The ADCS mission is to get access to sensors for attitude determination and then apply correction through actuators.

We designed our decision taking algorism to be as it follows :

[[File:Algorithm\_ADCS.PNG|thumb|center|800px]]

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As we can see our algorithm begins with theinitialization of our module (the IO, communication, sensors and actuators).Then a confirmation of well-functioning is sent to the OBC.

That’s where we reach the central loop. The OBC can give us several order which can be classified as follow:

\* If it asks us to start to take measure or to move (so to start the actuators), we check if a session in not already in progress and if it is not we perform the task and send the data.

\* If it asks us to stop measures or movement, we check if we were doing it and if it is the case, we stop doing

it.

\* Finally, if the OBC ask to shutdown, we verify if we were performing action and then stop them. This put

us to the end of our loop.