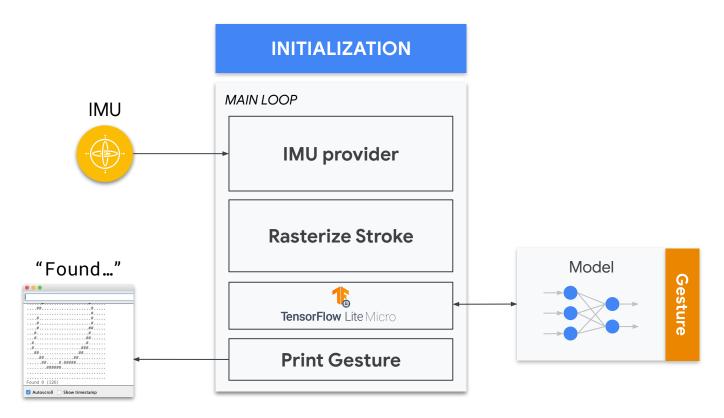
Magic Wand Application Architecture

Magic Wand Components

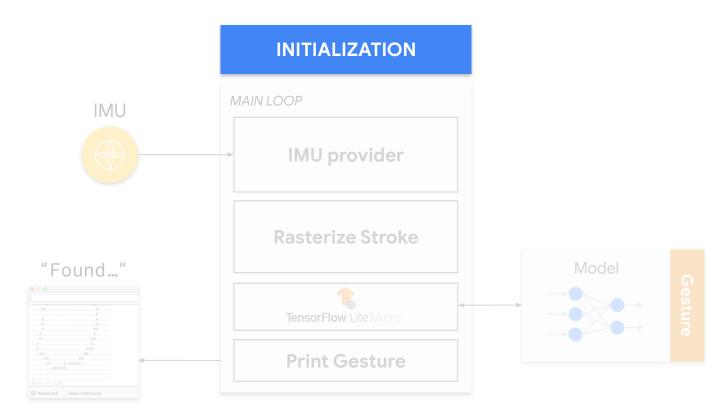
INITIALIZATION

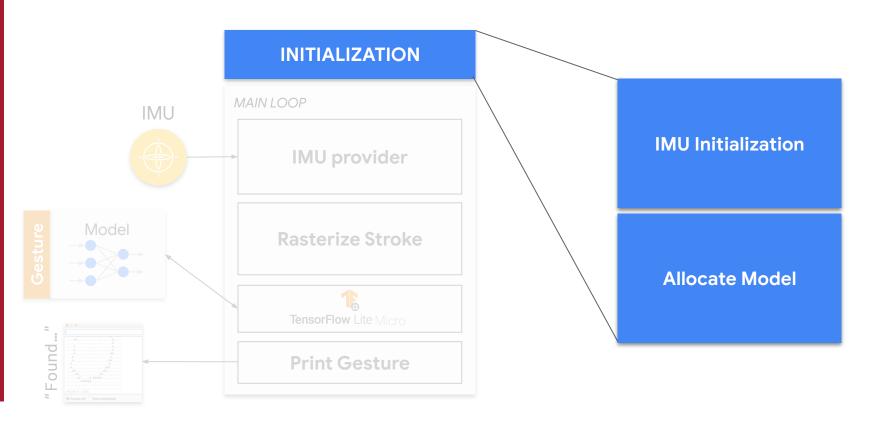
MAIN LOOP

Magic Wand Components



Magic Wand Components





IMU Initialization

Allocate Model

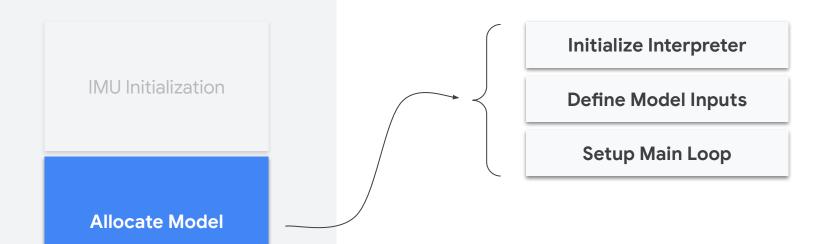
```
// Start IMU
if (!IMU.begin()) {
   Serial.println("Failed to initialize IMU!");
   while (1);
}
SetupIMU();
```

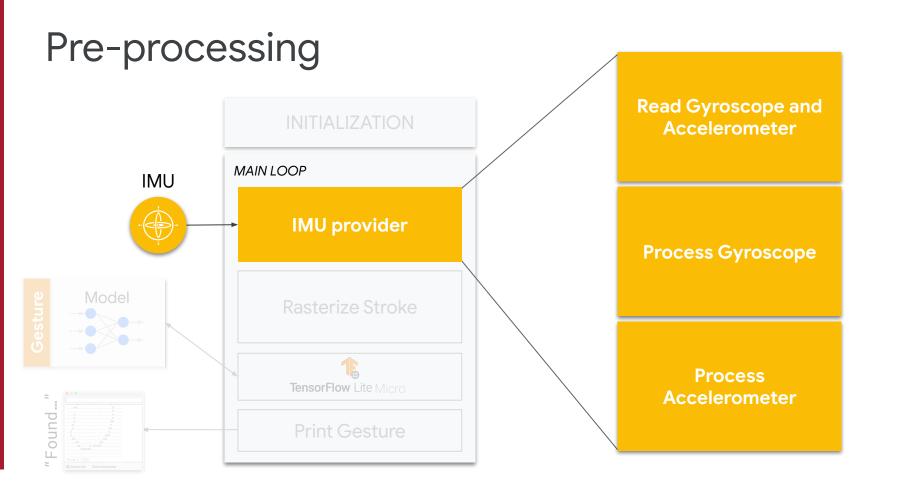
IMU Initialization

Allocate Model

```
void SetupIMU() {
   // Make sure we are pulling measurements into a FIFO.
   IMU.setContinuousMode();

acceleration_sample_rate = IMU.accelerationSampleRate();
   gyroscope_sample_rate = IMU.gyroscopeSampleRate();
}
```





Read Gyroscope and Accelerometer

Process Gyroscope

Read Gyroscope and Accelerometer

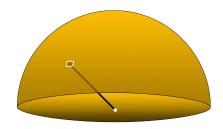
Process Gyroscope

```
Pressure Sensor Drift

1 2 3 4 5 6 7 8 9 10 Years
```

Read Gyroscope and Accelerometer

Process Gyroscope



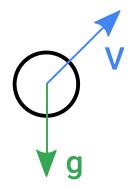
Read Gyroscope and Accelerometer

Process Gyroscope

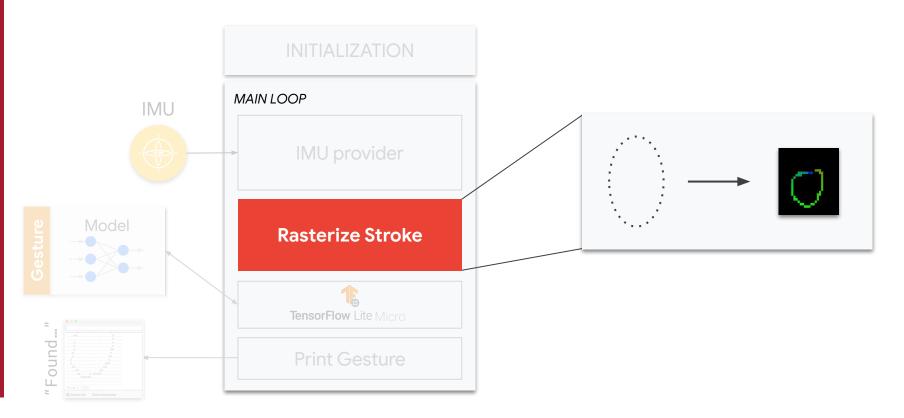


Read Gyroscope and Accelerometer

Process Gyroscope



```
if (accelerometer_samples_read > 0) {
   EstimateGravityDirection(current_gravity);
   UpdateVelocity(accelerometer_samples_read, current_gravity);
}
```

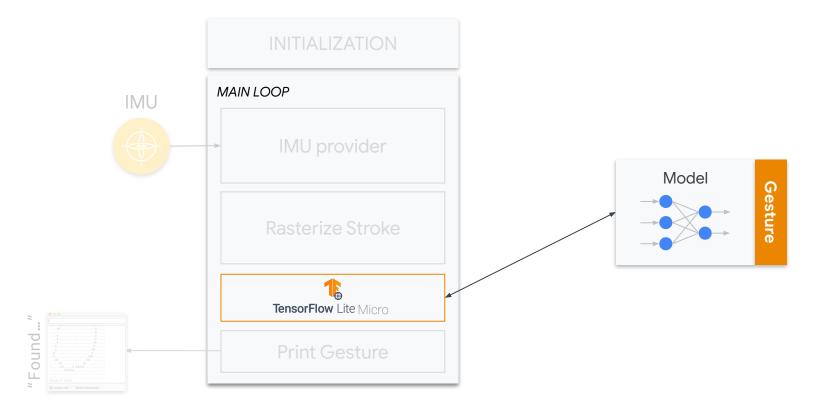


Rasterize

Rasterize Stroke

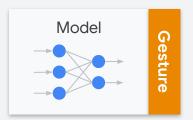


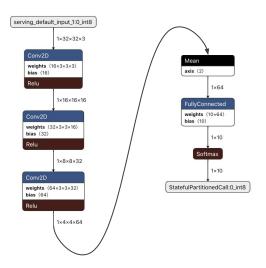
Interpreter + Model



Interpreter + Model

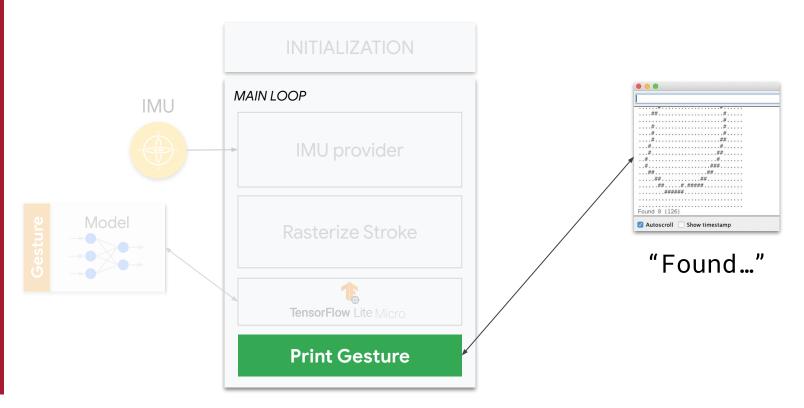






```
// Pass to the model and run the interpreter
TfLiteTensor* model_input = interpreter->input(0);
for (int i = 0; i < raster_byte_count; ++i) {
   model_input->data.int8[i] = raster_buffer[i];
}
TfLiteStatus invoke_status = interpreter->Invoke();
```

Output



Output

Print Gesture

```
// Parse the model output
int8_t max_score;
int max_index;
for (int i = 0; i < label_count; ++i) {
  const int8_t score = output->data.int8[i];
  if ((i == 0) || (score > max_score)) {
    max_score = score;
    max_index = i;
  }
}
TF_LITE_REPORT_ERROR(error_reporter, "Found %s (%d)", labels[max_index], max_score);
```