
AdafruitMMA8451 Library Documentation

Release 1.0

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CircuitPython module for the MMA8451 3 axis accelerometer.

CHAPTER 1

Dependencies

This driver depends on:

- [Adafruit CircuitPython](#)
- [Bus Device](#)

Please ensure all dependencies are available on the CircuitPython filesystem. This is easily achieved by downloading the [Adafruit library and driver bundle](#).

CHAPTER 2

Usage Example

See `examples/simpletest.py` for a demo of the usage.

CHAPTER 3

Contributing

Contributions are welcome! Please read our [Code of Conduct](#) before contributing to help this project stay welcoming.

4.1 Zip release files

To build this library locally you'll need to install the `circuitpython-build-tools` package.

```
python3 -m venv .env
source .env/bin/activate
pip install circuitpython-build-tools
```

Once installed, make sure you are in the virtual environment:

```
source .env/bin/activate
```

Then run the build:

```
circuitpython-build-bundles --filename_prefix adafruit-circuitpython-mma8451 --
↳library_location .
```

4.2 Sphinx documentation

Sphinx is used to build the documentation based on rST files and comments in the code. First, install dependencies (feel free to reuse the virtual environment from above):

```
python3 -m venv .env
source .env/bin/activate
pip install Sphinx sphinx-rtd-theme
```

Now, once you have the virtual environment activated:

```
cd docs
sphinx-build -E -W -b html . _build/html
```

This will output the documentation to `docs/_build/html`. Open the `index.html` in your browser to view them. It will also (due to `-W`) error out on any warning like Travis will. This is a good way to locally verify it will pass.

5.1 Simple test

Ensure your device works with this simple test.

Listing 1: examples/simpletest.py

```
1  # Simple demo of reading the MMA8451 orientation every second.
2  # Author: Tony DiCola
3  import time
4
5  import board
6  import busio
7
8  import adafruit_mma8451
9
10
11 # Initialize I2C bus.
12 i2c = busio.I2C(board.SCL, board.SDA)
13
14 # Initialize MMA8451 module.
15 sensor = adafruit_mma8451.MMA8451(i2c)
16 # Optionally change the address if it's not the default:
17 #sensor = adafruit_mma8451.MMA8451(i2c, address=0x1C)
18
19 # Optionally change the range from its default of +/-4G:
20 #sensor.range = adafruit_mma8451.RANGE_2G # +/- 2G
21 #sensor.range = adafruit_mma8451.RANGE_4G # +/- 4G (default)
22 #sensor.range = adafruit_mma8451.RANGE_8G # +/- 8G
23
24 # Optionally change the data rate from its default of 800hz:
25 #sensor.data_rate = adafruit_mma8451.DATARATE_800HZ # 800Hz (default)
26 #sensor.data_rate = adafruit_mma8451.DATARATE_400HZ # 400Hz
27 #sensor.data_rate = adafruit_mma8451.DATARATE_200HZ # 200Hz
```

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```

28 #sensor.data_rate = adafruit_mma8451.DATARATE_100HZ # 100Hz
29 #sensor.data_rate = adafruit_mma8451.DATARATE_50HZ # 50Hz
30 #sensor.data_rate = adafruit_mma8451.DATARATE_12_5HZ # 12.5Hz
31 #sensor.data_rate = adafruit_mma8451.DATARATE_6_25HZ # 6.25Hz
32 #sensor.data_rate = adafruit_mma8451.DATARATE_1_56HZ # 1.56Hz
33
34 # Main loop to print the acceleration and orientation every second.
35 while True:
36     x, y, z = sensor.acceleration
37     print('Acceleration: x={0:0.3f}m/s^2 y={1:0.3f}m/s^2 z={2:0.3f}m/s^2'.format(x, y,
→ z))
38     orientation = sensor.orientation
39     # Orientation is one of these values:
40     # - PL_PUF: Portrait, up, front
41     # - PL_PUB: Portrait, up, back
42     # - PL_PDF: Portrait, down, front
43     # - PL_PDB: Portrait, down, back
44     # - PL_LRF: Landscape, right, front
45     # - PL_LRB: Landscape, right, back
46     # - PL_LLF: Landscape, left, front
47     # - PL_LLB: Landscape, left, back
48     print('Orientation: ', end='')
49     if orientation == adafruit_mma8451.PL_PUF:
50         print('Portrait, up, front')
51     elif orientation == adafruit_mma8451.PL_PUB:
52         print('Portrait, up, back')
53     elif orientation == adafruit_mma8451.PL_PDF:
54         print('Portrait, down, front')
55     elif orientation == adafruit_mma8451.PL_PDB:
56         print('Portrait, down, back')
57     elif orientation == adafruit_mma8451.PL_LRF:
58         print('Landscape, right, front')
59     elif orientation == adafruit_mma8451.PL_LRB:
60         print('Landscape, right, back')
61     elif orientation == adafruit_mma8451.PL_LLF:
62         print('Landscape, left, front')
63     elif orientation == adafruit_mma8451.PL_LLB:
64         print('Landscape, left, back')
65     time.sleep(1.0)

```

5.2 adafruit_mma8451

CircuitPython module for the MMA8451 3 axis accelerometer. See examples/simpletest.py for a demo of the usage.

- Author(s): Tony DiCola

class `adafruit_mma8451.MMA8451` (*i2c*, *, *address*=<*sphinx.ext.autodoc.importer.MockObject object*>)

MMA8451 accelerometer. Create an instance by specifying: - *i2c*: The I2C bus connected to the sensor.

Optionally specify: - *address*: The I2C address of the sensor if not the default of 0x1D.

acceleration

Get the acceleration measured by the sensor. Will return a 3-tuple of X, Y, Z axis acceleration values in m/s².

data_rate

Get and set the data rate of the sensor. Must be a value of: - DATARATE_800HZ: 800Hz (the default) - DATARATE_400HZ: 400Hz - DATARATE_200HZ: 200Hz - DATARATE_100HZ: 100Hz - DATARATE_50HZ: 50Hz - DATARATE_12_5HZ: 12.5Hz - DATARATE_6_25HZ: 6.25Hz - DATARATE_1_56HZ: 1.56Hz

orientation

Get the orientation of the MMA8451. Will return a value of: - PL_PUF: Portrait, up, front - PL_PUB: Portrait, up, back - PL_PDF: Portrait, down, front - PL_PDB: Portrait, down, back - PL_LRF: Landscape, right, front - PL_LRB: Landscape, right, back - PL_LLF: Landscape, left, front - PL_LLB: Landscape, left, back

range

Get and set the range of the sensor. Must be a value of: - RANGE_8G: +/- 8g - RANGE_4G: +/- 4g (the default) - RANGE_2G: +/- 2g

CHAPTER 6

Indices and tables

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