Precautions for use

1. The IMU module is divided into bare board and metal shell versions. The metal shell version has been installed at the factory. All versions will affect the warranty after welding.
2. After the IMU module is powered on, turn on the host computer to display the 3D model, rotate the Z-axis heading angle of the module, the 3D model shakes, or the response is slow, please perform magnetic calibration on the PC host computer software.
3. The main control boards that support USB communication such as Raspberry Pi and Jetson Nano can be directly connected with the Type-C data cable. STM32 or other microcontrollers that support serial and I2C communication can be connected to the external pins of the IMU module.
4. The default communication baud rate of the IMU module is 9600 bps. If the connected device does not support this communication speed, it can be changed to 4800 bps~921600 bps. Be sure to confirm that the baud rates of the two are the same before they can communicate.
5. If the computer cannot be connected to the host computer after the USB connection module of the computer appears, please confirm whether the serial port driver has been installed.
6. If the module D1 interface is connected to the GPS module to form an inertial navigation unit, the GPS module needs to output the serial port data of the NMEA-0183 standard, and the serial port baud rate of the GPS needs to be set to 115200 bps.
7. The Z-axis angle under the nine-axis algorithm is an absolute angle. The local Cartesian coordinates coordinate system(ENU) is used as the coordinate system, and it cannot be returned to 0. When it rotates to 0 degrees, the direction of the Y-axis is the north.