

The

CAN ***sat***

Book



NAROM

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About the CanSat book

This book is written by Thomas Gansmoe, Stian Vik Mathisen, and Jøran Grande from NAROM together with Jens F. Dalsgaard Nielsen from Aalborg University and Nils Kristian Rossing from the Norwegian University of Science and Technology. The CanSat shield used in this book is developed by Jens F. Dalsgaard Nielsen and Simon Jensen from Aalborg University College.

The CanSat book is built up so that you can start from scratch and get a feeling of mastering the kit as you read through the book. In the beginning we will describe how you can get your Arduino board and shield up and running, and also go through the primary mission. In this book we have described a primary mission and how to accomplish the goals.

In most competitions in Europe, you have a standard primary mission which is equal to all participants. The teams will also have to complete a secondary mission of their own choosing. This will not be a part of this compendium.

Introduction to CanSat

What is a CanSat?

A CanSat is a representation of a real satellite, integrated within the volume and shape of a soft drink can (330 ml). The challenge for the students is to fit all the major subsystems found in a satellite, such as power, sensors and a communication system, into this minimal volume. The CanSat is then launched to an altitude of a few hundred meters by a rocket or dropped from a platform or captive balloon, and its mission begins: to carry out a scientific experiment and achieve a safe landing.

CanSats offer a unique opportunity for students to have a first practical experience of a real space projects. They are responsible for all aspects: selecting its mission, designing the CanSat, integrating the components, programming the on-board computer, testing, preparing for launch and then analysing the data.

The CanSat-kit

The CanSat-kit is based on an Arduino Uno board and a sensor shield board. Arduino is an open-source electronics prototyping platform based on flexible, easy-to-use hardware and software. It's intended for artists, designers, hobbyists, and anyone interested in creating interactive objects or environments. Arduino can sense the environment by receiving input from a variety of sensors and can affect its surroundings by controlling lights, motors, and other actuators.

Here are some examples on Arduino projects:

- Make an automatic night light which switches on when its dark
- Intrusion alarm
- Thermostat
- Line Follower Robot
- Ham radio Morse code keyed/propagation beacon.
- Graphical calculator that graphs serial inputs on a graphical LCD.
- Wi-Fi controlled RC-Car

Many more ideas can be found at <http://arduino.cc/playground/Projects/Ideas>

The sensor shield card has been developed at the University of Aalborg by Professor Jens Dalsgaard Nielsen and Simon Jensen. The shield has been designed to include:

- Communication radio (APC220) with antenna
- Pressure sensor (MPX4115)
- Temperature sensor (LM35DZ)
- Temperature sensor (NTC 10k)
- Three axis accelerometer (MMA7361L)
- SD storage card (OpenLog)

The sensor shield is designed to fit on top of the Arduino Uno R3 board.

The Primary Mission

Getting started

The Arduino Uno is a microcontroller board based on the ATmega328. It has 14 digital input/output pins (of which 6 can be used as PWM outputs), 6 analogue inputs, a 16 MHz crystal oscillator, a USB connection, a power jack, an ICSP header, and a reset button. It contains everything needed to support the microcontroller; simply connect it to a computer with a USB cable or power it with an AC-to-DC adapter or battery.

To get started you have your ARDUINO UNO board in front of you, a computer and a standard USB cable (A plug to B plug): the kind you would connect to a USB printer.

The open-source Arduino environment makes it easy to write code and upload it to the I/O board. It runs on Windows, Mac OS X and Linux. The environment is written in Java and based on Processing, AVR-gcc, and other open source software.

Installing software

Before you connect your Arduino board to the computer, make sure you have installed the Software and drivers needed to run with the board.

You can download the latest release of the Arduino integrated development environment (IDE) software by going to <http://arduino.cc> and click the "Download" link in the top menu. Here you can choose a download depending on what operating system you use.

- Download and run the latest version of the Arduino IDE (ver. 1.6.5)
- For Windows users with administrative rights on the computer, use the Windows installer. If not, download the zip-file and extract the file to a local folder on your computer.

It is recommended to use the installer if you have administrative rights. This will allow you to automatically install the drivers for the Arduino board.

Connecting the board

The Arduino Uno automatically draws power from either the USB connection of a computer or an external power supply. Connect the Arduino board to your computer using the USB cable. The green power LED (labelled PWR) should turn on.

Install drivers

If you used the zip-file or unchecked the "install driver" part during the installation, you might have to manually install the drivers to connect the Arduino board.

Installing drivers for the Arduino Uno with Windows 7/8, Vista or XP:

- Plug in your board and wait for Windows to begin its driver installation process. On some computers the drivers will install automatically. If not, follow the steps below.
- Click on the Start Menu, and open the *Control Panel*.

- While in the *Control Panel*, navigate to System and Security. Next, open the *Device Manager* which you will find under *System*.
- Look under *Ports (COM & LPT)*. You should see an open port named "*Arduino UNO (COMxx)*". In some cases you won't find "*Arduino Uno*", instead you will find "Unknown device" at the top.
- Right click on the "*Arduino UNO (COMxx)*" port and choose the "*Update Driver Software*" option.
- Next, choose the "*Browse my computer for Driver software*" option.
- Finally, navigate to and select the Arduino Uno's driver file, named "*ArduinoUNO.inf*", located in the "*Drivers*" folder of the Arduino Software download (not the "*FTDI USB Drivers*" subdirectory).
- Windows will finish up the driver installation from here.

Launch the Arduino application

Double-click the Arduino application in the folder where you extracted it.

Open example code

NAROM has a compilation of program codes which will be used during the course.

Open the example code by: File → Open → “CanSat-folder” → “.\\code\\ArduinoTest\\ArduinoTest.ino”.



```

ArduinoTest | Arduino 1.0.5-r2
File Edit Sketch Tools Help
ArduinoTest
/*
Arduino test-code for CanSat course at NAROM 2014
This code is intended to be used for an easy introduction to the Ar
The program reads data from 2 digital and 2 analog ports and prints
*/

int counter = 0, analog0, analog1; //Create variables as integers
float analog0_volt, analog1_volt; //Create variables as floating n
boolean digital2, digital3; //Create variables as boolean (H

void setup(){ //Setup. This section runs only once.
  Serial.begin(9600); //Sets the communication speed between
  pinMode(2, INPUT); //Sets the digital 2 pin to input mode
  pinMode(3, INPUT_PULLUP); //Sets the digital 2 pin to input mode
  delay(500); //0.5 seconds break.
} //end of setup

void loop(){ //Loop. This section runs in an
  //Collect data from all the inputs
  analog0 = analogRead(A0); //Reads data from analog port 0
  
```

Figure 1: Arduino IDE with test code

Select your board

You'll need to select the entry in the *Tools* → *Board* menu (Figure 2) that corresponds to your Arduino. Otherwise you won't be able to communicate with the Arduino Uno board.

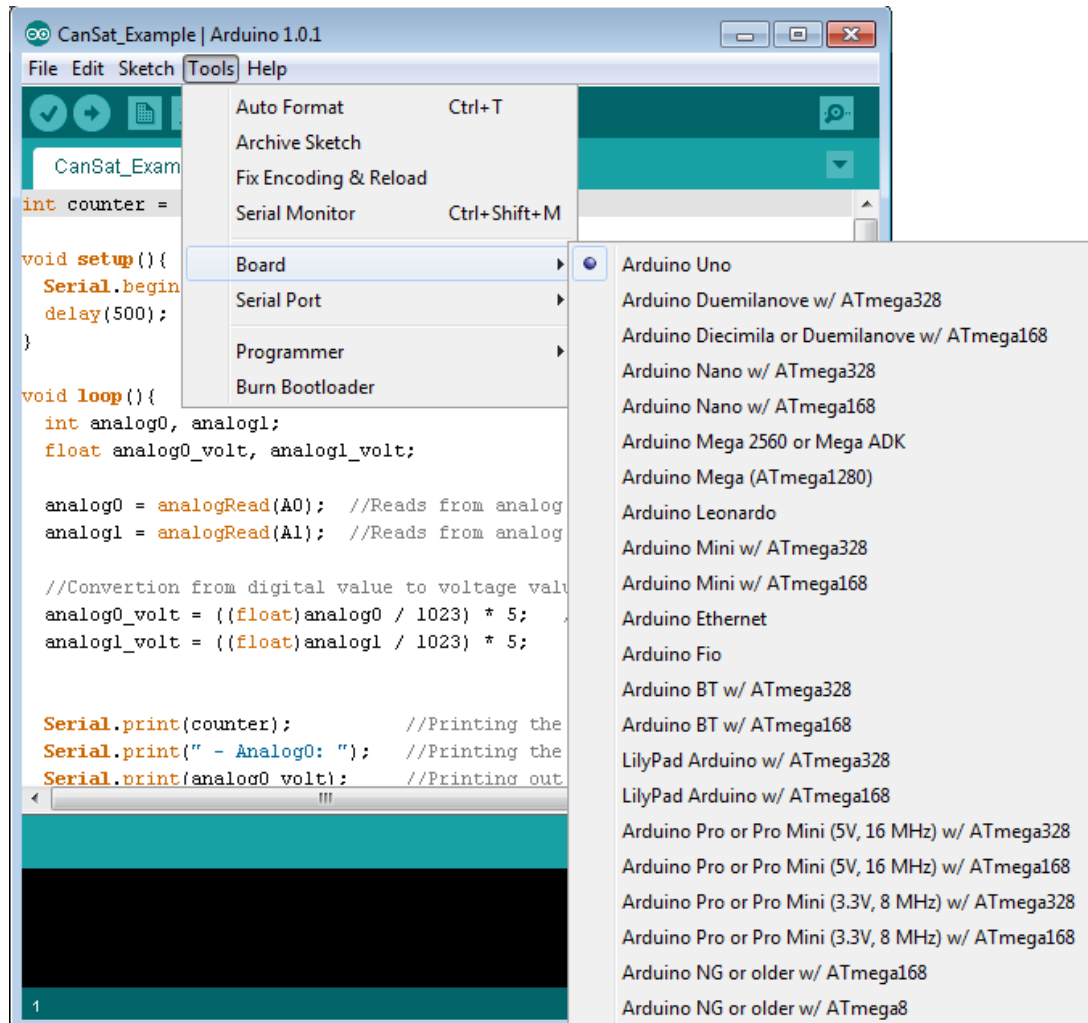


Figure 2: Selecting the Board

Select your serial port

Select the serial device of the Arduino board from the **Tools** → **Serial Port** menu. You will probably have several COM-ports available. The Arduino will most likely be the highest COM-port number. To make sure, you can disconnect your Arduino board and re-open the menu; the entry that disappears should be the Arduino board. Reconnect the board and select the correct serial port.

In the newest version of Arduino IDE (1.6.4), the correct com-port will be labelled (Arduino Uno) in the port list.

Uploading the program

Now, simply click the "Upload" button (Right arrow on the left, Figure 3) in the compiler. Wait a few seconds - you should see the RX and TX LEDs on the Arduino board flashing. If the upload is successful, the message "Done uploading." will appear in the status bar.

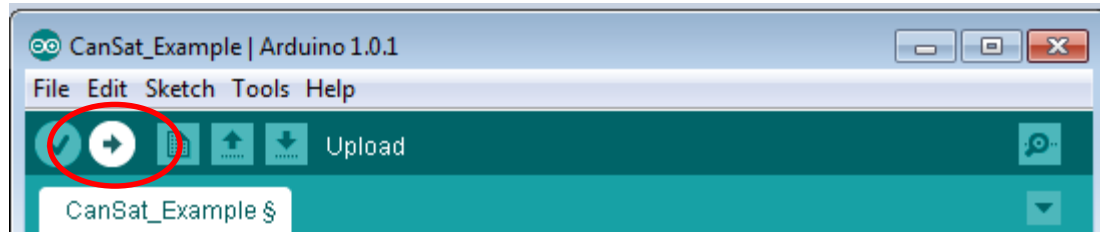


Figure 3: Uploading a code

Read data

Open the Serial Monitor to look at the data which is received from the Arduino Uno board. The Serial Monitor is opened by clicking the icon to the right in the toolbar (Figure 4). The Serial Monitor will open a new window which will give you a serial text stream of the data printed from the Arduino board.

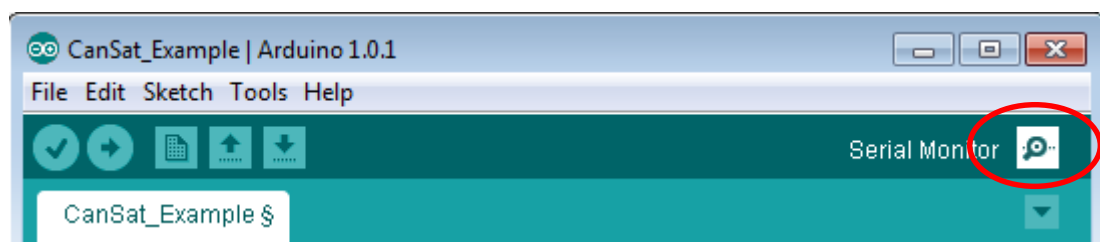


Figure 4: Opening the Serial Monitor

Testing the Arduino Uno board

To verify that you are receiving correct data you can test it by setting each channel to ground and power and read the output in the Serial Monitor. To do this you need a wire to connect between the input connectors and power connectors on the Arduino Uno board.












- Connect one end of the wire to **A0** port
- Connect the other end to **GND** port
- Analog0 in the Serial Monitor should now read 0.0 volts
- Remove the wire from **GND** and connect it to **5V**
- Analog0 should now read approximately 5.0 volts
- Remove the wire from **5V** and connect it to **3.3V**
- Analog0 should now read approximately 3.3 volts
- Repeat the same procedure with **A1, D2 and D3**
- Do you get the same value from the digital port in both 3.3V and 5V?

Assembling the components

Constructing the CanSat-shield

This section will show you step by step how to assemble the components for the CanSat shield.

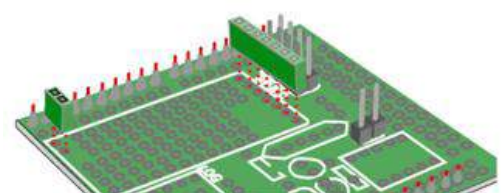
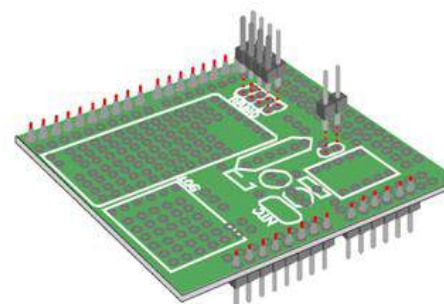
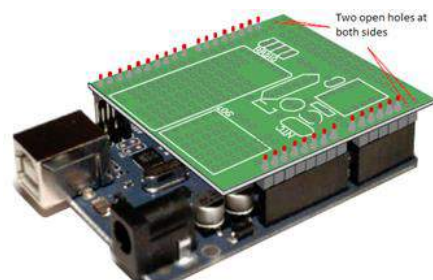
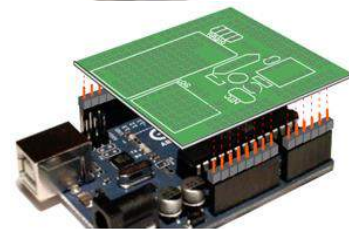
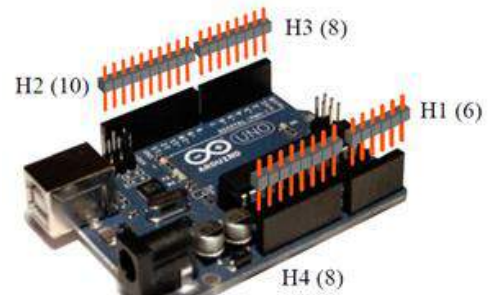
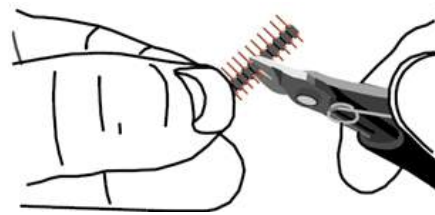
Part list

Arduino Uno R3		Header socket (Female pin connector) 7-pin and 2-pin	
CanSat Shield (Circuit board)		2-pin Jumpers	
OpenLog Data logger with SD-card			
APC220 Radio transmitter/receiver			
Temperature sensors LM35DZ and NTC (NTCLE100E3103JB0)			
MPX4115A Pressure sensor			
MMA7361L Accelerometer 3-axis			
Resistor 1x 75 Ohm 1x 10 kOhm			
Header (Male pin connector) 2 x 32-pin			

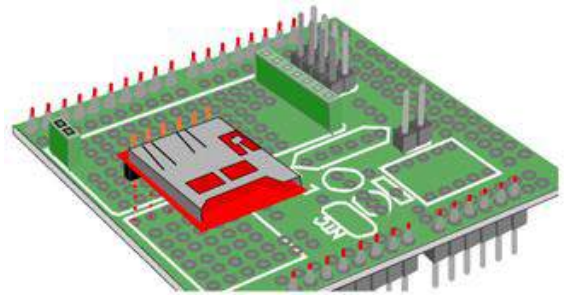
Assembling guide

1. Cut the header in to the following lengths:
 - 6 pins (H1)
 - 10 pins (H2)
 - 8 pins (H3)
 - 8 pins (H4)
2. Insert the headers into the Arduino board with the short end up.
3. Mount the shield board on top of the Arduino Uno.

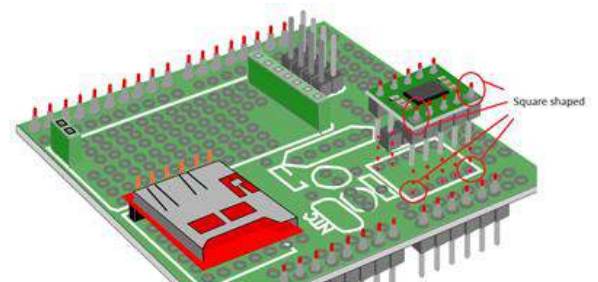
Note: The board should fit only one way.
4. Solder all the pins on the top of the circuit board and then remove it from the Arduino Uno. Make sure not to heat the pins to long while soldering. To long exposure to heat might damage the Arduino board.
5. Cut out two lengths of 4-pin header and one length of 2-pin header. Place them on the top of the shield board and solder them on the bottom (soldering side) as shown in the illustration. (Placed at the J1, J2 and J3 position)
6. The header socket allows us to easily connect and disconnect the radio for programming. If you are unfamiliar with this kit, it is highly recommended to use the header sockets. This may if necessary be removed to make it more robust. Place the sockets on top of the board and solder them at the soldering side.



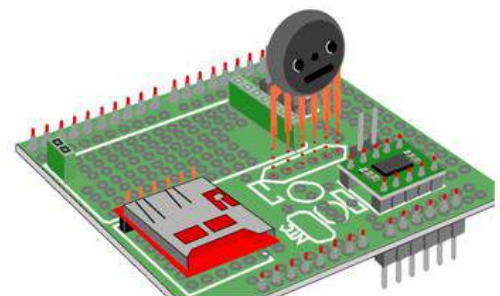
7. Solder the data logger onto the shield board using a 6-pin header. Use the short end of the header downwards through the shield board. Make sure you place the logger the correct way (See illustration). It is recommended to use some hot glue in between the board and the logger to support the logger. If not supported it may easily brake off or damage the soldering points.



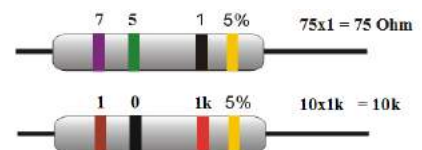
8. Use two lengths of 5 pin headers and solder the accelerometer board onto the shield board at the U1-position. Make sure to orient the sensor the correct way. The black IC-chip on the accelerometer board should be on the top (pointing upwards). Also note that two of the solder pads both on the shield board and the sensor have a square shape instead of a circle shape. **These squares should be aligned.**



9. Put the pressure sensor onto the shield board and solder it on the bottom side. Make sure to put the sensor the right way (As in the illustration).

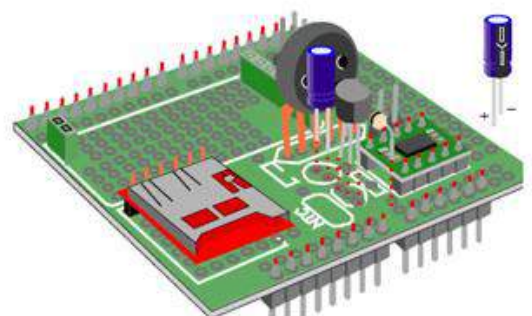


10. Solder on the 75 Ohms resistor to the R2 position
Note: There are two different resistors in the kit. Make sure you use the 75 Ohm resistor, not the 10k Ohm resistor.

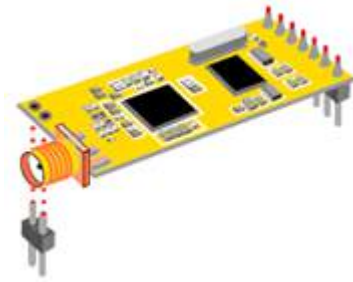


11. Put the temperature IC (LM35DZ) to T1. The orientation for the sensor is labelled on the board. If you put it the wrong way, it can "burn".

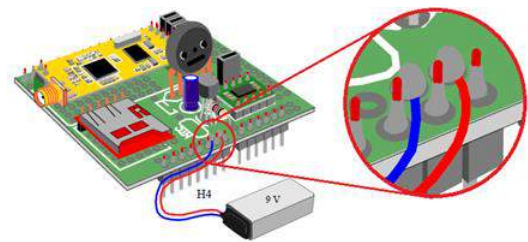
12. Continue with the 1μF capacitor to C1 position. The capacitors orientation is labelled with a plus sign (+) on the board. The longest pin on the capacitor is the positive one. The negative pin is also labelled (white) on the side of the capacitor.



13. Solder a 2-pin header to one of the radios. These pins will only be used as support to reduce the strain on the radio connector. Mount the radio to the shield board.

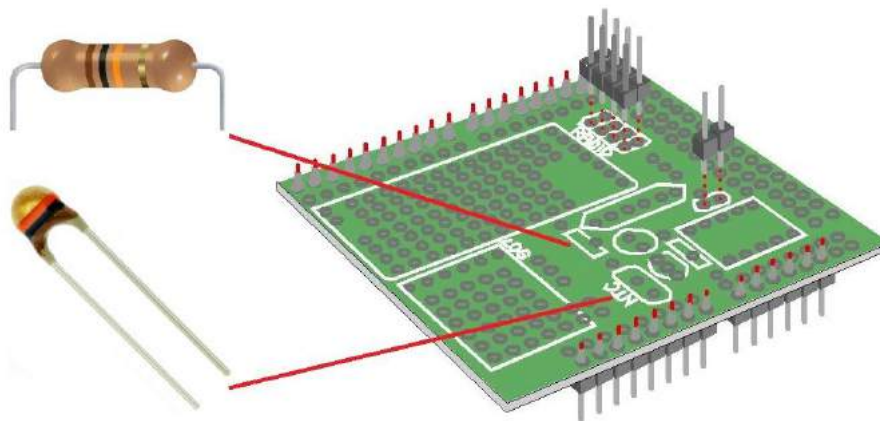


14. Solder the battery connector to the shield board. The wire connection points will break off easily. To avoid this you can use hot glue to glue the wires to the board, reducing the strain on the connection point.



The CanSat shield board is now ready to be tested. There are still two components which have not been installed; the NTC temperature sensor and the 10k Ohm resistor. The NTC temperature sensor is optional but recommended to connect. This temperature sensor has a faster response time than the LM35.

Note: If you choose to use the NTC sensor you will also have to install the 10k Ohm resistor (R1) to make the sensor work.



Testing the CanSat kit

After finishing the CanSat Shield board you need to test it to make sure that all of the components are working properly. The following steps will guide you through the test procedure:

1. Install the Shield board on top of Arduino Uno (Make sure the power is disconnected before mounting the Shield board).
2. Power up the CanSat by connecting the battery.
There is a green light on the Arduino Uno labelled "ON". This should always be illuminated when the Arduino Uno is powered on.
If you fail to get the power light on, test your battery and also make sure there are no short circuits on the Shield board.
3. Disconnect the battery, then connect the USB cable and check the "ON" light again.
4. Open the sketch file "*ShieldTest.ino*" in the Arduino IDE (1.0 or later version) and upload the sketch to the Arduino Uno board. This is a test program designed to give you measurements from all the sensors on the CanSat kit.
5. Start the "Serial Monitor" in the Arduino IDE.
You should get some data similar to what you see in the illustration below.

```
Counter: 0 | Time[s]: 0.00 | Temp: 2.10 V | NTC: 2.06 V | Pressure: 2.01 V | Acceleration [x,y,z]: 1.96 V, 1.91 V, 2.07 V,
Counter: 1 | Time[s]: 0.50 | Temp: 1.98 V | NTC: 2.02 V | Pressure: 1.99 V | Acceleration [x,y,z]: 1.95 V, 1.89 V, 2.04 V,
Counter: 2 | Time[s]: 0.99 | Temp: 1.94 V | NTC: 1.98 V | Pressure: 1.96 V | Acceleration [x,y,z]: 1.93 V, 1.87 V, 2.02 V,
Counter: 3 | Time[s]: 1.50 | Temp: 1.91 V | NTC: 1.96 V | Pressure: 1.94 V | Acceleration [x,y,z]: 1.91 V, 1.86 V, 2.00 V,
Counter: 4 | Time[s]: 2.00 | Temp: 1.88 V | NTC: 1.93 V | Pressure: 1.92 V | Acceleration [x,y,z]: 1.90 V, 1.84 V, 2.03 V,
Counter: 5 | Time[s]: 2.50 | Temp: 1.88 V | NTC: 1.93 V | Pressure: 1.91 V | Acceleration [x,y,z]: 1.89 V, 1.84 V, 2.02 V,
Counter: 6 | Time[s]: 3.00 | Temp: 1.87 V | NTC: 1.92 V | Pressure: 1.91 V | Acceleration [x,y,z]: 1.88 V, 1.82 V, 2.01 V,
Counter: 7 | Time[s]: 3.50 | Temp: 1.87 V | NTC: 1.92 V | Pressure: 1.90 V | Acceleration [x,y,z]: 1.88 V, 1.83 V, 2.00 V,
Counter: 8 | Time[s]: 4.00 | Temp: 1.85 V | NTC: 1.91 V | Pressure: 1.90 V | Acceleration [x,y,z]: 1.87 V, 1.82 V, 1.97 V,
Counter: 9 | Time[s]: 4.50 | Temp: 1.87 V | NTC: 1.92 V | Pressure: 1.90 V | Acceleration [x,y,z]: 1.87 V, 1.82 V, 1.96 V,
```

6. Description of the measured data

Counter: This will count the number of measurements done by the CanSat.

Time: This is the time in seconds since the CanSat was turned on.

Temp: Shows data from the first temperature sensor (LM35DZ).

NTC: Shows data from the optional temperature sensor (NTC).

Pressure: Shows data from the pressure sensor (MPX4115A).

Acceleration: Show data from the accelerometer (MMA7361L). This sensor will give you three readings, one for each axis (x, y and z).

By default the sampling speed will be at 2 Hz (Two lines per second) and all the measured values in volts.

7. The test program can be controlled by sending a character via the serial monitor. Enter a character at the command line and press enter.

The test program will accept the following commands:

"1" – Sets the sampling speed to 1 Hz (1 per second).

"2" – Sets the sampling speed to 2 Hz (2 per second).

"5" – Sets the sampling speed to 5 Hz (5 per second).

"R" – Resets the counter back to zero.

"V" – Changes all the sensor outputs to volts.

"S" – Changes all the sensor outputs to measured values in Celsius, Pascal and G (9,81N).

8. Test all the sensors by trying to manipulate the sensors.

Do you get response from all the sensors?

9. Test the accelerometer setting. Put a shunt (jumper) on the J1 port. This will regulate the sensitivity for the accelerometer from 1,5G to 6G. The output should be the same, but with a different resolution.

If you have got data from all the sensors and they seem to work fine the testing of the main functionality is done. The radio and data logger will be tested at a later point in this manual.

Note: The sensors may have some deviations from the actual conditions caused by offset in the sensors. There is a section on how to calibrate the sensor further down in this manual.

Notes:

Using the sensors

Intro

The CanSat kit used in this manual comes with a sensor board. Connected to this board are four sensors; a *pressure sensor*, two *temperature sensors* and a *three axis accelerometer*. These sensors produce a voltage depending on the value of the parameter the sensor measures. It can take on any value in a certain range; such a signal is called an analogue signal, viewed at the top in Figure 5. From the measured voltages, we can calculate the corresponding value, for instance converting voltage to temperature.

This section will show you how to convert the analogue voltage measured at the sensor, to the physical quantity with the correct unit.

Analogue to Digital

All digital components operate with discrete signals. Unlike the analogue signal, a signal that can only take on some discrete values is called a digital signal. In Figure 5 these two different signals are illustrated. The top graph shows an analogue (continuous) signal, and the bottom graph shows a digital (discrete) signal.

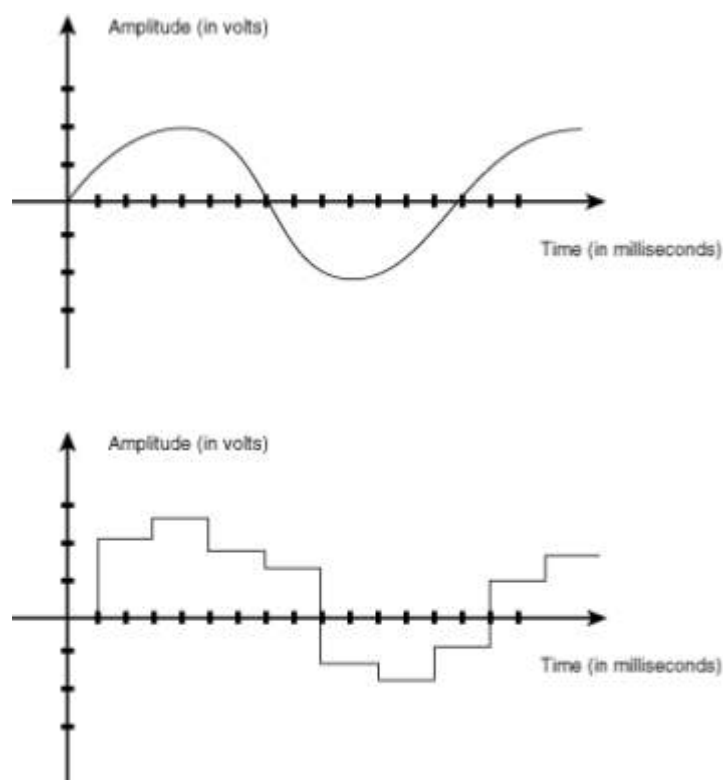


Figure 5: Analogue and digital signal

Desktop or laptop computers, as well as the small computer in the CanSat (called a microcontroller), can only process digital signals. To convert the analogue signal from the sensor into a digital one we

use an Analogue to Digital Converter (ADC), which as the name implies, converts an analogue signal into a digital signal.

The ADC converter is incorporated in the microcontroller and has 8 input channels. It is a 10 bit ADC; it will convert an analogue signal into a digital signal with a 10 bit binary number. One Bit represents one binary digit and can have a value of 0 or 1, which also can be represented by *High* or *Low voltage*, as well as *On* or *Off*. In programming 0 and 1 is also often represented by *True* (1) or *False* (0).

Each digit in the binary number can have 2 values, 0 or 1. A 10 bit binary number can have $2^{10} = 1024$ different values, and can represent an integer ranging from 0 to 1023. The microcontroller can understand digital numbers and use it for computations, which can be programmed into the processor by writing a program code. An example of such a code is the TestShield-code which was used in the previous part of this manual.

Each sensor in the CanSat is sampled by the ADC, which turns each analogue value into a 10 bit number. 0 volts is converted into the binary number 0000000000 = 0 and 5 volts into the binary number 1111111111 = 1023.

By representing the 5 volt input by 1024 levels we have a resolution of $5V/1023 = 4,89mV$. This shows us that with a 10 bit ADC, the smallest voltage change we can measure is 4,89 mV. This is important to notice when we start working with the sensitivity of the sensors.

The sequence of events is thus as follows:

1. The temperature sensor converts the measured temperature into a voltage. This is an analogue signal.
2. The ADC converts the analogue signal into a digital signal, which the processor can handle.
3. Inside the microcontroller the signal is stored as a 10 bit binary number, which can be used for computations.

Sensors

In the "Primary mission" part of this manual we will go through the pressure sensor and both of the temperature sensors. The accelerometer is not a part of the primary mission, and will therefore be described in the "Secondary mission" part of the manual.

Pressure Sensor (MPX4115a)

The pressure sensor used is the MPX4115A from Motorola. It uses a silicon piezoresistive sensor element. Figure 6 presents a cross-sectional view of the sensor.

If a material is called "piezoresistive", it means that the resistance of the material will change when a mechanical stress is applied. In this case the piezoresistive material is silicon. The changes of

resistance for silicon are far greater than for example steel, making this material very useful to use as a sensor element in a pressure sensor.

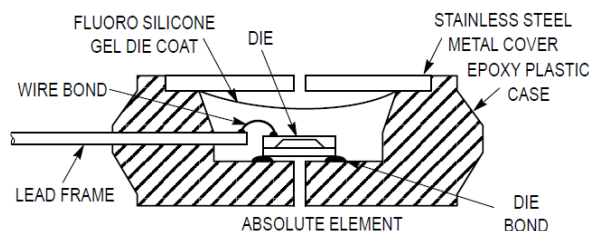


Figure 6: Cross-sectional view of the pressure sensor

Figure 7 shows a more detailed look into the sensor. It shows the dimensions of the sensor and the layout of the connections. To relate the measured voltages to ambient pressure values, the transfer function of the sensor is needed. Such a function describes the mathematical relation between the voltage output of the sensor and the equivalent pressure. This function can be found in the datasheets of the sensor. Figure 8 shows the output voltage versus the ambient air pressure for the sensor as we find it in the datasheet. The output voltage V_{out} is:

$$V_{out} = V_s(0.009P - 0.095)$$

Where P is the airpressure in kPa and V_s is the supply voltage.

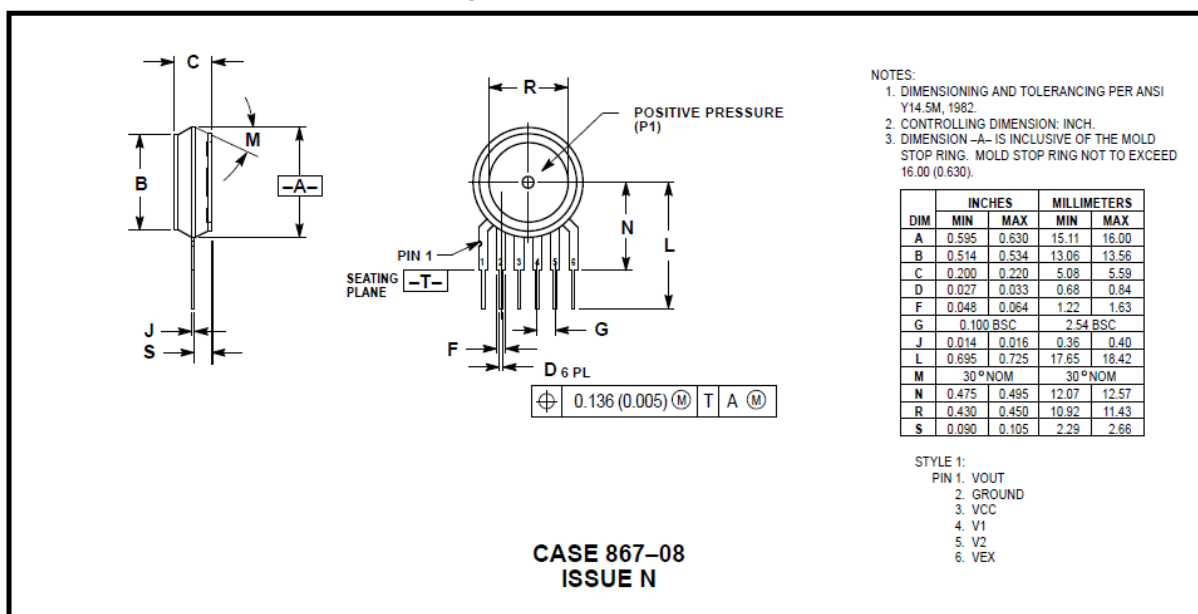


Figure 7: Case style of the pressure sensor

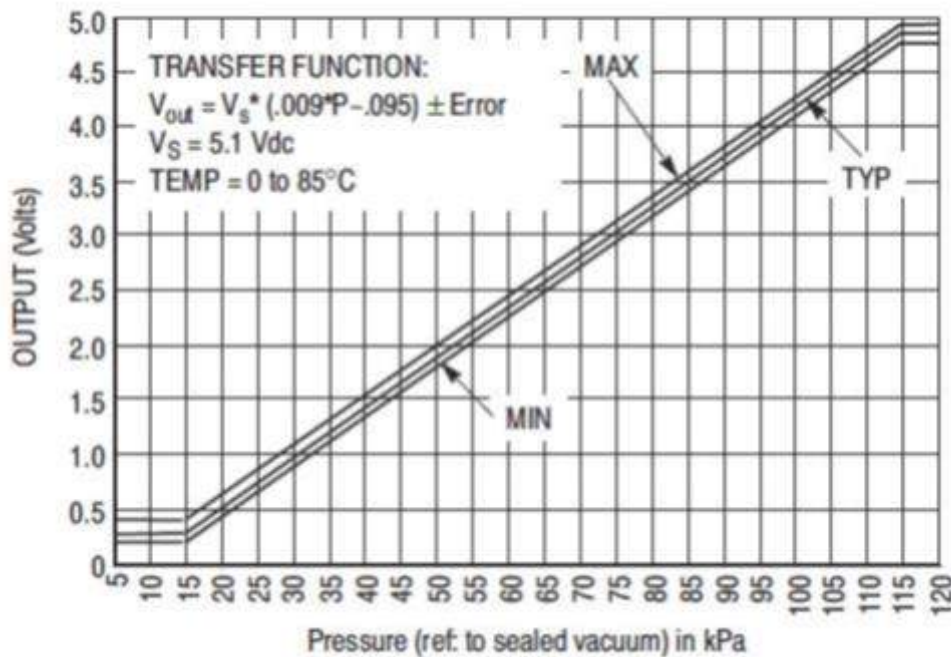


Figure 8: Transfer function of the pressure sensor

Temperature Sensor A (LM35DZ)

The LM35DZ temperature sensor is made for linear measurement in degrees Celsius temperature (or Kelvin). The sensor is made for measuring temperatures between 0°C and 100°C. The output voltage is 250mV at 25°C and the sensor has a sensitivity of 10mV/°C. You can use this information together with the information in the LM35 datasheet, which you will find on your DVD, to make a transfer function of the sensor. You may also plot this on your computer or calculator.

Sensor output [V] = Sensitivity [V/°C] * Temperature [°C] + Output at 0°C (Offset)

Temperature sensor B (NTC)

The temperature sensor used in the CanSat is the NTCLE203E3103JBO manufactured by Vishay/BC components. It is a NTC, or Negative Temperature Coefficient thermistor. The thermal conductivity rises with increasing temperature. Most ceramic materials exhibit such behaviour. Other materials however will have an opposite behaviour, with rising temperature the conductivity decreases. Most NTC thermistors are therefore made out of semi conductive materials, something in between an insulator and a conductor, with some special qualities.

Simply put, when the material is heated, the electrons in the material are energized, so even more electrons are able to move around, thus the material can conduct electricity more easily. When a material can conduct electricity more easily its resistance will decrease. Increased temperature will therefore lead to decreased resistance. This inverse relationship is the reason why this sensor is called a Negative Temperature Coefficient (NTC) resistor.

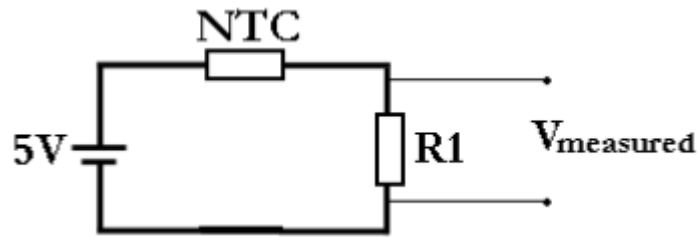


Figure 9: NTC measuring circuit

On the sensor board, the temperature sensor is connected in series with a resistor (R_1) which has a constant resistance of 10 k Ω , as seen in the simplified diagram shown in Figure 9. When resistors are connected in series the current in the circuit will be the same everywhere. The total resistance can be calculated by:

$$R_T = R_1 + R_{NTC}$$

$$I = \frac{U}{R} = \frac{5V}{(R_1 + R_{NTC})}$$

The same current, I , flows through the fixed resistor R_1 giving a voltage $V_{Measured}$ across the resistor. This can be put into the following equation:

$$I_{R1} = \frac{U_{R1}}{R_1} = \frac{V_{Measured}}{R_1}$$

Since the current is the same everywhere in the circuit, we can set up the following equation:

$$I_{R1} = I_{NTC}$$

$$\frac{5V}{(R_1 + R_{NTC})} = \frac{V_{Measured}}{R_1}$$

From this we can get the relation between the measured voltage ($V_{Measured}$) and the resistance of the NTC temperature sensor (R_{NTC}).

$$V_{Measured} = \frac{5V \cdot R_1}{(R_1 + R_{NTC})}$$

$$R_{NTC} = \frac{5V \cdot R_1}{V_{Measured}} - R_1$$

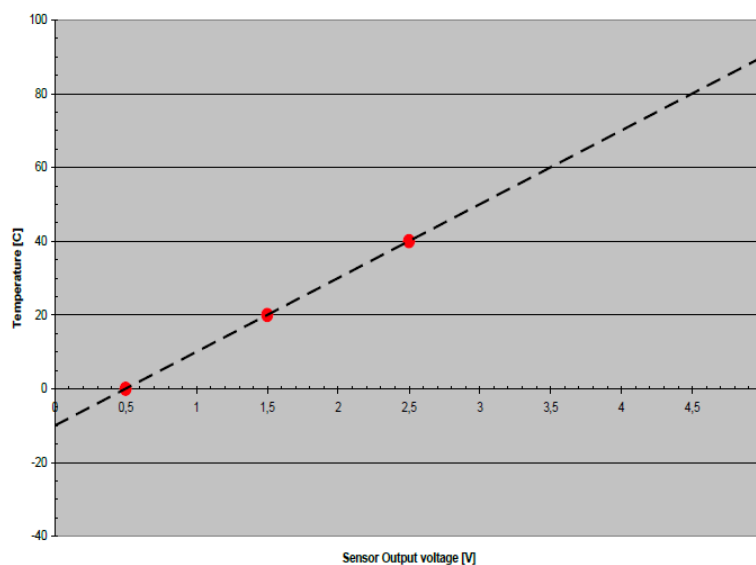
To get a complete transfer function you will also need the relation between the temperature, and the resistance of the sensor (R_{NTC}). You can find this in the sensor datasheet.

Calibrating the sensors

In some cases the transfer function between the temperature and the output voltage of the sensor is unknown. A simple method to determine the transfer function of the sensor, is to measure the output voltage at some (3-4) specific temperatures and plot the result into a graph. For our specific NTC sensor we can assume that the relationship is linear within the range of interest. Linear regression can be used to find the linear equation of best fit.

Linearity means that the relation between voltage and the parameter temperature is directly proportional. This relation can be expressed by the linear formula:

$$\text{Parameter} = A * \text{Voltage} + B$$



Note: This is only an example

Voltage [V]	Temperature [C]
0,5	0
1,5	20
2,5	40

Figure 10: Measured test results

The graph of figure 10 can be used to estimate the values of A and B. In this diagram you can plot the measured voltages on the x-axis, and the parameter (in this case temperature) on the y-axis. In the table next to the diagram you will find some example measurements for this sensor. These measurements are also plotted in the graph. Step two is to draw a straight line through the points. The more points you use the more accurate your result will be. However it will be more difficult to fit a line through each and every data point. Fit the line as closely as possible, and use it to determine the values of A and B from the standard linear formula above.

A: is the slope of the line,

B: is the intersection with the y-axis.

Altitude Calculations

The atmosphere is all around us; it is a thin gaseous layer surrounding our planet. The atmosphere is composed primarily of nitrogen (78%) and oxygen (21%). The remaining 1% consists of water vapour, CO₂ and other trace gasses. The Earth's atmosphere consists of different layers, each one having different properties (temperatures, pressure, composition, etc...).

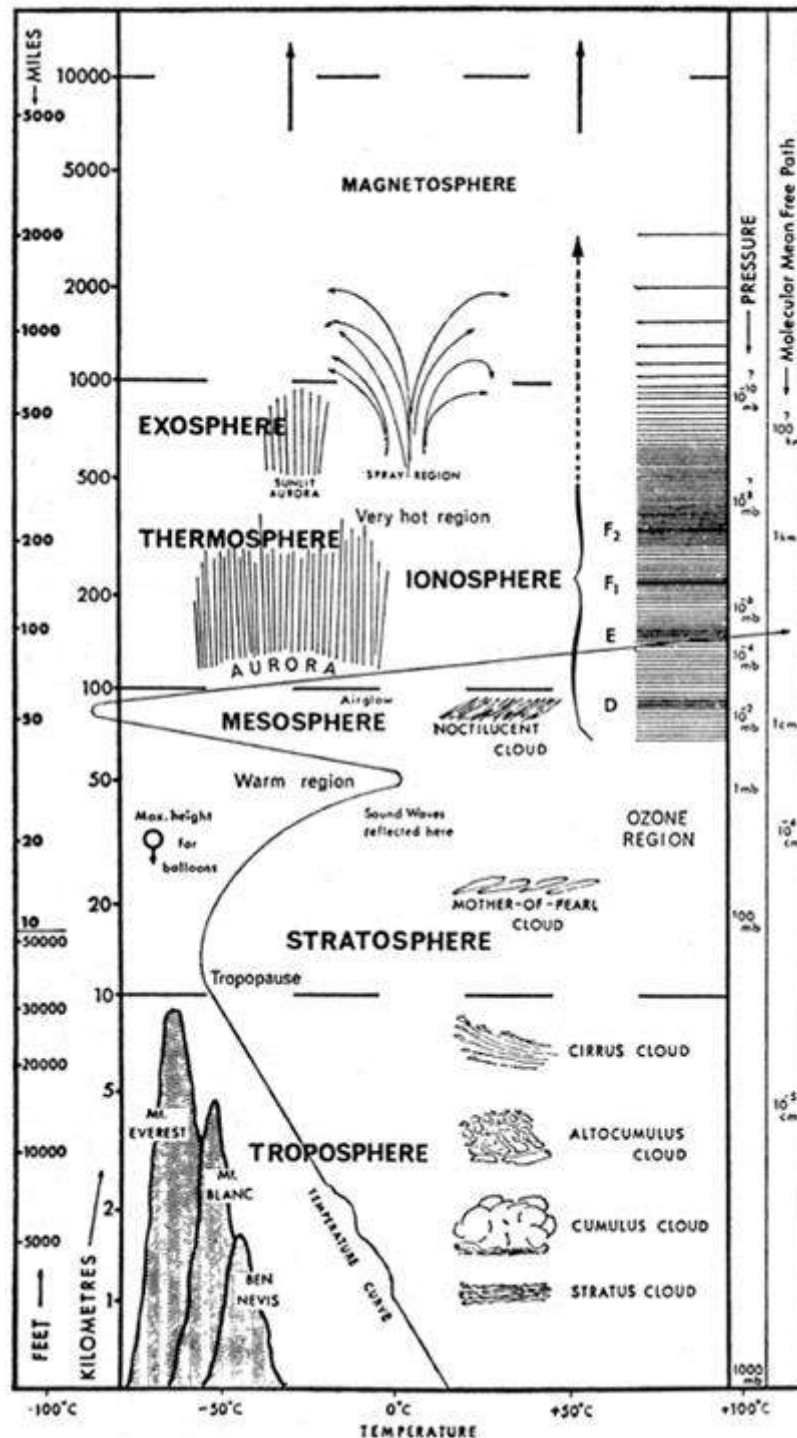


Figure 11: Atmosphere layers

The different layers are represented in Figure 11, along with various human and weather activities seen in these layers.

Unlike our CanSat, most satellites operate in the exosphere. Here the density of the atmosphere is very low. The CanSat however operates in the troposphere, which is the bottom layer of the atmosphere. This layer contains about 80% of the total mass of the atmosphere, and stretches to about 10 kilometres altitude. A great deal of the “weather” we observe on a day-to-day basis (wind and clouds for instance) occurs within this layer.

As seen in Figure 11, the temperature and pressure of the atmosphere varies with altitude.

Although the ambient temperature can rise and fall as you move through the different layers of the atmosphere. Within the troposphere, there is a linear relation between the temperature and altitude. On average, ascending one kilometre from sea level will result in a temperature drop of 6.5 degrees Celsius.

The equation below provides the relation:

- T - Temperature in Kelvin
- T_1 - Starting temperature at h_1 altitude
- h - Altitude in meters
- h_1 - Starting altitude
- α - Temperature gradient: -0.0065 K/m.

The relation between the pressure and the altitude is somewhat more complicated. The pressure is not only dependent on the altitude but also on the temperature. Let's start with the relation of pressure to temperature:

$$\frac{p}{p_1} = \left(\frac{T}{T_1} \right)^{-\frac{g_0}{\alpha R}}$$

- p - Pressure in Pascal
- p_1 - Start pressure in Pascal
- g_0 - Gravitational acceleration: 9.81 m/s^2
- R - Specific gas constant: $287.06 \text{ J/kg}\cdot\text{K}$

Inserting this formula into the temperature-altitude relation, we achieve the following expression for altitude as a function of temperature and pressure:

$$h = \frac{T_1}{\alpha} \left(\left(\frac{p}{p_1} \right)^{-\frac{\alpha R}{g_0}} - 1 \right) + h_1$$

Using the radio

Introduction

Telemetry is a technology that allows transmission of data from remote measurement devices. It is derived from the Greek words “tele”, meaning *remote*, and “metron”, meaning *measure*. Telemetry is an essential part of rocketry and satellite technology. Information is transmitted wirelessly using radio waves. On the ground these signals are collected by radio receivers. Large space agencies have networks of these ground stations stretching all over the globe, tracking, monitoring and receiving telemetry from their satellites.

Telemetry data can be divided into two groups: data from internal sources and data from external sources. Rockets and satellites are equipped with countless sensors that measure internal parameters. The measurements they take may relate to temperature, pressure, attitude, power usage, and a wide variety of other measurements. The information from these sensors is called “housekeeping data”. This is used to monitor the satellites health, and is necessary for the operation of the system.

Information from the external sources is mostly what interest scientists. This is the data collected from the payload. The payload of a research satellite typically takes the form of sensors or other equipment which measures and generates data about our planet, the space environment, the sun, the stars, or any number of other things depending on the mission. This information is called the “mission data” or “scientific data”. In your CanSat this would be the information from the sensor board. This data is sent to a ground station to be studied by scientists.

CanSat telemetry operations can be broken down into three distinct components: transmitting data, receiving data, and processing data. The transmitter board inside the CanSat collects information and transmits it as a radio signal. This signal is received by the ground station and sent to a laptop, where it is stored before being processed as experimental data.

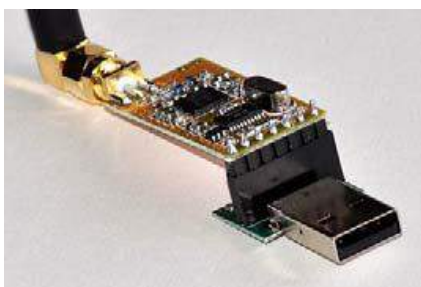
Transceiver

A transceiver is a device comprising both a transmitter and a receiver which are combined and share common circuitry or a single housing. When no circuitry is common between transmit and receive functions, the device is a transmitter-receiver.



In the Arduino CanSat kit we are using APC220 which is a transceiver, with a highly versatile low power radio solution that is easy to setup and integrate into any project requiring a wireless RF link.

It is perfect for robotic application which gives you wireless control. You can connect one of these modules with your microcontroller through TTL interface. And connect your PC with another APC220 module through a TTL/USB converter.



Setting up transceiver hardware

There are two ways of configuring the transceivers. They can be programmed directly from the Arduino board, or you can program them by using the program RF-Magic. RF-Magic has a lot of bugs, and some computers will have problems getting the program to run properly. We will explain both methods, but we

recommend using the Arduino.

Installing drivers

The transceiver at the ground station will be connected to the computer through a USB-TTL converter. This module needs a driver to work properly.

The latest VCP (Virtual Com Port) drivers for the USB-TTL module can be downloaded from Silabs.com (CP210x USB to UART Bridge VCP Drivers).

When you are at silabs.com website go to products and click on “USB Bridges”. Scroll down on the page until you see the “Kits and Development Tools” section.

Click on the “Virtual Com Port (VCP) Download” and download the file according to your platform.

When downloaded, unzip the file and run “CP210xVCPInstaller_x64”.

It's recommended to first install the USB-TTL converter drivers and then plug in the USB converter with the inserted APC module. When the module is inserted, Windows will recognize it and configure the necessary drivers. If Windows does not recognize the device or reports that the device is not functioning properly; remove it from the USB port and reinsert it.

Programming the transceivers with Arduino

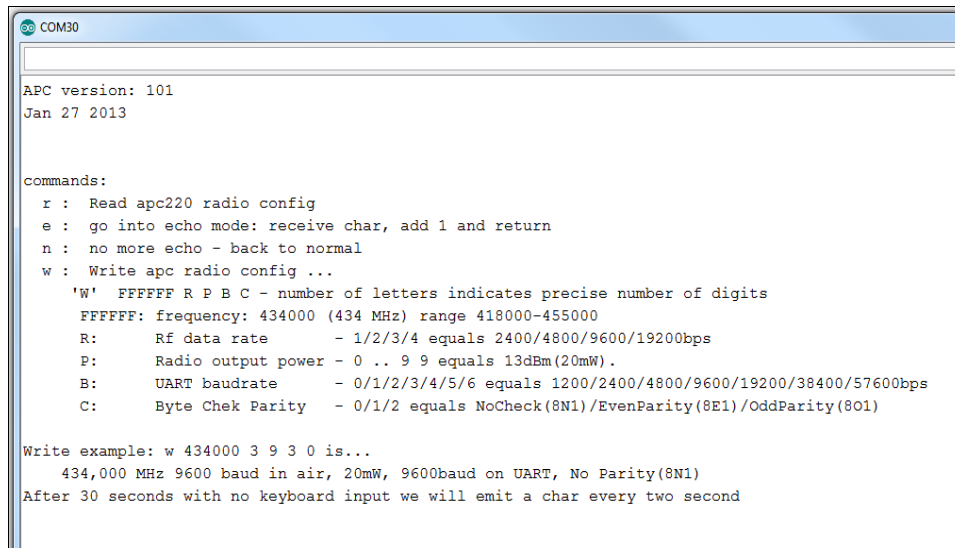
Connect the Arduino board to the computer and upload the program “apc220cfg.ino” which is found on the DVD (or NAROM's web site). Make sure you **upload the program before** you try to connect the transceiver to the Arduino board. Disconnect the USB cable (and battery) from the Arduino board and connect the transceiver to the Arduino as shown in figure 12.



Figure 12: Connecting the transceiver to the Arduino UNO board

The transceivers will be connected to the pins labelled GND, 8,9,10,11,12 and 13 on the Arduino board.

Reconnect the Arduino board through the USB cable and open the *Serial Monitor*. In the command line at the top, type in 'm' and hit *enter*. This will bring up the menu shown in Figure 13.



```
COM30
APC version: 101
Jan 27 2013

commands:
r : Read apc220 radio config
e : go into echo mode: receive char, add 1 and return
n : no more echo - back to normal
w : Write apc radio config ...
'W' FFFFFFF R P B C - number of letters indicates precise number of digits
FFFFFF: frequency: 434000 (434 MHz) range 418000-455000
R:      Rf data rate      - 1/2/3/4 equals 2400/4800/9600/19200bps
P:      Radio output power - 0 .. 9 9 equals 13dBm(20mW).
B:      UART baudrate    - 0/1/2/3/4/5/6 equals 1200/2400/4800/9600/19200/38400/57600bps
C:      Byte Chek Parity  - 0/1/2 equals NoCheck(8N1)/EvenParity(8E1)/OddParity(8O1)

Write example: w 434000 3 9 3 0 is...
434,000 MHz 9600 baud in air, 20mW, 9600baud on UART, No Parity(8N1)
After 30 seconds with no keyboard input we will emit a char every two second
```

Figure 13: Configuration of the transceiver

If you type 'r' and hit enter, the program will return the current configuration for the transceiver. To reconfigure the radio, type 'w' and the 6 parameters needed, with space between each parameter.

Note that you have to configure both transceivers with the same settings to be able to use them together.

RF-Magic

The transceivers can also be programmed by using RF-Magic, however the program has a lot of bugs, and we don't recommend using this program. Your hair will turn grey!

Once the drivers are correctly installed and the hardware is ready to use, start the interface program RF-Magic as administrator. Most likely during start, an error will be generated. This is because the program cannot find the device on the expected com-port.

If you have trouble connecting the USB-UART bridge with RF-Magic, check that you have it in the *Device Manager* and try to set the com-port number as low as possible.

When RF-Magic has found the device it will appear in the bottom of the window as shown in Figure 15.

Still not working? Try restarting the computer. If the problem consists; uninstall the driver and reinstall it.

When you have the RF-Magic up and running you can configure the radio to your designated frequency and bitrate. Remember to configure both radios, otherwise you won't be able to communicate between the CanSat and ground station.

For your CanSat you have been given a pre-set frequency. If not, a list of frequencies are listed in the Appendix. The bitrate should be set to 9600bps.

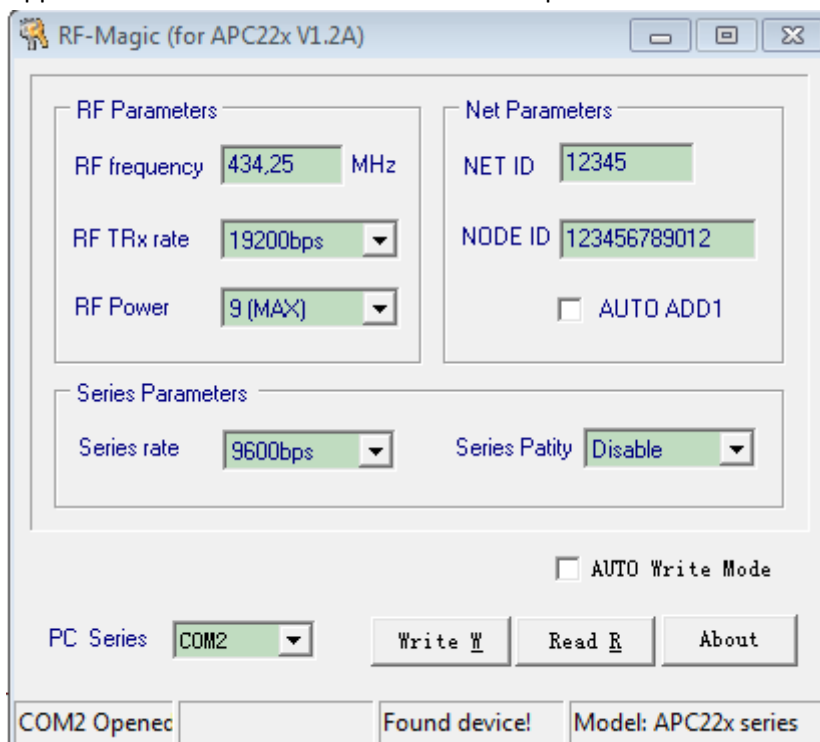


Figure 15: RF-Magic with working COM-port

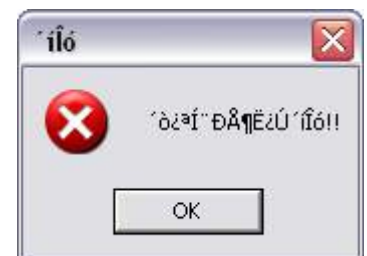


Figure 14: Error Message

Preparing CanSat Shield Radio

On the CanSat shield, Figure 1, there are two sets of jumper pins, **J2** and **J3**. When **J2** and **J3** is not connected you can program the Arduino. By setting the jumpers at **J2-1** and **J2-2** you can transmit data to the radio. When placing jumpers at **J3-1** and **J3-2** you enable data storage in the SD-card (if it's connected).

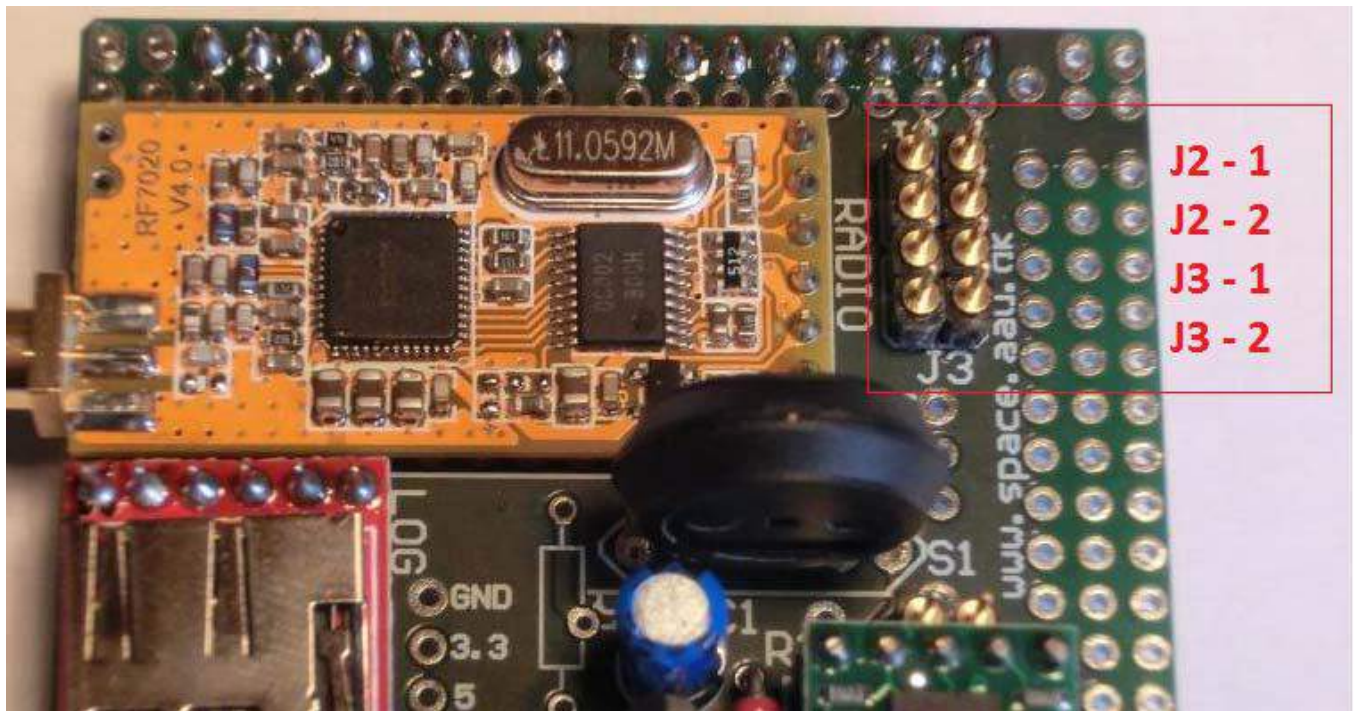


Figure 16: The CanSat Shield with radio

Testing the radio

When you are finished programming the CanSat kit you should test that the radio link is working properly. Place jumpers on **J2**, connect the receiver to the PC via the USB to UART Bridge (USB-converter) and open the Arduino software.

Change the COM-port from Arduino Uno R3 (COMxx) to Silicon Labs CP210x USB to UART Bridge (COMxx) in the Arduino software by going to **Tools → Serial Port**. If you don't remember which COM-port that is the correct one, go to the **Device Manager**.

Press the serial monitor to look at the data that is coming from the radio. To store data we use *Tera Term VT*.

Terminal v1.9b by Br@y++

Terminal by Bray is a freeware program that can read and store data coming from the serial ports. You can download the latest version from <https://sites.google.com/site/terminalbpp/>

Choose the correct Com-port and click connect in the top left corner in the program.

If you have an Arduino (or radio) connected you should receive data in the terminal.

If you want to store the data you can find a button labelled "StartLog". A popup will appear asking you where to store the log-file. Choose your folder and file name and press "Open". The terminal will now write all the data coming in from this point and until you press "StopLog".

After you are done logging data, you can open the text-file in any text editor. If the data is plain numbers with commas between it is easy to copy into Excel or other mathematical programs.

Parachute design

Satellites normally do not return to Earth in a parachute. At the end of their useful life, a satellite will be put in a different orbit. For satellites orbiting at a low altitude this could mean they will burn up in the atmosphere. Satellites further away will end up in a much more distant parking orbit and will circle our planet forever. Sometimes however the spacecraft has to return to earth with samples or astronauts. One of the solutions is then to descend in a parachute.

When the CanSat is deployed it must have a device to slow it down, otherwise it will crash into the surface. The parachute also helps ensure that the CanSat stays in an upright position. This is particularly important because it helps to maintain proper antenna orientation, which maximises the chances of receiving telemetry. This lesson will guide you through the different steps needed to design and built your parachute.

Required Descent Parameters

The values are still preliminary; they may change in the future. However they can be used as a temporary guideline. Uncertainties in the Launch Campaign could lead to a different value for the eventual descent velocities.

Minimal descent Velocity: 8 m/s

Maximal descent Velocity: 11 m/s

Maximum allowed mass: 350 grams

Drag coefficients:

Semi Spherical: 1.5

Cross Shaped: 0.8

Parapent: depends on the design (can be determined by tests)

Flat, hexagon: 0.8

Parachute production

When the design of the parachute is finished you can start the production process. There are however a few important issues to keep in mind during this process. Deployment of the parachute will be relatively violent, so the fabric and fibres you use need to be strong. Most often you can get nylon cord and ripstop fabric at a kite shop. These materials are ideally suited for the parachute.

When cutting the fabric keep in mind that some of the fabrics need to be cast double in order to sew it.

More handy tips on parachute production can be found here:

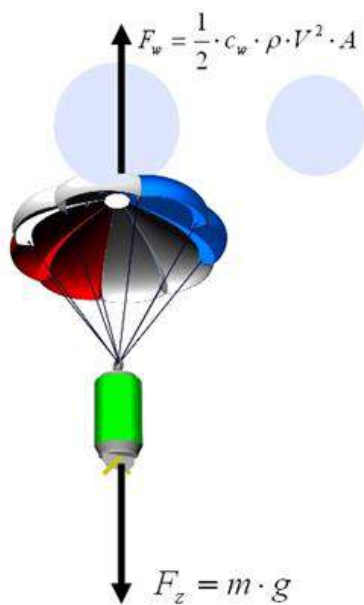
<http://www.nakka-rocketry.net/paracon.html>

When the parachute is done, the best way to check if it works is to actually test it.

Example Assignments

The following assignments can be performed when working on the parachute.

- Calculate the impact speed of the can without a parachute (when released from 1 kilometre altitude).
- Calculate the minimum required area for your parachute when you use a cross parachute. What size should the squares be on the chute?
- Perform the same calculation for a spherical parachute. What is the radius?
- Test the descent velocity of your parachute with a soda can?



- Try out different solutions for the parachute. A parachute with some holes in it or perhaps multiple small parachutes? Both will enhance the stability of the CanSat.

Descent Physics

Before we can start making the parachute we will have to figure out how big it should be. More specifically, we need to calculate how much surface area the parachute will need in order to fulfil the requirements.

Logic suggests that the bigger the parachute the slower the object's descent velocity. Later on this principle is shown with some basic equations. Although it would be very beneficial for the CanSat to have a very low descent rate, a limit has been set to ensure that the CanSat will land near the launch area. If the descent rate is too slow the CanSat may drift kilometres away along with the wind, which is

neither allowed nor desired. For safety reasons there has also been set a maximum descent rate.

To design the parachute we'll use some simple physics. We use a simplified model to estimate the area of the parachute, after which we can start on the construction.

During the descent two forces will be acting on the CanSat. Gravity will pull on the can and accelerate it towards the ground, and the drag force on the parachute will pull the CanSat in the opposite direction and slow down the descent rate. The two forces are shown in the image above.

When the CanSat is deployed, the force of gravity will cause it to accelerate. After a few seconds the drag force from the parachute will reach equilibrium with the force of gravity. From that point on, the acceleration will be zero and the CanSat will descend at a constant velocity. This constant velocity has to be greater than the minimum descent velocity specified in the requirements. For the following calculations we can use this minimum value as the constant velocity of the CanSat.

The gravity force is equal to:

$$F_g = m * g$$

In this equation:

m: Mass of the CanSat

g: Acceleration of gravity, equal to $9.81 \frac{m}{s^2}$

The drag force of the parachute is equal to:

$$F_D = 0.5 * C_D * \rho * A * V^2$$

In this equation:

A: Total area of the parachute (not just the frontal area)

C_D : Drag coefficient of the parachute. This value depends on the shape of the parachute.

ρ : Local density of the air, assumed to be constant at $1.225 \frac{kg}{m^3}$.

V: Descent velocity of the CanSat

Given a desired velocity, you can easily rewrite these equations to calculate the area needed for the parachute.

Semi-spherical Parachute Design

A semi-spherical appearance is the most common shape of a parachute. Although it is not hard to make one, it can be quite time-consuming to get the right shape. The figure below should help out.

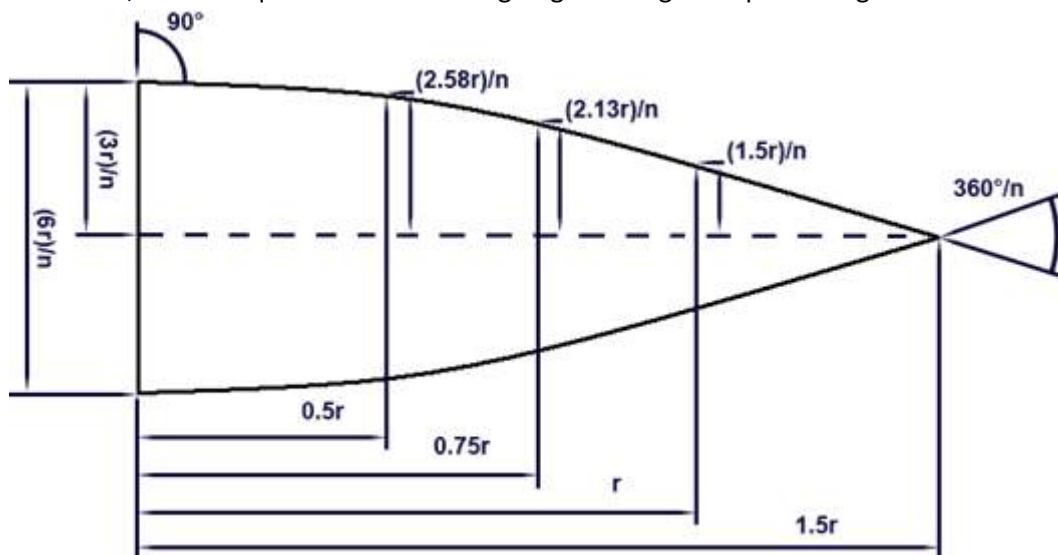


Figure 17: Semi-spherical parachute

n stands for the number of needed parts

r stands for the radius of the parachute.

Cross Parachute Design



Figure 18: Cross Parachute

Instead of using a semi spherical shaped parachute you can also choose a cross shape. The advantage of this shape is that it's easy to make. If you want to know more about cross shaped parachutes you can check the following link:

<http://www.nakka-rocketry.net/xchute1.html>

Parapent

A parapent shaped parachute acts a bit like a wing. Because of its shape you can use it to steer. The design of a parapent is more complex than that of the other shapes mentioned. You will have to do some more research if you wish to use this type of parachute.



Figure 19: Parapent

Flat parachute design

Most commonly available parachutes are in fact created from standard two-dimensional flat geometric figures, such as hexagons or octagons.

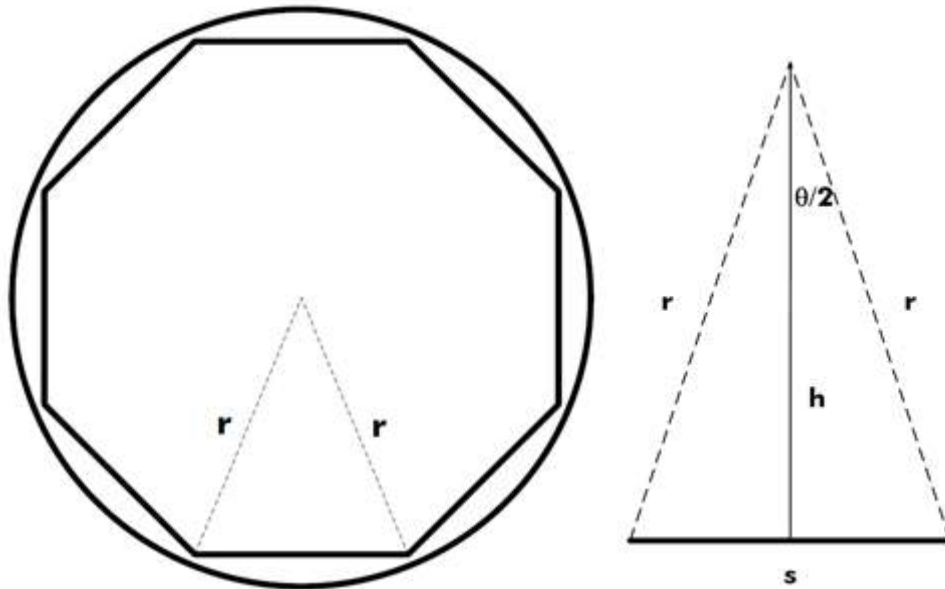


Figure 20: Octagon parachute

From Figure 20 above it is shown that the parachute consist of 8 equal triangles. Hence the total area for the parachute would be $A = 8 * AT$, where the area of one triangle is $AT = s * \frac{h}{2}$. By combining these two equations we get $A = \frac{8*s*h}{2}$. You can read more about how to calculate the area of a flat parachute here:

<http://www.sunward1.com/imagespara/The%20Mathematics%20of%20Parachutes%28Rev2%29.pdf>

As soon as you know the total area (A) together with the drag coefficient (Cd) you can easily determine the descent rate for your CanSat. If you do not know the drag coefficient for your parachute, you can do drop tests of the CanSat to find the terminal velocity.

CanSat Design

Introduction

The whole concept of CanSat is that neither weight nor volume shall be bigger than a standard soda can. Electronics must be mounted on a robust bracket that handles the stress of a launch and separation from a rocket. The parachute must be connected to the bracket, not the can! The can is just a shield to protect the electronics against direct impact.

The antenna should be a tread antenna because of its flexibility so when the CanSat lands, the antenna won't be damaged during impact.

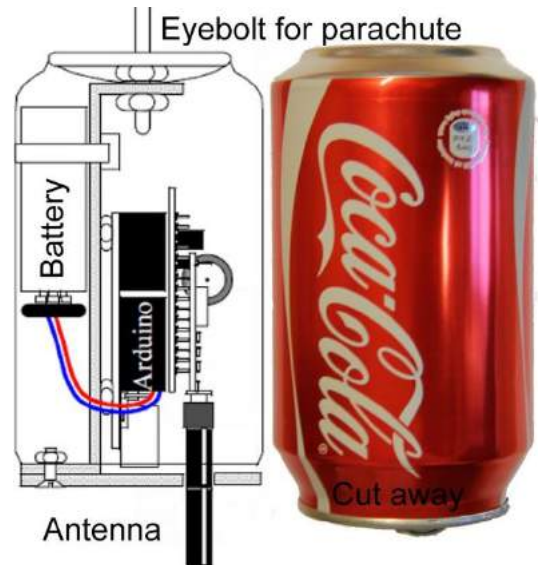


Figure 21: The CanSat with bracket

Competition requirements

NAROM has since 2009 held national CanSat competitions and also two European competitions in cooperation with the European Space Agency.

NAROM uses the following set of requirements that are compatible with the Intruder rocket.

- All the components of the CanSat, with the exception of parachute, antenna and GPS, must fit inside a European soda can: 115 mm high and 66 mm diameter.
- The maximum mass of the CanSat is limited to 350 grams.
- The CanSat should have a recovery system, such as a parachute.
- The deployable subsystems and recovery system can exceed the length of the primary structure, but can't be deployed before the CanSat is fully ejected from the rocket.
- Flight time is limited to 120 sec (If not other agreements have been made).
- The descent rate must be between 8 m/s and 11m/s (If not other agreements have been made).
- Explosives, detonators, pyrotechnics, flammable materials, dangerous materials and biological payloads are strictly forbidden. All materials used must be safe for personnel, equipment and the environment. Material Safety Data Sheets (MSDS) will be requested in case of doubt.
- The CanSat shall operate with a battery or solar panels. It must be possible for the systems to be powered on for three continuous hours.
- The CanSat must be able to withstand an acceleration of up to 20G.
- The battery must be easily accessible, in case it has to be replaced or recharged in the field.
- The total budget of the CanSat should not exceed €500.

Note that these requirements are just temporary guidelines. In the event of a competition the requirements will be announced.

The Bracket

There are several ideas on how the brackets should look like. We are going to make suggestion on how it can fit the Arduino board.

The drawing, Figure 22, shows the bracket with dimensions and placements of holes before it is bent. The material you can use for the plate is 0.5-1 mm aluminium.

The plate is bent 90° inwards on top and 90° outwards on the bottom. Where to bend the plate is shown on the drawing.

Remember holes for strips to fasten the battery.

To make the CanSat easy to turn on and off, a switch is recommended to be placed between the battery and the CanSat kit. But remember that the switch will be a weak link during launch campaign.

In Figure 23 we can see an example of how the CanSat could look like.

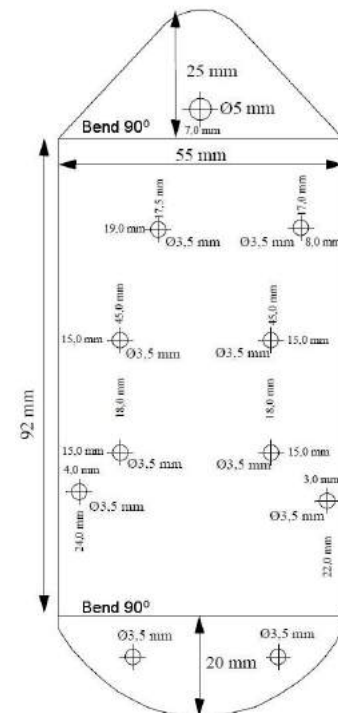


Figure 22: CanSat Bracket design



Figure 23: Finished CanSat

Antenna design

The antenna that is included with the APC220 radio is a 433MHz Rubber Duck antenna. This antenna is robust and great for testing, but won't fit inside a soda can.



Figure 24: Duck antenna

A good alternative is the simple thread antennas that can be soldered directly on to the transmitter output or attached to a SMA-connector. Normally such antennas will be a quarter-wavelength. The thickness is not critical; the most important is the flexibility and durability.

Antenna length can be calculated from equation below when the frequency (f), and velocity of light (c) is known:

If we have a frequency of 434 MHz, then the equation for calculating the length of a quarter wavelength is:

$$L = \frac{c}{4f} = \frac{(3 * 10^8)}{(4 * 434 * 10^6)} = 0.173m$$

By this calculation we find that the antenna should be 17.3 cm long. We can build this antenna by using a coaxial cable. Remove 17.3 cm of the plastic jacket and the metallic shield from the cable, leaving the centre core and dielectric insulator. Make sure that the shielded part of the cable reaches all the way out of the can before it is stripped.

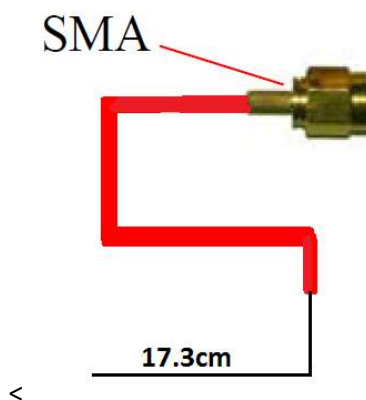


Figure 25: Thread antenna

Appendix

Frequencies

Frequencies (MHz)	Team	Frequencies (MHz)	Team
433,050		433,950	
433,100		434,000	
433,150		434,050	
433,200		434,100	
433,250		434,150	
433,300		434,200	
433,350		434,250	
433,400		434,300	
433,450		434,350	
433,500		434,400	
433,550		434,450	
433,600		434,500	
433,650		434,550	
433,700		434,600	
433,750		434,650	
433,800		434,700	
433,850		434,750	
433,900		434,800	

Component list

Compoent	Dealer	Ordering number
Arduino Uno R3	Farnell	2075382
LM35DZ (Temperatur)	Farnell	146-9236
Capacitor 1uF	Farnell	945-1455
Resistor 75 ohm	Farnell	934-2257
Resistor 10 kohm	Farnell	934-1110
Breakaway headers	Farnell	109-7955
Jumper 2.54mm 2p	Farnell	421-8176
USB2.0 Cable A/B	Farnell	8706794
MPX4115A (Trykksensor)	Farnell	145-7150
NTCLE100E3103JB0	Farnell	118-7031
Coax Cable RG316	Farnell	183-8802
Battery Connector (10 stk)	Farnell	1183124
Female Headers 7p	Farnell	2308805
Female Headers 2p	Farnell	3419046
MicroSD Card 2GB	Komplett	
Radio - APC220	DFRobot	TEL0005
MMA7361L	Pololu.com (USA)	1246
Parachute 18 inch Nylon	Apogeerockets	29112
Logger - OpenLog	Sparkfun	DEV-09530
Aalborg CanSat shield	Aalborg Uni./NAROM	

Pin-out diagram

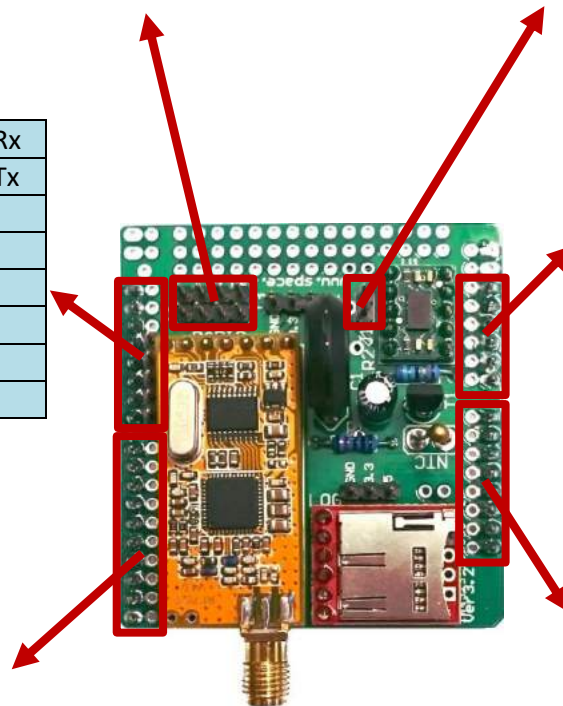
Arduino Tx	Arduino Rx	Arduino Tx	Arduino Rx
Radio Rx	Radio Tx	Logger Rx	Logger Tx

1.5/3 g selector
3.3V

Radio/logger Tx	Digital0/Rx
Radio/logger Rx	Digital1/Tx
Logger reset	Digital2
	Digital3
	Digital4
	Digital5
	Digital6
	Digital7

Analog5	Temperature (LM35)
Analog4	Acceleration Z-axis
Analog3	Acceleration Y-axis
Analog2	Acceleration X-axis
Analog1	Pressure
Analog0	Temperature (NTC)

	Digital8
	Digital9
	Digital10
	Digital11
	Digital12
	Digital13
	Gnd
	ARef
Analog4	SDA (I2C)
Analog5	SCL (I2C)



AAU-CanSat shield ver. 3.2 or earlier

Vin	Battery +
Gnd	Battery -
Gnd	
5V	
3.3V	
Reset	
IORef	