<table>
<tr><th>Address</th><th>Register Name</th><th>bit</th><th>Default</th><th>Content</th><th>mode</th><th>Dscription</th></tr>
<tr><td>0x00</td><td>BGW_CHIPID</td><td>7-0</td><td>0xF9</td><td>Chip_id</td><td>RO</td><td>The register contains the chip identification code.</td></tr>
<tr><td rowspan="2">0x02</td><td rowspan="2">ACCD_X_LSB</td><td>7-6</td><td>0x00</td><td>acc_x_lsb[0:1]</td><td>RO</td><td>Lest significant 2 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td>0</td><td>0x00</td><td>new_data_x</td><td>RO</td><td>0' : acceleation value has not been updated since it has been read out last
'1' : acceleation value has not been updated since it has been read out last</td></tr>
<tr><td>0x03</td><td>ACCD_X_MSB</td><td>7-0</td><td>0x00</td><td>acc_x_msb[9:2]</td><td>RO</td><td>Most significant 8 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td rowspan="2">0x04</td><td rowspan="2">ACCD_Y_LSB</td><td>7-6</td><td>0x00</td><td>acc_y_lsb[0:1]</td><td>RO</td><td>Lest significant 2 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td>0</td><td>0x00</td><td>new_data_y</td><td>RO</td><td>0' : acceleation value has not been updated since it has been read out last
'1' : acceleation value has not been updated since it has been read out last</td></tr>
<tr><td>0x05</td><td>ACCD_Y_MSB</td><td>7-0</td><td>0x00</td><td>acc_y_msb[9:2]</td><td>RO</td><td>Most significant 8 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td rowspan="2">0x06</td><td rowspan="2">ACCD_Z_LSB</td><td>7-6</td><td>0x00</td><td>acc_z_lsb[0:1]</td><td>RO</td><td>Lest significant 2 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td>0</td><td>0x00</td><td>new_data_z</td><td>RO</td><td>0' : acceleation value has not been updated since it has been read out last
'1' : acceleation value has not been updated since it has been read out last</td></tr>
<tr><td>0x07</td><td>ACCD_Z_MSB</td><td>7-0</td><td>0x00</td><td>acc_z_msb[9:2]</td><td>RO</td><td>Most significant 8 bit of acceleration read-back value
(two's-complement format)</td></tr>
<tr><td>0x0F</td><td>PMU_RANGE</td><td>3-0</td><td>0x03</td><td>range[3:0]</td><td>R/W</td><td>Selection of accelerometer g-range:
'0011b' -> ±2G range
'0101b' -> ±4G range
'1000b' -> ±8G range
'1100b' -> ±16G range
all other setting -> reserved(do not use)</td></tr>
<tr><td>0x10</td><td>PMU_BW</td><td>4-0</td><td>0x0F</td><td>bw[4:0]</td><td>R/W</td><td>Selection of data filter bandwidth:
'00xxxb' -> 7.81 Hz,
'01000b'->7.81 Hz,
'01001b' -> 15.63 Hz,
'01010b' -> 31.25 Hz,
'01011b' -> 62.5 Hz,
'01100b' -> 125 Hz,
'01101b' -> 250 Hz,
'01110b' -> 500 Hz,
'01111b' -> 1000 Hz
'1xxxxb' -> 1000 Hz</td></tr>
<tr><td rowspan="4">0x11</td><td rowspan="4">PMU_LPW</td><td>7</td><td>0x00</td><td>suspend</td><td>R/W</td><td rowspan="4">Main power mode configuration setting
<table><tr><th>Suspend</th><th>lowpower_en</th><th>Deep_suspend</th><th>Mode</th></tr><tr><td>0</td><td>0</td><td>0</td><td>NORMAL mode</td></tr><tr><td>0</td><td>0</td><td>1</td><td>Deep Suspend mode</td></tr><tr><td>0</td><td>1</td><td>0</td><td>Low power mode</td></tr><tr><td>1</td><td>0</td><td>0</td><td>Suspend mode</td></tr><tr><td colspan="3">All ther</td><td>Illegal</td></tr></table></td></tr>
<tr><td>6</td><td>0x00</td><td>lowpower_en</td><td>R/W</td></tr>
<tr><td>5</td><td>0x00</td><td>deep_suspend</td><td>R/W</td></tr>
<tr><td>4-1</td><td>0x00</td><td>Sleep_dur</td><td>R/W</td><td>Configures the sleep phase duration in LOW_POWER mode</td></tr>
<tr><td>0x14</td><td>BGW_SOFTRESET</td><td>7-8</td><td>0x00</td><td>softreset</td><td>WO</td><td>0xB6 -> triggers a reset</td></tr>
<tr><td rowspan="8">0x16</td><td rowspan="8">INT_EN_0</td><td>7</td><td>0x00</td><td>flat_en</td><td>R/W</td><td rowspan="8">'0' -> disable
'1' -> enable</td></tr>
<tr><td>6</td><td>0x00</td><td>orient_en</td><td>R/W</td></tr>
<tr><td>5</td><td>0x00</td><td>S_tap_en</td><td>R/W</td></tr>
<tr><td>4</td><td>0x00</td><td>d_tap_en</td><td>R/W</td></tr>
<tr><td>2</td><td>0x00</td><td>slope_en_z</td><td>R/W</td></tr>
<tr><td>1</td><td>0x00</td><td>slope_en_y</td><td>R/W</td></tr>
<tr><td>0</td><td>0x00</td><td>slope_en_x</td><td>R/W</td></tr>
<tr><td rowspan="8">0x17</td><td rowspan="8">INT_EN_1</td><td>6</td><td>0x00</td><td>int_fwm_en</td><td>R/W</td><td rowspan="8">'0' -> disable
'1' -> enable</td></tr>
<tr><td>5</td><td>0x00</td><td>int_ffull_en</td><td>R/W</td></tr>
<tr><td>4</td><td>0x00</td><td>data_en</td><td>R/W</td></tr>
<tr><td>3</td><td>0x00</td><td>low_en</td><td>R/W</td></tr>
<tr><td>2</td><td>0x00</td><td>high_en_z</td><td>R/W</td></tr>
<tr><td>1</td><td>0x00</td><td>high_en_y</td><td>R/W</td></tr>
<tr><td>0</td><td>0x00</td><td>high_en_x</td><td>R/W</td></tr>
<tr><td rowspan="4">0x18</td><td rowspan="4">INT_EN_2</td><td>3</td><td>0x00</td><td>low_en</td><td>R/W</td><td>'0' -> slow-motion
'1' -> no-motion interrupt function</td></tr>
<tr><td>2</td><td>0x00</td><td>high_en_z</td><td>R/W</td><td rowspan="3">'0' -> disable
'1' -> enable</td></tr>
<tr><td>1</td><td>0x00</td><td>high_en_y</td><td>R/W</td></tr>
<tr><td>0</td><td>0x00</td><td>high_en_x</td><td>R/W</td></tr>
</table>

RO : Read Only
WO : Write Only
R/W : Read and Write