



# InfraRed Imaging of astronomical targets with a Stabilised Camera IRISC



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## ⑤ Summary

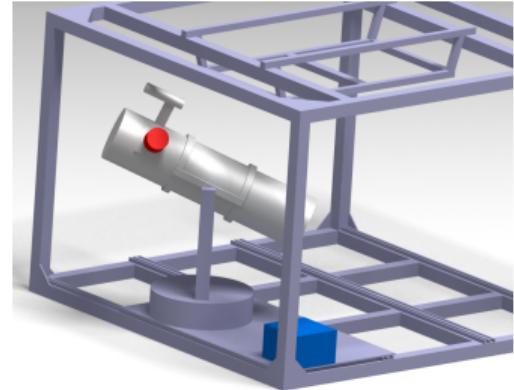
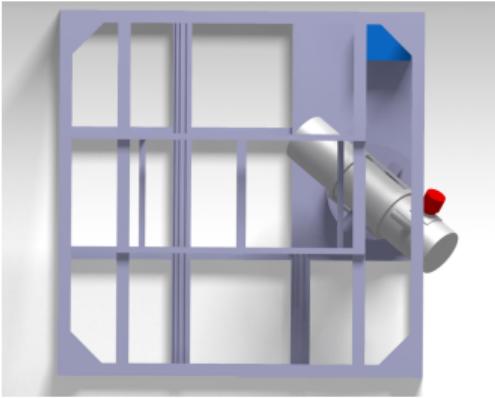
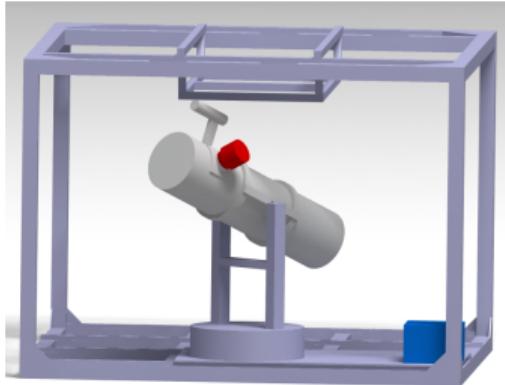
## ⑥ Questions

Our vision is to make astronomical research  
more accessible by developing a stabilised  
balloon-borne telescope

# Construction

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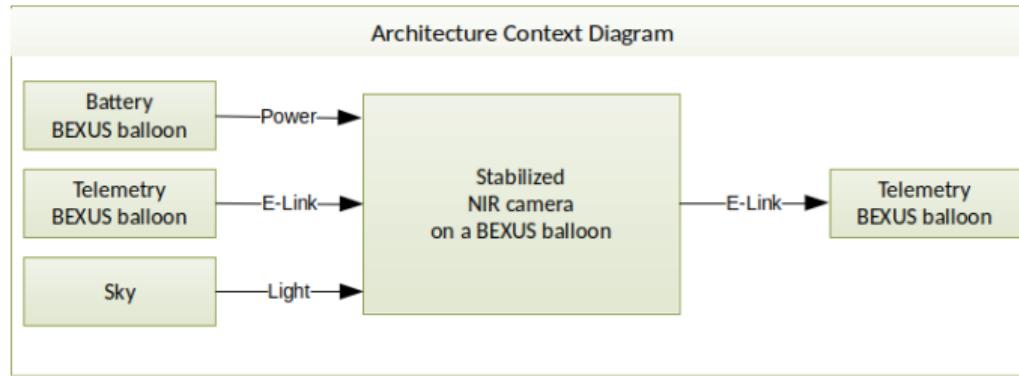


- Using a Newtonian telescope gives us the advantage of not needing an added baffle anymore since the primary mirror is situated on the rear part of the telescope, effectively using the telescope's structure as a baffle.
- For the electronics box, FEA analysis will be made in order to determine the heat produced by the components and therefore determine where heating or cooled will be required.

# Electrical ACD

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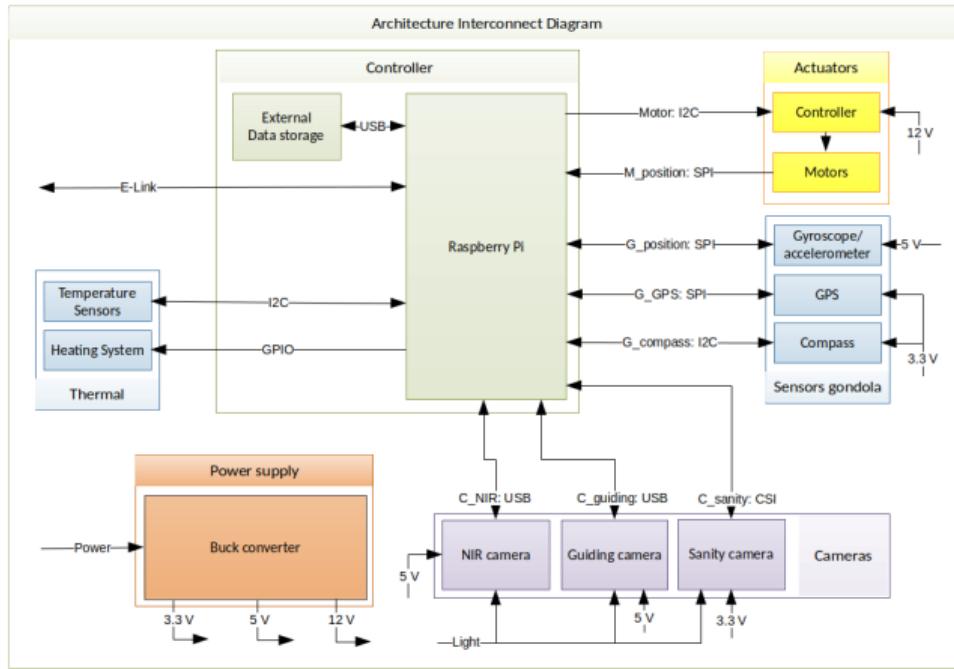
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# Electrical AID

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# Power Consumption

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	Power [W]	On-time [%]	Energy 4h [Wh]
NIR camera	1.5	100	6
Guiding camera	1.5	100	6
Controller	6.25	100	25
Sensors	1	100	4
Motors	$3 \times 4.2$	100	50.4
Heating system	10	20	8
Subtotal			99.4 Wh
Standby E (6h)			40 Wh
Total			139.4 Wh

# Bandwidth

Item	File size*	Downlink rate	Datarate
NIR camera	18 MB	60 sec	2.4 Mbits/sec**
Guiding camera	2 MB	60 sec***	0.27 Mbits/sec
Sanity camera	7 MB	On request	-
Sensors****	30 B	1 sec	240 bits/sec

\* File sizes reflect lossless compressing

\*\* Not planned to send all pictures down, thus will be reduced

\*\*\* Onboard save time is 15 sec

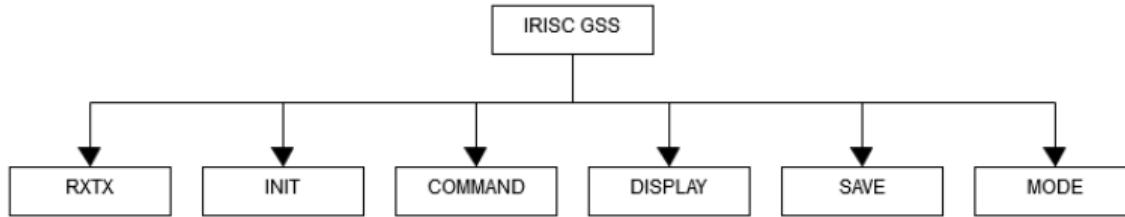
\*\*\*\* GPS; Compass; Gyroscope; Encoders; NIR temp sensor

# Ground Station

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- K.I.S.S.
- Written in C with GTK+

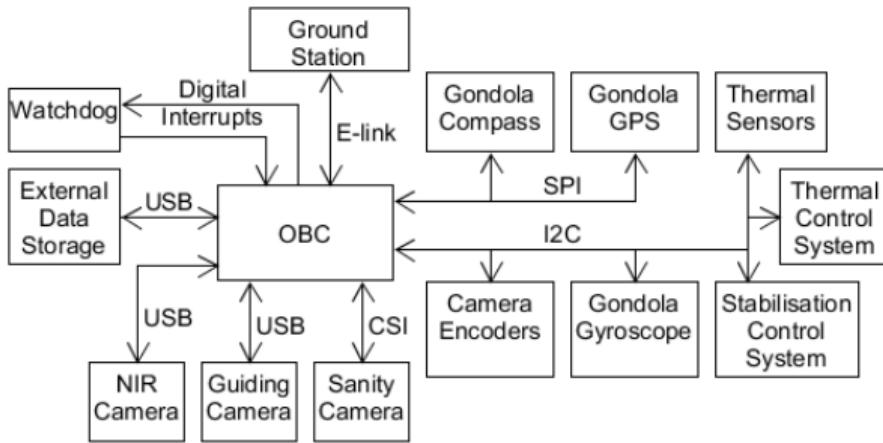


# On-board Software

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- The glue between the systems
- C on a simple linux distro
- Compression and storage



# Control system

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- Stabilisation of the gimbal: dynamic control system (e.g. PID)  
Sensor data: gyroscopes, accelerometer  
Includes mechanical model of gimbal, motors

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- Stabilisation of the gimbal: dynamic control system (e.g. PID)  
Sensor data: gyroscopes, accelerometer  
Includes mechanical model of gimbal, motors
- Selection and tracking of targets:  
Sensor data: magnetometer, GPS, gyroscopes, encoders  
Includes model of movements of astronomical targets

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Sensor data: gyroscopes, accelerometer  
Includes mechanical model of gimbal, motors
- Selection and tracking of targets:  
Sensor data: magnetometer, GPS, gyroscopes, encoders  
Includes model of movements of astronomical targets
- Feedback loop, measured states: utilisation of a Kalman filter to determine exact position & orientation

# Control system

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Minor objectives of the control system:

- Avoid looking directly into the Sun
- Thermal control of the camera sensor and electronics
- Motor control

# NIR Camera

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- CMOS Sensor: ZWO ASI183MM (mono-colour)  
resolution: 20.18 MP, sensor size: 13.2x8.8 mm
- NIR-conversion with 720 nm NIR filter
- Sensitivity: 720 nm to 1150 nm
- Rolling shutter: no mechanical shutter, no moving parts



Credits: ZWO ASI183MM (mono)

# Guiding Camera

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- For verification of the field of view
- Support of ground-based re-calibration of sensors (e.g. magnetometer, gyroscopes)
- Imaging sensor with a high sensitivity, resulting in shorter exposure times (compared to NIR camera)
- Imaging in visible wavelengths



Credits: Guiding camera by ZWO

# Telescope

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Figure: Telescope (with eyepiece in place of the camera)

## SkyWatcher BKP 130DS

- Newtonian telescope
- Weight (without camera) 3.66 kg
- Focal length: 650 mm
- Aperture: 130 mm
- FOV: 1.16 deg by 0.78 deg (in combination with the camera)
- Diffraction-limited-resolution: 1.94 arcsec
- Pixel size: 0.76 arcsec (in combination with the camera)

# Targets

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# Signal to Noise Ratio

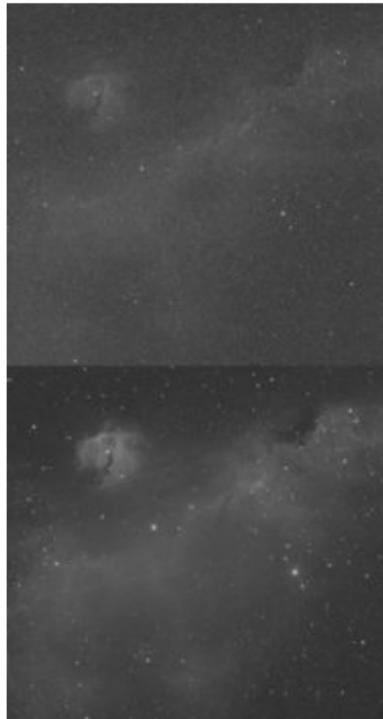
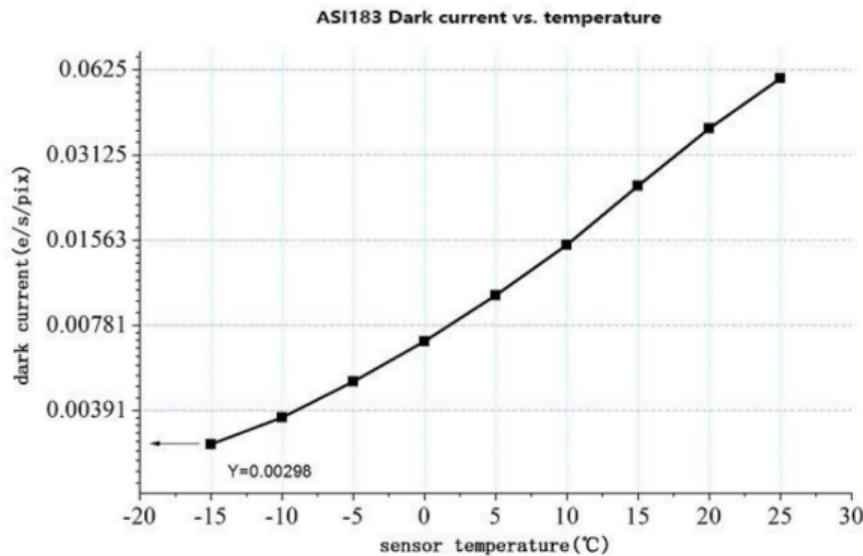


Figure: Dark current vs. temperature as given in the camera manual

A. Möslinger, K. Steele, D. Talavera, N. Ulfvarson, and E.F.M. Weterings

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# Data Analysis

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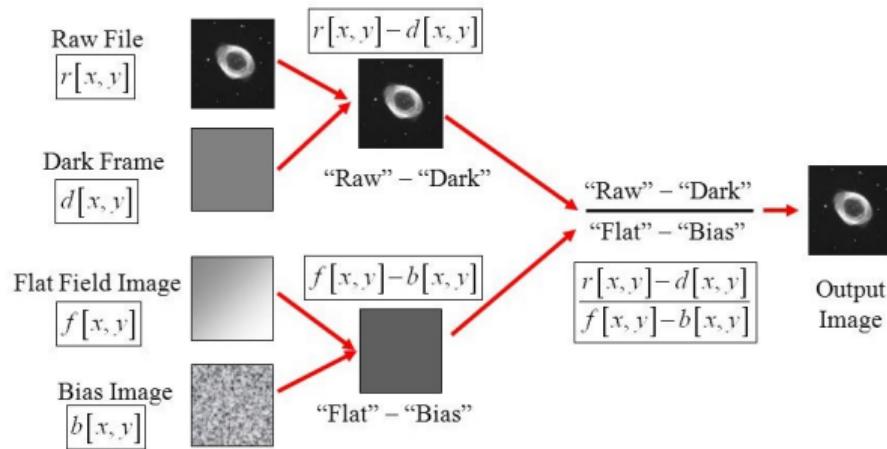
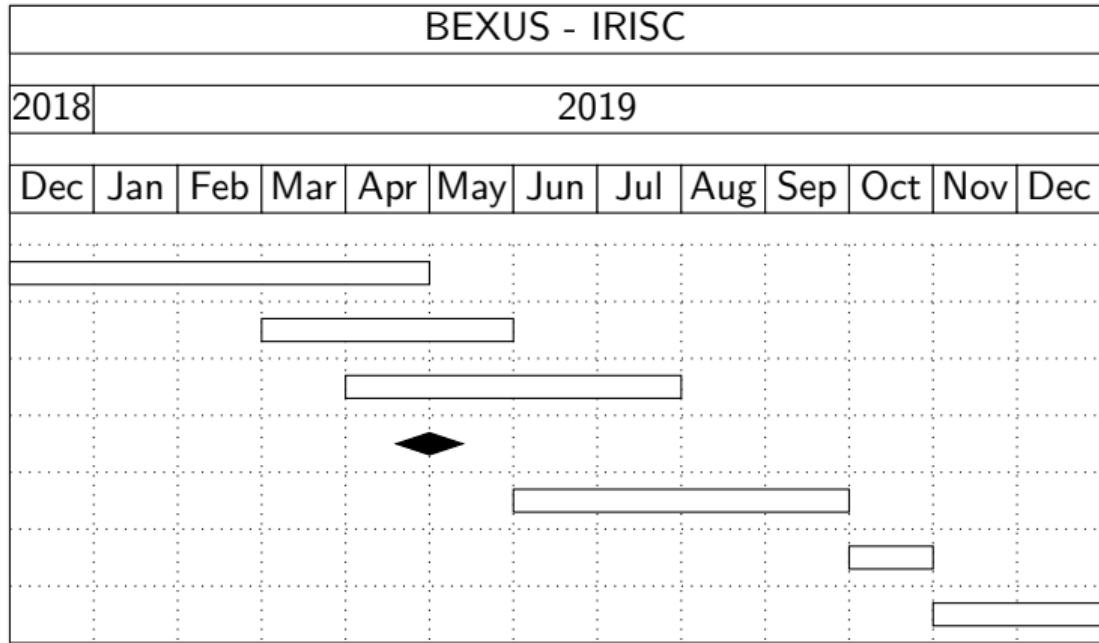


Figure: Standard astrophotography image calibration pipeline

- **Light Frames:** image of the target itself.
- **Dark Frames:** aperture blocked off light.
- **Flat Frames:** brightness balance of the sensor
- **Bias Frames:** readout noise due to the sensor.

# Schedule

Design Phase  
Unit testing  
Manufacturing Phase  
*First Prototype*  
Complete System Testing  
Launch Campaign  
Data Analysis Phase



## Website and Social media

- Facebook
- Twitter
- Instagram

# Summary

IRISC: In a Nutshell  
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- Proof of concept of a stabilised balloon-borne telescope with an NIR camera
- Empowered by the BEXUS project
- To achieve a higher degree of accessible and affordable astronomical research



# Thank you for your attention

Let us explore the NIR universe with a BEXUS balloon together!

A. Möslinger, K. Steele, D. Talavera, N. Ulfvarson, and E.F.M. Weterings  
and the rest of the IRISC team



# Cooling electrical systems in space

The only way to get rid of thermal energy, outside the lower atmosphere, is radiation.  
Passive solutions are:

- Highly efficient components.
- Passive cooler with fluid (convection).
- Solid thermal conducting material connected to the heat sources (conduction).

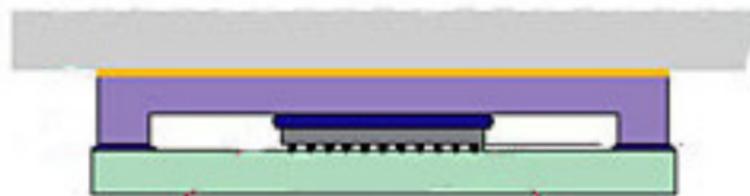
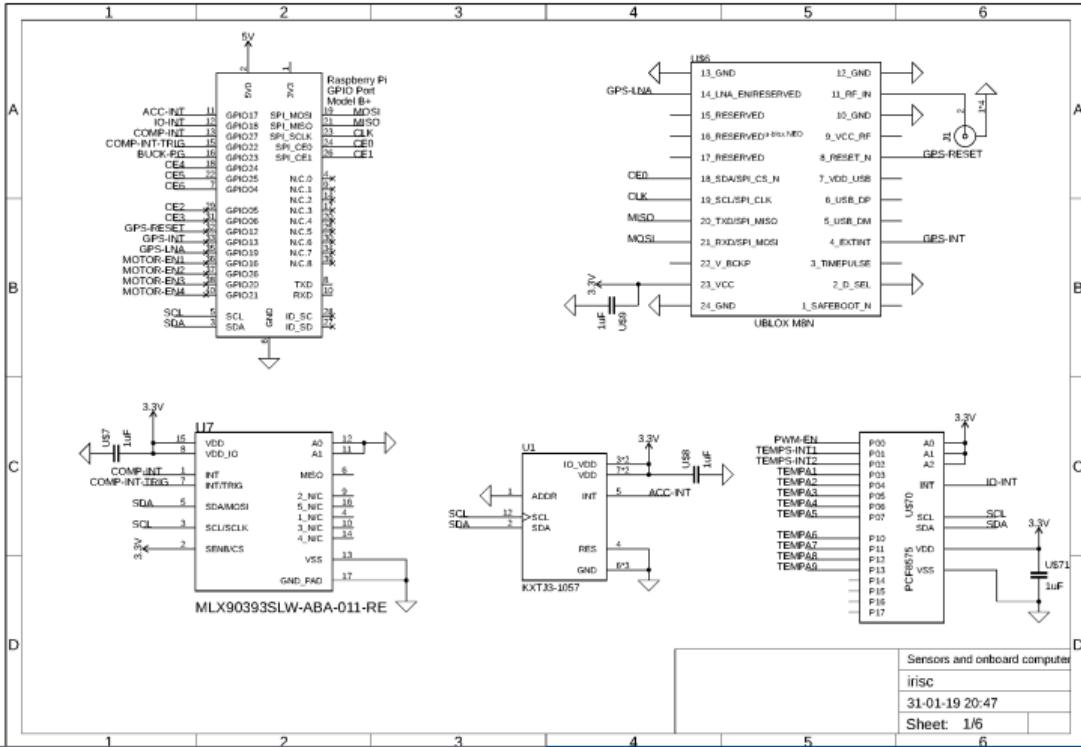


Figure: Clemens J. M. Lasance, cooling electronics

# Schematic: Sensors & onboard computer

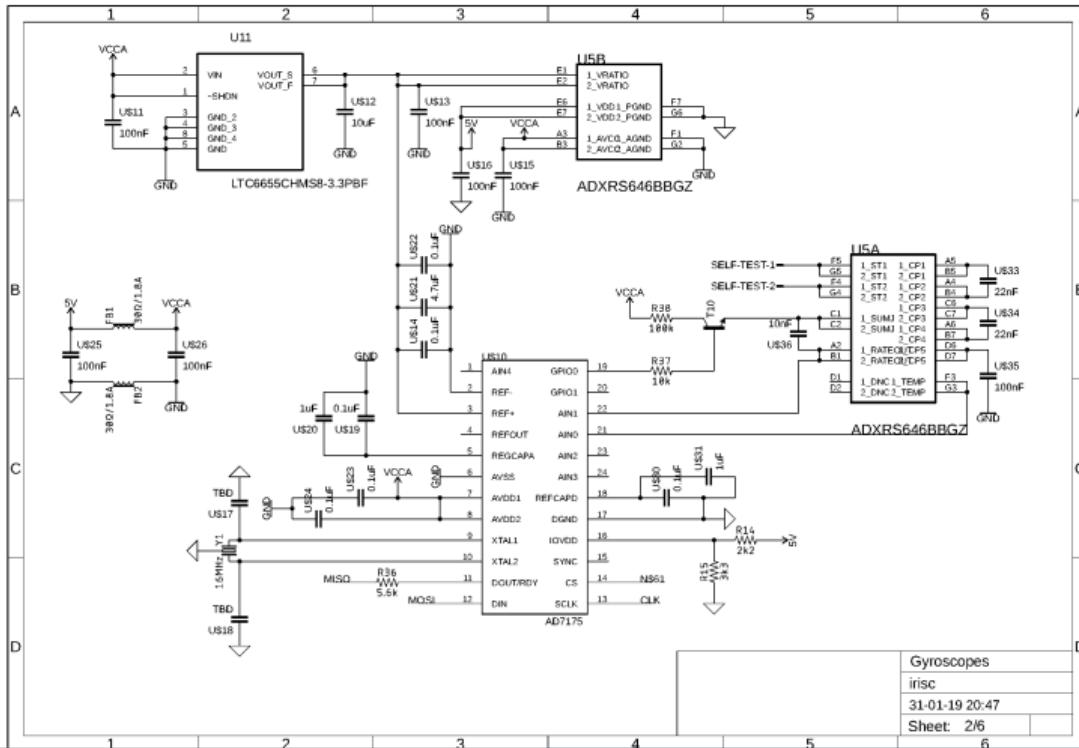


## Schematic: Gyroscopes

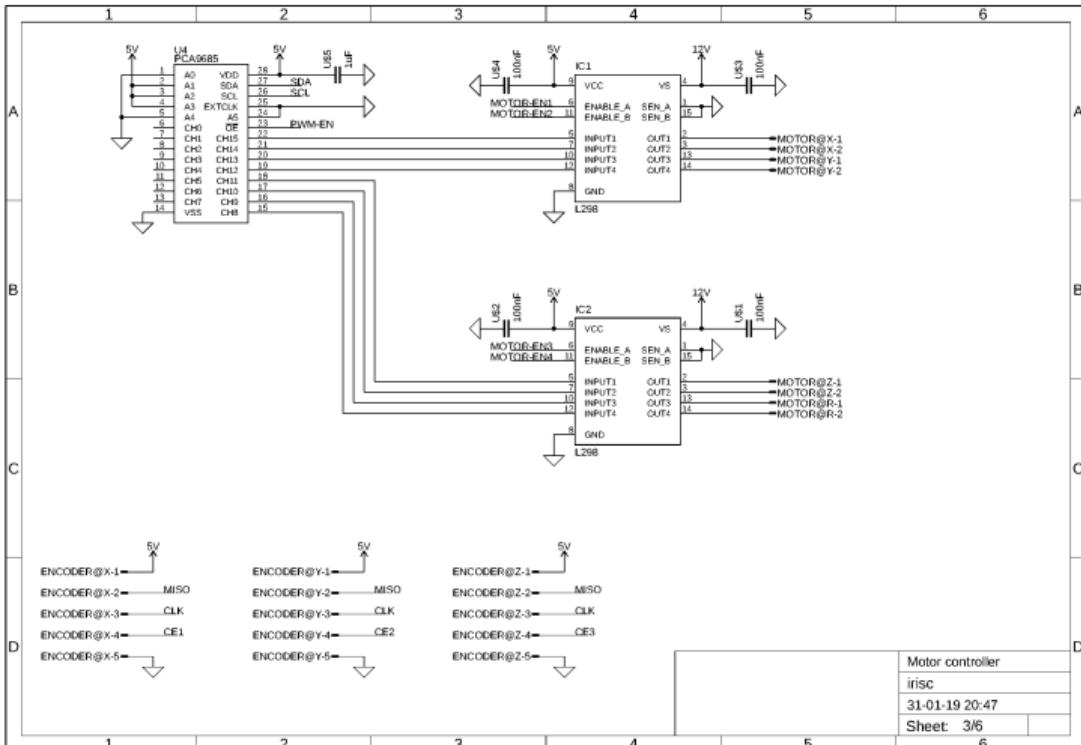
# IRISC: In a Nutshell

## System Science Project Management Summary Questions

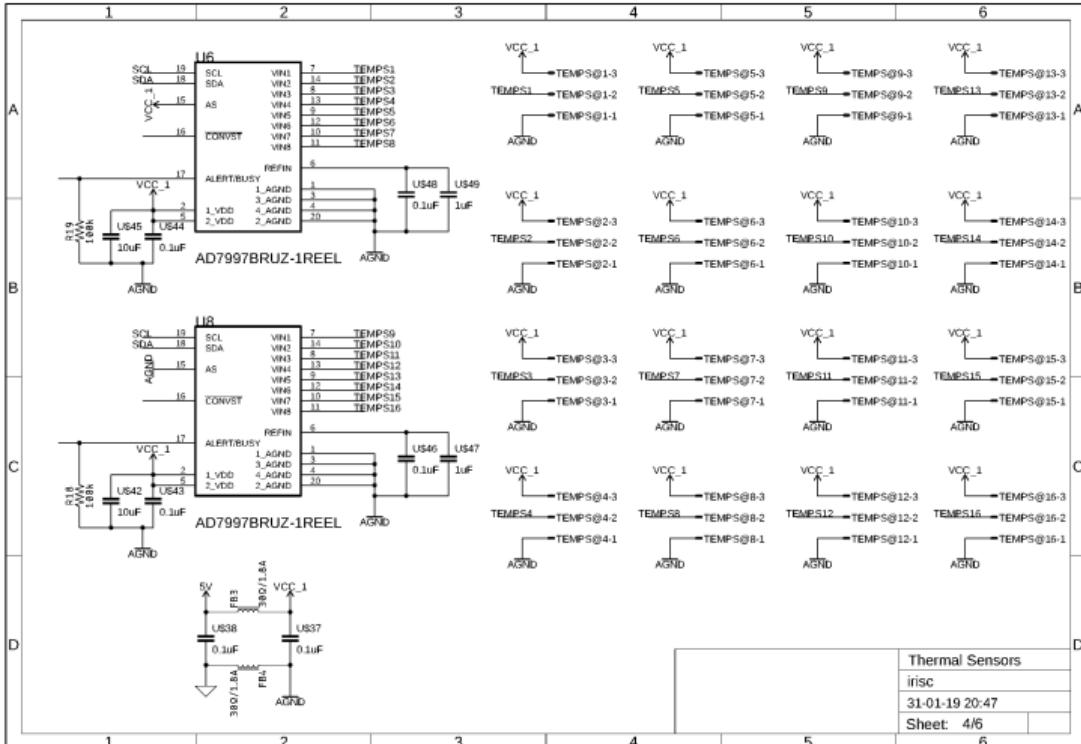
## Electrical Control System Budget



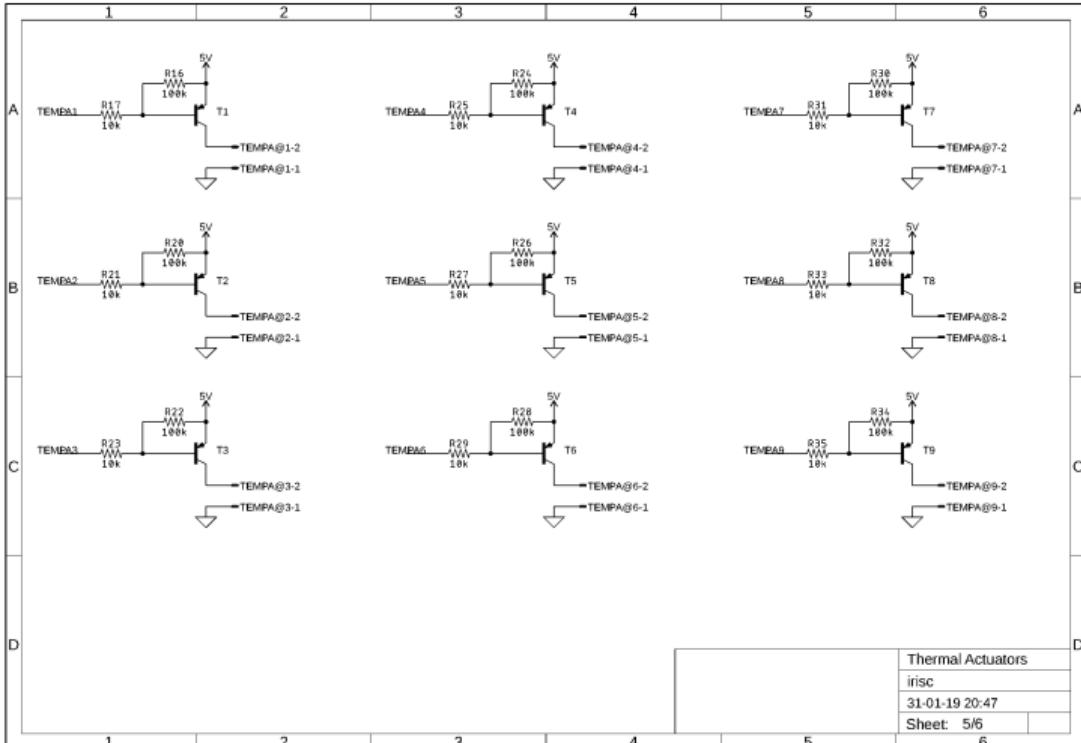
# Schematic: Motor Controller



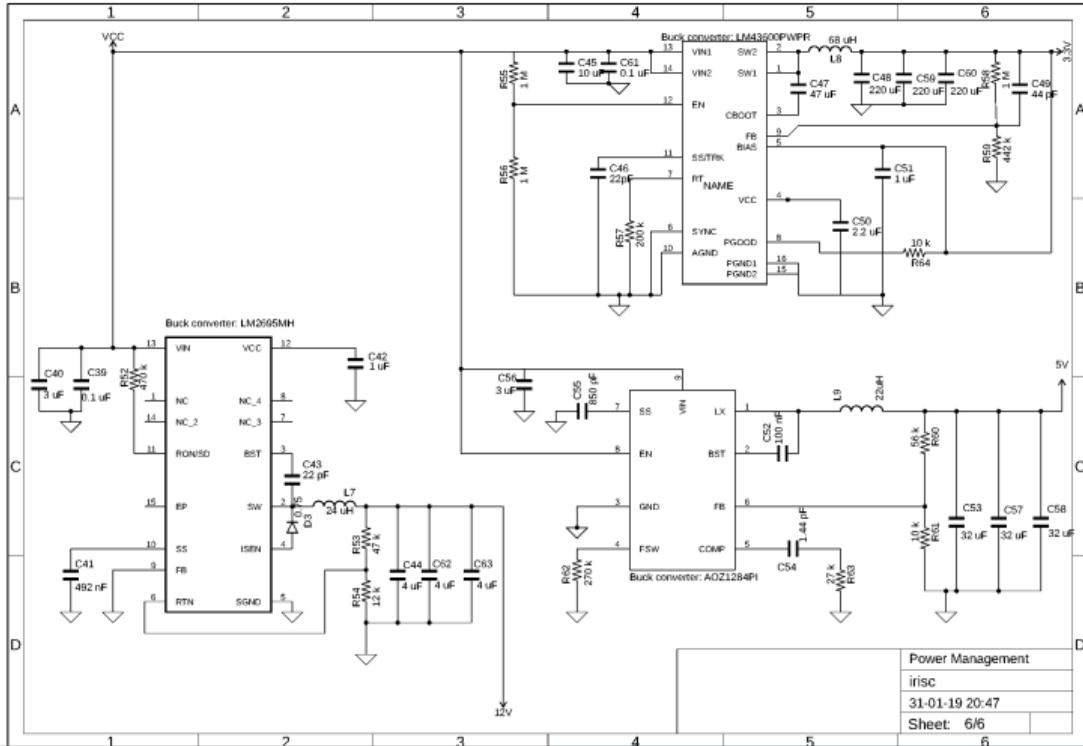
# Schematic: Thermal Sensors



# Schematic: Heating System



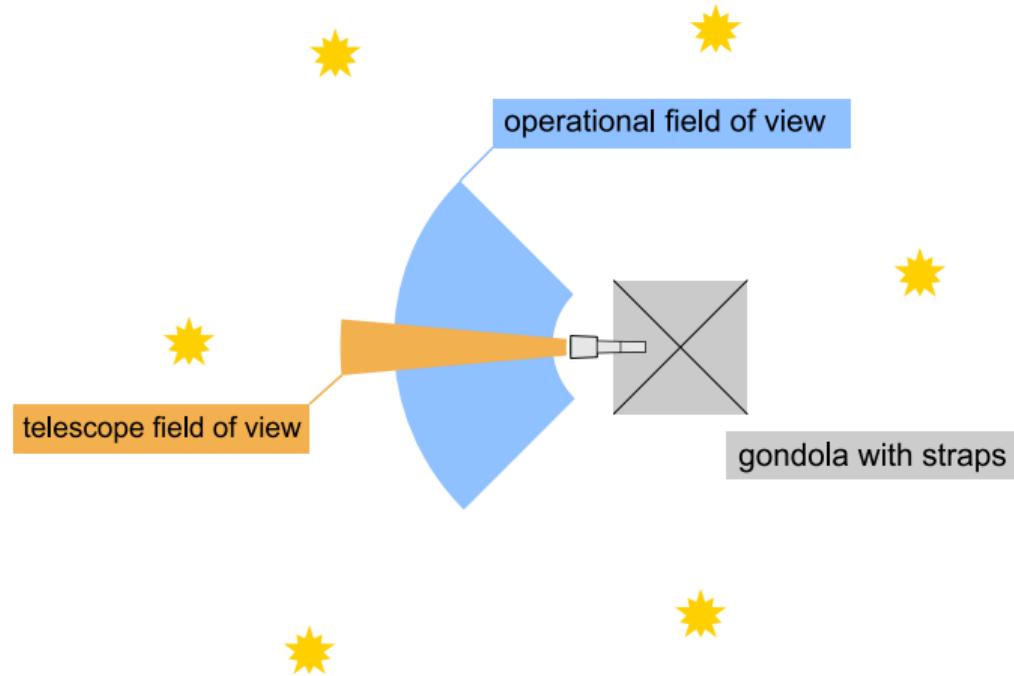
# Schematic: Power Management



# Control System

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Budget



# Budget

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- LTU Project funds
- Trusts and foundations
- Crowdfunding