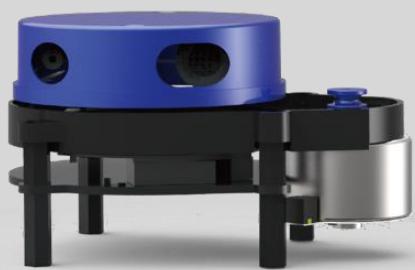




YDLIDAR X4

DEVELOPMENT MANUAL



Doc#: 01.13.000002

Contents

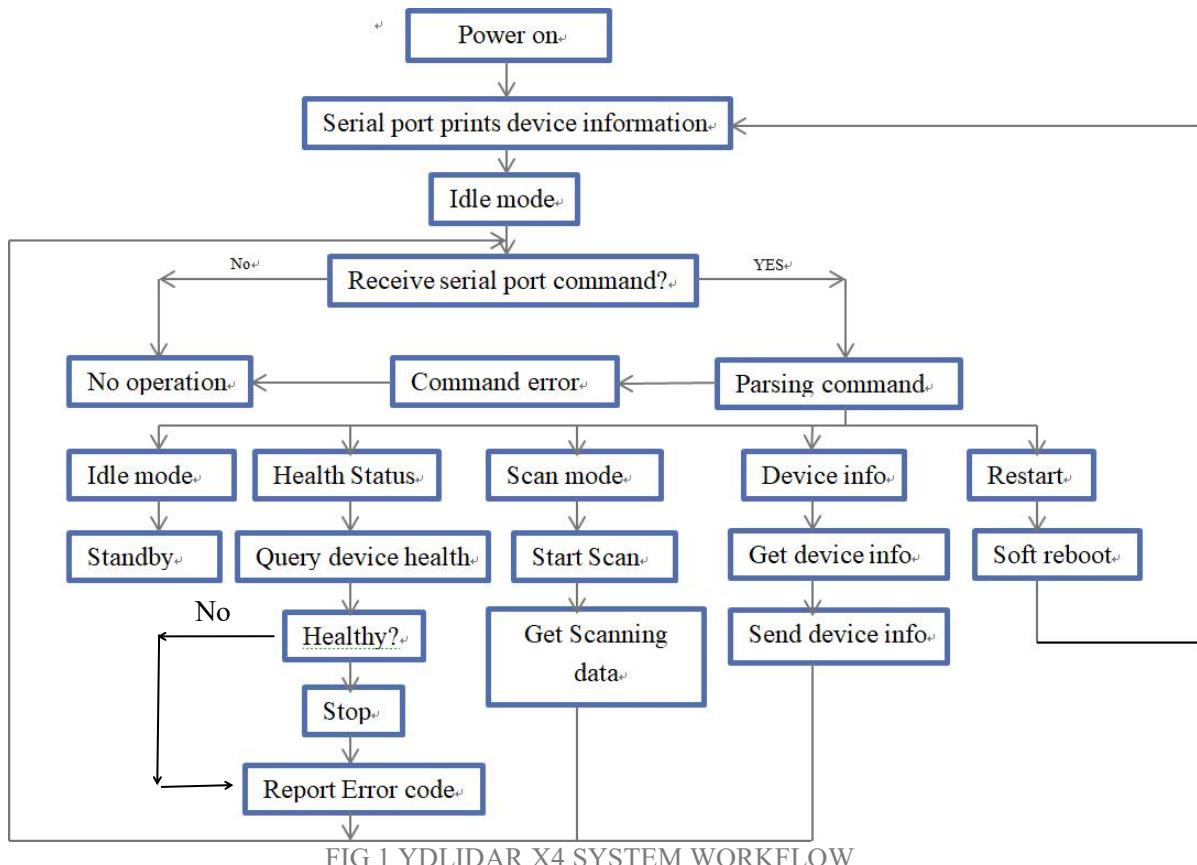
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WORKING MECHANISM

The system of YDLIDAR X4 (hereinafter referred to as X4) has set 3 working modes: idle mode, scan mode, and stop mode;

- **Idle mode:** When X4 is powered on, the default status is idle mode. In idle mode, the X4's ranging unit does not work and the laser is not lit.
- **Scan mode:** When the X4 enters the scan mode, the ranging unit turns on the laser and starts working. Lidar continuously performs laser sampling on the external environment and outputs it in real time.
- **Stop mode:** When X4 runs wrong, for example when turning on the scanner, the laser is off, the motor does not turn, etc., X4 will automatically turn off the distance measuring unit and feedback the error code.

System Workflow



SYSTEM COMMUNICATION

Communication mechanism

X4 interacts with external devices through commands and data through the serial port. When the external device sends a system command to X4, X4 will parse the system command and return the corresponding reply message. And according to the command content, X4 can switch the corresponding working status. The external system will parse the message according to the content of the message and obtain the response data.

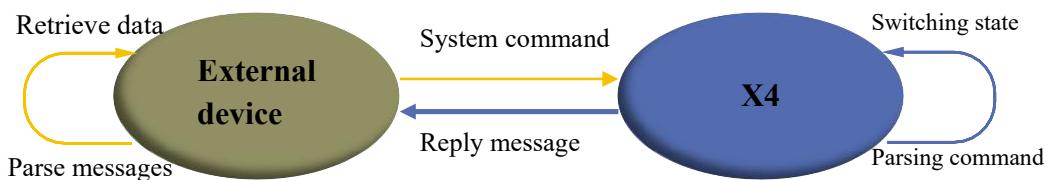


FIG 2 YDLIDAR X4 SYSTEM COMMUNICATION MECHANISM

System command

The external system can set the corresponding working status of X4 and send corresponding data by sending related system commands. The X4 system command is unified to 2 bytes. The start byte is uniformly 0xA5, and the second byte is the command content. The system commands issued by X4 are as follows:

CHART 1 YDLIDAR X4 SYSTEM COMMAND

System command	Description	Modes	Response mode
0xA5 (Start)	0x60	Scan mode	continuous response
	0x65	Stop mode	No response
	0x90	-	Single response
	0x91	-	Single response
	0x80	-	No response

System messages

The system message is a response message that the system feeds back based on the received system command. Different system commands, system message reply mode and response content are also different. There are three kinds of response modes: no response, single response, continuous response.

No response means that the system does not return any messages. A single reply indicates that the system's message length is limited, and the response ends once. Sustained response means that the system's message length is infinite, and it needs to send data continuously, for example when entering the scan mode.

Single reply and continuous reply messages use the same data protocol. The contents of the protocol are: start, response length, answer mode, type code and response content, and output through the serial port hexadecimal system.

CHART 2 YDLIDAR X4 SYSTEM MESSAGE DATA PROTOCOL

Start sign	Response length	Response mode	Type code	Content
16bits	30bits	2bits	8bits	-

Byte Offset:

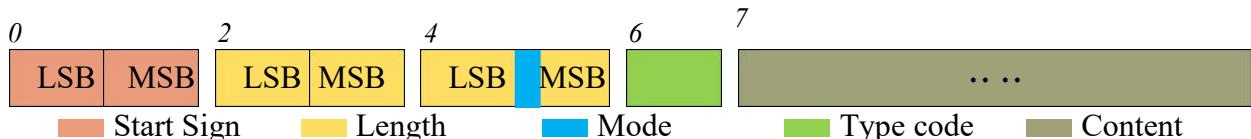


FIG 3 YDLIDAR X4 SYSTEM MESSAGE DATA PROTOCOL

- **Start sign:** The X4 packet is unified as 0xA55A;
- **Response length:** The response length indicates the length of the response content. However, when the response mode is continuous, the length is infinite, so the value is invalid.;
- **Response mode:** This bit is only 2 bits, indicating that this message is a single response or continuous response. Its value and corresponding mode are as follows:

CHART 3 YDLIDAR X4 RESPONSE MODE VALUE AND CORRESPONDING MODE

Response mode	0x0	0x1	0x2	0x3
Mode	Single response	Continuous response		Undefined

- **Type code:** Different system commands correspond to different types of codes.
- **Content:** Different system commands, feedback different data content. The data protocol is also different.

Note 1: The X4 data communication adopts the little-endian mode and the low-order mode.

Note 2: In the reply message, the lower 6 bits of the 6th byte belong to the response length and the upper 2 bits belong to the response mode.

DATA PROTOCOL

Different system commands have different packet contents. In the packets of different types of codes, the data protocol of the response content is also not the same. Therefore, the user needs to parse the data in the response content according to the corresponding data protocol, such as point cloud data, device information, etc.

Scan command [A5 60]

When an external device sends a scan command to X4, X4 goes into scan mode and feeds back point cloud data. The reply message is:

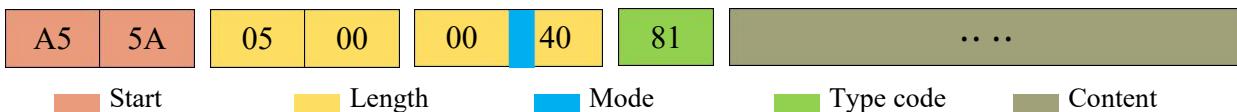


FIG 4 YDLIDAR X4 SCAN COMMAND

The response content is the point cloud data scanned by the system. According to the following data structure, the data is sent to the external device in hexadecimal to the serial port.

Byte:

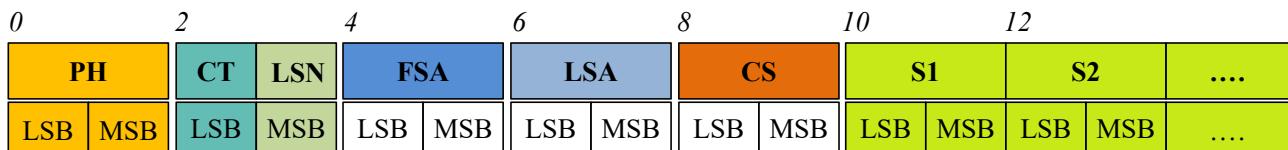


FIG 5 SCAN COMMAND RESPONSE CONTENT DATA STRUCTURE DIAGRAM

CHART 4 SCAN COMMAND RESPONSE CONTENT DATA STRUCTURE DESCRIPTION

Content	Name	Description
PH(2B)	Packet header	The length is 2B, fixed at 0x55AA, low in front, high in back.
CT(1B)	Package type	Indicates the current packet type. 0x00: Point cloud packet 0x01: Zero packet.
LSN(1B)	Sample quantity	Indicates the number of sample points contained in the current packet; there is only one zero point of data in the zero packet. The value is 1.
FSA(2B)	Starting angle	The angle data corresponding to the first sample point in the sampled data.
LSA(2B)	End angle	The angle data corresponding to the last sample point in the sampled data.
CS(2B)	Check code	The check code of the current data packet uses a two-byte exclusive OR to check the current data packet.
Si(2B)	Sampling data	The system test sampling data is the distance data of the sampling point.

➤ Zero resolution:

Start data packet: CT=1, LSN=1, Si=1

For the analysis of the specific values of distance and angle, see the analysis of distance and angle

➤ Distance analysis:

Distance solution formula:

$$\text{Distance}_i = \frac{Si}{4}$$

Si is sampling data. Sampling data is set to E5 6F. Since the system is in the little-endian mode, the sampling point S = 0x6FE5, and it is substituted into the distance solution formula, which yields

Distance = 7161.25mm.

First level analysis:

Starting angle solution formula: $\text{Angle}_{\text{FSA}} = \frac{\text{Rshiftbit}(\text{FSA}, 1)}{64}$

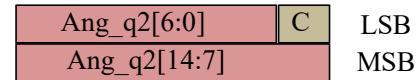


FIG 4 ANGLE DATA

End angle solution formula: $\text{Angle}_{\text{LSA}} = \frac{\text{Rshiftbit}(\text{LSA}, 1)}{64}$

Intermediate angle solution formula: $\text{Angle}_i = \frac{\text{diff}(\text{Angle})}{\text{LSN}-1} * (i - 1) + \text{Angle}_{\text{FSA}}$ (i = 2,3,...,LSN - 1)

Rshiftbit(data,1) means shifting the data to the right by one bit. diff(Angle) means the clockwise angle difference from the starting angle (uncorrected value) to the ending angle (uncorrected value), and LSN represents the number of packet samples in this frame.

Second-level analysis:

Angle correction formula: $\text{Angle}_i = \text{Angle}_i + \text{AngCorrect}_i$ (i = 1,2,...,LSN)

AngCorrect is the angle correction value, and its calculation formula is as follows, tand^{-1} is an inverse trigonometric function, and the return angle value is:

IF $\text{Distance}_i == 0$ $\text{AngCorrect}_i = 0$

ELSE $\text{AngCorrect}_i = \text{tand}^{-1}(21.8 * \frac{155.3 - \text{Distance}_i}{155.3 * \text{Distance}_i})$

In the data packet, the 4th to 8th bytes are 28 E5 6F BD 79, so LSN = 0x28 = 40(dec), FSA = 0x6FE5, LSA = 0x79BD, and bring in the first-level solution formula, and get:

$\text{Angle}_{\text{FSA}} = 223.78^\circ$, $\text{Angle}_{\text{LSA}} = 243.47^\circ$, $\text{diff}(\text{Angle}) = 19.69^\circ$

$\text{Angle}_i = \frac{19.69^\circ}{39} * (i - 1) + 223.78^\circ$ (i = 2,3,...,39)

Assume that in the frame data, $\text{Distance}_1 = 1000$, $\text{Distance}_{\text{LSN}} = 8000$, and bring in the second-level solution formula, you get:

$\text{AngCorrect}_1 = -6.7622^\circ$, $\text{AngCorrect}_{\text{LSN}} = -7.8374^\circ$, so:

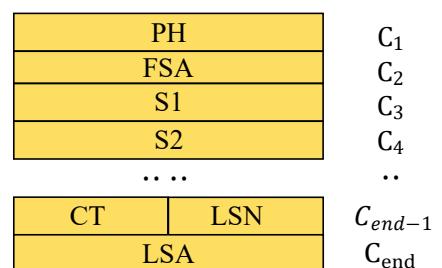
$\text{Angle}_{\text{FSA}} = \text{Angle}_1 + \text{AngCorrect}_1 = 217.0178^\circ$

$\text{Angle}_{\text{LSA}} = \text{Angle}_{\text{LSA}} + \text{AngCorrect}_{\text{LSA}} = 235.6326^\circ$

Similarly, Angle_i (i = 2,3,...,LSN - 1), can be obtained sequentially.

➤ Check code parsing:

The check code uses a two-byte exclusive OR to verify the current data packet. The check code itself does not participate in XOR operations, and the XOR order is not strictly in byte order. The XOR sequence is as shown in the figure. Therefore, the check code solution formula is:



$\text{CS} = \text{XOR}_1^e(C_i)$

$i = 1, 2, \dots, end$

FIG 7 CS XOR SEQUENCE

$\text{XOR}_1^{\text{end}}$ indicates the XOR of the element from subscript 1 to end. However, XOR satisfies the exchange law, and the actual solution may not need to follow the XOR sequence.

Stop command [A5 65]

When the system is in the scanning state, X4 always sends point cloud data to the outside. If you need to turn off scanning at this time, you can send this command to stop the system from scanning. After the stop command is sent, the system will be in the standby state. At this time, the ranging unit of the device is in the low power mode, and the laser is not lit.

The command is unresponsive, so the system will not respond to any messages after receiving the command.

Device Information [A5 90]

When an external device sends a Get Device Information command to A4 (A5 90), X4 will feedback the device's model, firmware version, and hardware version, and the device's factory serial number.

The reply message is:

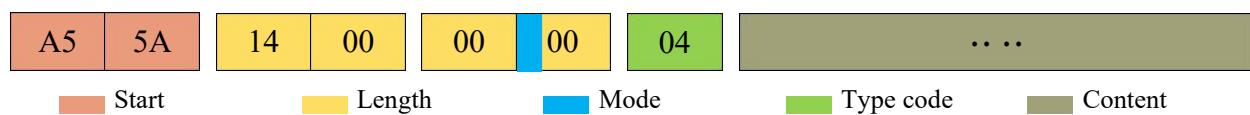


FIG 8 YDLIDAR X4 DEVICE INFORMATION

According to the protocol resolution: response length = 0x00000014, answer mode = 0x0, type code = 0x04.

That is, the number of response content bytes is 20. The response is a single response and the type code is 04. This type of response content satisfies the foLSBowing data structure:

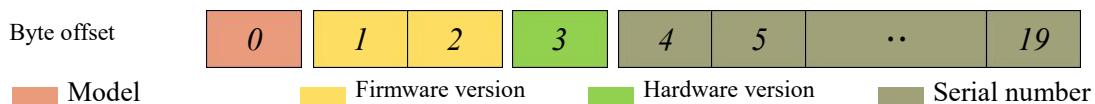


FIG 9 YDLIDAR X4DEVICE INFORMATION RESPONSE CONTENT DATA STRUCTURE

- **Model number:** One byte device model, such as the X4 model code is 04.
- **Firmware Version:** 2 bytes. The low byte is the major version number, and the high byte is the minor version number.
- **Hardware version:** 1 byte for hardware version.
- **Serial number:** 16 bytes, the only factory serial number.

Health status [A5 91]

When the external device sends the Get Device Health Status command (A5 91) to X4, X4 will feedback the device's status code. The reply message is:

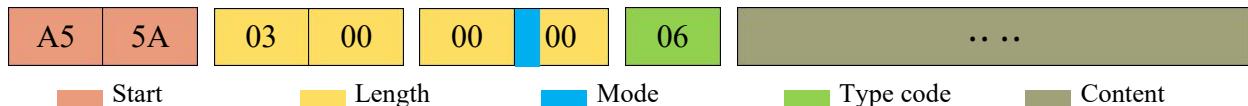


FIG 10 YDLIDAR X4 DEVICE HEALTH

According to the protocol resolution: response length = 0x00000003, answer mode = 0x0, type code = 0x06.

That is, the number of response content bytes is 3. The response is a single response and the type code is 06. This type of response content satisfies the following data structure:

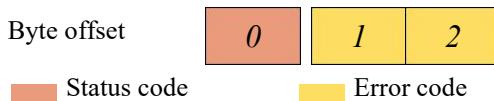


FIG 11 YDLIDAR X4 DEVICE HEALTH STATUS

- **Status code:** 1 byte. 0x0 indicates that the device is running normally; 0x1 indicates that the device is running; 0x2 indicates that the device is running incorrectly.
- **Error code:** 2 bytes. When a warning or error status occurs, the specific error code will be recorded in this field. 0x00 indicates that the device is operating without error.

Restart command [A5 80]

When the external device sends the Get Device command to A4 (A5 40), X4 will start a soft reboot and the system will restart. This command does not answer.

POWER CONTROL

In the X4 external interface, the relevant control interfaces (M_EN, M_SCTP) and the power control interface (DEV_EN) of the motor are provided. The user can set the three control signals to control the power consumption of the device.

Standby control

For the convenience of users, the default value of the X4 control signal (please refer to the data sheet) does not achieve the lowest power consumption. Therefore, when users need to debug the lowest power standby state, M_EN and DEV_EN need to be further control as follows:

M_EN = 0V, DEV_EN = 0V.

In this way, the motor and ranging functions are turned off, and the entire system is in the lowest power standby state.

Motor speed control

At the same time, the user can change the scanning frequency to meet the demand according to actual needs. The motor speed can be adjusted by changing the input voltage of the M_SCTP pin or changing the duty cycle of the input PWM signal (refer to the data sheet for specific control methods).