRVO	0	LDPL

2. Z only enabled

RegisterWrite(0x18,(regs[0x18]&0x98)|0x18)

\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$18	mask	1	0	0	1	1	0	0	0
\$18	result	DFBW	0	0	1	1	INTRG[1]	INTRG[0]	INTPIN

3. PDTH (Pulse Threshold) set to 4 g

RegisterWrite(0x1B,0x40)

\$1B	PDTH	PDTH[7]	PDTH[6]	PDTH[5]	PDTH[4]	PDTH[3]	PDTH[2]	PDTH[1]	PDTH[0]
\$1B	result	0	1	0	0	0	0	0	0

4. Pulse Duration for first pulse 30 ms

RegisterWrite(0x1C,0x3C)

\$1C	PW	PD[7]	PD [6]	PD [5]	PD [4]	PD [3]	PD [2]	PD [1]	PD [0]
\$1C	result	0	0	1	1	1	1	0	0

5. Latency time between the pulses 90 ms

RegisterWrite(0x1D,0x5A)

\$1D	LT	LT[7]	LT [6]	LT [5]	LT [4]	LT [3]	LT [2]	LT [1]	LT [0]
\$1D	result	0	1	0	1	1	0	1	0

6. Time Window for Second Pulse = 130 ms

RegisterWrite(0x1E,0x82)

\$1E	TW	TW[7]	TW [6]	TW [5]	TW [4]	TW [3]	TW [2]	TW [1]	TW [0]
\$1E	result	1	0	0	0	0	0	1	0

Table 2. User Registers Summary

Address	Name	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
\$00	XOUTL	XOUT[7]	XOUT[6]	XOUT[5]	XOUT[4]	XOUT[3]	XOUT[2]	XOUT[1]	XOUT[0]
\$01	XOUTH	—	—	—	—	—	—	XOUT[9]	XOUT[8]
\$02	YOUTL	YOUT[7]	YOUT[6]	YOUT[5]	YOUT[4]	YOUT[3]	YOUT[2]	YOUT[1]	YOUT[0]
\$03	YOUTH	—	—	—	—	—	—	YOUT[9]	YOUT[8]
\$04	ZOUTL	ZOUT[7]	ZOUT[6]	ZOUT[5]	ZOUT[4]	ZOUT[3]	ZOUT[2]	ZOUT[1]	ZOUT[0]
\$05	ZOUTH	—	—	—	—	—	—	ZOUT[9]	ZOUT[8]
\$06	XOUT8	XOUT[7]	XOUT[6]	XOUT[5]	XOUT[4]	XOUT[3]	XOUT[2]	XOUT[1]	XOUT[0]
\$07	YOUT8	YOUT[7]	YOUT[6]	YOUT[5]	YOUT[4]	YOUT[3]	YOUT[2]	YOUT[1]	YOUT[0]
\$08	ZOUT8	ZOUT[7]	ZOUT[6]	ZOUT[5]	ZOUT[4]	ZOUT[3]	ZOUT[2]	ZOUT[1]	ZOUT[0]
\$09	STATUS	—	—	—	—	—	PERR	DOVR	DRDY
\$0A	DETSRC	LDX	LDY	LDZ	PDX	PDY	PDZ	INT2	INT1
\$0B	TOUT	TMP[7]	TMP[6]	TMP[5]	TMP[4]	TMP[3]	TMP[2]	TMP[1]	TMP[0]
\$0C	—	—	—	—	—	—	—	—	—
\$0D	I2CAD	I2CDIS	DAD[6]	DAD[5]	DAD[4]	DAD[3]	DAD[2]	DAD[1]	DAD[0]
\$0E	USRINF	UI[7]	UI[6]	UI[5]	UI[4]	UI[3]	UI[2]	UI[1]	UI[0]
\$0F	WHOAM	ID[7]	ID[6]	ID[5]	ID[4]	ID[3]	ID[2]	ID[1]	ID[0]
\$10	XOFFL	XOFF[7]	XOFF[6]	XOFF[5]	XOFF[4]	XOFF[3]	XOFF[2]	XOFF[1]	XOFF[0]
\$11	XOFFH	—	—	—	—	—	XOFF[10]	XOFF[9]	XOFF[8]
\$12	YOFFL	YOFF[7]	YOFF[6]	YOFF[5]	YOFF[4]	YOFF[3]	YOFF[2]	YOFF[1]	YOFF[0]
\$13	YOFFH	—	—	—	—	—	YOFF[10]	YOFF[9]	YOFF[8]
\$14	ZOFFL	ZOFF[7]	ZOFF[6]	ZOFF[5]	ZOFF[4]	ZOFF[3]	ZOFF[2]	ZOFF[1]	ZOFF[0]
\$15	ZOFFH	—	—	—	—	—	ZOFF[10]	ZOFF[9]	ZOFF[8]
\$16	MCTL	LPEN	DRPD	SPI3W	STON	GLVL[1]	GLVL[0]	MOD[[1]]	MOD[0]
\$17	INTRST	—	—	—	—	—	—	CLRINT2	CLRINT1
\$18	CTL1	DFBW	THOPT	ZDA	YDA	XDA	INTRG[1]	INTRG[0]	INTPIN
\$19	CTL2	—	—	—	—	—	DRVO	PDPL	LDPL
\$1A	LDTH	LDTH[7]	LDTH[6]	LDTH[5]	LDTH[4]	LDTH[3]	LDTH[2]	LDTH[1]	LDTH[0]
\$1B	PDTH	PDTH[7]	PDTH[6]	PDTH[5]	PDTH[4]	PDTH[3]	PDTH[2]	PDTH[1]	PDTH[0]
\$1C	PW	PD[7]	PD [6]	PD [5]	PD [4]	PD [3]	PD [2]	PD [1]	PD [0]
\$1D	LT	LT[7]	LT [6]	LT [5]	LT [4]	LT [3]	LT [2]	LT [1]	LT [0]
\$1E	TW	TW[7]	TW [6]	TW [5]	TW [4]	TW [3]	TW [2]	TW [1]	TW [0]
\$1F	—	—	—	—	—	—	—	—	—

NOTES:

1. <http://www.esacademy.com/faq/i2c/general/i2cpseud.htm>



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