# Cheat sheet for ESP32 GNSS altimeter datalogger:

(Working for Log\_GNSS\_LDS70A.ino V1.1)

**Serial only:**

READ Read last file of last measurement. If argument is passed with READ:<< nfile>>: read file *nfile*

LIST Get list of files in SD card

**Serial and BLE:**

STOP Stops measurement

START Starts new measurement

RATE:<<N>>: Set sampling rate to N

CHECKATT Get attitude angles from IMU anf GPS coordinates and send them over BLE+serial for manual check. Calls also CHECKLASER

CHECKLASER Get Laser data for 1 second and send it over BLE and serial

COMS or ? List commands

LOGGPS:<<b>>: Log GPS data if b=1 (Default)

**BLE only:**

CHECKIMU Get IMU data and send them over BLE+serial for manual check

DYNMODEL:<<n>>: Set dynamic model to n. Sensor need to be recalibrated after changing the setting.  
n=4: Automotive (default, algorithm optimized for it), Used for applications with equivalent dynamics to those of a passenger car. Low vertical acceleration assumed.  
n=0: Applications with low acceleration, e.g. portable devices. Suitable for most situations  
n=6: Used for applications with a higher dynamic range and greater vertical acceleration than a passenger car. No 2D position fixes supported.

LOGRMX:<<b>>: change RMX log setting. b=0/1

IMUCAL:<<b>>: Change setting for regular check for IMU calibration. b=0/1

NAVPVT:<<b>>: Change log setting. b=0/1

NAVPVAT:<<b>>: Change log setting. b=0/1

ESFINS:<<b>>: Change log setting. b=0/1

ESFRAW:<<b>>: Change log setting. b=0/1

ESFMEAS:<<b>>: Change log setting. b=0/1

ESFALG:<<b>>: Change log setting. b=0/1