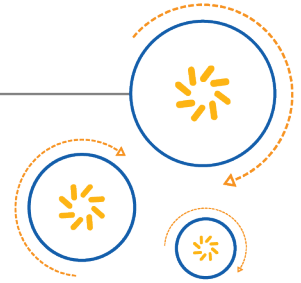




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Qualcomm Technologies, Inc.



# Qualcomm<sup>®</sup> Snapdragon Navigator<sup>™</sup>

## Developer Guide

80-P4698-20 A

June 16, 2017

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Qualcomm Technologies, Inc.  
5775 Morehouse Drive  
San Diego, CA 92121  
U.S.A.

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# 1 Introduction

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## 1.1 Purpose

This document describes how to use the Snapdragon Navigator API to develop applications that interact with Snapdragon Navigator. It is important to understand Snapdragon Navigator operation and install Snapdragon Navigator on the target before using this document. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18).

This document assumes that the reader has a basic knowledge of UNIX.

## 1.2 Conventions

Function declarations, function names, type declarations, and code samples appear in a different font, e.g., `#include`.

Code variables appear in angle brackets, e.g., `<number>`.

Commands and command variables appear in a different font, e.g., `copy a:*. * b:.`

## 2 Functional Overview

---

The Snapdragon Navigator API enables external applications to interact with the internal flight controller, permitting higher-level applications written in C or C++ to control the vehicle's movement.

For basic Snapdragon Navigator API usage, refer to [https://github.com/ATLFlight/snnav\\_api\\_examples](https://github.com/ATLFlight/snnav_api_examples).

Table 2-1 lists and describes the files provided by the Snapdragon Navigator API.

**Table 2-1 Snapdragon Navigator API files**

<b>Filename</b>	<b>Description</b>
snapdragon_navigator.h	Header file containing Snapdragon Navigator API function declarations
snnav_types.h	Header file containing Snapdragon Navigator API type declarations
snnav_cached_data.h	Header file containing Snapdragon Navigator API cached data struct declarations
libsnav_arm.so	Library containing Snapdragon Navigator API implementation

# 3 Getting Started

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## 3.1 Installing the Snapdragon Navigator Developer Files

Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions on how to install a Snapdragon Navigator Debian package.



# 4 Develop an Application

---

For basic Snapdragon Navigator API usage, refer to [https://github.com/ATLFlight/snnav\\_api\\_examples](https://github.com/ATLFlight/snnav_api_examples).

## 4.1 Writing the Source

To write a program for the applications processor that uses the Snapdragon Navigator API, include the `snapdragon_navigator.h` header file in C or C++ code. Use the example programs as a guide to using the API. Here are a few things to keep in mind:

- The vehicle can only be under API control if it is receiving commands frequently enough; this serves as a *heartbeat* to notify the vehicle that the external application is running. Commands must be sent periodically before the vehicle can enter API control.
- It is recommended to store the estimated position and yaw at startup, and use them to zero out the estimated position and yaw in the application. This sets the *origin* as the vehicle's state at takeoff.

The application must grab the estimated position and yaw just after the propeller state transitions to starting, *not* after the props state transitions to spinning. Transient pressure data due to the ground effect can have an unexpected impact on the Z estimate.

- Knowing the estimated position and yaw is useful, but in most cases, it is best to have the application use the desired position and yaw for control. Controlling the desired position and yaw is equivalent to moving around the setpoint of the internal position controller. This allows the internal position controller to control the higher order dynamics of the system.

### 4.1.1 Understanding the RC Command Interface

When developing an application to compute control commands in real units, such as following a trajectory or going to a waypoint with a calculated velocity profile, it is crucial to understand how the four unitless control commands are interpreted in different flight modes.

The general meaning of the four unitless commands is summarized in Table 4-1. For the meaning of each RC command type, see Table 4-2.

**Table 4-1 Snapdragon Navigator RC commands general meaning**

	<b>cmd0</b>	<b>cmd1</b>	<b>cmd2</b>	<b>cmd3</b>
<b>Positive</b>	Forward	Left	Up	Rotate counter-clockwise
<b>Negative</b>	Backward	Right	Down	Rotate clockwise

**Table 4-2 Snapdragon Navigator RC command details**

	<b>cmd0</b>	<b>cmd1</b>	<b>cmd2</b>	<b>cmd3</b>
SN_RC_OPTIC_FLOW_POS_HOLD_CMD	Speed in vehicle-relative X direction	Speed in vehicle-relative Y direction	Vertical speed	Yaw rate
SN_RC_VIO_POS_HOLD_CMD	Speed in vehicle-relative X direction	Speed in vehicle-relative Y direction	Vertical speed	Yaw rate
SN_RC_GPS_POS_HOLD_CMD	Speed in vehicle-relative X direction	Speed in vehicle-relative Y direction	Vertical speed	Yaw rate
SN_RC_ALT_HOLD_CMD	Pitch angle	Negative roll angle	Vertical speed	Yaw rate
SN_RC_ALT_HOLD_LOW_ANGLE_CMD	Pitch angle	Negative roll angle	Vertical speed	Yaw rate
SN_RC_THRUST_ANGLE_GPS_HOVER_CMD	Pitch angle	Negative roll angle	Thrust magnitude	Yaw rate
SN_RC_THRUST_ANGLE_CMD	Pitch angle	Negative roll angle	Thrust magnitude	Yaw rate
SN_RC_RATES_CMD	Pitch rate	Negative roll rate	Thrust magnitude	Yaw rate

## 4.2 Building the Source

### 4.2.1 On Target

To build an executable on target, use `gcc` or `g++`:

```
$ g++ my_sn_api_test.cpp -o my_sn_api_test -I/home/linaro/examples/inc -lsnav_arm
```

See the `Makefile` that builds the examples as a reference.

### 4.2.2 Cross Compilation with qnlSDK

Cross compilation is not yet supported but will be added in a future software release.

## 4.3 Running the Executable

1. Verify that Snapdragon Navigator is running.
2. Run the executable.

For example: `$ ./my_sn_api_test`

# 5 Snapdragon Navigator Interface

---

This chapter describes the Snapdragon Navigator interface enumerations, structures, and functions.

## 5.1 Commands

### 5.1.1 Function Documentation

#### 5.1.1.1 `int sn_update_data ( )`

Updates the internal cache of flight control data.

#### Detailed description

This function caches the current state of all other components that can be queried. This function must be called once per control loop before querying the flight software information. This function also handles initialization of API assets and must be called at least once before calling any other API function.

#### Returns

- 0 for success
- -1 for failure (flight software non-functional)

#### Dependencies

None.

### 5.1.1.2 int sn\_spin\_props ( )

Non-blocking attempt to spin propellers.

#### Detailed description

This function does not guarantee that propellers start spinning. Instead, safety checks are performed and then propellers started if deemed safe.

This function introduces a time delay before the propellers spin.

**Note:** For this function to have effect, the following conditions must be met:

- Propellers must not be spinning – Verify using the `sn_get_props_state()` function.
- Vehicle must be in a flight mode, that is, a heartbeat must already be established by calling `sn_send_rc_command()` or a similar function.

Check `SnPropsState` using the `sn_get_props_state()` function to verify that the command executed.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The `sn_update_data()` function must be called at least once prior to calling this function.

### 5.1.1.3 int sn\_stop\_props ( )

Non-blocking attempt to stop propellers.

#### Detailed description

This function does not guarantee that propellers stop spinning. Safety checks are performed internally and propellers stop if deemed safe.

**Note:** For this function to have effect, the following conditions must be met:

- Propellers must be spinning or starting – Verify using the `sn_get_props_state()` function.
- Vehicle must be in a flight mode, that is, a heartbeat must already be established by calling `sn_send_rc_command()` or a similar function.

Check `SnPropsState` using the `sn_get_props_state()` function to verify that the command executed.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

**Dependencies**

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

**5.1.1.4 int sn\_start\_static\_accel\_calibration ( )**

Non-blocking attempt to start static accelerometer calibration.

**Detailed description**

Calibration only starts if it is deemed safe and appropriate for vehicle to do so. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions.

During this calibration, ensure vehicle is completely stationary on a level surface. Use the information in the [GeneralStatus](#) struct to determine whether the calibration succeeds or fails.

**Note:** Vehicle must be rebooted after calibration to enable flight.

**Returns**

- 0 if attempt was received
- -1 for failure (flight software non-functional)

**Dependencies**

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

**5.1.1.5 int sn\_get\_static\_accel\_calibration\_status ( SnCalibStatus \* *status* )**

Gets the static accelerometer calibration status from the internal cache of flight control data. This function can be used to determine if calibration data exists or if the calibration procedure is in progress.

**Associated data types**

[SnCalibStatus](#)

**Parameters**

out	<i>status</i>	Pointer to value to be set to the status of the static accelerometer calibration.
-----	---------------	---

**Returns**

- 0 if attempt was received
- -1 for failure (flight software non-functional)

**Dependencies**

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.6 int sn\_start\_dynamic\_accel\_calibration ( )

Non-blocking attempt to start dynamic accelerometer calibration.

#### Detailed description

Calibration only starts if it is deemed safe and appropriate for vehicle to do so.

Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions.

Use the information in the [GeneralStatus](#) struct to determine whether the calibration succeeds or fails.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.7 int sn\_get\_dynamic\_accel\_calibration\_status ( SnCalibStatus \* status )

Gets the status of dynamic accelerometer calibration from the internal cache of flight control data. This function can be used to determine if calibration data exists or if the calibration procedure is in progress.

#### Associated data types

[SnCalibStatus](#)

#### Parameters

out	<i>status</i>	Pointer to the value to be set to the status of the dynamic accelerometer calibration.
-----	---------------	--

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.8 int sn\_start\_imu\_thermal\_calibration ( )

Non-blocking attempt to start thermal IMU calibration.

#### Detailed description

Calibration only starts if it is deemed safe and appropriate for vehicle to do so. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions.

During this calibration, ensure vehicle is completely stationary on a level surface.

Increase the vehicle temperature during this test to ensure that a large temperature range observed.

Use the information in the [GeneralStatus](#) struct to determine whether the calibration succeeds or fails.

**Note:** The vehicle must be rebooted after calibration to enable flight.

**Note:** A static calibration is required immediately after thermal calibration.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.9 int sn\_get\_imu\_thermal\_calibration\_status ( SnCalibStatus \* *status* )

Gets the status of thermal IMU calibration from the internal cache of flight control data. This function can be used to determine if calibration data exists or if the calibration procedure is in progress.

#### Associated data types

[SnCalibStatus](#)

#### Parameters

out	<i>status</i>	Pointer to the value to be set to the status of the IMU thermal calibration.
-----	---------------	--

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.10 int sn\_start\_optic\_flow\_camera\_yaw\_calibration ( )

Non-blocking attempt to start optic flow camera yaw calibration.

#### Detailed description

Calibration only starts if it is deemed safe and appropriate for the vehicle. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions on how to run this calibration.

**Note:** Vehicle must be rebooted after calibration to enable flight.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.11 int sn\_get\_optic\_flow\_camera\_yaw\_calibration\_status ( SnCalibStatus \* status )

Gets the status of optic flow camera yaw calibration from the internal cache of flight control data. This function can be used to determine if calibration data exists or if the calibration procedure is in progress.

#### Associated data types

[SnCalibStatus](#)

#### Parameters

out	status	Pointer to the value to be set to the status of the optic flow camera yaw calibration.
-----	--------	--

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.



### 5.1.1.12 int sn\_start\_magnetometer\_calibration ( )

Non-blocking attempt to start magnetometer (compass) calibration.

#### Detailed description

Calibration only starts if it is deemed safe and appropriate for the vehicle. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) for instructions on how to run this calibration.

**Note:** The vehicle must be rebooted after calibration to enable flight.

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.13 int sn\_get\_magnetometer\_calibration\_status ( SnCalibStatus \* *status* )

Gets the magnetometer calibration status from the internal cache of flight control data. This function can be used to determine if calibration data exists or if the calibration procedure is in progress.

#### Associated data types

[SnCalibStatus](#)

#### Parameters

out	<i>status</i>	Pointer to the value to be set to the status of the magnetometer calibration.
-----	---------------	---

#### Returns

- 0 if attempt was received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.14 int sn\_send\_esc\_rpm ( int \* rpm\_data, unsigned int size, int fb\_id )

Sends RPM commands to the ESCs and requests feedback.

#### Parameters

in	<i>rpm_data</i>	Pointer to the array containing RPM data to be sent to ESCs. RPMs are ordered in ascending order of ESC ID, e.g., [rpm_0, rpm_1, ..., rpm_n]
in	<i>size</i>	Number of rpm_data array elements.
in	<i>fb_id</i>	ID of the ESC from which feedback is desired. If fb_id = -1, no feedback is requested.

#### Detailed description

Sending this command does not guarantee that the ESCs spin the motors. If the vehicle is not in flight, the flight controller forwards the RPM commands to the ESCs. The ESC identified by fb\_id requests feedback.

**Note:** RPM commands must be sent at a rate between 100 Hz and 500 Hz.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.15 int sn\_send\_esc\_pwm ( int \* *pwm\_data*, unsigned int *size*, int *fb\_id* )

Sends PWM commands to the ESCs and requests feedback.

#### Parameters

in	<i>pwm_data</i>	Pointer to int array containing PWM data in the range [-800, 800] to be sent to ESCs. PWMs are ordered in ascending order of ESC ID, e.g. [pwm_0, pwm_1, ..., pwm_n].
in	<i>size</i>	Number of <i>pwm_data</i> array elements.
in	<i>fb_id</i>	ID of the ESC from which feedback is desired. If <i>fb_id</i> = -1, no feedback is requested.

#### Detailed description

The *pwm\_data* array contains ESC PWMs in the range of [-800, 800] in which 800 corresponds to 100% duty cycle and negative implies reversed direction.

Sending this command does not guarantee that the ESCs spin the motors. If the vehicle is not in flight, the flight controller forwards the PWM commands to the ESCs. The ESC identified by *fb\_id* requests feedback.

**Note:** PWM commands must be sent at a rate between 100 Hz and 500 Hz.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.16 `int sn_send_rc_command ( SnRcCommandType type, SnRcCommandOptions options, float cmd0, float cmd1, float cmd2, float cmd3 )`

Sends an "RC-like" command to the flight controller.

#### Associated data types

[SnRcCommandType](#)  
[SnRcCommandOptions](#)

#### Parameters

in	<i>type</i>	Specification of the desired input interpretation.
in	<i>options</i>	Options for interpreting the command.
in	<i>cmd0</i>	Value in the range [-1.0, 1.0] specifying a "forward/backward" type command in which "forward" is positive.
in	<i>cmd1</i>	Value in the range [-1.0, 1.0] specifying a "left/right" type command in which "left" is positive.
in	<i>cmd2</i>	Value in the range [-1.0, 1.0] specifying an "up/down" type command in which "up" is positive.
in	<i>cmd3</i>	Value in the range [-1.0, 1.0] specifying a "rotate" type command in which rotating counter-clockwise is positive.

#### Detailed description

This function sends four dimensionless control commands to the flight controller and establishes a heartbeat for the API application. The interpretation of the four commands depends on the mode, which can be obtained from the `current_mode` field of the [GeneralStatus](#) struct. The desired meaning of the four commands is specified with the `type` parameter. A heartbeat must be established by calling this function before the flight controller allows the API to take control, such as to start spinning the propellers.

See Section [4.1.1](#) for the meaning of the four commands in different contexts.

Suggested [SnRcCommandOptions](#) option usage:

- `RC_OPT_DEFAULT_RC` for intuitive joystick control, including a small deadband to prevent drift and more intuitive mapping
- `RC_OPT_LINEAR_MAPPING` for absolute control of outputs – Useful with the [sn\\_apply\\_cmd\\_mapping\(\)](#) function

**Note:** RC commands must be sent at a rate of at least 50 Hz.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)
- -2 if any command is NaN

## Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.17 int sn\_apply\_cmd\_mapping ( SnRcCommandType *type*, SnRcCommandOptions *options*, float *input0*, float *input1*, float *input2*, float *input3*, float \* *cmd0*, float \* *cmd1*, float \* *cmd2*, float \* *cmd3* )

Converts dimensioned commands into dimensionless commands.

## Associated data types

[SnRcCommandType](#)  
[SnRcCommandOptions](#)

## Parameters

in	<i>type</i>	Command type remapped to match the type used subsequently in the <a href="#">sn_send_rc_command()</a> function.
in	<i>options</i>	Options to apply during mapping. See <a href="#">sn_send_rc_command()</a> .
in	<i>input0</i>	Dimensioned command to be mapped into <i>cmd0</i> .
in	<i>input1</i>	Dimensioned command to be mapped into <i>cmd1</i> .
in	<i>input2</i>	Dimensioned command to be mapped into <i>cmd2</i> .
in	<i>input3</i>	Dimensioned command to be mapped into <i>cmd3</i> .
out	<i>cmd0</i>	Mapped unitless command 0 to be sent with the <a href="#">sn_send_rc_command()</a> function.
out	<i>cmd1</i>	Mapped unitless command 1 to be sent with the <a href="#">sn_send_rc_command()</a> function.
out	<i>cmd2</i>	Mapped unitless command 2 to be sent with the <a href="#">sn_send_rc_command()</a> function.
out	<i>cmd3</i>	Mapped unitless command 3 to be sent with the <a href="#">sn_send_rc_command()</a> function.

## Detailed description

This function remaps commands with real units into the appropriate dimensionless commands to be sent with [sn\\_send\\_rc\\_command\(\)](#) function. Mapping is based on on the type and options parameters. See Section [4.1.1](#) for more information.

## Returns

- 0 if command received
- -1 for failure (flight software non-functional)

## Dependencies

None.

**See also**

[sn\\_send\\_rc\\_command\(\)](#)

**5.1.1.18 const char\* sn\_get\_enum\_string ( char \* *type*, int *value* )**

Gets a human-readable string associated with a specific enum type and value.

**Parameters**

in	<i>type</i>	String specifying the type of enum value provided. For example, "SnMode", "SnMotorState", etc.
in	<i>value</i>	Value to be converted to a string (based on the type provided).

**Returns**

Pointer to the string corresponding to the provided enum.

**Dependencies**

None.

**5.1.1.19 const char\* sn\_get\_cmd\_name ( SnRcCommandType *type* )**

Gets the the name of an RC command from the type.

**Parameters**

in	<i>type</i>	RC command type of interest.
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**Returns**

Pointer to the command name.

**Dependencies**

None.

### 5.1.1.20 `const char* sn_get_dimensioned_units ( SnRcCommandType type, int index )`

Gets the the dimensioned units of an RC command from the type and index.

#### Associated data types

[SnRcCommandType](#)

#### Parameters

in	<i>type</i>	RC command type of interest.
in	<i>index</i>	Index in range [0, 3] corresponding to cmd0 through cmd3.

#### Returns

Pointer to the units of a particular command.

#### Dependencies

None.

### 5.1.1.21 `float sn_get_min_value ( SnRcCommandType type, int index )`

Gets the the minimum value in real units for an RC command from the type and index.

#### Associated data types

[SnRcCommandType](#)

#### Parameters

in	<i>type</i>	RC command type of interest.
in	<i>index</i>	Index in range [0,3] corresponding to cmd0 through cmd3.

#### Detailed description

This function returns the smallest possible command to be applied to the system. The returned value maps to a dimensionless value of -1.0.

Use [sn\\_get\\_dimensioned\\_units\(\)](#) to get a string descripton of the units.

#### Returns

Minimum-allowed value in real units.

#### Dependencies

None.

### 5.1.1.22 float sn\_get\_max\_value ( SnRcCommandType *type*, int *index* )

Gets the the maximum value in real units for an RC command from the type and index.

#### Associated data types

[SnRcCommandType](#)

#### Parameters

in	<i>type</i>	RC command type of interest.
in	<i>index</i>	Index in the range [0,3] corresponding to cmd0 through cmd3.

#### Detailed description

This function returns the largest possible command to be applied to the system. This value maps to a dimensionless value of 1.0.

Use the [sn\\_get\\_dimensioned\\_units\(\)](#) function to get a string descripton of the units.

#### Returns

Maximum-allowed value in real units.

#### Dependencies

None.



### 5.1.1.23 int sn\_send\_thrust\_att\_ang\_vel\_command ( float *thrust*, float *qw*, float *qx*, float *qy*, float *qz*, float *wx*, float *wy*, float *wz* )

Sends thrust, attitude, and angular velocity.

#### Parameters

in	<i>thrust</i>	Commanded thrust in grams.
in	<i>qw</i>	Scalar component of quaternion.
in	<i>qx</i>	X component of vector part of the quaternion.
in	<i>qy</i>	Y component of vector part of the quaternion.
in	<i>qz</i>	Z component of vector part of the quaternion.
in	<i>wx</i>	X component of angular velocity in rad/s.
in	<i>wy</i>	Y component of angular velocity in rad/s.
in	<i>wz</i>	Z component of angular velocity in rad/s.

#### Detailed description

This function sends the desired thrust in grams, desired attitude represented as a quaternion, and the desired angular velocity vector in rad/s to the flight controller.

The quaternion is in the following form:

$$q = qw + qx*i + qy*j + qz*k$$

**Note:** Be cautious – This function is for advanced users.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)
- -2 if any input arguments are NaN

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.24 int sn\_send\_trajectory\_tracking\_command ( SnPositionController *controller*, SnTrajectoryOptions *options*, float *x*, float *y*, float *z*, float *xd*, float *yd*, float *zd*, float *xdd*, float *ydd*, float *zdd*, float *yaw*, float *yaw\_rate* )

Sends position, angle, and derivatives for advanced trajectory tracking.

#### Parameters

in	<i>controller</i>	Desired position controller.
in	<i>options</i>	Options for trajectory tracking.
in	<i>x</i>	X component of the position vector in the specified frame.
in	<i>y</i>	Y component of the position vector in the specified frame.
in	<i>z</i>	Z component of the position vector in the specified frame.
in	<i>xd</i>	X component of the velocity vector in the specified frame.
in	<i>yd</i>	Y component of the velocity vector in the specified frame.
in	<i>zd</i>	Z component of the velocity vector in the specified frame.
in	<i>xdd</i>	X component of the acceleration vector in the specified frame.
in	<i>ydd</i>	Y component of the acceleration vector in the specified frame.
in	<i>zdd</i>	Z component of the acceleration vector in the specified frame.
in	<i>yaw</i>	Gravity-aligned yaw angle relative to the specified frame.
in	<i>yaw_rate</i>	Rate at which the gravity-aligned yaw angle changes.

#### Detailed description

This function allows precise control of the desired trajectories to use feed-forward acceleration angles.

**Note:** This function is intended for advanced users – A trajectory planner must be used to update these options at a minimum of 50 Hz.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)
- -2 if any input arguments are NaN
- -3 if the specified control mode is unavailable

#### Dependencies

None.

### 5.1.1.25 int sn\_set\_battery\_voltage ( float *voltage* )

Sets the battery voltage.

#### Parameters

in	<i>voltage</i>	Battery voltage (V).
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#### Detailed description

This function overrides the internal battery voltage estimate. This function must be called at a rate faster than 5 Hz for the value to be considered valid, otherwise the flight controller defaults to the internal estimate of battery voltage.

#### Returns

- 0 if command received
- -1 for failure (flight software non-functional)
- -2 if the voltage is less than or equal to zero, or is NaN

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.26 int sn\_get\_flight\_data\_ptr ( int *size\_cached\_struct*, SnavCachedData \*\* *snav\_cached\_data\_struct* )

Gets the pointer to the Snapdragon Navigator cached data structure.

#### Associated data types

[SnavCachedData](#)

#### Parameters

in	<i>size_cached_struct</i>	Structure size. Ensures that the header file stays in sync. This argument must be sizeof(SnavCachedData).
out	<i>snav_cached_data_struct</i>	Pointer to be filled with the cached data structure pointer values. This structure is updated with a call to <a href="#">sn_update_data()</a> .

#### Returns

- 0 if flight data pointer returns successfully
- -1 for failure to get the pointer to flight data

**Dependencies**

None.

### 5.1.1.27 `int sn_set_led_colors ( const uint8_t * led_colors_input_array, int led_colors_size, int led_colors_timeout_us )`

Sets the LED colors, overriding the Snapdragon Navigator LED colors.

**Parameters**

in	<i>led_colors_input_array</i>	Array of RGB triplets. The range for each value is 0-255.
in	<i>led_colors_size</i>	Size of the input color array – Value must be greater than zero, less than 25, and a multiple of 3.
in	<i>led_colors_timeout_us</i>	Timeout in microseconds for Snapdragon Navigator to take over LED control after the API color commands stop.

**Detailed description**

This function overrides the internal output of the LED colors. Currently only a single RGB triplet is used (first three bytes). The timeout variable specifies the time in microseconds when the LED output switches back to Snapdragon Navigator control after the API color commands stop updating. Color values are interpreted as binary (0 = Off, otherwise = On).

**Returns**

- 0 command received
- -1 critical failure (flight software is most likely non-functional)
- -2 bad length of the color data array
- -3 negative value provided as timeout

**Dependencies**

The [sn\\_update\\_data\(\)](#) function must be called at least once prior to calling this function.

### 5.1.1.28 int sn\_get\_esc\_state\_feedback ( SnMotorState \* *state\_feedback*, unsigned int *size*, unsigned int \* *used* )

Gets the ESC state feedback data from from the internal cache of flight control data.

#### Associated data types

[SnMotorState](#)

#### Parameters

out	<i>state_feedback</i>	Pointer to the array to be filled with states from ESCs. The array is filled in ascending order of ESC IDs, e.g. [state_0, state_1, ..., state_n]
in	<i>size</i>	Number of state_feedback array elements.
out	<i>used</i>	Pointer to the value to be set to the number of elements used of the state_feedback array

#### Detailed description

The given array must have a number of elements equal to the number of ESCs connected to the flight controller.

If the given array is too small to hold all of the feedback data, no data copies into the array and the function returns an error code.

**Note:** ESC feedback data is only updated if feedback is requested. See the [sn\\_send\\_esc\\_rpm\(\)](#) and [sn\\_send\\_esc\\_pwm\(\)](#) functions.

#### Returns

- 0 for success
- -1 for failure (flight software non-functional)
- -2 if the size of the array is not big enough to hold all of the feedback data

#### Dependencies

The [sn\\_update\\_data\(\)](#) function must be called to refresh the internal cache of flight control data.

#### See also

[sn\\_send\\_esc\\_rpm\(\)](#)  
[sn\\_send\\_esc\\_pwm\(\)](#)

## 5.2 Datatypes

### 5.2.1 Data Structure Documentation

#### 5.2.1.1 struct VersionInfo

Version information required to uniquely identify the software and device.

##### Data fields

Type	Parameter	Description
char	device_ identifier[20]	Version of the DSPaL library used.
char	compile_ date[16]	Null terminated string containing the compilation date.
char	compile_ time[16]	Null terminated string containing the compilation time.
char	library_ version[18]	Null terminated string representing version information.
char	library_ hash[41]	Null terminated string with a unique build identifier.
char	mac_ address[18]	Null terminated string containing wlan0 mac address if it was successfully polled.
char	dspal_ version[40]	Version of the DSPaL library used.
int32_t	esc_hw_ version[8]	Hardware revision of the ESCs.
int32_t	esc_sw_ version[8]	Software version of the ESCs.

#### 5.2.1.2 struct MvSdkVersionInfo

Machine vision (MV) version information.

##### Data fields

Type	Parameter	Description
char	version_ recommended[18]	Null-terminated string containing the recommended MV SDK version.
char	version_ found[18]	Null-terminated string containing the MV SDK version found on the system.
uint8_t	strict_checking	Specifies if the recommended MV SDK version is required.

### 5.2.1.3 struct SensorImuApiVersionInfo

Version of the sensor\_imu API.

#### Data fields

Type	Parameter	Description
char	version_ recommended[18]	Null-terminated string containing the recommended sensor_imu API version.
char	version_ found[18]	Null-terminated string containing the sensor_imu API version found on the system.
uint8_t	strict_checking	Specifies if the recommended sensor_imu API version is required.

### 5.2.1.4 struct GeneralStatus

General system state information for debugging system issues.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the most recent iteration of the main flight loop started. (Units: $\mu$ s)
uint32_t	loop_cntr	Number of times the control loop has run.
int32_t	desired_mode	Cast to enum: <a href="#">SnMode</a> . Desired mode that the flight controller attempts to transition to.
int32_t	current_mode	Cast to enum: <a href="#">SnMode</a> . Current flight controller mode.
float	voltage	Estimated input system voltage. (Units: V)
float	current	If available, the estimated electrical current being used by the system. (Units: A)
uint8_t	is_using_ external_ voltage	1 – Voltage is being measured by the external voltage driver. 0 – Voltage is measured using ESCs.
int32_t	props_state	Cast to enum: <a href="#">SnPropsState</a> . Propeller state.
uint8_t	on_ground	Flag representing flight controller's detection of the device being on the ground. 1 – Device on the ground, 0 otherwise.
int32_t	input_cmd_ type	Cast to enum: <a href="#">SnInputCommandType</a> . Input command type.
char	last_error_ code[32]	Null-terminated string to represent the last error code detected. To allow detection of infrequent errors, this string persists even if cleared by an error code.

### 5.2.1.5 struct DataStatus

Status of various sensors and estimators.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the struct was logged. (Units: ms)
uint32_t	loop_cntr	Number of times at which the control loop has run.

Type	Parameter	Description
int32_t	imu_0_status	Cast to enum: <a href="#">SnDataStatus</a> . IMU sensor status.
int32_t	baro_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Barometer sensor status.
int32_t	esc_feedback_status	Cast to enum: <a href="#">SnDataStatus</a> . ESC feedback status.
int32_t	mag_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Magnetometer sensor.
int32_t	gps_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Global positioning GPS sensor status.
int32_t	sonar_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Sonar sensor status.
int32_t	optic_flow_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Optic flow (DFT) sensor status.
int32_t	spektrum_rc_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Spektrum RC sensor status.
int32_t	api_rc_status	Cast to enum: <a href="#">SnDataStatus</a> . API RC command status.
int32_t	rc_active_status	Cast to enum: <a href="#">SnDataStatus</a> . Active RC command status.
int32_t	height_estimator_status	Cast to enum: <a href="#">SnDataStatus</a> . Height estimator status.
int32_t	attitude_estimator_status	Cast to enum: <a href="#">SnDataStatus</a> . Attitude estimator status.
int32_t	vio_0_status	Cast to enum: <a href="#">SnDataStatus</a> . Visual inertial odometry (VIO) status.
int32_t	voa_status	Cast to enum: <a href="#">SnDataStatus</a> . Visual obstacle avoidance (VOA) status.
int32_t	api_trajectory_status	Cast to enum: <a href="#">SnDataStatus</a> . Status of trajectory data.

### 5.2.1.6 struct UpdateRates

System and sensor update rates.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	loop_cntr	Number of times the control loop has run.
float	control_loop_freq	Main control loop update frequency. (Units: Hz)
float	imu0_freq	IMU0 update frequency. (Units: Hz)
float	imu1_freq	IMU1 update frequency. (Units: Hz)
float	imu2_freq	IMU2 update frequency. (Units: Hz)
float	baro0_freq	Baro0 update frequency. (Units: Hz)
float	mag0_freq	Mag0 update frequency. (Units: Hz)
float	sonar0_freq	Sonar0 update frequency. (Units: Hz)
float	rc0_freq	RC0 update frequency. (Units: Hz)
float	esc_fb_freq	ESC feedback update frequency. (Units: Hz)
float	gnss0_freq	GNSS0 update frequency. (Units: Hz)
float	gnss1_freq	GNSS1 update frequency. (Units: Hz)
float	voa_freq	VOA update frequency. (Units: Hz)



### 5.2.1.7 struct AttitudeEstimate

Estimate of the vehicle orientation.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp. (Units: $\mu$ s)
uint32_t	cntr	Counter incremented upon successful computation of the attitude estimate.
float	roll	Roll angle using Tait-Bryan ZYX. (Units: rad)
float	pitch	Pitch angle using Tait-Bryan ZYX. (Units: rad)
float	yaw	Yaw angle using Tait-Bryan ZYX. (Units: rad)
float	rotation_-matrix[9]	Rotation matrix from vehicle body to world in row-major order.
float	magnetic_yaw_offset	Yaw angle with respect to magnetic east = yaw + magnetic_yaw_offset. (Units: rad)
float	magnetic_declination	Yaw angle with respect to true east = yaw + magnetic_yaw_offset + magnetic_declination. (Units: rad)

### 5.2.1.8 struct CpuStats

Apps processor CPU status.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times data was updated
uint64_t	time_apps_us	Timestamp from the Apps processor. (Units: $\mu$ s)
uint64_t	time_apps_real_us	Timestamp from the Apps processor realtime clock. (Units: $\mu$ s)
float	cur_freq[4]	Current Apps processor CPU frequency. If the CPU is not online, Snapdragon Navigator reads NaN. (Units: GHz)
float	max_freq[4]	Maximum Apps processor CPU frequency – Can be throttled due to temperature. If the CPU is not online, Snapdragon Navigator reads NaN. (Units: GHz)
float	temp[22]	Temperature measurements from thermal zones. Reads NaN if the thermal zone is disabled. (Units: $^{\circ}$ C)

### 5.2.1.9 struct Imu0Raw

Inertial measurement unit 0 raw data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu$ s)
uint32_t	cntr	Number of measurements received.

Type	Parameter	Description
float	temp	IMU temperature. (Units: °C)
float	lin_acc[3]	Linear acceleration. (Units: gravity (~9.81 m/s/s))
float	ang_vel[3]	Angular velocity. (Units: rad/s)

### 5.2.1.10 struct Imu1Raw

Inertial measurement unit 1 raw data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu$ s)
uint32_t	cntr	Number of measurements received.
float	temp	IMU temperature. (Units: °C)
float	lin_acc[3]	Linear acceleration. (Units: gravity (~9.81 m/s/s))
float	ang_vel[3]	Angular velocity. (Units: rad/s)

### 5.2.1.11 struct Imu2Raw

Inertial measurement unit 2 raw data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu$ s)
uint32_t	cntr	Number of measurements received.
float	temp	IMU temperature. (Units: °C)
float	lin_acc[3]	Linear acceleration. (Units: gravity (~9.81 m/s/s))
float	ang_vel[3]	Angular velocity. (Units: rad/s)

### 5.2.1.12 struct Imu0Compensated

Inertial measurement unit (IMU) data after compensation.

#### Data fields

Type	Parameter	Description
int64_t	time	Time data was received. (Units: $\mu$ s)
uint32_t	cntr	Number of compensated measurements recorded.
float	temp	Temperature of IMU. (Units: °C)
float	lin_acc[3]	Linear acceleration. (Units: gravity (~9.81 m/s/s))
float	ang_vel[3]	Angular velocity. (Units: rad/s)

### 5.2.1.13 struct Imu0CalibrationThermal

Data results from IMU temperature calibration.

#### Data fields

Type	Parameter	Description
float	accel_slope[3]	XYZ slopes for accelerometer temperature calibration. (Units: gravity/ °C)
float	accel_offset[3]	XYZ offsets for accelerometer temperature calibration. (Units: gravity)
float	accel_-residual[3]	Average squared residual for accelerometer temperature calibration. (Units: gravity^2)
float	gyro_slope[3]	XYZ slopes for gyroscope temperature calibration. (Units: (rad/s)/ °C)
float	gyro_offset[3]	XYZ offsets for gyroscope temperature calibration. (Units: (rad/s)))
float	gyro_-residual[3]	Average squared residual for gyroscope temperature calibration. (Units: (rad/s)^2)

### 5.2.1.14 struct Imu0CalibrationOffset

IMU sensor offset values.

#### Data fields

Type	Parameter	Description
char	name[16]	Type of offset calibration (e.g., static or dynamic).
float	accel_offset[3]	XYZ accelerometer offsets from accelerometer offset calibration. (Units: gravity (~9.81 m/s/s))
float	avg_thrust	Average thrust found from in flight accelerometer calibration. (Units: g)
float	roll_trim_offset	Roll trim offset from in flight accelerometer calibration. (Units: g)
float	pitch_trim_-offset	Pitch trim offset from in flight accelerometer calibration. (Units: g)

### 5.2.1.15 struct Barometer0Raw

Raw barometer data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times data was read.
float	pressure	Atmospheric pressure measurement. (Units: Pa)
float	temp	Temperature of the sensor. (Units: °C)

### 5.2.1.16 struct Sonar0Raw

Raw sonar data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the struct was logged. (Units: $\mu s$ )
uint32_t	cntr	Number of times the data was read.
float	range	Range measurement. (Units: m)

### 5.2.1.17 struct Mag0Raw

Raw magnetometer data from the mag0 sensor.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu s$ )
uint32_t	cntr	Number of data packets received.
uint8_t	identifier	Type of compass sensor.
float	field[3]	XYZ components of the magnetic field in the sensor frame. (Units: $\mu T$ )

### 5.2.1.18 struct Mag1Raw

Raw magnetometer data from the mag1 sensor.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu s$ )
uint32_t	cntr	Number of data packets received.
uint8_t	identifier	Type of compass sensor.
float	field[3]	XYZ components of the magnetic field in the sensor frame. (Units: $\mu T$ )

### 5.2.1.19 struct Mag0Compensated

Mag0 sensor data after compensation.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the data was received. (Units: $\mu s$ )
uint32_t	cntr	Number of data packets received.

Type	Parameter	Description
uint8_t	identifier	Type of compass sensor.
float	field[3]	XYZ components of the magnetic field in the sensor frame.

### 5.2.1.20 struct Mag1Compensated

Mag1 sensor data after compensation.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the data was received. (Units: $\mu s$ )
uint32_t	cntr	Number of data packets received.
uint8_t	identifier	Type of compass sensor.
float	field[3]	XYZ components of the magnetic field in the sensor frame.

### 5.2.1.21 struct Mag0Calibration3D

Data results from Mag0 3D calibration.

#### Data fields

Type	Parameter	Description
float	matrix[9]	Scale parameters of mapping.
float	offset[3]	XYZ offset of mapping.

### 5.2.1.22 struct SpektrumRc0Raw

Raw Spektrum RC data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the struct was logged. (Units: $\mu s$ )
uint32_t	cntr	Number of times the data was read.
int32_t	protocol	Cast to enum: <a href="#">SnRcReceiverMode</a> . RC protocol identifier
uint8_t	num_channels	Number of RC channels being populated.
uint16_t	vals[16]	Raw Spektrum channel values.

### 5.2.1.23 struct ApiRcRaw

RC commands sent through the API.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times the data was read.
int32_t	cmd_type	Cast to enum: <a href="#">SnRcCommandType</a> . How the command is interpreted (if possible).
int32_t	cmd_options	Cast to enum: <a href="#">SnRcCommandOptions</a> . Options used to deviate from linear mapping.
float	cmd[4]	Unitless RC-type command in range [-1, 1].

### 5.2.1.24 struct ApiThrustAttAngVel

Thrust, attitude, and angular velocity commands sent through the API.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
float	thrust	Thrust.
float	qw	Attitude quaternion W value.
float	qx	Attitude quaternion X value.
float	qy	Attitude quaternion Y value.
float	qz	Attitude quaternion Z value.
float	ang_vel[3]	Angular velocity.

### 5.2.1.25 struct ApiPropsCmd

Received API spin or stop propellers commands.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
uint8_t	api_spin_props-rcvd	1 if spin-propellers command received, 0 otherwise.
uint8_t	api_stop_props-rcvd	1 if stop-propellers command received, 0 otherwise.

### 5.2.1.26 struct RcActive

RC commands for control.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times the data was read.
int32_t	source	Cast to enum: <a href="#">SnRcCommandSource</a> . Source of the active RC commands.
int32_t	cmd_type	Cast to enum: <a href="#">SnRcCommandType</a> . Specifies how the commands are interpreted (if possible). Irrelevant if the source is Spektrum RC.
int32_t	cmd_options	Cast to enum: <a href="#">SnRcCommandOptions</a> . Options used to deviate from linear mapping.
float	cmd[4]	Unitless RC-type command in range [-1, 1].

### 5.2.1.27 struct Camera0FrameInfo

Captured camera frame information from the downward camera.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times the data was read.
uint32_t	frame_num	Frame number received, starting at 0.
int64_t	frame_- timestamp	Timestamp of frame. (Units: $\mu$ s)
int64_t	preview_- timestamp	Timestamp of preview callback. (Units: $\mu$ s)
float	exposure	Normalized exposure setting used to take the frame.
float	gain	Normalized gain setting used to take the frame.
float	average_- luminance	Normalized average luminance of the frame.

### 5.2.1.28 struct OpticFlow0Raw

Downward facing tracker (DFT) data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	cntr	Number of times the data was read.
float	pixel_flow[2]	Pixel displacement between subsequent image frames. Pixel flow is in the opposite direction of camera (and therefore vehicle) movement. (Units: pixels)

Type	Parameter	Description
int32_t	sample_size	Number of inliers after calculation of displacement.
float	error_sum	Error metric, sum of squared error over sample size points.

### 5.2.1.29 struct OpticFlow0CalibrationTilt

Downfacing camera calibration for tilt angle (optic flow camera yaw calibration).

#### Data fields

Type	Parameter	Description
float	x_factor	Tilt factor in X. (Units: pixels/rad)
float	y_factor	Tilt factor in Y. (Units: pixels/rad)

### 5.2.1.30 struct Gps0Raw

Raw GPS data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which the data was received. (Units: $\mu$ s)
uint32_t	cntr	Number of complete messages received.
int32_t	identifier	Cast to enum: <a href="#">SnGnssReceiverType</a> . Type of GNSS receiver.
uint32_t	num_errors	Number of CRC errors.
uint32_t	gps_week	GPS week number. (Units: weeks)
uint32_t	gps_time_sec	Time of week. (Units: sec)
uint32_t	gps_time_nsec	Time of week. (Units: ns)
int32_t	latitude	Position latitude. (Units: $\text{deg} \times 10^7$ )
int32_t	longitude	Position longitude. (Units: $\text{deg} \times 10^7$ )
float	altitude	Altitude at mean sea level (MSL). (Units: m)
float	lin_vel[3]	Velocity of the north-east-up (NEU) frame. (Units: m/s)
uint8_t	fix_type	Fix type/quality.
uint8_t	num_satellites	Number of satellites used in the solution.
float	horizontal_acc	Horizontal accuracy of the position estimate. (Units: m)
float	speed_acc	Horizontal speed accuracy. (Units: m/s)
uint8_t	sv_ids[32]	Satellite identification number.
uint8_t	sv_cn0[32]	Satellite signal strength. (Units: C/N0)

### 5.2.1.31 struct TrajectoryDataRaw

Raw API data for trajectory control input.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp. (Units: $\mu$ s)



Type	Parameter	Description
uint32_t	cntr	Number of messages received.
int32_t	controller	Cast to enum: <a href="#">SnPositionController</a> . Desired position controller to use.
int32_t	options	Cast to enum: <a href="#">SnTrajectoryOptions</a> . Trajectory options.
float	position[3]	Desired position for the controller to achieve. (Units: m)
float	velocity[3]	Desired velocity for the controller to achieve. (Units: m/s)
float	acceleration[3]	Desired acceleration for controller to use as a feed-forward term. (Units: m/s/s)
float	yaw	Desired gravity aligned yaw angle for the controller to achieve. (Units: raw)
float	yaw_rate	Desired gravity aligned yaw angle rate for the controller to achieve. (Units: raw)

### 5.2.1.32 struct VioPosVel

VIO position and velocity control data.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp. (Units: $\mu$ s)
uint32_t	cntr	Counter that is incremented with each control loop.
float	position_-estimated[3]	Estimated XYZ position. (Units: m)
float	velocity_-estimated[3]	Estimated XYZ velocity. (Units: m/s)
float	yaw_estimated	Estimated yaw angle. (Units: rad)
float	position_-desired[3]	Desired XYZ position. (Units: m)
float	velocity_-desired[3]	Desired XYZ velocity. (Units: m/s)
float	yaw_desired	Desired yaw angle. (Units: rad)
uint8_t	is_valid	Is 1 if the VIO position and velocity data is valid.

### 5.2.1.33 struct GpsPosVel

GPS position and velocity control data.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp. (Units: $\mu$ s)
uint32_t	cntr	Counter that is incremented with each control loop.
int32_t	identifier	Cast to enum: <a href="#">SnGnssReceiverType</a> . Type of GNSS receiver.
float	position_-estimated[3]	Estimated XYZ position. +X is east, +Y is north, +Z is vertically up (Units: m)
float	velocity_-estimated[3]	Estimated XYZ velocity. (Units: m/s)

Type	Parameter	Description
float	yaw_estimated	Estimated yaw angle of the vehicle's body-fixed frame with respect to the East North Up (ENU) frame. (Units: rad)
float	position_-desired[3]	Desired XYZ position. (Units: m)
float	velocity_-desired[3]	Desired XYZ velocity. (Units: m/s)
float	yaw_desired	Desired yaw angle of the vehicle's body-fixed frame with respect to the ENU frame. (Units: rad)
uint8_t	is_enabled	If enabled (set to 1), this data is populated when the vehicle gets a GPS lock.

### 5.2.1.34 struct OpticFlowPosVel

Optic flow position and velocity control data.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp. (Units: $\mu$ s)
uint32_t	cntr	Number of times the data was read.
float	position_-estimated[3]	Estimated XYZ position. (Units: m)
float	velocity_-estimated[3]	Estimated XYZ velocity. (Units: m/s)
float	yaw_estimated	Estimated yaw angle. (Units: rad)
float	position_-desired[3]	Desired XYZ position. (Units: m)
float	velocity_-desired[3]	Desired XYZ velocity. (Units: m/s)
float	yaw_desired	Desired yaw angle. (Units: rad)
uint8_t	is_valid	1 if the optic flow position and velocity data are valid, otherwise 0.

### 5.2.1.35 struct EscRaw

Raw ESC data.

#### Data fields

Type	Parameter	Description
uint32_t	iter	Loop iteration in which data was logged.
int64_t	time	Time at which this data was published. (Units: $\mu$ s)
uint32_t	bytes_tx	Number of bytes received from ESCs. (Units: bytes)
uint32_t	bytes_rx	Number of bytes received from all ESCs. (Units: bytes)
uint32_t	errors_rx	Number of feedback read errors.
uint32_t	packet_number	Packet number.
uint8_t	packet_cntr[8]	Number of control packets received by each ESC.
uint32_t	packets_rx[8]	Number of packets received from each ESC. (Units: packets)

Type	Parameter	Description
int16_t	rpm[8]	Motor RPM.
int8_t	power[8]	Power applied by the ESC. (Units: %)
float	voltage[8]	Voltage measured by each ESC. (Units: V)
uint8_t	states[8]	ESC state.

### 5.2.1.36 struct VoaData

VOA data.

#### Data fields

Type	Parameter	Description
int64_t	time	Time at which this data was received. (Units: $\mu$ s)
uint32_t	cntr	DSP counter of data received.
uint64_t	apps_proc_time	Timestamp from the applications processor. (Units: $\mu$ s)
uint32_t	apps_proc_cntr	Counter of data sent from the applications processor.
int	num_points	Number of points used for VOA control.

### 5.2.1.37 struct VoaStatus

Information about state of VOA processing.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp of information (Units: $\mu$ s)
uint32_t	cntr	Monotonically increasing counter
uint8_t	voa_enabled	1 if VOA is enabled, 0 otherwise.
uint8_t	voa_running	1 if VOA is running and has the ability to modify control output, 0 otherwise.
uint8_t	voa_active	1 if VOA is currently modifying control output, 0 otherwise.

### 5.2.1.38 struct RelativeObstacleDistances

Raw obstacle distance information if available.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp of data. (Units: $\mu$ s)
uint32_t	cntr	Data log counter.
float	relative_ distances[4]	Array of distances sensed in the body coordinate frame and centered around the forward +X direction. Each number corresponds to an angle specified in the parameter file. By default, each number corresponds to 0.3 radians. (Units: m)

### 5.2.1.39 struct GpsOrigin

GPS latitude and longitude at the time of initial GPS lock.

#### Data fields

Type	Parameter	Description
int64_t	time	Timestamp of initial GPS lock. (Units: $\mu$ s)
int32_t	origin_latitude	Latitude at GPS lock.
int32_t	origin_longitude	Longitude at GPS lock.

### 5.2.1.40 struct FiducialMarkerWorldOffsetRaw

Raw world offset computation from fiducial markers.

#### Data fields

Type	Parameter	Description
uint64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	frame_id	Camera frame ID used for marker detection.
int64_t	frame_timestamp_ns	Timestamp of the camera frame used for marker detection. (Units: ns)
uint32_t	num_markers_used	Number of marker detections in the frame used in offset computation.
float	yaw_offset_raw	Raw Yaw offset. (Units: rad)
float	pos_offset_raw[3]	Raw XYZ offset (Units: m)

### 5.2.1.41 struct FiducialMarkerWorldOffsetData

Filtered world offset computation from fiducial markers.

#### Data fields

Type	Parameter	Description
uint64_t	time	Time at which the struct was logged. (Units: $\mu$ s)
uint32_t	num_raw_offset_updates	Number of times that the raw offsets were computed.
float	pos_offset[3]	Vector from origin of marker world frame to origin of Snapdragon Navigator world frame represented in the Snapdragon Navigator world frame. (Units: m)
float	yaw_offset	Yaw component of the rotation from the Snapdragon Navigator world frame to the marker world frame. (Units: rad)
float	pos_world[3]	Estimated position represented in the marker world frame. (Units: m)
float	yaw_world	Estimated yaw angle represented in the marker world frame. (Units: rad)

### 5.2.1.42 struct SimGroundTruth

Simulation ground truth.

#### Data fields

Type	Parameter	Description
float	time	Sim current time. (Units: s)
float	x	Sim true X position. (Units: m)
float	y	Sim true Y position. (Units: m)
float	z	Sim true Z position. (Units: m)
float	x_dot	Sim true X velocity. (Units: m/s)
float	y_dot	Sim true Y velocity. (Units: m/s)
float	z_dot	Sim true Z velocity. (Units: m/s)
float	roll	Sim true roll. (Units: deg)
float	pitch	Sim true pitch. (Units: deg)
float	yaw	Sim true yaw. (Units: deg)
float	R[9]	Sim world to body rotation matrix.

### 5.2.1.43 struct SnavCachedData

Snapdragon Navigator cached data for the [sn\\_get\\_flight\\_data\\_ptr\(\)](#) function.

#### Data fields

Type	Parameter	Description
<a href="#">VersionInfo</a>	version_info	Version information required to uniquely identify the software and device.
<a href="#">MvSdkVersion-Info</a>	mv_sdk_- version_info	Machine vision (MV) version information.
<a href="#">SensorImuApi-VersionInfo</a>	sensor_imu_- api_version_- info	Version of the sensor_imu API.
<a href="#">GeneralStatus</a>	general_status	General system state information for debugging system issues.
<a href="#">DataStatus</a>	data_status	Status of various sensors and estimators.
<a href="#">UpdateRates</a>	update_rates	System and sensor update rates.
<a href="#">Attitude-Estimate</a>	attitude_- estimate	Estimate of the vehicle orientation.
<a href="#">CpuStats</a>	cpu_stats	Apps processor CPU status.
<a href="#">Imu0Raw</a>	imu_0_raw	Inertial measurement unit 0 raw data.
<a href="#">Imu1Raw</a>	imu_1_raw	Inertial measurement unit 1 raw data.
<a href="#">Imu2Raw</a>	imu_2_raw	Inertial measurement unit 2 raw data.
<a href="#">Imu0-Compensated</a>	imu_0_- compensated	Inertial measurement unit (IMU) data after compensation.
<a href="#">Imu0-Calibration-Thermal</a>	imu_0_- calibration_- thermal	Data results from IMU temperature calibration.
<a href="#">Imu0-Calibration-Offset</a>	imu_0_- calibration_- offset	IMU sensor offset values.

Type	Parameter	Description
Barometer0-Raw	barometer_0_-raw	Raw barometer data.
Sonar0Raw	sonar_0_raw	Raw sonar data.
Mag0Raw	mag_0_raw	Raw magnetometer data from the mag0 sensor.
Mag1Raw	mag_1_raw	Raw magnetometer data from the mag1 sensor.
Mag0-Compensated	mag_0_-compensated	Mag0 sensor data after compensation.
Mag1-Compensated	mag_1_-compensated	Mag1 sensor data after compensation.
Mag0-Calibration3D	mag_0_-calibration_3d	Data results from Mag0 3D calibration.
SpektrumRc0-Raw	spektrum_rc_0_-raw	Raw Spektrum RC data.
ApiRcRaw	api_rc_raw	RC commands sent through the API.
ApiThrustAtt-AngVel	api_thrust_att_-ang_vel	Thrust, attitude, and angular velocity commands sent through the API.
ApiPropsCmd	api_props_cmd	Received API spin or stop propellers commands.
RcActive	rc_active	RC commands for control.
Camera0-FrameInfo	camera_0_-frame_info	Captured camera frame information from the downward camera.
OpticFlow0-Raw	optic_flow_0_-raw	Downward facing tracker (DFT) data.
OpticFlow0-CalibrationTilt	optic_flow_0_-calibration_tilt	Downfacing camera calibration for tilt angle (optic flow camera yaw calibration).
Gps0Raw	gps_0_raw	Raw GPS data.
TrajectoryData-Raw	trajectory_data_-raw	Raw API data for trajectory control input.
VioPosVel	vio_pos_vel	VIO position and velocity control data.
GpsPosVel	gps_pos_vel	GPS position and velocity control data.
OpticFlowPos-Vel	optic_flow_-pos_vel	Optic flow position and velocity control data.
EscRaw	esc_raw	Raw ESC data.
VoaData	voa_data	VOA data.
VoaStatus	voa_status	State of VOA processing.
Relative-Obstacle-Distances	relative_-obstacle_-distances	Raw obstacle distance information (if available).
GpsOrigin	gps_origin	GPS latitude and longitude at the time of initial GPS lock.
Fiducial-MarkerWorld-OffsetRaw	fiducial_-marker_world_-offset_raw	Raw world offset computation from fiducial markers.
Fiducial-MarkerWorld-OffsetData	fiducial_-marker_world_-offset_data	Filtered world offset computation from fiducial markers.
SimGround-Truth	sim_ground_-truth	Simulation ground truth.

## 5.2.2 Enumeration Type Documentation

### 5.2.2.1 enum SnMode

Mode ID codes returned by querying the flight system mode.

Enumerator:

**SN\_SENSOR\_ERROR\_MODE** Error – flight is not possible in current state.

**SN\_UNDEFINED\_MODE** Mode is not defined in this list.

**SN\_WAITING\_FOR\_DEVICE\_TO\_CONNECT** Waiting for an RC or DroneController to connect.

**SN\_EMERGENCY\_KILL\_MODE** Propellers were stopped – Most likely due to a crash.

**SN\_EMERGENCY\_LANDING\_MODE** Low fixed-thrust emergency descent.

**SN\_THERMAL\_IMU\_CALIBRATION\_MODE** Thermal accel/gyro calibration.

**SN\_STATIC\_ACCEL\_CALIBRATION\_MODE** Static accel offset calibration.

**SN\_OPTIC\_FLOW\_CAM\_YAW\_CALIBRATION\_MODE** Optic flow camera yaw calibration.

**SN\_MAGNETOMETER\_CALIBRATION\_MODE** Compass (magnetometer) calibration.

**SN\_CALIBRATION\_SUCCESS** Last active calibration was successful.

**SN\_CALIBRATION\_FAILURE** Last active calibration was not successful.

**SN\_ESC\_RPM\_MODE** API controls the ESC RPMs.

**SN\_ESC\_PWM\_MODE** API controls the ESC PWMs.

**SN\_RATE\_MODE** Thrust, roll rate, pitch rate, yaw rate; does not auto-stabilize.

**SN\_THRUST\_ANGLE\_MODE** Thrust, roll angle, pitch angle, yaw rate.

**SN\_ALT\_HOLD\_MODE** Vertical velocity, roll angle, pitch angle, yaw rate.

**SN\_THRUST\_GPS\_HOVER\_MODE** Thrust control with lateral position hold using GPS.

**SN\_GPS\_POS\_HOLD\_MODE** Body-relative 3D velocity and yaw rate using GPS.

**SN\_OPTIC\_FLOW\_POS\_HOLD\_MODE** Body-relative 3D velocity and yaw rate using optic flow.

**SN\_VIO\_POS\_HOLD\_MODE** Body-relative 3D velocity and yaw rate using VIO.

**SN\_THRUST\_ATT\_ANG\_VEL\_MODE** Thrust, attitude, and angular velocity.

**SN\_PRESSURE\_LANDING\_MODE** Vertical velocity-controlled descent with zero roll/pitch.

**SN\_PRESSURE\_GPS\_LANDING\_MODE** 3D velocity-controlled descent.

**SN\_GPS\_GO\_HOME\_MODE** 3D velocity-controlled return to home position.

**SN\_ALT\_HOLD\_LOW\_ANGLE\_MODE** Vertical velocity, roll angle, pitch angle, and yaw rate with limits on roll and pitch angles.

**SN\_POS\_HOLD\_MODE** Body-relative 3D velocity and yaw rate.

### 5.2.2.2 enum SnInputCommandType

Input command types.

Enumerator:

**SN\_INPUT\_CMD\_TYPE\_NONE** No input.

**SN\_INPUT\_CMD\_TYPE\_RC** RC-style input commands.

**SN\_INPUT\_CMD\_TYPE\_API\_THRUST\_ATT\_ANG\_VEL** Thrust attitude angular velocity input commands from the API.

**SN\_INPUT\_CMD\_TYPE\_API\_ESC** ESC input commands from the API.

**SN\_INPUT\_CMD\_TYPE\_API\_TRAJECTORY\_CONTROL** Trajectory control commands from the API.

### 5.2.2.3 enum SnRcCommandSource

RC command input source.

Enumerator:

- SN\_RC\_CMD\_NO\_INPUT** No input.
- SN\_RC\_CMD\_SPEKTRUM\_INPUT** Spektrum.
- SN\_RC\_CMD\_API\_INPUT** RC commands from API.

### 5.2.2.4 enum SnRcCommandType

RC command. This enum specifies how the dimensionless commands sent by the [sn\\_send\\_rc\\_command\(\)](#) function are interpreted and indirectly selects the desired operation mode. The actual mode can be verified with the [sn\\_get\\_mode\(\)](#) function.

Enumerator:

- SN\_RC\_RATES\_CMD** Command pitch rate, negative roll rate, thrust magnitude, and yaw rate.
- SN\_RC\_THRUST\_ANGLE\_CMD** Command pitch angle, negative roll angle, thrust magnitude, and yaw rate.
- SN\_RC\_ALT\_HOLD\_CMD** Command pitch angle, negative roll angle, Z speed, and yaw rate.
- SN\_RC\_THRUST\_ANGLE\_GPS\_HOVER\_CMD** Command pitch angle, negative roll angle, thrust magnitude, and yaw rate; holds lateral position using GPS when roll and pitch commands are zero.
- SN\_RC\_GPS\_POS\_HOLD\_CMD** Command vehicle-relative X and Y speeds, Z speed, and yaw rate using GPS.
- SN\_RC\_OPTIC\_FLOW\_POS\_HOLD\_CMD** Command vehicle-relative X and Y speeds, Z speed, and yaw rate using optic flow.
- SN\_RC\_VIO\_POS\_HOLD\_CMD** Command vehicle-relative X and Y speeds, Z speed, and yaw rate using visual inertial odometry (VIO).
- SN\_RC\_ALT\_HOLD\_LOW\_ANGLE\_CMD** Command pitch angle, negative roll angle, Z speed, and yaw rate with a maximum tilt angle limit.
- SN\_RC\_POS\_HOLD\_CMD** Command vehicle-relative X and Y speeds, Z speed, and yaw rate using any available sensors.
- SN\_RC\_NUM\_CMD\_TYPES** Do not use – Reserved to hold the number of RC command types.

### 5.2.2.5 enum SnPositionController

Position controller. This enum contains supported position controllers to specify how to interpret position, angle, and their derivatives into the [sn\\_send\\_trajectory\\_tracking\\_command\(\)](#) function. Each position controller uses an appropriate estimate of position and programs that use these controllers need to ensure that the correct reference frame is used.

Enumerator:

- SN\_POSITION\_CONTROL\_GPS** GPS-based position control.
- SN\_POSITION\_CONTROL\_VIO** VIO-based position control.
- SN\_POSITION\_CONTROL\_OF** Optic flow-based position control.
- SN\_POSITION\_CONTROL\_NUM\_TYPES** Do not use – Reserved for the number of position control types.



### 5.2.2.6 enum SnTrajectoryOptions

Options for trajectory tracking to be used in the `sn_send_trajectory_tracking_command()` function.

#### Enumerator:

**SN\_TRAJ\_DEFAULT** Default options.

**SN\_TRAJECTORY\_OPTIONS\_NUM** Do not use – Reserved for the number of trajectory options.

### 5.2.2.7 enum SnRcCommandOptions

RC command options. The options can be OR-ed to form hybrid options

#### Enumerator:

**RC\_OPT\_LINEAR\_MAPPING** Linear control (default).

**RC\_OPT\_ENABLE\_DEADBAND** Enable deadband.

**RC\_OPT\_COMPLIANT\_TRACKING** Enables the flight controller to modify and smooth input commands for feasibility. Obstacle avoidance features require this bit to be set, but commands might not be tracked precisely if this flag is set. Use this flag when stick inputs are used and disable it to track motion precisely.

**RC\_OPT\_DEFAULT\_RC** Default RC.

**RC\_OPT\_TRIGGER\_LANDING** Trigger landing. The vehicle determines which landing mode is appropriate based on which sensors are available and what mode is active.

### 5.2.2.8 enum SnPropsState

Collective state of all of the propellers – Identification code returned by querying the flight system propeller state.

#### Enumerator:

**SN\_PROPS\_STATE\_UNKNOWN** State of propellers is unknown.

**SN\_PROPS\_STATE\_NOT\_SPINNING** All propellers are not spinning.

**SN\_PROPS\_STATE\_STARTING** Propellers are starting to spin.

**SN\_PROPS\_STATE\_SPINNING** All propellers are spinning.

### 5.2.2.9 enum SnDataStatus

Identification code returned by querying the sensor data status.

#### Enumerator:

**SN\_DATA\_INVALID** Sensor data is invalid.

**SN\_DATA\_VALID** Sensor data is valid.

**SN\_DATA\_NOT\_INITIALIZED** Sensor data has not been initialized.

**SN\_DATA\_STUCK** Sensor data is unchanging.

**SN\_DATA\_TIMEOUT** Sensor data has not been updated past the data timeout threshold.

**SN\_DATA\_UNCALIBRATED** Sensor data has not been calibrated.

**SN\_DATA\_OFFSET\_UNCALIBRATED** Sensor data is missing offset calibration.

**SN\_DATA\_TEMP\_UNCALIBRATED** Sensor data is missing temperature calibration.

**SN\_DATA\_STARTING** Sensor is acquiring additional samples.

***SN\_DATA\_STATUS\_UNAVAILABLE*** Sensor data status unavailable.

***SN\_DATA\_NOT\_ORIENTED*** Sensor data missing the orientation parameter.

***SN\_DATA\_NO\_LOCK*** Sensor data unable to lock on.

***SN\_DATA\_WARNING*** Sensor is in a warning state.

***SN\_DATA\_TRANSITIONING*** Sensor data is transitioning.

### 5.2.2.10 enum SnMotorState

Individual state of a motor – Identification code returned by querying the state feedback from ESCs.

#### Enumerator:

***SN\_MOTOR\_STATE\_UNKNOWN*** State of motor is unknown.

***SN\_MOTOR\_STATE\_NOT\_SPINNING*** Motor is not spinning.

***SN\_MOTOR\_STATE\_STARTING*** Motor is starting to spin.

***SN\_MOTOR\_STATE\_SPINNING\_FORWARD*** Motor is spinning in the forward direction.

***SN\_MOTOR\_STATE\_SPINNING\_BACKWARD*** Motor is spinning in the backward direction.

### 5.2.2.11 enum SnCalibStatus

Identification code returned by querying the sensor calibration status.

#### Enumerator:

***SN\_CALIB\_STATUS\_NOT\_CALIBRATED*** Calibration data does not exist.

***SN\_CALIB\_STATUS\_CALIBRATION\_IN\_PROGRESS*** Calibration procedure is in progress.

***SN\_CALIB\_STATUS\_CALIBRATED*** Calibration data exists.

### 5.2.2.12 enum SnRcReceiverMode

Spektrum data transmission mode. This value is used to request binding and display the current mode.

#### Enumerator:

***SN\_RC\_RECEIVER\_MODE\_UNKNOWN*** Unknown DSM mode.

***SN\_SPEKTRUM\_MODE\_DSM2\_22*** DSM2 22 ms (6-channel maximum, every 22 ms).

***SN\_SPEKTRUM\_MODE\_DSM2\_11*** DSM2 11 ms (9-channel maximum, complete packet every 22 ms).

***SN\_SPEKTRUM\_MODE\_DSMX\_22*** DSMX 22 ms (6-channel maximum, every 22 ms).

***SN\_SPEKTRUM\_MODE\_DSMX\_11*** DSMX 11 ms (9-channel maximum, complete packet every 22 ms).

### 5.2.2.13 enum SnGnssReceiverType

Supported GNSS receiver types.

**Enumerator:**

***SN\_GNSS\_RECEIVER\_TYPE\_UNKNOWN*** Unknown receiver.

***SN\_GNSS\_RECEIVER\_TYPE\_CSR\_SSV*** CSR receiver.

***SN\_GNSS\_RECEIVER\_TYPE\_QC\_WGR*** CSR receiver.

***SN\_GNSS\_RECEIVER\_TYPE\_UBLOX*** U-blox receiver.

# A Troubleshooting

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## A.1 Propellers are not spinning when commanded

### A.1.1 Calling the `sn_start_props()` function

Ensure that the flight controller is not in `SN_WAITING_FOR_DEVICE_TO_CONNECT` mode.

The `sn_start_props()` function only takes effect if the flight controller is receiving data and has not timed out.

Propellers only start spinning if Snapdragon Navigator has determined that it is safe and appropriate. Many conditions can cause Snapdragon Navigator to deem it unsafe or inappropriate to start the propellers. Refer to *Qualcomm Snapdragon Navigator User Guide* (80-P4698-18) to review these conditions.

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6. **INDEMNITY.** You agree to defend, indemnify and hold QTI, its Affiliates, employees, directors, agents, licensors, successors and assignees (each an "Indemnified Party") harmless from any and all claims, penalties, demands, causes of action, liabilities, lawsuits, or damages, including attorneys' fees and costs, that result from or relate to the Materials or any product, including drones, made, used, sold, imported, exported, or distributed by You which uses the Materials or any part or derivative work thereof, even where such product uses the Materials without modification and even where the design of such product is identical to the design of any reference product, including drones. This indemnification includes, without limitation, any claims for damages to property or injury or death to persons and any investigation, enforcement action, civil penalty, or other action conducted or cost imposed by the United States Federal Aviation Administration (FAA) or any governmental entity of the United States or any other government. If any third party asserts a claim or initiates an action against an Indemnified Party for which You are responsible under this Section, QTI shall promptly notify You when it becomes aware of such claim or action, provided, however, that any delay in notification shall not relieve You from Your indemnification obligations under this Agreement. QTI shall have the right to participate in the defense of such claim or action, including any related settlement negotiations. No such claim or action may be settled or compromised without QTI's express written consent, which may be conditioned upon the execution of a release of all claims against the Indemnified Parties by the party bringing such claim or action.
7. **GENERAL RELEASE.**
- (a) **Release.** In consideration of QTI's allowing You to use the Materials, You on behalf of Yourself, Your, affiliates, agents, successors and assigns, hereby fully and forever release and discharge QTI (and all of its officers, directors, employees, agents, successors, assigns, control persons, subsidiaries and Affiliated companies, together the "Released Parties"), from any and all claims, demands, liabilities, obligations, responsibilities, suits, actions and causes of action against any of the Released Parties, whether liquidated or unliquidated, fixed or contingent, known or unknown, presently existing or which, through the passage of time, might arise in the future, related to or arising out of Your use of the Materials.
- (b) **Waiver and Acknowledgement.** You hereby expressly waives all rights under Section 1542 of the Civil Code of the State of California, and under any and all similar laws of any governmental entity. You hereby confirm that you are aware that said Section 1542 of the Civil Code provides as follows: "A general release does not extend to claims which the creditor does not know or suspect to exist in his favor at the time of executing the release, which if known by him must have materially affected his settlement with the debtor."
8. **INSURANCE.** If You make or distribute drones, or participate in making or distributing drones, You agree to and will maintain (throughout the time You are using any of the Materials in connection with such drones) insurance providing adequate coverage for potential product liability, personal injury, property damage, and privacy claims and litigation associated with such drones and/or Materials.

# C References

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## C.1 Related Documents

Title	Number
<b>Qualcomm Technologies</b>	
<i>Qualcomm Snapdragon Navigator User Guide</i>	80-P4698-18
<i>Qualcomm Snapdragon Navigator Example API Programs</i>	<a href="https://github.com/ATLFlight/snnav_api_examples">https://github.com/ATLFlight/snnav_api_examples</a>

## C.2 Acronyms and Terms

Acronym or term	Definition
ESC	Electronic speed controllers
RC	Radio controller
VIO	Visual inertial odometry
VOA	Visual obstacle avoidance