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Ultra-compact high-performance eCompass module: ultra-low-power 3D accelerometer and 3D magnetometer

Datasheet - production data



Features

- 3 magnetic field channels and 3 acceleration channels
- ± 50 gauss magnetic dynamic range
- $\pm 2/\pm 4/\pm 8/\pm 16$ g selectable acceleration full scales
- Anti-aliasing filter
- 16-bit data output
- SPI / I²C serial interfaces
- Analog supply voltage 1.71 V to 1.98 V
- Programmable interrupt generators for free-fall, motion and magnetic field detection
- Embedded self-test
- Embedded 256-level FIFO
- Embedded temperature sensor
- Embedded digital functions: step detector, step counter, significant motion and tilt
- ECOPACK[®], RoHS and “Green” compliant

Applications

- Tilt-compensated compasses
- Map rotation
- Position and free-fall detection
- Motion-activated functions
- Click/double-click recognition
- Pedometers
- Intelligent power saving for handheld devices
- Display orientation
- Gaming and virtual reality input devices
- Impact recognition and logging
- Vibration monitoring and compensation

Description

The LSM303AH is an ultra-low-power high-performance system-in-package featuring a 3D digital linear acceleration sensor and a 3D digital magnetic sensor.

The LSM303AH has user-selectable linear acceleration full scales of $\pm 2g/\pm 4g/\pm 8g/\pm 16$ g and is capable of measuring accelerations with output data rates from 1 Hz to 6400 Hz. The device has a magnetic field dynamic range of ± 50 gauss with output data rates from 10 Hz to 100 Hz. The LSM303AH includes an I²C serial bus interface that supports standard, fast mode, fast mode plus, and high-speed (100 kHz, 400 kHz, 1 MHz, and 3.4 MHz) and an SPI serial standard interface.

The LSM303AH has an integrated 256-level first-in, first-out (FIFO) buffer allowing the user to store data in order to limit intervention by the host processor. The FIFO buffer applies only to the accelerometer.

The embedded self-test capability allows the user to check the functioning of the sensor in the final application.

The system can be configured to generate an interrupt signal for free-fall, motion detection and magnetic field detection. The magnetic and accelerometer blocks can be enabled or put into power-down mode separately.

The LSM303AH is available in a plastic land grid array package (LGA) and is guaranteed to operate over an extended temperature range from -40 °C to $+85$ °C.

Table 1. Device summary

Part number	Temp. range [°C]	Package	Packaging
LSM303AH	-40 to +85	LGA-12	Tray
LSM303AHTR	-40 to +85	LGA-12	Tape and reel

Contents

- 1 Block diagram and pin description 10**
 - 1.1 Block diagram 10
 - 1.2 Pin description 11

- 2 Module specifications 13**
 - 2.1 Sensor characteristics 13
 - 2.2 Temperature sensor characteristics 15
 - 2.3 Electrical characteristics 15
 - 2.4 Communication interface characteristics 16
 - 2.4.1 SPI - serial peripheral interface 16
 - 2.4.2 I²C - inter-IC control interface 17
 - 2.5 Absolute maximum ratings 19

- 3 Terminology 20**
 - 3.1 Sensitivity 20
 - 3.1.1 Linear acceleration sensor sensitivity 20
 - 3.1.2 Magnetic sensor sensitivity 20
 - 3.2 Zero-g level 20
 - 3.3 Zero-gauss level 20
 - 3.4 Magnetic dynamic range 20

- 4 Functionality 21**
 - 4.1 Magnetometer 21
 - 4.1.1 Magnetometer power modes 21
 - 4.1.2 Magnetometer offset cancellation 23
 - 4.1.3 Magnetometer interrupt 23
 - 4.1.4 Magnetometer hard-iron compensation 25
 - 4.1.5 Magnetometer self-test 25
 - 4.2 Accelerometer 27
 - 4.2.1 Accelerometer power modes 27
 - 4.2.2 Accelerometer 6D / 4D orientation detection 29
 - 4.2.3 Accelerometer activity/inactivity function 29
 - 4.2.4 Accelerometer self-test 29

4.2.5	Accelerometer data stabilization time vs. ODR setting	31
4.2.6	Accelerometer anti-aliasing filter	31
4.3	IC interface	31
4.4	FIFO	32
4.4.1	Bypass mode	32
4.4.2	FIFO mode	33
4.4.3	Continuous mode	33
4.4.4	Continuous-to-FIFO mode	33
4.4.5	Bypass-to-Continuous mode	35
4.4.6	Module-to-FIFO	36
4.5	Embedded functions	36
4.5.1	Step detector/Step counter	37
4.5.2	Significant motion	37
4.6	Factory calibration	38
5	Application hints	39
5.1	Soldering information	40
5.2	High-current wiring effects	40
6	Digital interfaces	41
6.1	I ² C serial interface	41
6.1.1	I ² C operation	42
6.2	SPI bus interface	44
6.2.1	Accelerometer SPI write	45
6.2.2	Accelerometer SPI read in 3-wire mode	46
6.2.3	Magnetometer SPI write	46
6.2.4	Magnetometer SPI read in 3-wire mode	47
7	Register mapping	48
8	Register description	51
8.1	Module_8bit_A (0Ch)	51
8.2	WHO_AM_I_A (0Fh)	51
8.3	CTRL1_A (20h)	51
8.4	CTRL2_A (21h)	52
8.5	CTRL3_A (22h)	53

8.6	CTRL4_A (23h)	54
8.7	CTRL5_A (24h)	55
8.8	FIFO_CTRL_A (25h)	56
8.9	OUT_T_A (26h)	57
8.10	STATUS_A (27h)	57
8.11	OUT_X_L_A (28h)	58
8.12	OUT_X_H_A (29h)	58
8.13	OUT_Y_L_A (2Ah)	58
8.14	OUT_Y_H_A (2Bh)	58
8.15	OUT_Z_L_A (2Ch)	59
8.16	OUT_Z_H_A (2Dh)	59
8.17	FIFO_THS_A (2Eh)	59
8.18	FIFO_SRC_A (2Fh)	59
8.19	FIFO_SAMPLES_A (30h)	60
8.20	TAP_6D_THS_A (31h)	60
8.21	INT_DUR_A (32h)	61
8.22	WAKE_UP_THS_A (33h)	61
8.23	WAKE_UP_DUR_A (34h)	62
8.24	FREE_FALL_A (35h)	62
8.25	STATUS_DUP_A (36h)	63
8.26	WAKE_UP_SRC_A (37h)	64
8.27	TAP_SRC_A (38h)	64
8.28	6D_SRC_A (39h)	65
8.29	STEP_COUNTER_MINTHS_A (3Ah)	65
8.30	STEP_COUNTER_L_A (3Bh)	66
8.31	STEP_COUNTER_H_A (3Ch)	66
8.32	FUNC_CK_GATE_A (3Dh)	66
8.33	FUNC_SRC_A (3Eh)	67
8.34	FUNC_CTRL_A (3Fh)	68
8.35	OFFSET_X_REG_L_M (45h) and OFFSET_X_REG_H_M (46h)	68
8.36	OFFSET_Y_REG_L_M (47h) and OFFSET_Y_REG_H_M (48h)	68
8.37	OFFSET_Z_REG_L_M (49h) and OFFSET_Z_REG_H_M (4Ah)	68
8.38	WHO_AM_I_M (4Fh)	68

8.39	CFG_REG_A_M (60h)	69
8.40	CFG_REG_B_M (61h)	70
8.41	CFG_REG_C_M (62h)	71
8.42	INT_CTRL_REG_M (63h)	71
8.43	INT_SOURCE_REG_M (64h)	72
8.44	INT_THS_L_REG_M (65h)	72
8.45	INT_THS_H_REG_M (66h)	72
8.46	STATUS_REG_M (67h)	73
8.47	OUTX_L_REG_M, OUTX_H_REG_M (68h - 69h)	73
8.48	OUTY_L_REG_M, OUTY_H_REG_M (6Ah - 6Bh)	74
8.49	OUTZ_L_REG_M, OUTZ_H_REG_M (6Ch - 6Dh)	74
9	Advanced configuration register mapping	75
10	Advanced configuration registers description	76
10.1	PEDO_DEB_REG_A (2Bh)	76
10.2	SM_THS_A (34h)	76
10.3	STEP_COUNT_DELTA_A (3Ah)	76
10.4	CTRL2_A (3Fh)	77
11	Package information	78
11.1	LGA-12 package information	78
11.2	LGA-12 packing information	79
12	Revision history	81

List of tables

Table 1.	Device summary	1
Table 2.	Pin description	12
Table 3.	Sensor characteristics	13
Table 4.	Temperature sensor characteristics	15
Table 5.	Electrical characteristics	15
Table 6.	SPI slave timing values	16
Table 7.	I ² C slave timing values (standard and fast mode)	17
Table 8.	I ² C slave timing values (fast mode plus and high speed)	17
Table 9.	Absolute maximum ratings	19
Table 10.	RMS noise of operating modes	21
Table 11.	Current consumption of operating modes	21
Table 12.	Operating mode and turn-on time	22
Table 13.	Maximum ODR in single measurement mode (HR and LP modes)	22
Table 14.	Accelerometer operating modes	27
Table 15.	Low-pass filter in low-power, high-resolution and high-frequency modes	28
Table 16.	Current consumption of operating modes	28
Table 17.	Number of samples to be discarded	31
Table 18.	ODR function settings	36
Table 19.	Pin status	40
Table 20.	Serial interface pin description	41
Table 21.	I ² C terminology	41
Table 22.	Transfer when master is writing one byte to slave	42
Table 23.	Transfer when master is writing multiple bytes to slave	42
Table 24.	Transfer when master is receiving (reading) one byte of data from slave	42
Table 25.	Transfer when master is receiving (reading) multiple bytes of data from slave	43
Table 26.	SAD+Read/Write patterns	43
Table 27.	SAD + Read/Write patterns	43
Table 28.	Register map	48
Table 29.	Module_8bit_A register	51
Table 30.	Module_8bit_A register description	51
Table 31.	WHO_AM_I_A register default values	51
Table 32.	CTRL1_A register	51
Table 33.	CTRL1_A register description	51
Table 34.	ODR register setting: power down (PD) and low power (LP)	51
Table 35.	ODR register setting: high resolution (HR) and high frequencies (HF)	52
Table 36.	CTRL2_A register	52
Table 37.	CTRL2_A register description	53
Table 38.	CTRL3_A register	53
Table 39.	CTRL3_A register description	53
Table 40.	Self-test mode selection	54
Table 41.	CTRL4_A register	54
Table 42.	CTRL4_A register description	54
Table 43.	CTRL5_A register	55
Table 44.	CTRL5_A register description	55
Table 45.	FIFO_CTRL_A register	56
Table 46.	FIFO_CTRL_A register description	56
Table 47.	FIFO mode selection	56
Table 48.	OUT_T_A register	57

Table 49.	OUT_T_A register description	57
Table 50.	STATUS_A register	57
Table 51.	STATUS_A register description	57
Table 52.	OUT_X_L_A register default values	58
Table 53.	OUT_X_H_A register default values	58
Table 54.	OUT_Y_L_A register default values	58
Table 55.	OUT_Y_H_A register default values	58
Table 56.	OUT_Z_L_A register default values	59
Table 57.	OUT_Z_H_A register default values	59
Table 58.	FIFO_THS_A register	59
Table 59.	FIFO_SRC_A register	59
Table 60.	FIFO_SRC register description	60
Table 61.	FIFO_SAMPLES_A register	60
Table 62.	FIFO_SAMPLES_A register description	60
Table 63.	TAP_6D_THS_A register	60
Table 64.	TAP_6D_THS_A register description	60
Table 65.	4D/6D threshold setting FS @ 2 g	60
Table 66.	INT_DUR_A register	61
Table 67.	INT_DUR_A register description	61
Table 68.	WAKE_UP_THS_A register	61
Table 69.	WAKE_UP_THS_A register description	61
Table 70.	WAKE_UP_DUR_A register	62
Table 71.	WAKE_UP_DUR_A register description	62
Table 72.	FREE_FALL_A register	62
Table 73.	FREE_FALL_A register description	62
Table 74.	FREE_FALL_A threshold decoding @ 2 g FS	62
Table 75.	STATUS_DUP_A register	63
Table 76.	STATUS_DUP_A register description	63
Table 77.	WAKE_UP_SRC_A register	64
Table 78.	WAKE_UP_SRC_A register description	64
Table 79.	TAP_SRC_A register	64
Table 80.	TAP_SRC_A register description	64
Table 81.	6D_SRC_A register	65
Table 82.	6D_SRC_A register description	65
Table 83.	STEP_COUNTER_MINTHS_A configuration register	65
Table 84.	STEP_COUNTER_MINTHS_A configuration register description	65
Table 85.	STEP_COUNTER_L_A configuration register	66
Table 86.	STEP_COUNTER_L_A configuration register description	66
Table 87.	STEP_COUNTER_H_A register	66
Table 88.	STEP_COUNTER_H_A register description	66
Table 89.	FUNC_CK_GATE_A register	66
Table 90.	FUNC_CK_GATE_A register description	67
Table 91.	FUNC_SRC_A register	67
Table 92.	FUNC_SRC_A register description	67
Table 93.	FUNC_CTRL_A register	68
Table 94.	FUNC_CTRL_A register description	68
Table 95.	CFG_REG_A_M register	69
Table 96.	CFG_REG_A_M register description	69
Table 97.	Output data rate configuration	69
Table 98.	System mode	69
Table 99.	CFG_REG_B_M register	70
Table 100.	CFG_REG_B_M register description	70

Table 101.	Digital low-pass filter	70
Table 102.	CFG_REG_C_M register	71
Table 103.	CFG_REG_C_M register description	71
Table 104.	INT_CTRL_REG_M register	71
Table 105.	INT_CTRL_REG_M register description	71
Table 106.	INT_SOURCE_REG_M register	72
Table 107.	INT_SOURCE_REG_M register description	72
Table 108.	INT_THS_L_REG_M register	72
Table 109.	INT_THS_L_REG_M register description	72
Table 110.	INT_THS_H_REG_M register	72
Table 111.	INT_THS_H_REG_M register description	72
Table 112.	STATUS_REG_M register	73
Table 113.	STATUS_REG_M register description	73
Table 114.	OUTX_L_REG_M register	73
Table 115.	OUTX_H_REG_M register	73
Table 116.	OUTY_L_REG_M register	74
Table 117.	OUTY_H_REG_M register	74
Table 118.	OUTZ_L_REG_M register	74
Table 119.	OUTZ_H_REG_M register	74
Table 120.	Register map - advanced configuration functions	75
Table 121.	PEDO_DEB_REG_A register default values	76
Table 122.	PEDO_DEB_REG_A register description	76
Table 123.	SM_THS_A configuration register	76
Table 124.	SM_THS_A configuration register description	76
Table 125.	STEP_COUNT_DELTA_A configuration register	76
Table 126.	STEP_COUNT_DELTA_A configuration register description	76
Table 127.	CTRL2_A configuration register	77
Table 128.	CTRL2_A configuration register description	77
Table 129.	Reel dimensions for carrier tape of LGA-12 package	80
Table 130.	Document revision history	81

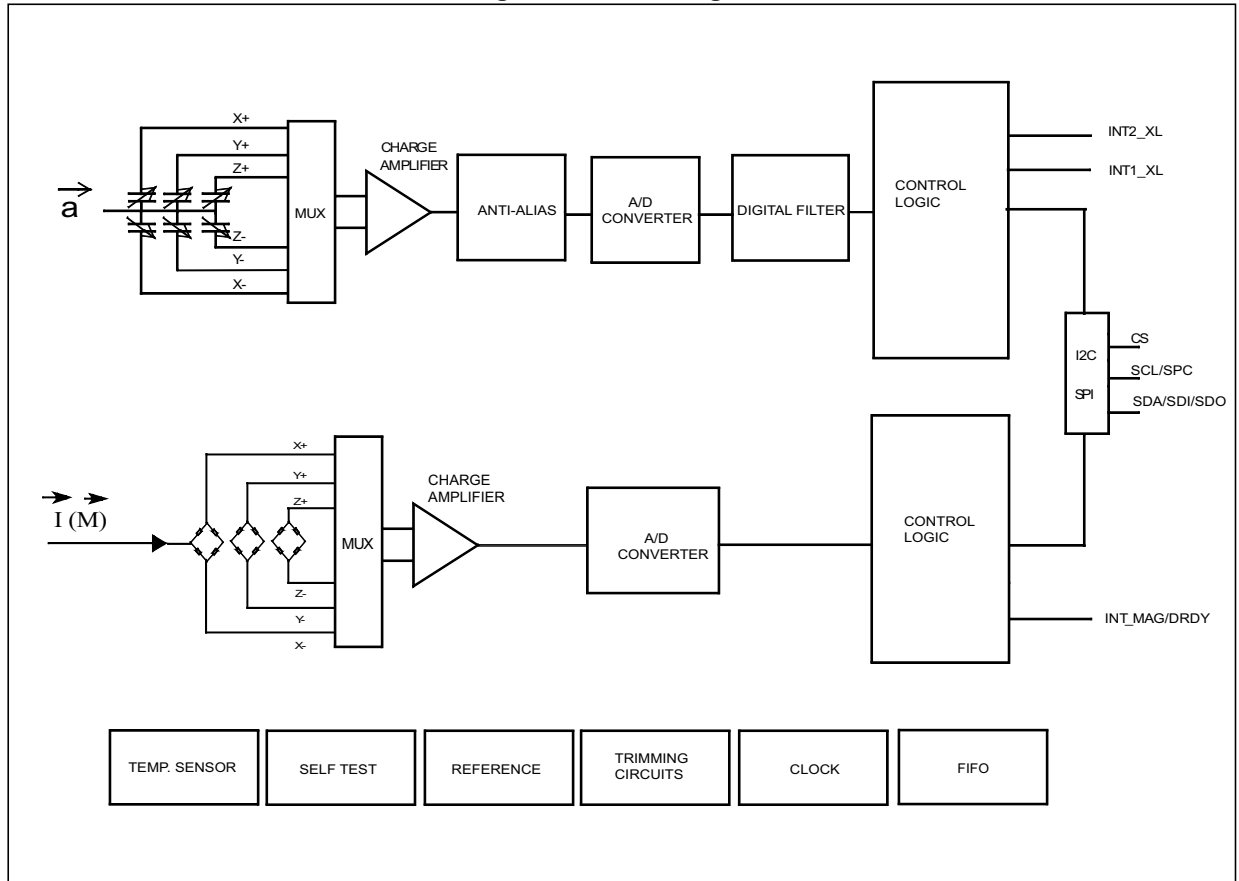
List of figures

Figure 1.	Block diagram	10
Figure 2.	Pin connections	11
Figure 3.	SPI slave timing diagram	16
Figure 4.	I ² C slave timing diagram	18
Figure 5.	Interrupt function	24
Figure 6.	Magnetometer self-test procedure	26
Figure 7.	Accelerometer self-test procedure	30
Figure 8.	Continuous-to-FIFO mode	33
Figure 9.	Trigger event to FIFO for Continuous-to-FIFO mode	34
Figure 10.	Bypass-to-Continuous mode.	35
Figure 11.	Trigger event to FIFO for Bypass-to-Continuous mode	35
Figure 12.	Module-to-FIFO mode example	36
Figure 13.	LSM303AH electrical connections	39
Figure 14.	Read and write protocol	44
Figure 15.	Accelerometer SPI write protocol	45
Figure 16.	Accelerometer multiple byte SPI write protocol (2-byte example)	45
Figure 17.	Accelerometer SPI read protocol in 3-wire mode	46
Figure 18.	Magnetometer SPI write protocol	46
Figure 19.	Magnetometer multiple byte SPI write protocol (2-byte example)	47
Figure 20.	Magnetometer SPI read protocol in 3-wire mode	47
Figure 21.	LGA-12 2x2x1 mm package outline and mechanical data	78
Figure 22.	Carrier tape information for LGA-12 package.	79
Figure 23.	LGA-12 package orientation in carrier tape	79
Figure 24.	Reel information for carrier tape of LGA-12 package	80

1 Block diagram and pin description

1.1 Block diagram

Figure 1. Block diagram



1.2 Pin description

Figure 2. Pin connections

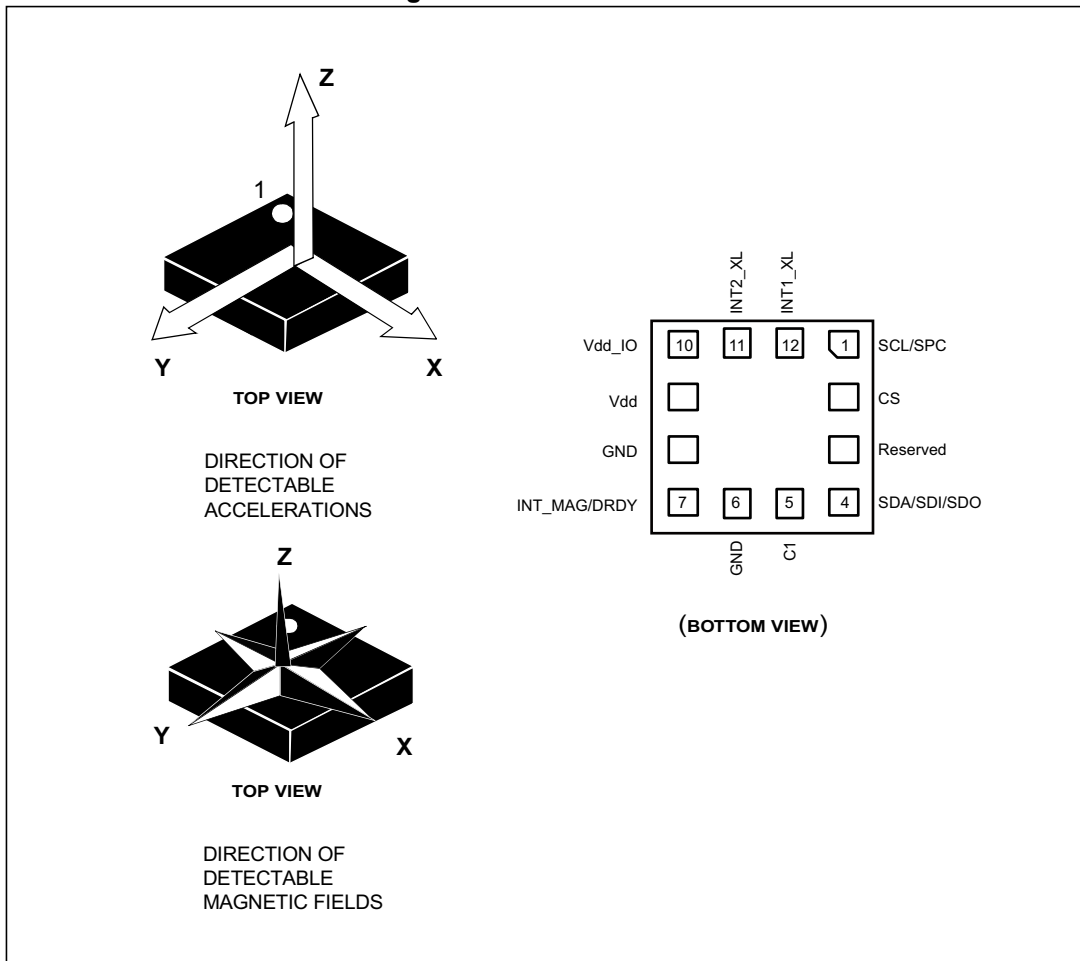


Table 2. Pin description

Pin#	Name	Function
1	SCL SPC	I ² C serial clock (SCL) SPI serial port clock (SPC)
2	CS	SPI enable I ² C/SPI mode selection 1: SPI idle mode / I ² C communication enabled; 0: SPI communication mode / I ² C disabled
3	Reserved	Reserved, connected to GND
4	SDA SDI SDO	I ² C serial data (SDA) SPI serial data input (SDI) 3-wire interface serial data output (SDO)
5	C1	Capacitor connection (C1 = 220 nF)
6	GND	0 V
7	INT_MAG/DRDY	Magnetometer interrupt/data-ready signal
8	GND	0 V
9	Vdd	Power supply
10	Vdd_IO	Power supply for I/O pins
11	INT2_XL	Accelerometer interrupt 2
12	INT1_XL	Accelerometer interrupt 1

2 Module specifications

2.1 Sensor characteristics

@ Vdd = 1.8 V, T = 25 °C unless otherwise noted ^(a).

Table 3. Sensor characteristics

Symbol	Parameter	Test conditions	Min.	Typ. ⁽¹⁾	Max.	Unit
LA_FS	Linear acceleration measurement range			±2		g
				±4		
				±8		
				±16		
M_FS	Magnetic dynamic range		±49.152		gauss	
LA_So	Sensitivity 16-bit ⁽²⁾	@ FS ±2 g		0.061		mg/digit
		@ FS ±4 g		0.122		
		@ FS ±8 g		0.244		
		@ FS ±16 g		0.488		
M_So	Magnetic sensitivity		1.5		mgauss/LSB	
LA_TCSO	Linear acceleration sensitivity change vs. temperature ⁽³⁾			0.01		%/°C
M_TCSO	Magnetic sensitivity change vs. temperature ⁽³⁾			±0.03		%/°C
LA_TyOff	Typical zero-g level offset accuracy ⁽⁴⁾⁽⁵⁾			±30		mg
M_TyOff	Magnetic sensor offset	With offset cancellation ⁽⁶⁾⁽⁷⁾		0		mgauss
LA_TCOff	Zero-g level change vs. temp. ⁽³⁾	Max. delta from 25 °C		±0.2		mg/°C
M_TCOff	Magnetic sensor offset change vs. temp.	With offset cancellation ⁽⁶⁾	-0.3		+0.3	mgauss/°C
LA_An	Linear acceleration RMS noise	ODR = 50 Hz, High-Resolution mode, FS = ±2 g		0.6		mg (RMS)
M_R	Magnetic RMS noise ⁽⁸⁾	High-performance mode		3		mgauss (RMS)
ST	Self-test positive difference ⁽⁹⁾ (accelerometer only)		70		1500	mg
M_ST	Magnetic self-test ⁽¹⁰⁾		15		500	mgauss
Top	Operating temperature range		-40		+85	°C

1. Typical specifications are not guaranteed.

a. The product is factory calibrated at 1.8 V. The operational power supply range is from 1.71 V to 1.98 V.

2. Sensitivity calculated at 16-bit.
3. Measurements are performed in a uniform temperature setup and they are based on characterization data in a limited number of samples, not measured during final test for production.
4. Typical zero-g level offset value after MSL3 preconditioning.
5. Offset can be eliminated by enabling the slope filter.
6. Based on characterization data on a limited number of samples, not measured during final test for production.
7. Excluding drift due to magnetic shock.
8. With low-pass filter or offset cancellation enabled.
9. "Self-test positive difference" is defined as: $\text{OUTPUT}[\text{mg}]_{(\text{CTRL3 ST2, ST1 bits}=01)} - \text{OUTPUT}[\text{mg}]_{(\text{CTRL3 ST2, ST1 bits}=00)}$.
10. Magnetic "self-test" is defined as $\text{OUTPUT}[\text{gauss}]_{(\text{self-test enabled})} - \text{OUTPUT}[\text{gauss}]_{(\text{self-test disabled})}$.

2.2 Temperature sensor characteristics

@ Vdd = 1.8 V, T = 25 °C unless otherwise noted ^(b).

Table 4. Temperature sensor characteristics

Symbol	Parameter	Test conditions	Min.	Typ. ⁽¹⁾	Max.	Unit
TSDr	Temperature sensor output change vs. temp.			1		digit/°C ⁽²⁾
TODR	Temperature refresh rate			12.5		Hz
Top	Operating temperature range		-40		+85	°C

1. Typical specifications are not guaranteed.
2. 8-bit resolution.

2.3 Electrical characteristics

@ Vdd = 1.8 V, T = 25 °C unless otherwise noted. ^(b)

Table 5. Electrical characteristics

Symbol	Parameter	Test conditions	Min.	Typ. ⁽¹⁾	Max.	Unit
Vdd	Supply voltage		1.71		1.98	V
Vdd_IO	Module power supply for I/O ⁽²⁾		1.71	1.8	Vdd+0.1	V
LA_Idd_HR	Accelerometer current consumption in high-resolution mode. Magnetic sensor in power-down.	12.5Hz-6400Hz ODR range		162		µA
LA_Idd_LP	Accelerometer current consumption in low-power mode. Magnetic sensor in power-down.	100 Hz ODR		16		µA
		50 Hz ODR		10		µA
		12.5 Hz ODR		6		µA
		1 Hz ODR		4.5		µA
M_Idd_HR	Magnetic current consumption in high-resolution mode. Accelerometer in power-down mode.	ODR = 20 Hz		200		µA
M_Idd_LP	Magnetic current consumption in low-power mode. Linear accel. in power-down mode.	ODR = 20 Hz		50		µA
Idd_PD	Current consumption in power-down			2.5		µA
VIH	Digital high-level input voltage		0.8*Vdd_IO			V
VIL	Digital low-level input voltage				0.2*Vdd_IO	V
VOH	High-level output voltage	IOH = 4 mA	Vdd_IO - 0.2			V
VOL	Low-level output voltage	IOL = 4 mA			0.2	V
T _{OP}	Operating temperature range		-40		+85	°C

1. Typical specifications are not guaranteed.
2. It is possible to remove Vdd maintaining Vdd_IO without blocking the communication bus, in this condition the measurement chain is powered off.

b. The product is factory calibrated at 1.8 V. The operational power supply range is from 1.71 V to 1.98 V.

2.4 Communication interface characteristics

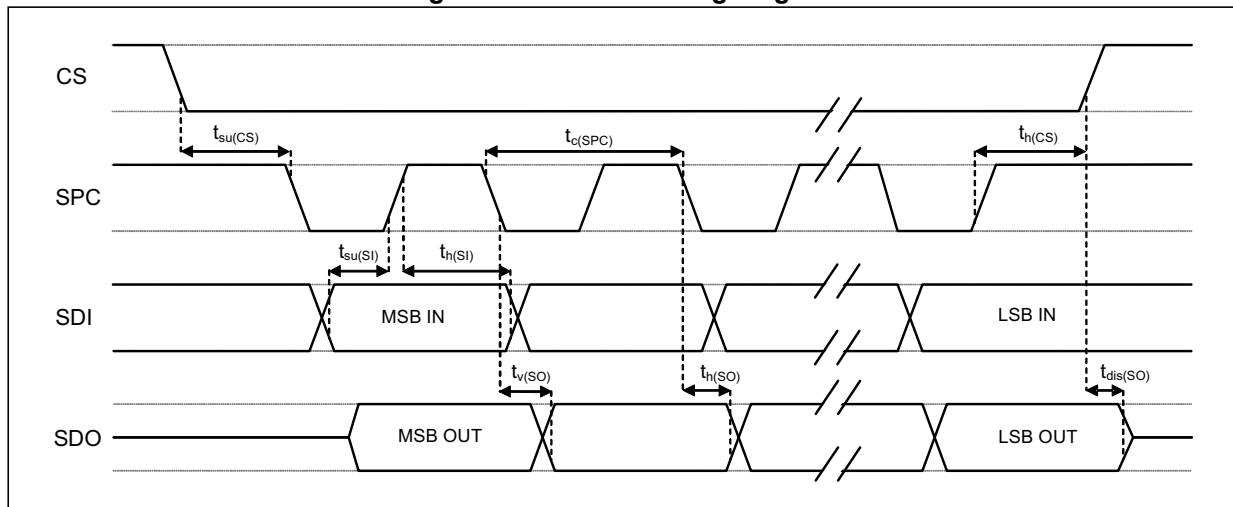
2.4.1 SPI - serial peripheral interface

Subject to general operating conditions for Vdd and Top.

Table 6. SPI slave timing values

Symbol	Parameter	Value ⁽¹⁾		Unit
		Min	Max	
$t_{c(SPC)}$	SPI clock cycle	100		ns
$f_{c(SPC)}$	SPI clock frequency		10	MHz
$t_{su(CS)}$	CS setup time	5		ns
$t_{h(CS)}$	CS hold time	20		
$t_{su(SI)}$	SDI input setup time	5		
$t_{h(SI)}$	SDI input hold time	15		
$t_{v(SO)}$	SDO valid output time		50	
$t_{h(SO)}$	SDO output hold time	5		
$t_{dis(SO)}$	SDO output disable time		50	

Figure 3. SPI slave timing diagram



Note: Values are guaranteed at 10 MHz clock frequency for SPI with 3 wires, based on characterization results, not tested in production.
 Measurement points are done at $0.2 \cdot V_{dd_IO}$ and $0.8 \cdot V_{dd_IO}$, for both input and output ports.

2.4.2 I²C - inter-IC control interface

Subject to general operating conditions for Vdd and Top.

Table 7. I²C slave timing values (standard and fast mode)

Symbol	Parameter	I ² C standard mode ⁽¹⁾		I ² C fast mode ⁽¹⁾		Unit
		Min	Max	Min	Max	
f _(SCL)	SCL clock frequency	0	100	0	400	kHz
t _{w(SCLL)}	Low period of the SCL clock	4.7		1.3		μs
t _{w(SCLH)}	High period of the SCL clock	4.0		0.6		
t _{su(SDA)}	Data setup time	250		100		ns
t _{h(SDA)}	Data hold time	0	3.45	0	0.9	μs
t _{h(ST)}	START condition hold time	4		0.6		
t _{su(SR)}	Setup time for a repeated START condition	4.7		0.6		
t _{su(SP)}	Setup time for STOP condition	4		0.6		
t _{w(SP:SR)}	Bus free time between STOP and START condition	4.7		1.3		

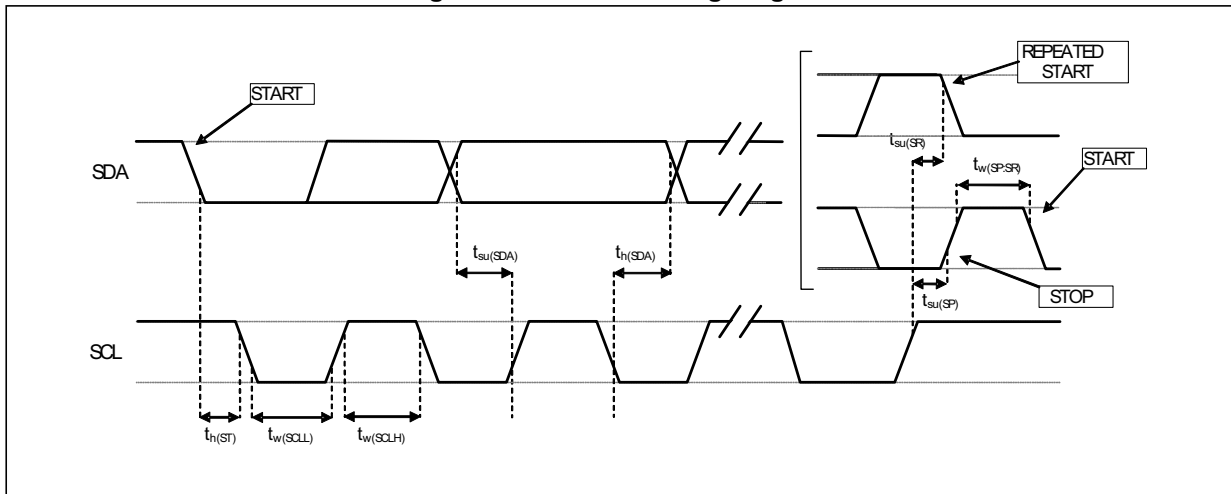
1. Data based on standard I²C protocol requirement, not tested in production.

Table 8. I²C slave timing values (fast mode plus and high speed)

Symbol	Parameter	I ² C fast mode plus ⁽¹⁾		I ² C high speed ⁽¹⁾		Unit
		Min	Max	Min	Max	
f _(SCL)	SCL clock frequency	0	1	0	3.4	MHz
t _{w(SCLL)}	Low period of the SCL clock	0.5		0.16		μs
t _{w(SCLH)}	High period of the SCL clock	0.26		0.06		
t _{su(SDA)}	Data setup time	50		10		ns
t _{h(SDA)}	Data hold time	0		0	0.07	μs
t _{h(ST)}	START condition hold time	0.26		0.16		
t _{su(SR)}	Setup time for a repeated START condition	0.26		0.16		
t _{su(SP)}	Setup time for STOP condition	0.26		0.16		
t _{w(SP:SR)}	Bus free time between STOP and START condition	0.5				

1. Data based on standard I²C protocol requirement, not tested in production.

Figure 4. I²C slave timing diagram



Note: Measurement points are done at $0.2 \cdot V_{dd_IO}$ and $0.8 \cdot V_{dd_IO}$, for both ports.

2.5 Absolute maximum ratings

Stresses above those listed as “absolute maximum ratings” may cause permanent damage to the device. This is a stress rating only and functional operation of the device under these conditions is not implied. Exposure to maximum rating conditions for extended periods may affect device reliability.

Table 9. Absolute maximum ratings

Symbol	Ratings	Maximum value	Unit
V _{dd}	Supply voltage	-0.3 to 2.2	V
V _{dd_IO}	I/O pins supply voltage	-0.3 to 2.2	V
V _{in}	Input voltage on any control pin (CS, SCL/SPC, SDA/SDI/SDO)	-0.3 to V _{dd_IO} +0.3	V
A _{POW}	Acceleration (any axis, powered, V _{dd} = 1.8 V)	3000 for 0.5 ms	<i>g</i>
		10000 for 0.2 ms	<i>g</i>
A _{UNP}	Acceleration (any axis, unpowered)	3000 for 0.5 ms	<i>g</i>
		10000 for 0.2 ms	<i>g</i>
M _{EF}	Maximum exposed field	10000	gauss
T _{OP}	Operating temperature range	-40 to +85	°C
T _{STG}	Storage temperature range	-40 to +125	°C
ESD	Electrostatic discharge protection (HBM)	2	kV

Note: Supply voltage on any pin should never exceed 2.2 V.



This device is sensitive to mechanical shock, improper handling can cause permanent damage to the part.



This device is sensitive to electrostatic discharge (ESD), improper handling can cause permanent damage to the part.

3 Terminology

3.1 Sensitivity

3.1.1 Linear acceleration sensor sensitivity

Sensitivity describes the gain of the sensor and can be determined by applying 1 *g* acceleration to it. As the sensor can measure DC accelerations this can be done easily by pointing the axis of interest towards the center of the Earth, noting the output value, rotating the sensor by 180 degrees (pointing to the sky) and noting the output value again. By doing so, ± 1 *g* acceleration is applied to the sensor. Subtracting the larger output value from the smaller one, and dividing the result by 2, leads to the actual sensitivity of the sensor. This value changes very little over temperature and time. The sensitivity tolerance describes the range of sensitivities of a large population of sensors.

3.1.2 Magnetic sensor sensitivity

Sensitivity describes the ratio of the output digital data expressed in LSB units and the applied magnetic field expressed in mG (milligauss). It can be measured, for example, by applying a known magnetic field along one axis and measuring the digital output of the device.

3.2 Zero-g level

The zero-*g* level offset (LA_TyOff) describes the deviation of an actual output signal from the ideal output signal if no acceleration is present. A sensor in a steady state on a horizontal surface will measure 0 *g* on the X-axis and 0 *g* on the Y-axis whereas the Z-axis will measure 1 *g*. The output is ideally in the middle of the dynamic range of the sensor (content of OUT registers 00h, data expressed as two's complement number). A deviation from the ideal value in this case is called zero-*g* offset. Offset is to some extent a result of stress to MEMS sensor and therefore the offset can slightly change after mounting the sensor onto a printed circuit board or exposing it to extensive mechanical stress. Offset changes little with temperature, see [Table 3](#) "Zero-*g* level change vs. temperature" (LA_TCOff). The zero-*g* level tolerance (TyOff) describes the standard deviation of the range of zero-*g* levels of a population of sensors.

3.3 Zero-gauss level

Zero-gauss level offset (M_TyOff) describes the deviation of an actual output signal from the ideal output if no magnetic field is present.

3.4 Magnetic dynamic range

The magnetic dynamic range is defined as the magnetic field driven along one sensitive axis, giving the maximum digital output value.

4 Functionality

4.1 Magnetometer

4.1.1 Magnetometer power modes

The LSM303AH magnetometer provides two different power modes: high-resolution and low-power modes.

The tables below summarize the magnetometer RMS noise values and current consumption in different product configurations.

When the low-pass filter is enabled, the bandwidth is reduced while noise performance is improved without any increase in power consumption.

Table 10. RMS noise of operating modes

CFG_REG_B_M[LPF] or CFG_REG_B_M[OFF_CANC]	(CFG_REG_A_M [LP = 0]) high-resolution mode		(CFG_REG_A_M [LP = 1]) low-power mode	
	BW [Hz]	Noise RMS [mg]	BW [Hz]	Noise RMS [mg]
0 (disable)	ODR/2	4.5	ODR/2	9
1 (enable)	ODR/4	3	ODR/4	6

Table 11. Current consumption of operating modes

ODR (Hz)	Current consumption (μ A) (CFG_REG_A_M [LP] = 0) high-resolution CFG_REG_B_M [OFF_CANC] = 0	Current consumption (μ A) (CFG_REG_A_M [LP] = 1) low-power CFG_REG_B_M [OFF_CANC] = 0	Current consumption (μ A) (CFG_REG_A_M [LP] = 0) high-resolution CFG_REG_B_M [OFF_CANC] = 1	Current consumption (μ A) (CFG_REG_A_M [LP] = 1) low-power CFG_REG_B_M [OFF_CANC] = 1
10	100	25	125	55
20	200	50	240	105
50	475	125	590	255
100	950	250	1180	505

The following table summarizes the turn-on time of the magnetometer in the two different power modes with the offset cancellation function enabled or disabled (see [Section 4.1.2: Magnetometer offset cancellation](#)).

Table 12. Operating mode and turn-on time

Operating mode	Turn-on time		
	CFG_REG_A_M[LP]	CFG_REG_A_M[OFF_CANC = 0]	CFG_REG_A_M[OFF_CANC = 1]
0 (high-resolution)		9.4 ms	9.4 ms + 1/ODR
1 (low-power)		6.4 ms	6.4 ms + 1/ODR

The LSM303AH offers single measurement mode in both high-resolution and low-power modes.

Single measurement mode is enabled by writing bits MD[1:0] to '01' in [CFG_REG_A_M \(60h\)](#).

In single measurement mode, once the measurement has been performed, the DRDY pin is set to high, data is available in the output register and the LSM303AH is automatically configured in idle mode by setting the MD[1] bit to '1'.

Single measurement is independent of the programmed ODR but depends on the frequency at which the MD[1:0] bits are written by the microcontroller/application processor.

Maximum ODR frequency achievable in single mode measurement is given in the following table.

Table 13. Maximum ODR in single measurement mode (HR and LP modes)

Maximum ODR	Power mode (CFG_REG_A_M[LP])
100 Hz	High resolution (LP = '0')
150 Hz	Low power (LP = '1')

In single measurement mode, for ODR < 10 Hz, current consumption can be calculated with the following formula:

$$(\text{Current_consumption_10Hz} - \text{Current_consumption_in_power_down}) / (10 \text{ Hz} / \text{ODR}) + \text{Current_consumption_in_power_down}$$

Where Current_consumption_in_power_down and Current_consumption_10Hz can be found, respectively, in [Table 5](#) and [Table 11](#).

4.1.2 Magnetometer offset cancellation

Offset cancellation is the result of performing a set and reset in the magnetic sensor.

The offset cancellation technique is defined as follows:

$$H_{\text{out}} = \frac{H_n + H_{n-1}}{2}$$

where H_n and H_{n-1} are two consecutive magnetic field measurements, one after a set pulse, the other after a reset pulse.

Considering a magnetic offset (H_{off}), the two magnetic field measurements are:

- Set: $H_n = H + H_{\text{off}}$
- Reset: $H_{n-1} = H - H_{\text{off}}$

The offset is cancelled according to the offset cancellation technique:

$$H_{\text{out}} = \frac{H_n + H_{n-1}}{2} = \frac{2H + H_{\text{off}} - H_{\text{off}}}{2} = H$$

In the LSM303AH offset cancellation is enabled by setting bit `OFF_CANC = 1` (and bit `OFF_CANC_ONE_SHOT = 1` in single measurement mode) in [CFG_REG_B_M \(61h\)](#).

Offset cancellation is automatically managed by the device in continuous mode.

Offset cancellation has to be managed by the user in single measurement mode averaging two consecutive measurements H_n and H_{n-1} .

If offset cancellation is disabled, a set of the magnetic sensor is performed anyway.

The set pulse frequency can be configured by setting the `Set_FREQ` bit in [CFG_REG_B_M \(61h\)](#).

4.1.3 Magnetometer interrupt

In LSM303AH magnetometer interrupt signal generation is based on the comparison between data and a programmable threshold.

To enable the interrupt function, in `INT_CTRL_REG_M` register (63h) the "IEN" bit must be set to '1'.

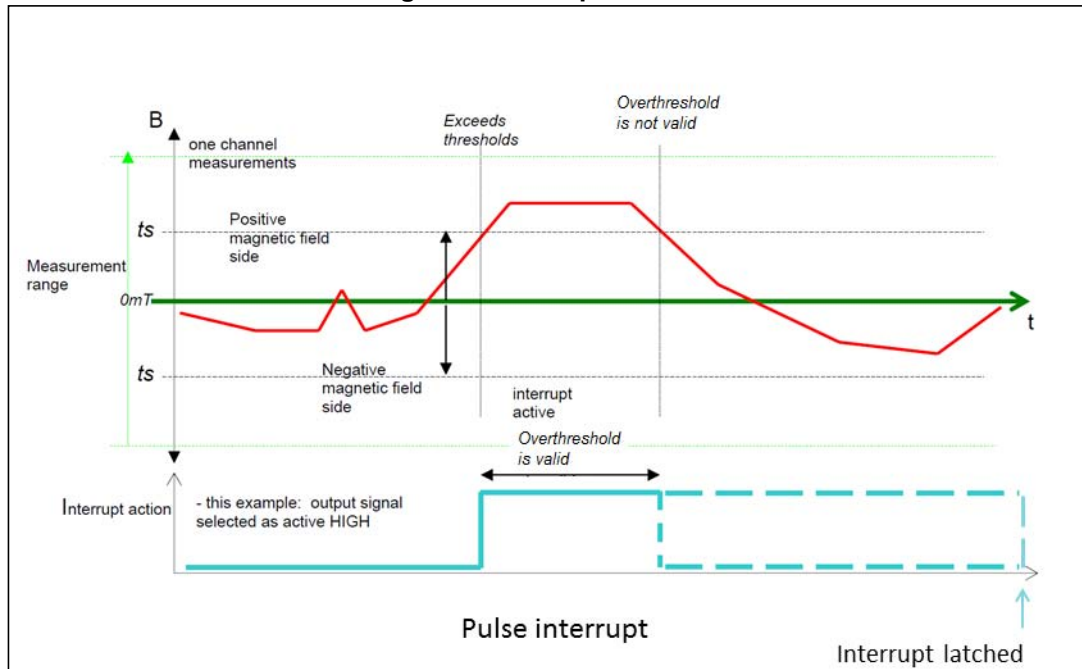
In the LSM303AH the user can select the axis/axes in which the interrupt function can be enabled. In order to do this, the `XIEN`, `YIEN`, and `ZIEN` bits in [INT_CTRL_REG_M \(63h\)](#) need be set properly.

The threshold value can be programmed by setting the [INT_THS_L_REG_M \(65h\)](#) and [INT_THS_H_REG_M \(66h\)](#) registers.

The threshold is expressed in absolute value as a 15-bit unsigned number. The threshold has the same sensitivity as the magnetic data.

When magnetic data exceeds the positive or the negative threshold, the interrupt signal is generated and the information about the type of interrupt is stored in the [INT_SOURCE_REG_M \(64h\)](#) register. In particular, when magnetic data exceeds the positive threshold the `P_TH_S_axis` bit is set to '1', while if data exceeds the negative threshold the `N_TH_S_axis` bit is set to '1'. If magnetic data lay between the positive and the negative thresholds, no interrupt signal is released.

Figure 5. Interrupt function



Two different approaches for the interrupt function are available:

- Typical: comparison is between magnetic data read by the sensor and the programmable threshold;
- Advanced: comparison is made between magnetic data after hard-iron correction and the programmable threshold.

These approaches are configurable by setting the INT_on_DataOFF bit in [CFG_REG_B_M \(61h\)](#).

If INT_on_DataOFF is set to '0' the typical approach is selected, otherwise if it is set to '1' the advanced approach is selected.

Two different interrupts are available:

- Pulsed interrupt signal: it goes high when the magnetic data exceed one of the two thresholds and goes low when the magnetic data are between the two thresholds. This kind of interrupt is selected by setting the IEL bit in [INT_CTRL_REG_M \(63h\)](#) to '0'.
- Latched interrupt signal: it goes high when the data exceed one of the two thresholds but is reset only once the source register is read and not when the magnetic data returns between the two thresholds. This kind of interrupt is selected by setting the IEL bit in [INT_CTRL_REG_M \(63h\)](#) to '1'.

The interrupt signal polarity can be set using the IEA bit in [INT_CTRL_REG_M \(63h\)](#).

If IEA is set to '1' then the interrupt signal is active high, while if it is set to '0' the interrupt signal is active low.

In order to drive the interrupt signal from the DRDY pad, the INT_MAG_PIN bit in [CFG_REG_C_M \(62h\)](#) must be set to '1'.

4.1.4 Magnetometer hard-iron compensation

Hard-iron distortion occurs when a magnetic object is placed near the magnetometer and appears as a permanent bias in the sensor's outputs.

The hard-iron correction consists of compensating magnetic data from hard-iron distortion.

The operation is defined as follows:

$$H_{\text{out}} = H_{\text{read}} - H_{\text{HI}}$$

where:

- H_{read} is the generic uncompensated magnetic field data, as read by the sensor;
- H_{HI} is the hard-iron distortion field;
- H_{out} is the compensated magnetic data.

The computation of the hard-iron distortion field should be performed by an external processor. After the computation of the hard iron-distortion field has been performed, the measured magnetic data can be compensated.

The LSM303AH offers the possibility of storing hard-iron data inside six dedicated registers from 45h to 4Ah.

Each register contains eight bits so that the hard-iron data can be expressed as a 16-bit two's complement number. The OFFSET_axis_REG_H registers contain the MSBs of the hard-iron data, while the OFFSET_axis_REG_L registers contain the LSBs.

Hard-iron data have the same format and weight of the magnetic output data. The hard-iron values stored in dedicated registers are automatically subtracted from the output data.

4.1.5 Magnetometer self-test

The self-test function is available for the magnetic sensor. When the magnetic self-test is enabled, a current is forced into a coil inside the device. This current will generate a magnetic field that will produce a variation of the magnetometer output signals. If the output signals change within the amplitude limits specified in [Table 3](#) then the sensor is working properly and the parameters of the interface chip are within the defined specifications.

The self-test procedure is described in the following figure.