Project Ladon Hackerboat Systems Architecture

# Hardware Architecture

The Hackerboat control system is built around a Beaglebone Black, located in a drybox in the forward compartment of the boat. This box contains the Beaglebone, RC receiver, AIS receiver, shore communications transceiver, GNSS receiver, IMU, and associated electronics.

In addition to the main control system box, there is a power distribution box and a motor control box. In the current iteration, the motor control box contains a set of automotive relays that control power to the different windings of the trolling motor.

The power distribution box contains switches and relays to control power distribution to different boat systems. It also contains a latching relay to control the armed status of the boat and maintain it through a power cycle.

## Main Board

The main board shall serve as a carrier for the Beaglebone Black as well as core navigation sensors and communications interfaces.

### Power Input, Conditioning, & Regulation

1. Battery power (12V nominal; 9-20V permitted) shall come in through a 0.375” pitch terminal strip on the top edge of the PCB.
2. The circuit shall be protected by a 3A-5.2A SMD PTC fuse. To protect the circuit from reverse connections, a P-channel MOSFET capable of passing 12A (AO4407A) shall be connected in series with the main power rail with the gate attached to ground. The gate voltage limit of this part (-20V) shall determine the maximum input voltage of the board. This circuit must not pass any current when the power connections are reversed.
3. There shall be a green power status light that is illuminated when the board is powered correctly and a red one illuminated when connected backwards. In addition, there shall be a red fuse status LED that lights when the fuse is open.

#### Battery Monitor

1. The battery monitor circuit shall be directly connected to one of the Beaglebone’s analog inputs.
2. Since these inputs are limited to 0-1.8V, the signal must be passed through a voltage divider and must be further protected by a 1.8V Zener diode to prevent voltage excursions from damaging the circuitry.
3. At 12V nominal input voltage, the expected output of the voltage divider shall be 1.44V.

#### Main 5V Supply

1. The main 5V system supply shall be provided by a V7805-2000 5V/2A switching regulator module. This is designed as a drop-in replacement for the venerable 7805 linear regulators, except with less heat dissipation and much higher efficiency.
2. This power rail shall be connected to the Beaglebone 5V input and the 5V inputs of most onboard peripherals.
3. This power rail shall be available on pins 1-4 of the Accessory Power Connector.

#### Lighting 5V Supply

1. Power for the status lights shall be provided by an identical regulator to the main 5V supply. It is independent to prevent any electrical issues with the lighting from disrupting the main control system.
2. The power rail to the lights shall be protected by a fuse identical to the main power input.

#### Rudder Servo Supply

1. The rudder servo supply shall be independent and set to 7.4V to accommodate the needs of COTS RC servos. It shall be designed to be turned on only when the software and system are in a mode where outputs are active. This is to reduce the possibility of pinch injuries in the exposed reduction gear.
2. Activating the disarm button shall immediately depower the servo supply.
3. To accomplish these aims, the enable line of the 7.4V regulator shall be driven by an AND gate with two inputs – one from a Beaglebone GPIO pin (level shifted as required) and one from the Enable line controlled by the enable/disarm relay on the power distribution board. The Beaglebone connection shall be via a level shifter connected to pin P8.17.
4. A green status LED shall illuminate when the 7.4V supply is active.
5. The output current to the servo shall be monitored by a current shunt resistor and an INA169 high-side current sense amplifier or equivalent connected to the ADC subsystem, chip U19, channel 7. Gain and shunt resistors shall be selected to provide an output of 1.65 V/A.
6. Backup overcurrent protection shall be provided by the saturation limits of the switching supply core.

#### 3.3V Supply

1. This supply is provided by the Beaglebone’s internal power regulation circuitry. It is brought out largely to supply the 3.3V rail for the level shifters that allow the Beaglebone’s GPIO pins to interface correctly with 5V input circuitry.
2. This rail shall be provided to external circuitry on pins 7-10 of the Accessory Power Connector.
3. It shall not be protected and must therefore be used with care to prevent disruption to the Beaglebone.
4. Indication of the status of this bus may be provided by the Beaglebone’s own power status light.

#### PoE Supply

1. The main board shall provide a 15V/1A power supply for Ubiquiti PoE devices. This shall be a boost supply that is always on.
2. Overcurrent protection shall be provided by core saturation.

#### Grounding

1. All grounds on the board shall be connected to a common ground plane occupying both sides of the PCB.
2. The corner mounting holes shall be plated through and connected to the common ground plane.

### Beaglebone Hardware

1. The Beaglebone Black shall be configured with the univ-all cape file in order to provide access to all of the pins for the internal software.

### IMU

1. The IMU shall be a 9 or 10 DoF unit from Adafruit. Acceptable units include <https://www.adafruit.com/products/1604>, <https://www.adafruit.com/products/1714>, and future pin-compatible replacements.
2. The main board shall have mounting holes for a compatible header and the four corner mounting holes.
3. The mounting holes on the PCB shall be grounded.
4. The four corner mounting holes shall be secured to the board with appropriate conductive standoffs.
5. The Vin connection shall be connected to the main 5V rail.
6. The I2C lines shall be connected to the I2C-1 bus on the Beaglebone, using 4.7K pull up resistors. These are 3.3V signals already, so no level shifting is required.
7. The alignment of the IMU relative to the hull of the boat shall be with the X axis pointing forward, the Y axis pointing to port, and the Z axis pointing up.

### Relay Drivers

The relay driver circuitry groups together power switching and health monitoring circuitry to each relay/solenoid drive channel.

#### General

1. Each relay driver channel shall have a high-side driver with built-in fault, short, and overtemp detection, such as the AUIPS6041G.
2. The input of each switch channel shall be driven with a level shifter from the corresponding 3.3V logic output of the Beaglebone.
3. The fault detection line shall be of an open-drain type, and shall be connected to the 3.3V rail via a pull-up.
4. Each switch input shall be pulled down to prevent unintended activation when the Beaglebone pin is in a high-Z state.
5. Each channel shall have a current monitoring circuit arranged so that the output is 1.65 V/A.
6. Each channel shall have status LEDs indicating both active (green) and fault (red) conditions for each channel
7. Each power output shall have clamp/flyback diodes.

#### Motor Controls

1. Controlling the motor requires driving six automotive relays. These relays shall be numbered 0-5 and connected to a standard 9-pin D-subminiature plug as the output.
2. This connector shall be labeled as Motor Control Relays or similar legend.
3. These lines shall pass out of the main drybox via a seven pin SP-13 connector and enter the motor control box through the existing pair of 4-pin M12 connectors.
4. Assignment of each motor control relay to its end function shall be controlled by software.

|  |  |  |  |
| --- | --- | --- | --- |
| Relay Channel | Drive Pin | Fault Pin | ADC Channel |
| 0 | P8.3 | P8.4 | U18, ch 0 |
| 1 | P8.5 | P8.6 | U18, ch 1 |
| 2 | P8.7 | P8.8 | U18, ch 2 |
| 3 | P8.9 | P8.10 | U18, ch 3 |
| 4 | P8.11 | P8.12 | U18, ch 4 |
| 5 | P8.13 | P8.14 | U18, ch 5 |

#### Horn

1. One channel shall be dedicated to driving the horn relay, and shall be named as such.
2. It shall use a single 2-pin C-GRID SL connection on the board, running to a 2-pin SP-13 connector in the box.
3. The horn drive relay shall be connected to this connector, and it shall switch main battery power through the horn mechanism.

|  |  |  |  |
| --- | --- | --- | --- |
| Relay Channel | Drive Pin | Fault Pin | ADC Channel |
| Horn | P8.17 | P8.18 | U19, ch 0 |

#### Enable/Disarm

1. There shall be two relays devoted to switching the enable/disarm latching relay – one to enable and one to disarm.
2. The disarm relay shall allow the Beaglebone software to disarm the boat in response to shore command or conditions other than someone pressing the emergency stop button.
3. The enable relay shall allow the Beaglebone to arm the boat without someone pressing the external go button. This allows the boat to re-arm itself when conditions are right and there are no humans available, as for example in the deep ocean.
4. The arm function shall be arranged so it can be controlled by making or breaking a solder jumper on the board.
5. See the Enable/Disarm Interface, below, for more information on the behavior of these relays.

|  |  |  |  |
| --- | --- | --- | --- |
| Relay Channel | Drive Pin | Fault Pin | ADC Channel |
| Enable | P8.24 | P8.26 | U18, ch 7 |
| Disarm | P8.15 | P8.16 | U18, ch 6 |

### R/C Receiver

1. The S-BUS signal from the R/C receiver is serial signal at 100 kbps, 8 data bits, 2 stop bits, and even parity (8e2). It is also inverted relative to the TTL serial standard (i.e. active high rather than the standard active low). The RC receiver also requires power from the 3-pin serial signal connector.
2. The external connectors shall be a pair of 3-pin CGRID SL connectors. Pin 1 shall be ground, Pin 2 shall be +5V, and Pin 3 shall be signal. A power decoupling cap shall be provided.
3. The signal input line shall be protected against voltage and current excursions with a 1K series resistor and a 5V Zener diode to ground.
4. To invert and shift the level from 5V to 3.3V, the signal shall be run through an open drain inverting buffer with the output pulled up to the 3.3V.
5. Due to a shortage of serial interfaces, it shall be possible to connect the R/C receiver via solder jumper to either the GNSS or the Fona Module serial interface. This is acceptable because in the case that the Fona is installed, the GNSS is superfluous. Since the R/C interface is one way, only the receive line may be connected.

### GNSS

1. The GNSS shall be an Adafruit Ultimate GPS Breakout (https://www.adafruit.com/products/746) or pin-compatible equivalent.
2. The main board shall have mounting holes for a compatible header and the two corner mounting holes.
3. The mounting holes on the PCB shall be grounded.
4. The corner mounting holes shall be secured to the board with appropriate conductive standoffs.
5. The Vin connection shall be connected to the main 5V rail. The RX and TX lines shall be connected to UART4. The Fix pin shall be connected to the Beaglebone at P9.15. The Enable line shall be connected to the Beaglebone at P9.12.
6. No protection or level shifting shall be required.

### Fona Module

1. The Fona module is an optional ship to shore interface. If installed, it shall be an Adafruit Fona 3G (<https://www.adafruit.com/products/3147>) or equivalent.
2. The main board shall have mounting holes for a compatible header and the two corner mounting holes.
3. The mounting holes on the PCB shall be grounded.
4. The corner mounting holes shall be secured to the board with appropriate conductive standoffs.
5. The serial interface shall be connected to UART5 and VIO to 3.3V. Other connections shall be as convenient. No level shifting shall be required for this module.
6. Note that this module has been rendered redundant by the 3G cell hotspot described in Ship to Shore Transceiver.

### ADC subsystem

1. One channel of the Beaglebone’s internal ADC, channel 1, shall be used to sense the Battery Monitor.
2. All other analog inputs shall be via a pair of ADC128D818 8-channel ADCs on a common I2C bus. They shall be powered from the 5V bus to give a 0-5V input range. Doing so requires level shifting the I2C bus; level shifting shall be provided by a single TXS0102 bi-directional level shifter.
3. The I2C lines shall be pulled up to their respective voltages by 4.7K resistors.
4. The 3.3V I2C bus shall be connected to I2C-2.
5. Each input line shall be filtered by an RC filter consisting of a 10K series resistor and a 22 nF parallel capacitor. No protection beyond the filters described above shall be provided for these signals.
6. Channels 1-6 of U19 shall be brought out to the Power Mon connector. This connector shall be a 2x6 0.1” pitch pin header. It is intended to bring in current and voltage sense signals from the motor and charge current/voltage monitors as well as powering those sensors.
7. Three pins shall be connected to +5V and three shall be connected to ground.
8. The other six shall be designated for motor current, motor voltage, charge current, charge voltage, and auxiliary ADC channels 0 and 1.

### Auxiliary GPIO

1. Eight I/O pins level shifted to 5V shall be provided on the Auxiliary GPIO connector. This shall be a 2x6 0.1” pitch pin header. Two pins shall be +5V and two shall be grounded.
2. Two of the pins shall carry the 5V I2C bus provided for the ADC subsystem. Three shall carry the SPI1 bus, and may optionally be used as GPIOs.
3. The remaining three shall be available as plain GPIOs.
4. In the case of the non-I2C pins, they shall be level shifted through a TXB0108 level shifter. This part shall provide all the available I/O protection to these pins.

### RS-485

1. The RS-485 interface is intended for future peripheral expansions, including a more advanced motor controller architecture.
2. The RS-485 transceiver chip shall be a half-duplex unit connected to UART1 through one of the onboard TXB0108 level shifters.
3. The direction line shall be similarly level shifted and shall be controlled from pin P9.14.
4. The PCB connector shall be a 3-pin CGRID SL with the following pinout. Pin 1 shall be line B, Pin 2 shall be line A, and Pin 3 shall be ground.

### Steering

1. The PWM channel for the steering shall be EHRPWM1A on pin P9.16.
2. It shall be level shifted to 5V through one of the onboard TXB0108 level shifters.
3. The 5V output line shall be protected by a 1K series resistor and a 5V Zener diode to ground.
4. The PCB connector shall be a 3-pin CGRID SL with the following pinout. Pin 1 shall be power (7.4V), Pin 2 shall be the PWM output signal, and Pin 3 shall be ground.

### Lights

1. The exact nature of the lighting interface is still in flux due to difficulties with the interface code.
2. The connector is a 3-pin CGRID SL with Pin 1 connected to the lighting +5V, Pin 2 connected to P9.22 via one of the TXB0108 level shifters, and Pin 3 connected to ground.
3. The signal pin shall be protected with a 1K series resistor and a 5V Zener to ground.

### Reset

1. The reset line into the Beaglebone is active low, and is provided with a 10K pullup to keep it inactive except as commanded. The external drive is intended to be a hall effect sensor mounted to the interior wall of the drybox, allowing the user to reset the Beaglebone with a small magnet.
2. Therefore, the sensor shall be provided with 5V and ground lines.
3. The signal line shall be high when the hall effect switch is active.
4. The signal shall be run through an inverting buffer and then a level shifter to produce the required active low 3.3V signal at the Beaglebone.
5. The PCB connector shall be a 3-pin CGRID SL with Pin 1 connected to the lighting +5V, Pin 2 connected to the reset line as described above, and Pin 3 connected to ground.
6. The signal pin shall be protected with a 1K series resistor and a 5V Zener to ground.

### Console

1. The console connector shall bring the receive and transmit lines of the Beaglebone serial console out to a PCB connector.
2. It shall be a 4-pin CGRID SL with Pin 1 NC, Pin 2 connected to RX, Pin 3 connected to TX, and Pin 4 connected to ground.
3. The RX and TX lines shall be protected with a 1K series resistor and a 5V Zener to ground, each.

### Enable/Disarm Interface

1. The enable/disarm interface provides a connection to the enable/disarm relay in the power distribution box.
2. This interface shall consist of an incoming enable signal, an incoming disarm signal, and outgoing relay drivers for enable and disarm.
3. Each of the two inputs shall be protected by a 1K series resistor and a 5V Zener diode to ground.
4. The enable relay driver shall be connected if and only if solder jumper SJ2 is connected.
5. A high (5V) signal on the enable line shall be required to activate the servo power.
6. Incoming enable and disarm signals shall be level shifted from 5V to 3.3V through one of the onboard TXB0108 level shifters.
7. The enable input to the Beaglebone shall be on pin P8.20 and the disarm input shall be on pin P8.22.
8. The PCB connector shall be a 5-pin CGRID SL. Pin 1 shall be connected to the input enable signal, Pin 2 to the input disarm signal, Pin 3 to ground, Pin 4 to the disarm relay output, and Pin 5 to the enable relay output.

### PoE Interface

1. The PoE interface shall consist of a pair of unshielded RJ45 connectors back to back. The LAN connector is intended to connect directly to the Beaglebone. The Device connector is intended to be connected to the Ubiquiti gear.
2. Pins 1-3 and 6 shall be directly connected between the two connectors.
3. Pins 4 and 5 on the Device connector shall be connected to the +15V PoE rail. The corresponding pins on the LAN side shall be unconnected.
4. Pins 7 and 8 of the Device connector shall be grounded. The corresponding pins on the LAN side shall be unconnected.

## Main Drybox Peripherals

The main drybox has room for several peripherals above and beyond the main board. The ones intended for current or near future installation but not previously discussed are described here.

### AIS Receiver

1. The AIS receiver shall be a dAISy unit. It shall be connected and powered through the Beaglebone’s USB host port (and optionally, a USB hub).
2. The antenna connection shall be a bulkhead BNC in the outside of the drybox.
3. The antenna shall be mounted as high as practicable.

### WiFi

1. There shall be two WiFi options – USB dongle and Ubiquiti. One and only one shall be installed.

#### USB Dongle

1. A standard USB WiFi dongle may be used to provide WiFi connectivity. If used with the AIS, it shall be plugged into an appropriate USB hub.

#### Ubiquiti

1. A Ubquiti Nanostation may be used to provide WiFi connectivity.
2. If used, it shall be powered through the PoE interface and plugged from there into the Beaglebone.

### Ship to Shore Transceiver

1. The ship to shore transceiver shall present a WiFi hotspot that the Beaglebone and any additional equipment may connect to.

#### Current

1. The current ship to shore transceiver shall be a portable 3G cell hot spot. This shall be used for all in-shore work due to its high bandwidth, reliability, and low cost.

#### Future

1. For off-shore work, the ship to shore transceiver shall be an Iridium GO or equivalent system.

## Power Distribution Box

The power distribution box provides a common distribution and control point for all power systems on the boat. It also maintains the enable/disarm state through a two-coil latching relay.

### Board Power

1. At all times when the battery is connected, the power distribution board shall draw power from the power input through a 5V linear regulator.
2. This regulator must be able to handle input voltages from 9VDC to 20VDC.

### Enable/Disarm Relay

1. The enable/disarm relay shall be a DPDT mechanical relay of the two-coil latching type. The drive for each coil shall be a wire-OR of the relay drive from the main board and a local relay driver activated by either the Enable or Stop button Time Delay Circuits.
2. The enable output signal shall be connected such that when the relay’s SET coil is energized, it will be connected to +12V and to ground when the RESET coil is energized.
3. The disarm output signal shall be wired with the opposite sense.
4. The +12V enable and disarm signals shall be regulated down to +5V with a 1K series resistor and a 5V Zener to ground.
5. The PCB connector for the connection to the main board shall be wired identically to the connector on the main board, as described in Enable/Disarm Interface.

### Enable and Stop Buttons

1. The Enable and Stop buttons shall be momentary SPDT pushbuttons sealed to IP67 or better and mounted on the outside hull.
2. They shall be given large, obvious actuators – red for stop and green for enable.
3. Both switches shall be wired so that their output signal is normally high.
4. On the PCB, each switch shall be wired to a 3-pin CGRID SL connector. Pin 1 is +5V, Pin 2 is signal, and Pin 3 is ground.
5. The signal pin shall be protected by a 1K series resistor and clamp diodes

### Time Delay Circuits

1. To prevent inappropriate activation of the Enable and Stop buttons, each shall drive its respective relay coil through a time delay circuit.
2. The time delay circuits shall be one-shots based around the two sides of a 556 dual timer chip. The output of each one-shot and its corresponding input signal shall be NOR’d together to produce an outgoing high pulse after the time delay.
3. These high pulses shall trigger the relay drivers to strobe the corresponding relay coil.
4. The trigger signal for each channel shall be fed forward through an RC low pass network consisting of a 10K resistor and a 1 uF capacitor. This is to ensure that the fed-forward signal remains high until the timer output signal has gone high.

#### Arm Button

1. The delay elements of the arm button shall be a 470K resistor and a 10 uF capacitor, giving a time delay of approximately 5.2 seconds.
2. The input shall be pulled up by a 10K resistor so that if the switch is disconnected, the Arm function will not activate.

#### Stop Button

1. The delay elements of the arm button shall be a 470K resistor and a 2.2 uF capacitor, giving a time delay of approximately 1.1 seconds.
2. The input shall be pulled down by a 1M resistor so that if the switch is disconnected, the Stop function will activate.

### Switch Controlled Circuits

1. The mechanical switches on the face of the power distribution box shall be SPDT, IP 67 or better, and must be rated for at least 6A and 20VDC.

#### Control Power

1. This switch shall control power to the main drybox.
2. If it is off, power shall not flow to the main drybox.

#### Horn Power

1. This switch shall control power to the horn, allowing it to be turned off during software testing and similar activities.

#### Auxiliary Power 1

1. This switch shall control power to auxiliary power circuit 1.

#### Auxiliary Power 2

1. This switch shall control power to auxiliary power circuit 2.

### Relay Controlled Circuits

1. Switches for the relay controlled circuits shall switch the coil of an automotive relay rated for at least 30A.

#### Main Power

1. This relay shall control power to all other relays and switches.
2. When it is in the off position, power must not flow to any system other than the power distribution box’s internal circuitry.

#### Motor

1. The motor relay switch shall draw power from the Enable coming from the Enable/Disarm relay.
2. Therefore, if the stop button is pushed, all power flowing to the motor must be cut.

## Motor Control Box

The motor control box shall contain seven SPDT automotive relays to switch the four motor wires to control motor direction and speed.

### Motor Outputs

1. The four motor wires shall be designated by color – red, white, yellow, and black.
2. In forward operation, black shall be connected to ground and the other three lines shall be connected to power and each other in different combinations to produce the five forward speeds.
3. In reverse operation, the polarity shall be flipped.
4. The input power lines shall be +12V (nominal) and ground.
5. A 30A hall effect current and voltage monitor shall be placed in series with the power line and wired back to the main control box.

### Relay Functions

#### Direction

1. Two relays shall control the direction. Their coils shall be wired in series.
2. Their output sides shall be wired such that when their coils are not energized, +12V (nominal) shall be supplied to the motor box’s positive rail and ground shall be connected to the negative rail.
3. When they are energized, the polarity of the output rails shall be flipped.

#### Red

1. When energized, this relay shall connect the red output to the motor box’s positive rail.
2. When not energized, it shall have no effect.

#### White

1. When energized, this relay shall connect the white output to the motor box’s positive rail.
2. When not energized, it shall have no effect.

#### Yellow

1. When energized, this relay shall connect the yellow output to the motor box’s positive rail.
2. When not energized, it shall have no effect.

#### Yellow-White

1. When energized, this relay shall connect the yellow output to the white output.
2. When not energized, it shall have no effect.

#### Red-White

1. When energized, this relay shall connect the red output to the white output.
2. When not energized, it shall have no effect.

### State Map

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Speed | Direction | Red | Yellow | White | Red-White | Yellow-White |
| F5 | Off | On | On | On | On | On |
| F4 | Off | Off | On | Off | On | Off |
| F3 | Off | Off | On | On | Off | Off |
| F2 | Off | Off | Off | On | Off | On |
| F1 | Off | Off | Off | On | Off | Off |
| Stop | Off | Off | Off | Off | Off | Off |
| R1 | On | Off | Off | On | Off | Off |
| R2 | On | Off | Off | On | Off | On |
| R3 | On | Off | On | On | Off | Off |
| R4 | On | Off | On | Off | On | Off |
| R5 | On | On | On | On | On | On |

# Software Architecture

The onboard software shall be written in C/C++ and shall run on the Beaglebone Black.

## Hardware Interfaces

1. The Beaglebone Black provides a great variety of hardware interfaces natively. Therefore, most of the interface circuitry is I/O protection, with a bit of glue logic and some high current drivers. There are also sixteen external ADC channels.

### Hardware Abstraction Layer

1. The hardware abstraction layer (HAL) shall provide a mechanism for abstracting the physical interfaces such that they can be modified at need without disturbing the rest of the code base.
2. In the case of inputs that are asynchronous with the main thread of execution, the HAL shall spawn a thread to handle the incoming data and store it as appropriate for the consumption of the main code.

#### Orientation

1. Orientation data shall come from the IMU at a rate of approximately 100 Hz. The raw data shall be in the form of three axis accelerations, three axis magnetometer readings, and three axis rotation rates. Data shall be read and processed by an OrientationInput object which encapsulates the hardware interface and reader thread. It shall present the data to the rest of the program as a pointer to its internal Orientation object. The Orientation object will, at minimum, have pitch, roll, and heading members.
2. While a full orientation solution would be nice to have, the only truly critical data coming from the IMU is heading. The pitch, roll, and heading shall be around the north, east, and down axes. Heading shall be measured in clockwise degrees from north. Pitch shall be measured in degrees from horizontal, with nose-up pitch positive. Roll shall be measured in degrees from horizontal, with starboard rail down positive. The pitch and roll shall be calculated as follows:
3. These pitch and roll values shall be calculated using the atan2() function to remove angular ambiguity.
4. The heading shall be calculated with the following formula:[[1]](#footnote-1)
5. Future implementations may use a Madgwick and Mahoney algorithm to determine orientation instead.

#### R/C receiver

1. The RCInput object shall be the interface between program logic and the the incoming serial data. It shall spawn a thread that listens to the incoming serial data, parses it, and stores it locally for later retrieval.
2. The data from the R/C receiver is packed into twenty-five (25) byte frames. The first byte of each frame is always 0x0f. The next 22 bytes (second byte through twenty-third byte) contain input data channels 0 - 15. Each channel is 11 bits wide, and they are close packed with no spacing. Channels 16 and 17 occupy the first two bits of the twenty-fourth byte. The fourth bit of the twenty-fourth byte is the failsafe bit – if it is set, then the R/C receiver is no longer receiving data from the transmitter. The last byte is the end byte, and it is always 0x00.
3. The RCInput object shall store all eighteen channels as a vector of uint16\_t ranging between 0 and 2047. It shall be possible for other code to query the value of any desired channel at any time. The values of channels 16 and 17 shall be either 0 or 2047, depending on whether the corresponding bits are cleared or set.
4. The status of the failsafe function shall be stored as a bool and shall be queriable from user code.
5. The RCInput object shall monitors its incoming datastream. If the datastream ceases or becomes corrupted, the RCInput object shall return false in response to the isValid() method. Otherwise, this method shall return true.
6. The RCInput object shall have the following methods to interpret specific channels:

* getThrottle() shall map channel 0 to an int between -5 and 5
* getRudder() shall map channel 3 to a double between -100 and 100
* getMode() shall return FAILSAFE if isFailSafe() returns true. Otherwise, it shall return RUDDER if channel 4 is far below the midpoint, COURSE is it far above, and IDLE if it is near the midpoint. Note that this corresponds to the three-position switch on the controller.
* getCourse() shall map channel 6 to a double between 0 and 360.

#### GNSS & AIS Input

1. Both the GNSS are AIS inputs shall be processed externally by gpsd. This delivered both data streams as a series of JSON messages on a TCP port. The gpsd package provides a command line utility, gpspipe, that connects a given gpsd server instance to the command line. The GPSdInput object shall use gpspipe to receive the data and the pstreams library to manipulate the incoming stream from program code.
2. The GPSdInput object shall have a set of methods to connect, disconnect, set the host and port, and test whether the connection is good. It shall spawn a listener thread to receive GPS and AIS data and expose that data to the rest of the program.
3. As each JSON message is received, the GPSdInput object shall check if it is a GPS or AIS message. It shall then create an object of the appropriate type, and call the parse() method of that object against the incoming message. If it fails, both the new object and the message are discarded.
4. If the incoming message is a GPS message and is successfully parsed, it shall be copied to a private GPSFix object. A pointer to this internal object shall be returned by the getFix() method.
5. If the incoming message is an AIS message, it shall be compared with the internally stored map of AIS contacts. If it has the same MMSI number as an existing contact, the fields of the incoming that are present shall be copied into the existing AIS contact and the last contact time shall be set to the current time.
6. There shall be a method to prune the AIS map for stale contacts and contacts that are too far distant to have an impact on the boat.

#### Rudder (Servo)

1. R/C servos are controlled with a PWM scheme running at between 50 and 100 Hz. The positive pulse is nominally between 1000 and 2000 µsec long but can range from 600 to 2400 µsec. 1500 µsec is the nominal midpoint.
2. The PWM peripheral on the Beaglebone is controlled by writing values to the appropriate values and hooking the peripheral up with the internal pinmux. The appropriate pinmux shall be configured using the config-pin script.
3. The input shall be accepted as either a raw µsec value or as a mapped value from -100 to 100.
4. The Servo object shall handle all interface with the files required to drive the PWM peripheral.

#### Throttle

1. The Throttle object shall drive the motor control relays to translate a given throttle command into the outputs required to get that speed from the motor. See Motor Control Box for more details on the relay functions.

#### Analog Input

1. The ADCInput object shall use a listener thread to read from the battery monitor (internal ADC) and external ADCs at a rate of at least 100 Hz. The resulting data will be available as either raw codes (0-4095) or as scaled values. The channels shall be callable by descriptive names; the relation to physical channels shall be set at object construction from a configuration file.
2. The calling code shall be able to set any number of offsets or gains independently. When a new value is sampled, the scaled value shall be calculated by adding the offset and multiplying by the gain, in that order.

#### GPIO

1. The Pin object shall present an interface to any given GPIO pin. It shall handle the pinmux configuration through the config-pin script and reading/writing the appropriate configuration and value files in /sys/class/gpio/gpio\*\*. The Pin object shall include methods for translating between different representations of the same gpio pin.
2. The Pin object shall be created pointed at a specific pin. The pin shall be defined by the connecter (either 8 or 9) and pin (1-46) on that connector. The object shall contain methods to set the direction (true for output, false for input), writing, and reading the pin. The readPin() method shall return 1 for high, 0 for low, and -1 for any read error. The object shall also contain methods for setting the internal pullup and pulldowns. Changes to pin configuration (direction, pull up/down, etc) shall require a call to the init() method to take effect.

#### Relays

1. The Relay module shall consist of two classes – a Relay class for describing a single relay and a RelayMap singleton for providing access to named relays from program code. The module shall also contain a typedef for a RelayTuple.

##### RelayTuple

1. A RelayTuple shall be of type std::tuple<double, bool, bool> where the elements represent the current in amps, the drive state of the relay (true = on), and the fault state of the relay (faulted = true), respectively.

##### Relay

1. A Relay object shall encapsulate a name (type std::string), a pointer to a drive Pin, and a pointer to a fault Pin. It shall also contain a pointer to an ADCInput object that contains a channel of the same name as the relay to provide current feedback.
2. The object shall contain methods to turn the target relay on and off, check the current, check for fault states, and return the current state of the relay as a tuple.

##### RelayMap

1. The RelayMap singleton shall contain a named map of Relay objects and shall use a hard-coded initializer defined in a system level configuration file. It shall have a function that returns a pointer to the Relay object associated with a given name.

#### Test Harness

1. To ease unit and integration testing of the HAL code and code that depends on it, all HAL classes shall declare HalTestHarness as a friend. This requires a forward declaration of HalTestHarness.
2. Each HAL class that requires test harnessing shall be represented by a method in the test harness class. This method shall provide an interface to extract mutable pointers to each private member of the target class required to provide test functionality.
3. The accessADC() method shall take a pointer to the target ADCInput object, a pointer to a pointer of type map<string, int> to represent the raw values, and a pointer to a pointer of type bool to represent whether the data is valid. The referenced pointers shall be directed to the \_raw and inputsValid private members of ADCInput, respectively.
4. The accessGPSd() method shall take a pointer to the target GPSdInput object, a pointer to a pointer of type GPSFix, and a pointer to a pointer of type map<int, AISShip>. The referenced pointers shall be directed to the \_lastFix and \_aisTargets private members of the given GPSdInput object, respectively.
5. The accessOrientation() method shall take a point to the target OrientationInput object, a pointer to a pointer of type Orientation, and a pointer to a pointer of type bool. The referenced pointers shall be directed to the \_current and sensorsValid members of the given OrientationInput object, respectively.
6. The accessRC method shall provide access to the following members of the given RCInput object:
   * \_throttle
   * \_rudder
   * failsafe
   * \_valid
   * rawChannels
   * inbuf
   * \_errorFrames
   * \_goodFrames
7. The accessRelay() method shall provide access to the drive and fault Pin objects of the given relay.
8. The initGPIOTest() method inverts the OS level direction of the GPIO referred to by the given Pin object and currently set as an input.
9. The writeGPIOTest() method shall write a new value to a Pin set as an input and previously modified with initGPIOTest().
10. The readGPIOTest() method shall read the current value of a Pin set as an output.

### Ship to Shore Communications

1. From the perspective of the Beaglebone, ship to shore communications shall be over a WiFi link. It must be agnostic to the exact nature of the ship to shore link, so that an Iridium Go may be substituted for a cell hotspot with no code changes.
2. The protocol used shall be MQTT. The default message broker for now shall be Adafruit.io. Connections shall be via SSL if possible.[[2]](#footnote-2)
3. Payloads may be JSON, CSV, or plain values, as noted per topic. All numeric values shall be double precision floats unless otherwise noted. The MQTT wrapper class shall provide methods to iterate through a list of publisher functions.
4. The MQTT object shall subscribe to the listed subscription topics on startup. Incoming commands shall be pushed to the command queue described in BoatState.

#### Topics Published by the Boat

|  |  |  |  |
| --- | --- | --- | --- |
| Topic Name | Format | Data | |
| SpeedLocation | CSV | | <speed, knots>,<lat, degrees>,<lon, degrees>,0 |
| Mode | CSV | | <boat mode>,<nav mode>,<auto mode>,<rc mode> |
| Bearing | Plain | | Current heading, degrees from magnetic north |
| BatteryVoltage | Plain | | battery voltage |
| RudderPostion | Plain | | rudder position, -100 to 100 |
| ThrottlePosition | Plain | | Throttle position, -5 to 5 |
| RudderK | JSON | | {“Kp”:<proportional>,”Ki”:<integral>,”Kd”:<differential>} |
| Course | Plain | | Course made good, degrees true |
| Health[[3]](#footnote-3) | JSON | | Packed JSON of HealthMonitor object |

#### Topics Subscribed to by the Boat

|  |  |  |  |
| --- | --- | --- | --- |
| Topic Name | Format | Data | |
| Command | JSON | | {“Command”:<function name>,”Arguments”:<args>} |

## Software Modules

1. This section covers the program logic, both core and supporting.
2. The main program shall run in timed frames at a rate of 50 ms per frame (20 Hz)
3. At the start of each frame, the code shall read all sensors.
4. The code shall then execute the current mode of the state machine.
5. Lastly, the code shall write to any outputs not written by the mode logic.

### Data Types

#### HackerboatState

1. All the custom datatypes shall be subclasses of the HackerboatState abstract base class. It shall define the following virtual methods:

|  |  |  |  |
| --- | --- | --- | --- |
| Method | Arguments | Returns | Description |
| parse | json\_t\* | bool; true on success | Populate this object from the given JSON |
| pack | void | json\_t\* | Serialize this object into JSON |
| isValid | void | bool; true if object is valid. | Determine whether the current object is in a valid state. |

1. The class shall define a public member recordTime, which shall be a timepoint as defined in the <chrono> library.
2. The class shall define two static utility methods, parseTime() and packTime(). These act as wrappers for the date library and provide a uniform conversion between timepoints and string representations of timestamps.

#### HackerboatStateStorable

1. The HackerboatStorable class shall bn abstracte a subclass of the Hackerboat class that provides a common interface for those datatypes that require database storage and retrieval.
2. The HackerboatStateStorable class shall define a new type, sequence, as an alias of int64\_t. This shall be used to store a monotonic sequence number in a protected data member. The sequence number shall increment each time this object is written to the database. There shall be a public method that returns the sequence number.
3. The class shall contain the following non-virtual but overloadable public methods:

|  |  |  |  |
| --- | --- | --- | --- |
| Method | Arguments | Returns | Description |
| countRecords | void | sequence | Returns number of rows in the corresponding database table. |
| writeRecord | void | bool (true if successful) | Write the contents of the current object to the corresponding database row, if it exists. |
| getRecord | sequence | bool (true if successful) | Populate the current object with the contents of the database row specified. |
| getLastRecord | void | bool (true if successful) | Populate the current object with the contents of the most recent row. |
| appendRecord | void | bool (true if successful) | Append the contents of the current object as the last row in the database. |

1. Each subclass must implement a storage() method that returns a handle to the database table corresponding to that subclass in the form of a reference to a HackerboatStateStorage object.
2. Each subclass may implement fillRow() and readFromRow() to write and read rows from the database table associated with this object. If either is implemented, both must be implemented. They shall default to writing and reading the sequence number and a text string containing the JSON representation of the object produced by the pack() method.

#### HackerboatStateStorage

1. A HackerboatStateStorage object shall encapsulate a reference to a table in a SQLite3 database file. It shall further contain prepared statements and methods for implementing all the methods described in HackerboatStateStorable .

#### Enumerations

1. The code shall use enumerations to represent values that can only take a limited number of named values.
2. All enums shall be of the type enum class.

##### BoatModeEnum

1. This enumeration shall contain the names of all the top-level modes of the boat. See Control Modes for more detail.

##### NavModeEnum

1. This enumeration shall contain the names of all the navigation modes of the boat. See Control Modes for more detail.

##### AutoModeEnum

1. This enumeration shall contain the names of all the autonomous modes of the boat. See Control Modes for more detail.

##### RCModeEnum

1. This enumeration shall contain the names of all the R/C modes of the boat. See Control Modes for more detail.

##### WaypointActionEnum

1. This enumeration shall contain the action that the Waypoint Navigation module takes when it reaches the end of the list of waypoints.

|  |  |  |
| --- | --- | --- |
| Action Name | Enum Name | Description |
| Idle | IDLE | Boat stops and does nothing – Navigation mode goes to Idle. |
| Anchor | ANCHOR | Hold position at the last waypoint. |
| Return | RETURN | Return to the origin point and hold position once there. |
| Repeat | REPEAT | Repeat the list of waypoints, starting with the first. |
| None | NONE | This is effectively the default uninitialized state. Functionally equivalent to Idle. |

#### EnumTable

1. To produce human-readable JSON, each enum shall be paired with a vector of strings corresponding to the names of the enum elements.
2. EnumTable shall have a public method which determines whether a given string names an element of the enum.
3. EnumTable shall have public methods allowing the user to get the string given the enum value or the enum value given the string.
4. The string values shall be defined in BoatState.

#### Timestamps

1. Timestamps shall conform to ISO8601 and shall have a precision of milliseconds or better. This shall be accomplished using Howard Hinnant’s date library.

#### BoatState

1. BoatState is intended to be a full log of the status of the boat, and therefore shall store the value of, or pointers to, information about every major subsystem. The intent is that a pointer to it can be passed to each mode object in the State Machine and provide the mode execute() methods with all the hooks required to control the boat.
2. BoatState shall be a subclass of HackerboatStateStorable.
3. BoatState shall maintain a colon separated list of current faults with boat systems. It shall provide methods to add faults, remove faults, clear the fault string, and count the number of entries it contains.
4. BoatState shall maintain a reference to the current state of each layer of the state machine, and shall have public accessors for this data.
5. BoatState shall have a queue for storing incoming commands from the ship to shore link. It shall be able to execute any number of queue elements from a single method call. It shall also have methods for clearing the queue and adding new members.
6. BoatState shall have a method for serializing its data as a CSV string.
7. BoatState shall have a member of type Waypoint that stores the list of waypoints as described in Waypoint Navigation. It shall also store the number of the current waypoint and the action to take when the last waypoint in the list is reached.
8. BoatState shall store the timepoints at which it last received data from the ship to shore link and from the R/C receiver.
9. BoatState shall maintain the location from which it launched.
10. BoatState shall maintain a pointer to the Health Monitoring subsystem.
11. BoatState shall maintain a copy of the last GPS fix.
12. BoatState shall maintain pointers to the Servo, Throttle, RCInput, ADCInput, GPSdInput, OrientationInput, and RelayMap subsystems.
13. BoatState shall maintain Pin objects for the Enable and Disarm inputs.
14. BoatState shall maintain a Pin object for the servo enable pin.

#### Command

1. The Command class is intended as a storage container for commands received on the command topic from the shore side MQTT broker.
2. A Command object shall be built with a pointer to the current BoatState (to allow it to act), the name of the command, and a json\_t\* pointer to the arguments.
3. The Command class shall have an execute() method that calls the current command. It shall take an argument indicating the number of commands from the queue to execute. It shall return the number of commands successfully executed (i.e. returning true).
4. All commands shall be implemented as private static methods of the Command class.

##### SetMode

1. This function shall request the desired boat level mode for the next iteration of the state machine. It is up to the current mode implementation whether this causes the mode to transition or not.
2. The argument JSON object shall consist of a single key named “mode”. The value of mode shall be the string name of the desired mode.

##### SetNavMode

1. This function shall request the desired navigation level mode for the next iteration of the state machine. It is up to the current mode implementation whether this causes the mode to transition or not.
2. The argument JSON object shall consist of a single member key “mode”. The value of mode shall be the string name of the desired mode.

##### SetAutoMode

1. This function shall request the desired autonomous level mode for the next iteration of the state machine. It is up to the current mode implementation whether this causes the mode to transition or not.
2. The argument JSON object shall consist of a single key named “mode”. The value of mode shall be the string name of the desired mode.

##### SetHome

1. If this function is called with no arguments, it sets the home point to the last GPS fix received.
2. This function may be called with the argument “location”. If this key contains the JSON representation of a valid Location object, the home point shall be set to the given location.

##### ReverseShell

1. This function shall open a reverse shell connection to allow fine grained control, configuration, and modification of the Beaglebone Black over the ship to shore link.
2. This function has not yet been implemented. Options include SSH over Pagekite and MOSH.

##### SetWaypoint

1. This function shall set the target waypoint number.
2. The argument shall be a single key named “number” with the value of the desired waypoint.
3. It shall check to make sure the desired waypoint exists. If it is greater than the number of waypoints, it shall set the target waypoint to the last waypoint. If it is less than zero, it shall set the current waypoint to the first waypoint.

##### SetWaypointAction

1. This function shall set the action that the boat takes on reaching the last waypoint in the list.
2. The argument JSON object shall contain a single key, “action”. Its value shall be a string representing one of the possible values of WaypointActionEnum.
3. If the argument does not contain the “action” key or the value of the key is not a valid value of WaypointActionEnum, this function does nothing and returns false.

##### DumpPathKML

1. This function shall dump a KML file containing a LineString object describing the course of the boat to date to the given web address.
2. This function is not yet implemented.

##### DumpWaypointKML

1. This function shall dump a KML file containing the waypoint list to the given web address.
2. This function is not yet implemented.

##### DumpObstacleKML

1. This function shall dump a KML file containing all obstacles known to the boat at the current time to the given web address.
2. This function is not yet implemented.

##### DumpAIS

1. This function shall dump a JSON representation of the current AIS database to the given web address.
2. This function is not yet implemented.

##### FetchWaypoints

1. This function shall fetch a new waypoint KML file from either a hard-coded default location or the given web address.
2. This function is not yet implemented. This function imposes substantial security risks and must be carefully considered before implementation.

##### PushPath

1. This is a duplicate of DumpPathKML and should be deleted.

##### SetPID

1. This function allows remote setting the rudder PID proportional, integral, and differential gains.
2. The argument JSON object may contain any combination of the keys “Kp”, “Ki”, and “Kd”, representing the proportional, integral, and differential gains, respectively.
3. The value of these keys shall be interpreted as double precision floating point numbers and written to the appropriate location in the BoatState object passed to this function.

#### HealthMonitor

1. The HealthMonitor class is intended to bring all vehicle health monitoring data into a single object, easing data acquisition, scanning, and logging.
2. HealthMonitor shall be a subclass of HackerboatStateStorable.
3. The object shall maintain a pointer to an ADCInput object used to read the incoming sensors.
4. It shall implement a single function readHealth() that populates the object with the system health data from around the boat.
5. The object shall gather and store the following vehicle health data:
   1. Servo current
   2. Battery Voltage (measured at control board)
   3. Main Battery Voltage
   4. Main Battery Current
   5. Charge Voltage
   6. Charge Current
   7. Motor Voltage
   8. Motor Current
   9. R/C RSSI value
   10. Cellular/Satellite RSSI value
   11. WiFi RSSI value

#### AIS

1. AIS data shall be received from gpsd as described in GNSS & AIS Input.
2. AIS data shall be in the format described in <http://catb.org/gpsd/gpsd_json.html> and <http://catb.org/gpsd/AIVDM.html>

##### AIS Enums

1. This module shall contain enumerations to describe the Message Type, Navigation Status, Ship Type, and EPFD Type fields described in <http://catb.org/gpsd/AIVDM.html>.

##### AISBase

1. The AIS module shall contain an abstract base class, AISBase. All AIS contact types shall be subclasses of this base class.
2. AISShip shall be a subclass of HackerboatStateStorable.
3. AISBase shall contain a virtual prune() method that, upon calling determine whether the current AIS object ought to be removed from the database.
4. AISBase shall have an MMSI member to store the contact’s identity.
5. AISBase shall contain a member storing the last time at which an AIS message was received from this contact.
6. AISBase shall contain a member storing the last reported location of the contact.

##### AISShip

1. AISShip shall contain a method for parsing the JSON packet delivered by gpsd.
2. AISShip shall be a subclass of AISBase.
3. AISShip shall contain a project() method that estimates the current location of the contact either now or at some timepoint in the future.
4. AISShip shall contain a merge() method that allows two AISShip objects with the same MMSI to be merged. The most recent data will be used when both contain valid values for a member.
5. AISShip shall contain the following public members:

|  |  |  |
| --- | --- | --- |
| Name | Type | Description |
| status | AISNavStatus | The navigation status of the vessel |
| shiptype | AISShipType | The type of vessel |
| epfd | AISEPFDType | The type of EPFD mounted by the vessel |
| turn | double | Rate of turn of the vessel in degrees per min |
| speed | double | Speed of vessel in knots |
| course | double | True course of vessel in degrees from true north. |
| heading | double | Magnetic heading of vessel in degrees from magnetic north. |
| callsign | string | Callsign of vessel |
| shipname | string | Name of vessel |
| imo | int | IMO number of vessel |
| to\_bow | int | Distance from the GNSS antenna to the bow in meters |
| to\_stern | int | Distance from the GNSS antenna to the stern in meters |
| to\_port | int | Distance from the GNSS antenna to the port rail in meters |
| to\_starboard | int | Distance from the GNSS antenna to the starboard rail in meters |

1. The prune() function shall recommend removal of this contact when any of the following conditions are met:
   1. No signal from the contact has been received in AIS\_MAX\_TIME (defined in config.h)
   2. The contact is farther away than AIS\_MAX\_DISTANCE (defined in config.h)
2. When called, the prune() function shall remove the corresponding row from the database.

#### GPS

1. The GPSFix class shall store the details of each incoming GPS fix from gpsd.
2. GPSFix shall be a subclass of HackerboatStateStorable.
3. GPSFix shall implement a method for parsing the JSON received from gpsd as described in GNSS & AIS Input.
4. The header file containing GPSFix shall contain an enum class called NMEAModeEnum that encodes the fix mode provided with each GPS report from gpsd. Possible values are NONE, NOFIX, FIX2D, and FIX3D.
5. GPSFix shall maintain the following public data members:

|  |  |  |
| --- | --- | --- |
| Name | Type | Description |
| fix | Location | The location of the current fix |
| gpsTime | sysclock | The GPS time of the current fix |
| mode | NMEAModeEnum | The mode of the current fix |
| device | string | Name of the source device (may be excluded if desired) |
| track | double | Course over ground, in degrees from true north |
| speed | double | Speed over ground, in m/s |
| alt | double | Altitude above MSL, in meters |
| climb | double | Rate of climb in m/s. |
| epx | double | Longitude error in meters, 95% confidence |
| epy | double | Latitude error in meters, 95% confidence |
| epd | double | Course error in degrees, 95% confidence |
| eps | double | Speed error in m/s, 95% confidence |
| ept | double | Timestamp error in second, 95% confidence |
| epv | double | Altitude error in meters, 95% confidence |
| epc | double | Climb error in m/s, 95% confidence |
| fixValid | bool | True if this is a valid fix |

#### Orientation

1. The Orientation class shall store the current pitch, heading, and roll of the boat.
2. The Orientation class shall be a subclass of HackerboatState.
3. The Orientation class shall be aware of the difference between true and magnetic headings, and shall have methods to convert between the two.
4. It shall use GeographicLib to calculate magnetic declination. Declination shall be recalculated only on request, because it is time consuming to do so.
5. It shall store pitch, roll, and heading as public data members of type double.
6. Pitch, roll, and heading shall default to NAN.

#### Location

1. The Location class shall provide a mechanism for storing and working with geographic locations.
2. The Location class shall be a subclass of HackerboatState.
3. The Location class shall store lat and lon as public data members of type double.
4. The header containing the Location class shall define CourseTypeEnum, which shall have the possible values of GreatCircle and RhumbLine.
5. All Location methods that calculate geographic relationships shall take a CourseTypeEnum as an argument, with the default value of GreatCircle.
6. All such methods will use GeographicLib to calculate courses and distances.
7. The Location class shall define a method bearing() which calculates the true bearing from the calling Location object to another given Location object.
8. The Location class shall define a method distance() which calculates the distance from the calling Location object to another given Location object.
9. The Location class shall define a method target() which returns a TwoVector with units of meters that transforms the calling Location to the given Location object.
10. The Location class shall define a method project() which adds a given TwoVector to the calling Location and returns a new Location object.

#### Utility Types

##### TwoVector

1. The TwoVector class shall store a two-dimensional vector.
2. All TwoVector methods shall be declared inline.
3. The TwoVector class shall implement access methods for both Cartesian and polar representations.
4. The TwoVector class shall provide rotation methods for both degree and radian input.
5. The TwoVector class shall provide scalar multiplication and division operators.
6. The TwoVector class shall provide vector addition and subtraction operators.
7. The TwoVector class shall provide the dot product as a multiplication operator.
8. The TwoVector class shall provide a unit() method which returns the unit vector.
9. The TwoVector class shall provide rad2deg() and deg2rad() static methods for angle conversions.

### Logs

The current logging code is clunky to use and doesn’t provide much in the way of protection against race conditions and the like. It is documented here for historical interest and to facilitate writing code until it is replaced.

#### Current

1. The logging class, LogError, shall be a singleton.
2. It shall implement an open() method which opens a given log file for writing.
3. The write() method shall take two arguments, a source and a message. The source argument shall name the origin of the error message and the message argument shall contain the text.
4. The write() method shall write a millisecond resolution timestamp in square brackets, followed by the source, a colon, and the message.
5. The close() method shall close the log file. Since this is a singleton and there is only one ofstream, this must be called immediately to prevent race conditions.

#### Planned

1. Logging shall be handled the EasyLogging++ library (<https://github.com/easylogging/easyloggingpp>)
2. Time format shall be [%Y-%M-%d-%H:%m:%s.%g], for example: [2016-11-03-20:12:22.136]
3. Each module may have its own custom logger in addition to the main logging facility.

### State Machine

1. The core of the software is a multi-layer state machine. Each layer has a base class that instantiates the StateMachineBase template. Each mode[[4]](#footnote-4) in that layer is a subclass of the layer’s base class. The template requires each mode to implement an execute() method. This method contains all logic for the given mode.
2. The execute() method returns a pointer to an object that is a subclass of its layer’s base class. To execute a step of the state machine, the code shall call the execute() method of the mode object that the current state machine pointer points at. It shall then replace the current state machine pointer with the new pointer returned from the call to the current mode’s execute() method.
3. The Navigation mode shall have an RC Command mode pointer and an Autonomous mode pointer as members.
4. Each layer’s base class shall implement a factory() method that returns a pointer to a new mode object of the desired mode type.
5. See Control Modes for a full description of all available modes.

### Waypoint

1. The Waypoint class loads waypoints in from an external KML file, keeps track of the current waypoint, and provides that waypoint as a Location object on request.
2. The Waypoint object shall, on command, load an external KML file. It shall search for a <Placemark> named “Waypoints”, and search within that <Placemark> for a <LineString>. If it finds an appropriate <LineString>, it will load the latitude and longitude points from the <coordinates> field, in order.
3. Loading a KML file shall overwrite the existing waypoint list if and only if it contains at least one valid coordinate.
4. The Waypoint class shall define appropriate methods for accessing and manipulating the locations of the waypoints and the current waypoint number.
5. Determining and steering the course to the next waypoint shall be handled by the appropriate modes’ execute() method(s).

### Obstacle Avoidance

There are two schemes here for obstacle avoidance – a stateless scheme designed to avoid pop-up obstacles, such as might be detected by cameras and a stateful scheme based on the A\* algorithm to dodge fixed obstacles, such as coastlines and AIS contacts. In the future, the stateful scheme can also be used for wind finding by a sailing version of the boat.

#### Vector Summation[[5]](#footnote-5)

1. The primary vector shall be the one pointed at the next waypoint. Its length shall be determined by the value of the WaypointStrength member of the BoatState object. All other navigation vectors shall be summed with it to determine the actual course.
2. If the A\* system is active, the active waypoint shall be the direction to the next intermediate waypoint as determined by the A\* algorithm.
3. The dodge code shall execute the following procedure for all known obstacle points, starting from one side of the obstacle detection field.
   1. Determine the bearing to the obstacle point.
   2. Determine if this obstacle point is within a given distance[[6]](#footnote-6) of the last obstacle point.
   3. If yes, add a vector perpendicular to the obstacle’s bearing, pointing in the same general direction as the last vector,[[7]](#footnote-7) and with a length proportional[[8]](#footnote-8) to the distance to the obstacle.
   4. If no, add a vector perpendicular to the obstacle’s bearing, pointing in towards the primary vector, and with a length proportional to the distance to the obstacle.[[9]](#footnote-9)
4. A noise term shall be added to the vector in order to prevent deadlock.
5. The vector calculated in paragraph (c) shall be summed with the primary vector to produce a target course.

#### A\*

1. The A\* algorithm shall take as input data current location, destination waypoint, an appropriate representation of those areas where the boat is not allowed,[[10]](#footnote-10) and the current AIS database.
2. The neighbors of any given point for the purposes of this algorithm shall be that set of points that can be reached by traveling for a given time step under current or predicted weather conditions. If the destination waypoint is within this locus of points, it shall be a neighbor.
3. g(n) is the number of segments in the path.
4. h(n) is the distance from the point under consideration to the destination waypoint divided by the average length of each segment to this point. This scaling factor is to make the values of g(n) and h(n) directly comparable.
5. The cost of a point that lies within a forbidden area or the exclusion zone around the predicted position of an AIS contact shall be infinite.
6. The A\* algorithm shall proceed until either:
   1. The elapsed time is longer than the pathfinding time horizon.
   2. One or more paths reach the target waypoint.[[11]](#footnote-11)
7. The A\* algorithm shall maintain its list of intermediate waypoints until the next time it is computed.

### PID Control

1. The primary use of PID control is to drive the rudder, but the logic is available for other purposes if required.
2. On construction, the PID object shall be passed pointers to input, output, and setpoint, which are all of type double.
3. The error term shall be the value of the setpoint minus the value of the input at the time of calculation.[[12]](#footnote-12)
4. The integral term is a running sum of the error term, bounded by the output limits stored within the PID object.
5. The differential term is the difference between the current input and the last input.
6. The output shall be calculated with this formula:
7. The PID object shall be settable for either a direct or reverse process, i.e. negative or positive response to a positive input, respectively.
8. The PID object shall have two modes – automatic and manual. In manual mode, the PID loop is calculated every time the Compute() method is called. In automatic, it calculates when Compute() is called if and only if the specified sample time has passed since the last time it calculated.
9. The PID constants shall be interpreted as being in terms of whole seconds. This means that the integral terms shall be divided by the frequency (in Hertz) and the differential term shall be multiplied by the frequency.
10. The PID constant shall store and return the initially entered values of the constants when queried.

### Database Storage

#### HackerboatStateStorage

1. Database interactions will be handled through the HackerboatStateStorage class.
2. Storage will be in SQLite3 database files
3. A static databaseConnection() method shall store the names of all open database files and provide shared handles for each open file.
4. The constructor shall take an initializer list of struct type column.
5. The column struct shall be defined locally and shall consist of two const char\* strings, name and type. These shall be used to drive the createTable() method.
6. The createTable() method shall be used to create the table referred to by the current object if it does not already exist.
7. The HackerboatStateStorage class shall provide methods that return shared statement references for querying, inserting, and updating records.

#### SQLiteParameterSlice

1. SQLiteParameterSlice shall encapsulate an interface to prepare a database row for insertion or appending to the table referred to in the shared statement that it is constructed with.
2. It shall define bind() methods for double, int, int64\_t, bool, std::string, and JSON values.

#### SQLiteRowReference

1. SQLiteRowReference shall encapsulate and interface to read data in from a given database row returned by the shared statement it is constructed with.
2. It shall define a <type>\_field() method to read each of the types that SQLiteParameterSlice can write.

## Control Modes

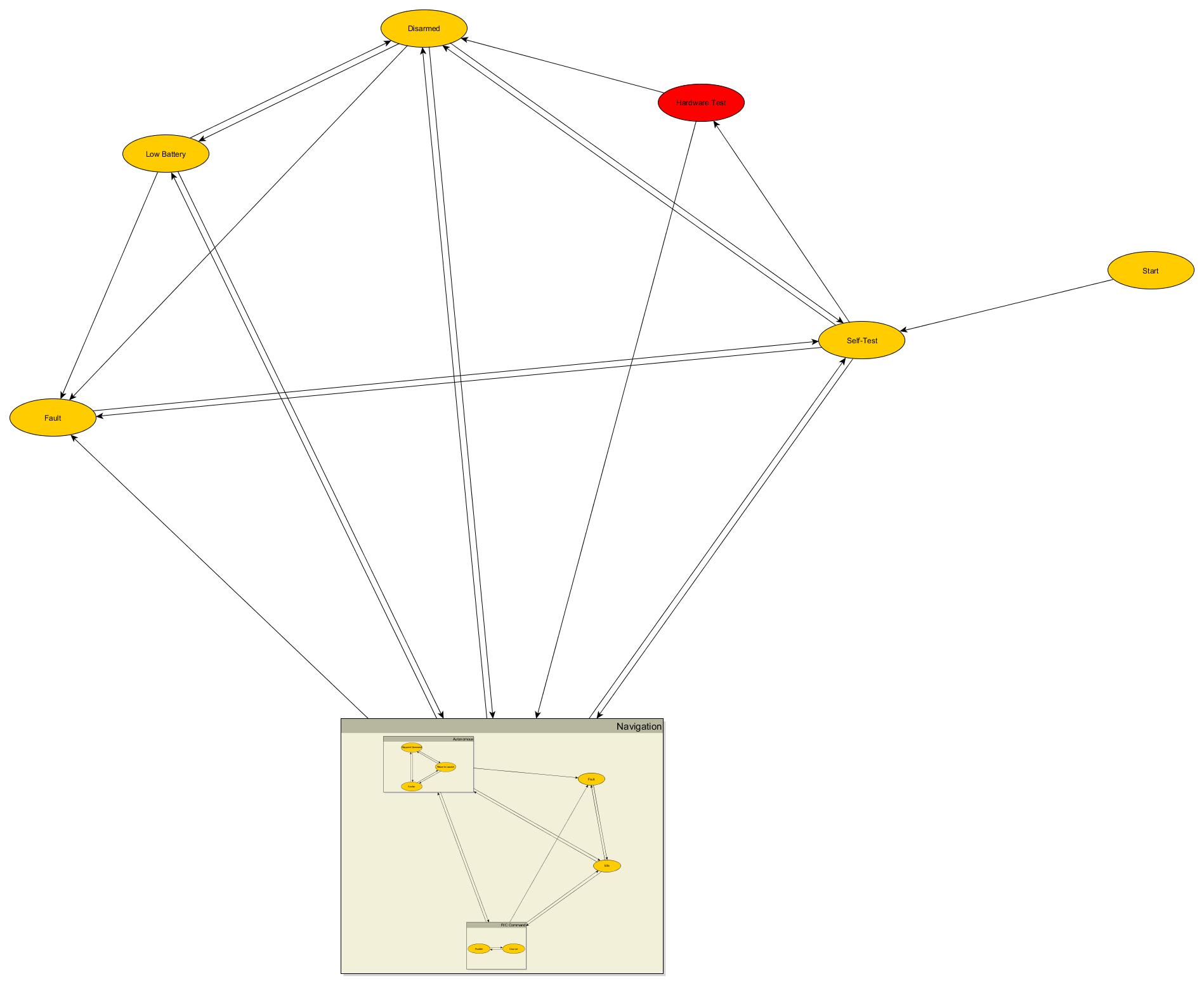
1. The control modes encapsulate the mission logic of the boat.
2. The modes shall be divided into levels for simplicity. Top level modes shall be as depicted in Figure 1.

Figure 1 Top Level Mode Diagram

1. All boat modes shall be subclasses of BoatModeBase.
2. BoatModeBase shall have a factory() method which takes a reference to a BoatState object and a BoatModeEnum variable. It shall return a pointer to a newly created object of the correct mode type.

### Startup

1. The boat shall enter the Startup mode immediately on starting.
2. This mode shall place all outputs in a safe state.
3. This mode shall load a copy of the last BoatState object from the database. This allows the boat to resume its previous mode in case of an unexpected reboot.
4. The boat will transition to Self-Test on the first frame.

### Self-Test

1. The Self-Test state shall determine whether all inputs and outputs of the system are functional.
2. The Self-Test state shall run for the period defined by SELFTEST\_DELAY (located in hal/config.h). During that run, it shall monitor all inputs for fault states. The boat must be still during this period.
3. On the first frame of execution, this mode will make an object local copy of the old BoatState object and clear the fault string.
4. Self-test shall check the following parameters each frame during the test period:
   1. The main battery voltage is above the voltage defined in SYSTEM\_START\_BATTERY\_MIN.
   2. The HealthMonitor object’s state is invalid.
   3. The RCInput object’s state is invalid.
   4. The ADCInput object’s state is invalid.
   5. The GPSInput object’s state is invalid.
   6. The GPS is not receiving valid fixes.
   7. The disarm input GPIO is not valid.
   8. The enable input GPIO is not valid.
   9. Any relay output is faulted.
5. The servo power shall be turned on in this mode.
6. Mode transitions shall not occur until after SELFTEST\_DELAY has elapsed.
7. If the only fault present is low battery, the boat mode will transition to the Low Battery mode.
8. If any other faults are present, the boat mode will transition to the Fault mode.
9. If the boat mode in the stored BoatState object is Navigation and the enable GPIO input is high, then the boat shall transition into the Navigation mode with the same sub-mode as the old BoatState object.
10. Otherwise, the boat mode shall transition to the Disarmed mode.

### Disarmed

1. The servo power shall be disabled.
2. The throttle shall be set to zero.
3. If the boat receives a Self-Test command from the shore, the boat shall transition to the Self-Test mode.
4. If the boat received a Navigation command from the shore, the boat shall pulse the Enable relay high.
5. If the enable GPIO input is high, this mode shall turn on the horn relay output for HORN\_TIME.
6. Once HORN\_TIME has elapsed, if the enable GPIO input is still high, the boat shall transition to the Navigation mode.

### Low Battery

1. If the battery voltage has recovered above SYSTEM\_START\_BATTERY\_MIN, the boat shall recover to the last good mode.
2. The servo power shall be disabled.
3. The throttle shall be set to zero.
4. If any other faults are detected while in this mode, the boat shall transition to fault mode.
5. The boat shall not accept mode commands while in this state.

### Fault

1. This mode shall test each of the fault conditions listed in Self-Test and remove any fault conditions that have healed since entering fault mode.
2. The servo power shall be disabled.
3. The throttle shall be set to zero.
4. If all fault conditions have healed, the boat shall transition to the last good mode.

### Navigation

1. The Navigation mode shall implement the next level down of the state machine. See the State Machine section for details.
2. The Servo power shall be turned on in this mode.
3. In the case of any state transition, the current navigation mode shall be preserved in the BoatState object.
4. If the boat receives a command to go into Self-Test or Disarmed, it shall transition into that state. All other state transition commands must be ignored.
5. After checking incoming commands, the Navigation mode shall call the current sub-mode’s execute() method.
6. If, after the sub-mode’s execute() method returns, the battery voltage is less than SYSTEM\_LOW\_BATTERY\_CUTOFF, this method shall set a “Low Battery” fault and transition to the LowBattery mode.
7. If the BoatState has any other fault or the new navigation sub-mode is Fault, the boat shall transition to Fault mode.
8. If the disarm GPIO is high, the boat shall transition to the Disarmed mode.

#### Idle

1. The Idle sub-mode shall center the rudder and set the throttle to zero.
2. The Idle sub-mode shall accept any command to change the current navigation mode.
3. The Idle sub-mode will check the RC/Auto switch on the remote control. If it is in the RC position, the boat shall transition to the RC sub-mode.
4. The Idle sub-mode shall check for faults in the rudder, throttle, servo power, ADC, orientation, and gps sub-systems.

#### Fault

1. The Fault sub-mode shall center the rudder and set the throttle to zero.
2. The Fault sub-mode shall check if the fault states checked for in the other navigation sub-modes have cleared. If they have, it shall transition to the Idle sub-mode.

#### RC Command

1. The RC mode shall implement the sub-modes described below. See the State Machine section for details.
2. The Servo power shall be turned on in this sub-mode.
3. This sub-mode shall monitor the servo enable, ADC, Orientation, and GPS for faults.
4. If the RC/Auto switch is set to Auto, the boat shall transition to the Autonomous sub-mode.
5. If the boat remains the Failsafe sub-mode for more than RETURN\_TIMEOUT, the boat shall transition to the Autonomous->Return sub-mode of the Navigation mode.

##### Idle

1. The idle sub-mode shall set the rudder and throttle to zero.
2. This sub-mode shall monitor the output of getMode() method of the RCInput object and transition to Rudder, Course, or Failsafe in response to controller switch positions.

##### Course

1. The course sub-mode shall steer a compass course set by the manual remote control, as described in the R/C receiver section.
2. This sub-mode shall execute the helm Compute() mode on each iteration.
3. This sub-mode shall modify the PID constants in response to changes in the stored constants in the BoatMode object. Note that these modifications will typically be in response to a call to SetPID from the shore.
4. This sub-mode shall monitor the output of getMode() method of the RCInput object and transition to Rudder, Failsafe, or Idle in response to controller switch positions.
5. This sub-mode shall set the throttle to the value returned by getThrottle().

##### Rudder

1. The rudder sub-mode shall set the rudder to the value returned by getRudder().
2. This sub-mode shall monitor the output of getMode() method of the RCInput object and transition to Course, Failsafe, or Idle in response to controller switch positions.
3. This sub-mode shall set the throttle to the value returned by getThrottle().

##### Fail Safe

1. The failsafe sub-mode shall set the rudder and throttle to zero.
2. This sub-mode shall monitor the output of getMode() method of the RCInput object and transition to Rudder, Course, or Idle in response to controller switch positions.

#### Autonomous

1. The RC mode shall implement the sub-modes described below. See the State Machine section for details. The Servo power shall be turned on in this sub-mode.
2. If the RC/Auto switch is set to RC, the boat shall transition to the RC sub-mode.
3. The Autonomous sub-mode shall monitor the servo enable, ADC, Orientation, and GPS for faults.
4. The Autonomous sub-mode shall monitor for low battery conditions
5. The Autonomous sub-mode shall monitor for the command to disarm the boat.

##### Idle

1. The Idle sub-mode shall set the rudder and throttle e to zero.
2. The Idle sub-mode shall accept and implement commands to change the Autonomous sub-mode to any other possible value (Waypoints, Return, or Anchor).

##### Waypoint

1. The Waypoint sub-mode shall plot a course to the waypoint stored in the BoatState object’s waypoints list and indicated by the current waypoint number in the same object.
2. The plotted course shall be a great circle.
3. If the Obstacle Avoidance functionality has been implemented, the Waypoint mode shall use it to modify the plotted course to the next waypoint.
4. The Waypoints sub-mode shall use a PID loop with the constants stored in the BoatState object to set the rudder.
5. If the Obstacle Avoidance has been implanted, it shall set the throttle command. Otherwise, the throttle shall be set to AUTONOMOUS\_DEFAULT\_THROTTLE in this mode.
6. When the boat comes within WAYPOINT\_TOLERANCE meters of the waypoint, it shall increment the waypoint selector to the next waypoint in the list.
7. If there is no next waypoint, this sub-mode shall reset the waypoint selector and/or transition modes as described in WaypointActionEnum.

##### Return to Launch

1. The Return sub-mode shall obey the requirements of the Waypoint sub mode with the following exceptions:
   1. The target waypoint shall be the origin point stored in the BoatMode object.
   2. Upon reach the target, the boat shall transition to Anchor sub-mode.

##### Anchor

1. In the Anchor sub-mode, the boat shall attempt to hold a given position.
2. If the target point is ahead of the boat, this sub-mode shall set forward throttle proportional[[13]](#footnote-13) to the position error distance. It shall also steer a direct course to the target point.
3. If the target point is ahead of the boat, this sub-mode shall set reverse throttle proportional to the position error distance. It shall also steer a reverse course[[14]](#footnote-14) to the target point.

# External Utilities

## User Interface

## Remote Control Setup

## Sailing Simulator

### Phase 1

### Phase 2

1. Sourced from http://www.cypress.com/file/130456/download [↑](#footnote-ref-1)
2. Note that the SSL code has not been implemented yet, because I have not figured out how to set it up correctly for the Paho client. [↑](#footnote-ref-2)
3. This has not yet been implemented due to concerns about Adafruit.io’s maximum element length. [↑](#footnote-ref-3)
4. Note that we use modes instead of states here in order to avoid excessive overloading of the term state. [↑](#footnote-ref-4)
5. Ch 4.4 of Arkin’s Behavior Based Robotics describes this as a schema-based behavior architecture. The two schemas at play here are move towards goal and avoid obstacles. [↑](#footnote-ref-5)
6. It’s not clear what value this ought to have – that should be determined by simulation and experiment. [↑](#footnote-ref-6)
7. The intent here is that if we are facing a wall, all the summed vectors shall point in the same direction and get us around the wall, rather than create a zero trap in the vector field. [↑](#footnote-ref-7)
8. The proportionality constant requires tuning. [↑](#footnote-ref-8)
9. The intent here is that if we have an obstacle to the left and the right, the resulting vectors will tend to push the boat towards the center course. [↑](#footnote-ref-9)
10. This is most likely going to be a buffer zone around land, known platforms, and the like. [↑](#footnote-ref-10)
11. The assumption here is that A\*’s ‘best first’ nature will result in an optimal path. If multiple paths reach the goal, the clear heuristic to use is the one that contains less segments. [↑](#footnote-ref-11)
12. In the case of a steered course, the input is equal to the error and the setpoint is zero. The reason for this is because the simple calculation does not take into account the fact that compass course wraps around. [↑](#footnote-ref-12)
13. Eventually we’ll use a PID loop for this, but not right now. [↑](#footnote-ref-13)
14. I.e. 180 degrees out from the target course, since we’re trying to point the stern rather than the bow at the target in this case. [↑](#footnote-ref-14)