

Orientation Tracking

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I. INTRODUCTION

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II. PRE-PROCESSING

The raw IMU data we get is 10-bit ADC values, which technically ranges from 0 to 1023. Since it's difficult to use those values directly in our filter, we have to convert them so that

they have real-world physical units and meanings. Our goal here is to convert the readings from the micro-controller to acceleration with a unit of m/s^2 and angular velocity with a unit of rad/s .

III. METHODS

IV. DISCUSSION

*A thank you or further information