

## Table of Contents

- [Hardware Setup](#)
- [Error Messages Overview](#)
  - [Quick Reference Table](#)
  - [Explanation](#)
- [Code Overview](#)
  - [Global Variables](#)
  - [Serial Initialization](#)
  - [Update Function](#)
  - [Verifying Checksum](#)
  - [Parsing Data](#)
  - [Logging](#)
  - [Important Notes](#)
- [Important Links](#)

## Hardware Setup

In Mission Planner, with the autopilot connected. Go to the "CONFIG" tab, and select the "Full Parameter List". In the parameter list, you will need to find one of the "[SERIAL#](#)" sections. This will depend on what autopilot you are using and what port you are connecting the Samamet to. Refer to the documentation of your specific autopilot for the mapping of the physical hardware ports, to their name in Mission Planner.

Under the "[SERIAL#](#)" section, change the "[SERIAL#\\_BAUD](#)" parameter to "9", or in the options drop-down, select "9600", to set the baud rate to 9600.

Then under the "[SERIAL#\\_PROTOCOL](#)" section, change the parameter to "28" or in the options drop-down, select "[Scripting](#)", to enable scripting on that serial port. This allows for the Lua script to access this port.

It is important to note that if you have multiple scripting ports active at once, the script will by default select the first port. So to ensure that the script is connected to the correct port, you can edit the below line:

```
1 local PORT = assert(serial:find_serial(0), "Could not find Scripting  
Serial Port")
```

To change `serial:find_serial(0)`, which finds the first serial port, to `serial:find_serial(1)`, to find the second serial port.

Instead of editing the script, you can simply ensure that the Samamet is on the first scripting port, and the other serial scripting device is set up for the second serial port.

## Error Messages Overview

### Quick Reference Table

Mission Planner Output	Log File	Error Type
ERROR: PTH has failed to send data	No data received	Disconnected sensor
ERROR: PTH Data failed checksum	Checksum fail	Corrupted/Incomplete data
ERROR: Failed to parse data	Data parsing fail	Corrupted/Incomplete data

### Explanation

There are several errors that can occur when running the script. The two main errors you will encounter are a disconnected sensor, or corrupted or incomplete data.

If the sensor is disconnected or experiences a temporary interrupt in its transmission of data, you would see the below error in the Mission Planner output.

```
1 6/11/2024 11:02:42 AM : ERROR: PTH has failed to send data
```

In the BIN file, under the Samamet's section in the error column, the message "No data received" will appear to signify a disconnected sensor.

A disconnected sensor could come from an improper connection between the Samamet and the autopilot. Verify that the connection is good and the cable does not have any shorts. Also ensure that the Samamet is receiving power and is on. Also ensure that the serial port is set up correctly in Mission Planner. Mainly check that the baud rate is set to the baud rate of the Samamet, which is 9600.

A checksum fail is primary way that corrupted or incomplete data is caught. If there is a checksum error, you will see the below message in Mission Planner.

```
1 6/11/2024 11:02:42 AM : ERROR: PTH Data failed checksum
```

In the BIN file, you will see "Checksum fail" in the error column for the Samamet.

Corrupted or incomplete data can also appear as a data parsing fail, which in Mission Planner, will be shown in the below message.

```
1 6/11/2024 11:02:42 AM : ERROR: Failed to parse data
```

In the BIN file, you will see "Data parsing fail" in the error column for the Samamet.

In the event of repeated corrupted or incomplete data from the Samamet, it is possible that the connection between Samamet and the autopilot could be experience interference or simply a partially incomplete connection.

## Code Overview

Over view of the `serial_pth.lua` script for decoding and logging data from the PTH serial sensor

**NOTE:** This document is in the order that the code is ran, not in the order that it is organized in the file.

## Global Variables

```
1 -- variable to count iterations without getting message
2 local loops_since_data_received = 0
3
4 -- table to hold the message that is currently being assembled
5 local message_table = {}
6
7 -- error type table
8 local ERROR_LIST = {
9     "No data received",      -- 1
10    "Checksum fail",         -- 2
11    "Data parsing fail",     -- 3
12 }
```

The `loops_since_data_received` variable stores how many loops since a new byte of data has been received on the serial line. If this value goes above a certain count, we can assume that the sensor is most likely disconnected, and can report and log an error

The `message_table` table stores the bytes of the message that we are currently assembling.

The `ERROR_LIST` table holds a list of possible errors we can receive. We use this list to pass through the kind of error we are experiencing to the `log_error()` function to be logged in the BIN file for later reference.

## Serial Initialization

```
1 -- initialize serial connection
2 local BAUD_RATE = 9600
3
4 -- find the serial first (0) scripting serial port instance
5 -- SERIALx_PROTOCOL 28
6 local PORT = assert(serial:find_serial(0), "Could not find Scripting
   Serial Port")
7
8 -- begin the serial port
9 PORT:begin(BAUD_RATE)
10 PORT:set_flow_control(0)
```

This sets up the serial connection between the PTH and the flight controller. A baud rate of 9600 is used since this is the speed the sensor operates at.

After we set the baud rate, we then find the first serial port that is currently open and using protocol 28, which is the ArduPilot protocol for scripting.

### NOTE:

1. make sure to set the correct baud rate of 9600 and protocol 28 on the serial line being used to ensure the sensor is connected.
2. If you have multiple serial ports set to protocol 28 (Scripting), make sure to have the Samamet on the highest port, or to set the 0 in `find_serial()` to a 1 to find the second port.

If we cannot find a serial port with the scripting protocol, the script throws an error.

The serial initialization is pulled from the ArduPilot [Serial Dump example](#).

## Update Function

Once the serial initialization is completed, the script then jumps to the end of the file (since that there is no other code outside of the functions) and runs the following return statement.

```
1 return update() -- run immediately before starting to reschedule
```

This statement calls the `update()` function, which is the main function in most ArduPilot lua scripts.

```
1 local n_bytes = PORT:available()
2
3 -- If we have received no bytes or have not received any new bytes,
   increment
4 -- the count of loops without data. If it reaches 11 or more
5 -- (100ms * 11 = 1.1sec), then log an error.
```

```
6 if n_bytes <= 0 then
7   loops_since_data_received = loops_since_data_received + 1
8   if loops_since_data_received >= 11 then
9     log_error(ERROR_LIST[1])
10    -- Send error message to mission planner with priority 0 (error)
11    gcs:send_text(0, "ERROR: PTH has failed to send data")
12    -- clear incomplete message (if there is one)
13    message_table = {}
14  end
15  return update, 100
16 end
```

First we update `n_bytes` and we check if it is zero. If it is zero, this means that there is no new data on the bus, meaning the sensor is disconnected, or it has not sent its data yet.

Since we run the loop ten times per second we keep track of how many loops have gone by with the `loops_since_data_received` counter. If we reach eleven or more iterations without new data, we log an error with the `log_error()` function (This will be discussed further in the "Logging" section), send an error out to the Mission Planner output, and clear the current message that has been parsed in the event that the sensor was disconnected in the middle of a data transmission.

We derive this number of failed loops from how often we schedule the `update()` function to run, which is every 100 milliseconds, and how often the PTH sends out its data, which is every second. To ensure that we are not flagging the time in between data transmissions from the sensor as an error, we need to wait more than one second. By waiting for eleven failed loops, we guarantee that we are waiting at least 1.1 seconds before we log an error ( $100\text{ms} \cdot 11 = 1100 = 1.1\text{sec}$ ). This gives the PTH time to send its data and will prevent us from logging any false errors.

```
1 -- read bytes from the serial line until we hit '0x0A' which is <LF>,
   the
2 -- ending of the message. Then process the message
3 loops_since_data_received = 0
4 while n_bytes > 0 do
5   local byte = PORT:read()
6   if byte == 0x0A then
7     -- omitted for later section
8   end
9   table.insert(message_table, byte)
10  n_bytes = n_bytes - 1
11 end
12
13 return update, 100 -- schedule the update function to
```

If there are any bytes available, we read one off of the serial line. We first check if it is the ASCII character `0x0A`, which is the 'line feed' or <LF> character, which is that character that the Samamet uses to signify the end of a message. If the current bytes is not the line feed character, we simply add the byte to `message_table` and repeat the loop again if there are any more bytes in the queue.

```
1 if byte == 0x0A then
2   table.insert(message_table, byte)
3   local message_string = string.char(table.unpack(message_table))
4   if not (verify_checksum(message_string)) then
5     log_error(ERROR_LIST[2])
6     gcs:send_text(0, "ERROR: PTH Data failed checksum")
7     message_table = {}
8     return update, 100
9   end
10  if not (parse_data(message_string)) then
11    log_error(ERROR_LIST[3])
12    gcs:send_text(0, "ERROR: Failed to parse data")
13    message_table = {}
14    return update, 100
15  end
16  -- reset for the next message
17  message_table = {}
18  return update, 100
19 end
```

If we find that the byte we read is in fact the line feed character, we know we have a full message we can decode.

First we verify that the checksum provided with the message, is correct. This occurs in the `verify_checksum()` function, the specifics of which will be discussed later in the ["Verifying Checksum"](#) section.

Below is the message format of the PTH sensor. At the end of the message, after the asterisk, is a two digit hexadecimal number, represented as a string. This is the checksum of the message.

```
1 $UKPTH,000E,098152.5,Pa,23.17,C,22.90,C,42.21,%,22.45,C*4A<CR><LF>
```

To calculate the checksum from the message, we take the "main body" of the message, that is the text inside, but **NOT INCLUDING** the "\$" and "\*". The main body of the message can be seen below.

```
1 UKPTH,000E,098152.5,Pa,23.17,C,22.90,C,42.21,%,22.45,C
```

Once we have the "main body" of the message, we can now calculate the checksum. As per the documentation for the sensor:

The checksum was calculated as the bit-wise exclusive OR of all 8-bit ASCII characters between, but not including, '\$' and '\*' and displayed as a 2-digit hexadecimal number

An explanation of the exclusive OR operation (XOR) can be found [here](#).

We take each of the 8-bit ASCII characters in the "main body" of the message string, and successively XOR each character with the next one.

In the example above, we start out with the ASCII character **U**. We then XOR **U** with the next character in the string, **K**. After we XOR these two characters together, we take the result of this operation, and then XOR it with the next character in the message, in this case **P**. We then repeat this process until we reach the end of the string.

Once we calculate the checksum from the message, we can now verify if the message is valid. We do this by comparing the value of the checksum we calculated, to the checksum sent with the message. If the two values do not match, we know that the data contained within the message, or the checksum bytes themselves, are corrupted in some manner.

If we find that the checksum is invalid, we report this error to Mission Planner, call `log_error()` to log an error in the BIN file, and clear `message_table`.

Once the data is verified, we can begin parsing and logging the data. The specifics will be discussed further in the "[Logging](#)" and "[Parsing Data](#)" sections.

We start by extracting the "main body" of the message into a string. We then take each section of the message, which is delimited by commas, and place them into a table.

Once we have a table of all of the sections in the message, we then can then extract the data sections and place them into their own table.

We then pass this new table of just data values to the `log_data()` function, which logs the data to the BIN file with names for each piece of data, and their appropriate units.

If the `log_data()` function detects that the input table does not meet the required size of 5 elements, it will return false, and not log the data. the `parse_data()` returns the return value of `log_data()` to `update()`.

When `parse_data()` returns false in the above case, or the other cases the function can detect, `update()` reports to Mission Planner that the data was not successfully, logs an error, and resets the message table.

If both `verify_checksum()` and `parse_data()` return true, the data that was read from the serial line was successfully logged. We can now clear the message table for the next message and continue to reschedule the `update()` function to read the next message.

```
1 return update, 100 -- reschedules the loop every 100ms
```

Here we schedule the update function to return every 100 milliseconds. We schedule the loop to run significantly faster than what the Samamet to prevent cases where we receive more than one message for each run of the `update()` function. Receiving more than one message causes us to log the messages that were recorded around a second apart, but in the log file, show to be around only three milliseconds apart. To prevent this we simply schedule the loop to run faster than the sensor

sends out its data, and perform some simple checks (that were discussed earlier) to prevent any false errors from being logged.

## Verifying Checksum

Snippet of the `verify_checksum()` function, with comments removed.

```
1 function verify_checksum(message_string)
2   local data_string = message_string:match("%$(.*)%*")
3
4   if data_string == nil then
5     return false
6   end
7
8   local incoming_checksum = message_string:match("%*([0-9A-F][0-9A-F])")
9
10  if incoming_checksum == nil then
11    return false
12  end
13
14  incoming_checksum = tonumber(incoming_checksum, 16)
15
16  local checksum = 0x0
17  local string_bytes = { data_string:byte(1, #data_string) }
18  for i = 1, #string_bytes do
19    checksum = (checksum ~ string_bytes[i])
20  end
21
22  if checksum ~= incoming_checksum then
23    return false
24  else
25    return true
26  end
27 end
```

We first take the message string and perform a regular expression (regex or regexp) match on the string. Here the Lua regex `"%$(.*)%*"` first looks for a "\$", once it finds one, it then matches any characters after the "\$" up until it finds a "\*". This extracts the main body of the message, which contains the data that we need to process for logging. An example of a full message can be seen below.

```
1 $UKPTH,000E,098152.5,Pa,23.17,C,22.90,C,42.21,%,22.45,C*4A<CR><LF>
```

Before we continue, we check if the regex failed, if it has, it will have returned a value of `nil`. We check for this, and if this is true, we return false for the caller to handle.

We then perform another regex on the message string again to extract the checksum. The regex



"%\* ( [0-9A-F] [0-9A-F] )" first finds a "\*". After it finds one, it then matches exactly two characters. Since we are matching for a hexadecimal number, the regex will only accept characters in hexadecimal numbers. This includes all digits between zero and nine, and all capital version of letters between and including A-F.

Once we have extracted the checksum, we verify that the regex was successful by making sure the resulting string is not `nil`. If it is `nil`, we return false for the caller to handle.

If we successfully extraced the checksum value, we then need to convert it to an integer since we cannot compare the string directly with the checksum value we will calculate later. To do this we call the `tonumber()` function. We pass in the string we want convert to a number, and the base of the number we are passing in. In this case with a hexadecimal number, we specify 16.

Now that we have extracted the main message body and the incoming checksum, we can now calculate the checksum ourselves and verify it is correct.

We start by creating the `checksum` variable to hold our calculated checksum and set it to zero. We do this so we can perform the first XOR with the first character in the string without causing any issues.

We then need to convert the `data_string` variable into an array of bytes. We need to do this for two reasons. One, we need to be able to iterate over the string easily, and two, Lua does not support doing bitwise operations, (such as XOR) on strings or characters directly.

```
1 local string_bytes = { data_string:byte(1, #data_string) }
```

The above code snippet first takes the first character in the string, and returns its ASCII value. We place this expression inside of a set of curly braces to take all of the ASCII values of the characters in the string and place them in a table.

Once we have done that we can finally calculate the checksum. As mentioned before. We calculate the checksum by simply XORing each character with the result of the previous XOR operation.

Once we have calculated the checksum, we compare it with the incoming checksum. If the two are not the same, we return false, meaning that the data has been corrupted at some point during the transmission. If the two values are the same, we return true, as the data has not been effected and we can continue processing the data.

For information on Lua's regular expressions, you can view these pages:

- [Pattern-Matching Functions](#)
- [Lua pattern matching](#)

For making patterns and regular expressions in Lua, you can use these web tools:

- [Lua Patterns Viewer](#)
- [Lua Pattern Tester](#)

## Parsing Data

Snippet of the `parse_data()` function

```

1 function parse_data(message_string)
2     local data_string = message_string:match("%$(.*)%*")
3
4     if data_string == nil then
5         return false
6     end
7
8     local data_table = {}
9
10    for str in string.gmatch(data_string, "([^\s\"',\".. \" ]+)" ) do
11        table.insert(data_table, str)
12    end
13
14    if #data_table ~= 12 then
15        return false
16    end
17
18    local measurements_table={}
19    for i=3,12,2 do
20        table.insert(measurements_table, data_table[i])
21    end
22
23    -- report data to Mission Planner, not necessary all the time
24    -- (OMMITED HERE FOR BREVITY)
25
26    return log_data(measurements_table)
27
28 end

```

We first take the message string and perform a regular expression (regex or regexp) match on the string. Here the Lua regex `"%$(.*)%*"` first looks for a "\$", once it finds one, it then matches any characters after the "\$" up until it finds a "\*". This extracts the main body of the message, which contains the data that we need to process for logging. An example of a full message can be seen below.

```

1 $UKPTH,000E,098152.5,Pa,23.17,C,22.90,C,42.21,%,22.45,C*4A<CR><LF>

```

Before we continue, we check if the regex failed, if it has, it will have returned a value of `nil`. We check for this, and if this is true, we return false for the caller to handle.

After we match the main body of the message, we can start preparing to extract the date from it. First we initialize the `data_table` table, which is where we will store each of the messages sections for processing.

Next we perform another regex on the message body. Here the regex `"([^\s\"',\".. \" ]+)"`, or

more simply written as "`( [^, ]+ )`" takes the string, and matches every character up until it finds a ",". It does this for all of the segments in the string. We then use the for loop to iterate over all of these segments and place them into are previously defined `data_table`.

We then check the size of `data_table` to ensure it got all twelve segments we are expecting, if not, we return false for the caller to handle.

We then take the measurement values from `data_table` and place them into a new table called `measurements_table`.

After we have extracted the measurement values, we can optionally send the values to the Mission Planner output, but is not required for the script to function.

Finally we call `log_data` and pass in the `measurements_table` as an argument. `log_data()` returns true or false depending on whether the table is the correct size. We then return this boolean value to the caller for them to handle.

For information on Lua's regular expressions, you can view these pages:

- [Pattern-Matching Functions](#)
- [Lua pattern matching](#)

For making patterns and regular expressions in Lua, you can use these web tools:

- [Lua Patterns Viewer](#)
- [Lua Pattern Tester](#)

## Logging

### Logging Data

Snippet of the `log_data()` function, with comments removed.

```
1 function log_data(measurements_table)
2   if #measurements_table ~= 5 then
3     return false
4   end
5   logger:write('SAMA', 'pres,temp1,temp2,hum,temp3,error',
6               'NNNNNN',
7               'POO%0-',
8               '-----',
9               measurements_table[1],
10              measurements_table[2],
11              measurements_table[3],
12              measurements_table[4],
13              measurements_table[5],
```

```
14         "Normal")
15     return true
16 end
```

Above is the `log_data()` function. This function takes in a table as an argument.

The function first checks if the table that is passed to it is the correct size, in this case 5, as that is the number of sensors on the PTH. If it does not pass this check, `log_data()` returns a **false** value, which is processed by the caller.

If the table passes this check, we then write the data to the BIN file.

The `logger:write` method take several arguments to define the various parameters that go into the log file.

The first argument, `'SAMA'`, is the section name for the data we are going to log in the file. This name has to be at most 4 characters, and cannot be the same as any other section name that ArduPilot logs. The second argument, `'pres,temp1,temp2,hum,temp3,error'`, specifies the name of each piece of data logged. These labels are stored under the section name in the log file, in total these names cannot exceed 64 characters.

The third argument, `'NNNNNN'`, specifies the type of each label. In this case `'N'`, specifies a `char[16]`, which is a string of a maximum of 16 characters. The fourth and fifth arguments specify the units and the multiplier of each of the units respectively. In the fourth argument `'P'` represents Pascals, for the pressure measurement, `'O'` represents degrees Celsius, for the temperature measurements, and `'%` for percentage, for the humidity measurements, and `'-'` for no units/string for the error column. For the fifth argument, the `'-'` specifies that we want no multiplier applies to our data.

Further explanations on the format, unit, and multiplier types can be found [here](#).

Once we specify the parameters for the data that is going to be logged, we then pass in the data we would like to log in the file. In this case, we use the 5 elements in the `measurements_table` table, and the string `"Normal"` for the error column. These are in the same order as the labels we specified in the second argument.

Further explanation on the arguments of the `logger:write()` method can be found [here](#).

Once we log the data we simply return true to the caller for them to handle. `logger:write()` unfortunately does not return a value to tell us whether it was successful so we can only assume that it wrote to the BIN file correctly.

## Logging Errors

The `log_error()` function, with comments removed.

```
1 function log_error(error_type)
2     logger:write('SAMA', 'pres,temp1,temp2,hum,temp3,error',
3                 'NNNNNN',
4                 'P00%0-',
5                 '-----',
6                 '0', '0', '0', '0', '0', error_type)
7 end
```

The `log_errors()` is very similar to the `log_data()` function, the only difference is that instead of writing any specific data, we simply write zeros to the log file, and log the type of error as a string (which will originate from the `ERROR_LIST` table). We do this as it is very obvious in the log file when there is an error, and we deal with it easily during post processing.

For an explanation of the arguments, in `logger:write()`, you can look in the ["Logging Data"](#) section

## Important Notes

If a Lua script has an error that the Lua interpreter detects, the script is generally not able to be restarted until the autopilot is manually restarted or a restart script command is sent. This is why there are several checks to ensure that the data parsing operations work as expected.

Doing this, and letting the script still run after an error is detected is important, as it prevents the script from crashing from a minor issue that fixes itself immediately, such as minor data corruption, or a short in a sensor connection, that causes a temporary disconnection. After the issue resolves itself, assuming the script can handle the error, the script can continue logging without having to land a drone and restart the script, which is vital for long and important flights.

## Important Links

Below is a list of the URLs linked to in the document in case that the hyperlinks are not usable or reachable, such as if the document is printed on paper.

1. ArduPilot Serial Dump Example

- [https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP\\_Scripting/examples/Serial\\_Dump.lua](https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP_Scripting/examples/Serial_Dump.lua)

2. Exclusive OR Wikipedia Article

- [https://en.wikipedia.org/wiki/Exclusive\\_or](https://en.wikipedia.org/wiki/Exclusive_or)

3. Formatting, Units, and Multipliers in ArduPilots Logging System

- [https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP\\_Logger/README.md](https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP_Logger/README.md)

4. ArduPilot adding a new log message

- <https://ardupilot.org/dev/docs/code-overview-adding-a-new-log-message.html>

5. Lua Pattern-Matching Functions

- <https://www.lua.org/pil/20.1.html>

6. Lua Pattern Matching

- <https://riptutorial.com/lua/example/20315/lua-pattern-matching>

7. Lua Patterns Viewer

- <https://gitspartv.github.io/lua-patterns/>

8. Lua Pattern Tester

- <https://montymahato.github.io/lua-pattern-tester/>

9. Supported log file data types

- [https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP\\_Logger/README.md](https://github.com/ArduPilot/ardupilot/blob/master/libraries/AP_Logger/README.md)

10. `logger:write()` method documentation

- <https://ardupilot.org/dev/docs/code-overview-adding-a-new-log-message.html>