

LVV-T2290

January 25, 2022

1 Slew, Track and Image taking with ComCam

This notebook is used for the level 3 integration tests from test plan LVV-P81 (<https://jira.lsstcorp.org/secure/Tests.jspa#/testPlan/LVV-P81>) as part of test cycle LVV-C176 (<https://jira.lsstcorp.org/secure/Tests.jspa#/testCycle/LVV-C176>). The following tests are currently run as part of this notebook:

- LVV-T2290 (<https://jira.lsstcorp.org/secure/Tests.jspa#/testCase/LVV-T2290>)

Execution steps are separated by horizontal lines. Upon completion, save the notebook and its output as a pdf file to be attached to the test execution in JIRA.

Last executed by E. Dennihy 20210928

Run the setup.ipnyb notebook to bring all components up and in their enabled position. Check Chronograph.

Bring ComCom online and tranistion it to EnabledState. Check Chronograph.

```
[1]: %load_ext autoreload
      %autoreload 2
```

```
[2]: import rubin_jupyter_utils.lab.notebook as nb
      nb.utils.get_node()
```

```
/tmp/ipykernel_13426/1665379685.py:2: DeprecationWarning: Call to deprecated
function (or staticmethod) get_node. (Please use lsst.rsp.get_node())
      nb.utils.get_node()
```

```
[2]: 'yagan02'
```

```
[3]: import os
      import sys
      import asyncio
      import logging

      import pandas as pd
      import numpy as np
```

```

from matplotlib import pyplot as plt

from lsst.ts import salobj
from lsst.ts.observatory.control.maintel import MTCS, ComCam
from lsst.ts.observatory.control import RotType

```

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```
[4]: logging.basicConfig(format="%(name)s: %(message)s", level=logging.DEBUG)
```

```
[5]: log = logging.getLogger("setup")
log.level = logging.DEBUG
```

```
[6]: domain = salobj.Domain()
```

```
[7]: mtcs = MTCS(domain=domain, log=log)
mtcs.set_rem_loglevel(40)
```

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```
[8]: await mtcs.start_task
```

```
[8]: [None, None, None, None, None, None, None, None, None, None]
```

```
[9]: comcam = ComCam(domain=domain, log=log)
```

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```
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```

```
[10]: comcam.set_rem_loglevel(40)
```

```
[11]: await comcam.start_task
```

```
[11]: [None, None, None]
```

```
[12]: await comcam.enable()
```

```
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```

Find four targets separated by 5° in azimuth and elevation in a square pattern around $az = 120^\circ$ and $el = 60^\circ$ and rotator angle at PhysicalSky and 1.8° .

At this position, the rotator stays within a couple of degrees of its initial position. This is because the CCW is not running (MTmount in simulation mode).

target_1 -> $az = 117.5^\circ$, $el = 57.5^\circ$

target_2 -> $az = 122.5^\circ$, $el = 57.5^\circ$

target_3 -> $az = 122.5^\circ$, $el = 62.5^\circ$

target_4 -> $az = 117.5^\circ$, $el = 62.5^\circ$

```
[15]: target_1 = await mtcs.find_target(az=117.5, el=57.5, mag_limit=8)
target_2 = await mtcs.find_target(az=122.5, el=57.5, mag_limit=8)
target_3 = await mtcs.find_target(az=122.5, el=62.5, mag_limit=8)
target_4 = await mtcs.find_target(az=117.5, el=62.5, mag_limit=8)

print(f"Target 1: {target_1}")
```

```
f"Target 2: {target_2}"  
f"Target 3: {target_3}"  
f"Target 4: {target_4}")
```

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Target 1: HD 198190Target 2: HD 197845Target 3: HD 192883Target 4: HD 193419

Slew to target 1:

```
[16]: await mtcs.slew_object(target_1, rot_type=RotType.PhysicalSky, rot=1.9)
```

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```

Once on target_1 and tracking, take an image with ComCam

```
[17]: exp1 = await comcam.take_object(15)
      print(f"Target 1 exposure: {exp1}")
```

```
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<IPython.core.display.HTML object>
Target 1 exposure: [2022012500001]
```

Slew to target_2:

```
[18]: await mtcs.slew_object(target_2, rot_type=RotType.PhysicalSky, rot=1.9)
```

```
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```

[illegible]

```
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```

Once on target_2 and tracking, take an image with ComCam

```
[19]: exp2 = await comcam.take_object(15)
      print(f"Target 1 exposure: {exp2}")
```

```
<IPython.core.display.HTML object>
<IPython.core.display.HTML object>
<IPython.core.display.HTML object>
Target 1 exposure: [2022012500002]
```

Slew to target_3

```
[20]: await mtcs.slew_object(target_3, rot_type=RotType.PhysicalSky, rot=1.9)
```

```
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```

[illegible]

Once on target_3 and tracking, take an image with ComCam

```
[21]: exp3 = await comcam.take_object(15)
print(f"Target 1 exposure: {exp3}")
```

```
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```


Slew to target 4

[illegible]

```
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```

Once on target_4 and tracking, take an image with ComCam

```
[23]: exp4 = await comcam.take_object(15)
      print(f"Target 1 exposure: {exp4}")
```

```
<IPython.core.display.HTML object>
<IPython.core.display.HTML object>
<IPython.core.display.HTML object>
Target 1 exposure: [2022012500004]
```

Stop tracking to prevent hitting the Rotator soft limit.

```
[24]: await mtcs.stop_tracking()
```

```
<IPython.core.display.HTML object>
```

Use ComCam recent images CCS to ensure that the images were taken (<http://ccs.lsst.org/RecentImages/comcam.html>).

Query the butler to verify that the images are there and check the metadata. This step must be verified using a separate notebook.

Wrap Up and Shut Down

This cell is not currently included as part of the test execution, but included here as needed to shutdown the systems

```
[ ]: await mtcs.set_state(salobj.State.STANDBY, components=["mtaos"])
```

```
[ ]: await mtcs.lower_m1m3()
```

```
[ ]: await mtcs.set_state(salobj.State.STANDBY, components=["mtm1m3"])
```

```
[ ]: await mtcs.set_state(salobj.State.STANDBY, components=["mtm2"])
```

```
[ ]: await mtcs.set_state(salobj.State.STANDBY, components=["mthexapod_1"])
```

```
[ ]: await mtcs.set_state(salobj.State.STANDBY, components=["mthexapod_2"])
```

```
[ ]: await mtcs.standby()
```

```
[ ]: await comcam.standby()
```