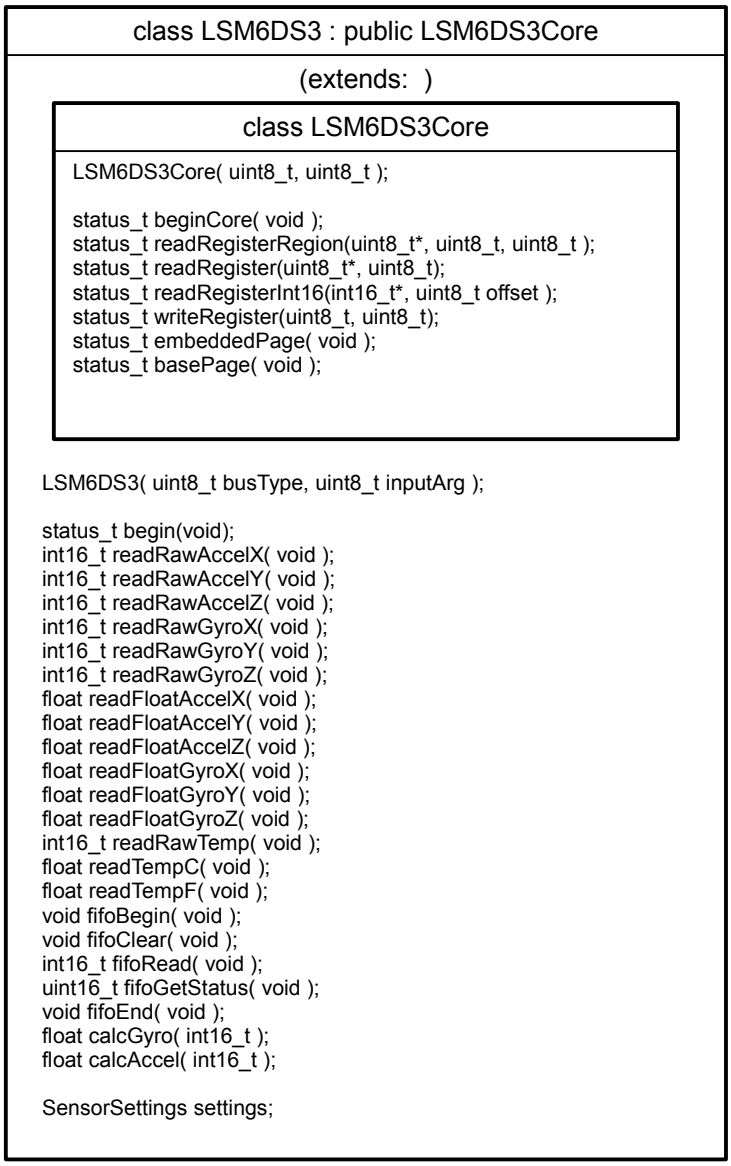
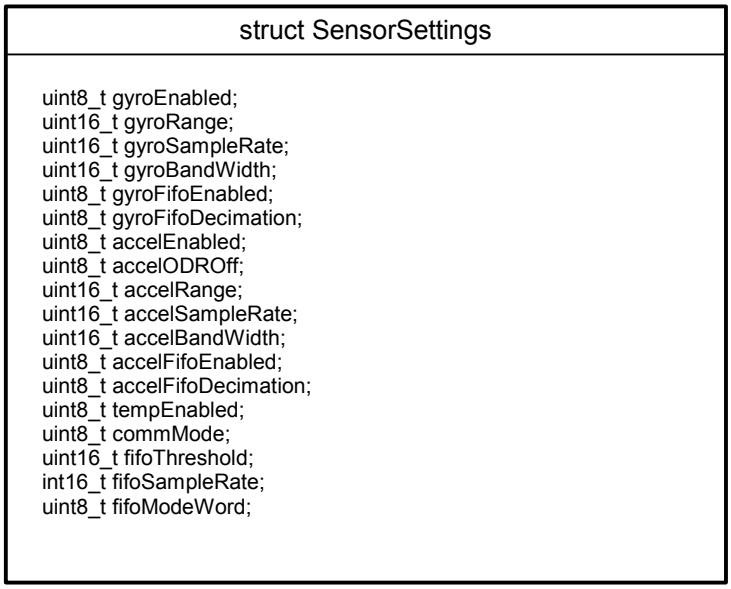

class LSM6DS3 : public LSM6DS3Core
(extends:)
class LSM6DS3Core
LSM6DS3Core(uint8_t, uint8_t);
status_t beginCore(void);
status_t readRegisterRegion(uint8_t*, uint8_t, uint8_t);
status_t readRegister(uint8_t*, uint8_t);
status_t readRegisterInt16(int16_t*, uint8_t offset);
status_t writeRegister(uint8_t, uint8_t);
status_t embeddedPage(void);
status_t basePage(void);
LSM6DS3(uint8_t busType, uint8_t inputArg);
status_t begin(void);
int16_t readRawAccelX(void);
int16_t readRawAccelY(void);
int16_t readRawAccelZ(void);
int16_t readRawGyroX(void);
int16_t readRawGyroY(void);
int16_t readRawGyroZ(void);
float readFloatAccelX(void);
float readFloatAccelY(void);
float readFloatAccelZ(void);
float readFloatGyroX(void);
float readFloatGyroY(void);
float readFloatGyroZ(void);
int16_t readRawTemp(void);
float readTempC(void);
float readTempF(void);
void fifoBegin(void);
void fifoClear(void);
int16_t fifoRead(void);
uint16_t fifoGetStatus(void);
void fifoEnd(void);
float calcGyro(int16_t);
float calcAccel(int16_t);
SensorSettings settings;


struct SensorSettings
uint8_t gyroEnabled;
uint16_t gyroRange;
uint16_t gyroSampleRate;
uint16_t gyroBandWidth;
uint8_t gyroFifoEnabled;
uint8_t gyroFifoDecimation;
uint8_t accelEnabled;
uint8_t accelODROff;
uint16_t accelRange;
uint16_t accelSampleRate;
uint16_t accelBandWidth;
uint8_t accelFifoEnabled;
uint8_t accelFifoDecimation;
uint8_t tempEnabled;
uint8_t commMode;
uint16_t fifoThreshold;
int16_t fifoSampleRate;
uint8_t fifoModeWord;