

In This Issue

[Angle Sensor Interfaces](#)

[Angle Sensor Demo Video](#)

Quick Links

[Sensor Selector Guide](#)

[Isolator Selector Guide](#)

[Online Store](#)

[Contact Us](#)

[Twitter](#)

[Google+](#)

[YouTube](#)

TMR Patent

NVE was recently granted U.S. patent number 9,322,889 titled "[Low Hysteresis High Sensitivity Magnetic Field Sensor](#)" related to TMR sensors.

See [story at right](#) for more information about one of our state-of-the-art TMR products.

Document Updates

[Short-form Sensor Catalog](#)

(added AAT009 Ridiculously Low-Power Angle Sensor)

New YouTube Videos

[AAT003 Angle Sensor and Arduino Controlling Camera Rotation](#)

[Ridiculously Low-Power Angle Sensor Powered by a Blueberry](#)

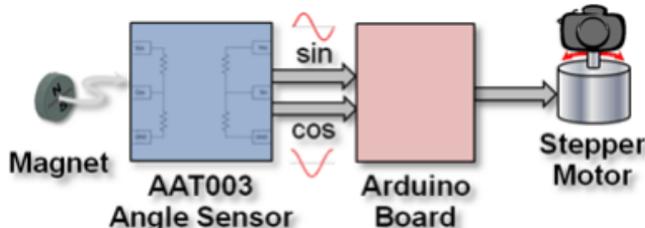
[Interfacing Angle Sensors to Microcontrollers](#)

Application Corner

Angle Sensor Interfaces

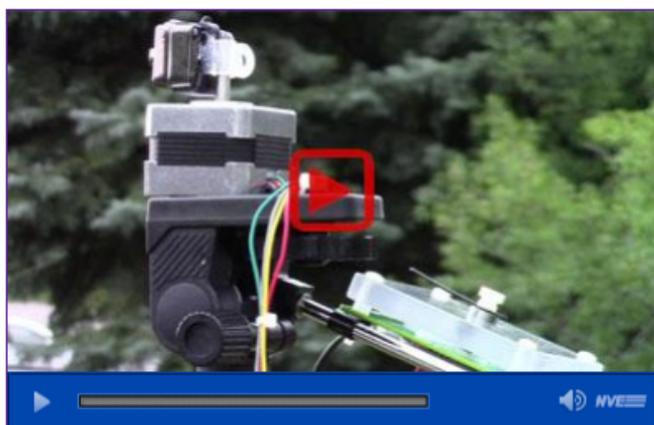
AAT sensors measure angular position based on rotating magnetic fields. With their large output signal and low output impedance, AAT003 angle sensors easy interface directly to Arduino and similar boards with integrated Analog-to-Digital Convertors.

This reference design uses an Atmel MEGA328 on an Arduino board:



The Arduino reads the sensor, calculates the angle, and drives the stepper motor. Because of the large sensor output, no amplification is needed prior to the Arduino.

To demonstrate, we control a stepper motor servo to rotate a micro video camera, and use the video frames for an updated picture of our building:



The demonstration uses an off-the-shelf [AAT003 Evaluation Board](#), which includes a sensor and magnet. For the demo, we mounted an Arduino board and a stepper motor shield mounted on the back.

A simple program reads the two sensor analog outputs and calculates the indicated angle using a two-variable arctangent:

```
void loop() {
  //Calculate angle indicated by AAT003 sensor
  AATangle = atan2(float(analogRead(0)-512),float(analogRead(1)-512));

  //Calculate error and adjust to move shortest direction
  error = MotorAngle - AATangle;
  if(error > pi) error = error - 2*pi;
  if(error < -pi) error = error + 2*pi;

  //Now motor to correct error
  if(error < -deadband) //Motor behind
  { digitalWrite(dir,S0H); //Step CW to catch up
    digitalWrite(step,S0H);
    digitalWrite(step,S0L);
    MotorAngle = MotorAngle + MotorStep; //Increment by one step
    if(MotorAngle > 2*pi) MotorAngle = MotorAngle - 2*pi; //Wrap angle <360
  }
  else if(error > deadband) //Motor ahead
  { digitalWrite(dir,S0L); //Step CCW to backup
    digitalWrite(step,S0H);
    digitalWrite(step,S0L);
    MotorAngle = MotorAngle - MotorStep; //Decrement by one step
    if(MotorAngle < 0) MotorAngle = MotorAngle + 2*pi; //Wrap angle positive
  }
}
```

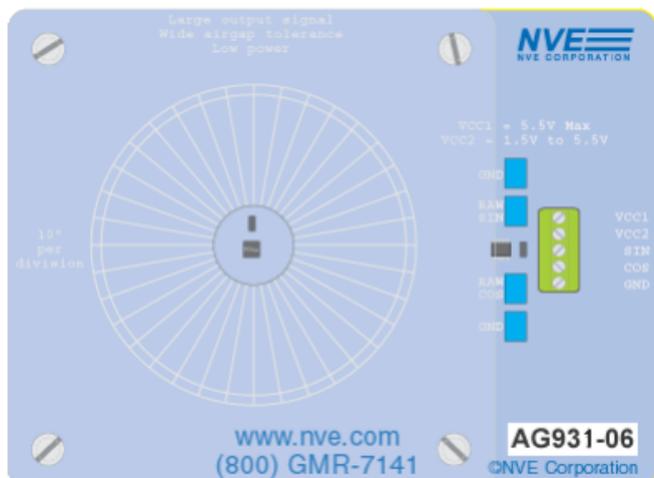
Read sensor's sin & cos outputs
Angle (radians)

[\[click to enlarge\]](#)

Key [AAT003](#) features include:

- 0.5° maximum angular measurement error
- Sine and cosine outputs
- 200 mV/V peak-to-peak output signals
- 40 kΩ typical device resistance; 20 kΩ output impedance
- Wide magnet airgap tolerance
- Ultraminiature 2.5 mm x 2.5 mm x 0.8 mm TDFN6

Sensors, magnets, and evaluation boards are in stock and available for immediate delivery.



Buy Online
\$9.95 shipping