

# Depth Sensors

## Overview

Depth sensors are a crucial means to receive feedback about more than just depth. By using four high-precision depth sensors, pitch and roll of the submarine can be calculated. Pitch and roll information can then be used to validate any information provided by an inertial measurement unit, and it is especially useful because depth sensors are not prone to the error induced by motors that a magnetometer is.

## Theory

Think of three of the depth sensors defining a plane in 3D space. The final depth sensor acts as a fixed point above that plane that rotates as the plane rotates. If the fixed point is off-center of the plane, then when the plane rotates 180 degrees (staying flat at all times), then roll and pitch can be determined.

## Resources

Part	Description	Datasheet
<a href="#">Depth Sensor</a>	Depth sensor in use on the submarine.	<a href="#">Datasheet</a>
ATMega1284P	Microcontroller to be used on the project.	<a href="#">Datasheet</a>
Resource	Description	
<a href="#">Arduino Tutorials</a>	Code tutorials for programming Arduino devices.	
<a href="#">ATMega1284P Arduino Core</a>	Arduino Core for the ATMega1284P	
<a href="#">RosSerial Documentation</a>	RosSerial is the communication protocol that allows implementation of a ROS node on a microcontroller.	

From:

<https://robosub.eecs.wsu.edu/wiki/> - **Palouse RoboSub Technical Documentation**

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<https://robosub.eecs.wsu.edu/wiki/ee/depth-sensors/start?rev=1474586719>



Last update: **2016/09/22 16:25**