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## External Heading Update (0x0D,0x17)

<b>Description</b>	<b>Provide a filter measurement from an external heading source</b>	
<b>Notes</b>	<p>The heading must be the sensor frame with respect to the NED frame.</p> <p>The heading update control must be set to external for this command to update the filter; otherwise it is NACK'd. Heading angle uncertainties of <math>\leq 0.0</math> will be NACK'd</p> <p>Please refer to your device user manual for information on the maximum rate of this message.</p> <p>On -25 models, if the declination source (0x0D, 0x43) is not valid, true heading updates will be NACK'd. On -45 models, if the declination source is invalid, magnetic heading updates will be NACK'd.</p>	
<b>Parameter Name</b>	<b>Data Type</b>	<b>Description</b>
<i>Field Length</i>	<i>u8</i>	<i>11</i>
<i>Descriptor</i>	<i>u8</i>	<i>0x17</i>
Heading	<a href="#">float</a>	Bounded by $\pm\pi$ [radians]
Heading Uncertainty	<a href="#">float</a>	1-sigma [radians]
Type	<a href="#">u8</a>	1 - True, 2 - Magnetic
<b>Ack/Nack Reply</b>	<a href="#">See standard MIP ack/nack reply format.</a>	