



G-Port Mavlink Protocol Usage Documentation

1. The protocol is Mavlink protocol, its content being privately defined.

 mavlink_msg_gimbal_control.h

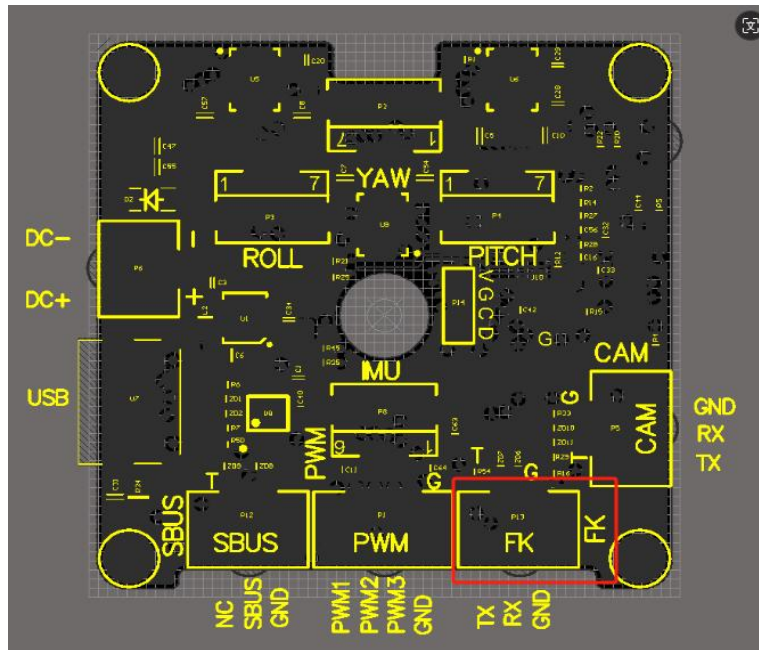
 mavlink_msg_gimbal_report.h

2、Mavlink For Example

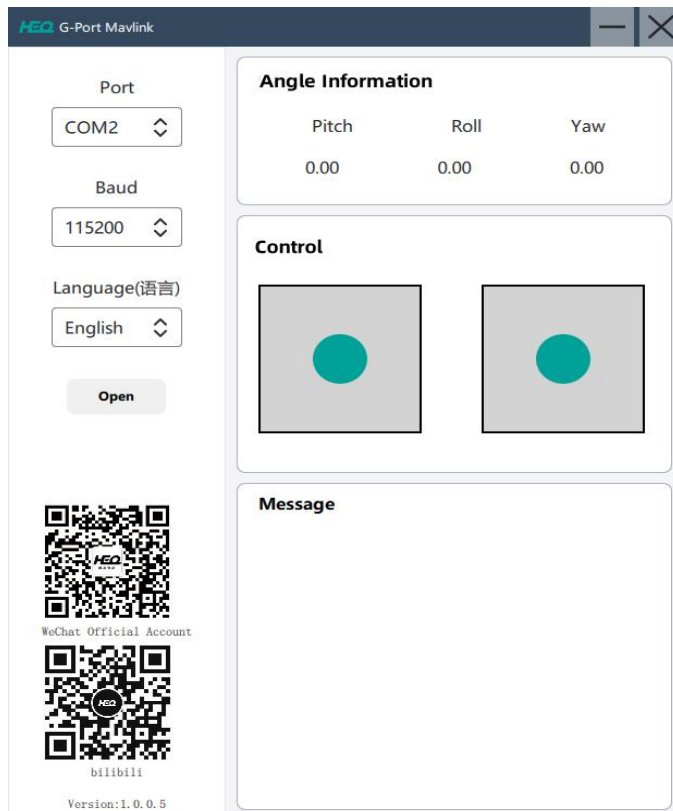
Function	ID	Data Load	Remark
Angular Velocity Control	201	struct __mavlink_gimbal_control_t	
<pre>typedef struct __mavlink_gimbal_control_t { float demanded_rate_x; /*< [rad/s] Demanded angular rate X.*/ float demanded_rate_y; /*< [rad/s] Demanded angular rate Y.*/ float demanded_rate_z; /*< [rad/s] Demanded angular rate Z.*/ uint8_t target_system; /*< System ID.*/ uint8_t target_component; /*< Component ID.*/ } mavlink_gimbal_control_t; // X correspond ROLL Y correspond PITCH Z correspond YAW</pre>			

Function	ID	Data Load	Remark
Gimbal Status	200	struct __mavlink_gimbal_report_t	
<pre>typedef struct __mavlink_gimbal_report_t { float delta_time; /*< [s] Time since last update.*/ float delta_angle_x; /*< [rad] Delta angle X.*/ float delta_angle_y; /*< [rad] Delta angle Y.*/ float delta_angle_z; /*< [rad] Delta angle X.*/ float delta_velocity_x; /*< [m/s] Delta velocity X.*/ float delta_velocity_y; /*< [m/s] Delta velocity Y.*/ float delta_velocity_z; /*< [m/s] Delta velocity Z.*/ float joint_roll; /*< [rad] Joint ROLL.*/ float joint_el; /*< [rad] Joint EL.*/ float joint_az; /*< [rad] Joint AZ.*/ uint8_t target_system; /*< System ID.*/ uint8_t target_component; /*< Component ID.*/ } mavlink_gimbal_report_t; //X correspond ROLL Y correspond PITCH Z correspond YAW</pre>			

3、Debug Interface Wiring Definition



4、Assistant Debugging After Development Completion (Please upgrade the MavLink firmware to use)



Note: Users need to have a certain level of development capability.