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In Partial Fulfillment

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Master of Science in Mechanical Engineering

by

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ABSTRACT

Title

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# Introduction

## Statement of Purpose

A previous thesis at California Polytechnic State University, San Luis Obispo[ CITATION Gud15 \l 1033 ] demonstrated the feasibility of a three degree-of-freedom parallel actuator telescope mount based loosely on the six degree-of-freedom Array for Microwave Background Anisotropy (AMiBA) telescope. The shorter load paths created by the parallel actuators result in a stiff, light system with a high natural frequency, which is good for accurate pointing. This simplified mount sacrifices full sky coverage for portability, and lower cost. The purpose of this thesis is to refine the proof-of-concept developed at Cal Poly with commonly available, lower priced components and to develop code which can be utilized by universities and astronomers to create their own parallel actuator telescope mounts.

## Description of System

Mr. Gudgel approached the issue of transportability, long exposure image rotation, and excess required mass with his telescope mount. In his investigation, he found that current telescope mounting systems could be improved for the use of amateur and small scale research purposes which did not require full sky coverage nor full 6 degree of freedom capabilities. His goal was to create a system which was less massive and more transportable without sacrificing stiffness or accuracy.

His solution to these issues was to design a mount system, based on the AMiBA telescope, which used linear actuators in parallel instead of rotational actuators in series. This allowed him to build image rotation into the system as well as to create simpler loading paths which lower the overall mass/strength required of each actuator.

## Scope of Thesis Project

The goal of this thesis is to build upon the partial proof-of-concept prototype in order to demonstrate the capability of the system to accurately point at and track stars. This includes improvements to the mechanical, electrical, and control system. A focus will be on the simplification of the system, cost saving, and the use of off-the-shelf parts in order to increase the feasibility of the design for educational and hobbyist use.

(Implement stepper motors in place of the existing gear motors, correct issues in design and manufacturing, and to demonstrate constant angular velocity movement).

# Background

## State of the Art

Telescope mounts have three angles of interest which are used to describe where the telescope is pointed and the orientation of the telescope towards that point. These three angles can be defined in various ways. These definitions can be directly converted from one to another. The most applicable definition is the use of altitude-azimuth. Altitude is defined as the angle above the horizon. Azimuth is the angle about an axis perpendicular to Earth’s surface starting from some reference point, generally north or south. The third angle, which is not a controlled angle in all mounting systems, is the rotation of the object with respect to the telescope itself. Usually, this last angle wants to be kept constant. (Insert alt-az reference image)

(theory of pointing a telescope -- the way we take latitude, longitude, right ascension, declination, and time and turn that into altitude, azimuth, and rotation.  It's not that you're doing anything new in this section, but it would be helpful to define the terms and algorithms as they're being used in this project.  Also, it looks nice and theoretical and math-y, which helps keep the MS (as opposed to Senior project) feel.)

### Traditional Telescope Mounts

Traditional telescope mounts generally use one actuator per angle of interest. These actuators are necessarily mounted in series such that each actuator must hold the entire weight of the telescope as well as that of each actuator above it. This results in large required actuation strength as well as massive systems to get the required stiffness.

The most basic mount, referred to as an altazimuth mount, has a rotational actuator which directly moves the azimuth angle. On top of that, is a second actuator which controls the altitude angle. The altazimuth mount generally has no way to directly control the image rotation angle and requires that functionality to be built into the telescope itself through means of an image derotation device.

The equatorial mount is an example of one which controls the image rotation. Instead of having an actuator which controls the angle, a mechanism allows the whole telescope to tilt to match the Earth’s rotational axis which causes the image rotation to remain constant. This unfortunately creates complicated load paths and often necessitates large counterweight systems.

### Hexapod Mount

The Stewart platform was initially conceived of as a method of simulating flight conditions for pilot training (Stewart, 1965). It is a mechanism based on six independently actuated legs which provide six degrees of freedom: x, y, z, pitch, roll, and yaw. Stewart platforms are used in machine tools, flight simulators, and astronomy (Koch, et al., 2009).

In 1969, Peter Fellgett proposed the use of the Stewart platform for astronomical purposes using hydraulic actuation. In 1989, a 1.5m prototype of a hexapod telescope was funded in Germany with the intent of proving the concept for use with a 12m telescope. The mechanical system was completed and demonstrated to meet the required specifications but the full telescope was not completed due to complications stemming from the reunification of East and West Germany. (Chini, 2000)

In 2006, observations began at the Array for Microwave Background Anisotropy (AMiBA). It is the largest hexapod telescope in operation. The hexapod mount was chosen for this application based on size, weight, accessibility and portability requirements. (Koch, et al., 2009)



Figure : AMiBA in neutral position. (Koch, et al., 2009)

### The Gudgel Mount

The Gudgel mount is a novel modification of the hexapod mount. It is composed of three linear actuators, a three degree-of-freedom ball-in-socket joint, six two degree-of-freedom joints, a baseplate, and a frame which contains and/or represents the telescope.

In this system a large portion of the load is supported by the ball-in-socket joint with the remaining load being shared between the three linear actuators.

#### State of Hardware

Insert pictures and information from Garrett’s thesis

#### State of Software

The software developed by Mr. Gudgel was used as an inspiration for this project but it was decided to change languages to increase simplicity and to take advantage of newer tools that have become available. The previous software was written in mbed C/C++. The new software is written in micropython



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# Theory

## Transformations

In order to find the actuator lengths required to match a particular set of altitude, azimuth, and image rotation angles, a known reference position must be defined. This reference position, called ‘home’, contains complete information of the locations of points of interest: both ends of each actuator, a point on the image axis, and the point of rotation. This position, along with rotation matrices, allows us to find the required lengths.

All desired angular positions are treated as rotations away from the home position. This requires three primary rotations which match the altitude, azimuth, and image rotation angles desired and three correction rotations which account for the home position not perfectly matching 0,0,0 altitude, azimuth, image rotation. These rotations can be combined in a particular order to find a resultant combined transformation. Because the correction rotations are constant angles, this can be simplified to:

In order to find the length of each actuator for a specific set of altitude, azimuth, and image rotation angles, first the combined transformation matrix must be evaluated with the set of angles and applied to each of the home positions of the actuator ends. This finds the new location of each actuator end. Then, the distance formula is applied between this location and the stationary base of the actuator in order to calculate the required length.

## Angular Velocities

Angular velocities are calculated by discretizing the movement over small time steps. The first step is to determine what length each actuator should have at some specific moment in the future. Basic kinematic equations with constant angular acceleration lead to:

Utilizing the transformations developed above in conjunction with these new angular positions results in the required lengths of each actuator.

The definition of linear velocity as the rate of change of position is then used to calculate the required angular velocity.

Once the system has run for time, the process starts over and a new future position is calculated.

## L6470 Stepper Motor Drivers

The L6470 stepper motor driver from ST is a fully integrated bipolar stepper motor driver with microstepping (STMicroelectronics). This driver is communicated with over i2c and is “smart”. An onboard microprocessor handles the stepper motor feedback and control. It allows for simple commands to be sent such as ‘Run’, ‘Move’, and ‘GoHome'. This greatly simplifies the control scheme for the project.

# Design

## Primary Issues of Previous System

Manufacturing

Price

Custom electronics

## Hardware Modifications

### Change from gear motor to stepper motor

The change from gear motors to stepper motors is a fundamental design change motivated by lowering cost and simplifying the control scheme (see Electrical Modifications).

#### Advantages

Stepper motors are the least expensive method of implementing precise angular motion. They are used in many industries including having a strong presence in the astronomy field (Anaheim Automation). Stepper motors, in conjunction with high quality drivers, are very simple to control for both position and velocity.

#### Disadvantages

The largest issue with the change to stepper motors is that it shifts closed loop control from the motor/encoder to a telescope camera and plate solver. As the camera and plate solver are beyond the scope of this project, it must be assumed that a commanded position change occurs instead of being able to track the change. This is a decent assumption if the stepper motors are rated appropriately for the system requirements.

### Manufacturing Repair

There were several issues with the build of the physical system. The two primary issues were non-concentricity of the couplers, which led to significant wobble in the rods, and too large of tolerances in the (beer cans) which added significant backlash to the system. The couplers were remanufactured which led to a visible increase in the smoothness of the telescope motion. Thrust bearings were installed between the rotary portions of the (beer cans) and all the joints were greased to prevent further wear and help smooth the motion.

### Frame instead of telescope

The telescope and rails used in the previous system are very heavy. It was decided to replace the telescope with an aluminum frame for the purpose of this project in order to ensure the accuracy of the assumption described in section 4.2.1.2.

## Electrical Modifications

The electronics were replaced by off the shelf products as much as possible. This was only possible because STMicroelectronics has created

### ST L6470 Stepper Motor Drivers

### Nucleo Boards

## Software Modifications

It was decided to write this project in Micropython because it allowed for easier development, the code could be easy for other users to modify, and it gives access to utilities like AstroPy.

# Testing and Verification

## Testing Set Up

All tests are performed using laser diodes mounted to the front of the telescope stand in frame. Three lasers are required to perform all the tests. The primary laser is used for repeatability tests and relative angular motion tests. This laser is mounted on an axis parallel to the telescope optical axis and goes through the center of the pivot point. The alignment of this laser is not critical for repeatability tests but is vital for relative motions tests. Deviation from the described positioning can have a major impact on comparative measurements.

The second and third lasers are used for measuring relative image rotation angle. They are also mounted parallel to the telescope optical axis but they do not need to go through the center of the pivot point. These two lasers should be on the same level such that if the telescope were pointed at a wall with all angles at 0, the two marks would be horizontal.

The apparatus should be oriented relative to a vertical surface (wall) with the X-Y plane parallel to the wall and the X-Z plane perpendicular to the wall. The origin of the apparatus should be as far as possible from the wall but the optical axis laser must remain on the wall at the extremes of the desired testing area.

## Test Descriptions

### Relative Positioning

The current system does not have an absolute reference for its positioning so all position testing must be done as relative testing. This is sufficient for the purpose of this thesis because a future refinement would be to incorporate feedback via a plate solver.

#### Rotation

The point rotation test is designed to test the relative accuracy of commanded image rotations. This test utilizes two laser diodes mounted on the front of the telescope. The telescope is commanded to a position with zero image rotation angle, then the two lasers are marked on the wall this will be the reference angle. Without moving the telescope base, it is commanded to another position with the same altitude and azimuth but different image rotation. The lasers are again marked on the wall. These sets of points are connected to create two lines which should be at the commanded image rotation angles relative to the horizontal. A photograph of these lines is then taken to be analyzed.

Using matlab (see appendix XXX for code), the angle of the reference angle and the angle of the second position are measured. Subtracting the reference angle from the angle of the second position, a relative angle is calculated. Comparing this to the expected angle results in a measure of the relative accuracy.

#### Altitude

### Velocity

Velocity testing is accomplished by commanding the apparatus to two points and marking them on the wall. When the apparatus is aimed at one of the points, command it along the vector that will intersect with the second point. Either film or time the motion between the two points.

### Repeatability

Repeatability is tested by moving between a series of points multiple times and seeing how much deviation there is between the first time and subsequent moves

### “Wobble”

I’m not sure what to call this section. Basically measuring how much variance in position the system can have when commanded to a specified angle.

## Future Refinement

Pairs of bearings at each motor

Better software

Interface with external software

## Summary

# Bibliography

Anaheim Automation. (n.d.). *Stepper Motor Guide*. Retrieved August 4, 2017, from Anaheim Automation: http://www.anaheimautomation.com/manuals/forms/stepper-motor-guide.php

STMicroelectronics. (n.d.). *L6470.* Retrieved July 2017, from STMicroelectronics: http://www.st.com/resource/en/datasheet/l6470.pdf

Appendix A –

Objective:

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Given:

* Placeholder text… Insert content here.

Find:

* Placeholder text… Insert content here.

Assumptions:

* Placeholder text… Insert content here.

Analysis:

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\*\*If you are adding equations, look up how to align them at a specific character, like the equal sign.\*\*

Appendix B –