Elijah Craig

This document explains how the ADCS and the IHU are communicating down to the byte by byte level.

ADCS Interface

Detailed Description of the ADCS and IHU Interface

Revision: 1.0.7



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# 1 Hardware Layer

The hardware interface between the ADCS and the IHU is I2C. It is a standard implementation of I2C with a clock wire and a data wire. See [Wikipedia’s I2C article](https://en.wikipedia.org/wiki/I%C2%B2C) for details on how it works.

# 2 Software Layer

The Attitude Determination Control System, located at address , is a slave board to the IHU. The ADCS senses and controls the satellites orientation when in orbit. The IHU will periodically request data from the ADCS to prepare an updated telemetry packet. The ADCS data will be read at . Upon receiving multiple commands, the reading done by ADCS will reflect the most recent command.

## 2.1 Location Data Request

The latitude and longitude are geographic coordinates[[1]](#footnote-1), represented by signed integers with .

### 2.1.1 IHU to ADCS

The first byte represents the command ID, 0x00.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x00 |  |  |  |  |  |  |  |

### 2.1.2 ADCS to IHU

The ADCS replies with an array of two geographic coordinates.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | Latitude Coordinate | | | | Longitude Coordinate | | | |

## 2.2 Orientation Data Request

Roll, Pitch, and Yaw are all angles, represented by unsigned integers where zero indicates , and indicates .

### 2.2.1 IHU to ADCS

The first byte represents the command ID, 0x01.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x01 |  |  |  |  |  |  |  |

### 2.2.2 ADCS to IHU

ADCS replies with an array of three unsigned integers.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | Roll Angle | | Pitch Angle | | Yaw Angle | |  |  |

## 2.3 Temperature Data Request

The temperatures are represented with an signed integer with .

### 2.3.1 IHU to ADCS

The first byte represents the command ID, 0x02.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x02 |  |  |  |  |  |  |  |

### 2.3.2 ADCS to IHU

The ADCS replies with an array of five signed integers.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 |
| 0x00 | Coil X Driver Temperature | Coil Y Driver Temperature | Coil Z Driver Temperature | ADCS (µController)  Temperature |
| 0x04 | GPS Temperature |  |  |  |

## 2.4 Coil Control Data Request

The PWM is represented by a unsigned integer.

### 2.4.1 IHU to ADCS

The first byte represents the command ID, 0x03.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x03 |  |  |  |  |  |  |  |

### 2.4.2 ADCS to IHU

The ADCS replies with an array of three integers.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | Coil X Driver PWM Out | | Coil Y Driver PWM Out | | Coil Z Driver PWM Out | |  |  |

## 2.5 Coil Current Data Request

The current is represented by a signed integer with .

### 2.5.1 IHU to ADCS

The first byte represents the command ID, 0x04.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x04 |  |  |  |  |  |  |  |

### 2.5.2 ADCS to IHU

The ADCS replies with an array of three currents.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | Coil X Driver Current | | Coil Y Driver Current | | Coil Z Driver Current | |  |  |

## 2.6 Orientation Commands

This is the general rotation command using aircraft principle axes. The ADCS will maintain the request until the [drift](#_2.10_Drift) request is sent.

### 2.6.1 IHU to ADCS

The first byte is the command ID, 0x05, and all three parameters are angles, as defined in [Section 2.2](#_2.2_Orientation_Data).

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x05 | Roll | | Pitch | | Yaw | |  |

### 2.6.2 ADCS to IHU

The ADCS replies with an error code defined in Code SOP 6.4.1[[2]](#footnote-2).

## 2.7 Satellite Maneuvers for Earth

The ADCS will maintain the request until the [drift](#_2.10_Drift) request is sent.

### 2.7.1 IHU to ADCS

There are two command IDs, each one associated with pointing either the camera or antenna at the point. This command passes in a latitude and a longitude as two signed integers, with geographic coordinates found in [Section 2.1](#_2.1_Location_Data), to find and maintain a fixed point towards a location on Earth.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00­­­­­ | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x06: Camera  0x07: Antenna | Latitude | | | | Longitude [31:8] | | |
| 0x08 | [7:0] |  |  |  |  |  |  |  |

### 2.7.2 ADCS to IHU

The ADCS replies with an error code defined in Code SOP 6.4.1[[3]](#footnote-3).

## 2.8 Satellite Maneuvers for Space

This command passes in an unsigned integer, and two signed integer with representing the equatorial coordinate[[4]](#footnote-4). The ADCS will maintain the request until the [drift](#_2.10_Drift) request is sent.

### 2.8.1 IHU to ADCS

The first byte is the command ID, the parameters are the respective equatorial coordinates.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x07: Camera | Right Ascension | | | | Declination [31:8] | | |
| 0x08 | [7:0] |  |  |  |  |  |  |  |

### 2.8.2 ADCS to IHU

The ADCS replies with an error code defined in Code SOP 6.4.1[[5]](#footnote-5).

## 2.9 Roast the Chicken

The first byte represents the command ID, 0x08. These functions are primarily for maintaining the health of the satellite. The function “Roast the Chicken” behaves similarly to a rotisserie, evenly distributing the received power from the sun, aiding to normalize temperatures. The ADCS will maintain the request until the [drift](#_2.10_Drift) request is sent.

### 2.9.1 IHU to ADCS

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x08 |  |  |  |  |  |  |  |

### 2.9.2 ADCS to IHU

The ADCS replied with an error code, defined in Code SOP 6.4.1[[6]](#footnote-6), indicating the satellite is now executing the maneuver “Roast the Chicken”.

## 2.10 Drift

The drifting command halts the work of the ADCS’s X, Y, and Z coils, and lets it tumble freely.

### 2.10.1 IHU to ADCS

The first byte represents the command ID, 0x09.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x09 |  |  |  |  |  |  |  |

### 2.10.2 ADCS to IHU

The ADCS replies with an error code defined in Code SOP 6.4.1[[7]](#footnote-7).

## 2.11 Two Line Elements

The Keplerian orbital elements are transferred in the format of two-line elements (TLE[[8]](#footnote-8)).

### 2.11.1 IHU to ADCS

The first byte represents the command ID, the second is string length, and the remaining bytes contain the data in ASCII. The string does not include the null character.

|  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Byte  Offset | 0x00 | 0x01 | 0x02 | 0x03 | 0x04 | 0x05 | 0x06 | 0x07 |
| 0x00 | 0x10 | String Length | Data | Data | Data | Data | Data | Data… |

### 2.11.2 ADCS to IHU

The ADCS replies with an error code defined in Code SOP 6.4.1[[9]](#footnote-9).

# 3 Example Communication

## 3.1 Data Request for Location

IHU: [0xAC]0x00 [ADCS write] location request

ADCS reads location data and stores it in its buffer

IHU: [0xAD] [ADCS read]

ADCS: 0x01ABD591FBCF4757 46.7309088°N, -117.1697756°E

## 3.2 Repeated Data Request

IHU: [0xAC]0x02 [ADCS write] temperature request

ADCS reads the temperature and stores it in its buffer

IHU: [0xAC]0x00 [ADCS write] location request

ADCS reads location data and stores it in its buffer

IHU: [0xAD] [ADCS read]

ADCS: 0x01ABD591FBCF4757 ,

## 3.3 Maneuver Request

IHU: [0xAC] 0x07008637B2FDD30C55 [ADCS write] maneuver request  
 RA: Dec:   
 ADCS reads requests and performs appropriately  
IHU: [0xAD] [ADCS read]  
ADCS: 0x00 Success

1. <https://en.wikipedia.org/wiki/Geographic_coordinate_system> [↑](#footnote-ref-1)
2. <https://github.com/CougsInSpace/Resources/blob/master/StandardOperatingProcedures/Code.pdf> [↑](#footnote-ref-2)
3. ibid [↑](#footnote-ref-3)
4. <https://en.wikipedia.org/wiki/Equatorial_coordinate_system> [↑](#footnote-ref-4)
5. <https://github.com/CougsInSpace/Resources/blob/master/StandardOperatingProcedures/Code.pdf> [↑](#footnote-ref-5)
6. ibid [↑](#footnote-ref-6)
7. ibid [↑](#footnote-ref-7)
8. <https://en.wikipedia.org/wiki/Two-line_element_set> [↑](#footnote-ref-8)
9. <https://github.com/CougsInSpace/Resources/blob/master/StandardOperatingProcedures/Code.pdf> [↑](#footnote-ref-9)