

GABLE IMU ONE SERIES DATASHEET

SE1 | SE2 | SE3 | SE5 | SE7

Document information

Name	Date	Revision	Source
ONE-SERIES Datasheet	14-04-2022	C	www.gable-imu.nl

Revision History

Revision number	Date	By	Description
A	08-01-2021	HCV	First release
B	10-06-2021	HCV	Updated figures and added order code description.
C	05-05-2022	SMB	Product name change and info for housed version

Table of Contents

Table of Contents	3
List of Tables.....	5
List of Figures	6
1 General information	7
1.1 Remarks on the documentation	7
1.1.1 Target audience.....	7
1.1.2 Disclaimer	7
1.1.3 Trademarks.....	7
1.1.4 Copyright.....	7
1.2 Safety instructions	7
1.2.1 Safety regulations.....	7
1.2.2 Exclusion of liability.....	8
1.2.3 Personnel qualification.....	8
1.2.4 Description of symbols	8
1.3 Ordering information.....	8
1.4 ONE-SERIES architecture	9
1.5 ONE-SERIES variants	9
1.5.1 SE1.....	9
1.5.2 SE2.....	9
1.5.3 SE3.....	10
1.5.4 SE5.....	10
1.5.5 SE7.....	10
2 ONE-SERIES specifications	11
2.1 XSENS® MTi-1 series performance specifications.....	11
2.2 Individual component specifications	11
3 Wiring of the ONE-SERIES.....	13
3.1 General wiring information	13
3.1.1 Cabling conductor losses.....	13
3.2 EtherCAT® and power connection.....	13
3.2.1 Mating connectors for OEM-version.....	14
3.2.2 Mating connectors for HSD-version	14
3.2.3 Pin assignment	14
3.2.4 Mating connectors	15
3.3 LED indicators	15
3.4 GNSS connection (if applicable).....	16
3.4.1 HSD (Housed) version and GNSS	16
3.4.2 OEM (PCB) version and GNSS.....	16
4 Mounting ONE-SERIES	17
4.1 Mounting of housed version (HSD)	17

4.2	Mounting of PCB version (OEM).....	18
4.3	Cable assemblies and accessories	18
5	Electrical and mechanical specifications	20
5.1	Supply voltage and power consumption	20
5.2	Housed variants (HSD).....	20
6	Configuration and settings	21
6.1	PDO mappings	21
6.2	Sending commands to the ONE-SERIES for configuration	22
6.3	Filter profiles.....	23
7	Packaging information.....	25
7.1	Package content	25

List of Tables

Table 1: Ordering code ONE-SERIES.....	8
Table 2: Orientation performance specifications.....	11
Table 3: ONE-SERIES gyroscope specifications.....	11
Table 4: ONE-SERIES accelerometer specifications.....	11
Table 5: ONE-SERIES magnetometer specifications.....	11
Table 6: ONE-SERIES orthogonality specifications	12
Table 7: EtherCAT® pin assignment	15
Table 8: Power pin assignment	15
Table 9: Mating connectors OEM-version.....	15
Table 10: Mating connectors HSD-version.....	15
Table 11: ONE-SERIES LED IDs and states	15
Table 12: Connectors and accessories	18
Table 13: Supply voltage range ONE-SERIES	20
Table 14: Power consumption ONE-SERIES	20
Table 15: PDO mappings	21
Table 16: Example command to change filter setting.....	22
Table 17: Complete Xbus message to change filter type to 'General/50'.....	23
Table 18: Example Command to get both HR (High Rate) PDOs only.....	23
Table 19: Filter Profiles for ONE-SERIES-2 and ONE-SERIES-3.....	23
Table 20: Package contents.....	25

List of Figures

Figure 1: ONE-SERIES Architecture.....	9
Figure 2: Voltage drop vs conductor cross sections.....	13
Figure 3: Connectors on front side (PCB-version).....	14
Figure 4: Connectors on front side (HSD-version).....	14
Figure 5: Connector pin locations HSD-version.....	14
Figure 6: ONE-SERIES top view showing LED IDs and location.....	16
Figure 7: ONE-SERIES HSD drawing.....	17
Figure 8: ONE-SERIES OEM drawing.....	18
Figure 9: GradConn SMA cable assembly.....	19
Figure 10: Norcomp Vulcon series M5 connectors.....	19
Figure 11: multi-band active GNSS antenna.....	19

1 General information

This document provides information on the technical details and usage of the Gable-IMU™ ONE-SERIES. The ONE-SERIES are fully functional, easy to build-in Inertial Measurement Units (IMUs) which can be directly connected to or installed into an existing EtherCAT® network. ONE-SERIES are available in a housed version (HSD) or as a small footprint PCB-version (OEM). The Gable-IMU™ ONE-SERIES can also be easily integrated into an existing EtherCAT P® network. Please consult Gable Systems for advice and/or support on these topics.

Gable Systems B.V.

Website: www.gable-imu.nl
www.gablesystems.com
Email: info@gablesystems.com

1.1 Remarks on the documentation

1.1.1 Target audience

This description is only intended for the use of trained specialists in control and automation engineering who are familiar with the applicable national standards. It is essential that the documentation and the following notes and explanations are followed when installing and commissioning ONE-SERIES.

It is the duty of the technical personnel to use the documentation published at the respective time of each installation and commissioning.

The responsible staff must ensure that the application or use of the devices described satisfy all the requirements for safety, including all the relevant laws, regulations, guidelines and standards.

1.1.2 Disclaimer

The documentation has been prepared with care. The devices described are, however, constantly under development.

Gable Systems reserves the right to revise and change the documentation at any point in time and without prior announcement. No claims for the modification of products that have already been supplied may be made on the basis of the data, diagrams and descriptions in this documentation.

1.1.3 Trademarks

Gable-IMU™ is a trademark of Gable Systems B.V.

EtherCAT® is a registered trademark and patented technology, licensed by Beckhoff Automation GmbH, Germany.

EtherCAT P® is a registered trademark and patented technology, licensed by Beckhoff Automation GmbH, Germany.

XSENS® is a registered trademark of XSENS Technologies B.V. and/or its parent, subsidiaries and/or affiliates in The Netherlands, the USA and/or other countries.

1.1.4 Copyright

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1.2 Safety instructions

1.2.1 Safety regulations

The following safety instructions should be read and noted! Specific safety instructions can be found in subsections throughout this document.

1.2.2 Exclusion of liability

All the components are supplied in specific hardware and software configurations appropriate for the application. Hardware or software configuration modifications other than those described in this document are not permitted, and nullify the liability Gable Systems B.V.

1.2.3 Personnel qualification

This description is only intended for trained specialists in control and automation familiar with the applicable national standards.

1.2.4 Description of symbols

In this documentation the following symbols are used with an accompanying safety instruction or note. Make sure to carefully read the instructions!

	INFORMATION This symbol indicates information that contributes to better understanding.
	CAUTION Makes the user alert to actions that could cause equipment damage, resulting in the equipment becoming unsafe, or to actions or operations that could have undesirable consequences.
	WARNING Makes the user aware of potentially hazardous events related to the ONE-SERIES that may result in injury of persons interacting with the device.

1.3 Ordering information

When ordering Gable-IMU™ 600 SERIES, the following order code must be used. See Table 1
You can also use our online product finder at www.gable-imu.nl to find the product that suits your demand.
Please consult our sales department for production quantities, graduated prices and custom solutions.

Table 1: Ordering code ONE-SERIES

SE2	-	HSD	-	VE
VARIANT:		FORM:		INTERFACE:
SE1		HSD = Housed version		VE = Vertical connectors
SE2		OEM = PCB version		RA = Right angle connectors
SE3				Blank = in case of HSD version
SE5				
SE7				

1.4 ONE-SERIES architecture

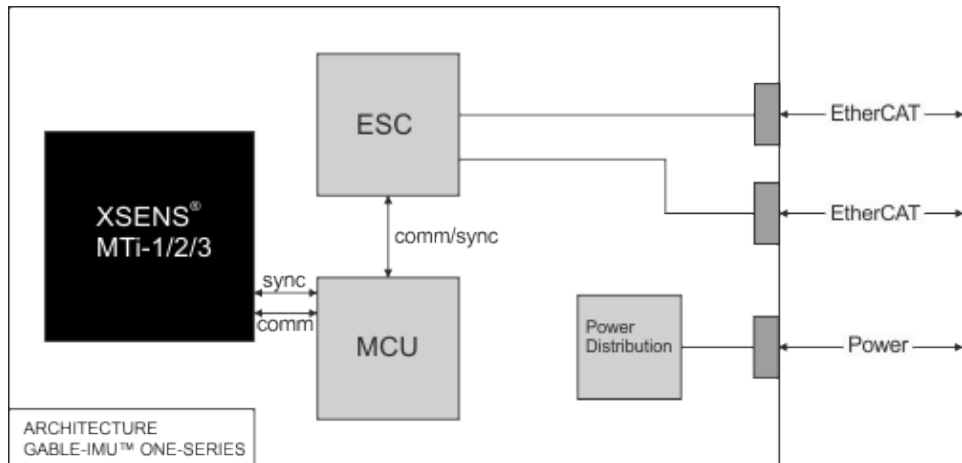


Figure 1: ONE-SERIES Architecture

The schematic representation in Figure 1: ONE-SERIES Architecture shows the architecture of the ONE-SERIES. The ONE-SERIES contains an XSENS^{®1} MTi-1 series IMU with a 3-axis gyroscope, 3-axis accelerometer and 3-axis magnetometer. The MTi-1 series IMU is integrated in a fully functional EtherCAT slave which coordinates the communication between the EtherCAT network and the MTi-1 series IMU. This is realized using a state of art EtherCAT Slave Controller (ESC) and an industrial grade microcontroller (MCU).

Optimally estimated orientation, position and velocity are available with output data rates up to 100Hz. Gyroscope and acceleration data are available at data rates up to 800 and 1000 Hz respectively.

1.5 ONE-SERIES variants

The ONE-SERIES is available in several EtherCAT[®] ready variants:

- SE1 Inertial Measurement Unit (IMU)
- SE2 IMU + Vertical Reference Unit (VRU)
- SE3 IMU + VRU + Altitude and Heading Reference System (AHRS)
- SE5 Global Navigation Satellite System (GNSS)
- SE7 IMU + VRU+ AHRS+GNSS + Inertial Navigation System (INS)

Depending on your ONE-SERIES variant, output data can be different which is explained in the following sections. The specific variant can be found on the label placed on the housing or PCB.

1.5.1 SE1

The SE1 is an IMU that outputs calibrated 3D rate of turn, 3D acceleration and 3D magnetic field. The SE1 also outputs coning and sculling compensated orientation increments and velocity increments (Δq and Δv). Advantages over a simple gyroscope-accelerometer combo-sensor are the inclusion of synchronized magnetic field, on-board signal processing and the easy-to-use synchronization and communication protocol. The signal processing pipeline and the suite of output options allow access to the highest possible accuracy at any output data rate up to 800 Hz. Moreover, the testing and calibration is already performed by XSENS[®] and results in a robust and reliable sensor module, which enables a short time to market for the users.

Source: XSENS[®] MTi-1 series Datasheet

1.5.2 SE2

The SE2 is a 3D VRU. On top of the functionality of the SE1, its algorithm computes 3D orientation data with respect to a gravity referenced frame: drift-free roll, pitch and unreferenced yaw. Although the yaw is unreferenced, it is superior to only gyroscope integration as a result of advanced on-board sensor fusion. The 3D acceleration is also available as so-called free acceleration, which has the local-gravity subtracted. The drift in

¹ <https://www.xsens.com/>

unreferenced heading can be limited by using the Active Heading Stabilization (AHS) functionality. The raw sensor signals are combined and processed at a high frequency to produce a real-time data stream with device's 3D orientation (roll, pitch and yaw) up to 100 Hz.

Source: XSENS® MTi-1 series Datasheet

1.5.3 SE3

The SE3 supports all features of the SE1 and SE2, and in addition is a full magnetometer-enhanced AHRS. In addition to the roll and pitch, it outputs a true magnetic North referenced yaw (heading) and calibrated sensors data: 3D acceleration, 3D rate of turn, 3D orientation and velocity increments (Δq and Δv) and 3D earth-magnetic field data. The raw sensor signals are combined and processed at a high frequency to produce a real-time data stream with device's 3D orientation (roll, pitch and yaw) up to 400 Hz.

Source: XSENS® MTi-1 series Datasheet

1.5.4 SE5

The SE5 enables a low-cost solution for an EtherCAT® based Global Navigation Satellite System (GNSS). This variant of our ONE-SERIES does not contain an IMU and therefore can only be used for GNSS measurements. Note, it does not support GEO-fencing.

1.5.5 SE7

The SE7 supports all features of the SE1, SE2 and SE3, and in addition the SE7 combines orientation data with position data supplied by an internal GNSS receiver. The SE7 represents the highest standard in GNSS/INS. This all-in-one navigation solution is lightweight and robust, as well as cost-effective and easy to integrate.

Source: XSENS® MTi-1 series Datasheet

2 ONE-SERIES specifications

This section presents the performance and the sensor component specifications for the Gable-IMU™ ONE-SERIES, based on the performance of the XSENS® MTi-1 series IMU.

2.1 XSENS® MTi-1 series performance specifications

Each XSENS® MTi-1 series IMU, inside the Gable IMU ONE-SERIES, has passed the XSENS® calibration process individually. The XSENS® calibration procedure calibrates for many parameters, including bias (offset), alignment of the sensors with respect to the PCB and to each other, and gain (scale factor). All calibration values are temperature dependent and temperature calibrated. The calibration values are stored in the non-volatile memory of the XSENS® MTi-6x0.

In addition, some calibration parameters are continuously improved and/or re-estimated through the on-board sensor fusion algorithms during normal operation.

Source: XSENS® MTi-1 series Datasheet

Table 2: Orientation performance specifications

Parameter	Condition	SE1 IMU	SE2 VRU	SE3 AHRS
Roll/Pitch	Static	N/A	0.5°	0.5°
	Dynamic	N/A	0.8°	0.8°
Yaw	Dynamic	N/A	Unreferenced	2°

All above specifications are RMS values based on typical application scenarios.

2.2 Individual component specifications

Table 3: ONE-SERIES gyroscope specifications

Gyroscope Specifications ²	Unit	Value
Standard full range	[°/s]	±2000
In-run bias stability	[°/h]	10
Bandwidth (-3dB)	[Hz]	255
Noise density	[°/s/√Hz]	0.007
g-sensitivity (calibrated)	[°/s/g]	0.001
Non-linearity	[%FS]	0.1
Scale Factor variation	[%]	0.5(typical) 1.5 (over life)

Table 4: ONE-SERIES accelerometer specifications

Accelerometer ²	Unit	Value
Standard full range	[g]	±16
In-run bias stability	[mg]	0.03
Bandwidth (-3dB)	[Hz]	324 (Z direction 262)
Noise density	[μg/√Hz]	120
Non-linearity	[%FS]	0.5

Table 5: ONE-SERIES magnetometer specifications

Magnetometer ²	Unit	Value
Standard full range	[G]	±8
Non-linearity	[%]	0.2
Total RMS noise	[mG]	0.5
Resolution	[mG]	0.25

² As XSENS® continues to update the MTi-600 series, these specifications are subject to change

Table 6: ONE-SERIES orthogonality specifications

Parameter ²	Unit	Value
Non-orthogonality (accelerometer)	[°]	0.05
Non-orthogonality (gyroscope)	[°]	0.05
Non-orthogonality (magnetometer)	[°]	0.05
Alignment (gyro to acc)	[°]	0.05
Alignment (mag to acc)	[°]	0.1
Alignment of acc to the MTi board	[°]	0.2

3 Wiring of the ONE-SERIES

This section describes the mounting and wiring options for the ONE-SERIES.

3.1 General wiring information

3.1.1 Cabling conductor losses

Power cables should be designed in such a way that their length prevents a voltage drop which is too large for the ONE-SERIES to still operate reliably. Current draw from other nodes connected to the OUT port of the ONE-SERIES also need to be taken into account. At a control voltage U_s of 24V, reliable operation cannot be guaranteed anymore when the voltage drop exceeds 12 V.

Figure 2 shows the different cable lengths and their relation to the voltage drop at a 3A current draw.

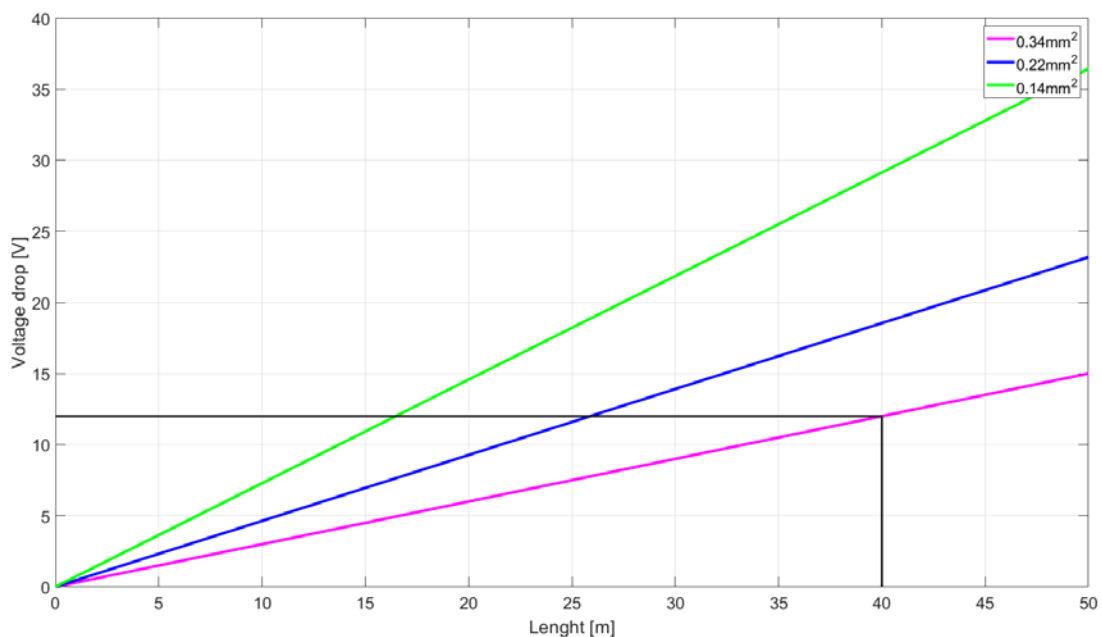


Figure 2: Voltage drop vs conductor cross sections

Example: A power cable of 40m with (copper) conductor cross section of 0.34mm² has a voltage drop of ~12V @ 3A.

3.2 EtherCAT® and power connection



CAUTION | Risk of damage to the device!

Bring the EtherCAT® system into a safe, powered down state before starting installation, disassembly or wiring of the ONE-SERIES.

3.2.1 Mating connectors for OEM-version



Figure 3: Connectors on front side (PCB-version)

The 3 connectors shown in Figure 3 are to be used for power and EtherCAT®. The leftmost connector is the power connector (3 pins), whereas the middle and rightmost connectors (4 pins) are EtherCAT® IN and EtherCAT® OUT respectively.

3.2.2 Mating connectors for HSD-version



Figure 4: Connectors on front side (HSD-version)

The 3 connectors shown in Figure 4 are to be used for power and EtherCAT®. The leftmost connector is the power connector (2 pins), whereas the middle and rightmost connectors (4 pins) are EtherCAT® IN and EtherCAT® OUT respectively.

3.2.3 Pin assignment

For the OEM version, the location of pin number 1 can be found in Figure 8. The pin location for the HSD-version can be found in Figure 5.

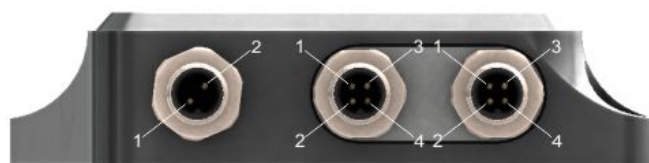


Figure 5: Connector pin locations HSD-version

Table 7: EtherCAT® pin assignment

Pin	Signal	Voltage
1	Rx+	-
2	Rx-	-
3	Tx+	-
4	Tx-	-
Housing	None	-

Table 8: Power pin assignment

Pin	Signal	Voltage
1	Vs	5 - 24V
2	PR	0V (GND)
3	N.C.	-
Housing	None	-

3.2.4 Mating connectors

The following connectors from Molex^{®3} can be used to connect to the ONE-SERIES to a power supply and EtherCAT® network. See Table 9 in case of the OEM-version and Table 10 in case of the HSD version.

Table 9: Mating connectors OEM-version

Connector	Molex® Number	Type	Amount
Pico-Clasp Female plug	5019390300	Power connector	1
Pico-Clasp Female plug	5019390400	EtherCAT connector	2

Table 10: Mating connectors HSD-version

Connector	Number	Manufacturer	Remark
Male connector M5 Vulcon™ series 2P	851-002-103R001	NORCOMP	Solder pin assembly, IP67
Male connector M5 Vulcon™ series 4P	851-004-103R001	NORCOMP	Solder pin assembly, IP67

3.3 LED indicators

The ONE-SERIES has 5 LEDs to inform the user about the status of the device. In the following table the different LEDs and their function are explained. The LED locations of the OEM-version are shown in Figure 6. The LED locations of the HSD-version are labelled on the casing, see Figure 4.

Table 11: ONE-SERIES LED IDs and states

LED	Color	State
IN	Green	Flashing: EtherCAT communication
OUT	Green	Flashing: EtherCAT communication
PWR	Green	On: Power ok
RUN	Green	Off: Device in INIT/unknown state On: Device in Run mode Flashing: Device in SAFEOP or PREOP state
ERR	Red	Off: ok Flashing: Internal communication error

³ <https://www.molex.com>

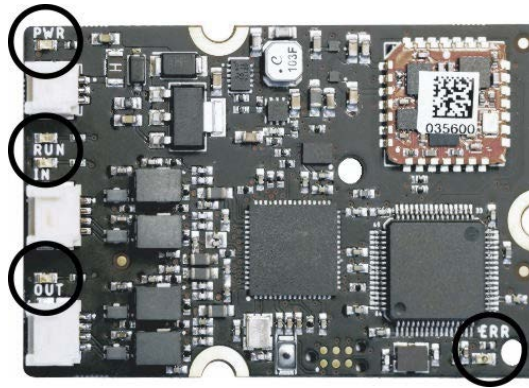


Figure 6: ONE-SERIES top view showing LED IDs and location

3.4 GNSS connection (if applicable)

3.4.1 HSD (Housed) version and GNSS

If applicable, any standard SMA mating connector can be used to attach to the internal GNSS receiver of the SE5 and SE7 HSD versions.

3.4.2 OEM (PCB) version and GNSS

On request, a cable assembly with PCB to SMA panel mount connector, Figure 9, is available for the SE5 and SE7 OEM versions. Any standard SMA mating connector can be used to connect to this SMA panel mount connector.

4 Mounting ONE-SERIES



CAUTION | Risk of mechanical damage to the device!

Follow the mounting instructions and recommendations to prevent damage and undesirable effects.

4.1 Mounting of housed version (HSD)

The housed variant of the ONE-SERIES is supplied with two hexagon head bolts DIN 916 A2 M2.5x5 (Allen key 2) which need to be used to fix the sensor to another system or device. The dimensions and location of the mounting holes can be found in Figure 7.



CAUTION | Risk of mechanical damage to the device!

Tighten the M2.5 bolts with a maximum tightening torque of 0.4 Nm.

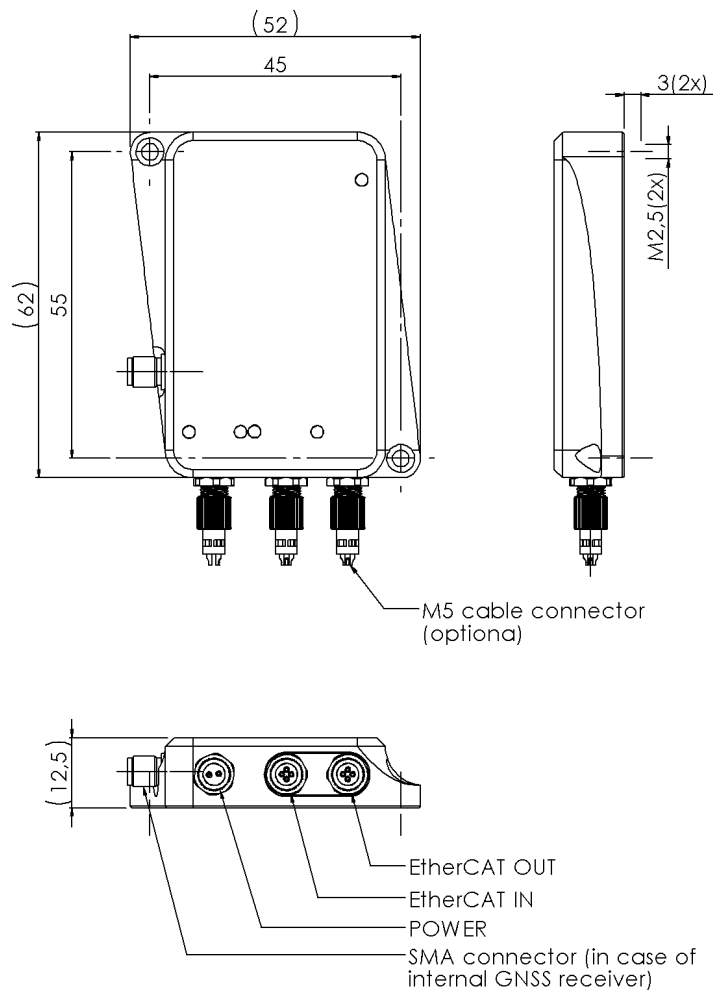


Figure 7: ONE-SERIES HSD drawing

4.2 Mounting of PCB version (OEM)



CAUTION | Risk of mechanical damage to the device!

It is recommended to tighten the PCB fasteners hand tight (0.2 Nm) to prevent damage to the PCB.



CAUTION | Risk of mechanical damage to the device!

A static free-workstation must be used when handling the ONE-SERIES OEM .

The PCB version of the ONE-SERIES can be mounted according to the dimensions per drawing of Figure 8 and the following instructions:

- Ensure a static free-workstation before unpacking and handling the PCB and electronic components. A electro static discharge (ESD) can damage electronic components.
- The ONE-SERIES OEM should be mounted to another system or device using three non-ferro M3 fasteners with a head diameter less than or equal to 5.6 mm.
- The dimensions and location of the mounting holes can be found in Figure 8.
- On request, Molex® Pico-Clasp to Norcomp M5 Panel mount connectors can be provided. Please install the panel mount connectors according to Norcomp specifications part number 851-004-103R001.
- On request, a GradConn IP67 SMA cable assembly can be provided, Figure 9, to connect to the internal GNSS receiver of variants SE5 and SE7. The assembly consists out of a SMA panel mount connector with a 200mm cable and I-PEX MHF 4L LK plug that can be connected to the PCB. Please consult the manufacturer information for mounting instructions of the SMA panel connector. Part number CAB442RF.

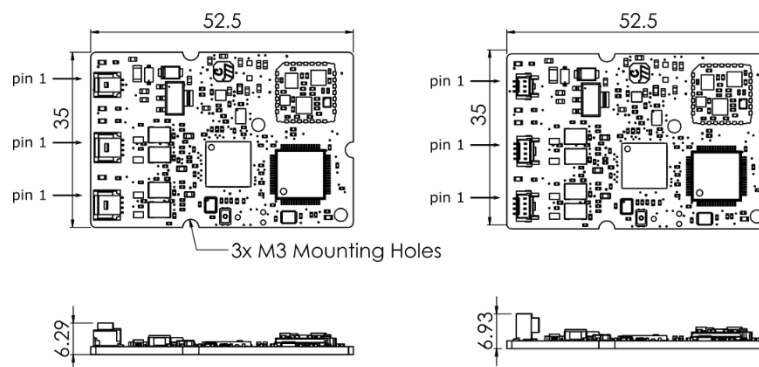


Figure 8: ONE-SERIES OEM drawing

4.3 Cable assemblies and accessories

The following cable assemblies and accessories are recommended and can be ordered directly from the specified manufacturer and/or through Gable Systems BV see Table 12.

Table 12: Connectors and accessories

Item	Manufact.	Number	Required SE1/2/3 OEM	Required SE1/2/3 HSD	Required SE5/7 OEM	Required SE5/7 HSD
Molex® Pico-Clasp to M5 panel mount connector (signal cable assembly)	Gable Systems	4pPic-4pM5pan	2		2	

<i>Molex® Pico-Clasp to M5 panel mount connector (power cable assembly)</i>	Gable Systems	3pPic-2pM5pan	1		1	
<i>M5 mating connector to RJ45 (signal cable assembly 500mm)</i>	Gable Systems	4pM5plug-RJ45	2	2	2	2
<i>M5 mating connector with flying lead (power cable assembly 500mm), Figure 10</i>	Gable Systems	2pM5plug	1	1	1	1
<i>PCB to SMA panel mount cable assembly 200mm, Figure 9</i>	GradConn	CAB442RF			1	
<i>Multi-band active GNSS antenna IP67 with SMA connector, Figure 11</i>	Ublox	ANN-MB-00-00			1	1



Figure 9: GradConn SMA cable assembly



Figure 10: Norcomp Vulcon series M5 connectors



Figure 11: multi-band active GNSS antenna

5 Electrical and mechanical specifications

This section describes the electrical operating conditions of the ONE-SERIES.

5.1 Supply voltage and power consumption

Power is supplied to the fieldbus, the processor logic, the inputs and the sensors from the power connector. The permissible input voltage range is shown in Table 13. The ONE-SERIES are over- and reverse voltage protected.

Table 13: Supply voltage range ONE-SERIES

Symbol	Minimal	Typical	Maximal	Unit
Us	5	24	26	V

Table 14: Power consumption ONE-SERIES

Variant	Typical	Unit	Description
SE1-SE2-SE3	1 ⁴	W	At 24V



CAUTION | Risk of mechanical damage to the device!

It is highly recommended to prevent hot connecting the ONE-SERIES to a live power supply. First install all cabling in a proper manner and according to local regulations before powering up the power supply.

5.2 Housed variants (HSD)

The ONE-SERIES has a two part robust machined housing which is completely sealed to achieve an ingress protection (IP) of 67.

Note: Warranty rights will be lost immediately after attempts to open the housing or otherwise tamper with it.

⁴ Preliminary value

6 Configuration and settings

The EtherCAT® communication between the ONE-SERIES and the EtherCAT® master goes through its PDO's (No CoE parameters).

6.1 PDO mappings

The PDO mappings for each ONE-SERIES can be found in Table 15.

Table 15: PDO mappings

PDO	Data format	Usage
Quaternions⁵	Structure with {qw, qx, qy, qz} each field being a REAL.	The <i>Quaternion fields</i> can be mapped to EtherCAT master inputs of matching data format.
Euler Angles⁵	Structure with {ex, ey, ez} each field being a REAL.	The <i>Euler Angles</i> can be mapped to EtherCAT master inputs of matching data format.
Gyroscope	Structure with {gx, gy, gz} each field being a REAL.	The <i>Gyroscope fields</i> can be mapped to EtherCAT master inputs of matching data format.
Acceleration	Structure with {ax, ay, az} each field being a REAL.	The <i>Acceleration fields</i> can be mapped to EtherCAT master inputs of matching data format.
MagneticField	Structure with { magX, magY, magZ} each field being a REAL.	The <i>MagneticField fields</i> can be mapped to EtherCAT master inputs of matching data format.
GyroscopeHR	Structure with { gxHR, gyHR, gzHR} each field being a REAL.	The <i>GyroscopeHR fields</i> can be mapped to EtherCAT master inputs of matching data format. These signals are available at rates up to 1000Hz (not synchronized to the internal XSENS® clock). See Table 16 and 22 MT_Low-Level_Documentation.pdf.
AccelerationHR	Structure with { axHR, ayHR, azHR} each field being a REAL.	The <i>AccelerationHR fields</i> can be mapped to EtherCAT master inputs of matching data format. These signals are available at rates up to 800Hz (not synchronized to the internal XSENS® clock). See Table 16 and 22 MT_Low-Level_Documentation.pdf.
Status	Structure with: { CRC errors – UDINT, Wakeup – BIT, Command_Response – USINT, Communication_Errors - UDINT}	The <i>Status fields</i> can be mapped to EtherCAT master inputs of matching data format. <i>CRC errors</i> : Number of CRC errors due to invalid XBus ⁶ frame CRC. <i>Wakeup</i> : Sensor is ready to use <i>Command_Response</i> : Response message after sending an XBus message to the XSENS® IMU <i>Communication_Errors</i> : Number of communication error(s) between the XSENS® IMU and the microcontroller.
Info	Structure with: { Baudrate – USINT, Firmware major version – SINT, Hardware major version – SINT, Filter_Profile – USINT, Device_ID – UDINT}	The <i>Status fields</i> can be mapped to EtherCAT master inputs of matching data format. <i>Baudrate</i> : Baudrate between XSENS® Mti-1 and microcontroller. <i>Firmware major version</i> : Major firmware version of the XSENS® Mti-1

⁵ Not available for the IMU Module-1

⁶ XBus: XSENS® digital data bus system.

Command	Field being USINT.	<p><i>Hardware major version</i>: Major hardware version of the XSENS® Mti-1</p> <p><i>Filter_Profile</i>: Active filter profile</p> <p><i>Device_ID</i>: XSENS® aMTi-1 Device ID</p> <p>The <i>Command</i> field is part of a XBus message used to configure the XSENS® IMU, and can be mapped to an EtherCAT master output with matching data format. The following preconfigured messages are defined:</p> <ul style="list-style-type: none"> 0 – Default return value 1 – Custom/Xbus message 2 – Config mode 3 – Measurement mode 4 – Software Reset 5 – Alignment Reset (Code 0x0004, see <i>MT_LowLevelCommunicationProtocol_Documentation.pdf</i>) 6 – SetFilter
Data	Array with entries being USINT.	The <i>Data</i> Array is part of a XBus message used to configure the XSENS® IMU, and can be mapped to EtherCAT master outputs with matching data format.
MID	Field being USINT.	The <i>MID (Message ID)</i> field is part of a XBus message used to configure the XSENS® IMU, and can be mapped to an EtherCAT master output with matching data format.
DataLenght	Field being USINT.	The <i>DataLenght</i> field is part of a XBus message used to configure the XSENS® IMU, and can be mapped to an EtherCAT master output with matching data format.

6.2 Sending commands to the ONE-SERIES for configuration

This section describes the commands which need to be send over EtherCAT® to change for example the filter settings or output data for the ONE-SERIES. All values from the XSENS® low level communication manual for MID, Data[] and DataLenght should be converted from Hexadecimal to decimal before sending.

Table 16: Example command to change filter setting

Step	EtherCAT® Message	Result	Comment
Go to config mode	Send: Command = 2	Acceleration, Gyroscope etc. will stop being updated (freeze)	-
Set Filter ⁷	Send in one cycle: Command = 1 MID = 100 Data[1] = 0 Data[2] = 50, 51, 52, 53 or 54 (See filter options Mti-1, page 48 low level communication protocol) DataLenght = 2	Status.Command_Response should show '101'	-

⁷ The command to change for example the filter settings need to be send in one EtherCAT frame.

Reset sensor	Send: Command = 3	Info.Filter_Profile should show the new filter type (50, 51 ,52 ,53 or 54)	Sensor is being reset and starts in measurement mode again.
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An XSENS® XBus message also consist of header bytes (Preamble and BID) and a CRC byte, but these will be generated internally by the ONE-SERIES and should not be included in any message. Only the light blue fields (see Table 17) should be send combined with the correct *Command* (see Table 16).

Table 17: Complete Xbus message to change filter type to 'General/50'

Preamble	BID	MID	DataLength	Data	CRC
0xFA	0xFF	0x64 (Decimal 100)	0x02 (Decimal 2)	0x32 (Decimal 50)	0x69

The default configuration of the ONE-SERIES does not include the *GyroscopeHR* and *AccelerationHR* PDOs. This is because the time synchronized and processed data at 100Hz is most commonly used. These PDOs can be activated separately by sending the correct command (see Table 18). To have both the processed data and the *GyroscopeHR* and *AccelerationHR* PDOs a message similar to the message in Table 15 needs to be send including the other PDO identifiers (MT_LowLevelCommunicationProtocol_Documentation.pdf).

Table 18: Example Command to get both HR (High Rate) PDOs only

Step	EtherCAT® Message	Result	Comment
Go to config mode	Send: Command = 2	Acceleration, Gyroscope etc. will stop being updated (freeze)	-
Set PDOs ⁸	Send in one cycle: Command = 1 MID = 192 Data[0.....7] = [128, 64, 0, 0, 64, 64, 0, 0] DataLenght = 8	Status.Command_Response should show '193' as a response to MID '192' .	-
Go to measurement mode	Send: Command = 3	Only the <i>GyroscopeHR</i> and <i>AccelerationHR</i> PDOs are active.	Sensor is being reset and starts in measurement mode again.

6.3 Filter profiles

SE2 and SE3 can be used with several filter settings depending on the environment and application. TABLE 19 provides guidelines on selecting appropriate filter settings for your specific application or use case.

Table 19: Filter Profiles for ONE-SERIES-2 and ONE-SERIES-3

Name	Number	Device	Typical applications
General	50	SE3	Suitable for most applications.
High magnetometer dependence	51	SE3	Heading corrections strongly rely on the magnetic field measured and should be used when the magnetic field is homogeneous.
Dynamic	52	SE3	Assumes that the motion is highly dynamic.
North referenced	53	SE3	Assumes a good Magnetic Field Mapping (MFM) and a homogeneous magnetic field. Given stable initialization procedures and observability of the gyro bias, after dynamics, this filter profile will trust more on the gyro

⁸ The command to change for example the configuration settings need to be send in one EtherCAT® frame.

VRU general	54	SE3 SE2	<p>solution and the heading will slowly converge to the disturbed magnetic field over the course of time. Magnetometers are not used to determine heading. Consider using this filter in environments that have a heavily disturbed magnetic field or when the application only requires unreferenced heading (See also section 4.3 of the XSENS® MTi-1 series datasheet).</p>
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An example for setting the filter to 'Responsive/VRU' can be found in section 0.

7 Packaging information

The Gable-IMU™ ONE-SERIES are packaged and shipped as single or multiple units.

7.1 Package content

The following contents are shipped (content quantities are for a single unit)

Table 20: Package contents

Variant	Content	Qty	Information
SE1/SE2/SE3-OEM-VE/RA	– ONE-SERIES PCB Assembly (Pre-installed vertical or right-angle connectors)	1	4.3 Cable assemblies and accessories
	– <i>On request connector set and/or accessories.</i>		
SE5/SE7-OEM-VE/RA	– ONE-SERIES PCB Assembly (Pre-installed vertical or right-angle connectors)	1	4.3 Cable assemblies and accessories
	– <i>On request connector set and/or accessories.</i>		
SE1/2/3-HSD	– ONE-SERIES in IP67 housing	1	4.3 Cable assemblies and accessories
	– Bag with 2 hexagon socket head screws	1	
	– <i>On request connector set and/or accessories.</i>		
SE5/7-HSD	– ONE-SERIES in IP67 housing	1	4.3 Cable assemblies and accessories
	– Bag with 2 hexagon socket head screws	1	
	– <i>On request connector set and/or accessories.</i>		