

Marvelmind API manual.

Version 2019.03.05

Product overview

Marvelmind API library is used by Marvelmind Dashboard software and provides interface for using by any user's software. API is coming as dynamic-link library (DLL) for MS Windows and shared library for Linux (x86 and ARM platforms).

In addition to the API library, the package includes C example software, which was used for testing of the API and includes calls of all API functions.

The example can be used as base for developing of user's software and for porting API library interface (file 'marvelmind_api.c') to other programming languages.

Tested on:

1. Operating system: Ubuntu 16.04;
CPU: Intel Core i5 3.1 GHz
2. Operating system: Raspbian (2018-11-13-raspbian-stretch-full);
Platform: Raspberry Pi 3 Model B+

Installation for Windows

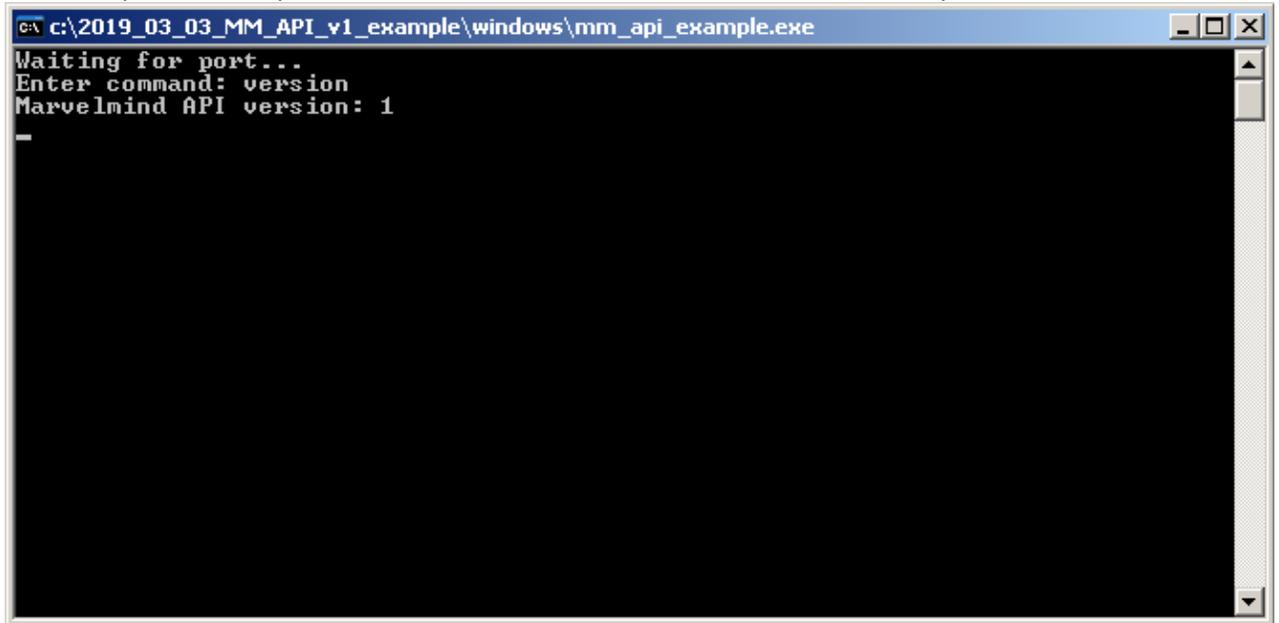
- Download Marvelmind API software package. Copy Dashboard API and example software to directory that you will use for the program. So the windows version of the example is coming with prebuilt executable file, you can immediately run 'mm_api_example.exe' from the 'windows' directory coming in API software package.

Installation for Linux

- Download Marvelmind API software package. Copy Dashboard API to directory that you will use for the program. Note the Linux version is provided for two hardware platforms: **x86** (most of laptops based on Intel or AMD CPU) and **arm** (for example, single-board computers like Raspberry PI)
- Copy library **libdashapi.so** corresponding to your platform to the directory **/usr/local/lib** by executing command **sudo cp libdashapi.so /usr/local/lib** in terminal opened in directory with **libdashapi.so**. After that, execute **sudo ldconfig** in terminal.
- May be you will need to give rights for your user to access serial port by adding him to **dialout** group:
 - Execute in terminal: **sudo adduser \$USER dialout**
 - Add to the directory **/etc/udev/rules.d** file "**99-tty.rules**" with following content:
#Marvelmind serial port rules
KERNEL=="ttyACM0",GROUP="dialout",MODE="666"
- Build the example software – execute 'make all' in terminal opened in 'source' directory coming with the package
- Run the example by typing './mm_api_example' in terminal

Check connection to API

After running example software press “space” button in terminal, type command ‘version’ and press enter. If the example software prints version of API, it can communicate with API library.



```
C:\2019_03_03_MM_API_v1_example\windows\mm_api_example.exe
Waiting for port...
Enter command: version
Marvelmind API version: 1
-
```

1. Marvelmind API library description.

API is coming as dynamic-link library (DLL) for MS Windows and shared library for Linux (x86 and ARM platforms). The library includes set of functions for monitoring and controlling Marvelmind system via modem connected to USB port of the computer. This section of document contains description of all these functions.

To provide more compatibility with different programming languages, most of complex data structures are passing via untyped pointers to memory. Functions description include offset of every data field in the memory pool. In the file 'marvelmind_api.c' from the example software you can see implementation of moving data between memory pools and fields in C structures.

Types of parameters in the description are shown in C syntax. Here is description of the types:

Type	Size (bytes)	Description
bool	1	Boolean type. Zero means false, non-zero means true
uint8_t	1	Unsigned integer value, 0...255
int8_t	1	Signed integer value in two's complement format , -128...127
uint16_t	2	Unsigned integer value, 0...65535
int16_t	2	Signed integer value in two's complement format , -32768...32767
uint32_t	4	Unsigned integer value, 0...4294967295
int32_t	4	Signed integer value in two's complement format , -2147483648...2147483647
void *	4/8	Memory pointer (address in memory). 4 bytes for 32-bit platforms, 8 bytes for 64-bit platforms.

Each function description includes set of API versions where this function is available. New API versions will support more functions for new features in Marvelmind system. Now not all features available in Dashboard are available via API, so if you need more API functions please ask to info@marvelmind.com.

List of supported functions:

Function	API versions
Get version of Marvelmind API library	V1+
Try to open serial port	V1+
Close serial port	V1+
Get version and CPU ID of Marvelmind device	V1+
Get list of devices	V1+
Wake device	V1+
Send device to sleep	V1+
Get telemetry data from beacon	V1+
Get latest location data	V1+
Get latest raw distances data	V1+
Get location update rate setting	V1+
Set location update rate setting	V1+
Add submap	V1+
Delete submap	V1+
Freeze submap	V1+
Unfreeze submap	V1+
Get submap settings	V1+
Set submap settings	V1+
Get ultrasonic settings of the beacon	V1+
Set ultrasonic settings of the beacon	V1+
Erase map	V1+
Reset device to default settings	V1+
Check if the device type is modem	V1+
Check if the device type is beacon	V1+
Check if the device type is hedgehog	V1+

1.1. Get version of Marvelmind API library.

Reads version of the API library. Required to ensure the needed functions are available in this version of library.

Function name: **mm_api_version**
Declaration in C: `bool mm_api_version(void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed false – error in execution

Parameters:

Type	Description
void *	Pointer to data to be filled

Structure of data returned via pointer.

Type	Description
uint32_t	Version of API library

1.2. Try to open serial port.

Opens port where Marvelmind device (modem or beacon) is connected via USB (virtual serial port). You don't need to specify serial port name, because the API searching all serial ports and checks if it corresponds to Marvelmind device or no.

Function name: **mm_open_port**
Declaration in C: `bool mm_open_port ();`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, port is opened false – error in execution

Parameters: none

1.3. Close serial port.

Closes port if it was previously opened by [mm_open_port](#) function.

Function name: **mm_close_port**
Declaration in C: `bool mm_close_port ();`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, port is closed false – error in execution

Parameters: none

1.4. Get version and CPU ID of Marvelmind device.

Reads version and CPU ID. Version includes information about firmware version and type of device hardware. CPU ID is the unique ID of the device item.

Function name: **mm_get_device_version_and_id**

Declaration in C: `bool mm_get_device_version_and_id (uint8_t address, void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, version and CPU ID data retrieved false – error in execution

Parameters:

Type	Description
uint8_t	Address of Marvelmind device (1...254)
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint8_t	Major version of firmware (example: "6", for version V6.07a)
uint8_t	Minor version of firmware (example: "7", for version V6.07a)
uint8_t	Second minor version of firmware (example: "1", for version V6.07a)
uint8_t	Device type ID (see appendix).
uint8_t	Firmware options (TBD).
uint32_t	CPU ID. Printing this value as hexadecimal gives CPU ID in form shown in dashboard and on the stickers on devices.

1.5. Get list of devices.

Reads list of Marvelmind devices known to modem. The list includes list of all devices connected by radio to modem's network, including sleeping devices.

Function name: **mm_get_devices_list**
Declaration in C: `bool mm_get_devices_list (void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, list of devices is retrieved false – error in execution

Parameters:

Type	Description
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint8_t	Number of following devices in the list (N)
N*9 bytes	Sequence of N devices structures, described in next table

Structure of each device in the list:

Type	Description
uint8_t	Address of device
bool	true = duplicated address - more than 1 device with same address was found false = not duplicated address
bool	true = device is sleeping false = device not sleeping
uint8_t	Major version of firmware (example: "6", for version V6.07a)
uint8_t	Minor version of firmware (example: "7", for version V6.07a)
uint8_t	Second minor version of firmware (example: "1", for version V6.07a)
uint8_t	Device type ID (see appendix).
uint8_t	Firmware options (TBD).
uint8_t	Flags: Bit 0: 1 – device connection complete – device has confirmed connection 0 – waiting for confirmation from device (like 'Connecting...' in dashboard). Bit 1...7 - TBD

1.6. Wake device.

Sends command to wake specified device. If wake command was sent and such device exists, the device will connect to modem in several seconds and will appear in [devices list](#).

Function name: **mm_wake_device**
Declaration in C: `bool mm_wake_device (uint8_t address);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, wake command was sent false – error in execution

Parameters:

Type	Description
uint8_t	1...254 - address of Marvelmind device to wake 0 – wake all devices

1.7. Send device to sleep.

Send to sleep existing device.

Function name: **mm_send_to_sleep_device**
Declaration in C: `bool mm_send_to_sleep_device (uint8_t address);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, sleep command was sent false – error in execution

Parameters:

Type	Description
uint8_t	1...254 - address of Marvelmind device to sleep 0 – send to sleep all devices

1.8. Get telemetry data from beacon.

Reads telemetry data of Marvelmind beacon.

Function name: **mm_get_beacon_telemetry**

Declaration in C: `bool mm_get_beacon_telemetry (uint8_t address, void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, telemetry is retrieved false – error in execution

Parameters:

Type	Description
uint8_t	Address of Marvelmind beacon (1...254)
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint32_t	Working time of the beacon, seconds (time from reset or waking up).
int8_t	RSSI, dBm – radio signal strength
int8_t	Measured temperature, °C
uint16_t	Supply voltage, mV
16 bytes	Reserved (0)

1.9. Get latest location data.

Reads latest updated coordinates pack from modem. Also reads user payload data if available.

Function name: **mm_get_last_locations**
Declaration in C: `bool mm_get_last_locations(void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, location data was retrieved false – error in execution

Parameters:

Type	Description
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
18*6 bytes	6 18-byte data structures of last updated coordinates, see table below
bool	true – new raw distances are available to read
5 bytes	TBD
uint8_t	User payload data size (M)
M bytes	User payload data

Structure of each location data item:

Type	Description
uint8_t	Address of device (1...254) 0 - this data item is not filled
uint8_t	Head index (TBD)
int32_t	X coordinate, mm
int32_t	Y coordinate, mm
int32_t	Z coordinate, mm
uint8_t	Status flags (TBD)
uint8_t	Quality of positioning, 0...100%
uint8_t	TBD
uint8_t	TBD

1.10. Get latest raw distances data.

Reads latest updated raw distances pack from modem.

Function name: **mm_get_last_distances**
Declaration in C: `bool mm_get_last_distances(void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, raw distances data was retrieved false – error in execution

Parameters:

Type	Description
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint8_t	Number of raw distances data items (N)
9*N bytes	N 9-byte data structures of last raw distances, see table below

Structure of each raw distance data item:

Type	Description
uint8_t	Address of ultrasonic RX device (1...254) 0 - this data item is not filled
uint8_t	RX Head index (TBD)
uint8_t	Address of ultrasonic TX device (1...254) 0 - this data item is not filled
uint8_t	TX Head index (TBD)
uint32_t	Distance from TX device to RX device, mm
uint8_t	TBD

1.11. Get location update rate setting.

Reads location update rate setting from modem.

Function name: **mm_get_update_rate_setting**
Declaration in C: `bool mm_get_update_rate_setting (void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, update rate was retrieved false – error in execution

Parameters:

Type	Description
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint32_t	Location update rate setting in mHz. So 1000 is returned for 1 Hz, 16000 for 16 Hz, 50 for 0.05 Hz mode.

1.12. Set location update rate setting.

Writes location update rate setting to modem.

Function name: **mm_set_update_rate_setting**
Declaration in C: `bool mm_set_update_rate_setting (void *pdata);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, update rate was changed false – error in execution

Parameters:

Type	Description
void *	Pointer to data

Structure of data by pointer (should be filled before function call):

Type	Description
uint32_t	Location update rate setting in mHz. So 1000 is returned for 1 Hz, 16000 for 16 Hz, 50 for 0.05 Hz mode. The system will use most close to specified update rate from the series: 0.05 Hz, 0.1 Hz, 0.2 Hz, 0.5Hz, 1 Hz, 2 Hz, 4 Hz, 8 Hz, 12 Hz, 16 Hz, 16+Hz.

1.13. Add submap.

Adds new submap.

Function name: **mm_add_submap**
Declaration in C: `bool mm_add_submap (uint8_t submapId);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, submap was added false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID to add (0...254)

1.14. Delete submap.

Delete existing submap.

Function name: **mm_delete_submap**
Declaration in C: `bool mm_delete_submap (uint8_t submapId);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, submap was removed false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID to delete (0...254)

1.15. Freeze submap.

Freezes submap.

Function name: **mm_freeze_submap**
Declaration in C: `bool mm_freeze_submap (uint8_t submapId);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, submap is frozen false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID to freeze (0...254)

1.16. Unfreeze submap.

Unfreezes submap.

Function name: **mm_unfreeze_submap**
Declaration in C: `bool mm_unfreeze_submap (uint8_t submapId);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, submap is unfrozen false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID to unfreeze (0...254)

1.17. Get submap settings.

Reads submap settings from modem.

Function name: **mm_get_submap_settings**

Declaration in C: `bool mm_get_submap_settings (uint8_t submapId , void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, submap settings were retrieved false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID (0...254)
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint8_t	Starting beacon trilateration
uint8_t	Starting set of beacons, beacon 1
uint8_t	Starting set of beacons, beacon 2
uint8_t	Starting set of beacons, beacon 3
uint8_t	Starting set of beacons, beacon 4
bool	true = 3D navigation enabled
bool	true = Submap is used only for Z coordinate
bool	true = manual limitation distance false = auto limitation distance
uint8_t	Maximum distance, meters (for manual limitation distances)
int16_t	Submap X shift, cm
int16_t	Submap Y shift, cm
int16_t	Submap Z shift, cm
uint16_t	Submap rotation, centidegrees
int16_t	Plane rotation quaternion, W (quaternion is normalized to 10000)
int16_t	Plane rotation quaternion, X
int16_t	Plane rotation quaternion, Y
int16_t	Plane rotation quaternion, Z
int16_t	Service zone thickness, cm
int16_t	Hedges height in 2D mode
bool	true = submap is frozen
bool	true = submap is locked
bool	true = stationary beacons are higher than mobile
bool	true = submap is mirrored
4 bytes	List of addresses of beacons in submap (0 = none)
8 bytes	List of ID's of nearby submaps (255 = none)
uint8_t	Number of service zone polygon points (P)
P*4 bytes	List of service zone polygon points structures (see below)

Structure of service zone polygon point:

Type	Description
int16_t	X, cm
int16_t	Y, cm

1.18. Set submap settings.

Writes submap settings to modem.

Function name: **mm_set_submap_settings**

Declaration in C: `bool mm_set_submap_settings (uint8_t submapId , void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, submap settings were changed false – error in execution

Parameters:

Type	Description
uint8_t	Submap ID (0...254)
void *	Pointer to data to be written (see ‘get submap settings’ function).

1.19. Get ultrasonic settings of the beacon.

Reads ultrasonic settings from specified beacon.

Function name: **mm_get_ultrasound_settings**

Declaration in C: `bool mm_get_ultrasound_settings (uint8_t address , void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, ultrasonic settings were retrieved false – error in execution

Parameters:

Type	Description
uint8_t	Address of the beacon (1...254)
void *	Pointer to data to be filled

Structure of data returned via pointer:

Type	Description
uint16_t	Frequency of ultrasound TX (not relevant for DSP RX-only beacons)
uint8_t	Number of TX periods (not relevant for DSP RX-only beacons)
bool	true= use AGC for RX false = manual gain for RX
uint16_t	Manual gain value (0...4000)
bool	true = Sensor RX1 is enabled in normal mode
bool	true = Sensor RX2 is enabled in normal mode
bool	true = Sensor RX3 is enabled in normal mode
bool	true = Sensor RX4 is enabled in normal mode
bool	true = Sensor RX5 is enabled in normal mode
bool	true = Sensor RX1 is enabled in frozen mode
bool	true = Sensor RX2 is enabled in frozen mode
bool	true = Sensor RX3 is enabled in frozen mode
bool	true = Sensor RX4 is enabled in frozen mode
bool	true = Sensor RX5 is enabled in frozen mode
uint8_t	Index of DSP RX filter (relevant only for DSP beacons) 0 = 19 kHz 1 = 25 kHz 2 = 31 kHz 3 = 37 kHz 4 = 45 kHz 5 = 56 kHz

1.20. Set ultrasonic settings of the beacon.

Write ultrasonic settings to specified beacon.

Function name: **mm_set_ultrasound_settings**

Declaration in C: `bool mm_set_ultrasound_settings (uint8_t address , void *pdata);`

Available for API versions: V1+

Returned value:

Type	Description
bool	true – function successfully executed, ultrasonic settings were changed false – error in execution

Parameters:

Type	Description
uint8_t	Address of the beacon (1...254)
void *	Pointer to data to be written (see ‘get ultrasonic settings’ function).

1.21. Erase map.

Erase map in modem – remove all submaps (except submap 0), reset submap 0 to initial state, remove all connected beacons from network.

Function name: **mm_erase_map**
Declaration in C: `bool mm_erase_map ();`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, map erased false – error in execution

Parameters: none

1.22. Reset device to default settings.

Reset device to default settings (radio, ultrasonic etc).

Function name: **mm_set_default_settings**
Declaration in C: `bool mm_set_default_settings (uint8_t address);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – function successfully executed, device was reset to default settings false – error in execution

Parameters:

Type	Description
uint8_t	Address of the device (1...254) 255 – reset to default the device connected via USB

1.23. Check if the device type is modem.

Checks if the specified device type corresponds to modem.

Function name: **mm_device_is_modem**
Declaration in C: `bool mm_device_is_modem (uint8_t deviceType);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – specified device type corresponds to modem

Parameters:

Type	Description
uint8_t	Device type to check

1.24. Check if the device type is beacon.

Checks if the specified device type corresponds to beacon.

Function name: **mm_device_is_beacon**
Declaration in C: `bool mm_device_is_beacon (uint8_t deviceType);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – specified device type corresponds to beacon

Parameters:

Type	Description
uint8_t	Device type to check

1.25. Check if the device type is hedgehog.

Checks if the specified device type corresponds to hedgehog.

Function name: **mm_device_is_hedgehog**
Declaration in C: `bool mm_device_is_hedgehog (uint8_t deviceType);`
Available for API versions: V1+
Returned value:

Type	Description
bool	true – specified device type corresponds to hedgehog

Parameters:

Type	Description
uint8_t	Device type to check

2. Description of C example for Marvelmind API.

C example is used for testing of Marvelmind API and can be used as basis for building of user application. The C example is the console application. It was tested on following platforms:

- CPU: Intel Core 2 Duo, OS: MS Windows XP;
- CPU: Intel Core i5, OS: Linux Ubuntu 16.04;
- Raspberry Pi 3 Model B+, OS: Raspbian (2018-11-13-raspbian-stretch-full)

On the Windows platform the example was built with CodeBlocks IDE and so the example includes CodeBlocks project file.

On the Linux platforms, the example was build with using make utility and so the example includes makefile for this.

The example includes following modules:

File name	Description
main.c	Module with main() function. Calls of functions of example and implements simple command line interface.
marvelmind_example.c marvelmind_example.h	marvelmindStart() – initialization of the example marvelmindFinish() – called after finishing work with API marvelmindCycle() – frequently called from main loop Also module includes several function for processing commands entered by user.
marvelmind_api.c marvelmind_api.h	marvelmindAPILoad() – loads API library marvelmindAPIFree() – frees memory used by API library All functions of communication with API library.
marvelmind_devices.c marvelmind_devices.h	Supports list of beacons retrieved from modem by calling ' get devices list ' command. Each beacon includes data about its location and distances to other beacons.
marvelmind_pos.c marvelmind_pos.h	Reads latest location data and latest raw distances . Updates these data in the devices list.
marvelmind_utils.c marvelmind_utils.h	Some helper functions used by other modules.

How the example works:

1. Try to [open](#) serial port until success.
2. When port is opened, the program reads version of device connected via USB. If this is modem, the program continues to execute next steps.
3. When connected to modem, the program reads the [devices list](#) with 1 Hz rate. The devices list is compared with currently stored in marvelmind_devices.c module and the list in marvelmind_devices.c is updated if any changes are detected. All changes are printed in console.
4. When connected to modem, the program reads [latest location data](#) with 20 Hz rate. If the flag of new raw distances data is set, the program reads [latest raw distances](#). The program compares locations and distances with data in devices list in marvelmind_devices.c and updates the data if they are changed. All changed data are printed in console.

5. If the program can't get latest location data for 10 times, it [closes the port](#) and returns to step 1 – tries to open the port again. Reopening of the port is needed for cases when modem was disconnected and connected back to USB.
6. If user press '**space**' button, the program shows 'Enter command: ' message and waits for user command. Most of API functions are called by user command, see below for details.

User commands:

If user press '**space**' button when program is running, the program shows message '**Enter command: ' . User should type command on keyboard and press **enter**.**

Next table contains format of all user commands:

Commands group	Description
API version	Format of command: version Action: Prints version of API library
Exit from program	Format of command: quit Action: Finishes program execution
Sleep/wake	Format of command: wake <address> Action: Execute wake command. Examples: wake 5 - send command to wake device 5 wake 0 - send command to wake all devices
	Format of command: sleep <address> Action: Execute sending to sleep command. Examples: sleep 5 - send to sleep device 5 sleep 0 - send to sleep all devices
Default	Format of command: default <address> Action: Execute reset to default settings command. Examples: default 5 - set default settings for device 5
Read telemetry	Format of command: tele <address> Action: Reads and prints telemetry data of beacon. Examples: tele 5 - read and print telemetry of beacon 5

Submap commands	<p>Format of command: submap add <submapId> Action: Execute command to add submap with specified submap ID. Example: submap add 1 - add submap 1</p>
	<p>Format of command: submap delete <submapId> Action: Execute command to delete submap with specified submap ID. Example: submap delete 1 - delete submap 1</p>
	<p>Format of command: submap freeze <submapId> Action: Execute command to freeze submap with specified submap ID. Example: submap freeze 0 - freeze submap 0</p>
	<p>Format of command: submap unfreeze <submapId> Action: Execute command to unfreeze submap with specified submap ID. Example: submap unfreeze 0 - unfreeze submap 0</p>
	<p>Format of command: submap get <submapId> Action: Execute command to get settings of submap with specified submap ID. Example: submap get 0 - get and print settings of submap 0</p>
	<p>Format of command: submap testset <submapId> Action: Execute command to set settings of submap with specified submap ID. The program writes some predefined settings for testing of the command; please see the example code. Example: submap testset 0 - modify settings of submap 0</p>
Map commands	<p>Format of command: map erase Action:</p>

	<p>Execute erase map command.</p> <p>Example: map erase - erase map in modem</p>
Update rate commands	<p>Format of command: rate get</p> <p>Action: Execute reading update rate setting command.</p> <p>Example: rate get - read and print update rate setting</p>
	<p>Format of command: rate set <value></p> <p>Action: Execute change update rate setting command. Value is given in Hz</p> <p>Example: rate set 0.5 - set update rate 0.5 Hz</p>
Ultrasound commands	<p>Format of command: usound get <address></p> <p>Action: Execute reading ultrasonic settings for specified beacon.</p> <p>Example: usound get 5 - read and print ultrasound settings of beacon 5</p>
	<p>Format of command: usound testset <address></p> <p>Action: Execute writing ultrasonic settings for specified beacon. The program writes some predefined settings for testing of the command; please see the example code.</p> <p>Example: usound testset 5 - modify ultrasound settings of beacon 5</p>

Appendix 1. Device types.

Here is the list of 'Device type ID' values for specific devices:

Device type ID	Device description
22	Beacon HW V4.5
23	Beacon HW V4.5 (hedgehog mode)
24	Modem HW V4.9
30	Beacon HW V4.9
31	Beacon HW V4.9 (hedgehog mode)
32	Beacon DSP
36	Mini-beacon TX
37	Beacon-TX-IP67

You can get device type id from [devices list](#) and [reading device version](#) commands.