Motorize 1980 dad's telescope

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December 11, 2021

Abstract

A 1980 (old and dusty) equatorial telescope is converted to an up-to-date, motorized and computer-connected telescope. We, me and my father, illustrate all the transformation steps from an old, dusty and unused telescope into an optimal tool for astrophotography.

Contents

Figure 1: Urania telescope and mount.

1 Telescope Description

The starting point of the project is of course the telescope. In our garage, for many years, a 1980 Urania telescope has eaten a lot of dust. The telescope's mirror resent of years in humidity and temperature jumps in the garage. In the beginning, we have cleaned the silvered-mirror with soap and water, but the silver still seemed to be a bit compromised. We do not talk long about this telescope, since we have soon substituted it with a brand-new Skywatcher Quattro. The latter is placed on the Urania mount, since it is still a nice mount and, in our advice, has still not surpassed robustness. Indeed, the mount is a very heavy (telescope and mount totally weight 20kg!) equatorial and motorized (still works!) mount.

For our money, but most importantly for our fun and entertainment, we decided to modernize our old telescope.

1.1 Urania telescope

We briefly add the specifics of the old Urania telescope, as a sort of respect for many years of honorable work before the deep dark in the garage.

The telescope is a Urania C.R.T. NX 155, as the one in figure **??**.

Specific name	value
type	reflector
technique	Newton
material	PVC
weight (kg)	10
aperture (mm)	155
focal length (mm)	1000
focal	f/6.5
resolution power	0.8
limit magnitude value (mag)	13.6
Mirror Treatment	Silica monoxide

Table 1: Urania C.R.T. NX 155 specifics.

1.2 Telescope's mount

The telescope is place onto an aeronautic Aluminum tripod equatorial mount.

Specific	value
weight (kg)	
type	fork
material	Aluminum alloy
RA axis diameter (mm)	30
RA axis material	cadmium steel
RA motor	3W synchronous

Table 2: Urania's mount specifics.

Starting from the bottom: three pods of 30cm depart from a central post. Each one has a wheel which permits the structure to move freely and then to fix the position using stops. The central post terminates with the second axis holder at an inclination equal to the Earth's ecliptic $23.43° = 23°26'$.

This axis must be aligned with the Polar star (labelling the North). In this way, a 3W synchronous motor can follow the sky movement.

Departing from this second axis, a two-arms fork is free to rotate around two degrees-of-freedom defining the right ascension (RA) and the declination (DEC). The two arms are separated by the distance $d = 15$mm which is the Urania telescope aperture.

1.3 Skywatcher 8P Quattro telescope

Skywatcher 8P Quattro Newtonian telescope (figure **??**) offers an optimal astrophotography performance. For this reason we have decided to substitute the Urania telescope with this brand-new Skywatcher telescope.

Specific name	value
type	reflector
technique	Newton
material	Carbon
weight (kg)	8.0
aperture (mm)	200
focal length (mm)	800
focal	f/4
resolution power	0.58
limit magnitude (mag)	13.3
collect light	820
magnification	400
Mirror Treatment	Aluminum Coating
Focuser	Crayford dual-speed 50.8/31.8

Table 3: Skywatcher 8P Quattro

Figure 2: Skywatcher Quattro telescope.

Since the Skywatcher telescope does not fit in the fork, we have thought to build a "saddle" onto which placing the telescope. The specifics of this installation are shown in the following section.

2 Telescope substitution: from Urania's tube to Skywatcher's tube

Passing from the Urania telescope to Skywatcher telescope we have faced the problem of how to insert the latter in the telescope mount. Indeed, since Skywatcher's telescope diameter is 200mm it does not fit inside the mount fork.

Our solution is to insert a seat in which to place the telescope. The barycenter of the telescope is not centered with the DEC axis, thus we have settled a post capable of holding weights to balance the forces. See figure **??** and **??**.
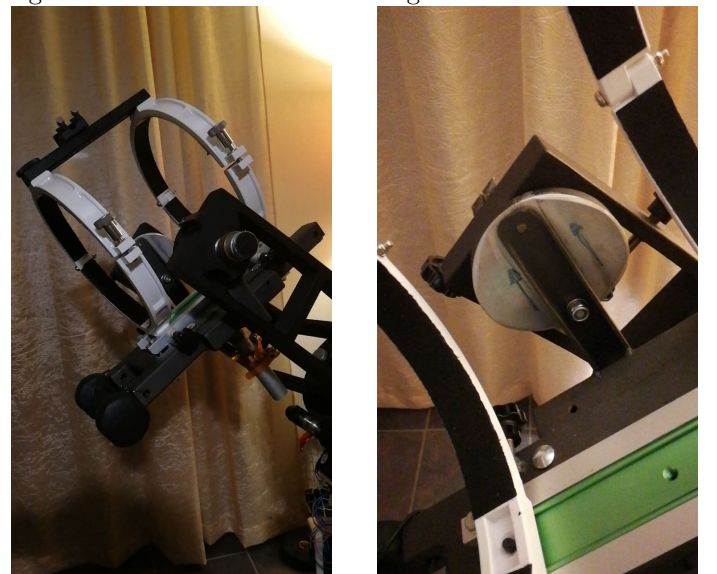

Figure 3: The mechanism built to insert Skywatcher's telescope into the Urania robust mount.

Figure 4: detail of the replacement plate that supports the new telescope.

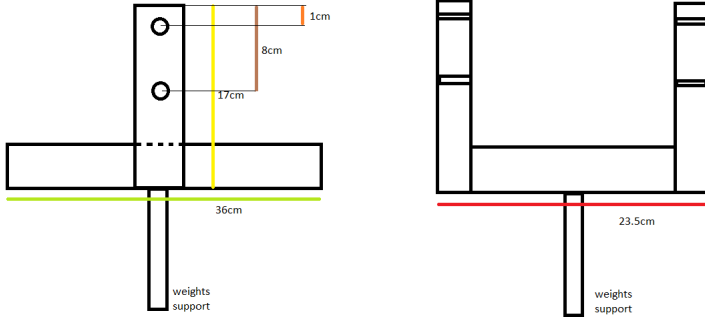The scheme with distances is visible in figure **??**.

Figure 5: Schematic view of the telescope mount insertion. This represents only the installation build with some squared metal bars upon which the two white loops (which hold the telescope tube) are fixed and are not illustrated in this scheme. The two holes in each arm serve to fix the structure on the mount.

Lastly, to enhance the fluidity of motion and reduce the backlash, the rotation mechanism is enriched with a system of two bearing for each fork arm, one interior and one fixed in the mount externally, see figure **??**.
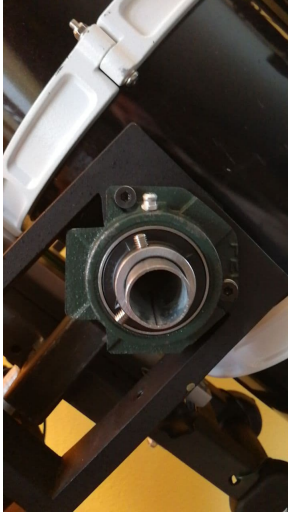

Figure 6: External bearing mounted on one fork arm.

3 Motorization: microcontrollers

3.1 The Arduino experience

We decide to write this section more as an advertisement to not follow this way than for other purposes.

The first, natural, approach was to try to use some at-home-technology. Alone on a shelf, an Arduino UNO R3 card was waiting to take part of another project with some friends: a 28BYJ-48 stepper motor and colorful cables. What a better occasion to be mounted on the telescope in turns of the 3W motor?

With some fortunate events, the stepper motor is adapted to the telescope's RA rotating worm shaft. Was it good as a tracker motor with a constant motion? The answer is no. Indeed, some tests revealed bad performances like the inconstant rotation and several stops due to lack of robustness of the motor. This result was easily supposed from the beginning, but this try was costs-less, *i.e.* free since all the components were at home. Indeed, citing Wayne Gretzky:

"you miss one hundred percent of the shots you don't take",

so it was a matter of must-a-do proof. It also gave us the opportunity to face some *engineering* problems.

During a little internet journey, we have found a new stepper motor with a nema 17 standard; we have bought two kinds: one of the more robust stepper motors on store and one less robust.

The 28BYJ-48 stepper motor, sadly, returns onto its shelf as, shortly after, would do the Arduino UNO card.

3.2 Stepper motors

In this subsection we write the specifics of the stepper motors used for the RA and DEC mechanization (for both we have used nema 17 motors) and the focuser (developed with a nema 11 stepper motor).

17HM15-0904S stepper motor

Electronics	
Manufacturer code	17HM15-0904S
Engine type	bipolar
Pitch angle (deg)	0.9
Torque (Ncm)	36
Rated current/phase (A)	0.9
Phase resistance (Ohm)	60
Voltage (V)	5.4
Inductance (mH)	$12 \pm 20\%$ (1 kHz)
Physical specifications	
Frame dimensions (mm^2)	42x42
Body length (mm)	40
Shaft diameter (mm)	5
Stem length (mm)	22
D-cut length (mm)	15
Number of cables	4
Lead number (mm)	300
Weight (g)	280

Table 4: Nema 17 (0.9A) stepper motor specifics.

17HM19-2004S1 stepper motor

Electronics	
Manufacturer code	17HM19-2004S1
Engine type	bipolar
Pitch angle (deg)	0.9
Torque (Ncm)	46
Rated current (A)	2
Phase resistance (Ohm)	1.4
Voltage (V)	2.8
Inductance (mH)	4
Physical specifications	
Frame dimensions (mm^2)	42x42
Body length (mm)	48
Shaft diameter (mm)	5
Stem length (mm)	24
D-cut length (mm)	24
Number of cables	4
Lead number (mm)	500
Weight (g)	370

Table 5: Nema 17 (2A) stepper motor specifics.

11HS12-0674S stepper motor

Electronics	
Manufacturer code	11HS12-0674S
Engine type	bipolar
Pitch angle (deg)	1.8
Torque (Ncm)	7
Rated current (A)	0.67
Phase resistance (Ohm)	5.6
Voltage (V)	3.8
Inductance (mH)	4.2
Physical specifications	
Frame dimensions (mm^2)	28x28
Body length (mm)	31.5
Shaft diameter (mm)	5
Stem length (mm)	20
Number of cables	4
Lead number (mm)	300
Weight (g)	110

Table 6: Nema 11 stepper motor for the focuser motion specifics.

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9ab27019d8e1b705a633b8a8f9078a39849eb76c

Figure 7: ESP32 D1 R32 picture.

3.3   ESP32

After buying the new stepper motor, on the internet we have found good impressions on the ESP32 microcontroller. ESP32 is a series of low-cost, low-power system on a chip microcontroller with integrated Wi-Fi and dual-mode Bluetooth. We've bought the ESP32 D1 R32, the one in figure **??**, for better attaching the motor using the CNC shield V3 (which is briefly explained in the following). Also, Arduino returned on the self with its friends.

We bumped into a OnStep project (at `https://onstep.groups.io/g/main/wiki/19670`) which an open source software providing the control of four stepper motors (RA, DEC, focuser and rotator for astrophotography), weather sensor handling, Wi-Fi and Bluetooth connection, polar alignment and other nice features. We decided to follow the "Wemos R32 and CNC V3" project.

3.4   CNC Shield V3

To better optimize space and wires connections, we have bought a CNC Shield V3 (aka CNC3), see figure **??**.

Figure 8: CNC3 Shield V3.

It is an add-on shield, built to be used for 3D printers. It has 4 slots, each one can host a motor driver.

3.5   Motor drivers

A stepper motors works only with a driver chip that controls the motor movements. Three types of drivers have been used during the configuration of the setup.

1. DRV8828;

2. TMC2209;

3. TMC2208.

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[1]See `https://all3dp.com/2/vref-calculator-tmc2209-tmc2208-a4988/` for more details.

In each driver the right amount of current is set, otherwise the stepper motor could work improperly. This current depends on the stepper motor current per phase parameter. Typically, drivers have a tunable screw for the tension V_{ref}. For each type of driver, the formula to calculate the tension V_{ref} depending on the current/phase are different.[1]

The procedure is the following:

- rotate the screw in the counter clock direction;

- using a multimeter, check that the tension is zero;

- slightly rotate the screw until the tension is the desired one.

We recommend reducing the theoretical value by a 10%-30% to prevent motor dangers.

3.5.1 DRV8825

For these drivers the tension to be set is roughly the half of the value of the nominal current/phase of the motor. For example, if the motor has a current/phase 1A, the tension would be 0.5V.

Current phaser (A)	Current (A)
0.90	0.45
2.00	0.90

Table 7: DRV8828 drivers setup current. Note that we have set a value smaller than the one calculated to prevent motor to break.

3.5.2 TMC2208 and TMC2209

For these drivers the tension value is roughly the same of the current/phase value, *e.g.* if $I = 1$A the tension would be $V_{ref} = 1$V. Be aware that the TMC2208 has a maximum current output of 1.2A.

The calculation is

$$\frac{I}{\sqrt{2}} = \frac{325mV}{110m\Omega + 20m\Omega} \cdot \frac{1}{\sqrt{2}} \cdot \frac{V_{ref}}{2.5V} \Rightarrow V_{ref} = I \cdot 1\Omega.$$

Remember to reduce to value by a 10%-30%.

Driver	Current/phase (A)	Current (A)
TMC2208	0.90	0.81
TMC2208	2.00	1.63
TMC2209 (focuser)	0.67	0.50

Table 8: DRV8828 drivers setup current. Note that we have set a value smaller than the one calculated to prevent motor to break.

3.6 Power supply

The power supply is provided by a 19V 5A power supply as in table **??**.

voltage output (V)	current output (A)
19.3	4.74

Table 9: Nominal tension and current outputs of the power supply.

For our initial purposes it was enough, indeed 5A are enough to feed quite well two stepper motors and a poor electronics. A rough estimation poses 1.8A for DEC motor, 0.9A for RA motor and few milliampéres for the ESP32. The reader is strongly encouraged to check the total current its circuit needs before buying a power supply.

3.7 Sensors: Wi-Fi connection, Real time clock (RTC) and weather sensor (BMP280)

An ESP8688 WeMos D1 mini is connected to the CNC3 as shown in `https://onstep.groups.io/g/main/wiki/19670`.

This OnStep has a software addon called the Smart Web Server (SWS) which provides WiFi or Ethernet connections over IP. Many devices support this type of connection including cell-phones, tablets, laptop/desktop computers, etc. Using this library, it is possible to use programs such as Stellarium via ASCOM drivers provided by the OnStep project `http://www.stellarjourney.com/index.php?r=site/software_telescope`.

4 Motorization: the mechanics

The motorization of the telescope passes through two mechanics adjustments:

1. motorize the RA movement, exploiting the native tracker mechanism;

2. motorize the DEC movement, which natively has no gears.

4.1 RA motorization

The telescope's mount has already a tracking mechanism motorized by a 3W synchronous motor. So, in principle, it is only a matter of substitute this old motor, with a new programmable stepper motor.

The gears are composed by:

- a 359 teeth stage (1 tooth for each degree, fantastic);

- an endless screw (worm) mounted on a shaft through a clutch.

Using this structure, for a continuous sky tracking, the elder motor would complete a round of the worm in 4 minutes. Thus, this mechanism rotates the mount with the velocity of a degree in 4 minutes (which is the velocity of the sky moving away in the night).

We have reduced the ratio by a third adding two other gears (see figure **??**): 60 teeth gear positioned in the shaft and a 20 teeth gear on the motor shaft.

ratio gear 1	ratio gear 2	total ratio
1/360	1/3	1/1080

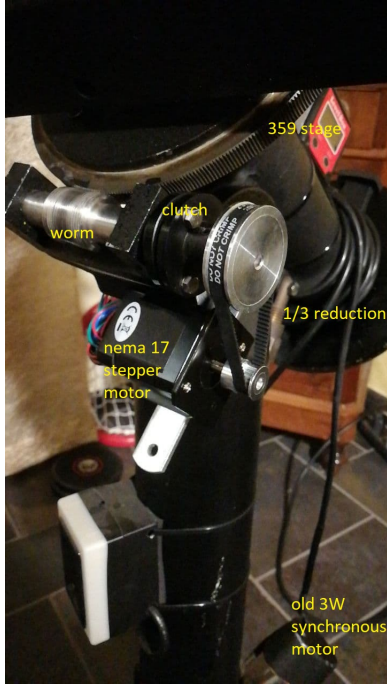*Table 10: Total reduction of RA mechanization.*

Figure 9: Nema 17 stepper motor and gear adjustment.

We have choose to install a nema 17 stepper motor with the specifics in table **??**

4.2 DEC motorization

The mechanization of the DEC axis was a bit more complicated since there was not a built-in gear to use. We tried different versions. A first successfully try was to exploit a stand-alone disk. On the edge of the latter are present some ticks and grades: it was used a declination angle teller.

As told above, we have tried different configurations but same stepper motor is used.

4.2.1 DEC V1

The first version is made using the built-in graded disk mounted on the telescope. On this, is attached a 32cm long chain strip. Then, a 1/3 reduction shaft is positioned between the first gear and the stepper motor's gear. The total reduction with all gear specifics is reported in table **??**. Figure **??** is a picture of the mechanism.

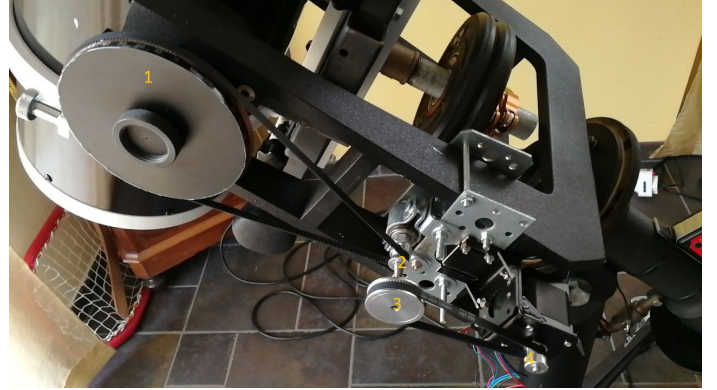| DEC-V1 stages				
Gear number	1	2	3	4
number of teeth	188	20	60	20
total ratio	$\sim \frac{1}{28}$			

Table 11: DEC mechanism's gear specifics.

Figure 10: DEC mechanism.

This solution seemed to be efficient, but easy to adjust. Also, the stage reduction is too low for a good movement precision.
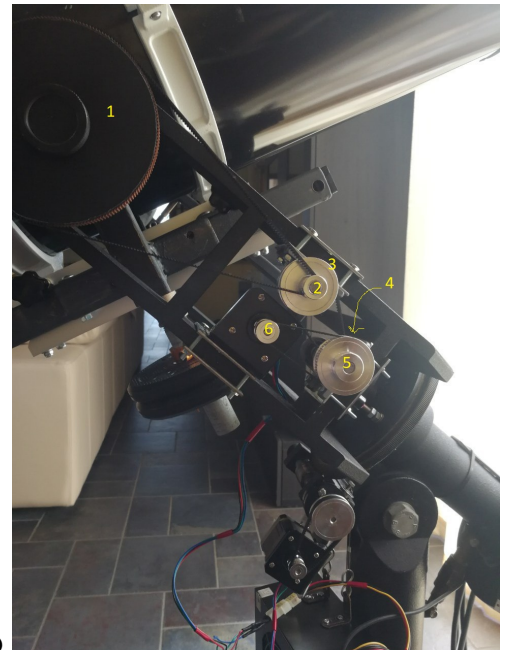
4.2.2 DEC V2

<<<<< HEAD The second version is made uses again the built-in graded disk mounted on the telescope. Also on this, is attached a 32cm long chain strip.

======= The second version made uses again the built-in graded disk mounted on the telescope. Also on this construction is glued a 32cm long chain strip. Then, a 1/9 reduction is positioned between the first stage and the stepper motor. The total reduction with all gear specifics is reported in table **??**. Figure **??** is a picture of the mechanism.

>>>>> 9ab27019d8e1b705a633b8a8f9078a39849eb76c

DEC-V2 stages						
Gear number	1	2	3	4	5	6
number of teeth	188	20	60	20	60	20
total ratio	$\sim \frac{1}{84}$					

Table 12: DEC mechanism's gear specifics.

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Figure 11: DEC V2 mechanism.

Then, a 1/9 reduction is positioned between the first stage and the stepper motor. The total reduction with all gear specifics is reported in table **??**. Figure **??** is a picture of the mechanism. =======
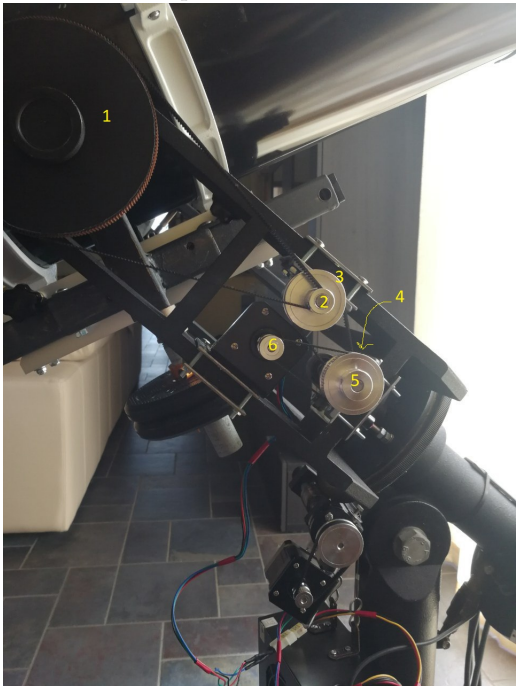

Figure 12: DEC V2 mechanism.

DEC-v3.jpg

4.3 DEC V3

The third version uses a 3D printed double-belt gear mounted on the telescope. Then, a 1/10 ratio is obtained using a worm gear and another 1/3 is obtained between the worm and the final gear. The total reduction with all gear specifics is reported in table **??**. Figure **??** is a picture of the mechanism. »»»> 9ab27019d8e1b705a633b8a8f9078a39849eb76c

DEC-V2 stages					
Gear number	1	2	3	4	worm
number of teeth	180	30	60	20	10
total ratio	$\sim \frac{1}{180}$				

Table 13: DEC mechanism's gear specifics.

stepper-motors-cables.png

4.4 Focuser motorization

Another improvement is the motorization of the focuser. Using a nema 11 stepper motor, we have created the motor supports and the gears using a 3D printer. The reduction stage is 3, see figure **??**.

5 Cable management

The wiring between the electronics and the motors is made focusing on the main idea to attach and detach them rapidly. We thought to use Ethernet cables. They are a versatile solution but how to connect them to the four cables governing the stepper motor?

Stepper motors have four cables, see figure **??**, which have to be driven to the CNC3.

BOX.jpg

5.1 Ethernet cables

Ethernet cables are composed typically by 8 thin cables, each one carrying very few Amperes, approximately $0.3 - 0.5A$. Since stepper motors require currents of the order of $1A$, we decided to use them in couple, according to the general Ethernet cabling scheme. Thus, the four motor cables are doubled and fixed into the eight way Ethernet socket.
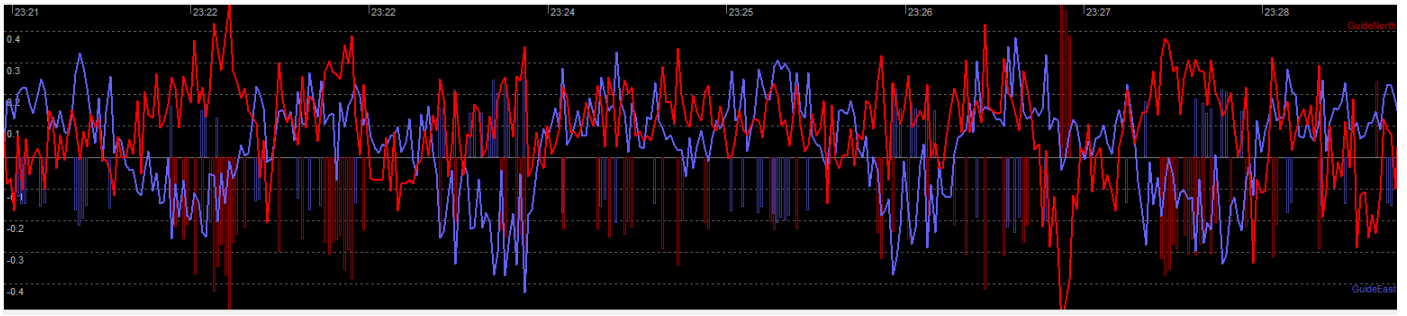
Figure 14: DEC V3 test: PHD2 log view using pixel as units.

Then, the main box is prepared to receive the Ethernet cables. In the most remote drawers of the garage, we have found an old and burned electronic card with four Ethernet sockets, a power supply entry and an on/off switch. Using a multimeter we have checked the pins of each slot and created the connections to the CNC3 shield.

In figures **??**, **??** and **??** are shown some examples of Ethernet wiring.

5.2 Plastic boxes

Using a 3D printer, we have created the focuser motor box with the Ethernet exit, and so we did for the RA motor. The microcontroller, the CNC3 shield, the power supply and all the electronics have been thrown in a box. The stepper motors drivers after a while become very hot, then we have decided to put a fan in the box. In figures **??**, **??** and **??** are shown the resulting plastic boxes.

RA-box.jpg
FOCUSER-box.jpg

6 Tracking

Sidereal tracking is done by the OnStep software, of course. Otherwise, since the polar alignment may not be perfect we have decided to equip the telescope with an auto-guiding system controlled by the PHD2 app. This, in our mind, should optimize the tracking and permits long-exposure photography which is necessary for optimal results.

Although separated by the previously mechanization, this auto-guiding system interacts with the mount using ASCOM OnStep telescope drivers, and provide corrections to the tracking.

6.1 Telescope   guidescope

On the telescope is fixed a 240mm focal length guidescope Svbony SV106.

6.2 Guidescope   camera

The camera is an old red webcam inserted into the guidescope using an adpter.[2]
The result is pretty weird, but it works! Just look at the following sections PHD2 logs!

7 The   software

Now comes the software part. In our mind, we wouldn't want to spend much time on programming. We desired a plug-and-play solution, or something similar. A software with easily controlling and possibly which can talk via ASCOM drivers with Stellarium (or others), PHD2 and others astrophotography programs.

7.1 OnStep

On the internet, we have found a great, open-source, free and customizable software called OnStep.[3] We have followed the instructions for the WeMos D1 + CNC V3 project, configured the Config.h file and upload the sketch on the ESP32 board. Finally, the box is placed on the mount and connected with the Ethernet cables to the motors

7.2 PHD2

Push It Dummy-2 is the software that controller the auto-guiding system. PHD2 is telescope guiding software that simplifies the process of tracking a guide star, letting you concentrate on other aspects of deep-sky imaging. There are plenty tutorials on the internet showing how to use PHD2, so we do not enter so much into details.[4] But we only want to stress out that, after few important configuration passes, the auto-guiding is really simple and promises very good results!

7.2.1 Wizard   configuration

Connection is really simple using the "wizard" option suggested in every tutorials. The "unbinned pixel size" is one of the first parameters you have to fix in the wizard which are not quite clear. You should be able to get the unbinned pixel size from the camera spec sheet or the manufacturer's web site. If this is not the case, you can get the unbinned pixel size by taking the dimension of the sensor and diving it by the number of pixels.
The "bin level" is the technique to combine proximal bins to form a "superpixel".[5] This has the effect of reducing the noise but at the price of reducing the image definition.
Another remarkable option to fill is the telescope mount's driver, which in this case are the ASCOM OnStep telescope drivers.

7.2.2 Dark   libraries

Before starting the first guiding session, it is useful to spend 5 minutes to create a dark library. To do so, just press the "Dark" tool on the top and create a new dark library. Cover the guidescope, and start the acquisition.
After the acquisition, remove the cover; this should make clearer acquisitions.

7.2.3 Connect   all!

After the configuration, press the first icon in the bottom left and press "connect all". Now the camera and the mount are connected to PHD2.

7.2.4 Calibration

Search a bright star whose declination is between 10 to -10 degrees. Start the acquisition pressing the "cycle" icon (the second from the left), then press the "star with a magnifying glass" that selects the most bright star. Finally, push the PHD2 icon; this will start the calibration and requires few minutes.

7.2.5 Guiding

If dark libraries and calibration are done, the guiding can start. If it is not present, search in the settings the plot visualization that let you know the adjustments that PHD2 is doing. In our case, it is a useful tool to see if our work were precisely enough.
A useful tool is the "use multiple stars" in the guiding settings. The latter permits holding multiple star, and we think this is another improvement to stability in auto-guiding.

7.3 Stellarium

Stellarium is the software we use to search objects. The impressive feature is that, after paring it via ASCOM drivers with the mount, it is possible to tell the telescope to move at the star pointed out in Stellarium.[6]
The telescope is now free to start few tests to check the goodness of our work!

8 Tests

The test are aimed to estimate the precision of the mount. Of particular interest are the test using PHD2 which measure the precision in micro-adjustments for the auto-guiding system.
The application used to study the PHD2 plots is the PHD2LogViewer app. The latter can upload all the guiding session you make, since every session is stored in the PHD2 folder. The app also make raw statistical analysis which are good parameters to think about. The root-mean-square (RMS) describe the spread of the data points around some average peak value (like standard deviation). The value of RMS should be 1 arcsecond or lower for a good guiding.

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[2]See this useful tutorial `https://telescopeguides.com/how-to-use-a-webcam-with-a-telescope/`.

[3]Wiki groups:`https://onstep.groups.io/g/main/wiki/3860`.
Github:`https://github.com/hjd1964/OnStep`.

[4]`https://www.youtube.com/watch?v=Kd4qzW7uV38` or the pdf `https://openphdguiding.org/man-dev/Basic_use.htm`.

[5]`https://www.photometrics.com/learn/imaging-topics/binning-2`.

[6]See `https://www.youtube.com/watch?v=DUdYv311HFw`.