

First begin communication between imu and arduino.

The make the function that calculate the error reading

Request 6 register and Read values from accelerometer and divide each value by 16384 the previously selected sensitivity in order to get the output in degrees per second.

Then divide it by 1000 number of times imu read the value

Make the same thing for gyroscope

After end this functions begin transmission again and read from accelerometer

Then calculate elapsed time to be in second

Request data from imu from register gyroscope to read x and y only

Then calculate roll and pitch

If one of them more than 60 the led will blink