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# Specifications for the Attitude Control and Determination System-XCubeSat

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# Chapter 1

## Introduction

The objective of this document is to summarize in one place the specifications related to the software of the Attitude Control and Determination System, henceforth ADCS of the nano-satellite X-CubeSat developed by the students of cole Polytechnique, Paris. We have divided the document into the following sections

- Definition of the architecture of the ADCS
- External Interfaces available on the ADCS
- Sensors and peripherals on the ADCS
- Data formats used for computing
- Protocols for testing

This document shall be useful for all people currently concerned with the conception of the ADCS and eventually for students who will take over the project in the months to come. This document is however, far from being complete and additions, corrections and deletions will be made till the day of delivery.

## Chapter 2

# Architecture of the ADCS

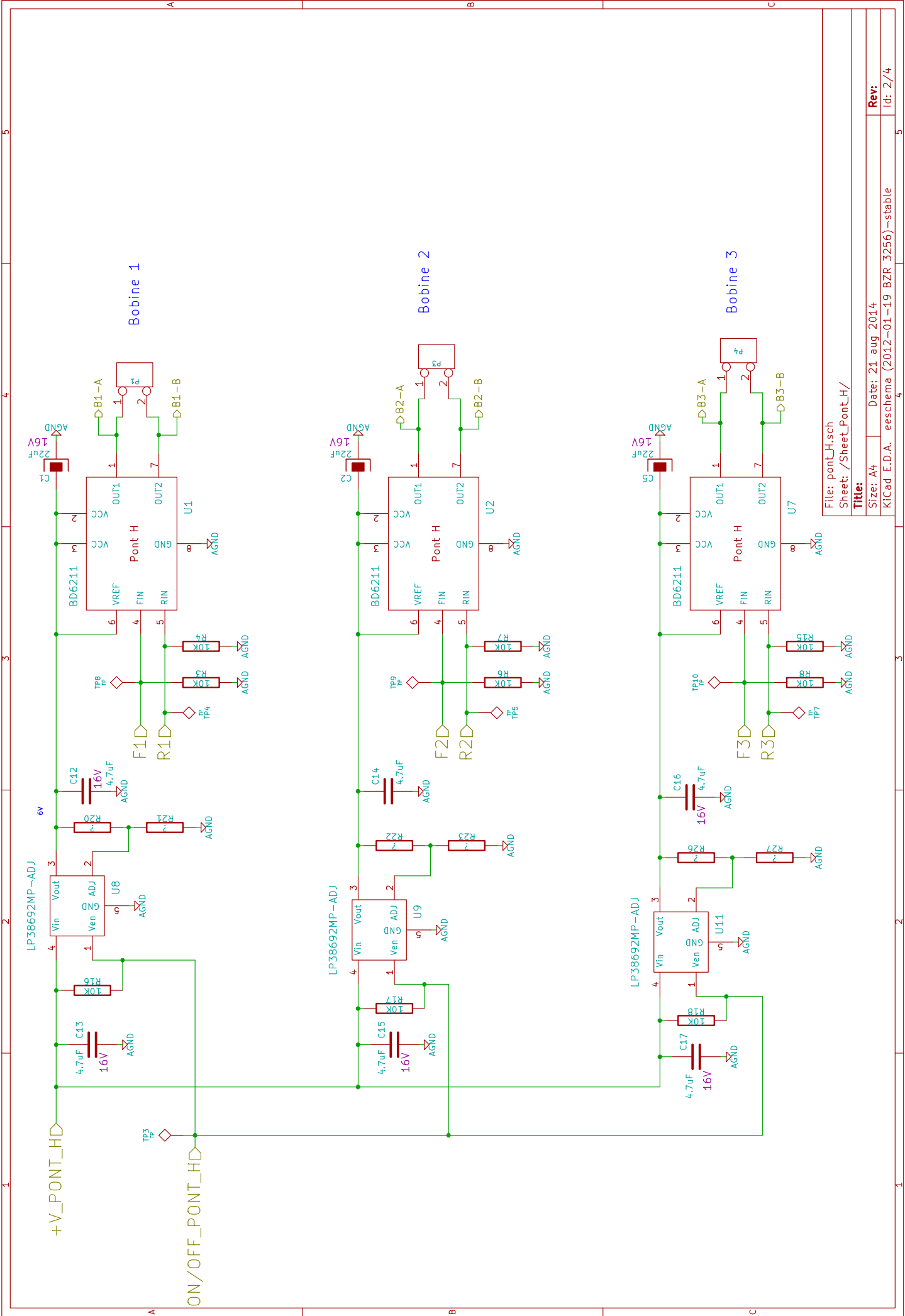
The ADCS uses a microprocessor manufactured by ST Microelectronics based on the ARM Cortex-M4 Architecture. The model used is STM 32F405 RGT6

The available interfaces, sensors and other peripherals available on the ADCS are:

- 32 MB External Memory
- 7(or 9) sun sensors
- Magnetometer
- Gyrometer
- H-Bridges to modulate power to the magneto-torquers
- A Serial interface with the On-Board Computer (*Ordinateur de Bord* henceforth, ODB)

Following is the complete plan for the ADCS:





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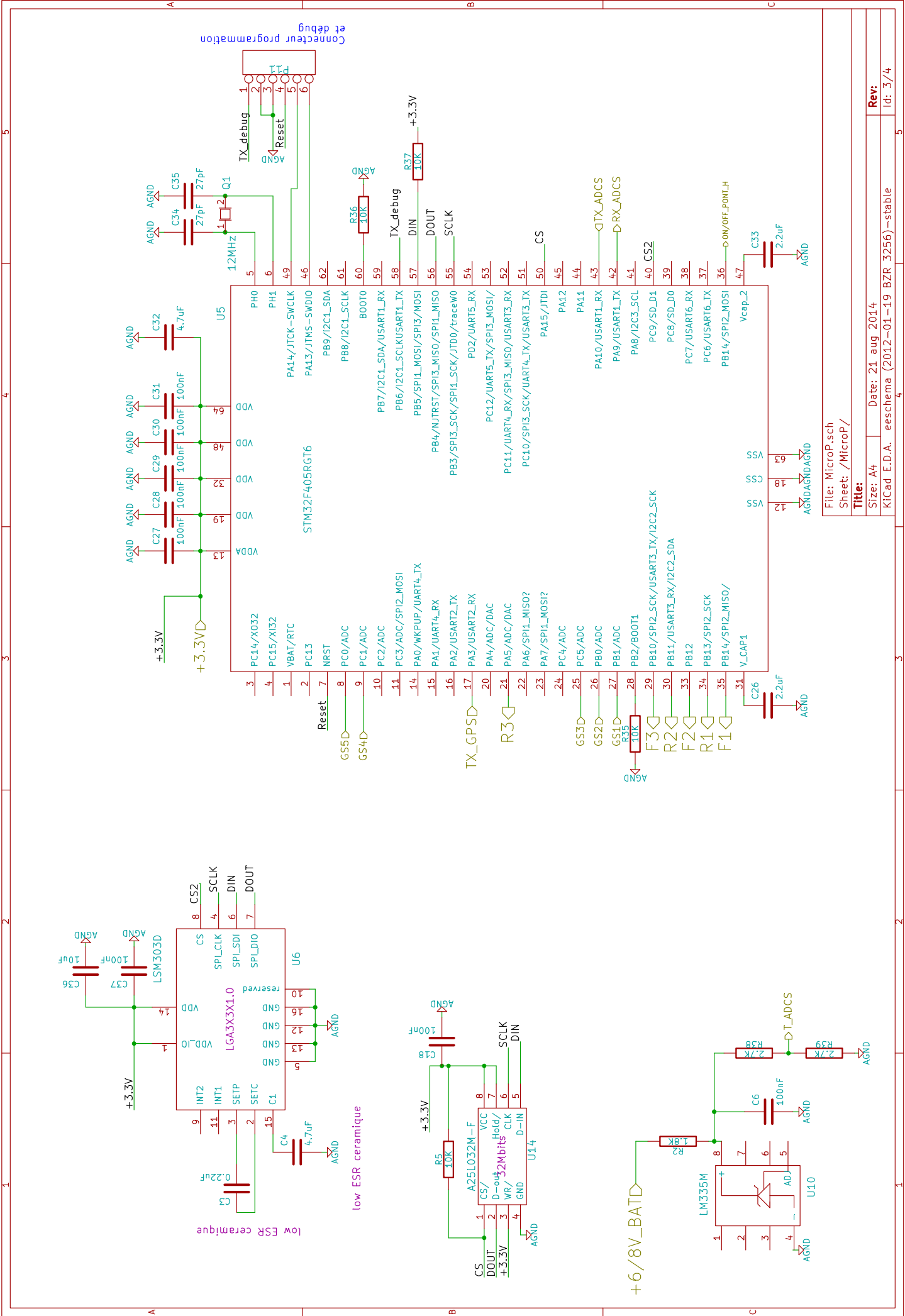
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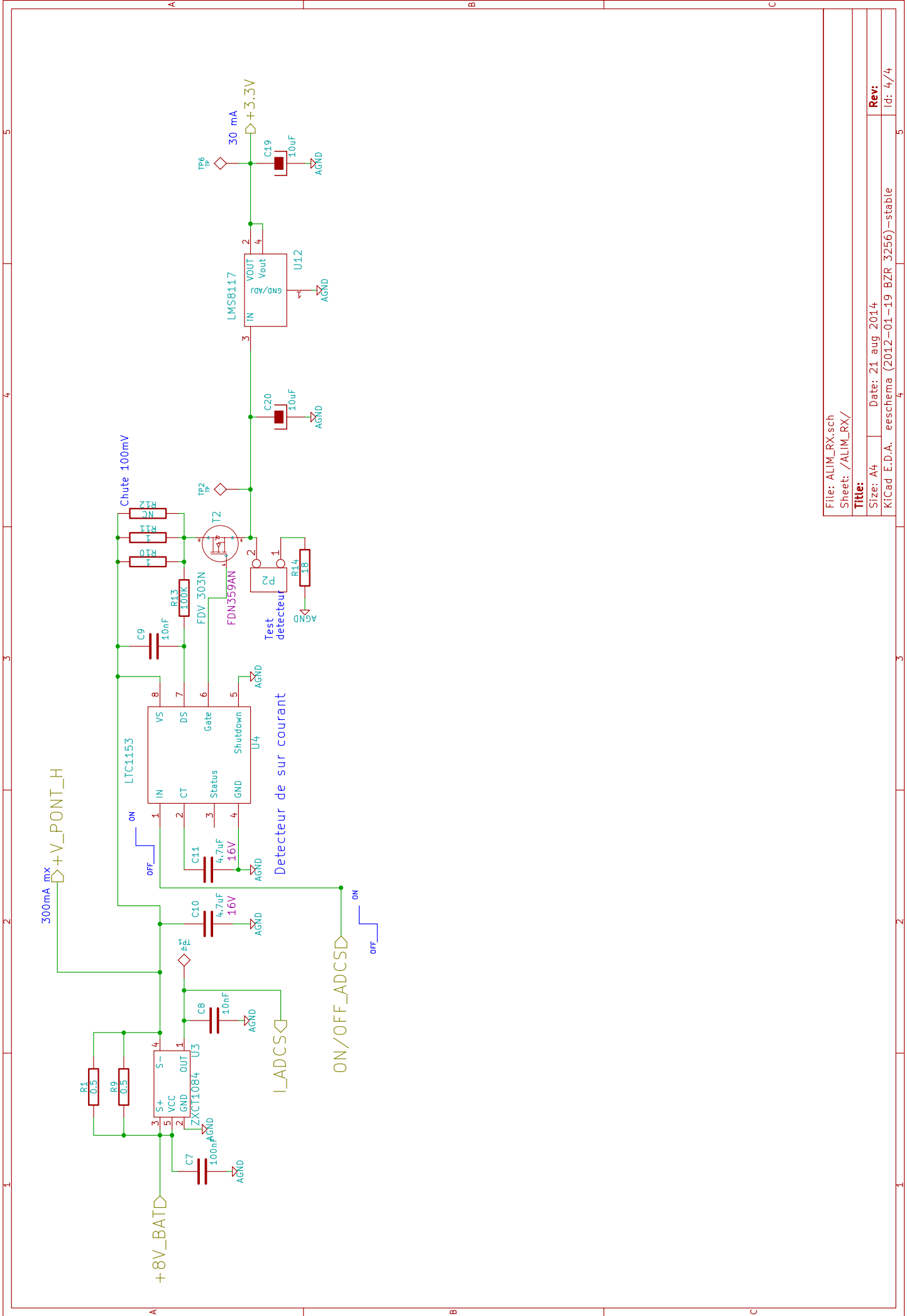
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## Chapter 3

# External interfaces

# Chapter 4

## Software Architecture

### 4.1 Division of the software

The ADCS software is divided into the following layers

1. **API Firmware:** In this layer, all the low-level functionalities are collected. By low-level functionalities, we mean all those functionalities which are not directly relevant to the functioning of the algorithms. This layer doesn't provide any data to the algorithms. Rather, this layer is concerned only with initializing and configuring the various peripherals that we have on the ADCS.
2. **Driver:** This layer acts as a bridge between the lower level API firmware and the higher-level specialized functions that we require to run our algorithms. Ideally, in this layer we find the functions which get the raw data from the sensors, convert or calibrate them as necessary and send them to the algorithms for further use.
3. **Specialized Functions:** The specialized functions are the functions which implement the algorithms for determining and controlling the attitude of the satellite. These functions are high-level functions and require the data provided to them by the *Driver* layer above to function.

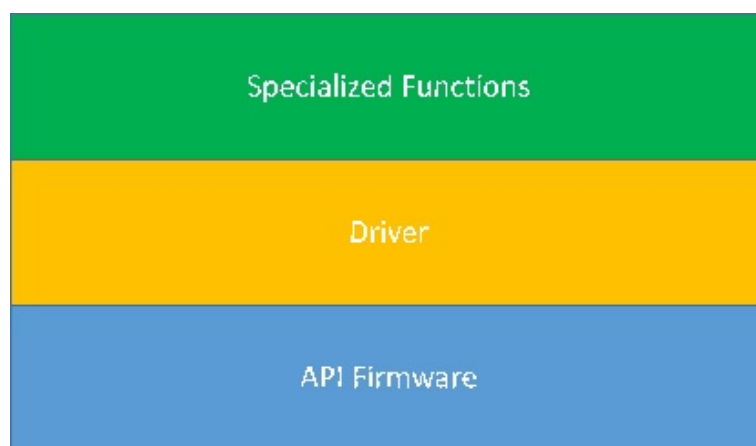


Figure 4.1: *Division of the software in three layers each independent of the other*



three components. For the magnetometer however, we can eventually consider calibrating the data with the temperature. Identically for the gyrometer as well.

Finally, this step also relates to reading the terrestrial magnetic field map and the albedo map from the external memory. All this data once collected, calibrated and treated will be given to the algorithms, which we explain below.

4. **Attitude Determination and Control Phase:** Once the data has been generated (after eventual calibrations), we have the layer where the actual control of the satellite takes place. The details of the algorithms will be presented in an ulterior section.
5. **PD-like controller:** This is what controls the satellite by providing us as output the magnetic moment to be generated in the magnetic coils. The controller then gives its output to the Coils-Attitude Control Interface.
6. **Interface Coils-Attitude Control:** This layer corresponds to the calculations to be done to configure the magneto-torquers. The magneto-torquers are controlled by Pulse-Width Modulation(PWM). For PWM, we require the frequency of modulation (in KHz) and the duty cycle (in percent). The result of the algorithms, however, is the magnetic moment to be generated by the magnetic torquers. Thus we require precise data on the behaviour of the magnetic coils used to convert this magnetic moment into a duty-cycle. (The frequency of modulation shall be fixed for all the coils)
7. **Magnetic Coils:** This is the layer which corresponds to the actual control that will be applied via the magnetic coils. The coils are powered via PWM for a fixed frequency usually around 15-20KHz.

As mentioned earlier, the ADCS disposes the following list of peripherals:

- 32 MB External Memory
- 7(or 9) sun sensors
- Magnetometer
- Gyrometer
- H-Bridges to modulate power to the magneto-torquers
- A Serial interface with the On-Board Computer (*Ordinateur de Bord* henceforth, ODB)

Each of these peripherals need to be configured and their outputs need to be specified so that the algorithms used for the determining and controlling the attitude function optimally.

# Chapter 5

## Data formats

# Chapter 6

## Testing