

JY901 Attitude Angle Sensor SPECIFICATION



Model : JY901

Description : Nine axis attitude angle sensor

Production Standard

Enterprise quality system standard: ISO9001:2016

Tilt switch production standard: GB/T191SJ 20873-2016

Criterion of detection: GB/T191SJ 20873-2016

Revision date: 2017.9.21



Version	Update content	Author	Date
V4.0	Release	Snow	20170921



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1 Description

- ♦ JY901 series module integrates high-precision gyroscopes, accelerometer, geomagnetic sensor, high-performance microprocessors and advanced dynamics solves dynamic Kalman filter algorithm to quickly solve the current real-time movement of the module attitude.
- The use of advanced digital filtering technology, can effectively reduce the measurement noise and improve measurement accuracy.
- Integrates gesture solver, with dynamic Kalman filter algorithm, can get the accurate attitude in dynamic environment, attitude measurement precision is up to 0.05 degrees with high stability, performance is even better than some professional Inclinometer!
- ◆ Integrate voltage stabilization circuit, working voltage is 3.3v ~ 5v, pin level compatible 3.3V and 5V embedded system .
- Supports serial port and IIC interfaces. Serial port rate is adjustable from 2400bps ~ 921600 bps, IIC interface supports full 400K rate.
- Highest 200Hz output data rate. The output data and rate can be adjusted.
- The 4-way expansion ports can configured as analog input, digital input, digital output, PWM output function.
- With GPS connectivity. Acceptable in line with NMEA-0183 standard serial GPS data form GPS-IMU navigation unit.
- Stamp hole gold plating PCB design, can be embedded in the user's PCB board.
- 4layer PCB technology, thinner, smaller, and more reliable.



2 Features

- 1) Input voltage: 3.3V-5V
- 2) Consumption current: <25mA
- 3) Volume: 15.24mm X 15.24mm X 2mm
- 4) Pad pitch: up and down 100mil (2.54mm), left and right 600mil (15.24mm)



- 5) Measuring dimensions: Acceleration: 3D Angular Velocity: 3D Attitude angle: 3D Magnetic field: 3D Atmospheric pressure:1D GPS: 3D
- 6) Range: Acceleration: $\pm 16g$, angular velocity: $\pm 2000 \circ / s$.
- 7) Stability: Acceleration: 0.01g, angular speed 0.05° / s.
- 8) Attitude stabilization measurement: 0.01 °.
- 9) Data output: time, acceleration, angular velocity, angle, field, port status, pressure (JY-901B), height (JY-901B), latitude and longitude (to be connected to GPS), ground speed (to be connected to GPS).
- 10) The data output frequency 0.1Hz to 200Hz.
- 11) Data Interface:
 Serial (TTL level baud rate support2400,4800,9600(default),19200,38400,57600, 115200,230400,460800,921600), I2C (IIC maximum support high speed 400K)
- 12) Expansion port functions: analog input (0 ~ VCC), digital input, digital output, PWM output (period 1us-65535us, resolution 1us)

3 Pin Description



Pin	Function
VCC	Power supply, 3.3V/5V input
RX	Serial data input, TTL level
TX	Serial data output, TTL level
GND	GND



SCL	IIC clock line
SDA	IIC data line
D0	Extended port 0
D1	Extended port 1
D2	Extended port 2
D3	Extended port 3

4 Axial Direction

As shown in the figure above, the coordinates of the module are indicated, and the right is the X axis, the upper is Y axis, the Z axis is perpendicular to the surface of the paper to yourself. The direction of rotation is defined by the right hand rule, that is, the thumb of the right hand is pointed to the axial direction, and the four is the direction of the bending of the right hand.

5 Hardware Connection

5.1 Serial Connection

5.1.1 Connect to PC

When connected to the PC software, you need a USB -TTL module. Recommend the following two USB -TTL module:





1. Serial module TTL: Firstly connect the module with the USB - TTL and then connect them to the computer. The ways of connecting module with USB -TTL are:

VCC TX RX GND of the module connected to +5V/3.3V RX TX GND of the serial module respectively. It is noteworthy that TX and RX need to be crossed--- RX connected to TX,TX connected to RX.

 Serial debugging artifacts: set switch 1 to ON, set switch 2 to (silk) 2, switch S1 dial to the lower (near the figure near "other" silk screen), VCC TX RX GND of the module connected to +5V/3.3V RX TX GND of the serial module respectively.





5.1.2 Connect to MCU



5.2 IIC Connection

JY-901 modules can be connected through the IIC interface to MCU, connection method as shown below. Note that, in order to connect several modules on IIC bus, module IIC bus is open-drain output, MCU need a 4.7K resistor pulled to VCC when connecting the module.

Reminder: The power supply VCC is 3.3V which should be powered by other power. The direct use of the power supply of the module may cause voltage drop, so that the actual voltage of the module can not reach to 3.3-5V.





6 Software Methods

6.1 Installation USB - TTL Module Driver

First, the module is connected via USB-TTL module to the computer, install the USB-TTL module driver. The drive CP210X:http://pan.baidu.com/s/106Rleae?frm=fujian

After installing the USB-TTL module driver, and then Device Manager can query corresponding serial number, as below figure shows:



Open the software MiniIMU.exe, Click "Port" and select the com number you just saw in the device manager.





Click the "Type" and select model "JY901".

niiIMU 技术论坛 http://elecmaster.net		
Type Port Baud - Start Record 3D Config	Help -	
JY61 leVelocity Angle Magnitude		
JY61BT		
JY61P		
IV61DM	ax ay az	
JY901		<u> </u>
JY901BT		
JY901M		
JY901IMU		
		10
		20
		3 - (C) - m
		S 34% 0.4
Welcome!		

Click the "Baud" and select "9600", after all those selections are completed, the software can display data.



MiniIMU 3	技术论坛	http://elec	master.net			-					
Гуре Ро	rt Bau	d • Start	Record	3D	Config	Help •					
Acceler	ati	2400 4800	Angle	Mag	ni tude						A X Y / 1
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Click the "3D" and you can bring up the three-dimensional display interface, which displays the three-dimensional posture of the module.





6.2 Restore Factory Setting

There are two methods, short circuit method and instruction methods.

Short Circuit Method : D2 pin are short to VCC pin, then power on the module, the module LED lights long bright, lasts about two seconds, LED light is off, complete restore factory settings operation.



Instruction method : JY-901 module connected to a PC via USB-TTL module , click the Settings tab, click "Recovery". After restore the factory settings ,need to restart the module again. (This method requires advance knowledge to know baud rate of the module, if the baud rate does not match the command will not take effect, try using a short-circuit recovery method).



6.3 Module Calibration

Reminder: The module calibration and configuration should be carried out under the online state which displayed in the low right corner of the software configuration bar.

The module need to be calibrated before the module is used. The calibration of JY901 includes accelerometer calibration and magnetic calibration.

6.3.1 Accelerometer Calibration

The accelerometer calibration is used to remove the zero bias of the accelerometer. When the sensor is out of the factory, there will be different degrees of bias error. After manual calibration, the measurement will be accurate.

Methods as follow:

- 1. Firstly keep the module horizontally stationary, in the "Config" of the software click "Acceleration" and a calibration interface will pop up.
- 2. Check the "Auto Calculate" option, the software will automatically calculates the zero bias value and then click "Write parameter"

JY9Config		
ReadConfig		
System Default Sleep Alarm) Algrithm: Axis 9 👻 direction: Herizon	- Instruction startup
Calibrate 1 Acceleration Magnitude Range Accleration: 16 g/s2 • Gyro:	AccCal Accelerator calibrate should keep modul horizontal. the side with components facing up.	e librate
Content Time Accleration Pressure Latitude longitude	x: 67 Y: 86 z: 77	Port GPS original
Comunicate Communication rate: 9600 💌 re	Read Parameter Write Parameter	change
Port	Status 3	
DO model: AIN - pulse width: 0	cycle: 0	
D1 model: AIN 👻 pulse width: 0	cycle:	
D2 model: AIN - pulse width: 0	cycle: 0	
D3 model: AIN 👻 pulse width: 0	cycle: 0	
		0nline
Mode Set OK!		



6.3.2 Magnetic Calibration

6.3.3 Z axis To 0

Reminder: Z axis to 0 is valid for JY61P only.

The z-axis angle is an absolute angle, and it takes the northeast sky as the coordinate system can not be relative to 0 degree.

Z axis to 0 is to make the initial angle of the z axis angle is relative 0 degree. When the module is used before and z - axis drift is large, the z - axis can be calibrated, When the module is powered on, the Z axis will automatically return to 0.

Calibration methods as follow: firstly keep the module static, click the "Config" open the configuration bar and then click "Zero Z Angle" option, you will see the the angle of the Z axis backs to 0 degree in the module data bar.

JY9Config				
System	Sleep Als	rm Algrithm:	Axis 9 🔻 directio	n: Herizon 🗸 🔲 Instruction startup
Calibrate Accelerati	on Magnitude	Height	Zero Z Angle	📝 Gyro Auto Calibrate
Range Accleration:	: 16 g/s2 🔻 Gyro:	2000 deg/ 👻	Bandwidth: 20	Hz 👻
Content Time Press	<table-cell> Accleration ure 🔲 Latitude longitude</table-cell>	a 🔽 Velocity 🗖 Ground velocity	✓ Euler angle Quaternion	Magnetism Port Positioning GPS original accuracy
Comunicate Communicatior	n rate: 9600 💌	retrieval rate:	10Hz 👻	0x50 change
Port				
DO model: AI	N 👻 pulse width:	0]	cycle: 0
D1 model: AI	N 👻 pulse width:	0]	cycle: 0
D2 model: AI	N 👻 pulse width:	0]	cycle: 0
D3 model: AI	N 👻 pulse width:	0 💌 ()	cycle: 0
				Online
Mode Set OK!			A+. 0	



副 MinitMIL 技术

htttp://www.wit-motion.com

lime		Acceleration		AngleVeloc	ity	Magnitude	
SystemTime:	10:43:57	х:	-0.0010 g	х:	0.0000 °/s	X:	0 mG
ChipTime:	0-0-0	¥:	0.0000 g	¥:	0.0000 °/s	¥:	0 mG
RelativeTime:	623.683	Z:	1.0010 g	Z:	0.0000 °/s	Ζ:	0 mG
		Т:	-12.76 °C	Т:	-12.76 °C	H :	0 mG
Port		Pressure		Angle		q	
DO:	0	Temprature:	-12.76 °C	х:	-0.016 °	q0:	0.00000
D1:	0	Pressure:	0 Pa	¥:	-0.005 °	q1:	0.00000
D2:	0	Height:	0.00 m	Z:	0.000 °	q2:	0.00000
D3:	0			Τ:	-12.76 °C	q3:	0.00000
3PS		GPS					
Longitude:	0° 0.00000'	Satellite Nu	m: 0				A
Latitude:	0° 0.00000'	PDOP:	0.00				Ð
GPS Height:	0.0 m	HDOP:	0.00				
GPS Yaw:	0.0 °	VDOP	0.00				
GPS Velocity:	0.000 km/h						34%

6.3.4 Height Setting 0

The height setting 0 is an operation to make the height of the module returns to 0, the height output of the module is calculated on the basic of the air pressure. Only with barometer modules(JY901B, JY61PB) output height.

6.3.5 Gyroscope Automatic Calibration

The gyroscope calibration is to calibrate the angular velocity, and the sensor will calibrate automaticly.

6.4 Set Return Content

Setting method: The content of returned data can be customized according to the user's needs, click "Config" to open configuration bar, and hook the data content option that you want. Take JY901 as an example, the default output of the module is acceleration, angular velocity angle and magnetic field.

Longitude and ground velocity information are effectively when connected to the GPS module. In order to get the correct data we need to set the content.



-							
System				1			
Default	t SI	Leep Al	arm Algrith	m: Axis 9 👻	direction: Herizo	on ▼ □ In st	struction artup
Calibrate							
Acceler	ration	Magni tude	Height	Zero Z	Angle 📝 Gyr	o Auto Calib	rate
Ranze		7					
Acclerat	.ion: 16 g	√s2 ▼ Gvro	2000 deg/	➡ Bandwid	th: 20 Hz 👻		
Content							
California (1994)		procession of the second se	100 AF 7			sm 🥅 Por	t
Ti	ime	💟 Accleratio	n 🗹 Yeloci	ity 📝 Euler	r angle 🔄 Magnet		
Ti	ime ressure	Latitude	n 🗹 Yeloci C Ground veloci	ity 📝 Euler d 📃 Quato ity	r angle 🔄 magnet ernion 📄 Positi	oning 🔲 GPS	original
Ti	ime ressure	✓ Accleration ✓ Latitude 1 longitude	n 🔽 Veloci	ity 🔽 Euler d ity 🔲 Quato	r angle 🔛 magnet ernion 📄 Positi accura	oning 🥅 GPS :y	original
Ti Fr Comunicate	ime ressure e	Accleration	n Veloci	ty VEules	r angle Magnet ernion Positi accura	oning GPS	original
Ti Pr Comunicate Communica	ime ressure e tion rate:	Accleration	n Veloci Cround veloci	d Quato ty Quato te: 10Hz	r angle magnet ernion Positi accura	Oning GPS	original change
Ti Pr Comunicate Communica Port	ime ressure e tion rate:	Accleration Latitude longitude	n Veloci Ground veloci	ity V Euler d ity Quate te: 10Hz	r angle magnet. ernion Positi accura	oning GPS	original change
Ti Pr Comunicate Communica Port DO model:	ime ressure e tion rate: AIN -	<pre>v Accleratio Latitude longitude 9600 v pulse width:</pre>	n Veloci Ground veloci retrieval ra	d ity Quate ity 10Hz	r angle magnet. ernion Positi- accura •	oning GPS	original change
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Ti Pr Comunicate Communicate Port D0 model: D1 model:	ime ressure tion rate: AIN ~ AIN ~	Accleration Latitude longitude 9600 pulse width: pulse width:	n Veloci Ground veloci	ty V Euler d ity Quate te: 10Hz	 r angle magnet. ernion Positi- accura cycle: cycle: 	0 •	original
Ti Ti Comunicate Communicate Communicate Dort Do model: D1 model: D2 model:	AIN ~ AIN ~	Accleration Latitude longitude 9600 pulse width: pulse width:	n Veloci Ground retrieval ra	d ity Quate te: 10Hz	 rangle magnet: ernion Positiaccura cycle: cycle: cycle: 	oning GPS 0x50 • 0 • 0 • 0 • 0 •	original
Ti Comunicate Communicate Communicate Port DO model: DI model: D2 model: D3 model:	ime ressure tion rate: AIN ~ AIN ~ AIN ~	Accleration Latitude longitude 9600 • pulse width: pulse width: pulse width:	n Veloci Ground veloci retrieval ra	d Quato ty Quato te: 10Hz	 rangle magnet: ernion Positiaccura cycle: cycle: cycle: cycle: 	Ox50 0 0 0 0 0 0	original

6.5 Set Return Rate

Setting methods: click "Config" to open configuration bar and than set the "retrieval rate" is 0.1HZ-200HZ optional.

The default return rate of the module is 10HZ, the highest return rate supports 200HZ.

10HZ refers to 10 packets returned every second. There contains 33bytes in a data packet in default.

Reminder: If there being a lot of return content and low baud rate of communication, the module will automatically reduce the frequency and output at a maximum allowable output rate. The default baud rate is 115200.



System							
Default	t [Sleep	larm Algrit	hm: Axis 9 🔻	direction: Herizor	start	uguna
Calibrate							
Accele	ration	Magni tude	Heigh	t Zero Z	Angle 📝 Gyro	Auto Calibrat	e
Range							
Acclerat	ion: 16	g∕s2 ▼ Gyr	o: 2000 deg/	👻 🛛 Bandwi	ith: 20 Hz 👻		
Content		🔽 åcclerati	on 🔽 Velou	vitv 🕅 R.J.		n 🕅 Paul	
	une	- Latituda	- Grow		- Angre - Magnetis	ing 🔲 GPS or	iginal
P1	ressure	longi tude	e velo	nity 📃 Qua	ernion 📄 iosicion accuracy	/	1 GI Hat
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Paut			8×5.				
DO model:	AIN	pulse width	: 0 🜲	0	cycle:)	
D1 model ·	AIN	pulse width	: 0		cvcla: 0)	
DI MODEL.	LTY				- C		
D2 model:	ALN	▼ pulse width		0	cycle:	· 🖃	
D3 model:	AIN	 pulse width 	: U 🚔	0	cycle: [

6.6 Set Baud Rate

Module supports multiple baud, 9600 default. Change baud rate only when the module connect to PC program successfully, choose the baud rate and Click "Change" button.

Reminder: After changing the baud rate, the module does not immediately take effect, need to re-power and then it will take effect.



			htttp://www.wit-m	notion.com
Computer	大师 JY-90L资料 Network	ATK ICUM XCOM	Logic 11116 Hantak02 PDCA MPU605027	
維持君悦意 Moto 前梓铭ter 维持君悦意 Moto 明ter	Cont. 2 MiniMU 152 Hists ht Type Por Baud SystemTime: ChipTime: RelativeTime	p://elecmaster.ne 2 9:46:45 2015-1-0 0:0:0.0 : 163.467	V9Config ResdConfig System Befealt Sleep Alarn Algriths: Aris 9 v direction: Merizon v Instruction Calibrate Acceleration: Magnitude Meight Zero Z Angle Ø Oyro Auto Calibrate Range Acceleration: 16 g/2 v Gyro; 2000 deg/ v Bandridth: 20 Mr. v	₹
	Port DO: D1: D2: WILD D3:	0 0 0 0	Content Time Accleration Velocity Fuler angle Pagnetism Port Pressure Latitude Ground Quaternion Stitisming OFS original Commicate OF retrieval rate: 10Mr - Or50 change O	
GPS.up Da	GPS Longitude: Latitude: GPS Height: GPS Height:	0° 0.00000° 0° 0.00000° 0.0 m 0.0 °	4000 1 100 sedal: AIX + 38400 0	
P S	GPS Velocity Welcome!	: 0.000 km/h	0nline 0nline 31% ↑ 0.2% D3 Mode Set OK 31% ↑ 0.2% 0.0% (1) Mode Set OK (1) (1) (1) (1) (1) (1) (1) (1) (1) (1)	3 19:46 11 ≉ ≠ 2017/10/25

6.7 Data Recording

There is no memory chip in the sensor module, and the data can be recorded and saved in the software.

Method are as follows: Click "Record" and "Start" will save the data as a file.





NiniIMU 技术论坛 h	http://elecma	ster.net			-						ب ا	
Type Port Baud	• Start F	Record 30	Config	Help 🔹								
T. Accoloration 1	1 16 1 11										1 (
d Acceleration Ar	igreverocità	Angie	nagnitude								1	/ / III.
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134,938,0,1938	0.0698	0.9971	50, 4761	-120.6665	8 2397	6.1359	-12 1674	-28	6523	-15,1200		
134.938 0.2271	0.0864	0.9565	54. 4434	-122.0703	6.9580	6.6797	-13. 3868	-28.	7183	-15.1300		
134.938 0.2437	0.0986	0.9673	53.8940	-119.5679	5.1880	7.2235	-14.5789	-28.	8062	-15.1600		
134.938 0.2671	0.1108	0.9512	53.4668	-117.7979	4.1504	7.7783	-15.7489	-28.	9160	-15.1300		
134.938 0.2842	0.1230	0.9453	55.7861 EE 0470	-114.0137	5.0049	8.3551	-15.8860	-29.	1259	-15.1200		
134.936 0.2939	0.1240	0.9014	56 3354	-111.3112	5. 1965 6. 0425	0.9204	-10 1057	-29.	2566	-15.1600		
134.995 0.3521	0.1631	0. 8794	55, 3589	-104, 3091	7. 3242	10.1184	-20, 1544	-29	3610	-15, 1800		
134.995 0.3496	0.1577	0.9414	52.6733	-96.4966	9.0332	10.6622	-21.1102	-29.	4489	-15.1400		
134.995 0.3799	0.1685	0.9048	55.5420	-94.4824	10.9863	11.2335	-22.0660	-29.	5203	-15.1500		
134.995 0.4077	0.1802	0.8604	57.9834	-89.3555	12.6953	11.8378	-22.9834	-29.	5752	-15.1300		
135.006 0.4102	0.1812	0.8911	52.9785	-80. 9326	12.0239	12.3761	-23.8074	-29.	6246	-15.0900		
135.007 0.4209	0.1899	0.8926	47.1802	-76.9653	10.1318	12.8705	-24.5819	-29.	595U 7704	-15.1300		
135.007 0.4219	0.1690	0.9105	45.1155	-75 9888	9.0450	13.3429	-26.0760	-29.	8718	-15,1800		
135,037 0,4644	0. 2139	0.8506	45.1660	-75.7446	8,6060	14.3317	-26. 8451	-29.	9817	-15, 1200		
135.037 0.4775	0.2227	0.8394	42.1143	-69.9463	8.3618	14.7986	-27.5592	-30.	0861	-15.1800		
135.037 0.4824	0.2285	0.8511	39.1235	-62.8662	8.3008	15.2325	-28.1909	-30.	1740	-15.1800	5	3 A ', ()
135.096 0.4937	0.2285	0.8496	36.3770	-57.8613	7.9956	15.6281	-28.7732	-30.	2618	-15.2000		
135.096 0.4946	0.2261	0.8696	34.1187	-54.0161	7.3242	15.9961	-29.3115	-30.	3442	-15.2000		
1.55 1.11 11 5118.5	11 2.529	11 8477	SAL 2500	-n.) /8.37	5 4321	in 3531	-24 8.184		4541	=15 1500		

The saved file is in the directory of the software Data.tsv:

The file begins with a value indicating the data. "Time" stands for time, "ax, ay, az" respectively represents the acceleration of X, Y, Z axis. "wx, wy, wz" respectively represents the angular velocity of X, Y, Z axis. "AngleX, AngleY, AngleZ" respectively represents the angle of the X, Y, Z axis. T represents the temperature.

Data can be imported into the Exel or analysis in Matlab. In the Matlab environment running xxx.m document and it can plot of the data.

6.8 Installation Direction

The default installation direction of the module is horizontal installation. When the module needs to be vertically placed, it can be installed vertically.

Vertical installation method: Put the module around X-axis rotation 90 degrees vertical placement. In the "Config" of the software, click "Vertical" option. The calibration can be used after the setup is completed.





System		ann Alarm	Al-11-11-1 40	nie 9 - Januarian Has	iron _ Instruction
Deraure		Лаш	Algrician. 10	direction. Act	startup
Calibrate				<u> </u>	
Acceler	ation	Magnitude	Height	Zero Z Angle	Gyro Auto Calibrate
Range	-				2.2
Acclerat	ion: 16 g	√s2 ▼ Gyro:	2000 deg/ 👻	Bandwidth: 20 Hz	×.
Content					
🕅 Ti	me	🔽 Accleration	🔽 Velocity	🔽 Euler angle 🕅 Mag	netism 📃 Port
📄 Pr	essure	🔲 Latitude longitude	Ground velocity	🔲 Quaternion 📄 Pos:	itioning 🔲 GPS original uracy
Comunicate					
Communicat	tion rate:	9600 👻 1	etrieval rate: 1	OHz 👻	0x50 change
Port					
DO model:	AIN 👻	pulse width: 0	÷ 0	cycl	Le: 0
D1 model:	AIN 👻	pulse width: 0	÷ 0	cycl	Le: 0 🚖
D2 model:	AIN 👻	pulse width: 0		cyc]	Le: 0
D3 model:	AIN 👻	pulse width: 0	÷ Ū	cyc]	Le: 0
			Y		
					0-11-0

6.9 Sleep/ Wake up

Sleep: The module paused working and entered the standby mode. Power consumption is reduced



after sleeping.

Wake up: The module enters the working state from standby state.

The module defaults to a working state, in the "Config" of the software, click "Sleep" option to enter the sleep state, click "Sleep" again to release sleep.

Section						
Default	Sleep	Alarm	Algrithm: Axi	s 9 🔻 directio	on: Herizon 👻	Instruction startup
Calibrate						
Accelerati	on Magn	ni tude	Height	Zero Z Angle	👿 Gyro Aut	o Calibrate
Range						
Accleration	16 g/s2	▼ Gyro: 200)0 deg/ 👻	Bandwidth: 20	Hz 👻	
Content						
🥅 Time	🔽 Ac	cleration	🗸 Velocity	🔽 Euler angle	📄 Magnetism	🥅 Port
📄 Press	ure 🔳 La lo	titude ongitude [🗖 Ground velocity	🔲 Quaternion	Positioning accuracy	🔲 GPS original
Comunicate						
Communication	1 rate: 9600	▼ retr	ieval rate: 10	Hz 👻	C	x50 change
Port	N 🔻 pulse	e width: 0	÷ 0-		cycle: 0	×
Port DO model: AI					cycle: 0	×
Port DO model: AI D1 model: AI	N 🗸 pulse	e width: O				
Port DO model: AI D1 model: AI D2 model: AI	N - pulso	e width: 0 e width: 0			cycle: 0	
Port DO model: AI D1 model: AI D2 model: AI	N V pulso	e width: 0 e width: 0			cycle: 0	
Port DO model: AI D1 model: AI D2 model: AI D3 model: AI	N v puls. N v puls. N v puls.	e width: 0 e width: 0 e width: 0			cycle: 0 cycle: 0	

6.10 Set Bandwidth

Bandwidth: The module outputs only the data within the measurement bandwidth, and the data which is larger than the bandwidth will be filtered automatically.

In the "Config" of the software, click "Bandwidth" option to set it, the default setting is 20HZ.



System							
Default		Sleep /	larm Algri	thm: Axis 9	 direction: } 	lerizon 👻	startup
Calibrate							
Accele	ration	Magni tude	Heig	ht Zer	o Z Angle	🖉 Gyro Auto	Calibrate
Range						_	
Acclerat	ion: 16	g/s2 🔻 Gyr	o: 2000 deg	/ 🚽 🛛 Band	width: 20 Hz	+	
_							
Content		🔽 Acclerat	ion 🔽 Vel	ocity 🕅 🖬	nlor orgio 🥅 🖷	motirm	Port
	une	Latituda	Cer.	und _	urer angre 🛄 Wa	eitionin-	GPS original
P1	ressure	longi tud	e vel	ocity 🗖 🕻	uaternion 🔲 a	curacy	O or 2 of 1 gringer
Comunicate							
Communica	tion rate	. 9600 -	retrieval	rate: 10Hz	•	Ox	50 change
Port							
DO model:	AIN ·	 pulse width 	.: 0 🚔	0	cy	rcle: 0	×
D1 model:	AIN	- pulse width	.: 0	0	су	cle: 0	
	AIN	 pulse width 	. 0	D	cv	cle: 0	
D2 model	ATN .		. 0 🔺		~		
D2 model:	ALI	 purse widtr 		U	cy	cie.	T
D2 model: D3 model:							

6.11 Set IIC Address

The module's IIC address is 0x50, which can be changed by software. Change the IIC address only when the module connect to PC program successfully, and enter the new 16 hexadecimal IIC address and click the "change" button.

Reminder: The IIC address of the module will not be changed immediately, and it will take effect when the module restart.



Default	Sleep Alarm Algrit	hm: Axis 9 🔻 direction: Herizon 👻 🔲 Instr	ruction tup
Calibrate			
Acceleration	Magni tude Height	t 🛛 🛛 Zero Z Angle 🖉 Gyro Auto Calibrat	.e
Range Accleration: 16	g/s2 🔻 Gyro: 2000 deg/	▼ Bandwidth: 20 Hz ▼	
Content			
🥅 Time	📝 Accleration 🛛 📝 Veloc	rity 🛛 📝 Euler angle 🦳 Magnetism 🕅 Port	
📄 Pressure	🗖 Latitude 🛛 🗖 Groum longitude 🖉 veloc	nd 👘 🔲 Quaternion 🕅 Positioning 🥅 GPS or rity 👘 Quaternion	iginal
Comunicate			
Communication rate	: 9600 🔻 retrieval r	ate: 10Hz 🗸 0x50 c	hange
Port			
DD model: AIN	🔹 pulse width: 0	cycle: 0	
DO MODEL.	🔹 pulse width: 0	cycle: 0 🖨	
D1 model: AIN ,		cycle: 0	
D1 model: AIN •	🔹 pulse width: 0 🚔		
D1 model: AIN		cvcle: 0	
D1 model: AIN . D2 model: AIN . D3 model: AIN .	 pulse width: pulse width: 0 	cycle: 0 🚖	

6.12 Set Extended Port

The JY-901 module has 4 multiple function expansion ports, which can be set to different functions according to the need. Set extended port only when the module connect to PC program successfully.

The extended port supports analog input mode, digital input mode, digital output mode, PWM output mode. D1 port also supports GPSRX mode, port state by default is analog input mode.

The port status packet which the module exports contains the status information of the extended port. In different modes, the port state data DxStatus has the following meanings:

Mode	Implication
Analog input mode	Analog voltage
Digital input mode	Port high and low level state
Digital high level output mode	Port output state
Digital low level output mode	Port output state
PWM output mode	PWM high level width
CLR (D1)	The XY relative attitude 0



Analog input mode is used to measure the analog voltage on the port, such as a potentiometer or a sensor, etc.

Formula is As follows:

 $U=DxStatus/4096*U_{vcc}$

Uvcc is the power supply voltage of the module, because the module has LDO, if the module power supply voltage is greater than 3.5V, Uvcc is 3.3V. If the module supply voltage is less than 3.5V, Uvcc equal to the supply voltage minus $0.2V_{\circ}$

For digital input mode, if the voltage is high, DxStatus=1, else, DxStatus=0.

For digital output mode:

Voltage is high, DxStatus=1.

Voltage is low, DxStatus=0.

PWM output mode is used for the output of the PWM wave, the cycle and the high level width can be adjusted, the unit is us. In the PWM output mode, the port state data is used to indicate the high level of the PWM, the unit us.

PortCont	rol						Port Status
DOMode:	AIN V	PulsWidth16377	•		Period: 20000	*	DO:
D1Mode:	GPSRX 🗸	PulsWidth12319	•		Period: 20000	-	D1:
D2Mode:	AIN 🗸	PulsWidth6377	•	-0	Period: 20000	-	D2:
D3Mode:	AIN 🗸	PulsWidthO	Ð.		Period:]	+	D3:

6.13 Six axis/ Nine axis Algorithm

JY61P uses the 6 axis algorithm, and the z axis angle is calculated mainly according to the angular velocity integral.

JY901 uses the 9 axis algorithm, the z axis angle is mainly calculated according to the magnetic field, there will be no drift phenomenon.

When the JY901 environment is disturbed by magnetic field, the 6 axis algorithm can be used to detect the angle.

Nine axis algorithm to use 6 axis algorithm: in the PC configuration bar, the algorithm changed to "Axis6", and then additional calibration and Z axis zeroing calibration. The calibration will be ready for use.

Reminder: here only JY901 can do the algorithm conversion, and the system defaults to the 9 axis algorithm. JY61P is unable to convert algorithms.



aconing							
ystem							
Default	Sle	ep Al	arm Algrithm	Axis 9 - direc	ction: Herizon	a ▼ □ I	Instruction startup
alibrate				Axis 6			
Acceleratio	n	Magni tude	Height	Zero Z Angl	e 🛛 📝 Gyro	Auto Cali	brate
ange							
Accleration:	16 g/s	s2 🔻 Gyro	: 2000 deg/ ▼	Bandwidth:	20 Hz 👻		
ontent							
Time		Accleratio	on 🔽 Velocit	V 📝 Fuler eng	le 🥅 Magneti	sm 🔽 Po	rt
termine and the second second				a 🔊 norei auf		N. C.	
🥅 Pressu	re	Latitude longitude	Ground velocit	y 🔲 Quaternio	n 🔲 Positio accurac	ning 📃 GP V	S original
m Pressu Comunicate	re	Latitude Ongitude	Ground velocit	y 🔲 Quaternio	n 🔲 Positio accurac	ning 📃 GP V	S original
 Pressu Comunicate Communication	re rate:	E Latitude longitude 9600 -	Ground velocit	y Quaternio	n Positio accurac	ning 🔲 GP 7 0x50	S original
m Pressu omunicate Communication ort	re rate:	E Latitude longitude 9600 -	Ground velocit	y Quaternio	n Positio accurac	ning 🔲 GP. 7 0x50	S original
m Pressu omunicate Communication ort D model: AIN	re rate:	Latitude longitude 9600 -	retrieval rate	y Quaternio	n Positio accuracj cycle:	ning GP. 9 0x50	S original
municate communication ort D model: AIN 1 model: AIN	re rate:	Latitude longitude 9600 • pulse width: pulse width:	Ground velocit retrieval rate	y Quaternio	n Positio accuracy cycle:	ning GP. 7 0x50	S original
The second secon	re rate:	Latitude longitude 9600 • pulse width: pulse width: pulse width:	C Ground velocit retrieval rate	y Quaternio	n Positio accuracy cycle: [cycle: [cycle: [ning GP. 7 0x50	S original
Pressu omunicate Communication ort D model: AIN 1 model: AIN 2 model: AIN 3 model: AIN	re rate:	Latitude longitude 9600 • pulse width: pulse width: pulse width: pulse width:	Ground velocit retrieval rate	y Quaternio	n Positio accuraci cycle: [cycle: [cycle: [ning GP. 7 0x50	S original

7 Communication Protocol

Level: TTL level (non RS232 level, if the module is wrong to the RS232 level may cause damage to the module)

Baud rate: 2400, 4800, 9600 (default), 19200 38400, 57600, 115200, 230400, 460800, 921600, stop bit and parity bit 0

7.1 Module to PC Software

7.1.1 Time Output

0x55	0x50	YY	MM	DD	hh	mm	SS	msL	msH	SUM
YY	: Year,	20YY Y	ear							
MN	1: Month									
DD	: Day									
	Tel: (+	86) 755–33	185882 E	E-mail: wi	t@wit-mot	ion.com	Web: www	.wit-mot	tion.com	



hh: hour mm: minute ss: Second ms: Millisecond Millisecond calculate formula: ms=((msH<<8)|msL) Sum=0x55+0x51+YY+MM+DD+hh+mm+ss+ms+TL

7.1.2 Acceleration Output:

0x55	0x51	AxL	AxH	AyL	АуН	AzL	AzH	TL	TH	SUM
Cal	culate form	nula:								
$a_x =$	((AxH<<8	3) AxL)/32	2768*16g(g is Gravi	ity acceler	ation, 9.	8m/s^2)			
a _y =	((AyH<<8	3) AyL)/32	768*16g(g is Gravi	ty acceler	ation, 9.	8m/s ²)			
a _z =	((AzH<<8	3) AzL)/32	768*16g(g is Gravi	ty acceler	ation, 9.	8m/s²)			
Ten	operature	calculated	formular	:						
T=((TH<<8)	TL) /100	°C							
Che	ecksum:									
Sur	n=0x55+0	x51+AxH	[+AxL+Ay	H+AyL+	AzH+AzI	L+TH+TL	1			
Not	te:									
1,	the data	is transmi	tted in acc	ordance v	with the 16	6 hexadec	imal, not	ASCII	code	
2,	Each dat	ta is transr	nitted in a	low byte	and a higl	h byte, an	d the two	is comb	oined int	0
	a sho	ort type of	f symbol.	Such as X	X axis acc	eleration	data Ax,	where A	AxL is t	he low
	byte,	AxH is h	igh byte.							
	The	conversion	n method	is as follo	ws:					
	Assu	iming Dat	a is the ac	tual data,	DataH for	r its high	byte, Dat	aL for it	s low by	vte part,
	then	: Data= ((:	short) Dat	aH<<8) I	DataL. He	re we mu	st pay at	tention to	o that fo	rce the
	Data	H to be c	onverted i	nto a sym	bol of the	e short typ	pe of dat	a and th	en after	shift 8

7.1.3 Angular Velocity Output

0x55	0x52	wxL	wxH	wyL	wyH	wzL	wzH	TL	TH	SUM		
Cal	Calculated formular:											
W _x =	w _x =((wxH<<8) wxL)/32768*2000(°/s)											
w _y =	wy=((wyH<<8) wyL)/32768*2000(°/s)											
W _z =	=((wzH<<	8) wzL)/32	2768*200	0(°/s)								
Ten	nperature	calculated	formular	:								
T=((TH<<8)	TL) /100	°C									
Che	ecksum:											
Sum=0x	55+0x52+	wxH+wx	L+wyH+v	vyL+wzH	+wzL+TI	H+TL						

bit, and the type of Data is also a symbol of the short type, so it can show a negative.



7.1.4 Angle Output:

0x55	0x53	RollL	RollH	PitchL	PitchH	YawL	YawH	TL	TH	SUM
Cal	culated for	rmular:								
Rol	l (x axis)	Roll=((H	RollH<<8)	RollL)/3	2768*180	(°)				
Pitc	h (y axis) Pitch=((PitchH<	<8) PitchL	.)/32768*	180(°)				
Yav	v (z axis)	Yaw=((YawH<<8) YawL)/3	2768*180)(°)				
Ten	perature o	calculated	formular	:						
T=((TH<<8)	TL) /100	°C							
Che	Checksum:									
Sun	n=0x55+0	x53+Roll	H+RollL+	PitchH+P	vitchL+Ya	wH+Yaw	L+TH+T	Ľ		

Note:

- 1. Attitude angle use the coordinate system for the Northeast sky coordinate system, the X axis is East, the Y axis is North, Z axis toward sky. Euler coordinate system rotation sequence defined attitude is z-y-x, first rotates around the Z axis. Then, around the Y axis, and then around the X axis.
- 2. In fact, the rotation sequence is Z-Y-X, the range of pitch angle (Y axis) is only ±90 degrees, when the pitch angle (Y axis) is bigger than 90 degrees and the pitch angle (Y axis) will become less than 90 degrees. At the same time, the Roll Angle(X axis) will become larger than 180 degree. Please search on Google about more information of Euler angle and attitude information.
- **3.** Since the three axis are coupled, the angle will be independent only when the angle is small. It will be dependent of the three angle when the angle is large when the attitude angle change, such as when the X axis close to 90 degrees, even if the attitude angle around the X axis, Y axis angle will have a big change, which is the inherent characteristics of the Euler angle

7.1.5 Magnetic output:

0x55	0x54	HxL	HxH	HyL	HyH	HzL	HzH	TL	TH	SUM
Cal	culated fo	rmular:								
Mag	gnetic (x	axis) Hx	=((HxH<-	<8) HxL)						
Mag	gnetic (y	axis) Hy	=((HyH <	<8) HyL))					
Mag	gnetic (z	axis) Hz	=((HzH<	<8) HzL)						
Ten	operature	calculated	formular:							
T=((TH<<8)	TL) /100	°C							
Che	ecksum:									
Sun	n=0x55+0	x53+HxH	+HxL+Hy	yH+HyL+	HzH+Hz	L+TH+TI	-			



7.1.6 Data output port status:

0x55	0x55	D0L	D0H	D1L	D1H	D2L	D2H	D3L	D3H	SUM
Cal	culated fo	rmular:								
D0	= (D0H<<	<8) D0L								
D1	= (D1H<<	<8) D1L								
D2	= (D2H<<	<8) D2L								
D3	= (D3H<<	<8) D3L								
Not	te:									
An	alog inpu	t port mo	de:							
U=	DxStatus/	1024*U _{vc}	2							
Uve	cc is the p	ower supp	oly voltage	e of the m	odule, bec	cause the	module ł	nas LDC), if the r	nodule
power su	upply volt	age is gre	ater than 3	3.5V, Uvc	c is 3.3V.	If the mo	dule sup	ply volt	age is le	ss than
3.5V, Uv	vcc equal t	to the supp	oly voltage	e minus 0.	2V					

Digital input mode:

Voltage level is high, the data is 1,

Voltage level is low, the data is 0.

Digital output mode:

Output is high, the data is $1\,{}_{\circ}$

Output is low, the data is 0_{\circ}

PWM output mode:

When the port is set to PWM output mode, port status data indicates high level width , the unit is us.

7.1.7 Atmospheric pressure and Height output:

0x55	0x56	P0	P1	P2	P3	H0	H1	H2	H3	SUM
Cal	culated fo	rmular:								
Atm	ospheric p	ressure	P = ((P3<	<24) (P2	<<16) (P	1<<8) P0	(Pa)			
Hei	ght H = ((H3<<24)	(H2<<16	6) (H1<<	8) H0 (cm)				

Checksum:

Sum=0x55+0x54+P0+P1+P2+P3+H0+H1+H2+H3

7.1.8 Longitude and Latitude Output:

0x55	0x57	Lon0	Lon 1	Lon 2	Lon 3	Lat0	Lat 1	Lat 2	Lat 3	SUM
0.1	1 . 1 0	1								

Calculated formular:

Longitude Lon = ((Lon 3<<24)| (Lon 2<<16)| (Lon 1<<8)| Lon 0

In NMEA0183 standard, GPS output format is ddmm.mmmmm (dd for the degree, mm.mmmmm is after decimal point), JY-901 removed output decimal point, so the degree of longitude can be calculated:

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dd=Lon/10000000;

mm.mmmmm=(Lon%1000000)/100000; (% calculate Remainder)

Latitude Lat = ((Lat 3<<24)| (Lat 2<<16)| (Lat 1<<8)| Lat 0 (cm)

In NMEA0183 standard, GPS output format is ddmm.mmmmm (dd for the degree, mm.mmmmm is after decimal point), JY-901 removed output decimal point, so the degree of longitude can be calculated:

dd=Lat/10000000;

```
mm.mmmmm=(Lat%1000000)/100000; (% calculate Remainder)
```

Checksum:

```
Sum=0x55+0x54+ Lon 0+ Lon 1+ Lon 2+ Lon 3+ Lat 0+ Lat 1+ Lat 2+ Lat 3
```

7.1.9 Ground speed output:

0x55	0x58	GPSHeightL	GPSHeightH	GPSYawL	GPSYawH
GPSV0	GPSV 1	GPSV 2	GPSV 3	SUM	

Calculated formular:

```
GPSHeight = ((GPSHeightH \le 8) | GPSHeightL)/10 (m)
```

GPSYaw =((GPSYawH <<8)| GPSYawL)/10 (°)

GPSV = $(((Lat 3 \le 24)) (Lat 2 \le 16)) (Lat 1 \le 8) | Lat 0)/1000 (km/h)$

Checksum:

Sum=0x55+0x54+ GPSHeightL + GPSHeightH + GPSYawL + GPSYawH + GPSV0+ GPSV 1+ GPSV 2+ GPSV 3

7.1.10 Quaternion:

0x55	0x59	Q0L	Q0H	Q1L	Q1H	Q2L	Q2H	Q3L	Q3H	SUM
Cal	culated fo	rmular:								
Q0=	=((Q0H<<	<8) Q0L)/3	32768							
Q1=	=((Q1H<<	<8) Q1L)/3	32768							
Q2=	=((Q2H<<	<8) Q2L)/3	32768							
Q3=	=((Q3H<<	<8) Q3L)/3	32768							
Che	ecksum:									
Sur	m=0x55+0	x59+Q0L	+Q0H+Q	1L +Q1H	+Q2L+Q2	2H+Q3L+	-Q3H			

7.1.11 Satellite positioning accuracy output:

0x55	0x5A	SNL	SNH	PDOPL	PDOPH	HDOPL	HDOPH	VDOPL	VDOPH	SUM
C	Calculate	d form	ılar:							
	Tel	: (+86)	755-331	85882 E-	mail: wit	@wit-motio	n.com Web	: www.wit-	motion.com	
					2	•				



```
Satellite quantity: SN=((SNH<<8)|SNL)
Location positioning accuracy: PDOP=((PDOPH<8)|PDOPL)/32768
Horizontal positioning accuracy: HDOP=((HDOPH<8)|HDOPL)/32768
Vertical positioning accuracy: VDOP=((VDOPH<8)|VDOPL)/32768
Checksum:
Sum=0x55+0x59+ SNL + SNH + PDOPL + PDOPH + HDOPL + HDOPH + VDOPL + VDOPH
```

7.2 Software to Module

Remider:

- 1. Factory settings default to use serial port, band rate is 9600, frame rate is 10HZ. Configuration can be configured through PC software. All configuration are power down storage, so you just need to configure it just once on the line.
- 2. Data format

0xFF	0xAA	Address	DataL	DataH	
------	------	---------	-------	-------	--

7.2.1 Register Address table

Address	Symbol	Meaning
0x00	SAVE	Save
0x01	CALSW	Calibration
0x02	RSW	Return data content
0x03	RATE	Return data Speed
0x04	BAUD	Baud rate
0x05	AXOFFSET	X axis Acceleration bias
0x06	AYOFFSET	Y axis Acceleration bias
0x07	AZOFFSET	Z axis Acceleration bias
0x08	GXOFFSET	X axis angular velocity bias
0x09	GYOFFSET	Y axis angular velocity bias
0x0a	GZOFFSET	Z axis angular velocity bias
0x0b	HXOFFSET	X axis Magnetic bias
0x0c	HYOFFSET	Y axis Magnetic bias
0x0d	HZOFFSET	Z axis Magnetic bias
0x0e	D0MODE	D0 mode
0x0f	D1MODE	D1 mode
0x10	D2MODE	D2 mode
0x11	D3MODE	D3 mode
0x12	D0PWMH	D0PWM High-level width
0x13	D1PWMH	D1PWM High-level width

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0x14	D2PWMH	D2PWM High-level width	
0x15	D3PWMH	D3PWM High-level width	
0x16	D0PWMT	D0PWM Period	
0x17	D1PWMT	D1PWM Period	
0x18	D2PWMT	D2PWM Period	
0x19	D3PWMT	D3PWM Period	
0x1a	IICADDR	IIC address	
0x1b	LEDOFF	Turn off LED	
0x1c	GPSBAUD	GPS baud rate	
0x30	YYMM	Year, Month	
0x31	DDHH	Day, Hour	
0x32	MMSS	Minute, Second	
0x33	MS	Millisecond	
0x34	AX	X axis Acceleration	
0x35	AY	Y axis Acceleration	
0x36	AZ	Z axis Acceleration	
0x37	GX	X axis angular velocity	
0x38	GY	Y axis angular velocity	
0x39	GZ	Z axis angular velocity	
0x3a	НХ	X axis Magnetic	
0x3b	НҮ	Y axis Magnetic	
0x3c	HZ	Z axis Magnetic	
0x3d	Roll	X axis Angle	
0x3e	Pitch	Y axis Angle	
0x3f	Yaw	Z axis Angle	
0x40	TEMP	Temperature	
0x41	D0Status	D0Status	
0x42	D1Status	D1Status	
0x43	D2Status	D2Status	
0x44	D3Status	D3Status	
0x45	PressureL	Pressure Low Byte	
0x46	PressureH	Pressure High Byte	
0x47	HeightL	Height Low Byte	
0x48	HeightH	Height High Byte	
0x49	LonL	Longitude Low Byte	
0x4a	LonH	Longitude High Byte	
0x4b	LatL	Latitude Low Byte	
0x4c	LatH	Latitude High Byte	
0x4d	GPSHeight	GPS Height	
0x4e	GPSYaw	GPS Yaw	
0x4f	GPSVL	GPS speed Low byte	

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0x50	GPSVH	GPS speed High byte
0x51	Q0	Quaternion Q0
0x52	Q1	Quaternion Q1
0x53	Q2	Quaternion Q2
0x54	Q3	Quaternion Q3

7.2.2 Save Configuration

0xFF	0xAA	0x00	SAVE	0x00

SAVE: Save

- 0: Save current configuration
- 1: set to default setting

7.2.3 Calibrate

0xFF	0xAA	0x01	CALSW	0x00
4 111 4	1			

CALSW: Set calibration mode

- 0: Exit calibration mode
- 1: Enter Gyroscope and Accelerometer calibration mode
- 2: Enter magnetic calibration mode
- 3: Set height to 0

7.2.4 Set Installation direction

0XFF 0XAA 0X25 DIRECTION 0X00		0xFF	0xAA	0x23	DIRECTION	0x00
-------------------------------	--	------	------	------	-----------	------

DIRECTION: set installation direction

- 0: set to horizontal installation
- 1: set to vertical installation

7.2.5 Sleep/ Wake up

0xFF 0xAA	0x22	0x01	0x00
-----------	------	------	------

Sent this instruction to enter sleep state, sent it once again, module enter the working state from the standby state.



7.2.6 Algorithm transition

0xFF $0xAA$ $0x24$ ALG $0x00$

- ALG: 6-axis/ 9-axis algorithm transition
 - 0: set to 9-axis algorithm
 - 1: set to 6-axis algorithm

7.2.7 Gyroscope automatic calibration

|--|

GYRO: gyroscope automatic calibration

- 0: set to gyroscope automatic calibration
- 1: removed to gyroscope automatic calibration

7.2.8 Set return content

		0xFF	0xAA	0x02	RSWL	RSWH	Ι	
RSV	W byte de	efinition						
byte	7	6	5	4	3	2	1	0
Name	0x57	0x56	0x55	0x54	0x53	0x52	0x51	0x50
	pack	pack	pack	pack	pack	pack	pack	pack
default	0	0	0	1	1	1	1	0

0x50 pack: time pack

- 0: Not output 0X50 pack
- 1: Output 0X50 pack

0x51 pack: Acceleration pack

- 0: Not output 0x51 pack
- 1: Output 0x51 pack

0x52 pack: Angular velocity pack

- 0: Not output 0x52 packet
- 1: Output 0x52 pack
- 0x53 pack: Angle Pack
 - 0: Not output 0x53 pack
 - 1: Output 0x53 pack
- 0x54 pack: Magnetic Pack
 - 0: Not output 0x54 pack
 - 1: Output 0x54 pack

0x55 pack: Port status pack

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- 0: Not output 0x55 pack
- 1: Output 0x55 pack

0x56 pack: Atmospheric pressure & Height Pack

- 0: Not output 0x56 pack
- 1: Output 0x56 pack
- 0x57 pack: Longitude and Latitude Output Pack
 - 0: Not output 0x57 pack
 - 1: Output 0x57 pack
- 0x58 pack: GPS speed Pack
 - 0: Not output 0x58 pack
 - 1: Output 0x58 pack
- 0x59 pack: Quaternion Pack
 - 0: Not output 0x59 pack
 - 1: Output 0x59 pack
- 0x5A pack: Satellite position accuracy
 - 0: Not output 0x5A pack
 - 1: Output 0x5A pack

7.2.9 Set return rate

	0xFF	0xAA	0x03	RATE	0x00
RATE: retu	Irn rate				
0x01:	0.1Hz				
0x02:	0.5Hz				
0x03:	1Hz				
0x04:	2Hz				
0x05:	5Hz				
0x06:	10Hz (defau	ult)			
0x07:	20Hz				
0x08:	50Hz				
0x09:	100Hz				
0x0a:	125Hz				
0x0b:	200Hz				
0x0c:	Single				
0x0d:	Not output				

After the setup is complete, need to click save, and re-power the module to take effect.



7.2.10 Set baud rate

	0xFF	0xAA	0x04	BAUD	0x00
BAUD:					
0x00:	2400				
0x01:	4800				
0x02:	9600 (defau	lt)			
0x03:	19200				
0x04:	38400				
0x05:	57600				
0x06:	115200				
0x07:	230400				
0x08:	460800				
0x09:	921600				

7.2.11 Set X axis Acceleration bias

0xFF 0xAA 0x05 AXOFFSETL AXOF

AXOFFSETL: X axis Acceleration bias low byte

AXOFFSETH: X axis Acceleration bias high byte

AXOFFSET= (AXOFFSETH <<8) | AXOFFSETL

Note: When set the acceleration bias, the output equal the value of the acceleration sensor output value minus the bias value

7.2.12 Set Y axis Acceleration bias

0xFF	0xAA	0x06	AYOFFSETL	AYOFFSETH
------	------	------	-----------	-----------

AYOFFSETL: Y axis Acceleration bias low byte

AYOFFSETH: Y axis Acceleration bias high byte

AYOFFSET= (AYOFFSETH <<8) | AYOFFSETL

Note: When set the acceleration bias, the output equal the value of the acceleration sensor output value minus the bias value.

7.2.13 Set Z axis Acceleration bias

0xFF	0xAA	0x07	AZOFFSETL	AZOFFSETH
- ·		1 · 1	1 /	

AZOFFSETL: Z axis Acceleration bias low byte

AZOFFSETH: Z axis Acceleration bias high byte

AZOFFSET= (AZOFFSETH <<8) | AZOFFSETL

Note: When set the acceleration bias, the output equal the value of the acceleration sensor output

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value minus the bias value.

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7.2.14 Set X axis Angular velocity bias

0xFF 0xAA 0x08 GXOFFSETL GX	OFFSETH
-----------------------------	---------

GXOFFSETL: Set X axis Angular velocity bias low byte

GXOFFSETH: Set Y axis Angular velocity bias high byte

GXOFFSET= (GXOFFSETH <<8) | GXOFFSETL

Note: When set the Angular velocity bias, the output equal the value of the sensor output value minus the bias value.

7.2.15 Set Y axis Angular velocity bias

	0xFF	0xAA	0x09	GYOFFSETL	GYOFFSETH
--	------	------	------	-----------	-----------

GYOFFSETL: Set X axis Angular velocity bias low byte

GYOFFSETH: Set X axis Angular velocity bias high byte

GYOFFSET= (GYOFFSETH <<8) | GYOFFSETL

Note: When set the Angular velocity bias, the output equal the value of the sensor output value minus the bias value.

7.2.16 Set Z axis Angular velocity bias

	0xFF	0xAA	0x0a	GXOFFSETL	GXOFFSETH
--	------	------	------	-----------	-----------

GZOFFSETL: Set Z axis Angular velocity bias low byte

GZOFFSETH: Set Z axis Angular velocity bias low byte

GZOFFSET= (GZOFFSETH <<8) | GZOFFSETL

Note: When set the Angular velocity bias, the output equal the value of the sensor output value minus the bias value.

7.2.17 Set X axis magnetic bias

	0xFF	0xAA	0x0b	HXOFFSETL	HXOFFSETH
--	------	------	------	-----------	-----------

HXOFFSETL: Set X axis magnetic bias low byte

HXOFFSETH: Set X axis magnetic bias high byte

HXOFFSET= (HXOFFSETH <<8) | HXOFFSETL

Note: When set the magnetic bias, the output equal the value of the sensor output value minus the bias value.



7.2.18 Set Y axis magnetic bias

0xFF	0xAA	0x0c	HXOFFSETL	HXOFFSETH

HXOFFSETL: Set Y axis magnetic bias low byte

HXOFFSETH: Set Y axis magnetic bias high byte

HXOFFSET= (HXOFFSETH <<8) | HXOFFSETL

Note: When set the magnetic bias, the output equal the value of the sensor output value minus the bias value.

7.2.19 Set Z axis magnetic bias

0xFF	0xAA	0x0d	HXOFFSETL	HXOFFSETH

HXOFFSETL: Set Y axis magnetic bias low byte

HXOFFSETH: Set Z axis magnetic bias high byte

HXOFFSET= (HXOFFSETH <<8) | HXOFFSETL

Note: When set the magnetic bias, the output equal the value of the sensor output value minus the bias value.

7.2.20 Set port D0 mode

|--|

D0MODE:

0x00: Analog Input (default)

0x01: Digital Input

0x02: Digital Output high

0x03: Digital Output low

0x04: PWM Output

7.2.21 Set port D1 mode

0xFF 0xAA 0x0f D1MODE 0x00

D1MODE:

0x00: Analog Input (default)

0x01: Digital Input

0x02: Digital Output high

0x03: Digital Output low

- 0x04: PWM Output
- 0x05: Connect to TX of GPS



7.2.22 Set port D2 mode

D2MODE:

0x00: Analog Input (default)

0x01: Digital Input

0x02: Digital Output high

0x03: Digital Output low

0x04: PWM Output

7.2.23 Set port D3 mode

0xFF 0xAA 0x11 D3MODE 0x00	0xFF	0xAA	0x11	D3MODE	0x00
----------------------------	------	------	------	--------	------

D3MODE:

0x00: Analog Input (default)

0x01: Digital Input

0x02: Digital Output high

0x03: Digital Output low

0x04: PWM Output

7.2.24 Set the PWM width of Port D0

0xFF 0xAA	0x12	D0PWMHL	D0PWMHH
-----------	------	---------	---------

D0PWMHL: the PWM width of Port D0 low byte D0PWMHH: the PWM width of Port D0 high byte D0PWMH = (D0PWMHH<<8) | D0PWMHL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.

7.2.25 Set the PWM width of Port D1

	0xFF	0xAA	0x13	D1PWMHL	D1PWMHL
--	------	------	------	---------	---------

D1PWMHL: the PWM width of Port D1 low byte

D1PWMHH: the PWM width of Port D1 high byte

D1PWMH = (D1PWMHH<<8) | D1PWMHL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.



7.2.26 Set the PWM width of Port D2

	0xFF	0xAA	0x14	D2PWMHL	D2PWMHL
--	------	------	------	---------	---------

D2PWMHL: the PWM width of Port D2 low byte

D2PWMHH: the PWM width of Port D2 high byte

D2PWMH = (D2PWMHH<<<8) | D2PWMHL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.

7.2.27 Set the PWM width of Port D3

	0xFF	0xAA	0x15	D3PWMHL	D3PWMHL
--	------	------	------	---------	---------

D3PWMHL: the PWM width of Port D3 low byte

D3PWMHH: the PWM width of Port D3 low byte

D3PWMH = (D3PWMHH<<<8) | D3PWMHL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.

7.2.28 Set period of Port D0

0xFF	0xAA	0x16	D0PWMTL	D0PWMTH

D0PWMTL: PWM period of Port D0 low byte

D0PWMTH: PWM period of Port D0 high byte

D0PWMT = (D0PWMTH<<8) | D0PWMTL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.Period is 20000us, just set D0PWMT 20000.

7.2.29 Set period of Port D1

0xFF 0xAA 0x17 D1PWMTH D1PWMT	
-------------------------------	--

D1PWMTL: PWM period of Port D1 low byte

D1PWMTH: PWM period of Port D1 high byte

D1PWMT = (D1PWMTH<<8) | D1PWMTL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.Period is 20000us, just set D0PWMT 20000.

7.2.30 Set period of Port D2

	0xFF	0xAA	0x18	D2PWMTH	D2PWMTL	
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D2PWMTL: PWM period of Port D2 low byte D2PWMTH: PWM period of Port D2 high byte

D2PWMT = (D2PWMTH<<8) | D2PWMTL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.Period is 20000us, just set D0PWMT 20000.

7.2.31 Set period of Port D3

	0xFF	0xAA	0x19	D3PWMTH	D3PWMTL
--	------	------	------	---------	---------

D3PWMTL: PWM period of Port D3 low byte

D3PWMTH: PWM period of Port D3 high byte

D3PWMT = (D3PWMTH<<8) | D3PWMTL

Note: The unit of PWM high-level width and period is us, such as high-level width is 1500us, just set D0PWMH 1500.Period is 20000us, just set D0PWMT 20000.

7.2.32 Set IIC Address

		0xFF	0xAA	0x1a	IICADDR	0x00
--	--	------	------	------	---------	------

IICADDR:

IIC address of the module, default is 0x50. IIC address using 7bit address, can not exceed the maximum 0x7f. After the setup is complete, need to click save, and re-power the module to take effect.

7.2.33 Set LED

	0xFF	0xAA	0x1b	LEDOFF	0x00
OOFF:					

LED

0x01: Turn off LED 0x00: Turn on LED

7.2.34 Set GPS baud

		-				_
	0xFF	0xAA	0x1c	GPSBAUD	0x00	
GPSBAUD:						•
Baud: T	Time informa	tion pack				
0x00:	2400					
0x01:	4800					
0x02:	9600 (defau	ult)				
0x03:	19200					
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0x04: 38400 0x05: 57600 0x06: 115200 0x07: 230400 0x08: 460800 0x09: 921600

After set it up, you need to save the configuration button and then restart the module.

8 IIC Protocol

JY-901 module can be fully accessed through IIC, the maximum IIC communication speed support 400khz, slave module address is 7bit, default address is 0x50, you can change the command through the serial port or the methods of IIC writing address ways. Many GY-901 modules can be connect to IIC bus at the same time, The precondition is that the module has the different IIC address.

IIC protocol module using the register address accessible way. The length of each address are 16bits, two bytes. The register address is defined in the following table:

RegAddr	Symbol	Meaning
0x00	SAVE	Save
0x01	CALSW	Calibration
0x02	RSW	Return data content
0x03	RATE	Return data Speed
0x04	BAUD	Baud rate
0x05	AXOFFSET	X axis Acceleration bias
0x06	AYOFFSET	Y axis Acceleration bias
0x07	AZOFFSET	Z axis Acceleration bias
0x08	GXOFFSET	X axis angular velocity bias
0x09	GYOFFSET	Y axis angular velocity bias
0x0a	GZOFFSET	Z axis angular velocity bias
0x0b	HXOFFSET	X axis Magnetic bias
0x0c	HYOFFSET	Y axis Magnetic bias
0x0d	HZOFFSET	Z axis Magnetic bias
0x0e	D0MODE	D0 mode
0x0f	D1MODE	D1 mode
0x10	D2MODE	D2 mode
0x11	D3MODE	D3 mode
0x12	D0PWMH	D0PWM High-level width
0x13	D1PWMH	D1PWM High-level width
0x14	D2PWMH	D2PWM High-level width
0x15	D3PWMH	D3PWM High-level width
0x16	D0PWMT	D0PWM Period

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0x17	D1PWMT	D1PWM Period
0x18	D2PWMT	D2PWM Period
0x19	D3PWMT	D3PWM Period
0x1a	IICADDR	IIC address
0x1b	LEDOFF	Turn off LED
0x1c	GPSBAUD	GPS baud rate
0x30	YYMM	Year, Month
0x31	DDHH	Day, Hour
0x32	MMSS	Minute, Second
0x33	MS	Millisecond
0x34	AX	X axis Acceleration
0x35	AY	Y axis Acceleration
0x36	AZ	Z axis Acceleration
0x37	GX	X axis angular velocity
0x38	GY	Y axis angular velocity
0x39	GZ	Z axis angular velocity
0x3a	НХ	X axis Magnetic
0x3b	НҮ	Y axis Magnetic
0x3c	HZ	Z axis Magnetic
0x3d	Roll	X axis Angle
0x3e	Pitch	Y axis Angle
0x3f	Yaw	Z axis Angle
0x40	TEMP	Temperature
0x41	D0Status	D0Status
0x42	D1Status	D1Status
0x43	D2Status	D2Status
0x44	D3Status	D3Status
0x45	PressureL	Pressure Low Byte
0x46	PressureH	Pressure High Byte
0x47	HeightL	Height Low Byte
0x48	HeightH	Height High Byte
0x49	LonL	Longitude Low Byte
0x4a	LonH	Longitude High Byte
0x4b	LatL	Latitude Low Byte
0x4c	LatH	Latitude High Byte
0x4d	GPSHeight	GPS Height
0x4e	GPSYaw	GPS Yaw
0x4f	GPSVL	GPS speed Low byte
0x50	GPSVH	GPS speed High byte
0x51	Q0	Quaternion Q0
0x52	Q1	Quaternion Q1

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0x53	Q2	Quaternion Q2
0x54	Q3	Quaternion Q3

8.1 IIC Write the Module

When IIC	write t	he m	odule,	the	format	is	as	below:	
----------	---------	------	--------	-----	--------	----	----	--------	--

IICAddr<<	RegAddr	Data1L	Data1H	Data2L	Data2H	•••••
1						

First IIC host sends a Start signal to JY-901 module, then write IICAddr to register address and then write RegAddr, write the Data1L Data1H Data2L Data2H Sequentially, , when the last data has been written, the host sends a stop signal to the module to release the IIC bus.

When finish writing the data, the register will be updated and module will execute the order. At the same time, the address of the module will add 1 automatically . The address Pointer will point to next address. So it can be written Continuously

For example:

Set D0 as Digital output high

RegAddr :0x0e DataL:0x02 DataH:0x00

Logic Analyzer captures waveforms as shown below:



Register set up by the module approach is consistent with the serial protocol, please refer 7.1

8.2 IIC Read the Module

IIC read the module, the format is as follow

|--|

First IIC host sends a Start signal to JY-901 module, then write IICAddr to register address, then IIC host sends a read signal(IICAddr<<1)|1) to JY-901 module, if the IIC address is 0x50(default),then the host send 0xa0

Thereafter the module will export the data follow the rule: low byte first, high byte Sequentially. The host will make SDA bus low after receiving each byte, and sends a response signal to the module .After the specified number of data has been received completely, the host stop sending response signal back to the module, then the module will stop export data.The host send a stop signal to end this operation.

For example:



Read the Angle of the module,

RedAddr: 0x3d, read 6 bytes continuously, the logic analyzer captures waveforms as shown below:



Start reading out data from 0x3d,the data is 0x9C, 0x82,0x28,0xFF, 0xE6,0x24. That means X-axis angle is 0x829C, Y-axis angle is 0xFF28, Z-axis angle is 0x24E6. According to section 5.1.4, X axis angle is -176.33 °, Y-axis angle is -1.19 °, Z-axis angle is 51.89 °

9 Application Area



Medical instruments



Internet of things



Construction machinery







Geological monitoring





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JY901 Attitude Angle Sensor

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