飞控->上位机

帧	帧头	功能字	长度	数据	校验
STATUS	AAAA	01	LEN	int16 ROL*100 int16 PIT*100 int16 YAW*100 int16 ALT_CSB(超声波高度,单位毫米) int32 ALT_PRS(气压计高度,单位厘米) u8 ARMED : A0加锁 A1解锁	SUM
SENSER	AAAA	02	LEN	int16 ACC_X int16 ACC_Y int16 ACC_Z int16 GYRO_X int16 GYRO_Y int16 GYRO_Z int16 MAG_X int16 MAG_Y int16 MAG_Z	SUM
RCDATA	AAAA	03	LEN	int16 THR int16 YAW int16 ROL int16 PIT int16 AUX1 int16 AUX2 int16 AUX3 int16 AUX4 int16 AUX5 int16 AUX6	SUM
GPSDATA	AAAA	04	LEN	int32 LAT int32 LNG float GPS_ALT/cm float GPS_SPD/cm int16 GPS_HAC*100 int16 GPS_VAC*100 u8 GPS_STA u8 GPS_SVN	SUM
VOTAGE	AAAA	05	LEN	uint16 Votage1*100 uint16 Votage2*100 uint16 Votage3*100	SUM
	AAAA	06	LEN	uint16 PWM_MOTO12345678(范围0-1000)	SUM
	AAAA	07	LEN		SUM
	AAAA	08	LEN		SUM
	AAAA	09	LEN		SUM
	AAAA	0A	LEN		SUM
	AAAA	0B	LEN		SUM
	AAAA	0C	LEN		SUM
	AAAA	0D	LEN		SUM
	AAAA	0E	LEN		SUM
	AAAA	0F	LEN		SUM
PID1	AAAA	10	LEN	int16 ROL_P int16 ROL_I int16 ROL_D int16 PIT_P int16 PIT_I int16 PIT_D int16 YAW_P int16 YAW_I int16 YAW_D	SUM
PID2	AAAA	11	LEN	int16 ALT_P int16 ALT_I int16 ALT_D int16 POS_P int16 POS_I int16 POS_D int16 PID1_P int16 PID1_I int16 PID1_D	SUM
PID3	AAAA	12	LEN	int16 PID2_P int16 PID2_I int16 PID2_D int16 PID3_P int16 PID3_I int16 PID3_D int16 PID4_P int16 PID4_I int16 PID4_D	SUM
PID4	AAAA	13	LEN	int16 PID5_P int16 PID5_I int16 PID5_D int16 PID6_P int16 PID6_I int16 PID6_D int16 PID7_P int16 PID7_I int16 PID7_D	SUM
PID5	AAAA	14	LEN	int16 PID8_P int16 PID8_I int16 PID8_D int16 PID9_P int16 PID9_I int16 PID9_D int16 PID10_P int16 PID10_I int16 PID10_D	SUM
PID6	AAAA	15	LEN	int16 PID11_P int16 PID11_I int16 PID11_D int16 PID12_P int16 PID12_I int16 PID12_D	SUM
	AAAA	16	LEN	int16 OFFSET_ROL*1000 int16 OFFSET_PIT*1000	SUM
	AAAA	17	LEN		
	AAAA	18	LEN		
	AAAA	19	LEN		
	AAAA	1A	LEN		
	AAAA	1B	LEN		
	AAAA	1C	LEN		SUM

所有的PD,扩大100倍,I扩大1000倍进行传输

上位机->飞控

帧	帧头	功能字	长度	数据	校验	返回确认
CONMAND	AAAF	01	LEN	01 ACC校准 02 GYRO校准 03 ACC与GYRO校准 04 MAG校准 05 BARO校准 A0 飞控锁定（仅用于手机蓝牙控制） A1 飞控解锁（仅用于手机蓝牙控制）	SUM	YES
	AAAF	02	LEN	01 请求返回PID 01 请求返回Offset rol pit	SUM	NO
RCDATA	AAAF	03	LEN	int16 THR int16 YAW int16 ROL int16 PIT int16 AUX1 int16 AUX2 int16 AUX3 int16 AUX4 int16 AUX5 int16 AUX6	SUM	NO
	AAAF	04	LEN		SUM	
	AAAF	05	LEN		SUM	
	AAAF	06	LEN		SUM	
	AAAF	07	LEN		SUM	
	AAAF	08	LEN		SUM	
	AAAF	09	LEN		SUM	
	AAAF	0A	LEN		SUM	
	AAAF	0B	LEN		SUM	
	AAAF	0C	LEN		SUM	
	AAAF	0D	LEN		SUM	
	AAAF	0E	LEN		SUM	
	AAAF	0F	LEN		SUM	
PID1	AAAF	10	LEN	int16 ROL_P int16 ROL_I int16 ROL_D int16 PIT_P int16 PIT_I int16 PIT_D int16 YAW_P int16 YAW_I int16 YAW_D	SUM	YES
PID2	AAAF	11	LEN	int16 ALT_P int16 ALT_I int16 ALT_D int16 POS_P int16 POS_I int16 POS_D int16 PID1_P int16 PID1_I int16 PID1_D	SUM	YES
PID3	AAAF	12	LEN	int16 PID2_P int16 PID2_I int16 PID2_D int16 PID3_P int16 PID3_I int16 PID3_D int16 PID4_P int16 PID4_I int16 PID4_D	SUM	YES
PID4	AAAF	13	LEN	int16 PID5_P int16 PID5_I int16 PID5_D int16 PID6_P int16 PID6_I int16 PID6_D int16 PID7_P int16 PID7_I int16 PID7_D	SUM	YES
PID5	AAAF	14	LEN	int16 PID8_P int16 PID8_I int16 PID8_D int16 PID9_P int16 PID9_I int16 PID9_D int16 PID10_P int16 PID10_I int16 PID10_D	SUM	YES
PID6	AAAF	15	LEN	int16 PID11_P int16 PID11_I int16 PID11_D int16 PID12_P int16 PID12_I int16 PID12_D	SUM	YES
	AAAF	16	LEN	int16 OFFSET_ROL*1000 int16 OFFSET_PIT*1000	SUM	YES
	AAAF	17	LEN		SUM	
	AAAF	18	LEN		SUM	
	AAAF	19	LEN		SUM	
	AAAF	1A	LEN		SUM	
	AAAF	1B	LEN		SUM	
	AAAF	1C	LEN		SUM	
	AAAF		LEN		SUM	
	AAAF		LEN		SUM	
	AAAF		LEN		SUM	
	AAAF		LEN		SUM	

上位机发送给飞控的设置数据(功能字为Bx)的数据,在飞控收到后,需要返回相同的数据给上位机(飞控发送回上位机时,帧头需更换为88),上位机收到返回数据后,会进行校验,通过后完成此次通信,校验不通过会重复发送该帧数据,重复10次,如果10次还未通信成功,会报通信错误.