Offboard mode state machine: offboard mode enables direct control from companion computer by setting yaw or velocity vector

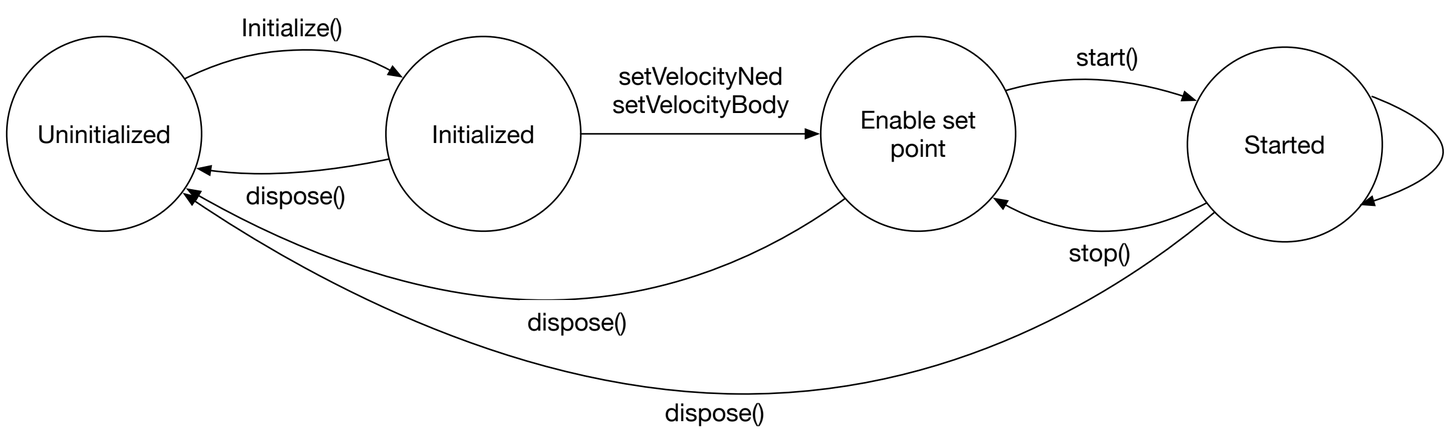
APIs that can be called at all times
isActive()

Quirks
- must set the set points before starting the offboard mode
- in the actual documentation, Altitude is spelled Attitude (setAttitude instead of setAltitude)

To use offboard mode you must first create a setpoint using any of the setpoint setter methods (e.g. set_velocity_ned() or set_velocity_body()). You can use any setpoint you like - the vehicle will start acting on the current setpoint as soon as the mode starts.

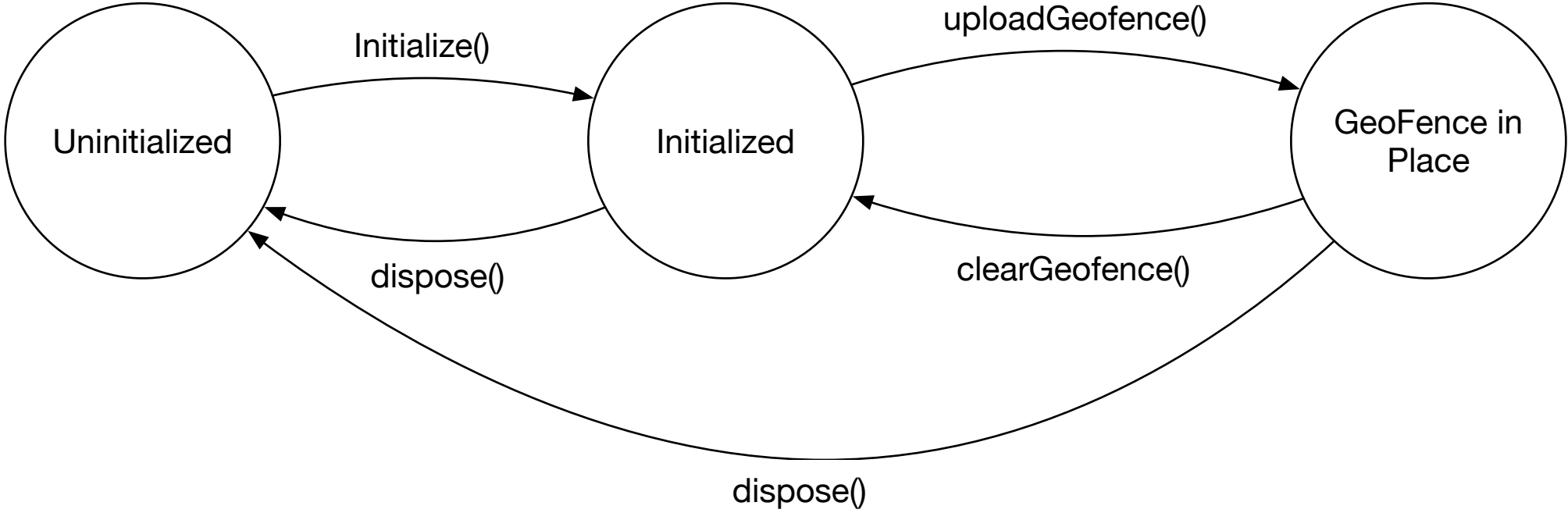
```
// Create a setpoint before starting offboard mode (in this case a null setpoint)
offboard.set_velocity_body({0.0f, 0.0f, 0.0f, 0.0f});
```

`https://mavsdk.mavlink.io/main/en/cpp/guide/offboard.html`

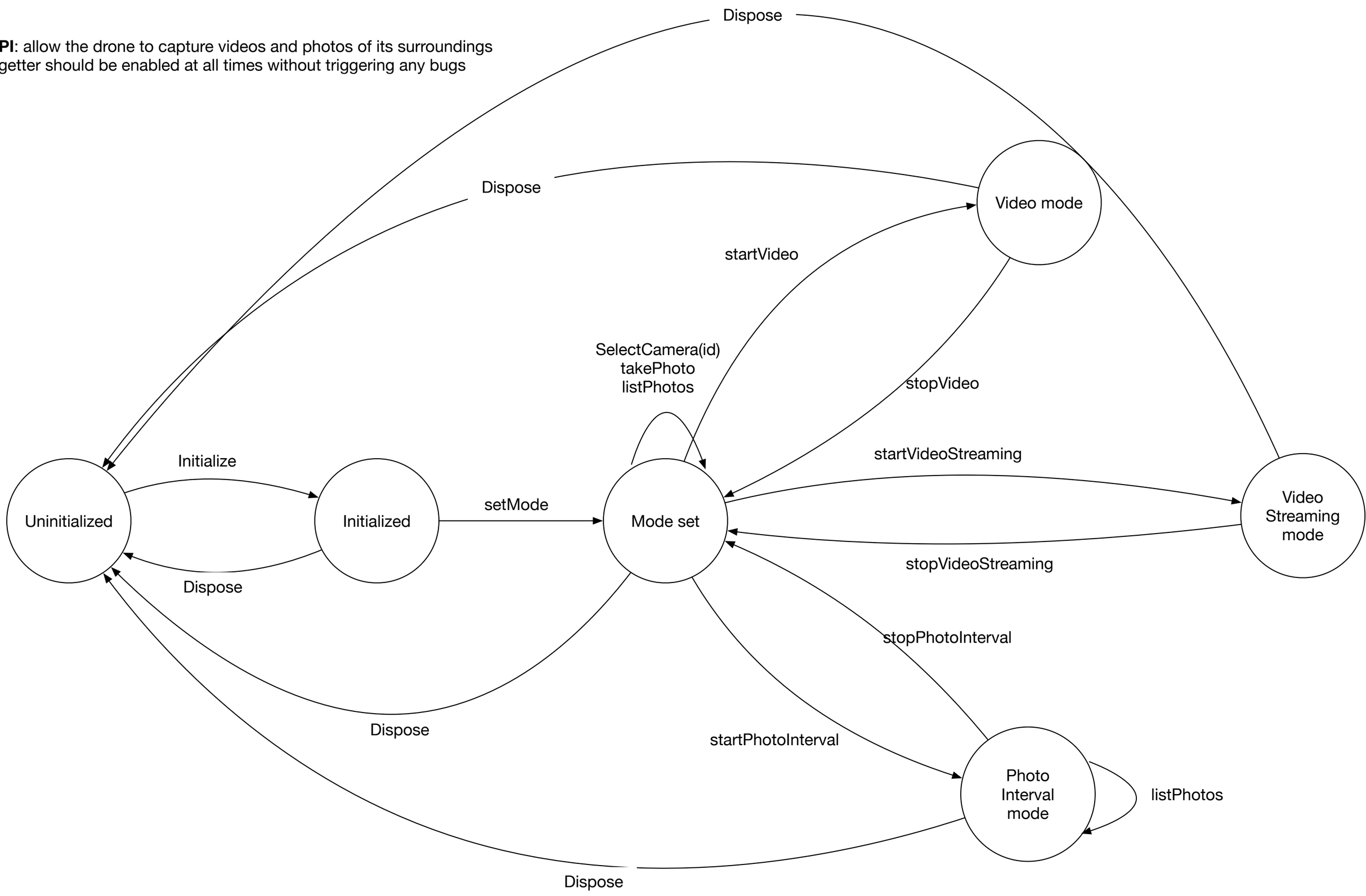


setAccelerationNed
setActuatorControl
setAltitude
setAltitudeRate
setPositionGlobal
setPositionNed
setPositionVelocityNed
setVelocityBody
setVelocityNed

geofence API: enable setting a geofence

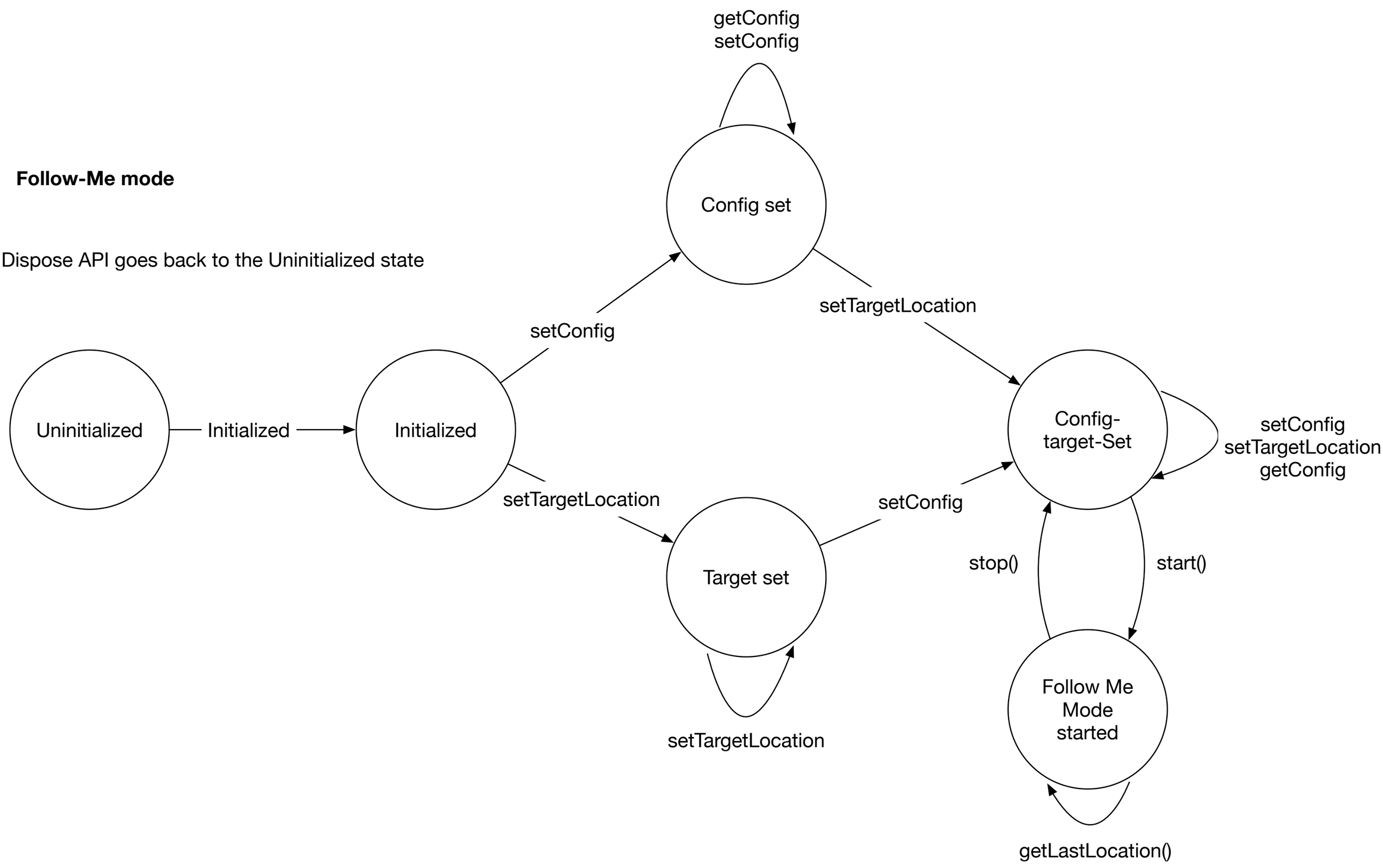


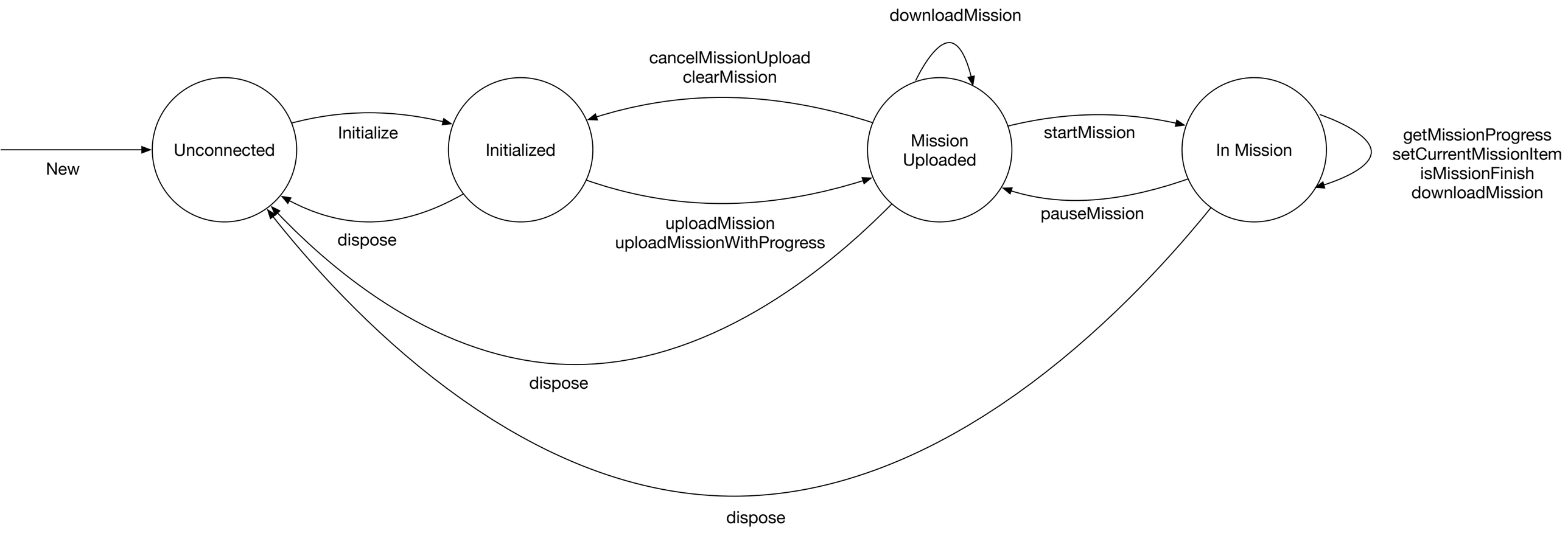
Camera API: allow the drone to capture videos and photos of its surroundings
All the getter should be enabled at all times without triggering any bugs



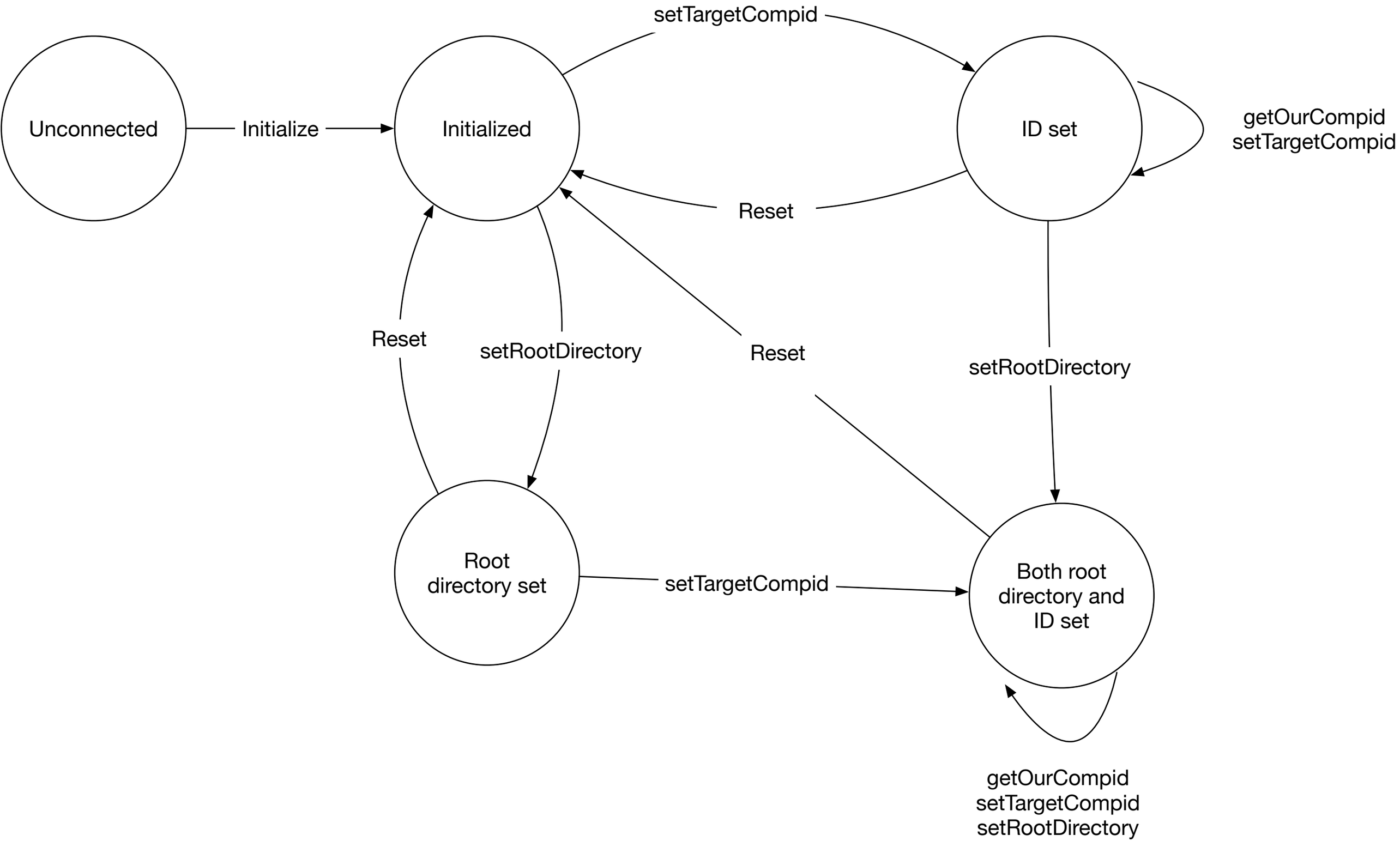
Follow-Me mode

Dispose API goes back to the Uninitialized state




downloadMission
cancelMissionUpload
clearMission
Unconnected
Initialize
Initialized
Mission
Uploaded
startMission
In Mission
getMissionProgress
setCurrentMissionItem
isMissionFinish
downloadMission
New
dispose
uploadMission
uploadMissionWithProgress
pauseMission
dispose
dispose

FTP Mode


Unconnected
Initialize
Initialized
setTargetCompid
ID set
getOurCompid
setTargetCompid
Reset
Reset
setRootDirectory
Reset
setRootDirectory
Root
directory set
setTargetCompid
Both root
directory and
ID set
getOurCompid
setTargetCompid
setRootDirectory

Mocap: allow motion capture without using GPS (when the signal is weak)
Boring not included

Mocap Mode