You are here: [MIP API](#) > [Commands](#) > [Aiding (0x13)](#) > Frame Configuration (0x13,0x01)

Frame Configuration (0x13,0x01)

Description	Defines an aiding frame associated with a specific sensor frame ID.
Notes	The frame ID used in this command should mirror the frame ID used in the aiding command (if that aiding measurement is measured in this reference frame). This transform satisfies the following relationship: Where: is rotation matrix defined by the rotation component and is the translation vector is a 3-element position vector expressed in the external sensor frame is a 3-element position vector expressed in the vehicle frame Rotation can be defined using Euler angles OR quaternions. If Format selector is set to Euler Angles, the fourth element in the rotation vector is ignored and should be set to 0. When the tracking_enabled flag is 1, the Kalman filter will track errors in the provided frame definition; when 0, no errors are tracked. Example: GNSS antenna lever arm Frame ID: 1 Format: 1 (Euler) Translation: [0,1,] (GNSS with a 1 meter Y offset in the vehicle frame) Rotation: [0,0,0,0] (Rotational component is not relevant for GNSS measurements, set to zero)

Parameter Name	Data Type	Description
Field Length	*u8*	*6*
Descriptor	*u8*	*0x01*
Function Selector	u8	This command supports the following MIP function selectors: `Write Read Save Load Default [WRSLD]`

Frame Id [WRSLD]	u8	Reference frame number. Limit 4.		
Format [WR]	u8 enum	Format of the transformation.		
		Name	**Value**	**Description**
		EULER	1	Translation vector followed by euler angles (roll, pitch, yaw).
		QUATERNION	2	Translation vector followed by quaternion (w, x, y, z).
Tracking Enabled [W]	bool	If enabled, the Kalman filter will track errors.		
Translation [W]	Vector3f	Translation X, Y, and Z.		
Rotation [W]	Rotation	Rotation as specified by format.		
Ack/Nack Reply	**See standard MIP ack/nack reply format.**			
Response Data	**Data Type**	**Description**		
Response Length	*u8*	*5*		
Response Descriptor	*u8*	*0x81*		
Frame Id	u8	Reference frame number. Limit 4.		
Format	u8 enum	Format of the transformation.		
		Name	**Value**	**Description**
		EULER	1	Translation vector followed by euler angles (roll, pitch, yaw).
		QUATERNION	2	Translation vector followed by quaternion (w, x, y, z).
Tracking Enabled	bool	If enabled, the Kalman filter will track errors.		
Translation	Vector3f	Translation X, Y, and Z.		
Rotation	Rotation	Rotation as specified by format.		

Structures

Rotation

Description		
Parameter Name	**Data Type**	**Description**
Euler	Vector3f	Rotation represented as euler angles in RPY format [rad]. Range +/- pi.
Quaternion	Quatf	Rotation represented as a quaternion in WXYZ format.