

TERMITE OS

THE TELESCOPE OPERATING SYSTEM

termiteOS Documentation

Release alpha

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A telescope Operating System base on zmq and Protocol Buffers. Documentation <https://nachoplus.github.io/termiteOS/index.html>

INTRODUCTION

Termite OS is a modular, adaptable, easily extendable telescope operating system developed primarily, but not exclusively, in python.

It wants to answer to several limitations that most of the commercial mount controllers have. It wants to be a platform where you can incorporate all kinds of functionalities that the professional or amateur astronomer may need in a simple way.

Possible use case:

- To motorize a DIY mount or retrofit a old one.
- Make your telescope be able to track the ISS or any other satellite.
- Implement new protocol commands.
- New native protocols, i.e. indilib
- Control over the objects catalogs built into your telescope.
- Integrate pointing model in your mount.
- Connect a GPS to your mount and use his data for location and time.
- Define the horizon of your observatory.
- WiFi or Bluetooth access to your mount
- Develop new motion strategies.

With termiteOS you will address all this things and more.

Termite OS is a **work in progress** but much of the functionality is already available:

- Stepper controller using Raspberry PI and the integrated DRV8825 widely used in the 3D printer world
- LX200 command set
- Slew and celestial track
- Satellite tracking

Ongoing functionality:

- Arduino base hardware
- BLDC motors
- Servo motors
- Web interface
- Constellation pointing

ARCHITECTURE

Each termiteOS functionality is implemented as a separate program called a 'node'. The nodes communicate each other using the zmq protocol. The organization between the nodes is hierarchical thus a node can have several children but has only one parent or none in the case of the 'root node'.

ZMQ (<http://zeromq.org/>) is used for transport and on <https://developers.google.com/protocol-buffers/> for message definitions and serialization.

Each node has its own ZMQ port and a set of commands and responds to through that port. Each node opens connections with its parent node and with all its children so that messages can be exchanged.

These nodes can run on the same or different CPUs taking advantage of all the features of the ZMQ protocol.

**CHAPTER
THREE**

LICENSE

GPL3 Copyright (c) July 2018 Nacho Mas

Logo made with <https://www.designevo.com/en/> DesignEvo

TECHNICAL INFORMATION

Launcher

- **Launcher** program launch a set of node following the instruction in yaml file

This program allow to launch at once all nodes needed for a specific hardware/funtionality.

Example of a yaml configuration file:

```
simple:
  type: telescope
  host: localhost
  port: 5000
  nodes:
    - LX200:
      type: tcpproxy
      host: localhost
      port: 5001
      params: {'tcpport':6001,'End':'#'}
    - tracker:
      type: TLEtracker
      host: localhost
      port: 5002
      nodes:
        - trackertcp:
          type: tcpproxy
          host: localhost
          port: 5003
          params: {'tcpport':6003}
```

This example is equivalent to run on the command shell all following commands:

```
miteTelescope --port 5000 --name simple
mitetcpproxy --port 5001 --name LX200 --parent_host localhost --parent_port 5000 --params {'tcpport':6001,'End':'#'}
miteTLEtracker --port 5002 --name tracker --parent_host localhost --parent_port 5000
mitetcpproxy --port 5003 --name trackertcp --parent_host localhost --parent_port 5002 --params {'tcpport':6003}
```

You can find other examples in ‘termoteOS/machines/’

Command line:

miteLaunch

Launch all nodes defined in YAMLFILE

```
miteLaunch [OPTIONS] YAMLFILE
```

Arguments

YAMLFILE

Required argument

API

Launch tools to run a rig. Run several daemons at once

`termiteOS.launch.launchmachine (yamlfile)`

Launch an arrangement of daemons defined in a yaml file

`termiteOS.launch.launchnode (nodedict, parent_host='', parent_port=False)`

Launch a node defined in dictionary. Called recursively

`termiteOS.launch.run_in_separate_process (func, *args, **kws)`

Run function in a separate process. To background executables

Nodes

Nodes are separate programs. The nodes communicate each other using the zmq protocol. The organization between the nodes is hierarchical thus a node can have several children but has only one parent or none in the case of the 'root node'.

Nodes are based on <http://zeromq.org/> for transport and on <https://developers.google.com/protocol-buffers/> for message definitions and serialization.

Each node has its own ZMQ port and a set of commands and responds to through that port. Each node opens connections with its parent node and with all its children so that messages can be exchanged.

These nodes can run on the same or different CPUs taking advantage of all the features of the ZMQ protocol.

All nodes are derive from nodeSkull base class which implements all the comunication logic and basic commands.

TLEtracker

- **TLEtracker** node calculate satellite TLE speed and RA/DEC and send to the mount

With this node the mount is able to follow any object with TLE.

Command line:

miteTLEtracker

Launch a TLEtracker node

```
miteTLEtracker [OPTIONS]
```

Options

--name <name>
module name

--port <port>
Port listen

--parent_host <parent_host>
Parent host to connect to. If False the node become a ROOTHUB

--parent_port <parent_port>
Parent port to connect to

TLTracker commands

follow

Follow satellite

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

hub

- **hub** node has not own commands. Only used to connect other nodes

Command line:

miteHub

Launch a hub node

```
miteHub [OPTIONS]
```

Options

--name <name>
module name

--port <port>
Port listen

--parent_host <parent_host>
Parent host to connect to. If False the node become a ROOTHUB

--parent_port <parent_port>
Parent port to connect to

hub commands

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

joystick

- **joystick** node to manual move the mount with a joystick

Command line:

miteJoy

Launch a joystick node

```
miteJoy [OPTIONS]
```

Options

--name <name>
module name

--port <port>
Port listen

--parent_host <parent_host>
Parent host to connect to. If False the node become a ROTHUB

--parent_port <parent_port>
Parent port to connect to

joystick commands

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes available commands

param arg (None)

returns a string contain all commands

tcpproxy

- **tcpproxy** node acts as a proxy connector between other node and an specific TCP port

All commands received through the TCP port are relay to the myCmdPort port of the node connected to.

Using this node allow us to connect to a specific node (the parent node of tcpproxy node) with a regular *telnet host port*

Command line:

mitetcpproxy

Launch a tcpproxy node

```
mitetcpproxy [OPTIONS]
```

Options

--name <name>
module name

--port <port>
Port listen

--parent_host <parent_host>
Parent host to connect to. If False the node become a ROOTHUB

--parent_port <parent_port>
Parent port to connect to

--params <params>
Dictionary with extra parameters default={"tcpport":6001,"End": cant be empty}

tcpproxy commands

help

Print help text. Do nothing. Normally overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

Telescope

- **telescope** node implement a telescope mount basic commands (goto,slew,track..)

Two axis equatorial mount telescope.

Command line:

miteTelescope

Launch a telescope node

```
miteTelescope [OPTIONS]
```

Options

--name <name>
module name

--port <port>
Port listen

--parent_host <parent_host>
Parent host to connect to. If False the node become a ROOTHUB

--parent_port <parent_port>
Parent port to connect to

telescope commands

ack

None

align2target

None

firware_date

None

firware_ver

None

getLocalDate

None

getLocalTime

None

getSideralTime

None

getTargetDEC

None

getTargetRA

None

getTelescopeDEC

None

getTelescopeRA

None

help

Print help text. Do nothing. Normaly overloaded by a child class

info

None

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

pulseE

None

pulseN

None

pulseS

None

pulseW

None

setMaxSlewRate

None

setTargetDEC

None

setTargetRA

None

slew

None

slewRate

None

stopSlew

None

tree

Print all self and children nodes available commands

param arg (None)

returns a string contain all commands

Node commands

TLEtracker commands

follow

Follow satellite

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes available commands

param arg (None)

returns a string contain all commands

costellation commands

follow

None

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

hub commands

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

joystick commands

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes available commands

param arg (None)

returns a string contain all commands

tcpproxy commands

help

Print help text. Do nothing. Normaly overloaded by a child class

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

tree

Print all self and children nodes available commands

param arg (None)

returns a string contain all commands

telescope commands

ack

None

align2target

None

firmware_date

None

firmware_ver

None

getLocalDate

None

getLocalTime

None

getSideralTime

None

getTargetDEC

None

getTargetRA

None

getTelescopeDEC

None

getTelescopeRA

None

help

Print help text. Do nothing. Normaly overloaded by a child class

info

None

ls

list the node commands

nodes

list the children nodes:

param arg (None)

returns a python list all children node names

ping

None

pulseE

None

pulseN

None

pulseS

None

pulseW

None

setMaxSlewRate

None

setTargetDEC

None

setTargetRA

None

slew

None

slewRate

None

stopSlew

None

tree

Print all self and children nodes availabled commands

param arg (None)

returns a string contain all commands

Drivers

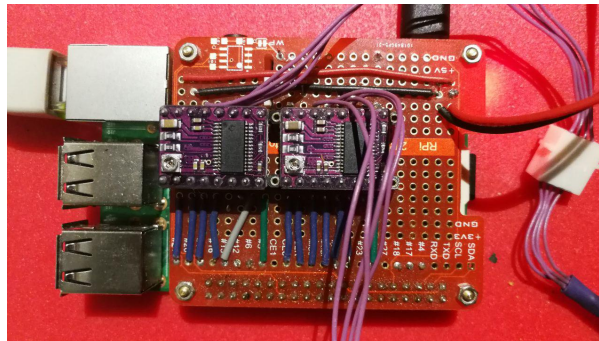
Drivers interact with the real hardware and normaly are used in the **node** code.

Motors

Raspberry Drivers

rpiDRV8825Hat

This is a DIY Raspberry Pi Hat base on the popular stepper control chip DRV8825



API DIY DRV8825 driver Hat interface.

This board has two DRV8825 able to driver 2 motors See hardware on termiteOS/driver/rpi/hardware

INTERFACE TO OTHER MODULES:

- motorBeta
- pinout
- microsteps
- clutch()
- reset()
- sleep()
- set_microsteps(microsteps)
- sync(motorBeta)

```
class termiteOS.drivers.rpi.rpiDRV8825Hat.rpiDRV8825Hat (raspberry, driverID,  
                                                         **kwds)
```

This class define the PIN mapping and basic methods for the rpiDVR8825 Hat

Note: Possible values of driverID can be 0 or 1.

clutch (*ON_OFF*)

Engage or Disengage(free spinnig) the motors

fault (*gpio, level, tick*)

Callback function to check internal driver faults

reset (*ON_OFF*)
Reset the driver circuit

set_dir (*dir*)
Set the direction of motion

set_microsteps (*microsteps*)
Set microstepping mode of the driver

sleep (*ON_OFF*)
Sleep or wake up the driver circuit

stepcounter (*gpio, level, tick*)
Callback function to update internal position counter

sync (*position*)
Set the actual internal position == position

test ()
Test the Hat sending steps

rpiSpeedPWM

A PWM driver

API Raspberry PWM motor driver.

```
class termiteOS.drivers.rpi.rpiSpeedPWM.rpiSpeedPWM(driverID, microsteps, FullTurn-
                                                    Steps, gear=1, name='Axis',
                                                    raspberry='localhost')
```

This class do the PWM control calling the underlying pigpiod daemon.

Note: Up to dates only PID control is implemented.

SetPoint (*setpoint*)
Establish the _SetPoint value

clutch (*ON_OFF*)
Engage or Disengage(free spinnig) the motors

fault (*gpio, level, tick*)
Callback function to check internal driver faults

goto (*setpoint, blocking=False*)
Absolute movement

gotoEnd
True if the axis finally arrive to destination(_SetPoint), False otherwise

isStopped
True if is stopped, False otherwise

move (*relsetpoint*)
Relative movement

pos
Actual position (Corrected motorBeta)

reset (*ON_OFF*)
Reset the driver circuit

run (**args, **kwargs*)

setRPM (*rpm*)

Set and start PWM to obtain rpm

setSpeed (*v*)

Set and start PWM to obtain radians/seconds

set_dir (*dir*)

Set the direction of motion

set_microsteps (*microsteps*)

Set microstepping mode of the driver

sleep (*ON_OFF*)

Sleep or wake up the driver circuit

stepcounter (*gpio, level, tick*)

Callback function to update internal position counter

stop ()

Not implemented

stopPWM ()

Stop PWM generation without any check

sync (*newposition*)

Establish newposition as current position (motorBeta)

test ()

Test the Hat sending steps

trackSpeed (*trackSpeed*)

Set axis track speed. Track speed*timestep is add to the _SetPoint value

`termiteOS.drivers.rpi.rpiSpeedPWM.threaded` (*fn*)

Multithread wrapper. Used as a function decorator

Miscellaneous

TBD

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