

# Space Systems Lab Firmware and Mission Requirements Document

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## 0.1 General Requirements

This software is to support the KRUPS missions. The current mission is KRUPS Aboard Norwegian GhostSat (KANGS). The hardware paradigm is based around an ESP32-S3.

This work is porting Matt Ruffner's firmware for Adafruit Feather M0/M4 to the ESP32-S3. This includes switching from the Arduino IDE to ESP-IDF.

The goal of this project is to make the firmware more modular and configurable for each mission and hardware.

The first chapter of this document outlines the overall architecture design and background information for this project. The second chapter details each library, driver, wrapper, and other software components that we wrote for this project. It provides design decisions and the reasoning behind them as well as how to interface with them. The third and on details the software requirements for each hardware component for each mission.

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# Chapter 1

## Architecture Design

### 1.1 Background Information

#### 1.1.1 freeRTOS

freeRTOS is a real time operating system. A real time operating system works by having tasks that run at different priorities. The tasks are scheduled by the operating system and those tasks occur through a deterministic process. The tasks can communicate with each other using message queues. The tasks can also synchronize with each other using semaphores.

#### 1.1.2 ESP-IDF

ESP-IDF is the Espressif IoT Development Framework. It is the official development framework for the ESP32 and ESP32-S3. It is a set of libraries and tools that are used to develop software for the ESP32 and ESP32-S3.

### 1.2 Overall Architecture Design

The firmware's framework is designed to be modular and configurable for each hardware. The backbone of the firmware is using freeRTOS tasks to handle the different modules. Each task is its own module that encapsulates the relevant hardware. The tasks communicate with each other using a publisher/subscriber model.

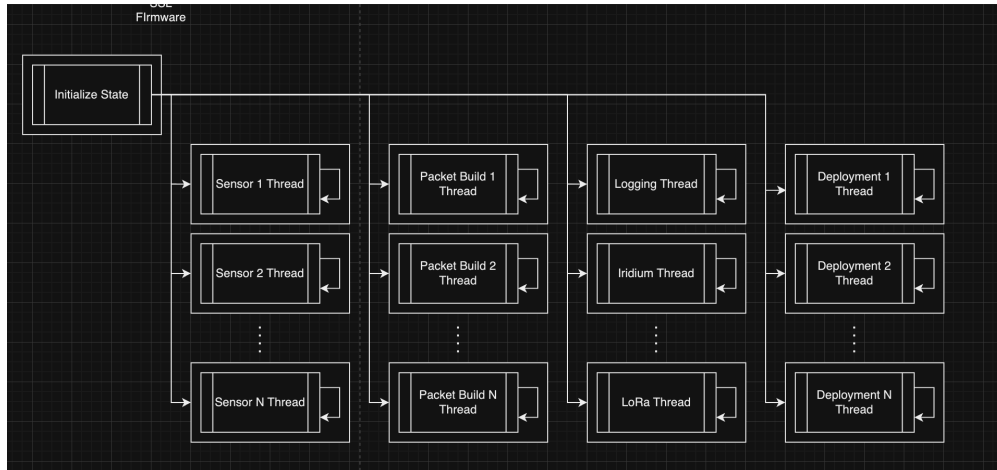


Figure 1.1: Firmware Architecture

In the figure 1.1, the main tasks there are four types of tasks.

### 1.2.1 Task

#### Sensor Tasks

Each sensor task manages one sensor or group of sensors, see 1.2. At startup it configures the sensors with the necessary parameters, then it calls a looping task. That task, takes the semaphore for the used serial communication interface (I2C, SPI, UART, etc). It sends the command to the sensor to get the data, reads the response, and then releases the semaphore. The task then sends the data to the packet build tasks queues.

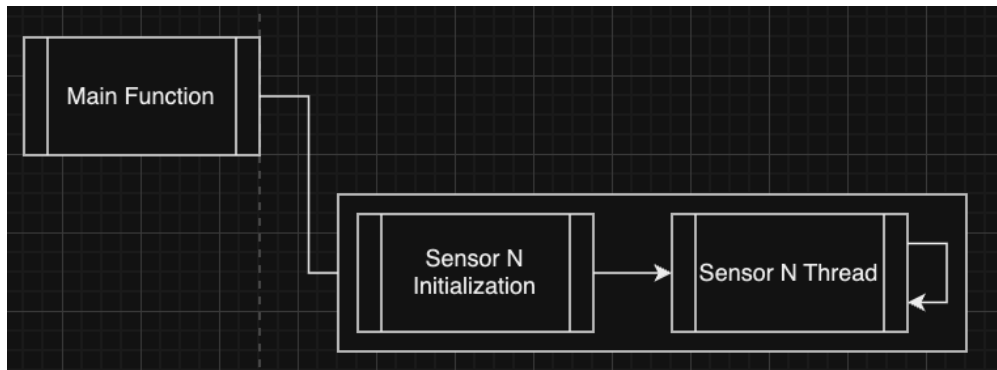


Figure 1.2: Sensor Task Architecture

#### Packet Build Tasks

#### Wireless Communication Tasks

#### Deployment Tasks

### 1.2.2 Middleware

## Chapter 2

# Software Components

### 2.1 Wrappers

#### 2.1.1 I2C Wrapper





## Chapter 3

# KRUPS Aboard Norwegian GhostSat (KANG)

### 3.1 Kentucky Flight Computer (KFC) Requirements

### 3.2 FemptoSats Requirements

The FemptoSats submission is to test the viability of using Wifi/LoRa for intercapsule communication.

#### 3.2.1 Sensors Requirements

The FemptoSats will have the following sensors:

- BME280 Temperature/pressure/humidity sensor
- BNO086 9 - Axis IMU

##### **BME280 Temperature/pressure/humidity sensor**

The BME280 will be run with the following configuration settings:

##### **BNO086 9 - Axis IMU**

The BNO086 will be run with the following configuration settings:

#### 3.2.2 Wireless Communcation Requirements

the FemptoSat will use the following Wireless Communcation modules:

- Integrated Wifi
- LoRa

The Wifi will fail over to the LoRa when the Wifi gets out of range

### 3.3 Rocketstation Transmitter (RST) Requirements

uart to raspi to shut off need

### **3.4 Rocketstation Requirements**

uart to raspi to shut off need

### **3.5 Groundstation Requirements**