DJI SDK常用方法

**板载电脑初始化：**

LinuxSetup linuxEnvironment(argc, argv);//环境初始化  
Vehicle\* vehicle = linuxEnvironment.getVehicle();//载具初始化

vehicle->obtainCtrlAuthority(functionTimeout);//获取飞控控制权限

1. **控制**

ACK::ErrorCode takeoffStatus = vehicle->control->takeoff(timeout);//起飞并获取状态码

ACK::ErrorCode landingStatus = vehicle->control->land(timeout);//降落并获取状态码

vehicle->control->positionAndYawCtrl(xCmd, yCmd, zCmd,

yawDesiredRad / DEG2RAD);//通过位置角度控制飞机

1. **订阅、广播机制（记得在程序最后移除订阅或广播）**

subscribeStatus = vehicle->subscribe->verify(timeout);//版本匹配？

bool pkgStatus = vehicle->subscribe->initPackageFromTopicList(

pkgIndex, numTopic, topicList10Hz, enableTimestamp, freq);//初始化遥测数据包

subscribeStatus = vehicle->subscribe->startPackage(pkgIndex, timeout);//开始发包

vehicle->subscribe->removePackage(pkgIndex, timeout);//停止发包

currentSubscriptionGPS = vehicle->subscribe->getValue<TOPIC\_GPS\_FUSED>();//获取包的内容

ACK::ErrorCode ack = vehicle->broadcast->setBroadcastFreq(freq, 1);//开始广播

第一个参数为设置好的频道的广播频率，第二个为超时时间

currentBroadcastGP = vehicle->broadcast->getGlobalPosition();//获取广播的内容

通道信息定义

Channels definition for A3/N3/M600  
 \* 0 - Timestamp  
 \* 1 - Attitude Quaternions  
 \* 2 - Acceleration  
 \* 3 - Velocity (Ground Frame)  
 \* 4 - Angular Velocity (Body Frame)  
 \* 5 - Position  
 \* 6 - GPS Detailed Information  
 \* 7 - RTK Detailed Information  
 \* 8 - Magnetometer  
 \* 9 - RC Channels Data  
 \* 10 - Gimbal Data  
 \* 11 - Flight Status  
 \* 12 - Battery Level  
 \* 13 - Control Information

1. 状态、验证码

ACK::ErrorCode subscribeStatus;//申明状态码类

ACK::getError(subscribeStatus)//获取错误

ACK::getErrorCodeMessage(subscribeStatus, func);//转化为错误信息

vehicle->broadcast->getStatus().flight//获取（起飞）状态

DJI::OSDK::VehicleStatu//飞机状态码在此下面

<https://developer.dji.com/onboard-api-reference/namespaceDJI_1_1OSDK_1_1VehicleStatus.html>

常见错误代码：

<https://developer.dji.com/onboard-api-reference/classDJI_1_1OSDK_1_1ErrorCode_1_1CommonACK.html#details>