SED

Student Experiment Documentation

Document ID: BX25_IRIS_SEDv1-1_21Mar17

Mission: BEXUS 25

Team Name: IRIS

Experiment Title: InfraRed albedo measurements In the Stratosphere

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Version:	Issue Date:	Document Type:	Valid from
1.1	**23 March 2017**	**PDR**	**17 December 2016**

Issued by:

The IRIS Team

Approved by:

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Change Record

Version	Date	Changed chapters	Remarks
0.0	2017-01-01	New Version	Blank Document
1.0	2017-01-27	All	PDR
1.1	2017-03-23	Abstract, Chap. 1.4, 2, 3, 4, 5, 6, 8, App B Added: Chap: 4.5.1, 4.10, 5.2.1, 5.2.2, App E, App F	PDR feedback
2.0			CDR
3.0			IPR
4.0			EAR, Pre-Campaign
5.0			Final Report

Abstract: Student Experiment Documentation of InfraRed albedo measurements In the Stratosphere for BEXUS from Luleå University of Technology.
Keywords: BEXUS, infrared, albedo, IRIS, SED - Student Experiment Documentation, LTU - Luleå University of Technology, SNSB, DLR, ESA, SSC, ZARM, Eurolaunch

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Preface

This document is a part of the preliminary design review ~~(PDR)~~ for the IRIS experiment. Its main purpose is to provide the reader with information on all basic knowledge about how the mission is designed and planned to perform albedo measurements from a high altitude balloon (HAB). The Student Experiment Documentation ~~(SED)~~ consists of the following chapters, analysed below:

- Chapter 1 - Introduction:
  This chapter explains briefly the scientific material on which this mission was based. The mission's objectives and concept is displayed. Information about the team and the team members can be found here.
- Chapter 2 - The Experiment Requirements and Constraints:
  Here, the technical functionalities are defined. These are needed to be met according to the specific requirement standards to ensure the reliability of the experiment.
- Chapter 3 - Project Planning:
  This chapter describes the schedule, the distribution of work, the available resources, the risks that have been taken into consideration and the outreach approach of the experiment.
- Chapter 4 - Experiment Description:
  This chapter clarifies the setup of the experiment, the interfaces and components, the design of the various subsystems, and the ground support equipment in need for the robustness of the experiment.
- Chapter 5 - Experiment Verification and Testing:
  This chapter displays the verification matrix and the several types of tests that will be performed in order to assure the correct operation of the experiment.
- Chapter 6 - Launch Campaign Preparation:
  In this chapter, information about the Input for the Campaign, Flight Requirement Plans, Preparation, and Test Activities at Esrange, Timeline and Countdown for the Flight, are explained along with the Post-Flight Activities
- Chapter 7 - Data Analysis:
  This chapter presents the data analysis plan, the launch campaign, results obtained, and most importantly the lessons learned from this experiment.
- Chapter 8 - Abbreviations and References:
  Contains all the abbreviations found in the document.

Information about the Experiment Review, Outreach, Additional Technology Information and Checklists are found in the Appendices in the end of the document.
The scientific terms that have been studied are emphasised in *italics*, and they are used to further comprehend the necessary scientific background for the conduction of the mission's scientific research.

This is an updated version of the first release of IRIS mission Design Document.

The REXUS/BEXUS programme is performed under a bilateral Agency Agreement between the German Aerospace Center (DLR) and the Swedish National Space Board (SNSB). The Swedish share of the payload has been made available to students from other European countries through a collaboration with the European Space Agency (ESA) [1].

EuroLaunch, a cooperation between the Esrange Space Center of SSC and the Mobile Rocket Base (MORABA) of DLR, is responsible for the campaign management and operations of the launch vehicles. Experts from DLR, SSC, ZARM and ESA provide technical support to the student teams throughout the project [2].

Suggested journals and books that have been an inspiration and give insight into the scientific background of IRIS, apart from the ones used as references in the current documentation:

- International Journal of Climatology. [3]
- International Journal of Atmospheric Sciences. [4]
- The Arctic Climate System, By Mark C. Serreze, Roger G. Barry. [5]
- The Cryosphere, An interactive open-access journal of the European Geoscience Union.[6]
- Polar meteorology, World Meteorological Organisation. [7]

Acknowledgements

This work has been generously supported by REXUS/BEXUS organisers, SNSB, DLR, ESA, SSC, ZARM, ESRANGE, IRF Kiruna, our university LTU, Thomas Khun, Olle Persson, our endorsing professor Mathias Milz and our technical mentor Piotr Skrzypek. Our team has received support and advice from an immense number of individuals and organisations, so many in fact, that it would be impossible to mention them all without forgetting someone. Though the extents of the contributions vary greatly, they are all important for the success of our mission, and the entire team is and will be eternally grateful for everything that has been done for us. It is our sincere hope, however, that everyone who has been involved will feel a sense of pride when reading this document.

Without your support this project would not have been possible, and we will do everything in our power to make the most of this unique opportunity.

Thank you!
IRIS Team

Abstract

IRIS consists of an apparatus which aims to measure the incoming radiation from the Sun and Earth's reflection, in order to determine local albedo variations, throughout the troposphere and the stratosphere. Terms such as the red edge, Solar Zenith Angle ~~(SZA)~~, atmospheric extinction and clouds' microphysical properties, will be examined and are taken into consideration. The measurements will be performed by photodiodes pointing upwards and downwards, which cover the visible, ~~(VIS)~~ the near-infrared, ~~(NIR)~~ and infrared ~~(IR)~~ spectrum. A camera facing downwards will define the surface that lies directly beneath the gondola and a camera facing upwards will facilitate the obervation through the determination of cloud presence. Sensors, pointing upwards and downwards, will allow the differentiation between the intensity from these two directions, and how it varies depending on the altitude. The photodiodes and the cameras will be placed respectively on the outer endpoint of each of the two booms, whose other endpoint shall be attached on the frame of the gondola. A high-altitude balloon traversing through the troposphere and the stratosphere is required for the distinguishment of the albedo variations, as other remote sensing methods are not as effective. The experiment, specially planned and designed for this mission, is taking into consideration all the requirements, constrains and risks needed to be ruminated. Thus, effectiveness of measurements is securely provided. Measuring the radiation balance of the Arctic region will aid in the development of future numerical models describing the radiative balance and the climate all over planet Earth. The supreme aim is to reduce error accumulated from remote satellite measurements.

1 Introduction

1.1 Scientific/Technical Background

The *albedo* is a non-dimensional, unit-less quantity, which indicates the quality of reflectance a surface can return. The *bond albedo* specifically, is a measure of the ratio of incident and reflected radiation. Albedo is connected directly to the heat energy budget of the planet, since the solar radiation that is not absorbed from the Earth's surface and the clouds in the atmosphere, is directly reflected into space. Thus, the long-term trend of albedo is that of cooling.
Variety and quality of the *local vegetation*, *atmospheric compositions*, type of *clouds* found throughout the troposphere and stratosphere, the *Solar Zenith Angle (SZA)* and the *wavelength* of incoming light from the Sun[8] are all factors that influence deterministically the albedo. Therefore, it is of great interest to further investigate thoroughly into how they influence the temperature equilibrium of our planet.

For the ground albedo measurements, surface type, colour and moisture and the SZA, are the most important variables to be taken into consideration.[9]
The variety and quality of vegetation is, for this reason, directly connected to the albedo. The type and healthiness of vegetation contributes to its reflectance. The *"red edge"*, consisting of wavelengths between 680-750 nm, is the spectral signature characteristic of terrestrial vegetation. This is due to the strong absorption by chlorophyll in the red region, in contrast to a strong reflectance in the near-infrared. Measurements of the red edge can provide valuable information about the chlorophyll concentration of the observed vegetation. Thereon, these measurements can be used to distinguish between living and dead plants, in order to detect and describe the anomalies of the terrestrial albedo. Previous studies have showed that the finest indicator of the level of chlorophyll contained in vegetation, is the edge of the *red edge peak*. The area of the red edge peak is useful for estimating the leaf area index. To conclude, the red edge measurements are useful, not only for the determination of the nutritional status of vegetation, but also for that of its health. [10]

Moreover, the different *types of clouds* [11] and *atmospheric compositions* influence radiation scattering through atmospheric extinction.
Clouds have a prodigious impact on the albedo, since depending on their height, temperature, thickness and composition, they play a major role to radiation scattering. This is because they consist of various droplet formations, whose size of effective radius has different scattering properties. Along with the anthropogenic aerosol particles and their absorption properties, these characteristics greatly affect the albedo and radiation scattering.

Another factor that affects the albedo is the SZA. The SZA is an indicator of radiance. It is the angle between the local zenith point and the midpoint (line of sight) of the sun. For this reason it is calculated as a function of time, day and latitude. The albedo of most surfaces depends highly on the SZA, with a general trend of increase in albedo for increasing SZA. Consequently, SZA is an essential parameter to be defined in order

to correctly calculate the local albedo of an area. Snow is an exception to this case; showing almost no variation and in some cases even a decreasing albedo for larger SZA [12]. Usually, the larger the SZA is, the weaker becomes the exposure in sun's rays, because the same amount of light is spread to a larger area.

A study conducted by Steven A. Lloyd, published in 1990[13], concluded that the radiation field in the polar atmosphere is vastly different than that of lower latitudes due to several factors. The atmospheric scattering is increased for wavelengths below 340nm because of ozone depletion: ozone holes significantly affect wavelengths in the region between 280-310 nm. For smaller values of SZA, particularly below 60 degrees, surface albedo is important to consider. When this angle increases, less direct sunlight reaches the surface, but a large value of surface albedo still has some effect. All of these effects are important for estimating the rate of ozone destruction, though the most important one appears to be cloud cover.

For satellite remote sensing radiative transfer is a necessary tool. It models the sinks and sources of radiation, in other words how the intensity changes throughout the atmosphere. It specifically has terms for the absorption (transmittance), emission and scattering. It is however an empirical formula that requires assumptions, such as the local thermodynamic equilibrium (LTE). The full radiative transfer equation (RTE) in differential form is stated below:

$$\frac{dI}{ds} = -(\beta_a + \beta_s)I + \beta_a B(T) + \beta_s \int_{4\pi} P(\Omega',\Omega)I(\Omega')d\Omega'$$

Here I is the intensity, s the path through the atmosphere, β_a and β_s are the absorption and scattering coefficients, Ω is the angle, $B(T)$ the Planck function and $P(\Omega',\Omega)$ the scattering probability.[14] This equation is used by RTE models such as Futbolin.[15]

It is important to consider that the polar regions, such as Lappland, are extremely important for the global climate, but they have not yet been studied enough. Their unstudied properties related to the modelling and parameterization of climate change are needed to analytically define in detail the parameters that influence the radiation budget. In terms of Albedo measurements, polar arctic regions have not been studied as intensely as other areas in lower latitudes. A small number of ground measurements have been performed in the past. Mostly polar orbit (PO) weather and PO imagining satellites are used to monitor the albedo and other important factors that aid the creation of climate prediction models. NOAA and CERES, NASA are two of the main researchers that assist in albedo monitoring. Hence, BEXUS provides a unique opportunity to study this otherwise remote place, since the balloon will be launched from Esrange Space Center in northern Sweden.

1.2 Mission Statement

The overall purpose of IRIS is to contribute to error elimination in remote sensing satellite measurements, by measuring the albedo (ratio of intensity between incoming and reflected outgoing radiation) and its change throughout the troposphere and the stratosphere. Specifically, in contrast to all remote sensing satellite measurements, IRIS will gather data from much thinner atmospheric layers, by the use of light sensors and a High Altitude Balloon (HAB). This process will increase the possibility of error estimation accumulated from remote sensing measurements.

1.3 Experiment Objectives

Obj.1 IRIS mission is based on the following primary scientific objectives:

1.1 Effective measurement of ground albedo.

1.2 Ratio variation of incoming radiation to outgoing reflectance throughout the troposphere and the stratosphere.

1.3 Estimation and elimination of accumulated error from satellite remote sensing measurements.

1.4 Build a simple but yet reliable experiment.

Obj.2 IRIS wishes to investigate the following secondary objectives, if conditions are met:

2.1 Relation of chlorophyll levels to albedo variations.

2.2 Comparison with PO satellite remote sensing measurements.

2.3 Record of variations and distinguishment between snow and/or cold cloud albedo.

1.4 Experiment Concept

IRIS will investigate the albedo for VIS, NIR and IR wavelengths and at various altitudes, above the polar circle. The mission will be carried out by an apparatus utilising light sensors and cameras mounted on a HAB.

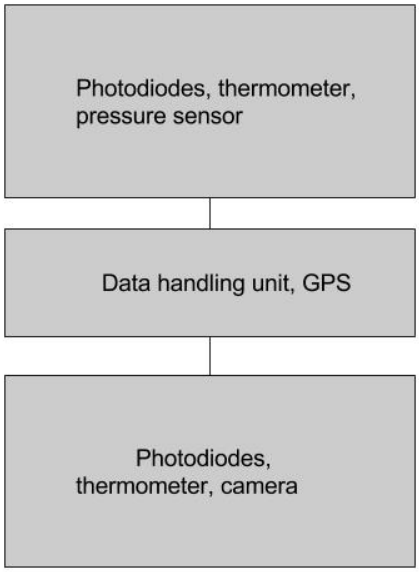


Figure 1.4.1: ~~IRIS experiment setup~~

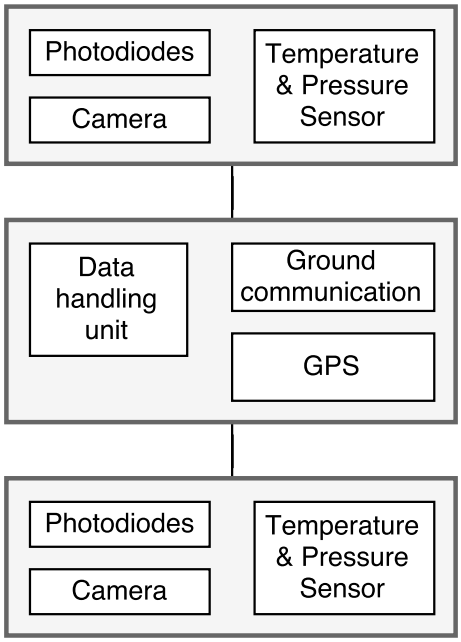


Figure 1.4.2: IRIS experiment setup

IRIS mainly consists of two sensor arrays, connected to a data storage unit. There are two separate sensor arrays, one located on the top of the gondola, looking upwards and the other one located at the bottom, looking downwards. Each array contains a number of photodiodes, which will measure the intensity of the specific wavelength bands required to conduct the scientific research. In each sensor box, there are also mounted colour cameras. The basic functional blocks are demonstrated in fig. 1.4.1.

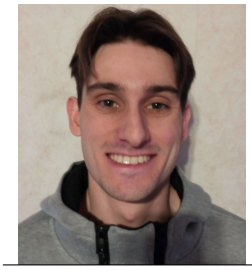
1.5 Team Details

1.5.1 Contact Point

Contact	Contact Information
Project Manager	Gustaf Ljungné Tarfalavägen 5A 98144 Kiruna, Sweden gustaf.ljungne@gmail.com +46709610679
The team	iris.bexus@gmail.com (Team email)
Contact at LTU	Associate Professor Thomas Kuhn thomas.kuhn@ltu.se Associate Professor Mathias Milz mathias.milz@ltu.se

1.5.2 Team Members

Everyone in IRIS is rewarded 15 ECTS points for the course Space Engineering Project II, P7001R by participating in BEXUS.[16]

Name and Role	Information
Gustaf Ljungné **Project Manager** 	Electrical engineering fourth year, currently working on a master in instrumentation and spacecraft design. Interests include, but are not limited to: technology, electronics, weight lifting, people skills. My role in IRIS is as the project manager. I coordinate the team and its departments.
Guillermo Ledo López **Head of Mechanical Department** 	Aerospace engineer, studying a master's degree on spacecraft design at LTU. Interested in space, physics, engineering, nature and science fiction, among others. As the head of the Mechanics department, my roles include the design of the structures and thermal control used in IRIS and the coordination of my department. I expect the heaviest workload to begin once a final configuration for the experiment has been selected and manufacturing starts.

François Piette

Mechanical Department and Head of Economics Department

I am an Aerospace Engineer student from the University of Liège (ULg), and I am currently completing my degree at Luleå University of Technology as an exchange student. I have high interest in aircraft and space launchers in Europe. In the mechanical department I am mainly in charge of CAD drafts with CATIA. In the Economics department we are actively looking for grants to secure the necessary funding. Also we are trying to establish partnerships with scientific institutes in the Arctic region. I am expecting a constant increase of the workload in each step of the design.

Lisa Jonsson

Head of Electronics Department

Currently studying the fourth year of MSc in space engineering with focus on instrumentation and control systems of spacecrafts and satellites. My tasks are to manage the electronic department, divide the workload between the members of the electronics team, choosing sensors and instruments according to the science department's specification and designing the electronics needed for the experiment.

Hampus König

Electronics Department

Currently in the fourth year of M.Sc in space engineering focused on instrumentation and spacecraft design. My tasks include choosing sensors according to the science department's specification and designing the electronics that are needed for the experiment.

Arttu Tiainen
Electronics Department

Currently on the second and thus last year of the MSc in spacecraft design and I did my thesis on inter-satellite link antennas. Additionally I have several years of work experience in embedded electronics design and a small consultation company. My tasks include building and programming a prototype for the measurement system and supportive and advisory tasks of the electronics design.

August Svensson
Electronics Department

Currently in the third year of a MSc in space engineering with a specialisation in spacecraft and instrumentation. My tasks involve the verification and testing of the electronics and sensors, as well as electronic design.

Edgar Martín
Head of Software Department

Aerospace engineering graduate, currently undertaking a master's program in spacecraft design. Among my interests are programming, electronics and entrepreneurship. As member and head of the software department, my tasks include system architecture design, programming and maintenance of the code, as well as internal management of the department. The expected workload is to be concentrated at the final stages, when the components from the hardware team are available.

Andreas Wallgren
Software Department

Currently thesis/final project remaining on a MSc in space engineering, with a focus on atmospheric and space physics. Relevant interests include a general fascination of mathematics; in particular information manipulation in e.g. signal processing. As a member of the software department, the task is to contribute to stable and reliable software to ensure correct data and error -handling to aid a successful mission. The bulk of the work will begin with the integration of the hardware-to-be-used. Because no system ever co-operates, the workload will be heavy and hopefully rewarding.

Eleni Athanasiou
Head of Science Department

I am an Electrical Engineer, currently studying Spacecraft Design (MSc) at LTU. I have work experience on Industrial Engineering automation control systems, and on the development and test of hardware parts for accelerator and non accelerator experiments for High Energy Physics (HEP). My general interests include: particle physics , superconductivity, cryogenics, cutting edge technology, biomedical engineering, sociology, photography and painting. For the IRIS experiment I am the Head of Science Department, and my duties consists of the following:

- Develop and analyse the scientific background and objectives of IRIS.
- Post-experiment data analysis.
- Distribution of tasks within the Science department, manage and conduct communication with the other departments, as well as with the Project manager.

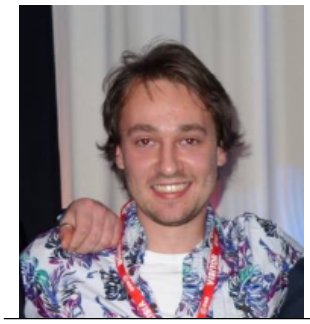
Ingo Wagner
Science Department

BSc in Earth and Space Science, currently enrolled at LTU in a master's program in Atmospheric and Space Science. My interests in science range from oceans to space and stars with a focus on the physics. In the science department my role is the development of the scientific goal as well as the application of data analysis models. As it is the nature of these roles the workload will be focused on the beginning and end of the project.

Oriol Peláez Mercadal
Science Department and Head of Optics Department

Energy and Mining resource engineering graduate, studying a master's degree on Earth's atmosphere and Solar System at LTU. I like all kind of sports and technology, as well as science and everything related with space, specially the research for new horizons, either in exoplanets or close to us, like Mars or in some of our Solar System moons. I am also very interested in space mining and terraformation, which I think is a discipline that will be very important in the near future, so harvesting resources from planets and asteroids will be very significant for the next generations in order to perform interplanetary travels. My role include development of science background and data analysis. Also, I am the Head of the Optics department, which is in charge to control the optical design of the instrumentation.

Alexander Korsfeldt Larsén
Public Relations



After a year in the telemarketing sector I enrolled at Luleå University of Technology, and I am now doing my fourth year in the Space Engineering Master Programme. Though my education is specialised towards electronics and instrumentation, my main task in this project is to handle most of the team's external communication. I am also responsible for our web page and our social media presence.

2 Experiment Requirements and Constraints

2.1 Functional Requirements

F.1 The experiment shall measure the intensity of visible light outside the gondola, looking towards the zenith.

F.2 The experiment shall measure the intensity of visible light outside the gondola, looking towards the nadir.

F.3 The experiment shall measure the intensity of infrared light outside the gondola, looking towards the zenith.

F.4 The experiment shall measure the intensity of infrared light outside the gondola, looking towards the nadir.

F.5 The experiment shall correlate the pressure at which the measurements were taken.

F.6 The experiment shall correlate the temperature at which the measurements were taken.

F.7 The experiment shall correlate the position at which the measurements were taken.

F.8 The experiment shall measure the position on the three axis of space with respect to the launching point.

2.2 Performance Requirements

P.1 ~~The experiment shall be able to distinguish between incoming and outgoing from Earth radiation.~~ Moved to D.28

P.2 The experiment shall measure the electromagnetic spectrum from 0.3 μm to 2.5 μm with a minimum sensitivity of 200 $mW \cdot m^{-2}$.

P.3 The experiment shall measure the 0.43 μm to 0.45 μm with a precision of $\pm$0.005 μm.

P.4 The experiment shall measure the 0.45 μm to 0.51 μm with a precision of $\pm$0.005 μm.

P.5 The experiment shall measure the 0.53 μm to 0.59μm with a precision of $\pm$0.005 μm.

P.6 The experiment shall measure the 0.63 μm to 0.67 μm with a precision of $\pm$0.005 μm.

P.7 The experiment shall measure the 0.85 μm to 0.88 μm with a precision of $\pm$0.005 μm.

P.8 The experiment shall measure the 1.36 μm to 1.38 μm with a precision of $\pm$0.005 μm.

P.9 The experiment shall measure the 1.56 μm to 1.65 μm with a precision of $\pm$0.005 μm.

P.10 The experiment shall measure the 2.00 μm to 2.50 μm with a precision of $\pm$0.005 μm.

P.11 ~~The sampling rate of the experiment shall be between 5 and 10 seconds.~~ See P.18 and P.19

P.12 The sampling delay shall not exceed 30 seconds.

P.13 The experiment shall measure the pressure from 5 to 1100 $mbar$.

P.14 The experiment shall measure the pressure with a minimum accuracy of ± 10 $mbar$.

P.15 The experiment shall measure the temperature from -90 to 30 $^{\circ}C$.

P.16 The experiment shall measure the temperature with a minimum accuracy of ± 1 $^{\circ}C$.

P.17 The experiment shall measure the position with a minimum accuracy of ± 10 m.

P.18 During the ascend phase the sampling frequency shall be 3 seconds.

P.19 During the float phase the sampling frequency shall be 10 seconds.

2.3 Design Requirements

D.1 ~~The experiment shall not include components that could prove to be dangerous for people.~~

D.2 ~~The experiment shall not include components that disturb or harm the launch vehicle.~~

D.3 ~~The experiment shall not include components that disturb or harm other experiments.~~

D.4 The experiment shall not weight more than 8 kg upon launch.

D.5 The experiment shall withstand vertical accelerations within the BEXUS launch and flight profile.

D.6 The experiment shall withstand horizontal accelerations within the BEXUS launch and flight profile.

D.7 The experiment's data storage unit should withstand shocks of up to 35 g during landing.

D.8 The experiment shall withstand vibrations related to handling and transportation before and after flight.

D.9 The experiment shall withstand pressures within the BEXUS flight profile.

D.10 ~~The experiment shall withstand temperatures within the BEXUS flight profile.~~

D.11 The experiment shall not be at risk of falling from the gondola during flight and launch.

D.12 ~~The experiment shall not slide or translate inside the gondola during flight and launch.~~

D.13 The experiment should be attached to the gondola rails if possible.

D.14 The fastening to the gondola rails shall be carried out with M6 bolts with 23 mm thread length.

D.15 The experiment shall use a sufficient number of brackets on bottom plates in order to facilitate mounting of experiments.

D.16 The experiment shall operate at temperatures within the BEXUS vehicle flight and launch profile.

D.17 ~~All critical experiment components shall be accessible within 2 minutes.~~

D.18 The replacement time of the replaceable experiment components shall be within 15 minutes.

D.19 The experiment shall use a maximum electrical energy of 275 Wh.

D.20 The experiment shall use Ethernet 10/100 Base-T with RJ45 connectors for interfacing with the provided E-link.

D.21 The experiment shall use Ethernet 10/100 Base-T with RJ45 connectors for interfacing with the ground station.

D.22 The experiment shall use a 4 pin, male, box mount receptacle MIL-C-26482P series 1 connector with an 8-4 insert arrangement as power interface.

D.23 The data storage unit shall withstand any post-landing environment within the mission profile without corruption or loss of data for at least 3 days.

D.24 ~~The experiment shall be able to handle two aborted launches.~~

D.25 The experiment shall not use a downlink rate greater than 200 kbit/s.

D.26 The experiment may include sacrificial joints or other contingency plans to avoid being damaged upon landing if it protrudes from the gondola.

D.27 The position of the experiment should be selected in order to reduce "noise" interference from other experiments.

D.28 The experiment shall be able to distinguish between incoming and outgoing from Earth radiation.

D.29 The sampling time of optical instruments shall be synchronized.

2.4 Operational Requirements

O.1 The experiment sensors shall be clean from dust before launch.

O.2 The experiment shall accept commands from the ground station at any time.

O.3 The procedures to turn the experiment on and off should be kept simple.

O.4 The experiment shall perform autonomously in the event of loss of communication with the ground station.

O.5 The experiment shall be able to correctly handle aborted launch attempts during any point leading up to, including pre-flight tests, the launch.

2.5 Constraints

C.1 The E-Link data transfer rates are limited by coverage and quality of reception, imposing restrains on the uplink/downlink available rate.

C.2 ~~Protrusion of parts outside the gondola is restricted by the flight operators.~~

C.3 ~~The position of the experiment is not fixed at this stage.~~

C.4 The budget for the experiment is limited by external sponsorship.

C.5 The weather conditions are to affect the experiment and its outcomes if the sky is overcast for secondary mission objectives.

C.6 Time of delivery of components is limited on the team's location, affecting manufacturing times.

3 Project Planning

This following section will explain the work distribution and expected workload for each member. It is based on when the different reviews have deadlines and what main tasks exist within the different departments.

3.1 Work Breakdown Structure (WBS)

IRIS's WBS can be seen in fig. 3.1.1. The WBS is divided into the eight departments that the team consists of, and the work packages are the main tasks in each department.

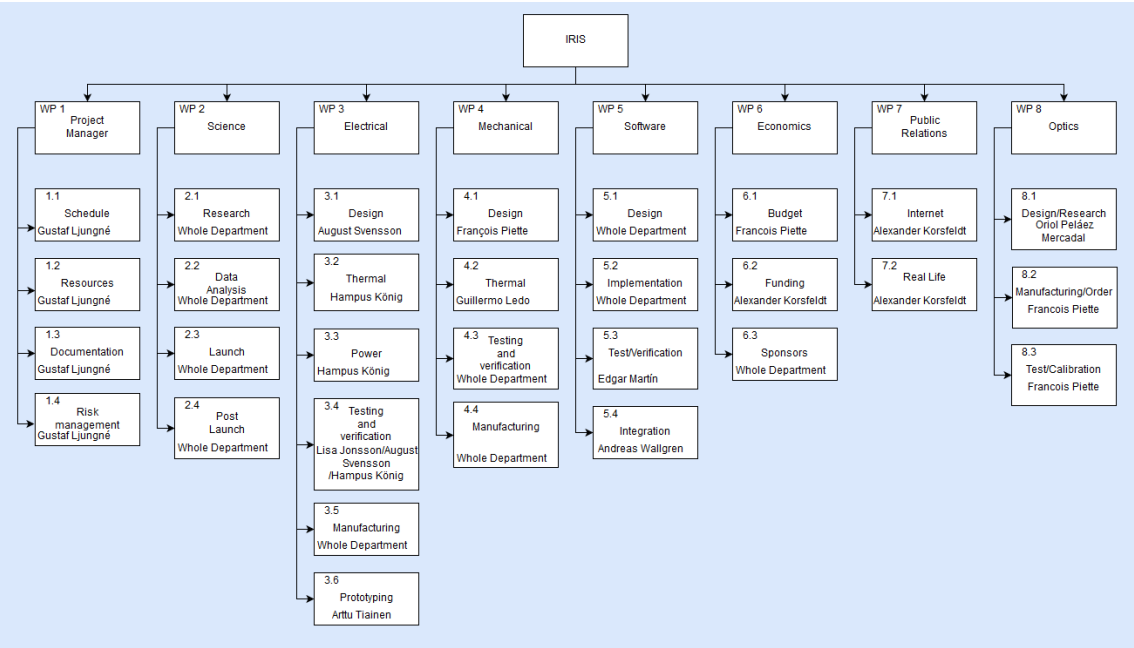


Figure 3.1.1: The WBS for IRIS

For WBS for each department see app. E.

3.2 Schedule

Fig. 3.2.1 and 3.2.2 is the estimated time and tasks distribution within the IRIS team. Included are all reviews, launch, student traning week and exam periods. For more detail see app. E.

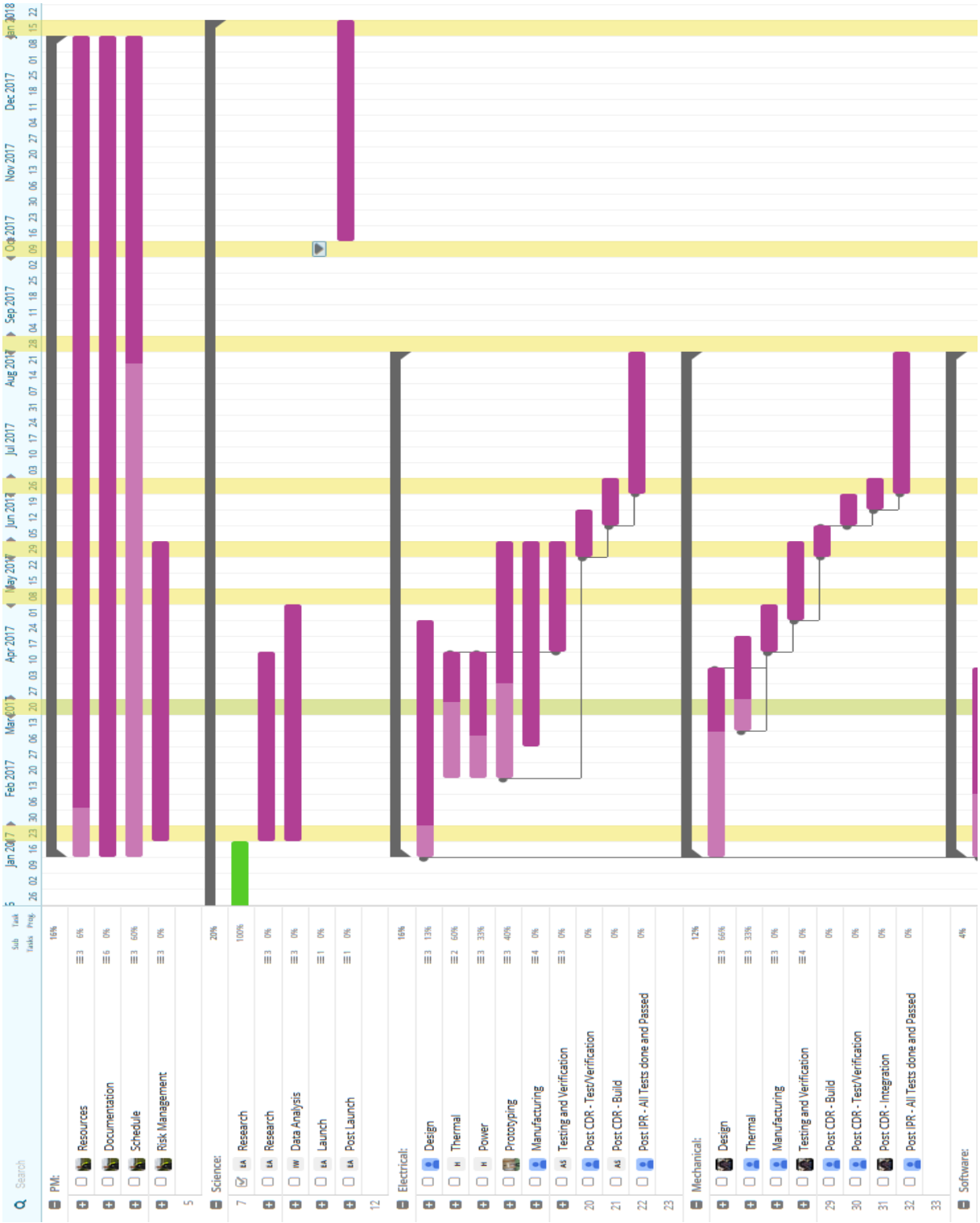


Figure 3.2.1: Gantt chart, part 1

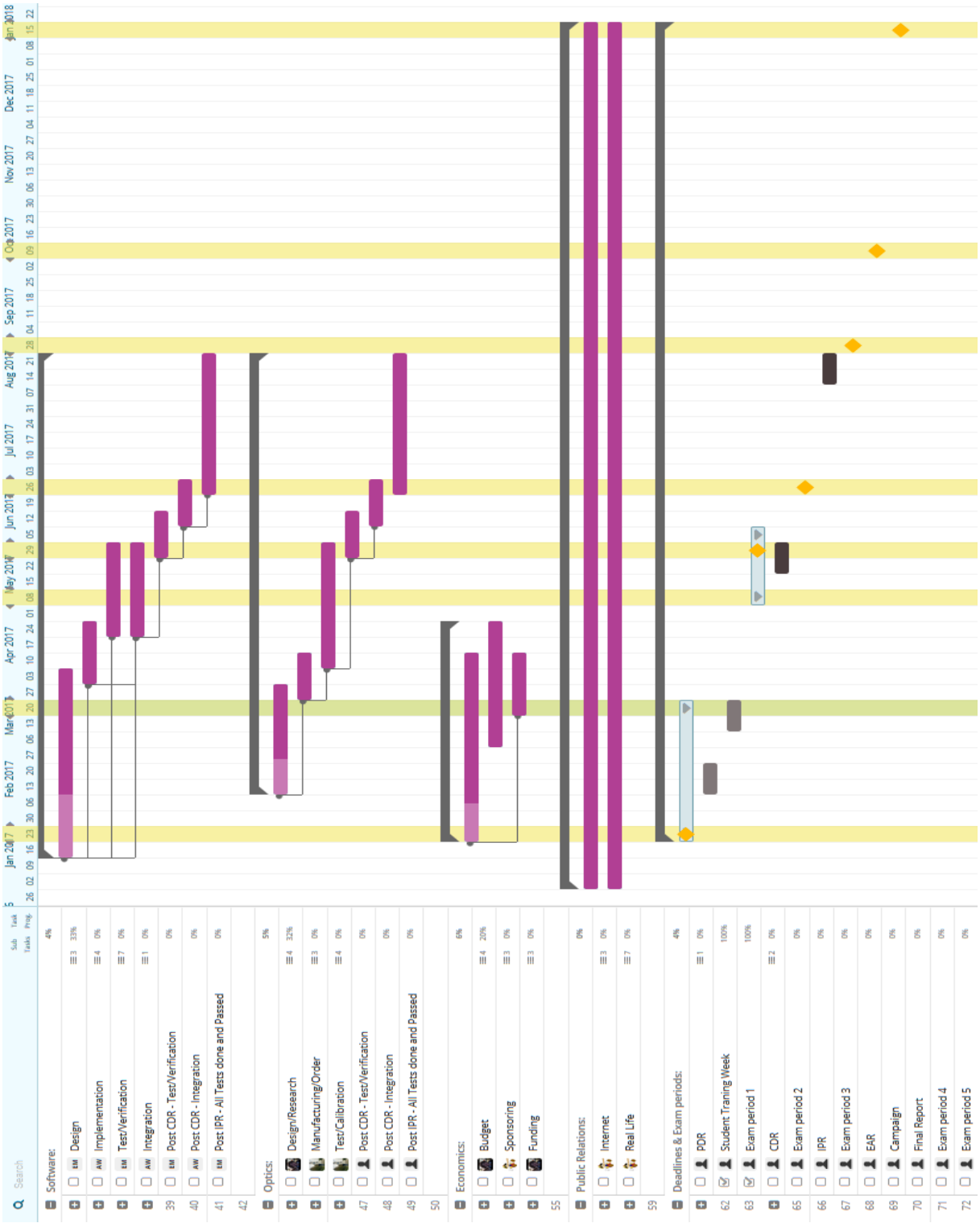


Figure 3.2.2: Gantt chart, part 2

3.3 Resources

3.3.1 Manpower

Tab. 3.3.1 and 3.3.2 show that the work hours are estimated to be distributed among the team members.

Table 3.3.1: Colour code for the work distrubution

Colour Code	Amount of time (100 % is 20h)
	More than 80 %
	60 to 80 %
	40 to 60 %
	Less than 40 %
	Not present

Table 3.3.2: Work load in hours for each team member

Month / Member	Jan	Feb	Mar	Apr	May	Jun	Jul	Aug	Sep	Oct	Nov	Dec	Jan
Gustaf													
Eleni													
Lisa													
Edgar													
Guillermo													
François													
Alexander													
Arttu													
Ingo													
Oriol													
Hampus													
August													
Andreas													

3.3.2 Budget

The current budget estimation is shown below in tab. 3.3.3. These calculations are rough, and will be updated as the design phase progresses, but they show that the total expenditures are currently higher than the secured funding. The costs for suitable lenses proved to be much higher than anticipated, and so the team is currently investigating means to obtain additional hardware funding and/or sponsorship from the manufacturers. Costs for the Outreach Programme have now been estimated; most notably this estimation includes participation in two larger conferences, namely the 23rd ESA PAC Symposium held in Visby in June 2017 and the EGU General Assembly held in Vienna in April 2018. Also included is travel costs for individual team members to hold presentations

at universities in their home countries. The team is currently working on applications for various research grants, which will allow these outreach activities to be performed. It is important to note that the cost of spare parts have not yet been considered. A decision will be taken shortly on which parts are essential to have extras of. Most of the tests required for the mission can be performed at LTU, and so will not incur extra costs. Costs for the remaining tests are being investigated. More information about individual components can be found in section 4.3.

Table 3.3.3: Budget estimations

Incoming/outgoing	**Amount**	**Where the money comes from/goes to**
Outgoing	€1,000	Electrical components
Outgoing	€4,500	Sensor filters and lenses
Outgoing	€450	Mechanical parts
Outgoing	€750	Manufacturing, mechanical (materials+labour)
Outgoing	€7,000	Outreach and travel costs
Incoming	€3,000	LTU Project Course
Incoming	€3,000	SNSB
~~Incoming~~	~~TBD~~	Å~~Forsk Foundation~~
Incoming	TBD	LKAB Academy
Incoming	TBD	Sveriges Ingenjörer - Miljöfonden
Incoming	TBD	Progressum
Total Incoming	€6,000	(Amount will increase once external funding gets approved)
Total Outgoing	€13,700	(Spare parts not included. Outreach and travel costs can be scaled down if required)
Total Balance	-€7,700	

3.3.3 External Support

Table 3.3.4: External Support

Support to	**Information**

Whole Team	**Name:** Mathias Milz **Title:** Associate Professor **Research Area:** Atmospheric science **Relation to the Team:** Endorsing Professor **Department:** LTU, Department of Computer Science, Electrical and Space Engineering **Email:** mathias.milz@ltu.se **Phone:** +46(0)980 67541
Whole Team	**Name:** Thomas Kuhn **Title:** Associate Professor **Research Area:** Atmospheric science **Relation to the Team:** Examiner **Department:** LTU, Department of Computer Science, Electrical and Space Engineering **Email:** thomas.kuhn@ltu.se **Phone:** +46(0)980 67538
Software/Whole Team	**Name:** Piotr Skrzypek **Title:** Flight Software Systems Engineer **Research Area:** On-board software **Relation to the Team:** Technical Mentor, Software **Department:** Systems Department **Email:** Piotr.Skrzypek@esa.int **Phone:** +31715655052
Whole Team	**Name:** Olle Persson **Title:** Operations Administrator, LTU centre of excellence **Department:** LTU, Department of Computer Science, Electrical and Space Engineering **Email:** olle.persson@ltu.se **Phone:** +46(0)920 497571
Whole Team	**Name:** Victoria Barabash **Title:** Doctor **Research Area:** Atmospheric science / Physics of the upper atmosphere **Department:** LTU, Department of Computer Science, Electrical and Space Engineering, Division of Space Technology **Email:** victoria.barabash@ltu.se **Phone:** +46(0)980 67532

Software	**Name:** Anita Enmark **Title:** Doctor **Research Area:** Atmospheric science **Department:** LTU, Department of Computer Science, Electrical and Space Engineering **Email:** Anita.Enmark@ltu.se **Phone:** +46(0)980-67534
Electrical	**Name:** Soheil Sadeghi **Title:** Associate Senior Lecturer **Research Area:** Onboard space systems **Department:** LTU, Department of Computer Science, Electrical and Space Engineering, Division of Space Technology **Email:** soheil.sadeghi@ltu.se **Phone:** +46 (0)920 497574
Electrical/Mechanical	**Name:** Rita Edit Kajtar **Title:** PhD Student position **Research Area:** Atmospheric science **Department:** LTU, Department of Computer Science, Electrical and Space Engineering **Email:** rita.edit.kajtar@ltu.se **Phone:** +46 (0)920 497573
Mechanical (Manufacturing)	**Name:** Kent Johansson **Company:** Åkleby Mekaniska AB **Address:** Åkleby, Åvik 541 91 Skövde Sweden **Phone:** +46(0)500-460313 **Fax:** +46(0)500-460313 **Mobile:** +46(0)709461578 **Email:** aklebymek@telia.com
Mechanical (Manufacturing)	**Name:** Johan Ljungné **Company:** Björnasäter Smide **Address:** Stora Björnasäter 540 17 Lerdala Sweden **Email:** johan.ljungne@gmail.com **Mobile:** +46(0)709609810
Mechanical/Electrical	**Name:** Joakim Öman **Company:** SSC **Location:** Esrange Space Center **Division:** Science Services: Instrumentation **Email:** Joakim.Oman@sscspace.com

Mechanical/Electrical	**Name:** Kent Andersson **Company:** SSC **Location:** Esrange Space Center **Division:** Science Services: Instrumentation **Email:** Kent.Andersson@sscspace.com

3.4 Outreach Approach

The main idea of the IRIS Outreach Program is to focus on reaching a younger audience, e.g. university and high school students. This will be achieved through social media, the IRIS website, and by holding presentations at universities, high schools, and various events. Articles in local and national newspapers, as well as on university websites, are also part of our outreach plan. The current plan is to contact national media, including newspapers, television, and radio, once the first prototype of the experiment is completed.

The team's website can be found at https://www.bexusiris.com/. The old URL still works. The website contains all essential information about the project and the team members behind it, as well as a short description of the REXUS/BEXUS programme. Articles written by the various departments will be regularly published, so the website also acts as a blog or development diary. All important documents produced by the IRIS team will be uploaded to this site, and made available to the public. The idea is that future students participating in this programme, or a similar one, can use our site as a resource. It also contains logos with links to all of our sponsors and stakeholders.

IRIS has a Facebook page, located at facebook.com/bexusiris/. News and photos are shared here in a format easily accessible. Whenever an article is posted on our website, a link to the article, as well as a short summary, will be posted here. The team also has an Instagram account that will be used to upload pictures on a regular basis. It can be found at @bexus_iris.

3.5 Risk Register

- TC – Technical/implementation
- MS – Mission (operational performance)
- SF – Safety
- VE – Vehicle
- PE – Personnel
- EN – Environmental
- OR - Outreach
- BG - Budget

Table 3.5.1: The rankings of probability (**P**) and severity (**S**)

Probability P	**Severity S**
A. Minimum – Almost impossible to occur	1. Negligible – Minimal or no impact
B. Low – Small chance to occur	2. Significant – Leads to reduced experiment performance
C. Medium – Reasonable chance to occur	3. Major – Leads to failure of subsystem or loss of flight data
D. High – Quite likely to occur	4. Critical – Leads to experiment failure or creates minor health hazards
E. Maximum – Certain to occur, maybe more than once	5. Catastrophic – Leads to termination of the REXUS and/or BEXUS programme, damage to the vehicle or injury to personnel

Table 3.5.2: Risk Register

ID	**Risk (and consequence if not obvious)**	**P**	**S**	**P × S**	**Action**
MS10	Hercules impact if the experiment protrude from the gondola	B	4	Low	Prepare spare parts of the experiment.
MS20	Failure of several sensors	C	2	Low	Choose appropriate sensors for the flight and thoroughly test them.
MS30	The balloon rotation will influence results on each sensors	E	2	Medium	Including sensors (electronic gyro/accelerometer) to estimate rotation rate might help data analysis.
MS40	Temperature sensitive components that are essential to fulfil the mission objective might be below their operating temperature	C	3	Low	Safe mode to prevent the components to operate out of its operating temperature range.
MS50	The MCU/Central computer unit might fail, it will prevent any further collect of data	B	3	Low	Requires several tests of the robustness of the system. If it cannot be assessed, a redundant system will be required.
~~SF10~~	~~Mechanical failure of bolts~~	~~B~~	~~5~~	~~Medium~~	~~Stress calculation and testing is required.~~

SF20	Self-loosening of bolts and nuts. Mechanical failure of bolts	B	5	Medium	Redundancy to prevent the experiment to fall off. Stress calculation and testing is required.
SF30	Parts of the experiment may fall off the gondola during flight or pre-launch	B	5	Medium	Redundancy to prevent the experiment to fall off.
TC10	Failure of the experiment during testing	C	3	Low	Prepare spare parts of the experiment.
TC20	Insufficient technical experience	C	3	Very Low	Laboratory equipment and external support guidance.
EN10	Full coverage of low and dense clouds will lead to one type of measurements	C	2	Low	The mission objective need to be prepare to this case.
EN20	No snow covered ground during the flight	D	2	Low	The mission objective need to be prepare to this case.
EN30	Low Sun zenith angle	D	1	Low	A low SZA is not problematic because we will still be able to measure the light being scattered from the top.
EN40	The post-landing environment conditions might corrupt or destruct the data	C	4	Medium	Testing of the data storage robustness against post-landing environmental conditions during several days.
EN50	Accumulation of dust particles on sensitive equipment, e.g. lenses or filters	C	2	Low	Accurately estimate the risk, limit unnecessary expose of sensitive equipment to environment. A protective cover of lenses can prevent the accumulation of dust.
EN60	Formation of waterdroplets on sensitive equipment, e.g. lenses	A	2	Very Low	Accurately estimate the risk, limit unnecessary expose of sensitive equipment to enviroment.

BG10	The expected budget is not met	B	3	Low	By assuring sufficient funding before critical phase or by reducing the number of costly components.
BG20	Failed outreach approach	B	1	Very Low	Adapt communication approach to each potential target groups we address.
OR10	One flight might not be enough to achieve the scientific goals	D	2	Low	Prepare eventually for other flights with other balloons to increase data sample.
PE10	Team members leaves the team	C	2	Low	Even if people leave other team members can cover that.Files uploaded in common folders, frequent meetings and updates to understand each other's work.
PE20	Communication: team member misunderstands objectives/requirements	B	2	Low	Regular weekly meetings scheduled between the departments and get expert advice from external support. (See section 3.3.3)
PE30	University schedule overlaps with project responsibilities	C	2	Low	Proper scheduling of BEXUS and university workload. Resource Allocation.
PE40	Members lacking motivation	B	2	Very Low	Frequent talks and presentations within meetings to have a clear goal in mind.
PE50	Fail or lack of communication between members	B	2	Very Low	Frequent meetings organised, members encouraged by their team members to discuss their difficulties.

PE60	Unplanned events that will have a negative impact on the project's timeline.	C	2	Low	Enough number of team members to cover each others work - good interpersonal communication between members.

4 Experiment Description

4.1 Experiment Setup

The IRIS experiment consists of two sensor arrays - one at the bottom of the gondola, pointing downwards, and the other one at the top, pointing upwards - and a data storage unit. The main sensors needed for the experiment are light sensors in the infrared and visible wavelength spectrum, namely photodiodes. These have fisheye lenses mounted on them to expand their field of view. A camera is also going to be included on both sensor boxes. Interior temperature sensors are included, to check whether the equipment is working inside their safe temperature ranges. An atmospheric pressure sensor and a GPS will also be included.

Data is managed by microcontrollers and is sent both to the data storage unit and to the ground station, while another microcontroller uses the internal temperature measurements to manage an active thermal control system, composed of electrical heaters. A detailed view of the subsystems that are going to form the experiment can be found in fig. 4.1.1.

4.2 Experiment Interfaces

4.2.1 Mechanical

The experiment is composed of three main units, namely the upper sensor box, the bottom sensor box and the brain box. A general view of the IRIS mechanical design can be seen on fig. 4.2.1. The upper and bottom sensor box are protruding from the gondola by using booms, while the brain box is kept inside the gondola. ~~The upper box, which contains the upper sensor array and the data storage unit, is attached to the upper gondola frame by four (4) clamps, next to the telemetry boxes as shown on fig. **??**. The bottom box, which contains the electronics for the floor mounted unit, is attached to the provided gondola rails, as shown on fig. **??** using four (4) M6 bolts with 23 mm thread length, as specified on the REXUS/BEXUS User Manual.~~
~~An aluminium plate is fitted to the bottom of the gondola on the outer side, using two (2) M6x23mm bolts, two (2) M6 nuts and two (2) M6 washers. The floor mounted unit, containing the bottom sensor array and the camera, is attached to this plate. This design has been selected for the large field of view it allows for the sensors, without the need for a protruded design. A view of the mounting of the floor mounted unit is shown on fig. **??** and **??**.~~

Two booms are used for each sensor box to provide a stiff and stable structure. This design might be overengineered and requires more analysis. Each pair of booms extend $1m$ away from the gondola frame to minimise the interference with the belts of the gondola. The upper and bottom sensor box were designed to be as symmetric as possible, in order to reduce the number of additional spare parts. However the mounting of the booms cannot be identical. For the upper booms we use clamps to mount the booms on the gondola structural frame, as shown on fig. 4.2.4. 4 M6$\times$60 are used to assure the structural stability of the booms.

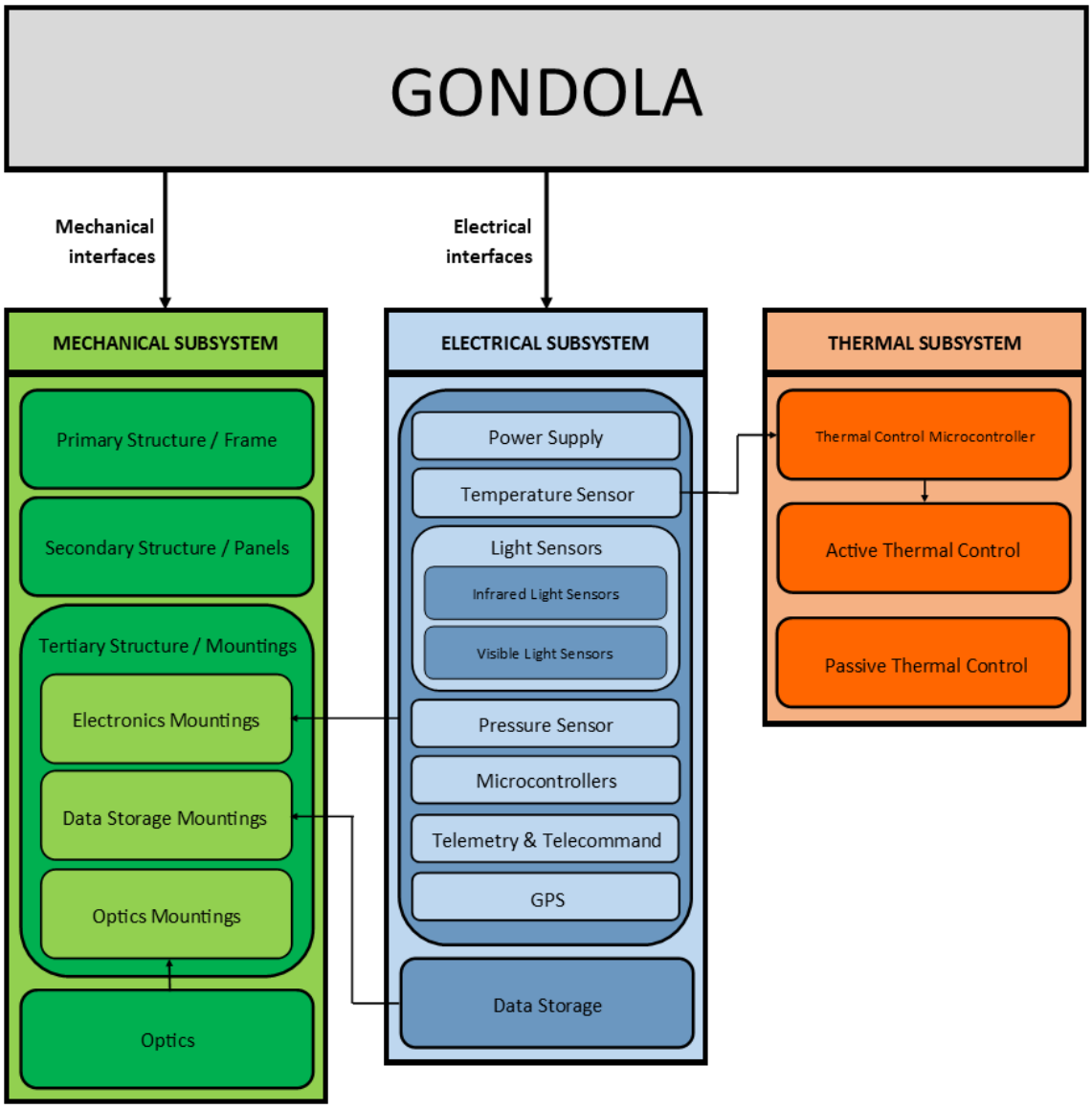


Figure 4.1.1: Subsystem diagram of the IRIS experiment.

For the bottom booms similar clamps are used to mount them on the mounting rails, as shown on fig. 4.2.3. 12 M6×23 are used to assure the structural stability of the booms.

The sensor box mounted on each of the upper and bottom booms have an identical mounting on each. As shown on fig. 4.2.5, 4 M6×60 are used with washers and nuts to mount it to the booms. Further analysis of this structure is under investigation.

The brain unit has been designed to be large enough in order to mount it on the gondola rails, which drove us to reduce its height. The brain box is mounted by using the mounting rails of the gondola with M6×23 bolts, as shown on fig.4.2.2.

Static load and shock tests will be conducted to check whether the chosen nuts and

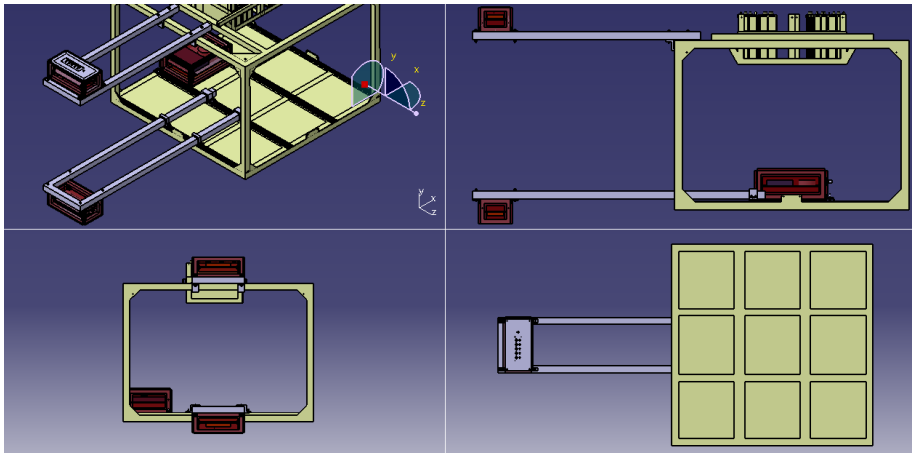


Figure 4.2.1: General view of the experiment from four different perspectives: Isometric perspective (upper left), plane xy (upper right), plane yz (lower left), and plane xz (lower right).

bolts meet the requirements stated in section 2.3.

Table 4.2.1: Bolts, nuts and washers used to mount the bottom, upper and brain box on the gondola.

Box	Bolts	Nuts	Washers
Upper Sensor Box	8 M6×60	8 M6	16 M6
Bottom Sensor Box	12 M6×23, 4 M6×60	16 M6	20 M6
Brain Box	4 M6×23	4 M6	4 M6

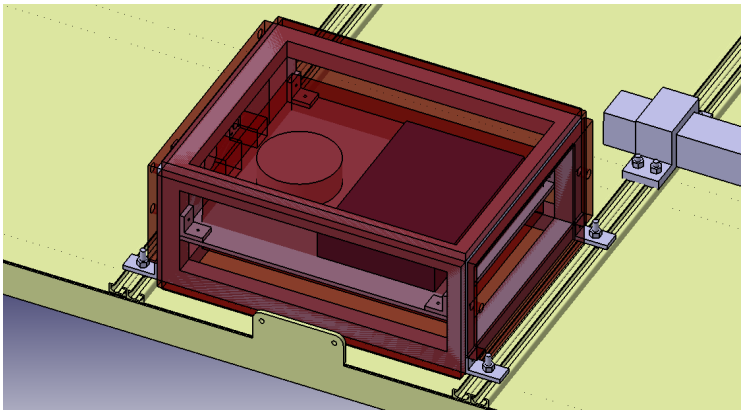


Figure 4.2.2: Top view of the "Brain" unit mounted on the gondola mounting rails.

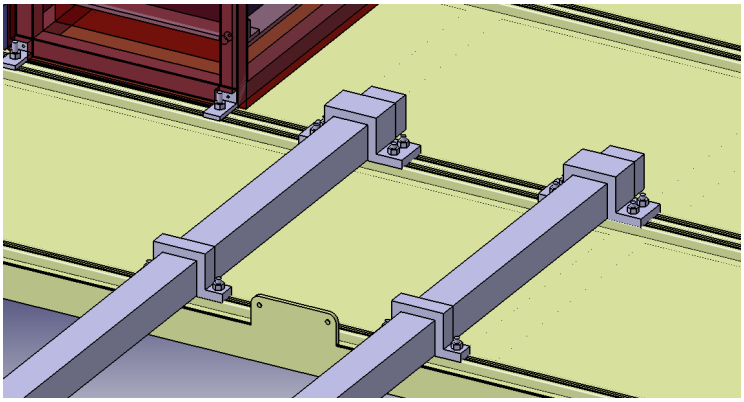


Figure 4.2.3: Top view of the lower booms mounted on the gondola mounting rails.

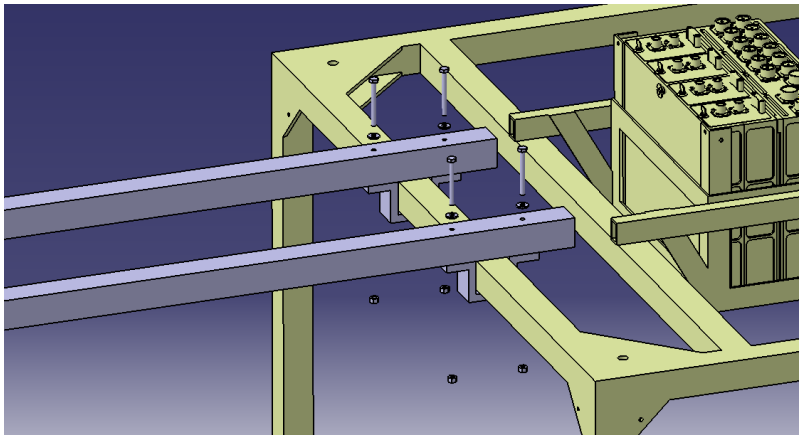


Figure 4.2.4: Top view of the upper booms mounted with clamps on the gondola frame (next to the airborne unit).

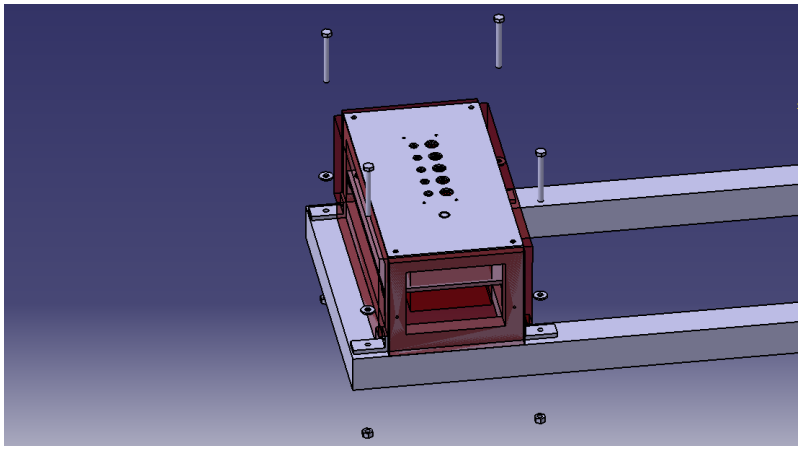


Figure 4.2.5: Top view of the sensor box mounting on the booms (upper and bottom).

4.2.2 Electrical

According to the BEXUS User Manual, an Ethernet protocol shall be used in this experiment, and the connector shall be an Amphenol RJF21B with a standard RJ45 connector.

The transfer rates are expected to be 200 kbps nominal and 200 kbps peak downlink. The expected uplink rates will just be command strings, not greater than 256 bytes per request. For more information about transfer rates, please refer to section 4.8.2.3.

The experiment uses the provided 28.8 V/1 mA (13 Ah) battery pack consisting of eight SAFT LSH20 batteries in series, where each battery has got a built-in 5 A fuse (not changeable) for protection, and the combined recommended continuous maximum current draw is 1.8 A. The expected max current is 1.24 A and the expected average current draw is 0.62 A. The connector to the battery which will provide power to the IRIS experiment shall be a 4" male, box mount receptacle MIL – C-26482P series 1 connector with an 8-4 insert arrangement (MS3112E8-4P) as specified in the BEXUS User Manual.

4.2.3 Radio Frequencies (Optional)

Will not be used.

4.2.4 Thermal (Optional)

Will not be used.

4.3 Experiment Components

Component	Supplier	Mass	Dimensions	Amount	Cost	Notes	Status
Serial Camera Module 4D Systems	Mouser Electronics	6 g	32x32x21 mm (varies with focus)	2	€100 (total)	Low weight, cheap	Not ordered
Garmin GPS Receiver 18x-LVC	Elfa	160 g	diameter: 85 mm, height: 50 mm	1	€110	Compact, cheap	Not ordered
Barometric Pressure Sensor MS5607-02BA03	Digikey	TBD (1-2 g ?)	5.0x3.0x1.0 mm	3	€84 (total)	High resolution, large measuring range	Not ordered
Photodiode G12183-030K Longwave	Hamamatsu	TBD	9.4x22.4mm	8	€100 (total)	Large measuring range	Not ordered
Photodiode S1336-8BK	Hamamatsu	TBD	14.1x20.2mm	12	€100 (total)	Large measuring range	Not ordered
Op-amp LMP2022	Digikey	-	4.0x4.0x2.0 mm (approx.)	20	€2.5		Not ordered
A/D-Converter ADS1115	Digikey	-	3.1x5.1x1.1 mm (approx.)	6	€6.3		Not ordered
Watchdog Timer TPL5010	Digikey	-	3.0x3.0x1.0 mm (approx.)	1	€0.8		Not ordered
Raspberry Pi 2 Model B+	Elfa	42 g	85x56x1.4 mm (without considering USB ports, etc.)	1	€25	Easy to use, cheap	Not ordered
Arduino Nano	Elfa	7 g	18x45 mm	~~3~~ 2	€25	Easy to use, cheap	Not ordered

DC/DC Converter 15W 18-36Vin 5Vout 300-3000mA	Mouser Electronics	15 g	25x25x10 mm	3	€30	Low consumption of supply current	Not ordered
DC/DC Converter 3W 18-36Vin 3.3Vout 300-3000mA	Elfa	8.8 g	32.3x14.8 x10.2 mm	3	€19.34	-	Not ordered
FTDI TTL-232R-5V	Farnell	TBD (<50g)	1.8 m, 5 mm ⌀	2	€16.6	-	Not ordered
Raspberry Pi 3 Model B+	DX.com	N/A	N/A	1	80 EUR	For Prototype	Ordered and Delivered
UNO R3 Development Board Microcontroller for Arduino	DX.com	N/A	N/A	~~3~~ 2	8 EUR	For Prototype	Ordered and Delivered
Night Vision 8MP NoIR Camera Board V2 for Raspberry Pi	DX.com	N/A	N/A	1	80 EUR	For Prototype	Ordered and Delivered

DHT11 Digital Temperature Humidity Sensor Module for Arduino	DX.com	N/A	N/A	~~3~~ 2	32 EUR	For Prototype	Ordered and Delivered
~~Diode Relay~~	~~Farnell~~	~~TBD~~	~~20.5x10.1 x1 mm~~	~~TBD~~	~~3 EUR~~	...	~~Not~~ ordered
~~Diode Circuit Transistor BSS138~~	~~Elfa~~	~~TBD~~	~~TBD~~	~~TBD~~	~~1 EUR~~	...	~~Not ordered~~
Data Storage Unit	TBD	TBD	TBD	TBD	~~€~~100	...	Not ordered
Optical Filter 440BP20**	Omega Optical	TBD	TBD	TBD	$98.80	**WR**:430-450 nm, **AR**:430-450 nm, **CW**:440 ± 5 nm **FWHM**:20 ± 5 nm	Not ordered
Optical Filter	Edmund Optics	TBD	TBD	TBD	$125.00	**WR**:450-510* nm, **AR**:450-500 nm, **CW**:475 ± 5 nm, **FWHM**:50 ± 5 nm	Not ordered
Optical Filter 560BP60 RAPID-BAND	Omega Optical	TBD	TBD	TBD	$175.00	**WR**:530-590 nm, **AR**:530-590 nm, **CW**:560 ± 2 nm, **FWHM**:60 ± 4 nm	Not ordered

Optical Filter 650BP40 RAPID-BAND	Omega Optical	TBD	TBD	TBD	$175.00	**WR**:630-670 nm, **AR**:630-670 nm, **CW**:650 ± 2 nm, **FWHM**:40 ± 4 nm	Not ordered
Optical Filter	Edmund Optics	TBD	TBD	TBD	$125.00	**WR**:850-880***** nm, **AR**:850-900 nm, **CW**:875 ± 5 nm, **FWHM**:50 ± 5 nm	Not ordered
Optical Filter	Edmund Optics	TBD	TBD	TBD	$149.00	**WR**:1360-1380***** nm, **AR**:1350-1400 nm, **CW**:1375 ± 5 nm, **FWHM**:50 ± 5 nm	Not ordered
Optical Filter	Edmund Optics	TBD	TBD	TBD	$149.00	**WR**:1560-1660***** nm, **AR**:1575-1625 nm, **CW**:1600 ± 5 nm, **FWHM**:50 ± 5 nm	Not ordered
Optical Filter FB2250-500	Thorlabs	TBD	TBD	TBD	2,808.00 SEK	**WR**:2000-2500 nm, **AR**:2000-2500 nm, **CW**:2250 ± 50 nm, **FWHM**:500 ± 100 nm	Not ordered
Smartphone fisheye lenses	TBD	TBD	TBD	4	$ 50	TBD	Not ordered

Fisheye lenses DSL315	Sunex	TBD	TBD	6	$ 129	TBD	Not ordered
Aluminium rough-cast plate	Alfer/Elfa	TBD	200x250x0.8 mm	TBD	77.20 SEK	...	Not ordered
Aluminium perforated plate (round-holes)	Alfer/Elfa	Mass	200x250x1.5 mm	TBD	204 SEK	...	Not ordered
Mounting plate Aluminium	Pentair Schroff/Elfa	Mass	84x220x2 mm	TBD	179 SEK	...	Not ordered
Mounting plate Aluminium	Pentair Schroff/Elfa	Mass	84x280x2 mm	TBD	193 SEK	...	Not ordered
Mounting plate Aluminium	Pentair Schroff/Elfa	Mass	84x460x2 mm	TBD	256 SEK	...	Not ordered
Mounting plate Aluminium	Pentair Schroff/Elfa	Mass	84x400x2 mm	TBD	187 SEK	...	Not ordered
Mounting plate Aluminium	Pentair Schroff/Elfa	Mass	84x340x2 mm	TBD	218 SEK	...	Not ordered
Sheet aluminium, blank	Alfer/Elfa	Mass	500x250x0.3 mm	TBD	33.10 SEK	High Priority	Not ordered
Sheet aluminium, blank	Alfer/Elfa	Mass	500x250x0.5 mm	TBD	50.60 SEK	High Priority	Not ordered
Sheet aluminium, blank	Alfer/Elfa	Mass	500x250x0.8 mm	TBD	57.60 SEK	High Priority	Not ordered

Angle Bracket	TBD	TBD	20x20mm	24	1 Euro	...	Not ordered
Bosch Rexroth 40 series, 1400mm	Bosch	1.5 kg/m	40x40x1400 mm	2	30 Euro per 2000mm	...	Not ordered
Bosch Rexroth 40 series, 1100mm	Bosch	1.5 kg/m	40x40x1100 mm	2	30 Euro per 2000mm	...	Not ordered
Bosch Rexroth 40 series, 240mm	Bosch	1.5 kg/m	40x40x240 mm	2	30 Euro per 2000mm	...	Not ordered
Bosch Rexroth 40 series Corner Cube	Bosch	TBD	40x40x40 mm	4	10 Euro each	...	Not ordered
Bosch Rexroth 20 series, 300mm	Bosch	0.4 kg/m	20x20x300 mm	4	20 Euro per 3000mm	...	Not ordered
Bosch Rexroth 20 series, 260mm	Bosch	0.4 kg/m	20x20x260 mm	8	20 Euro per 3000mm	...	Not ordered
Bosch Rexroth 20 series, 220mm	Bosch	0.4 kg/m	20x20x220 mm	4	20 Euro per 3000mm	...	Not ordered
Bosch Rexroth 20 series, 110mm	Bosch	0.4 kg/m	20x20x110 mm	8	20 Euro per 3000mm	...	Not ordered
Bosch Rexroth 20 series, 100mm	Bosch	0.4 kg/m	20x20x100 mm	4	20 Euro per 3000mm	...	Not ordered
Bosch Rexroth 20 series, 80mm	Bosch	0.4 kg/m	20x20x80 mm	8	20 Euro per 3000mm	...	Not ordered

Bosch Rexroth 20 series Corner Cube	Bosch	TBD	20x20x20 mm	24	5 Euro each	...	Not ordered
Watertight box	Hammond Manufacturing	TBD	TBD	1	€100	...	Not ordered
Styrofoam insulation	TBD	TBD	TBD	TBD	TBD	...	Not ordered

Explanations: **WR** = Wanted Range, **AR** = Actual Range, **CW** = Center Wavelength, ***** = Exact range not found

Table 4.3.2: Sensor Box: Mass and volume

Experiment mass (in kg):	2,277
Experiment dimensions (in m):	0,32×0,17×0,132
Experiment footprint area (in m2):	0,045
Experiment volume (in m^3):	0,006
Experiment expected COG position:	x = -1,546 [m]; y = -0,379 [m]; z = -0,002 [m] for the bottom sensor box. x = -1,546 [m]; y = 0,589 [m]; z = -0,003 [m] for the upper sensor box.

Table 4.3.3: Upper Sensor Box and Booms: Mass and volume

Experiment mass (in kg):	6,571
Experiment dimensions (in m):	1,13×0,32×0,162
Experiment footprint area (in m2):	0,362
Experiment volume (in m3):	0,01
Experiment expected COG position:	x = -1,244 [m]; y = -0,527 [m]; z = -0,003 [m]

Table 4.3.4: Bottom Sensor Box and Booms: mass and volume

Experiment mass (in kg):	7,804
Experiment dimensions (in m):	1,45×0,32×0,162
Experiment footprint area (in m2):	0,008
Experiment volume (in m3):	0,011
Experiment expected COG position:	x = -1,09 [m]; y = 0,316 [m]; z = -0,003 [m]

Table 4.3.5: Central "Brain" Box mass and volume

Experiment mass (in kg):	3,807
Experiment dimensions (in m):	0,363×0,28×0,16
Experiment footprint area (in m2):	0,0871
Experiment volume (in m3):	0,013
Experiment expected COG position:	x = -0,053 [m]; y = 0,239 [m]; z = 0,424 [m]

4.4 Mechanical Design

4.4.1 Sensor Box

The sensor box design is identical for the upper and bottom parts. In tab. 4.3.2, the two respective centers of gravity of the sensor boxes without the booms are shown. The frame structure of each sensor box is made of aluminium beams with a profile of 20×20 mm; it is currently planned to use the Bosch Rexroth profile to produce this frame structure. Angle brackets are used inside each sensor box to mount a plate for the corresponding electronic components, as shown in fig. 4.4.1.

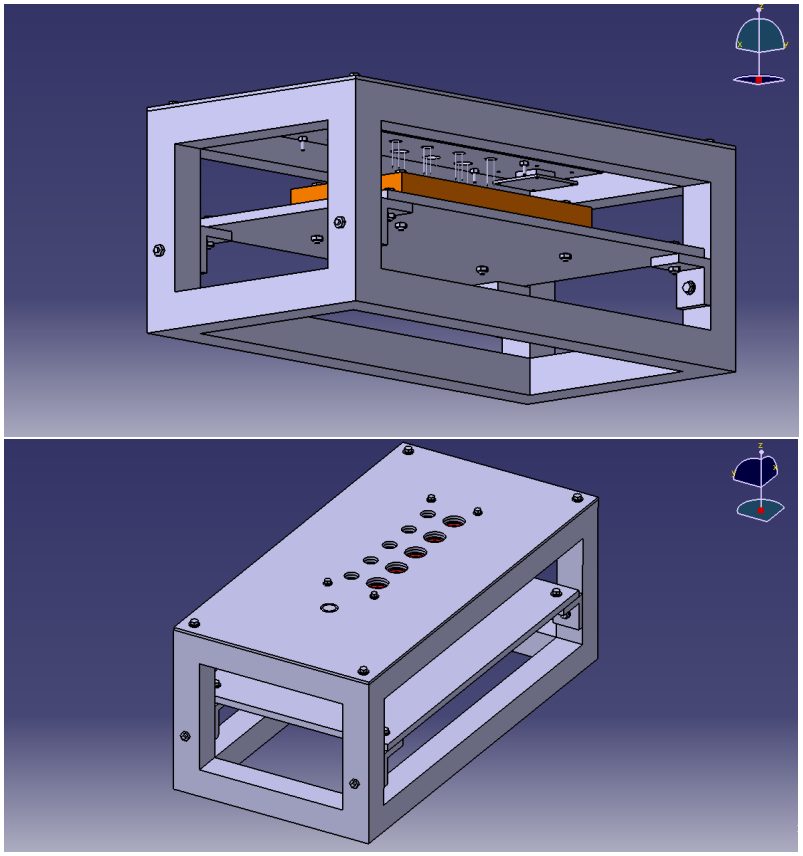


Figure 4.4.1: Sensor box view without the thermal insulation. The orange box represents the electronic units.

The sensor box is mainly composed of two subsystems: the optical subsystem -composed of photodiodes, filters and lenses- and the electronic subsystem -in charge of sending the photodiodes signal to the brain unit-. Each of these subsystems are mounted on aluminium plates, as shown in fig. 4.4.2.

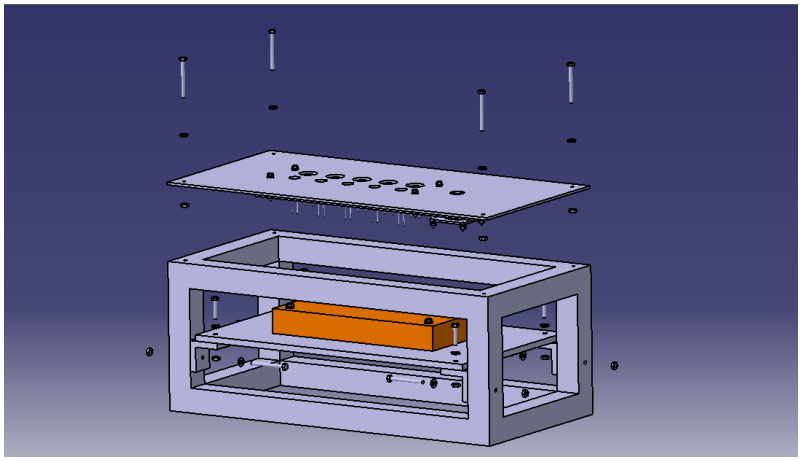


Figure 4.4.2: Exploded view of the sensor box mountings of the optical and electronics system.

The optical subsystem is assembled together by using several layers of aluminium plates to constraint the photodiodes and filters. For each of these optical components, a lower plate is used as a support for the component, and an upper plate is then placed on top of it for holding it in place. Fig. 4.4.3 shows how this mounting procedure can be accomplished.

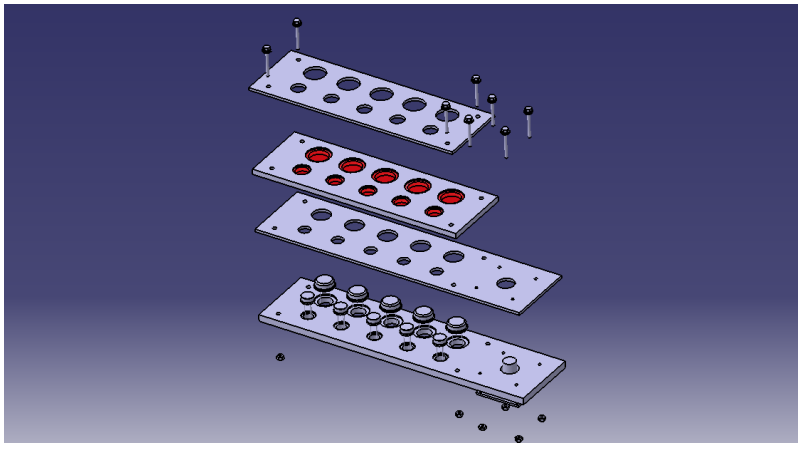


Figure 4.4.3: Exploded view of the optics subsystem mounting with an emphasis on photodiodes and filters mounting.

Because of the special charactereristics of the optical systems, components off-the-shelf cannot be used. Therefore, the optics plate must be manufactured. All other components in the sensor box are almost completely off-the-shelf components.

4.4.2 Brain Box

The brain box of IRIS is the central processing unit where data is handled and stored. The brain box is mainly composed of the computer unit, GPS sensor and electronics system.

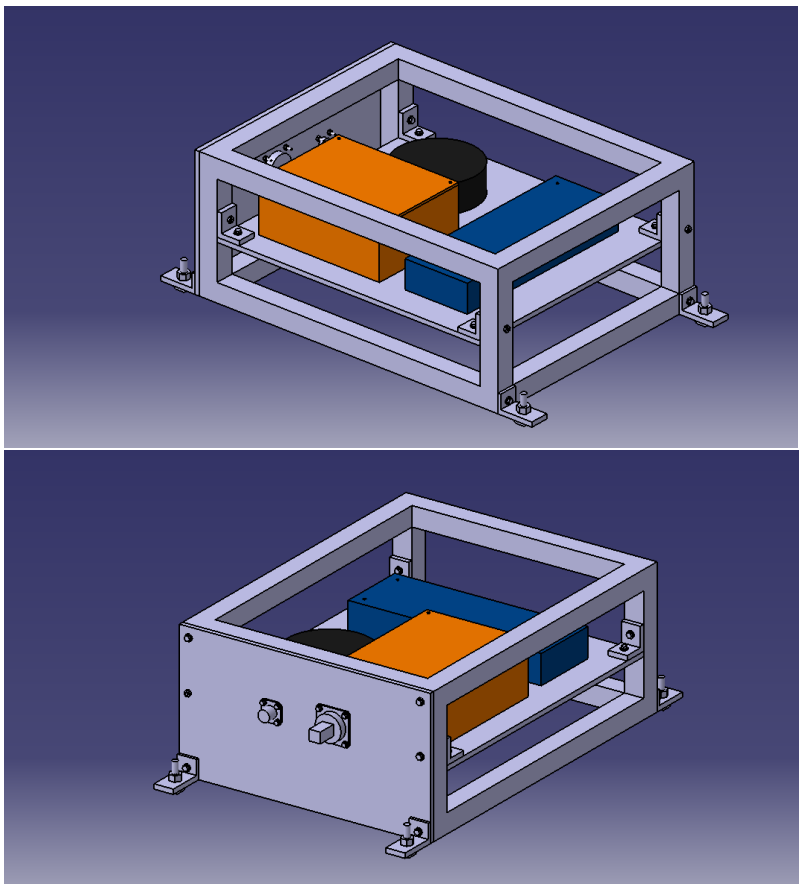


Figure 4.4.4: View of the components forming the sensor box.

During the thermal analysis of the brain box, the high operating temperature of the Raspberry Pi had to be coped with. At the same time it was intended to design a water-tight box for the data storage unit, in case the landing conditions are harmful. Therefore, it was concluded that isolating the Raspberry Pi with the data storage unit in a thermally insulated box inside the Brain box could solve both problems. As it can be seen in tab. 4.6.1, the RPi is the only component that have to be in positive Celsius to operate correctly. Thus, this component requires additional thermal insulation, while it is unecessary to increase the insulation of the brain box.

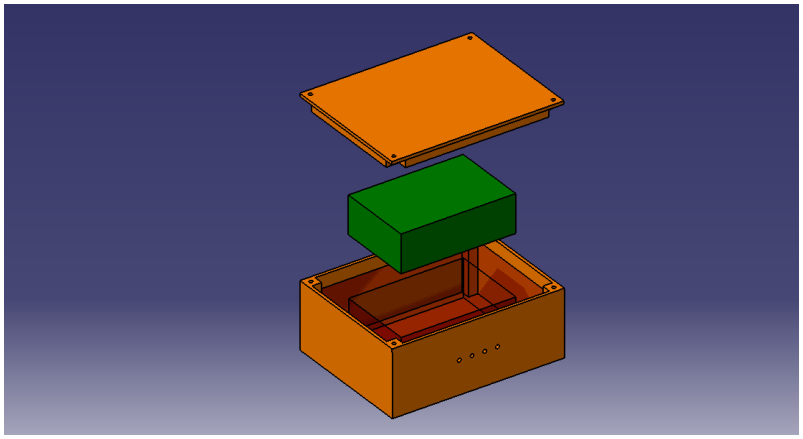


Figure 4.4.5: RaspBerry Pi and Data Storage Unit robust, thermally insulated and watertight box.

~~The floor mounted unit is composed of a sensor array and a camera. Each of these components is mounted on a box attached to the floor of the gondola on its outer side. By attaching an specially designed plate around the beams of the gondola frame and then fastening this box to this plate, the number of holes on the gondola plates is minimised. A description of the mounting of these components in the box is shown on fig. 4.4.4.~~

~~The bottom box, attached to the provided gondola rails, is composed of an Arduino microcontroller and other necessary electronic components that control the bottom sensor array, which is located on the floor mounted unit. The inside of the aluminium panel box is covered by a layer of thermal insulating material, namely polyurethane, where the electronic unit is sealed. The mounting of the components of the bottom box is shown on fig. **??**.~~

~~The upper box, attached to the gondola upper frame, is composed of a sensor array, an Arduino microcontroller, a Raspberry Pi board, a GPS receiver and other electronic components. Different cutaway of the structure are represented on fig. **??**, **??**, **??** and **??**. The frame bar structure of this box is encircled by a layer of thermally insulating material to keep the thermal sensitive components within their thermal survivability range. Heaters and an active thermal control device are also inside this box to allow for active thermal control of this box. To further ensure the survivability of this box -as it will contain the data collected during the experiment- it will be constructed to be water-proof.~~

Beams and plates used on the experiment are created in aluminium alloys (Al). Additional nuts and bolts for attaching some of these elements together -as well as the equipment to the structure- are made of steel.

~~It should be noted that despite the presence of crash pads on the bottom of the gondola, there is a risk of the lower sensor array being crushed if the gondola lands on a hard protrusion on the ground, such as a rock. Using sacrificial joints to prevent the failure of the instruments is still under investigation.~~

4.5 Electronics Design

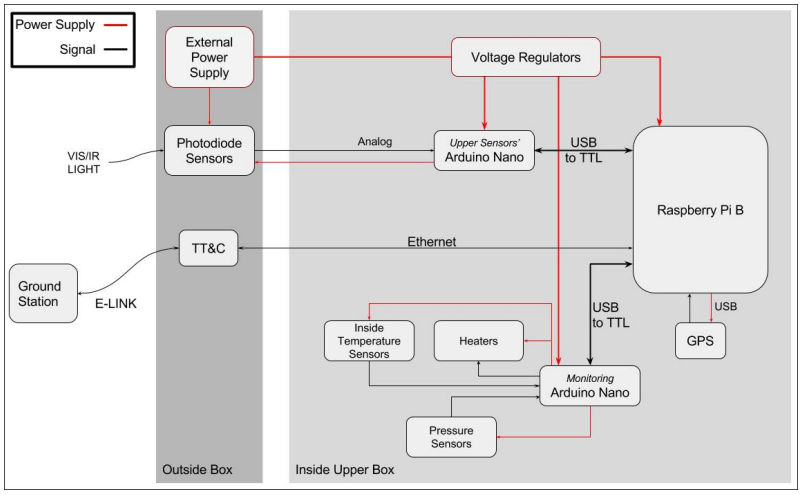


Figure 4.5.1: ~~A block diagram of the electronics and interfaces that will be planted in the upper box.~~

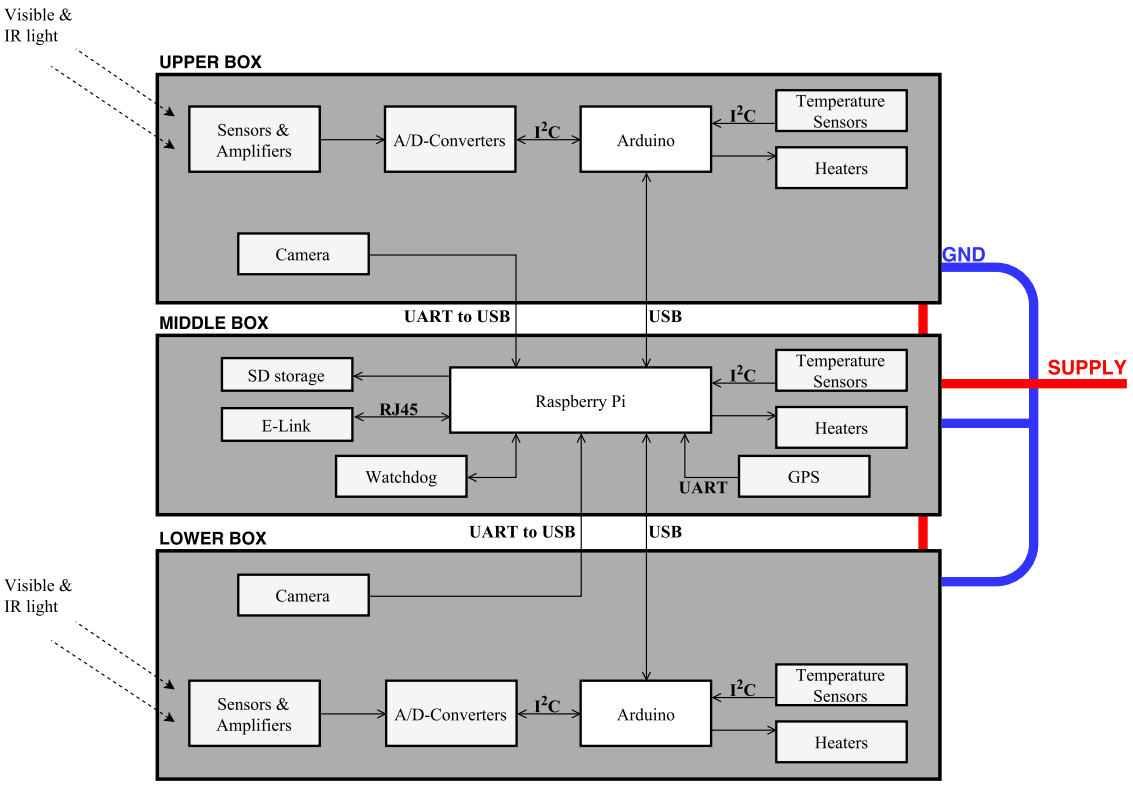


Figure 4.5.2: A block diagram of the electronics' signals and interfaces of the experiment.

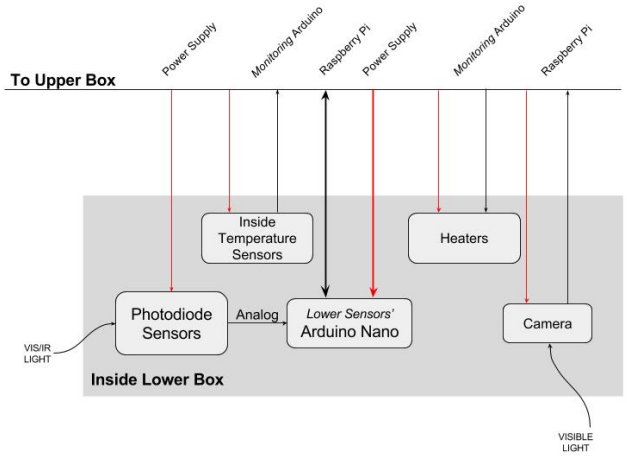


Figure 4.5.3: ~~A block diagram of the electronics and interfaces that will be planted in the lower box.~~

~~Fig. 4.5.1 shows the design and interfaces of the electronics that will be placed in the upper box. Fig. 4.5.3 shows the design and interfaces of the electronics that will be placed in the lower box.~~

Fig. 4.5.2 shows the general electrical signal diagram of the system, with interfaces.

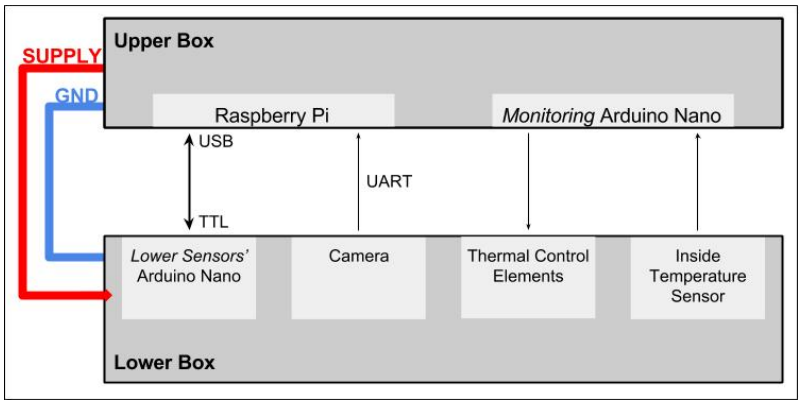


Figure 4.5.4: ~~An overview of the interaction between the upper and lower box.~~

Fig. 4.5.4 ~~shows how the upper and lower box will be connected.~~

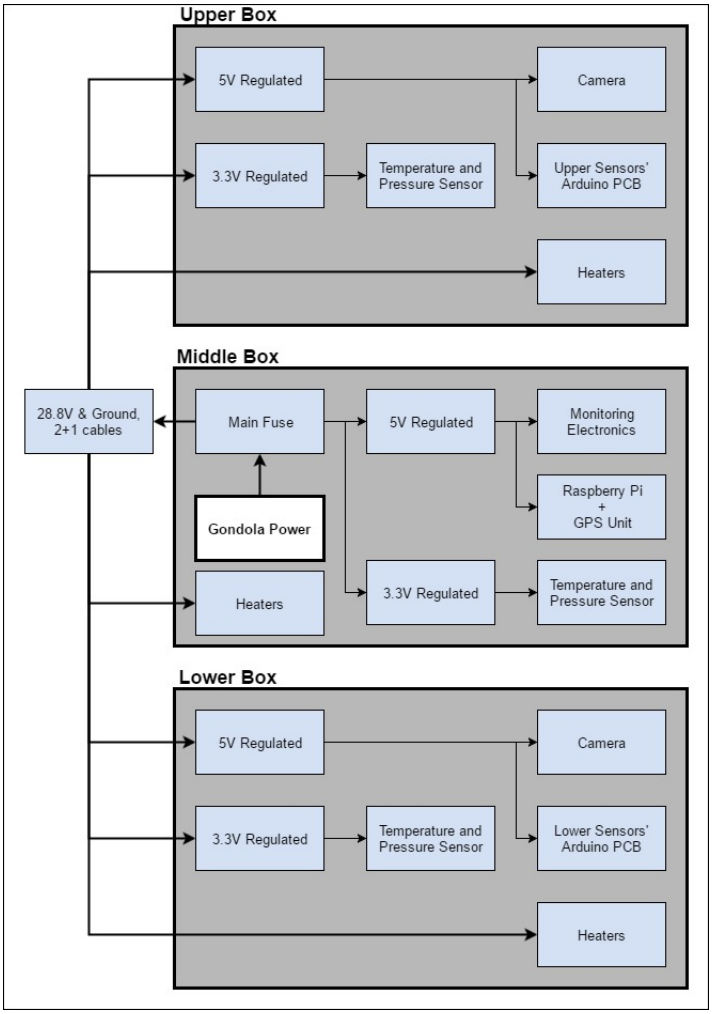


Figure 4.5.5: A block diagram of the power supply of the system.

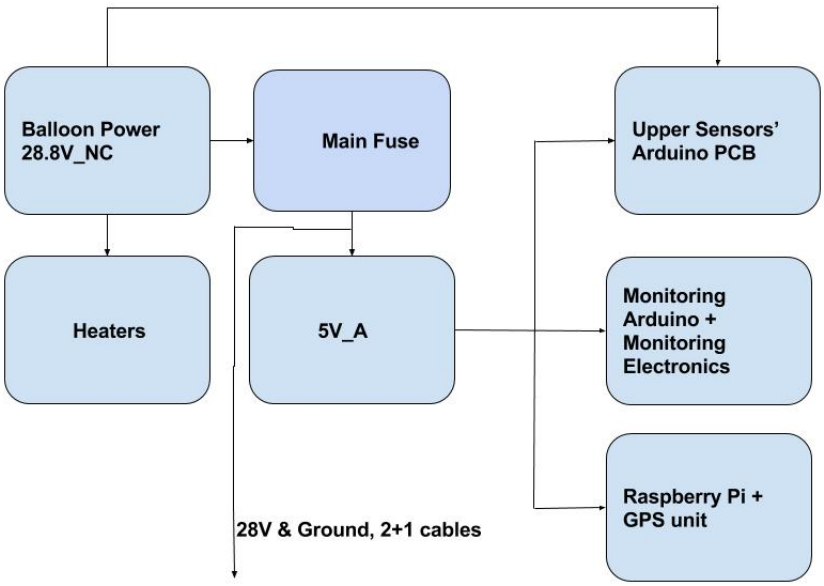


Figure 4.5.6: ~~A block diagram of the power supply of the upper box~~

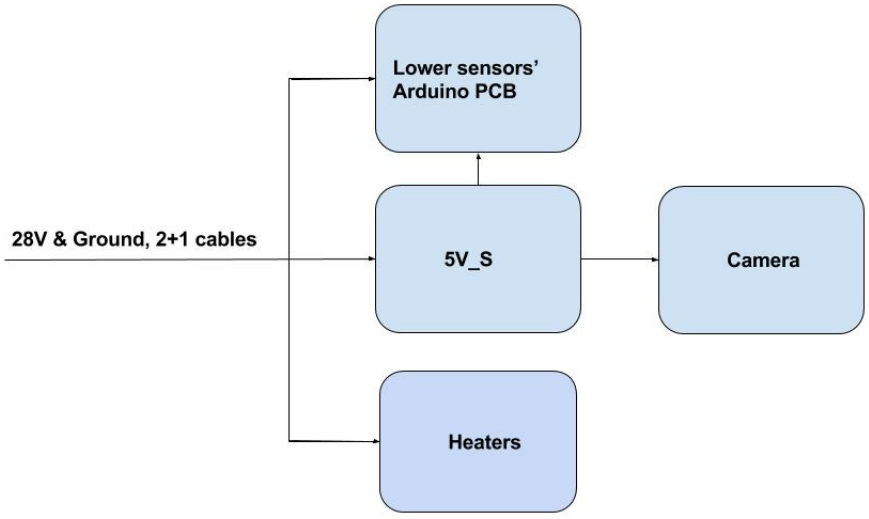


Figure 4.5.7: ~~A block diagram of the power supply of the lower box.~~

~~Fig. 4.5.6 is showing the power supply setup in the upper box. 28.8 V from the gondola~~

~~is distributed to the heaters, the upper sensors' Arduino and a fuse. From the fuse, 28.8 V are converted to 5V in a DC/DC converter and then fed to the upper sensors' Arduino PCB, the monitoring Arduino plus the monitoring electronics (which consists of a temperature and a pressure sensor). The GPS device is powered by the Raspberry Pi via USB and the photo diodes are powered by the Arduino. From the fuse, three cables, 28 V and ground, go into the lower box.~~

Fig. 4.5.5 shows the power supply diagram of the experiment. The gondola's 28.8 V power is connected to the middle box inside the gondola. In the middle box, the regulated 5 V powers the Raspberry Pi and the external watchdog timer. From the middle box, 28.8 V is fed to the upper and the lower boxes, where the voltages are regulated inside to power the electronics. The heaters in each box are supplied with 28.8 V and are controlled by the local microcontroller through a FET.

~~Fig. 4.5.7 is showing the power supply setup in the lower box. 28 V controlled by the fuse are fed to the lower sensors' Arduino PCB, the heaters and a DC/DC converter which provides 5 V to the camera. The temperature sensor in the lower box will be powered by the monitoring Arduino located in the upper box.~~

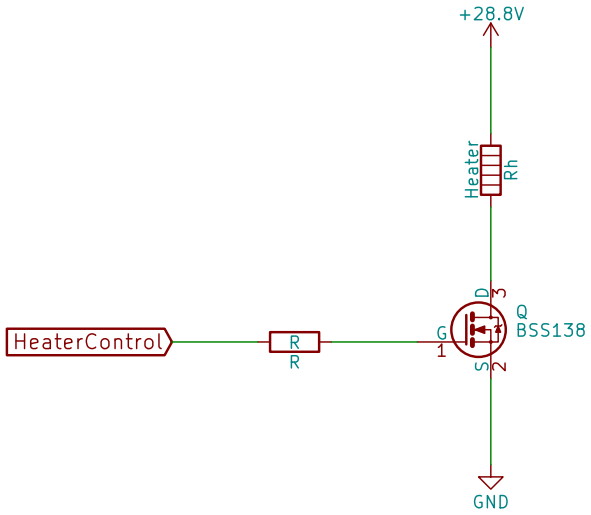


Figure 4.5.8: Simple heater circuit.

Fig. 4.5.8 is showing a simple circuit for heating. The heater is controlled by a PWM signal *HeaterControl* from the microcontroller using a transistor. The heater resistance R_h shall be chosen to be high enough so the power dissipated will not exceed the power

budget in case of software failure.

~~Fig. 4.5.11 is showing the circuit for measuring light with different wavelengths using photo diodes. On one sensor board, the 10 photodiodes are connected to five analog inputs on the Arduino board. This is realised by including switches in between the diode output and the board, letting it switch between sampling the first five readings and the other five readings, continually. During the period that the controller is reading the first five photo diodes' voltage, the other five are effectively disconnected, and vice versa for the next period. The Arduino controls the diodes' voltage supply, using its digital output pin and a FET transistor to trigger the relays by drawing current from the supply battery.~~

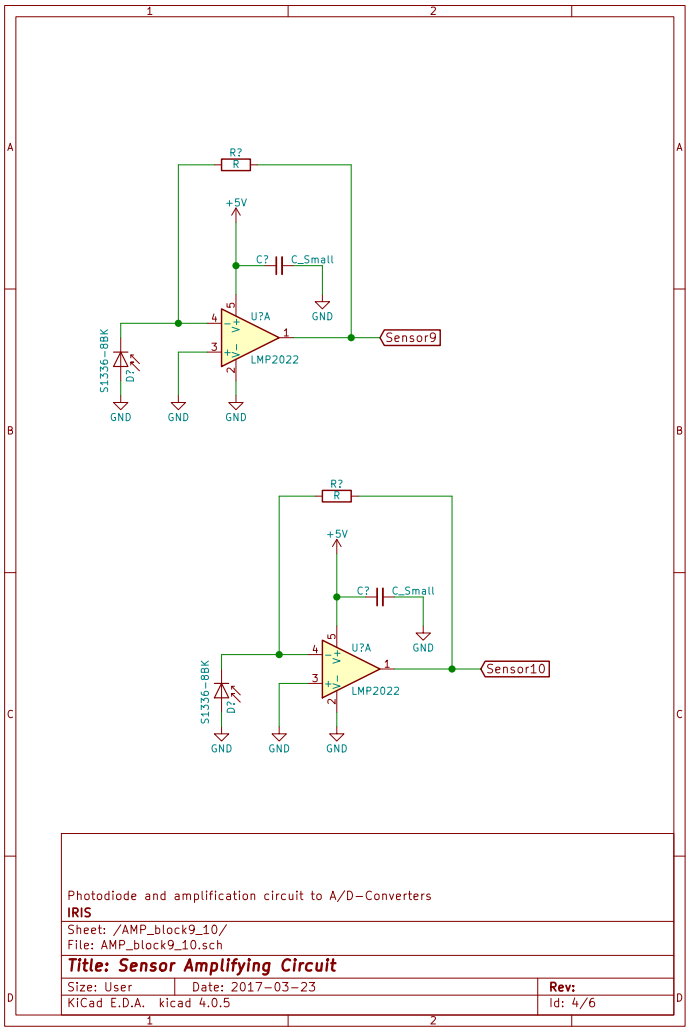


Figure 4.5.9: Photodiode amplifier circuit.

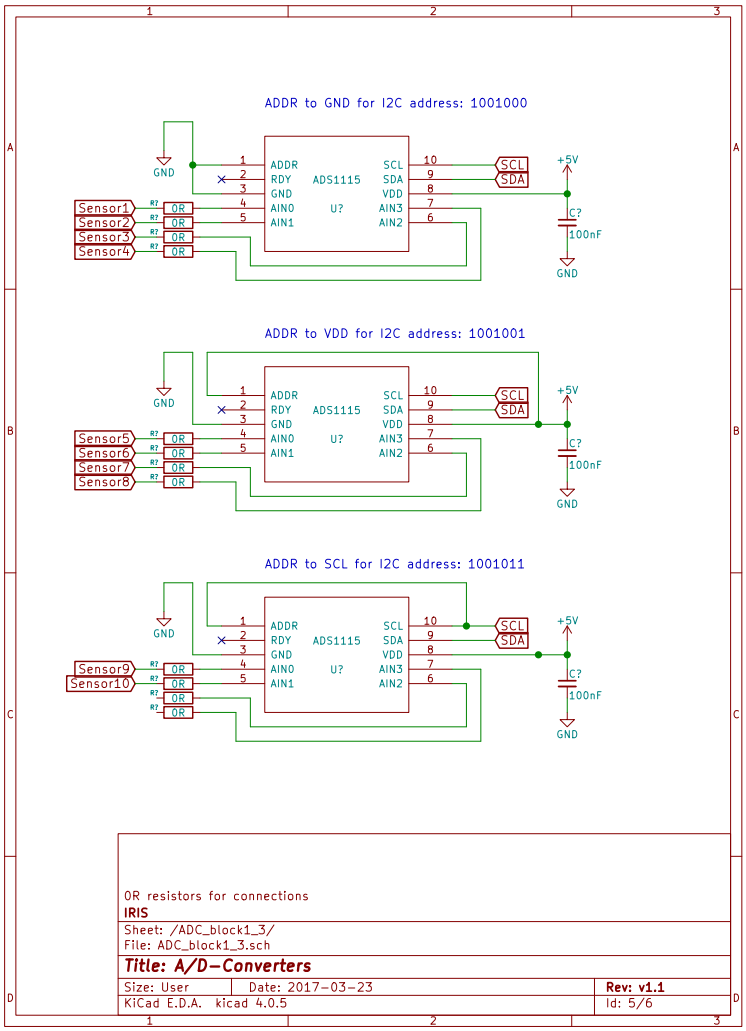


Figure 4.5.10: I2C connection, A/D-Converters to Arduino.

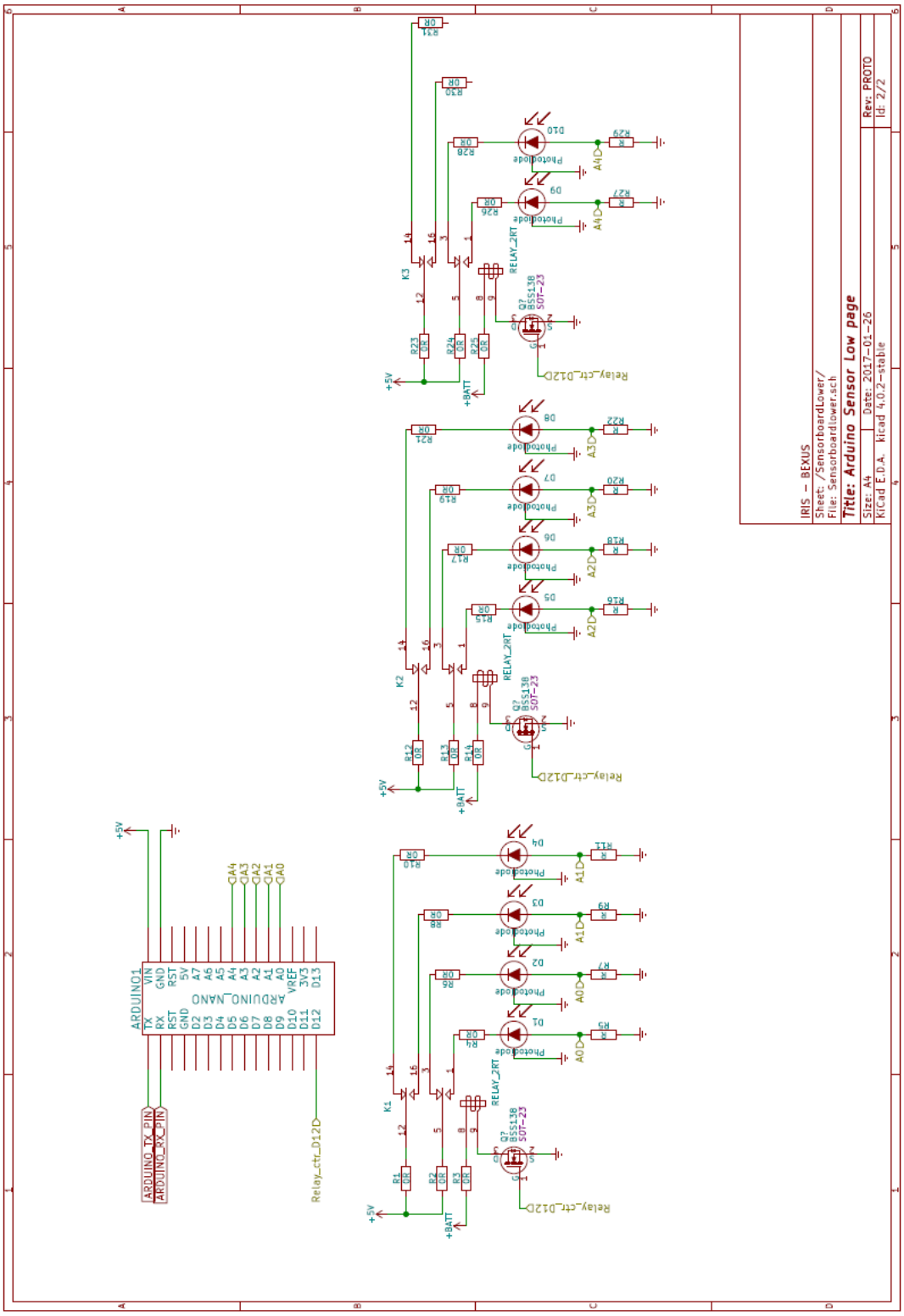


Figure 4.5.11: ~~Photodiode circuit~~

Figures 4.5.9 and 4.5.10 show (in part) the sensor circuits, from photodiode, to A/D-

Converter, to the I2C interface connected to the Arduino. The zero ohm resistors in fig. 4.5.10 are there to make it easier during assembly, if some complications arise, and unexpected connections are needed. The ADDR pin determines the I2C address of the ADS1115 ADC, giving different 7-bit addresses for different connections: GND, VDD or SCL. The 16-bit ADS1115 ADC has pins for four single-ended analog inputs, with built-in multiplexing.

The LMP2022 is used in the amplifying circuit. It's a low-noise, low-drift op amp, for precision and for the rough thermal environment.

4.5.1 Additional of the Prototype Project

As a sideline of the IRIS design a tabletop prototype is made. The purpose of the Prototype Instrument Project (PIT) is to produce as tabletop prototype of the IRIS project without the specific and expensive measurement payload. The aim is to help and fast track the work of the software and hardware teams of the main IRIS group.

PIT is a simplified version of the IRIS payload built with similar microprocessors and communications. Additionally to aiding with the implementation and design of the IRIS instrument, part of the testing can be done with the prototype and thus allow more time for the instrument specific testing.

4.6 Thermal Design

~~The lowest temperature ever recorded on the altitude range of HAB flights is -90 $^{\circ}C$ [2], which allows to set this temperature as the lowest possible minimum temperature the experiment might encounter.~~
Tab. 4.6.1 shows the expected operating maximum and minimum temperature of each component, as well as their longevity temperature range.

Table 4.6.1: Component thermal range table

ID	Component	Operating T($^{\circ}C$)		Survivable ($^{\circ}C$)		Comments
		Min	Max	Min	Max	
1	Serial Camera Module	-30	85	-40	105	
2	GPS Reciever	-30	80	-40	90	
3	Barometer	-40	85	-40	125	
4	Photodiode G12183-030K Longwave	-40	85	-55	125	
5	Photodiode S1336-8BK	-40	100	-55	125	
6	Raspberry Pi Model B+	0	70	-20	85	
7	Arduino Nano	-40	85	-40	85	
8	~~DC/DC Converter~~	~~0~~	~~70~~	~~-65~~	~~150~~	
9	~~Diode Relay~~	~~-25~~	~~65~~	~~-25~~	~~65~~	
10	~~Diode Circuit Transistor~~	~~-55~~	~~150~~	~~-55~~	~~150~~	
11	DC/DC Converter 5V	-40	85	-55	105	
12	DC/DC Converter 3.3V	-40	85	-50	125	
13	Sensor Amplifier (LMP2022)	-40	125			
14	AD Converter ADS1115	-40	125			
15	Heater Control Transistor (BSS138)	-55	150			
16	Watchdog Timer (TPL5010)	-40	105	-65	150	
17	USB to Serial Converter Cable (FTDI TTL-232R-5V) (USB-end connector)	-40	85			

The thermal control subsystem is divided into passive and active thermal control. The former is carried out by thermal insulation located on the inner side of the boxes containing the equipment. Active thermal control is accomplished by the use of heaters, which are controlled by the respective microcontroller in the upper and lower boxes and the Raspberry in the central box. ~~The MCU is using the temperature measurements from the interior thermometers to ensure the components are going to be working under their operational temperature ranges, as shown in fig. 4.1.1.~~ Temperature measurements from the interior thermometers are used to ensure that all the electrical components are working within their operating ranges.

~~In order to design the thermal control system, a first approximation analysis of thermal power balance was conducted. It is intended to represent a worst-case scenario, where thermal losses are the highest possible. For this model, the following assumptions were~~

~~made:~~

In order to design the active thermal control system, it was necessary to approximate the heat losses with only the passive thermal control system. Three cases with different assumptions were considered, from worst to best-case scenario. The results of this analysis can be found in app. F. At the end of the analysis, it was concluded that the middle-case scenario was the most realistic estimation.

- ~~Exterior temperature is -90 $^{\circ}C$.~~
- ~~Interior temperature of each of the three boxes is 0 $^{\circ}C$.~~
- ~~Each box shows three of its sides to the Sun, which are assumed to be perpendicular to it.~~
- ~~No thermal insulation is present in any of the boxes.~~
- ~~Only heat generated by the electronics contained in the boxes and incoming solar radiation are considered to contribute to power input. The former is obtained from tab. 4.7.1 as the power consumed by each component.~~
- ~~Only convective and radiative thermal losses are considered. Thermal losses towards the gondola structure due to conduction were not considered due to lack of data about the thermal power generation of the gondola.~~

This analysis provides the following results for thermal power balance on each box:

- Upper Sensor Box: $63.63\ W$
- Lower Sensor Box: $63.63\ W$
- Central "Brain" Box: $-11.52\ W$
- Central RPi Box: $-4.312\ W$

These results shows that if during the flight the Sun is present, a reflective surface or paint layer will be needed to prevent the sensor box to heat up. However, the worst-case scenario also showed us that heating within the sensor box might be needed if the Sun is not present during the whole flight.
~~These results are intended to provide an upper limit for the requirements of the thermal control system, and as such should not be considered as the normal working values.~~

Based on these thermal calculations, two heaters are needed in the upper box, two in the central box and two in the lower box to keep the temperature within the operating range of the electronic devices.

4.7 Power System

To fulfil the power needs for the project, a battery pack is available for use. The pack is stated to be able to provide 28.8 V/1 mA and has 13 Ah. One other constraint that must be considered is the 1.8 A continuous use of current as stated in the BEXUS user manual. With these constraints well defined, the list of components can be added, and determined in case additional power will be required. The first estimate of the power for the experiment seems to fit within these margins as stated below in tab. 4.7.1. The power budget will also be able to support a possible number of heaters, which will be placed at strategic locations, if they are considered necessary after the problem areas have been identified.

Table 4.7.1: Power consumption estimation, (wattages summed over total component numbers)

ID	Component	Voltage [V]	Current [mA]	Power [W]	Total [Wh]
1	Serial Camera Module	5	90	~~0.45~~ 0.90	9
2	GPS Receiver	5	90	0.45	4.5
3	Temp. and Pressure sensor	3.3	0.0014	0.01386	0.1386
4	Photodiode G12183-030K Longwave	5	N/A	N/A	N/A
5	Photodiode S1336-8BK	5	N/A	N/A	N/A
6	Raspberry Pi 2 Model B	5	600	3	30
7	Arduino Nano	5	2×19	0.19	1.9
8	~~Diode Relay~~	~~5~~	~~100~~	~~0.5~~	~~5~~
9	~~Diode Circuit Transistor~~	N/A	N/A	N/A	N/A
10	Watchdog Circuit	-	-	-	-
11	A/D-Converters	5	0.15	0.0045	0.045
12	Sensor Op-amp	5	1.1	0.11	1.1
13	DC/DC Converters, 5V	-	-	1.19	11.9
14	DC/DC Converters, 3.3V	-	-	0.00438	0.0438
15	Heaters	28.8	69	12	120
15	**Total**	N/A	N/A	18	180
16	**Available from gondola**	N/A	N/A	N/A	374.4

The total consumption of power assumes that the heaters are on 50 % of the time and the consumption does not exceed the power available from batteries. When the peak power consumption is calculated in chapter 6.1.3 it is assumed that the heaters are on 100 % of the time. Even then the consumption does not exceed the power available from the gondola.

All DC/DC converters have heat loss when reducing the voltage, usually the efficiency is between 88 to 90 % so it's reasonable to increase the consumption with approximately 15 % from what is shown in tab. 4.7.1.

4.8 Software Design

4.8.1 Purpose

The software will be responsible for monitoring, housekeeping and data handling of the experiment IRIS. A monitoring and housekeeping subsystem will be designed, and environmental experiment data shall be stored and a portion transmitted to a ground station to aid a successful mission.

4.8.2 Design

4.8.2.1 Process overview

The system has been designed to fulfil three main functions: handling measured data, telemetry for sending back data to ground, and monitoring and housekeeping internal systems.

Most of the measured data is to be stored on an internal memory in the form of a SD-card. Some data from the camera uses the downlink during the early parts of the mission, specifically the ascent, to utilise the larger downlink rates and ease constraints on the memory budget and reduce the risk of experiment result returning NULL. The central hub and coordinator will be a SOC, in particular a Raspberry Pi (RPi). The RPi shall be responsible for data handling, data storage, telemetry and talking to the MCU:s (Arduino) that relay data from the sensors to the RPi.

There will be a total of two MCU's. The two MCU's will be responsible for data collection and thermal monitoring and control in their respective box. Two MCU's will be interfaced with the sensors in a nominal mission capacity, while the third MCU will be used as a system monitor for error handling and control of thermal systems.

The process, including interfaces, is described graphically in fig. 4.8.1. where the brackets encapsulate the software role for each component with respect to the three main functions listed.

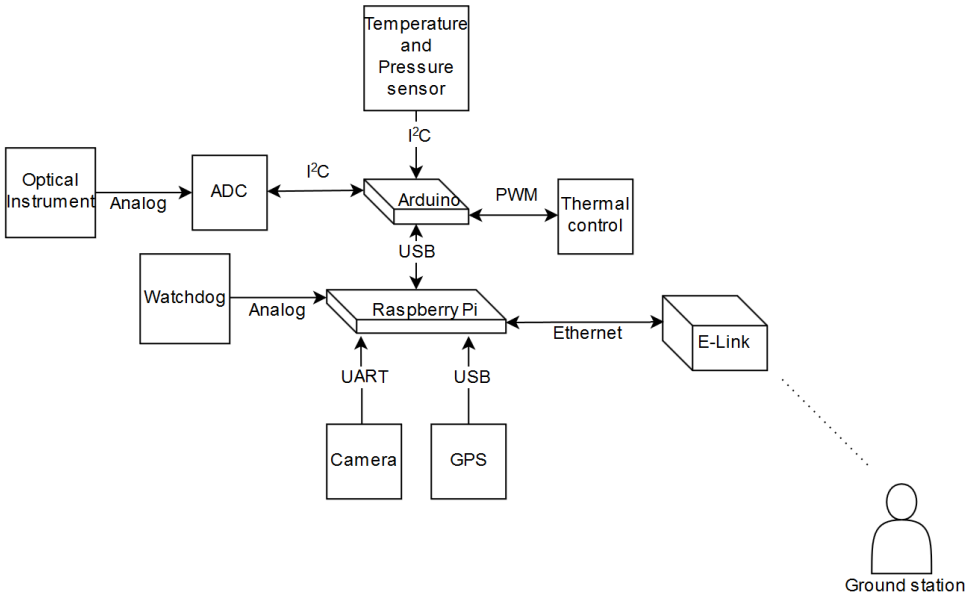


Figure 4.8.1: Process Overview Diagram

4.8.2.2 General safety related concepts

~~The experiment features a monitoring system independent from the main data handling system, which is in charge of handling errors, restarting the system in case of major malfunction and controlling environmental factors (operating temperature for sensors).~~ All components that can, shall include individual failsafes in form of rebooting schemes, in case of unsuspected events. The RPi will also be connected to an external watchdog. Some of the possible failure modes are described in tab. 4.8.1.

4.8.2.3 Interfaces

~~The platform uses mainly two interfaces: Serial communication among the components,~~ The platform interfaces between components can be seen in tab. 4.8.1, and Ethernet Base 10/100 for communicating with the E-Link. The module shall be able to transmit part of the data gathered and stored, operate autonomously in the event of loss of communication with ground station, and ensure a correct transmission from the sensors to the storage unit.

The telemetry sent via the E-link has a TBD size, and every packet will feature a header and terminator. Tab. 4.8.2 depicts the packet design for the telemetry data.

Table 4.8.1: General safety concerns

Topic	Possible errors and safety concerns	Mitigation measures
Initialization	- Any of the connected devices through UART does not initialize. ADC or storage fails to start.	- ~~If the monitor is initialized but none of the other interfaces are, the monitor will try to reboot the system.~~ - If the Ethernet interface with the E-link is initialized but no other interface is, a critical failure message will be sent. One restart attempt will happen after that. - Each component that fails to intiate will go to rebooting procedure. - ~~If all the system initializes but the monitor interface, a warning will be sent through the downlink.~~
Data storage	- Possible corruption or loss of data	- Shut down the system before touchdown, disconnect power from the storage unit to avoid damage. - Be wary of using FAT, the allocation table has been known to corrupt or wrongly allocate files after unexpected power off. - Use journaling.
Heaters	- Temperature inside the experiment boxes is under/over the thresholds before lift-off.	- Monitor temperature on the experiment before lift-off will be monitored and action will be taken.
Sensors performance	- Any malfunction in sensors is detected.	- Readings will continue to be taken, but a flag/message indicating faulty measurements will be added.
E-link connection	- Connection is lost or not working.	- The system will continue to work with pre-stored conditions for loss of communications. - Data transmission will be halted until connection is recovered.
Test	- The system has rebooted, or dedicated command has been received.	- During test mode little data will be stored and testing telemetry will be sent through the command link for troubleshooting. It will be determined by the number of tasks to be performed.

Table 4.8.2: Telemetry and telecommand messages

Name	MID	DATA	STAT	CHK
Description	Message ID	Transmitted message	Status	Checksum
Size	2 bytes	1-16 bytes	1 byte	2 bytes
Use	States the nature of the message and its length	The data transmitted	Gives telemetry data or mode of operation	Checks errors of the message

The telecommand functionality will follow the same packet distribution as the telemetry design, but featuring a fixed 1 byte transmitted data section for the command.

The minimum expected bandwidth is 100 kbps and the maximum of 200 kbps. The uplink of commands is expected to be sporadic messages for command, minimum of 0 kbps, nominal of 20 bytes and peak of 50 bytes.

Regarding the internal communication system, the interfaces will be serial communication and the reception of the data from the sensors is done in analog fashion. The pressure and temperature sensor feature a serial I2C interface, and the actuation on the thermal control system will be done using PWM signals.

The communication protocol with the off-the-shelf components using serial such as the GPS and camera is TBD. However, for the communication between the Arduino MCUs and RPi the communication will be as follows in tab. 4.8.3.
Because the camera will have a UART interface it is necessary to make sure that it is sufficiently fast. It was determined that the UART will be fast enough. The reason for

this choice over USB was that the camera came with UART interface and to limit the number of USBs as much as possible connected to the RPi which may have power issues when multiple USB's are connected, because of the thin strip-conductors within the RPi.

Table 4.8.3: Inner communication packet design

Name	MID	VAL	STAT	PAR
Description	Message ID	Transmitted value	Status	Parity bit
Size	8 bits	8-12 bits	1 bit	1 bit
Use	States procedence of the message and the sensor generating the value	The value transmitted	States the calibration of the sensor	Checks errors of the message

To avoid corrupt data on transmission, a checksum in larger and a parity bit in short messages is included. Critical messages (such as commanded shut down from ground) will be sent twice for the experiment not to be blocked by these.

Please refer to section 4.5 for more information on the analog interfaces.

4.8.2.4 Data acquisition and storage

The RPi used in the experiment has an inbuilt microSD card slot. This is used to store the boot information for the board's software and the data gathered by the sensors. The estimated amount of data from the sensors is two bytes from each of the photodiodes, and between 400 and 800 kB for the single camera reading. Position, temperature and pressure readings are also considered a total amount of 1 kB.

The experiment shall take measurements with a delay of between 3 seconds, and the approximate flight time is around six hours. Therefore, the expected amount of data generated is 4 GB, which can be solved with one 8 GB microSD card.

Part or the complete of the data will be sent back to the ground station. The station features a fully capable computer that integrates enough storage capacity for the data that has been sent.

The data files to be used for this purpose are txt files generated as a CSV file to store the sensor data, and JPEG format to store the information about the images.

4.8.2.5 Process Flow

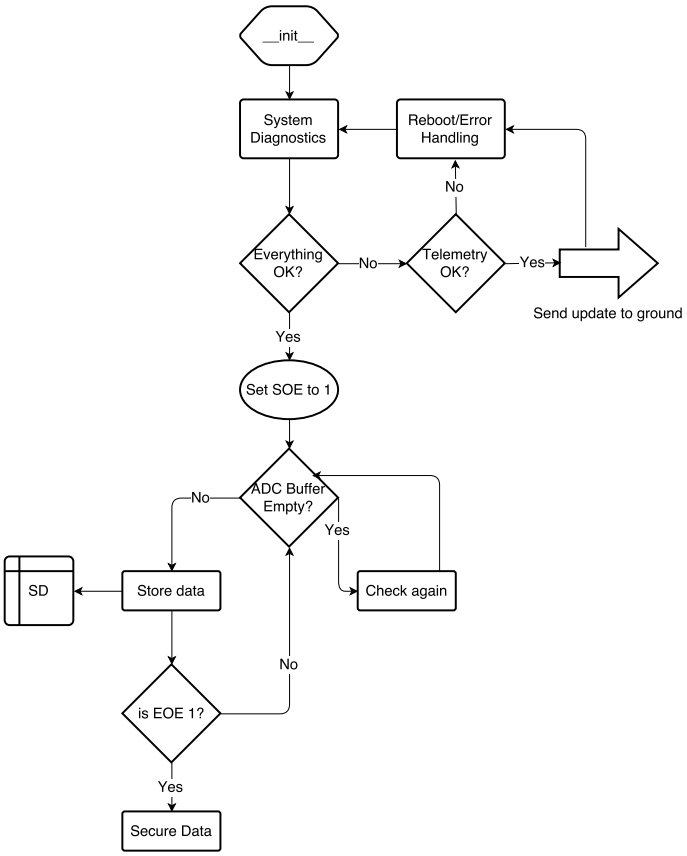


Figure 4.8.2: RPi Process Flow

The SOC is initialized according to its boot procedure by applying power, which then initializes all objects. The monitoring object is initialized on both of the Arduino MCU's and is responsible for individual thermal control and data collection. The watchdog will be initiated and updated by the SOC regularily if everything is nominal. If everything checks out, SOE will be set to 1 and data collection can start. The sensor object will start generating data, which will fill the buffer of the MCU's interfaced with the external sensors. The ADC will be continuously measured by the MCU, and the SOC will ask the MCU's for available data.

4.8.2.6 Modularization and pseudo code

The system software architecture can be divided into three different modules with different functions. This functions are data acquisition, system monitoring and housekeeping and data handling and storage.

The data acquisition module will be in charge of reading the sensors. It will be programmed in Arduino IDE. The main objects included in this module will be:

- **Data gathering:** Will provide the functions to other objects to make a readout of the sensors.
- **Serial Interface:** Will be in charge of handling the requests from the serial interface and send the relevant information.
- **Calibration:** Will provide a function to calibrate the sensors, and will return the values associated with them.
- **Mode:** Will store the information about the mode of operation and will decide which actions are taken by the rest of the module.
- **Initialization:** Will be the first object to take action, initializing all the other objects and checking that they are functioning correctly.

The second module will be in charge of monitoring all the other modules, ensuring that they work correctly and taking action when they do not perform as intended. It will also be in charge of controlling the environment and will relay the information of internal housekeeping to the main unit. The main objects of the module will be:

- **Data gathering:** Will provide the functions to other objects to make a readout of the sensors.
- **Serial Interface:** Will be in charge of handling the requests from the serial interface and send the relevant information.
- **Actuator:** Will be in charge or providing the control mechanism for the thermal resistance to heat the module in case temperature runs out of limits.
- **Monitoring:** Will check all the subsystems and will set the modes of operation of them.
- **Error control:** Will set the modes of operation of the subsystems in function of the errors reported. Will also shut down the main computer when the flight is about to end.
- **Initialization:** Will initialize all the objects and will check that all the other modules have started correctly.

Finally, the third module is the main system data handling and storage. It will also provide the interface to the E-Link, allowing to communicate with the ground station. It will run an operating system based on Linux, and the code will be programmed in Python. The main objects of this module are:

- **Data collection:** Will communicate with other modules to ask for the values of the sensors.
- **Mode:** Will hold the mode of operation for the actions that have to be taken. Will also execute the shutdown command when commanded by the monitoring module.

- **Data storing:** Will handle the files to store the values and will provide the function to other objects.

- **System inialization:** Will initialize all the interfaces and objects.

- **Ethernet interface:** Will provide the functions necessary to communicate through the E-link and will generate the package to be sent.

- **Serial interface:** Will provide the functions to handle communications through the Serial interfaces.

It is still to be determined which of the modules should include an I2C connection object to provide the handling of the interfaces to the sensors.

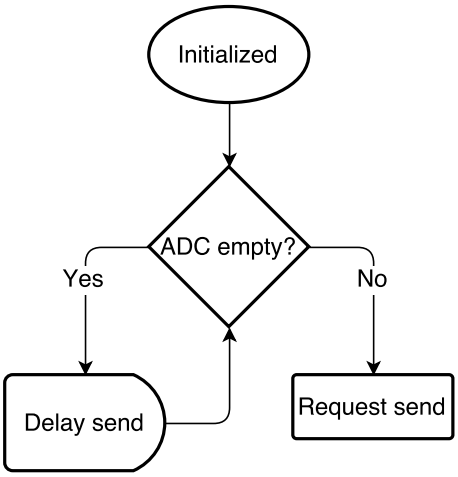


Figure 4.8.3: Sensor MCU Process Flow

The initialization signal from the SOC lets the MCU know it's OK to start collecting analogue data, which will be fed from the sensors, converted to digital and sent to the SOC.

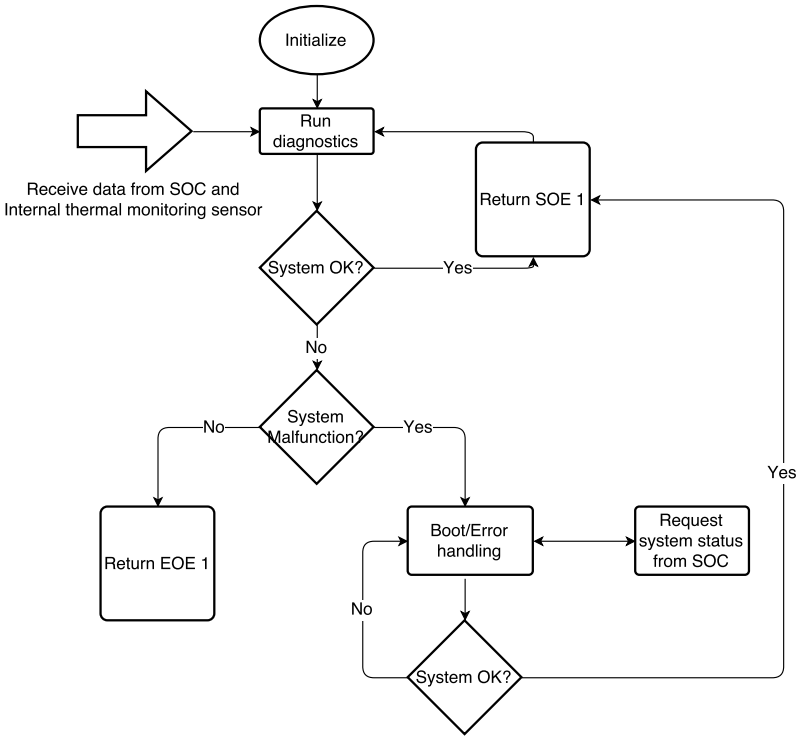


Figure 4.8.4: ~~Monitor MCU Process Flow~~

4.8.3 Implementation

The languages to implement the code are Arduino and Python. Arduino is an IDE based on C++ with custom built functions, that verifies, compiles and uploads the code to the Arduino-compatible boards (based on Atmel controllers). However, it can be programmed outside this environment with Atmel studio and the output runfile uploaded to the controllers without using the environment.

Regarding Python, it is included as part of Anaconda IDE. It is an interpreted language that allows for handling and representing high amounts of data. It is as well integrated with the RPi environment. The possible libraries to be included would be Ethernet handling libraries, as well as for creating and storing text files and images.

4.9 Ground Support Equipment

The ground support equipment will consist of a computer with an Ethernet interface connected to the ground station to receive the data. It is still TBD if the ground station will use Python or Matlab to provide a GUI to evaluate images in real time.

4.10 Optics Design

The department of Optics is in charge of optimising the optical components to obtain data. The aim is to improve the design of photodiodes, filters and fisheye lenses to improve the quality of the obtained data.

4.10.1 Photodiodes

The photodiodes are the main components of the optics, so they absorb the photons and, thanks to that, it is possible to measure the intensity of light of a determined region. On the photodiodes, the filters and the fisheye lenses will be added in order to meet the requirements of the experiment.

Since the field of view of the photodiodes is relatively narrow, it would be of an advantage to enlarge it.

As it is shown in fig. 4.10.1, the photodiodes have a certain directivity. This shows how the response varies, depending on the incident angle of the light.

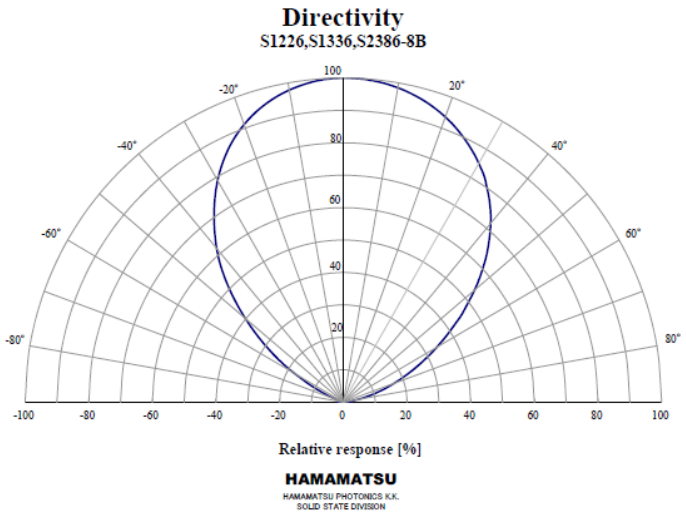


Figure 4.10.1: Directivity of Hamamatsu photodiodes

The main reason why the fisheye lenses are necessary is because it is intended to gather the rays of light in the most perpendicular way possible.

4.10.2 Filters

Special filters are required to maintain high data quality precision. The reason for this is that the experiment requires differentiation between the intensities for several ranges of the electromagnetic spectrum.

4.10.3 Lenses

Increasing the Field of View (FoV) of the photodiodes will provide a greater accuracy of data collection from a larger surface range. The need for lenses was considered necessary and through calculations it does not add any fallacious measurements caused by the SZA and the FoV of the sensors.

4.10.4 Interferences

It is important to take into account that the field of view of the photodiodes will be partly obstructed by the parts that hold the balloon (for instance the four belts going out from the gondola and the wire they hold) and the balloon itself. Some calculations have been done to approximate the angle that will be covered by the balloon. (Fig.4.10.2)

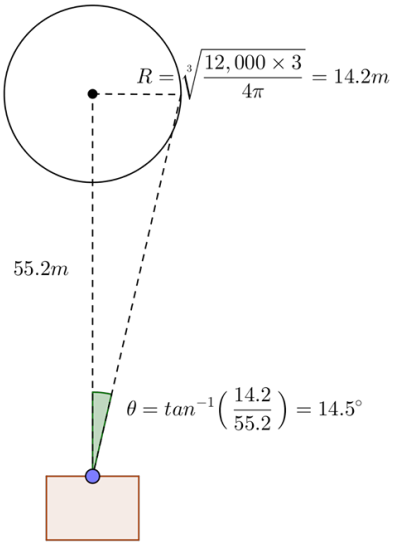


Figure 4.10.2: Visual obstruction caused by the balloon

The mechanical department has designed two booms, one for each photodiode array facing upwards and downwards, in order to reduce the obstruction that would be caused by placing the sensors directly outside of the gondola. Therefore, the booms, each of the length of 1 meter, shall considerably reduce the obstructions to an acceptable minimum.

5 Experiment Verification and Testing

5.1 Verification Matrix

- I - Verification by inspection
- R - Verification by review-of-design
- A - Verification by analysis or similarity
- T - Verification by test

Table 5.1.1: Verification Matrix

ID	Requirement text	Verification	Test number	Status
F.1	The experiment shall measure the intensity of visible light outside the gondola, looking towards the zenith.	R	-	To be done
F.2	The experiment shall measure the intensity of visible light outside the gondola, looking towards the nadir.	R	-	To be done
F.3	The experiment shall measure the intensity of infrared light outside the gondola, looking towards the zenith.	R	-	To be done
F.4	The experiment shall measure the intensity of infrared light outside the gondola, looking towards the nadir.	R	-	To be done
F.5	The experiment shall correlate the pressure at which the measurements were taken.	T	Test 1, 10	To be done
F.6	The experiment shall correlate the temperature at which the measurements were taken.	T	Test 2, 10	To be done
F.7	The experiment shall correlate the position at which the measurements were taken.	T	Test 10, 12	To be done

F.8	The experiment shall measure the position on the three axis of space with respect to the launching point.	T	Test 12	To be done
~~P.1~~	~~The experiment shall be able to distinguish between incoming and outgoing from Earth radiation.~~	~~R~~	-	~~To be done~~
P.2	The experiment shall measure the electromagnetic spectrum from 0.3 μm to 2.5 μm with a minimum sensitivity of 200 $mW \cdot m^{-2}$	R, T	Test 5	To be done, see test plan
P.3 to P.10	The experiment shall measure the 0.43 μm to 0.45 μm, 0.45 μm to 0.51 μm, 0.53 μm to 0.59 μm, 0.63 μm to 0.67 μm, 0.85 μm to 0.88 μm, 1.36 μm to 1.38 μm, 1.56 μm to 1.65 μm, 2.00 μm to 2.50 μm with a precision of $\pm$0.005 μm.	R, T	Test 5	To be done, see test plan
~~P.11~~	~~The sampling rate of the experiment shall be between 5 and 10 seconds.~~	~~A, T~~	~~Test 10~~	~~To be done, see test plan~~
P.12	The sampling delay shall not exceed 30 seconds.	A, T	Test 10	To be done, see test plan
P.13	The experiment shall measure the pressure from 5 to 1100 $mbar$.	R, T	Test 1,10	To be done, see test plan
P.14	The experiment shall measure the pressure with a minimum accuracy of 10 $mbar$.	R, T	Test 1,10	To be done, see test plan

P.15	The experiment shall measure the temperature from -90 to 30 $^{\circ}C$.	R, T	Test 2, 10	To be done, see test plan
P.16	The experiment shall measure the temperature with a minimum accuracy of ± 1 $^{\circ}C$.	R, T	Test 2, 10	To be done, see test plan
P.17	The experiment shall measure the position with a minimum accuracy of ± 10 m.	R, T	Test 10, 12	To be done, see test plan
P.18	During the ascend phase the sampling frequency shall be 3 seconds.	T	Test 10	To done, see test plan
P.19	During the float phase the sampling frequency shall be 10 seconds.	T	Test 10	To be done, see test plan
~~D.1~~	~~The experiment shall not include components that could prove to be dangerous for people.~~	~~R~~	-	~~To be done~~
~~D.2~~	~~The experiment shall not include components that disturb or harm the launch vehicle.~~	~~R~~	-	~~To be done~~
~~D.3~~	~~The experiment shall not include components that disturb or harm other experiments.~~	~~R~~	-	~~To be done~~
D.4	The experiment shall not weigh more than 8 kg upon launch.	R, A, T	Test 13	To be done, see test plan
D.5	The experiment shall withstand vertical accelerations within the BEXUS flight and launch profile.	A, T	Test 6	To be done, see test plan

D.6	The experiment shall withstand horizontal accelerations within the BEXUS launch and flight profile.	A, T	Test 6	To be done, see test plan
D.7	The experiment's data storage unit should withstand shocks of up to 35 *g* during landing.	A, T	Test 6	To be done, see test plan
D.8	The experiment shall withstand vibrations related to handling and transportation before and after flight.	A, T	Test 4	To be done, see test plan
D.9	The experiment shall withstand pressures within the BEXUS flight profile.	R, T	Test 1	To be done, see test plan
~~D.10~~	~~The experiment shall withstand temperatures within the BEXUS flight profile.~~	~~R, T~~	~~Test 2~~	~~To be done, see test plan~~
D.11	The experiment shall not be at risk of falling from the gondola during flight and launch.	R, T	Tests 4, 6	To be done, see test plan
~~D.12~~	~~The experiment shall not slide or translate inside the during flight and launch~~.	R, A	-	To be done
D.13	The experiment should be attached to the gondola rails if possible.	R	-	To be done
D.14	The fastening to the gondola rails shall be carried out with M6 bolts with 23 mm thread length.	R	-	To be done
D.15	The experiment shall use a sufficient number of brackets on bottom plates in order to facilitate mounting of experiments.	R	-	To be done

D.16	The experiment shall operate at temperatures within the BEXUS vehicle flight and launch profile.	R, T	Test 2	To be done, see test plan
~~D.17~~	~~All experiment critical components shall be accessible within 2 minutes.~~	~~R, T~~	~~Test 14~~	~~To be done, see test plan~~
D.18	The replacement time of the replaceable components shall be within 15 minutes.	R, T	Test 14	To be done, see test plan
D.19	The experiment shall use a maximum electrical energy of 275 Wh.	R, A, T	Tests 7, 9	To be done, see test plan
D.20	The experiment shall use Ethernet 10/100 Base-T with RJ45 connectors for interfacing with the provided E-link.	R	-	To be done
D.21	The experiment shall use Ethernet 10/100 Base-T with RJ45 connectors for interfacing with the ground station.	R	-	To be done
D.22	The experiment shall use a 4 pin, male, box mount receptacle MIL-C-26482P series 1 connector with an 8-4 insert arrangement as power interface.	R	-	To be done
D.23	The data storage unit shall withstand any post-landing environment within the mission profile without corruption or loss of data for at least 3 days.	R, T	Test 15	To be done, see test plan

~~D.24~~	~~The experiment shall be able to handle two aborted launches.~~	~~R~~	-	~~To be done~~
D.25	The experiment shall not use a downlink rate greater than 200 kbit/s.	A	-	To be done
D.26	The experiment may include sacrificial joints or other contingency plans to avoid being damaged upon landing if it protrudes from the gondola.	T	Test 6	To be done
D.27	The position of the experiment should be selected in order to reduce "noise" interference from other experiments.	R	-	To be done
D.28	The experiment shall be able to distinguish between incoming and outgoing from Earth radiation.	R	-	To be done
D.29	The sampling time of optical instruments shall be synchronized.	T	Test 10, 11	To be done
O.1	The experiment sensors shall be clean from dust before launch.	I, T	Test 5	To be done, see test plan
O.2	The experiment shall accept commands from the ground station at any time.	A, T	Test 3	To be done, see test plan
O.3	The procedures to turn the experiment on and off should be kept simple.	T	Test 14	~~To be done~~Try the power on / power off system.

O.4	The experiment shall perform autonomously in the event of loss of communication with the ground station.	R, T	Tests 3, 8	To be done, see test plan
O.5	The experiment shall be able to correctly handle aborted launch attempts during any point leading up to, including pre-flight tests, the launch.	R, T	Test 8	To be done, see test plan

5.2 Test Plan

The test ordering follows a system where the test considered most time consuming in case of failure are prioritised. The tests were graded using High, Medium and Low classifications to illustrate the time it takes to be able to redo the test.

Test classification interpretation key:

- High:
  - Tests that require substantial external help or facilities, may cause difficulties in booking times.
  - Tests that may break non-spare components that that may take a long time to re-order.
  - Re-test availability time on the order of weeks to months
- Medium:
  - Tests that require internal co-ordination or may break critical components that takes not insignificant time replacing.
  - Re-test availability time on the order of days
- Low:
  - Tests that can be performed individually by single departments, non-invasive tests.
  - Re-test availability time on the order of hours

5.2.1 Test classification

Tests within a certain classification are initially considered equally important to prioritise, but will include a number for sake of reference.

High Priority

- Test 1: Low Pressure Test
- Test 2: Thermal Test
- Test 3: E-link Test
- Test 4: Vibration Test

Medium Priority

- Test 5: Photodiodes Calibration Test
- Test 6: Shock Test
- Test 7: Power Test
- Test 8: Autonomy Test
- Test 9: Experiment Electronic and Power Subsystem Test

Low Priority

- Test 10: Data Collection Test
- Test 11: Data Collection Synchronisation Test
- Test 12: GPS verification Test
- Test 13: Weight Verification
- Test 14: Experiment Assembly and Disassembly Test
- Test 15: Data Storage Unit Robustness Test
- Test 16: Experiment Prototype Test

5.2.2 Test description

Table 5.2.1: Test 1: Low pressure test description

Test number	1
Test Type	Low Pressure
Test facility	TBD (Esrange Space Center TBC)
Tested item	The whole experiment
Test level/procedure and duration	Test procedure: TBD (reproduce pressure similar to stratospheric pressure at 30 km. Verify that all subsystems are operational and reliable) Test duration: 5 hours.
Test campaign duration	3 days (1 day build-up, 1 day verification, 1 day testing)
Test campaign date	July-August
Test completed	NO

Table 5.2.2: Test 2: Thermal test description

Test number	2
Test Type	Thermal
Test facility	Esrange Space Center
Tested item	The whole experiment
Test level/procedure and duration	Test procedure: TBD (reproduce temperature of -80°C to verify that all subsystems are operational and reliable. Test of the active/passive thermal control unit). Test duration: 5 hours.
Test campaign duration	3 days (1 day build-up, 1 day verification, 1 day testing)
Test campaign date	July-August
Test completed	NO

Table 5.2.3: Test 3: E-link test description

Test number	3
Test Type	E-link
Test facility	TBD (Kiruna Space Campus or Esrange Space Center)
Tested item	TBD
Test level/procedure and duration	Test procedure: TBD Test duration: TBD
Test campaign duration	TBD
Test campaign date	TBD
Test completed	NO

Table 5.2.4: Test 4: Vibration test description

Test number	4
Test Type	Vibration
Test facility	Kiruna Space Campus
Tested item	TBD
Test level/procedure and duration	Test procedure: TBD Test duration: TBD.
Test campaign duration	TBD
Test campaign date	TBD
Test completed	NO

Table 5.2.5: Test 5: Photodiodes Calibration test description

Test number	5
Test Type	Calibration and Verification
Test facility	Kiruna Space Campus laboratory
Tested item	Photodiodes, lenses and filters
Test level/procedure and duration	Test procedure: TBD (A given object, with well-known electromagnetic spectrum response, is used to examine the accuracy of the photodiodes, the functionality of the lenses and filters, determine the influence of dusts on the sensors). Test duration: TBD ($\sim$10 minutes)
Test campaign duration	Recurrent test until and during the launch campaign.
Test campaign date	April
Test completed	NO

Table 5.2.6: Test 6: Shock test description

Test number	6
Test Type	Shock
Test facility	Kiruna Space Campus laboratory
Tested item	The mechanical structure alone first and secondly the whole experiment.
Test level/procedure and duration	Test procedure: TBD. Test duration: TBD .
Test campaign duration	4 days
Test campaign date	July-August
Test completed	NO

Table 5.2.7: Test 7: Power test description

Test number	7
Test Type	Power
Test facility	5 Kiruna Space Campus
Tested item	All the components using electronic power.
Test level/procedure and duration	Test procedure: TBD Test duration: TBD (7hours, to reproduce pre-flight and flight conditions).
Test campaign duration	2 days (1day build-up, 1 day testing).
Test campaign date	July-August
Test completed	NO

Table 5.2.8: Test 8: Autonomy test description

Test number	8
Test Type	E-link
Test facility	TBD (Kiruna Space Campus or Esrange Space Center)
Tested item	TBD
Test level/procedure and duration	Test procedure: TBD Test duration: TBD.
Test campaign duration	TBD
Test campaign date	TBD
Test completed	NO

Table 5.2.9: Test 9: Experiment electronic and power subsystem test description

Test number	9
Test Type	Experiment electronic, control & power subsystem test
Test facility	Kiruna Space Campus laboratory
Tested item	Electronic Subsystems; the upper and lower Arduino photodiode circuits, cameras, barometers, heaters, the monitoring subsystem and data storage unit. Also power system.
Test level/procedure and duration	Basic testing of all components on breadboard, subsystems and all electronic subsystems together. Checking all parameters.
Test campaign duration	Two weeks
Test campaign date	April - May 2017
Test completed	NO

Table 5.2.10: Test 10: Data Collection test description

Test number	10
Test Type	Software
Test facility	Kiruna Space Campus laboratory
Tested item	Micro-controller Unit and Experiment sensors
Test level/procedure and duration	Test procedure: TBD Test duration: 5 hours. Based on previous BEXUS flight durations.
Test campaign duration	2 days (1 day build-up, 1 day testing)
Test campaign date	June
Test completed	NO

Table 5.2.11: Test 11: Data Collection Synchronisation Test

Test number	11
Test Type	Calibration and Verification
Test facility	Kiruna Space Campus Laboratory
Tested item	Data collection
Test level/procedure and duration	Test procedure: TBD (Data collection simulation) Test duration: TBD ($<$ 30 min).
Test campaign duration	1 day
Test campaign date	April
Test completed	NO

Table 5.2.12: Test 12: GPS test description

Test number	12
Test Type	~~Calibration and~~ Verification
Test facility	Kiruna Space Campus Laboratory
Tested item	GPS unit
Test level/procedure and duration	Test procedure: TBD (Drive a car or climb a building to verify the GPS accuracy) Test duration: TBD (30 min).
Test campaign duration	1 day
Test campaign date	April
Test completed	NO

Table 5.2.13: Test 13: Weight verification test description

Test number	13
Test Type	Weight Verification
Test facility	Kiruna Space Campus laboratory
Tested item	The whole experiment
Test level/procedure and duration	Test procedure: TBD Test duration: TBD (1 min).
Test campaign duration	1 day
Test campaign date	July-August
Test completed	NO

Table 5.2.14: Test 14: Assembly & Disassembly test description

Test number	14
Test Type	Assembly and Disassembly
Test facility	Kiruna Space Campus
Tested item	The whole experiment.
Test level/procedure and duration	Test procedure: TBD (All components are placed on a table, a chronometer is used to determine the time necessary to assemble the experiment. After assembly, the chronometer is restarted to calculate the time necessary to disassemble and replace components). Test duration: TBD (1 hour).
Test campaign duration	2 days
Test campaign date	July-August
Test completed	NO

Table 5.2.15: Test 15: Data storage unit robustness test description

Test number	15
Test Type	Robustness
Test facility	Kiruna Space Campus laboratory
Tested item	Data Storage Unit
Test level/procedure and duration	Test procedure: TBD (The data storage unit will be tested in various conditions to assure its resistance for post-landing environmental conditions. Example: put data storage in water, soil, snow,etc. Verify mechanical resistance of the data storage. Determine if sacrificial joints might be needed.) Test duration: TBD (2-3 days).
Test campaign duration	1 month
Test campaign date	April
Test completed	NO

Table 5.2.16: Test 16: Experiment prototype test description

Test number	16
Test Type	Experiment prototype function test
Test facility	Off-site
Tested item	Prototype electronic Subsystems; the Arduino photodiode simulator, cameras, barometers, the monitoring subsystem and data storage unit. Also power system.
Test level/procedure and duration	Basic testing of all components on breadboard, subsystems and all electronic subsystems together. Checking all parameters.
Test campaign duration	Week
Test campaign date	April - May 2017
Test completed	NO

5.3 Test Results

No tests has been conducted yet.

6 Launch Campaign Preparation

6.1 Input for the Campaign/Flight Requirements Plans

6.1.1 Dimensions and Mass

Table 6.1.1: Sensor Box: Mass and volume

Experiment mass (in kg):	2,277
Experiment dimensions (in m):	0,32×0,17×0,132
Experiment footprint area (in m2):	0,045
Experiment volume (in m^3):	0,006
Experiment expected COG position:	x = -1,546 [m]; y = -0,379 [m]; z = -0,002 [m] for the bottom sensor box. x = -1,546 [m]; y = 0,589 [m]; z = -0,003 [m] for the upper sensor box.

Table 6.1.2: Upper Sensor Box and Booms: Mass and volume

Experiment mass (in kg):	6,571
Experiment dimensions (in m):	1,13×0,32×0,162
Experiment footprint area (in m2):	0,362
Experiment volume (in m3):	0,01
Experiment expected COG position:	x = -1,244 [m]; y = -0,527 [m]; z = -0,003 [m]

Table 6.1.3: Bottom Sensor Box and Booms: mass and volume

Experiment mass (in kg):	7,804
Experiment dimensions (in m):	1,45×0,32×0,162
Experiment footprint area (in m2):	0,008
Experiment volume (in m3):	0,011
Experiment expected COG position:	x = -1,09 [m]; y = 0,316 [m]; z = -0,003 [m]

Table 6.1.4: Central "Brain" Box mass and volume

Experiment mass (in kg):	3,807
Experiment dimensions (in m):	0,363×0,28×0,16
Experiment footprint area (in m2):	0,0871
Experiment volume (in m3):	0,013
Experiment expected COG position:	x = -0,053 [m]; y = 0,239 [m]; z = 0,424 [m]

6.1.2 Safety Risks

There is an apparent concern that parts of the apparatus could get detached from the gondola, or possible failure of bolts. ~~There are no apparent safety concerns with the~~

~~experiment regarding launch campaign preparation~~

6.1.3 Electrical Interfaces

Please refer to tab. 6.1.5 for information on the electrical interfaces with the gondola.

Table 6.1.5: Electrical interfaces applicable to BEXUS.

BEXUS Electrical Interfaces		
E-Link Interface: E-Link required? Yes		
	Number of E-Link interfaces:	1
	Data rate - downlink:	200 kbit/s
	Data rate – uplink:	1 kbit/s
	Interface type (RS-232, Ethernet):	Ethernet
Power system: Gondola power required? Yes		
	Peak power (or current) consumption:	34.77 W
	Average power (or current) consumption:	17.87 W
Power system: Experiment includes batteries? No		
	Type of batteries:	
	Number of batteries:	
	Capacity (1 battery):	Ah
	Voltage (1 battery):	V

6.1.4 Launch Site Requirements

The IRIS team will require a working space to mount ~~the three boxes of the experiment on the gondola, and connect them~~ the sensor boxes on the booms, and these on the gondola frame. It will also be needed to mount the RPi box inside the brain box, and this one on the gondola rails. Finally, it will also be required to electrically connect the boxes together and to the gondola electrical interfaces (refer to section 4.2.2), as well as to dismount the experiment from the gondola after the flight. For this to be achieved, the following items will be required:

- Thirteen (13) chairs
- At least one (1) table
- One (1) toolbox
- One (1) power outlet

6.1.5 Flight Requirements

There is no minimum float time for the experiment as measurements will be taken during the whole flight. Therefore, float time should be as long as possible.

In case of cloud-cover the IRIS experiment needs to be able to take measurements from above the clouds. Thus, float altitude should be at least high enough for the gondola to raise above the clouds that may be present at the day of launch. Most clouds, like cirrus clouds, are located in the troposphere, below the expected floating altitude of the HAB [11]. Nevertheless cloud cover poses no problem for the scientific goals of the mission.

IRIS requires daylight in order to obtain the intended scientific data. As a result, launch should take place between sunrise and noon, to maximise the amount of daylight present during the flight. The minimum daylight time required should be during the ascend and 1 hour during the float time. If the flight is during the night we cannot guarantee to collect any meaningful data.

6.1.6 Accommodation Requirements

~~Sensor blocks shall be placed on top and beneath the gondola respectively.~~ The booms carrying the sensor boxes shall be attached the upper gondola frame and its lower mounting rails respectively. They shall also be located on the same side of the gondola, as they can only be mounted on these locations due to the mechanical design of the experiment. Refer to section 4.2.1 for a sketch of the correct placement of the sensor boxes.

~~Gondola crash pads shall be mounted on the gondola before attempting to mount the experiment. This way the bottom sensor box can be attached while the gondola is resting on a surface, and accidental crushing of this particular sensor block under the weight of the gondola can be avoided.~~

~~Both sensor blocks have sensors pointing perpendicularly to the upper and lower surfaces of the gondola, which have a field of view close to 360° x 180°. Any other objects protruding from the upper or lower surfaces of the gondola should be placed as far away from the sensor blocks as possible to minimise interference~~.

Both sensor boxes shall remain uncovered during the whole flight, but they may be covered before and after flight if it is deemed necessary for handling the gondola by the launch and recovery crews.

6.2 Preparation and Test Activities at Esrange

Table 6.2.1: Checklist for flight preparation

Timeline	Events	check
Late access	Remove sensor covers	☐

Before the flight all the lenses need to be cleaned. Afterwards they shall be covered so that they won't get dirty again.

6.3 Timeline for Countdown and Flight

As part of the late access window before the launch the cover of the lenses shall be removed.

The experiment will start measuring data at the time of launch. This will be activated by a command send through the link. It will stop recording data when it is at 10000 ft from ground prior to touchdown, to avoid data loss. The experiment, however, will be switched on prior to the restriction of access, or will be active at any time if power is correctly provided.

When the balloon reaches cruise altitude the experiment may need to switch the frequency at which the data is either gathered or sent to ground. For this, a command will be sent from the ground station. The experiment will however shut down automatically at the specified altitude, or by command prior to that point if considered necessary by the science team or due to low battery readings.

Tab. 6.3.1 summarizes the most important moments on countdown and during flight. Note that this is only a first guess and may suffer changes in the future.

Table 6.3.1: Experiment timeline during countdown and flight

Time	**Action**
T-4H	Experiment check-outs, ground
T-2H30	Experiment check-outs, mounted
T-1H30	late access, remove sensor covers
T-1H00	Experiment check-outs, through E-Link
T+0	E-Link command to start recording, receiving data
T+∼83	Command to reduce acquisition rate
T+∼4H	Check reception of shutdown

6.4 Post-Flight Activities

The SD Memory card needs to be retrieved to save the full data collected during the flight. As our team is based in Kiruna, receiving the data from Esrange should not pose any difficulties.

Afterwards the science team will start analysing the data, providing preliminary results for the post-flight meeting and later a full analysis for the final report. Scientific publications are also planed as well as possible presentations at conferences such as EGU - general assembly.

7 Data Analysis and Results

7.1 Data Analysis Plan

The data from the sensors will be used to compute the irradiances that comes in from the sun and that is reflected from the surface and lower part of the atmosphere. By comparing the two values the bond albedo can be calculated.
The measurements during the ascend phase will give the change of the albedo along the (increasing) height.

A model for radiative transfer (RT) in the atmosphere shall be used. A model like e.g.'FUTBOLIN' [15] will be used to model the different radiative components that are coming in onto the surface as well as the outgoing reflected flux, at the according radiation conditions. These RT models are important for satellite measurements as they are used for the retrieval. By comparing the measured values with the model results, both this model and our measurements can be evaluated. If our measurements and the modelled values are in disagreement, further data analysis could reveal where the error is located and eventually improve the model. An improved radiative transfer model will help to improve the accuracy of satellite measurement evaluation.

For the error analysis many factors have to be taken into account, from the movement of the gondola, the position of the sun in the sky to the potential shadows cast by cables and possibly other experiments.

It is possible that the sun in October, in northern Sweden, is very low on the horizon and therefore it will not directly contribute to the sensors mounted on the top array. Nevertheless, this should not be a problem as a lot of radiation is scattered in the atmosphere. The measurement should reflect the true flux coming from the top and the flux from the bottom.

7.2 Launch Campaign

TBD

7.3 Results

There will be three measurement periods during the flight: the ascent, the float phase and the descent.
During ascent the albedo is expected to vary significantly, because some radiation is absorbed by water vapour in the troposphere. This absorption does not apply for the VIS wavelength spectrum. In the case of clouds or haze much light in the VIS spectrum will be scattered. Therefore, the incident radiation at the top is expected to increase with altitude. In the case of cloud coverage the albedo is expected to increase, as clouds have a high reflectance.
While the balloon is floating the albedo is expected to stabilise, only varying when passing over possible water bodies, such as lakes and rivers or when passing over single clouds.

The measurements during the descent phase should resemble those during the ascent phase.

One expected outcome of the subsequent analysis should be to find a better relation with the albedo throughout changing altitude, contributing to the correction of the errors in the satellite measurements.

This can be achieved by comparing and contrasting the data from both methodologies and calculating the error made from the remote sensing satellites, which measurements are less accurate than the HAB used in this project, as the data in the HAB case is gathered in-situ.

7.4 Lessons Learned

TBD

8 Abbreviations and References

8.1 Abbreviations

AR	Actual Range
ADC	Analog-to-digital converter
BEXUS	Balloon Experiment for University Students
CAD	Computer Aided Design
CATIA	Computer Aided Three-dimensional Interactive Application
CERES	Clouds and the Earth's Radiant Energy System
CW	Center Wavelength
COG	center of gravity
DLR	Deutsches Zentrum für Luft- und Raumfahrt
ECTS	Europeant Credit Transfer System
EM	Electromagnetic
EOE	End of Experiment
EGU	European Geosciences Union
ESA	European Space Agency
ESRANGE	European Space and Sounding Rocket Range
EXIST	Examination of Infrasound in the Stratosphere and Troposphere
FET	Field-Effect Transistor
FoV	Field of View
FUTBOLIN	Full Transfer by Ordinary LINe-by-line methods
GPS	Global Positioning System
HAB	High Altitude Balloon
HEP	High Energy Physics
I2C	Inter-Integrated Circuit
IDE	Integrated Software Environment
IR	Infrared part of the EM spectrum
IRIS	InfraRed albedo measurements In the Stratosphere
LKAB	Luossavaara-Kiirunavaara Aktiebolag
LTE	Local Thermodynamic Equilibrium
LTU	Luleå University of Technology
MCU	Micro Controller Unit
MORABA	Mobile Rocket Base
MSc	Master of Science
NASA	National Aeronautics and Space Administration

NIR	Near-Infrared part of the EM spectrum
NOAA	National Oceanographic and Atmospheric Administration
PIT	Prototype Instrument Project
PCB	Printed Circuit Board
PDR	Preliminary Desing Review
PO	Polar Orbit
PWM	Pulse-Width Modulation
REXUS	Rocket Experiment for University Students
RJ45	Registered Jack 45
RPi	Raspberry Pi
RT	Radiative Transfer
RTE	Radiative Transfer Equation
SAFT	Société des Accumulateurs Fixes et de Traction
SD	Secure Digital (Storage)
SED	Student Experiment Documentation
SNSB	Swedish National Space Board
SOC	System On Chip
SOE	Start of experiment
SSC	Swedish Space Corporation
SZA	Solar Zenith Angle
TBC	To Be Confirmed
TBD	To Be Determined
UART	Universal Asynchronous Receiver Transmitter
ULg	University of Liège
VIS	Visible part of the EM spectrum
WR	Wanted Range
WBS	Work Breakdown Structure
ZARM	Zentrum für angewandte Raumfahrttechnologie und Mikrogravitation

8.2 References

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A Experiment Reviews

B Outreach and Media Coverage

The team's website can be found at: www.bexusiris.com.

IRIS has a Facebook page, located at: facebook.com/bexusiris/.

Our Instagram account is found at: @bexus_iris.

An article about IRIS, as well as our sister project EXIST, has been published by the Atmospheric Science Group at Luleå University of Technology. It can be found here: atmospheres.research.ltu.se

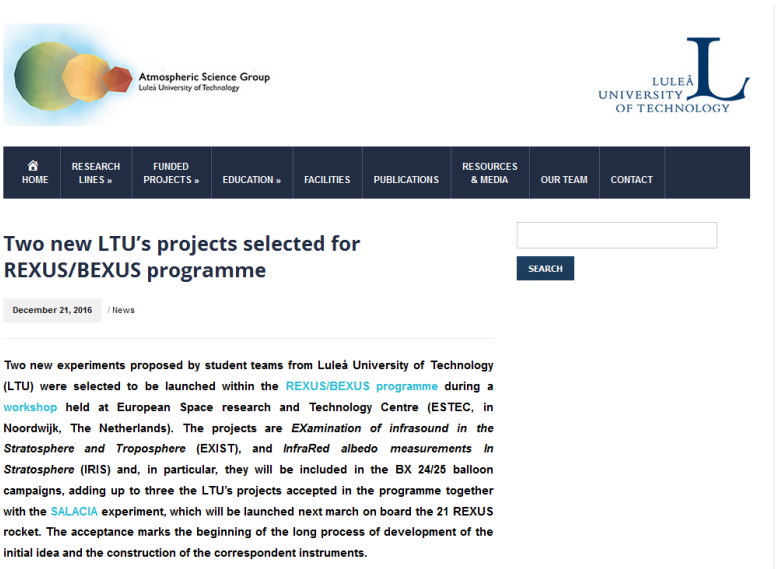

Figure B.0.1: Article about IRIS and EXIST

Another article, based on an interview of members from both IRIS and EXIST, was written by LTU's Communicator Linda Alfredsson. It was published on the university webpage 2017-02-24 and is available in both Swedish and English. Link

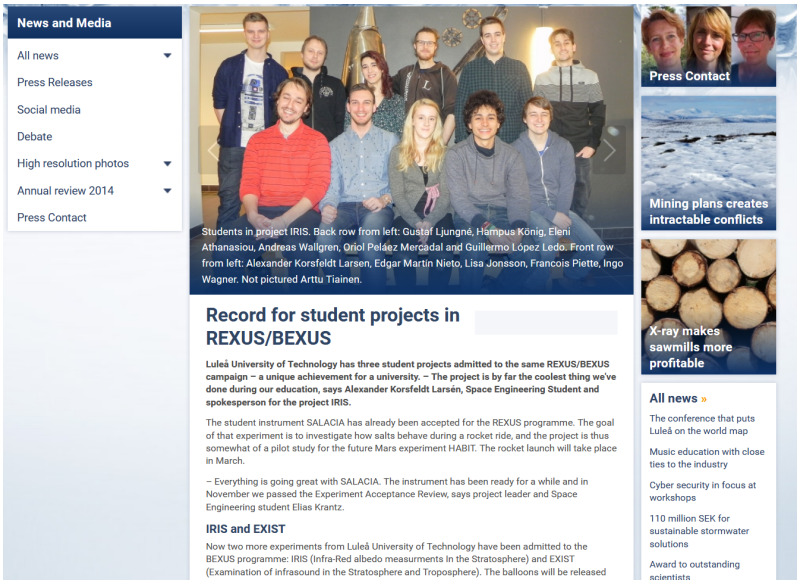

Figure B.0.2: Interview published on the LTU website.

A radio interview was aired on the Swedish radio station P4 Norrbotten on 2017-03-05. Link.

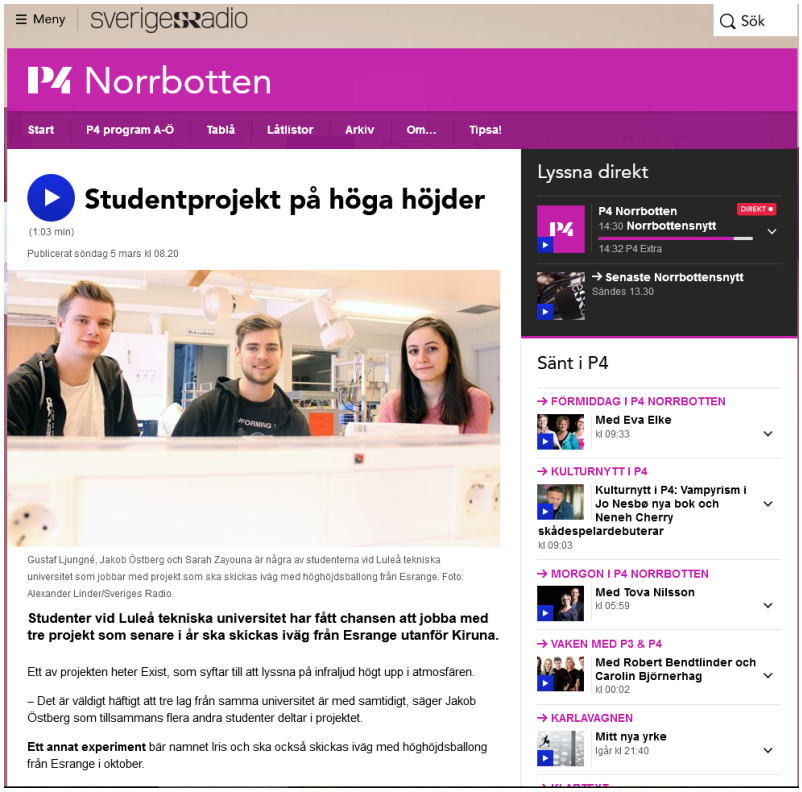

Figure B.0.3: Interview on the radio station P4 Norrbotten

A 20 minute presentation, with an additional 10 minutes for questions, was held for participants of the Space Instruments R7013R course at Luleå University of Technology.

The presentation took place on 2016-12-16. Information about the course can be found at this link.

On 2017-03-22 a short presentation was held together with EXIST for politicians from the county council of Norrbotten, Sweden. We told them about the REXUS/BEXUS programme and about the scientific goals of our experiments. Emphasisis was also put on why we think it is so important to have programmes like this available for students.

On 2017-01-28 IRIS took part in the Space Day 2017, an event organised at Folkets Hus in central Kiruna. Here we presented our project to the general public of Kiruna, sharing a booth with EXIST and the REXUS team SALACIA.

IRIS plans to attend Rymdforum 2017, a conference held in Kiruna May 8-10. This will grant us an opportunity to demonstrate our project and meet representatives from various space companies, space agencies, and the Swedish government. Posters and such will be designed and created in preparation for this event.

The IRIS logo, fig. B.0.4, was created with the aid of Martin Tomasson, a student at Chalmers University of Technology, Göteborg. In addition to a balloon the logo shows incoming light, with the colours of the EU flag, being reflected as the flags of every nation represented in the IRIS project. These countries are Sweden, Belgium, Finland, Spain, Greece, Bulgaria, and Germany.

Figure B.0.4: The IRIS Project logo

In the middle of March, 2017, we received hoodies with our team logo on them that we purchased from T&S Reklam tsreklam.se. The company sponsored 50 % of the cost in exchange for us providing links to their websites in posts on our webpage and Facebook-page. A picture of the hoodies is shown in fig. B.0.5 below.

Figure B.0.5: The IRIS Team Hoodies

C Additional Technical Information

TBD

D Checklists

TBD

E WBS and Gantt Chart

This appendix contains the WBS and Gantt chart for each department in the IRIS team.

E.1 WBS

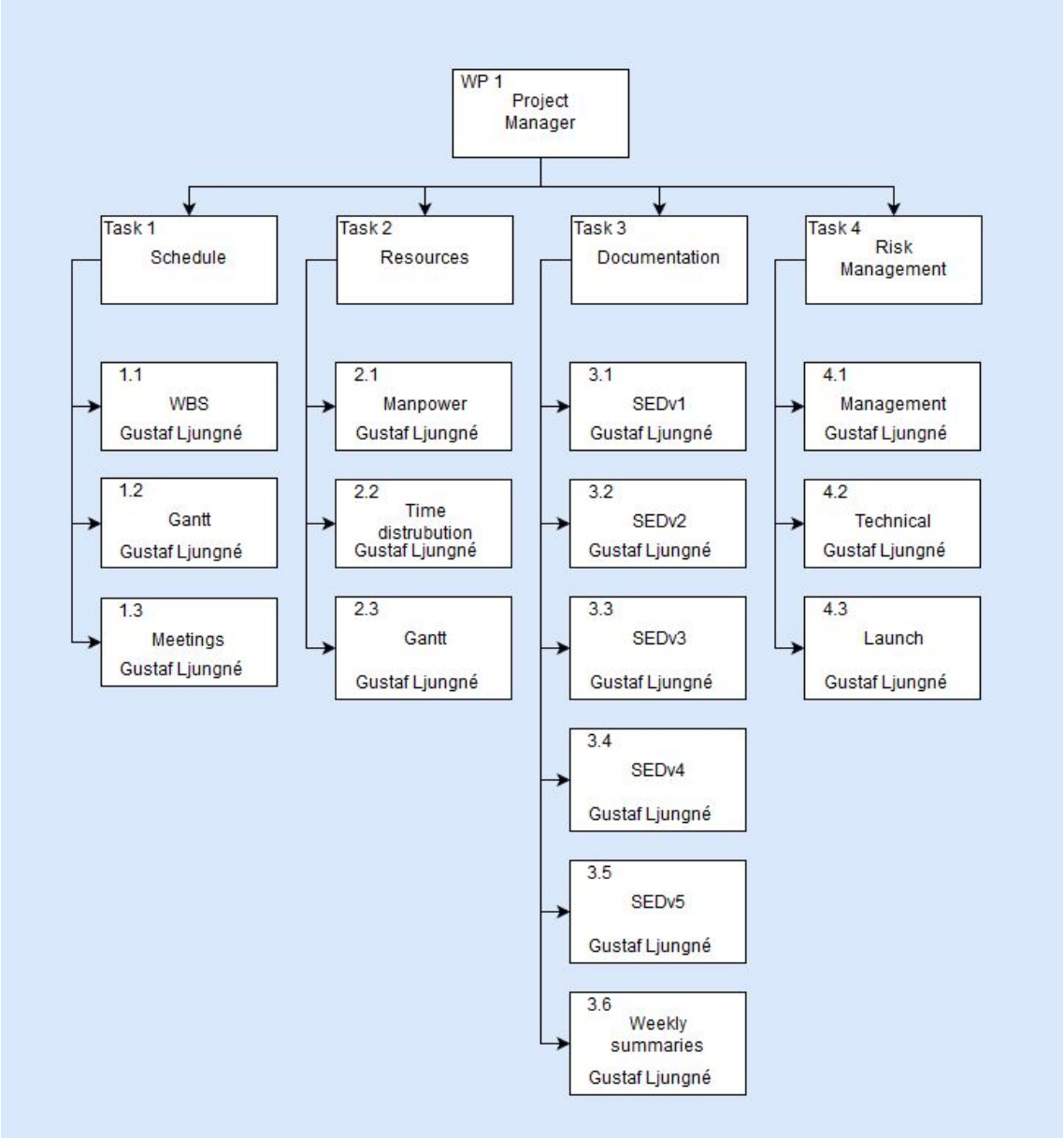

Figure E.1.1: WBS - Project Manager

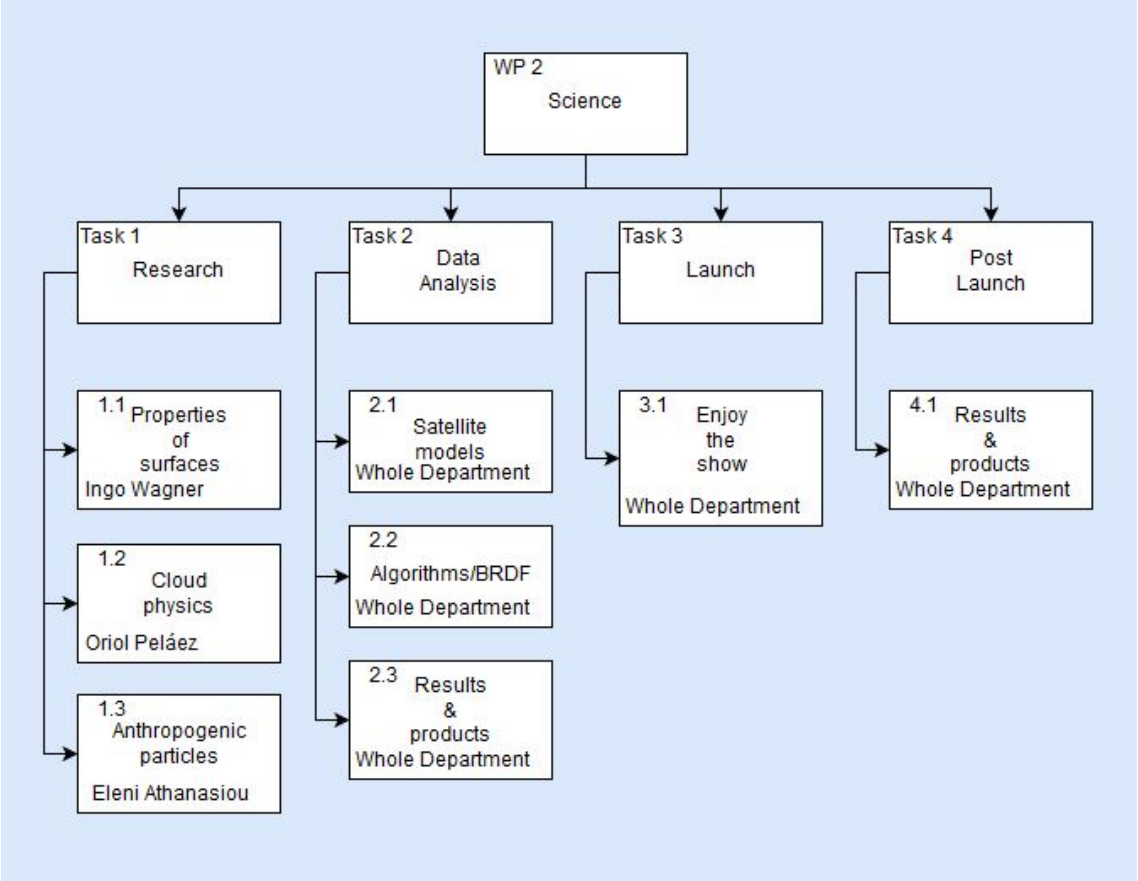

Figure E.1.2: WBS - Science

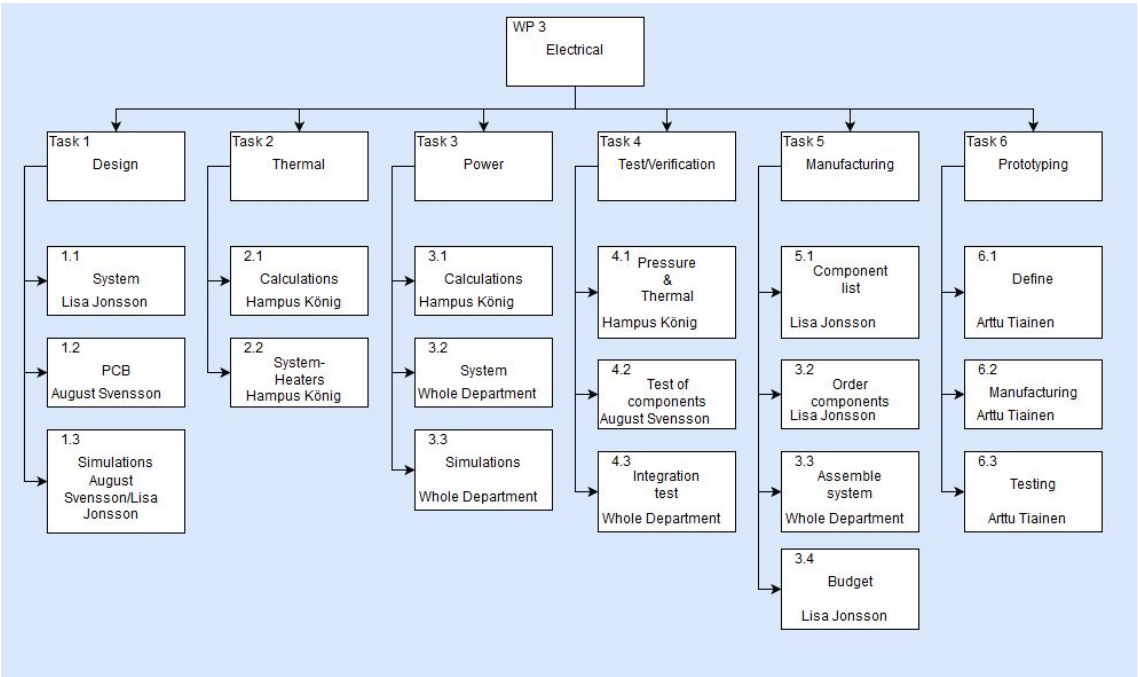

Figure E.1.3: WBS - Electrical

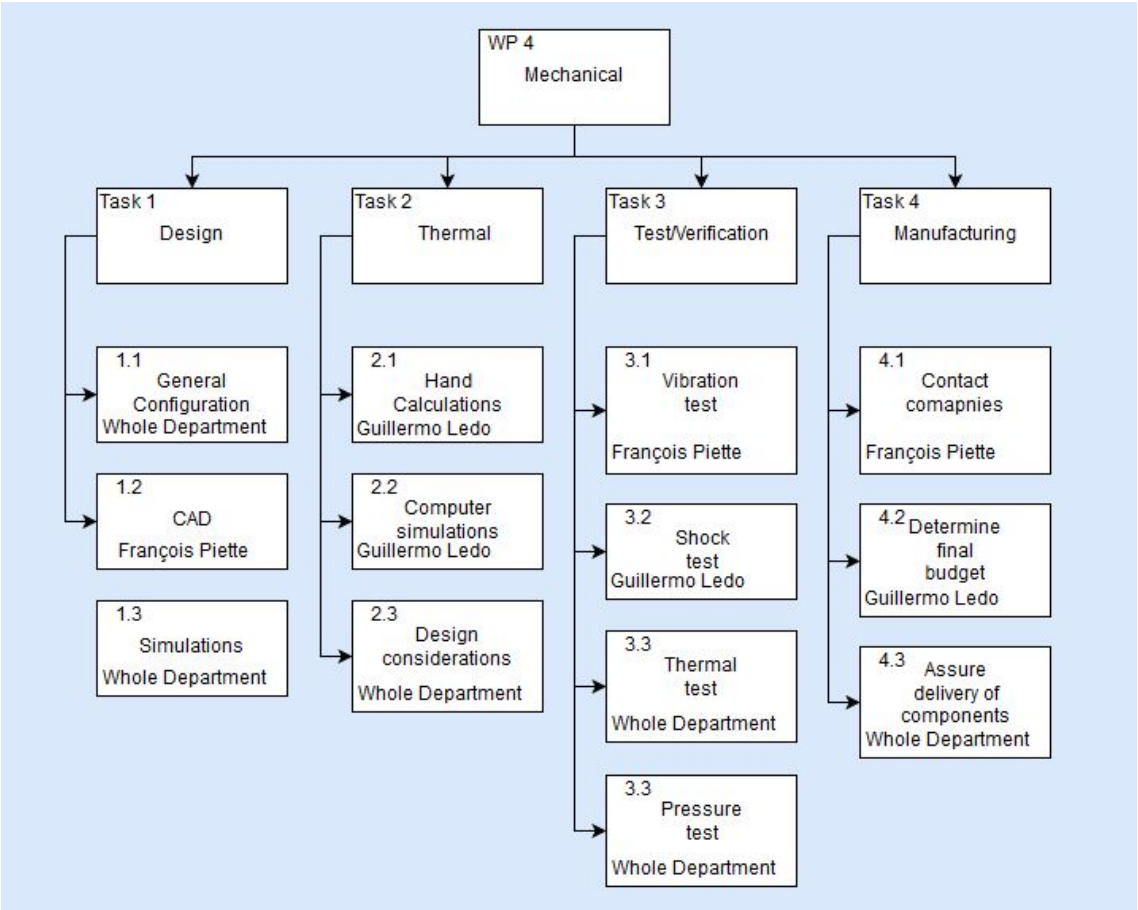

Figure E.1.4: WBS - Mechanical

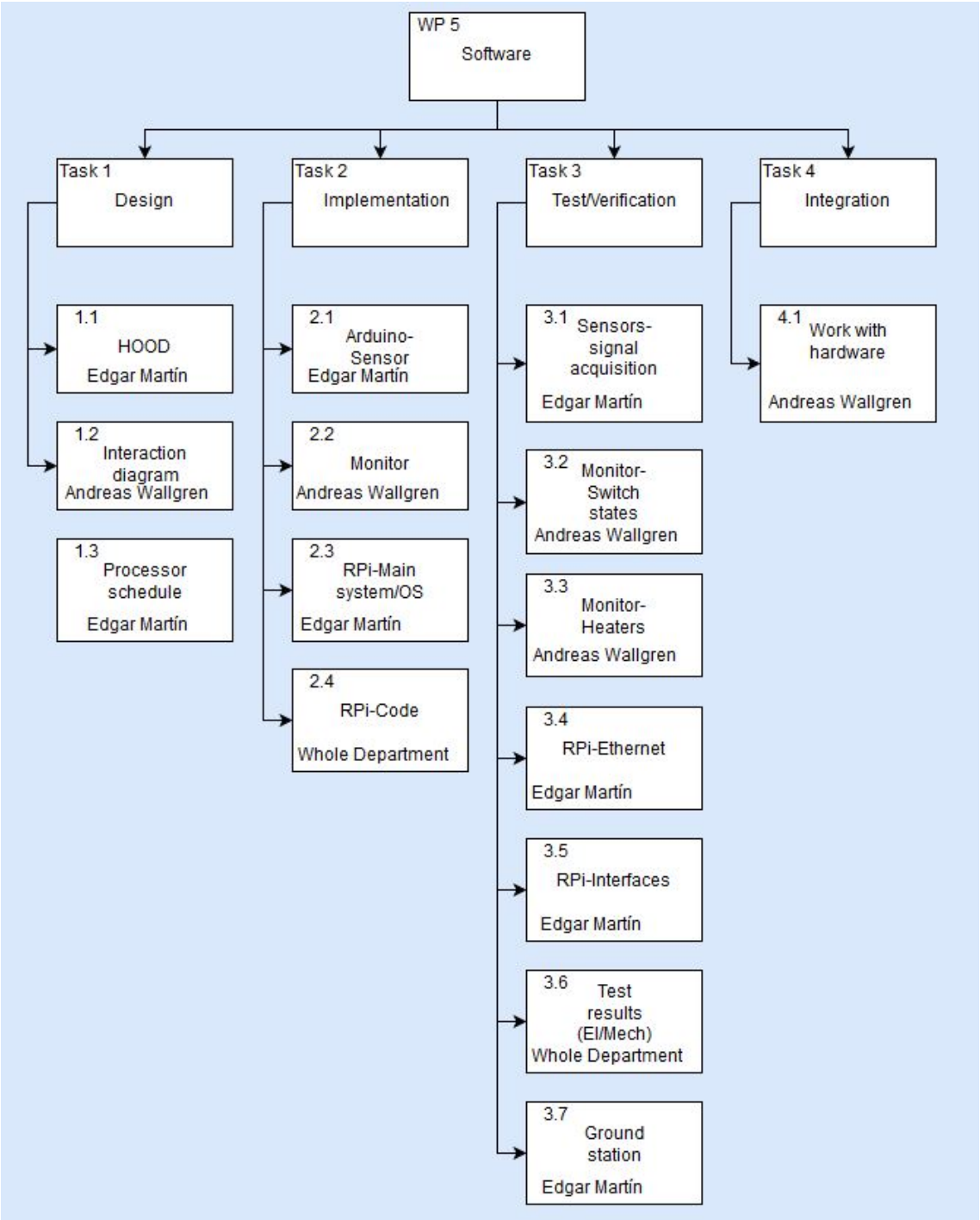

Figure E.1.5: WBS - Software

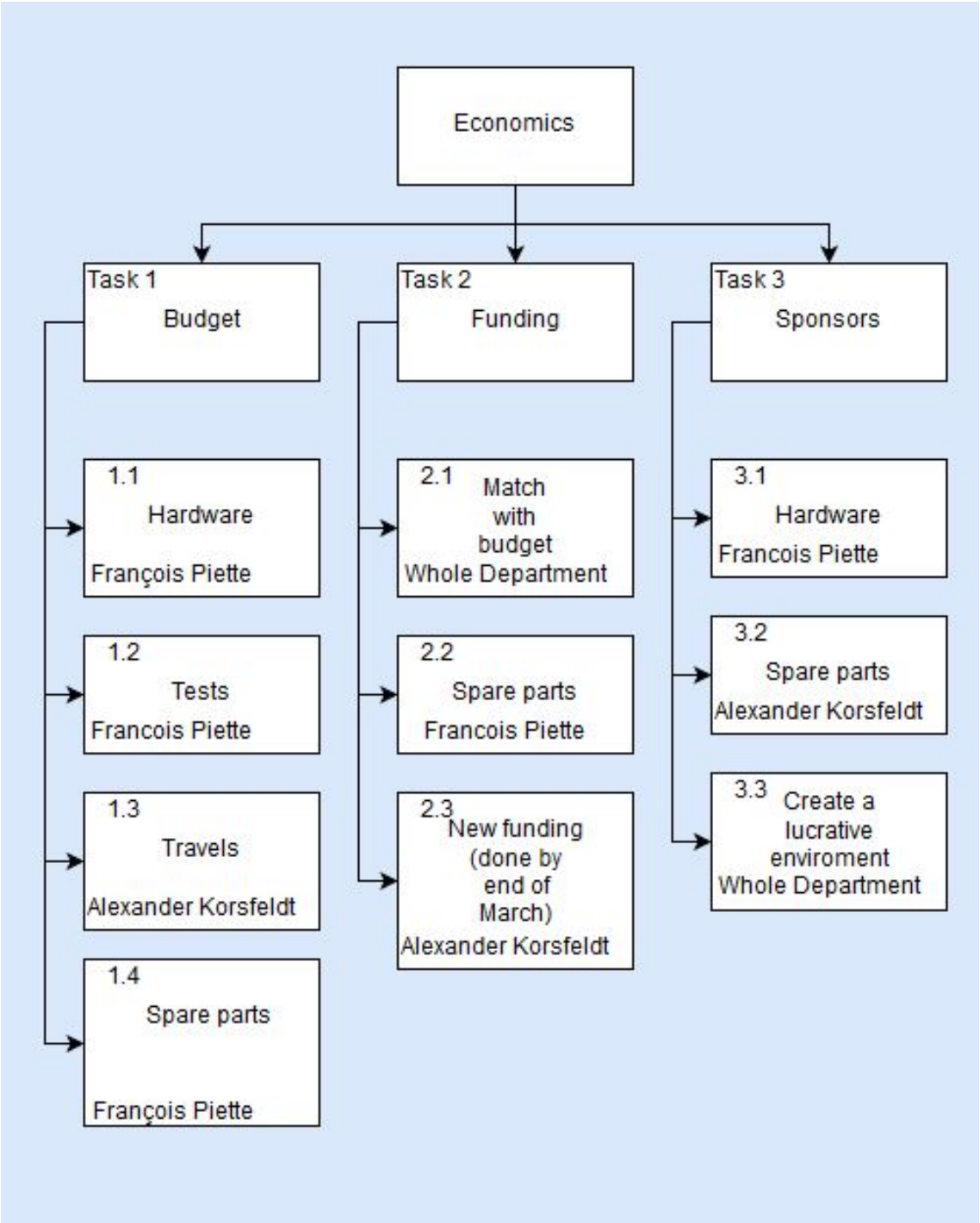

Figure E.1.6: WBS - Economics

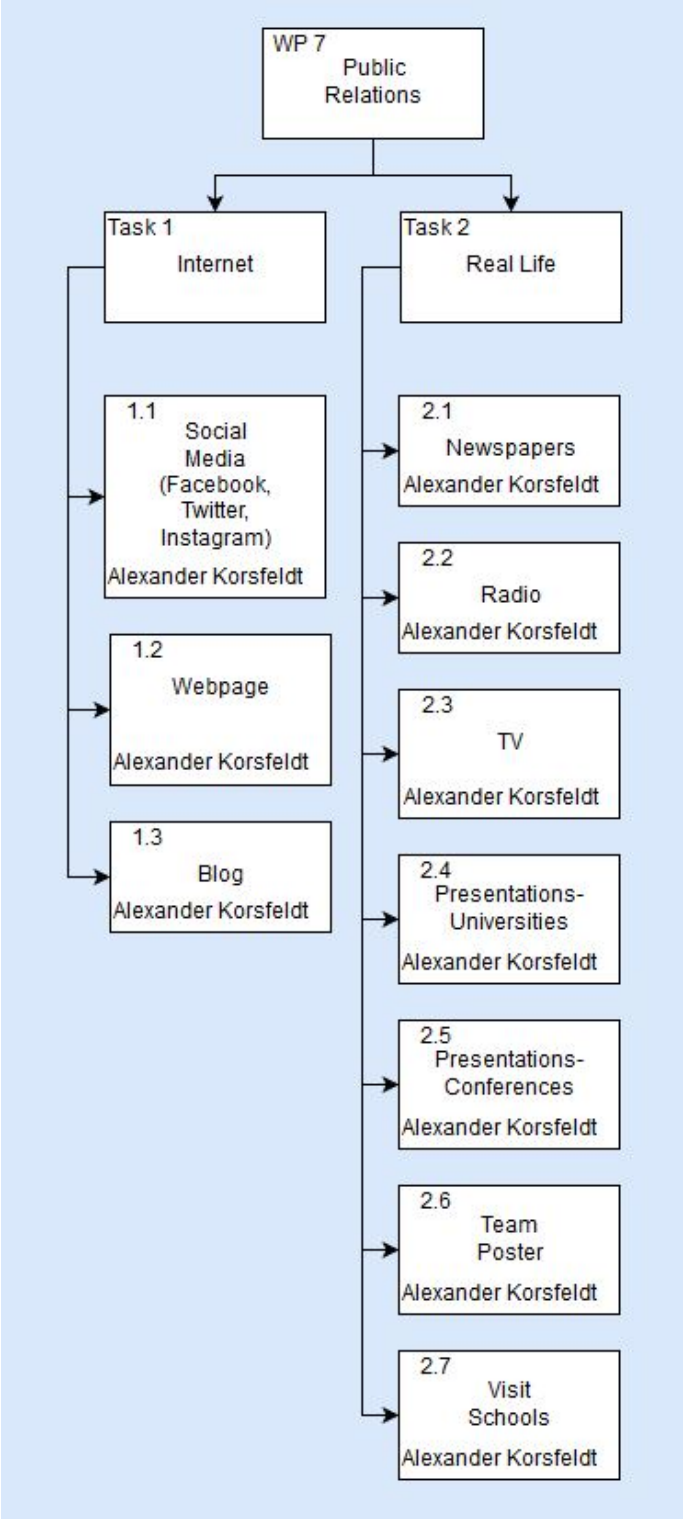

Figure E.1.7: WBS - Public Relations

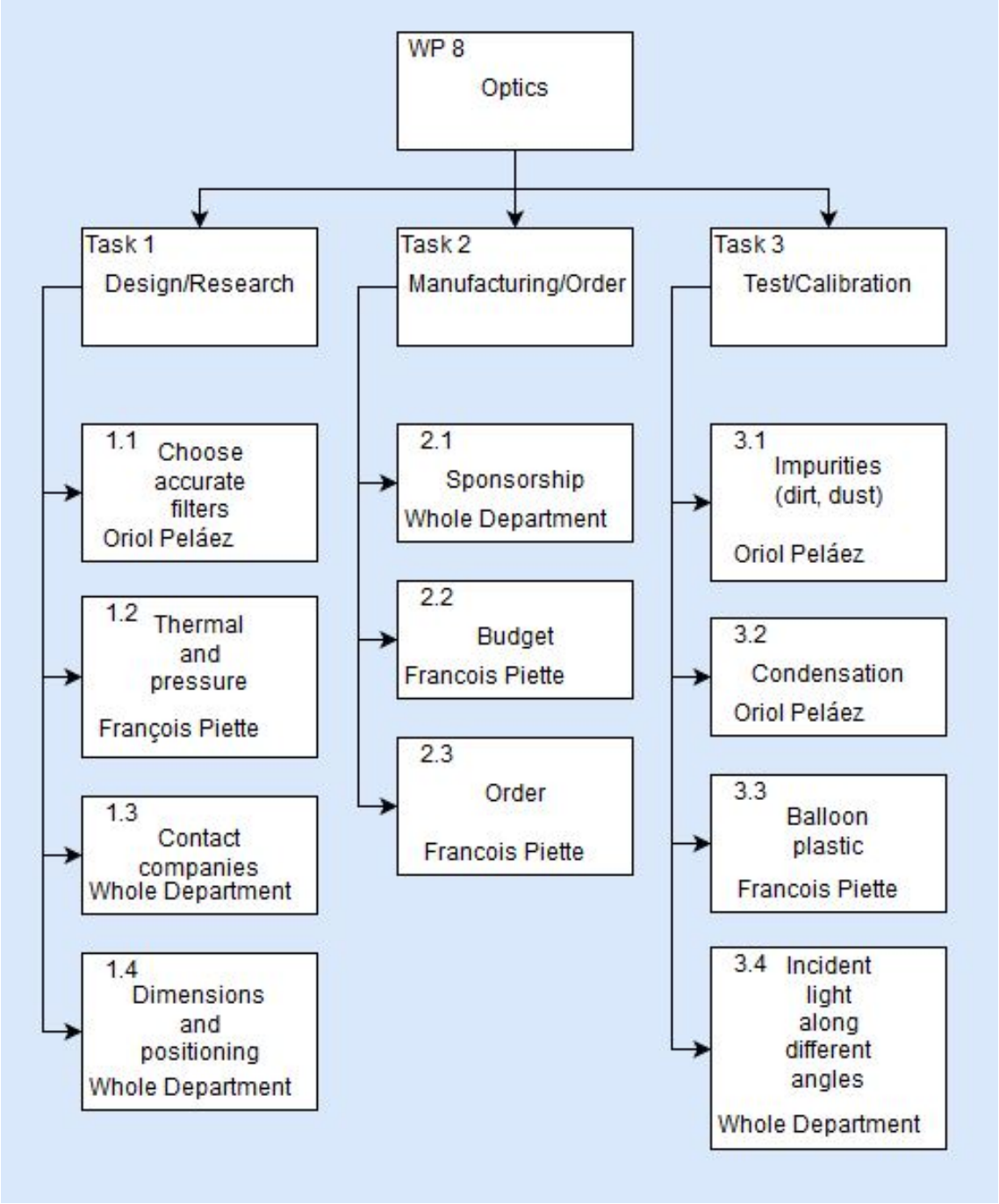

Figure E.1.8: WBS - Optics

E.2 Gantt Chart

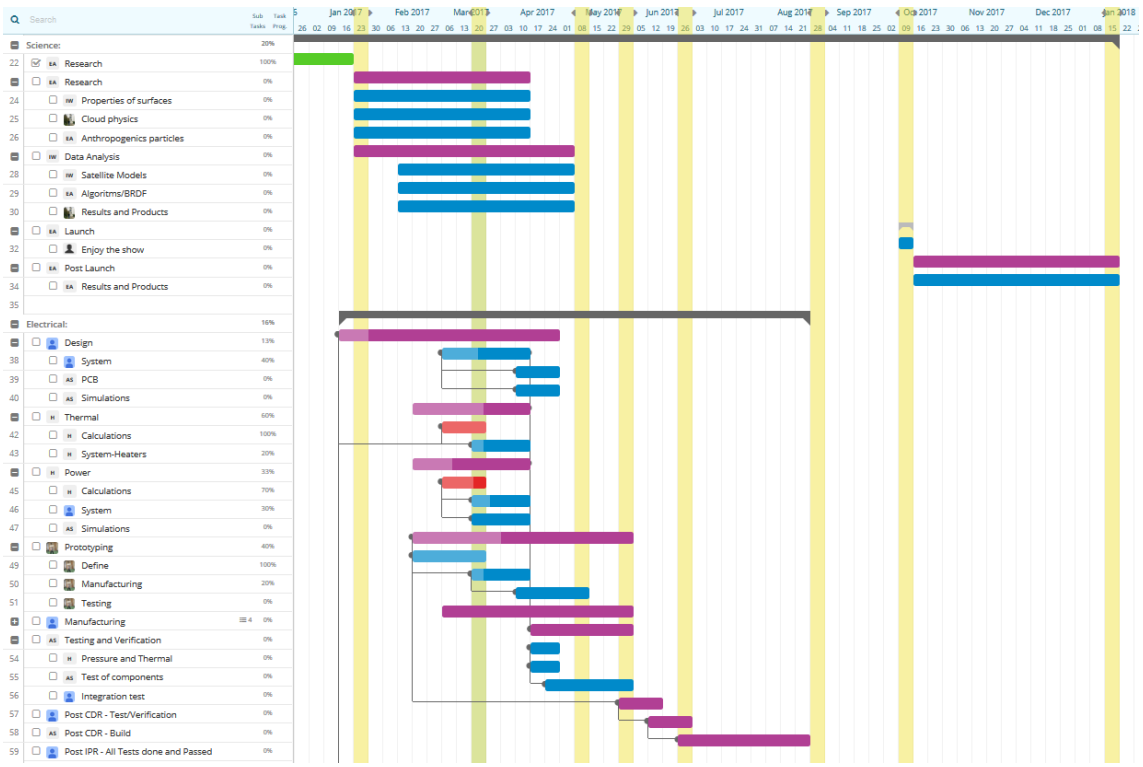

Figure E.2.1: Gantt - Electrical and Science

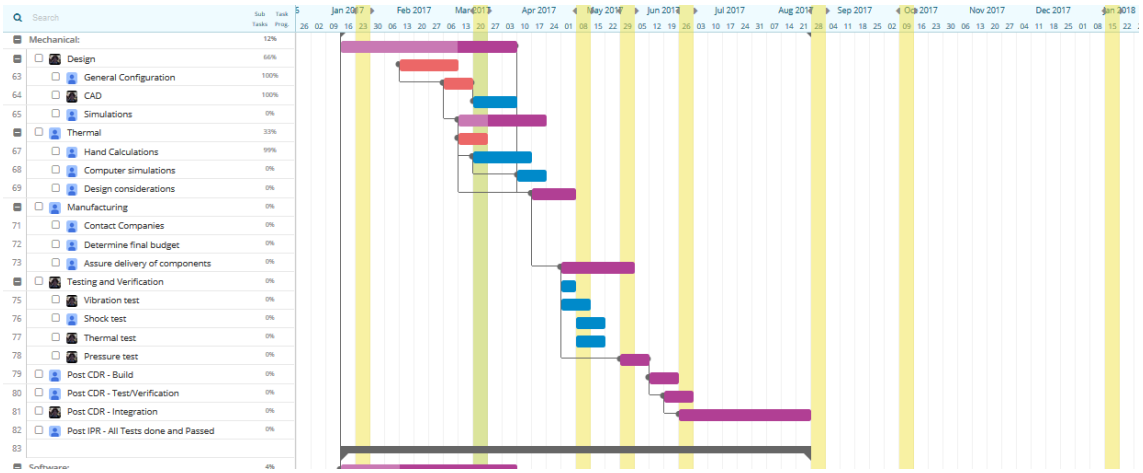

Figure E.2.2: Gantt - Mechanical

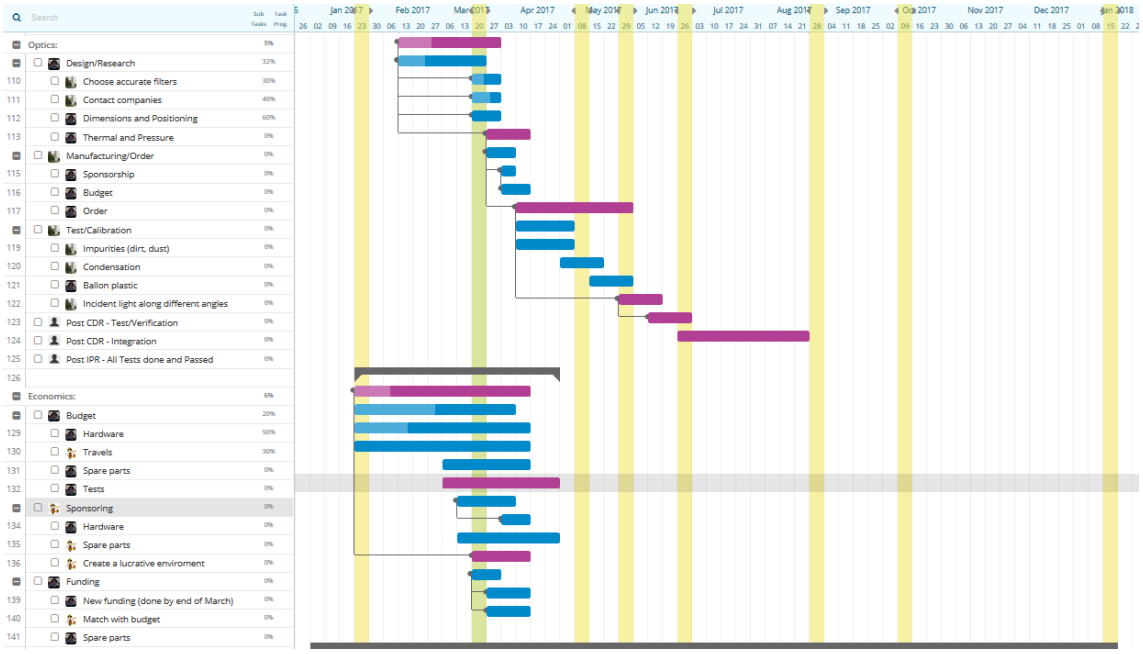

Figure E.2.3: Gantt - Optical and Economics

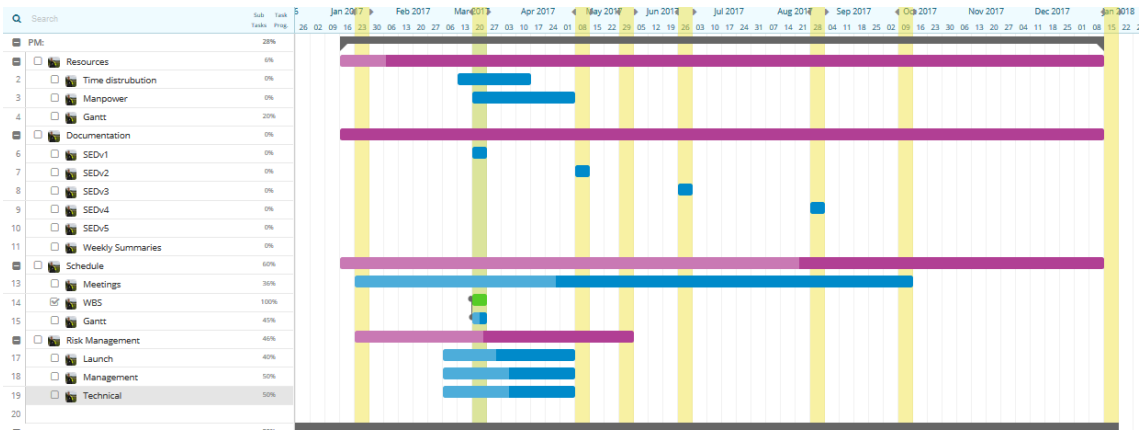

Figure E.2.4: Gantt - Project Managment

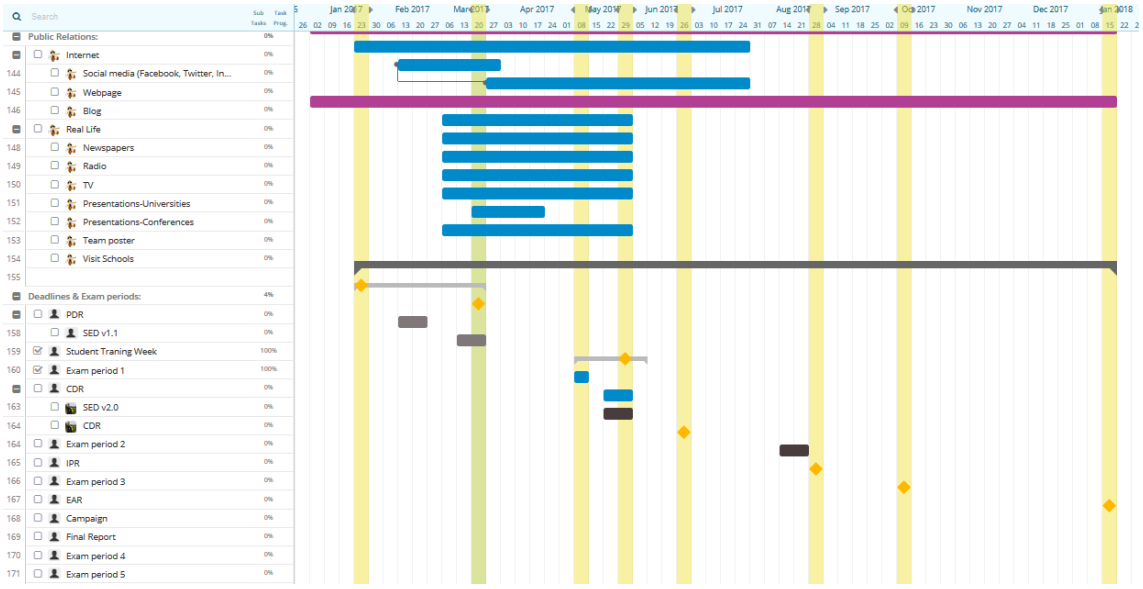

Figure E.2.5: Gantt - Public Relations and Exams/deadlines

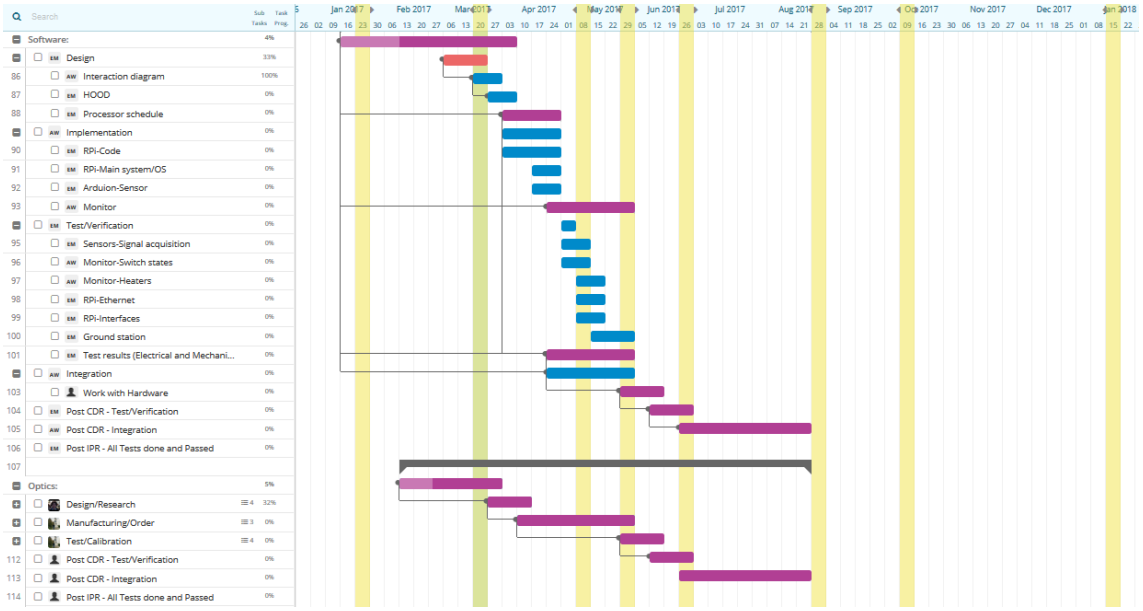

Figure E.2.6: Gantt - Software

F Heat Budget Estimation

In this appendix the method used to estimate the heat budget is presented. Three cases with different assumptions have been considered, starting from a worst-case scenario, followed by a middle-case scenario and finally a best-case scenario. The following assumptions were chosen for each cases:

Table F.0.1: The three thermal cases considered for the heat budget estimation.

	Assumptions
Worst-case scenario	• No power heat dissipation • Solar radiation on the smallest surface for the sensor box. No solar radiation for the brain box. • Forced convection (v=5m/s) for the sensor boxes. Free convection for the brain box. • Maximum conduction area (external surface of the boxes).
Middle case	• 50% power heat dissipation. • Solar radiation on three surfaces with an angle of 45° for the sensor box. No solar radiation for the brain box. • Forced convection (v=5m/s) for the sensor boxes. Free convection for the brain box. • Maximum conduction area (external surface of the boxes).
Best case	• 50% power heat dissipation • Solar radiation on three surfaces with an angle of 45° for the sensor box. No solar radiation for the brain box. • Free convection. • Minimum conduction area (angle brackets+contact with booms).

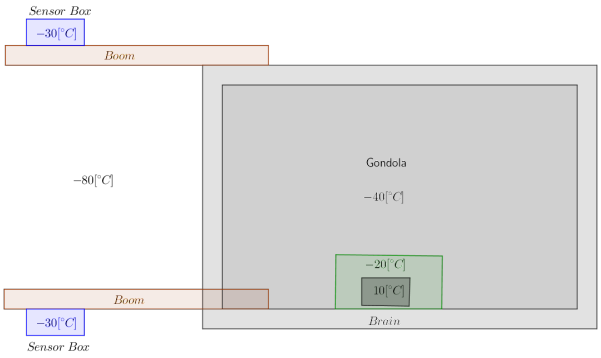

Figure F.0.1: Optimal temperature considered during the estimation of the heat budget.

In each case the same optimal temperature inside the boxes have been assumed, as shown on Fig. F.0.1. These values were selected based on the operating temperature of the components, presented in section 4.6. A safety margin of 10°C was been selected to assure the good behaviour of the electronic components.

In the following section the process used to estimate the heat budget of the middle-case scenario is presented. The estimation process of the other two cases can be deduced from the method presented. The heat budget is calculated for the four boxes: the upper and bottom sensor boxes, the brain box and the Raspberry Pi box (located inside the brain box). The heat budget for the upper and bottom sensor boxes are the same and therefore they are presented as one single box budget.

F.1 Heat Outputs

F.1.1 Conduction

To estimate the loss of heat by conduction the following equation is to be solved:

$$Q = \frac{A\Delta T}{\sum R} \tag{1}$$

Where Q is the heat $[W]$, A is the area in contact $[m^2]$, ΔT is the difference of temperature between the inside and the outside environment $[K]$ and R is the thermal resistance, defined as:

$$R = \frac{L}{k} \tag{2}$$

Where L is the characteristic length $[m]$ and k is the thermal conductivity $[Wm^{-1}K^{-1}]$. The characteristic length is usually the dimension parallel to the heat flow direction. Often the characteristic length is the thickness of the structure. On Fig. F.1.1 the general configuration of IRIS boxes is represented: it is shown that the characteristic length is

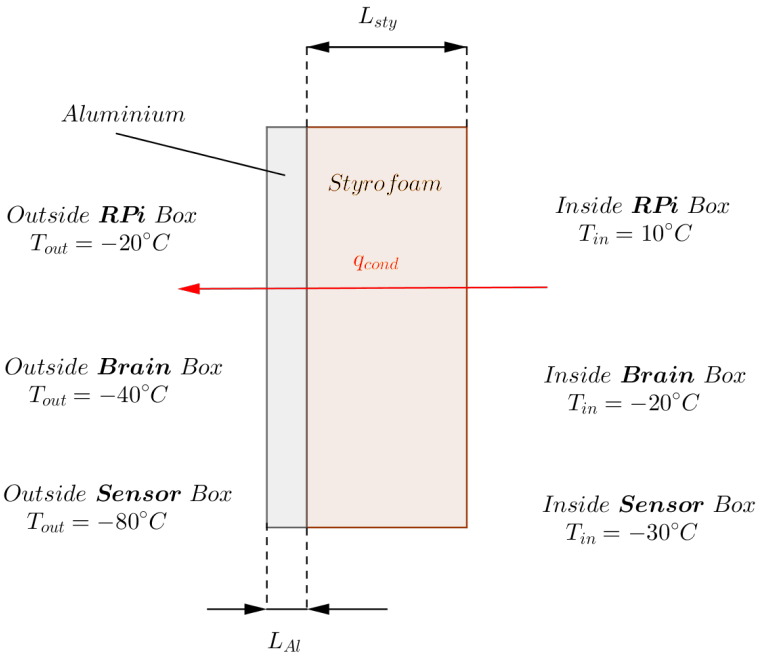

Figure F.1.1: Conduction conditions for the Sensor, Brain and Raspberry Pi box.

the thickness of the material and is parallel to the heat flow.

For each box, it is assumed that conduction has similar parameters on each face. This simplifies the estimation by using the total area of the box in Eq. 1.

The thermal conductivity of Styrofoam-brand foam is estimated to be $0.035\ Wm^{-1}K^{-1}$, and the conductivity of aluminium is estimated to be $130\ Wm^{-1}K^{-1}$. Using this data, it is now possible to estimate the heat losses by conduction for each box.

	$L\ [m]$	$R\ [KW^{-1}]$	$A\ [m^2]$	ΔT	$Q\ [W]$
Sensor Box	$L_{Al} = 0.02$; $L_{sty} = 0.04$	$R_{Al} = 1.538 \times 10^{-4}$; $R_{sty} = 1.1428$	0.238	50	10.41
Brain Box	$L_{Al} = 0.02$; $L_{sty} = 0.04$	$R_{Al} = 1.538 \times 10^{-4}$; $R_{sty} = 1.1428$	0.4108	20	7.188
RPi Box	$L_{Al} = 0.0025$; $L_{sty} = 0.02$	$R_{Al} = 1.923 \times 10^{-5}$; $R_{sty} = 0.571$	0.054	30	2.835

Table F.1.1: Conduction Heat Budget Estimation for the middle case scenario.

F.1.2 Convection

To estimate the loss of heat by convection, the following equation is to be solved:

$$Q = hA\Delta T \tag{3}$$

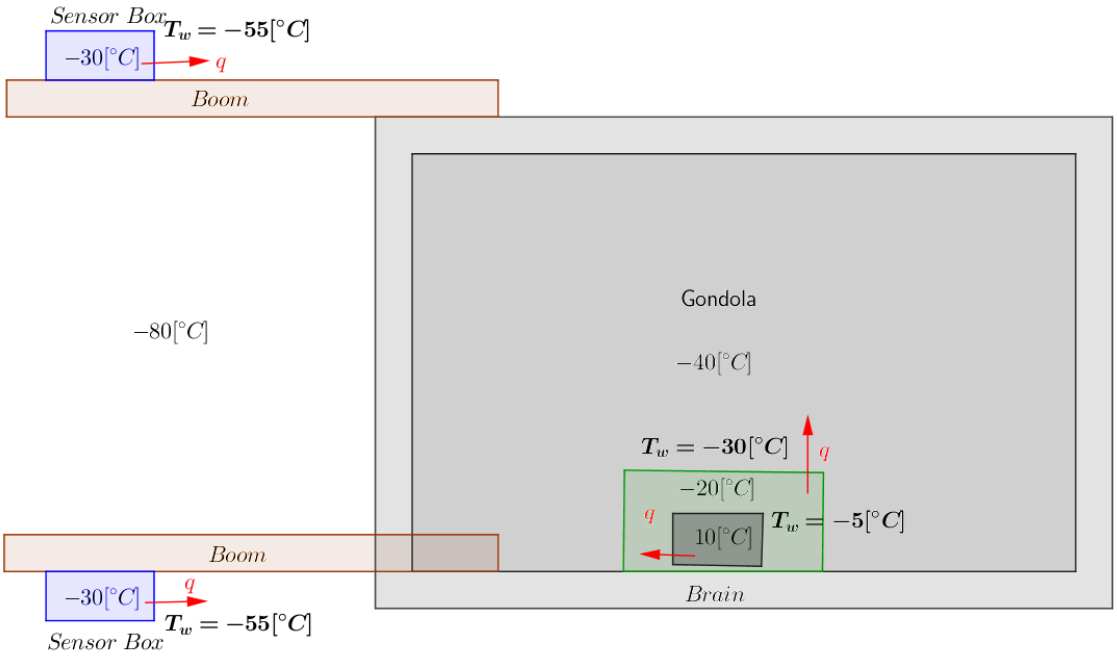

Figure F.1.2: Wall temperature estimation for the sensor, Brain and Raspberry Pi boxes.

where h is the convective heat transfer coefficient, A is the area, and ΔT is the difference of temperature between the fluid and the wall.

The temperature of the wall is unknown but it can be estimated as the average between the inside and the outside temperatures:

$$T_w = \frac{T_{in} + T_{out}}{2} \tag{4}$$

The wall temperature of each box is represented on fig. F.1.2. By knowing the wall temperature it is possible to calculate the difference of temperature for each box.

Based on the data presented in the document "*U.S. Standard Atmosphere Supplements, 1966*" by NASA, the properties of the air at stratospheric altitude can be estimated. Properties of air were measured at latitude of $60°$ at an altitude of 25 km at a temperature of $-45\ °C$ (page 134), and similar data were measured at a latitude of $70°$ and an altitude of 25 km at a temperature of $-76\ °C$ (page 140). Therefore the following properties for the air in the stratosphere are known:

	$k\ [Wm^{-1}K^{-1}]$	$\rho\ [kgm^{-3}]$	$\mu\ [kgm^{-1}s^{-1}]$	$C_p\ [Jkg^{-1}K^{-1}]$
$T = -40°C$	0.02047	4.205×10^{-2}	1.484×10^{-5}	1000
$T = -80°C$	0.01785	3.233×10^{-2}	1.312×10^{-5}	1000

Table F.1.2: Air properties from an altitude of 25 km at high latitude with an atmospheric temperature of $-45\ [°C]$ and $-76\ [°C]$.

This data allows to determine useful thermodynamic properties that will be used in subsequent steps:

	$\nu\ [m^2s^{-1}]$	$\alpha\ [m^2s^{-1}]$	$\beta\ [K^{-1}]$	Pr [-]
$T = -40°C$	3.529×10^{-4}	4.868×10^{-4}	0.0043	0.725
$T = -80°C$	0.01785	3.233×10^{-2}	1.312×10^{-5}	0.735

Table F.1.3: Thermodynamic air properties based on the data on tab. F.1.2.

The most complex part about convection is to estimate the convective heat transfer coefficient, h. By using the air properties presented previously, it is possible to empirically estimate this parameter for free and forced convection. The two methods will be presented shortly in the following subsection. Generally the convective heat transfer coefficient is estimated by using an empirical law to calculate the Nusselt number, which is linked to the heat transfer coefficient by the following equation:

$$Nu = \frac{hL}{k} \tag{5}$$

where h is the convective heat transfer coefficient, L is the characteristic length and k is the thermal conductivity of the fluid. The characteristic length for vertical plates in free convection corresponds to the dimension which is parallel to gravity. For horizontal plates the following formula is generally used:

$$L = \frac{Area}{Perimeter} \tag{6}$$

For free convection the following characteristics lengths are considered:

	$L\ [m]$
Sensor Box: Vertical Plate	0.132
Sensor Box: Horizontal Plate	0.055
Brain Box: Vertical Plate	0.16
Brain Box: Horizontal Plate	0.079
RPi Box: Vertical Plate	0.055
RPi Box: Horizontal Plate	0.027

Table F.1.4: Characteristic lengths for free convection.

The characteristic length for forced convection can be considered to be the length in the direction of the flow. For forced convection along the longest length of the sensor box, the following characteristic lengths are considered:

	$L\ [m]$
Sensor Box: Vertical Plate	0.32
Sensor Box: Horizontal Plate	0.0333

Table F.1.5: Characteristic lengths for forced convection.

N.B. : The Brain and RPi box are not considered for forced convection because they are inside the gondola.

Free Convection

For free convection, the Nusselt number is a function of the Rayleigh and Prandtl number and therefore it is necessary to first calculate them. However, the Rayleigh number requires to calculate the Grashof number. The Grashof and Prandlt number can be estimated based on the properties of the fluid:

$$Gr = \frac{g\beta(T_w - T_{inf})L^3}{\nu^2} \tag{7}$$

$$Pr = \frac{\nu}{\alpha} = \frac{c_p\mu}{k} \tag{8}$$

where g is the gravity, β is the thermal expansion coefficient, T_w is the wall temperature, T_{inf} is the temperature of the fluid, L is the characteristic length and ν is the kinematic viscosity.

After calculating the Grashof and Prandtl numbers, the Rayleigh number can be obtained:

$$Ra = GrPr \tag{9}$$

Based on the Rayleigh number range, different empirical formulae exist for calculating the Nusselt number. Also, the Nusselt empirical law depends on the orientation of the plate. Therefore, different equations for horizontal and vertical plates must be used.

The empirical law used for free convection at a vertical wall for this case is:

$$Nu = 0.68 + \frac{0.67Ra^{1/4}}{[1 + (\frac{0.492}{Pr})^{9/16}]^{4/9}} \tag{10}$$

For horizontal plates the following equation is used:

$$Nu = 0.59Ra^{1/4} \tag{11}$$

Finally, it is possible to estimate the convective heat coefficient for the brain and RPi boxes:

	Gr [-]	Ra [-]	Nu [-]	h $[Wm^{-2}K^{-1}]$	q $[W]$	q_{tot} $[W]$
Brain: Vertical Plate 1	13846.41	10038.14	5.847	0.748	0.437	0.874
Brain: Vertical Plate 2	13846.41	10038.14	5.847	0.748	0.335	0.67
Brain: Horizontal Plate	1680.97	1218.64	3.49	0.901	0.921	1.842
Brain: **Total**						3.385
RPi: Vertical Plate 1	754.91	547.28	3.176	1.23	0.129	0.258
RPi: Vertical Plate 2	754.91	547.28	3.176	1.23	0.11	0.22
RPi: Horizontal Plate	100.106	72.57	1.72	1.3	0.274	0.548
RPi: **Total**						1.026

Table F.1.6: Free convection heat budget estimation for the Brain and Raspberry Pi boxes.

Forced Convection

For the forced convection the Reynolds number of the flow around the boxes has to be estimated first. In this special case, we have assume that the flow speed would be 5m/s. First the Reynolds number has to be calculated:

$$Re = \frac{u\rho L}{\mu} \tag{12}$$

Where u is the velocity of the flow, ρ is the density, L is the characteristic length, and μ is the dynamic viscosity. By calculating the Reynolds number the Nusselt number can be calculated:

$$Nu = 0.664 Re^{1/2} Pr^{1/3} \tag{13}$$

Finally it is possible to estimate the convective heat coefficient to determine the heat budget with forced convection :

	Re [-]	Nu [-]	h $[Wm^{-2}K^{-1}]$	q $[W]$	q_{tot} $[W]$
Sensor : Vertical Plate 1	1626.36	24.17	3.27	3.451	6.902
Sensor : Vertical Plate 2	1626.36	24.17	3.27	1.833	3.666
Sensor : Horizontal Plate	683.93	15.67	5.04	6.854	13.708
Sensor : **Total**					24.276

Table F.1.7: Forced convection with a flow velocity $v = 5m/s$ heat budget estimation for the Sensor box.

F.1.3 Radiation

Radiation losses are caused by the tendency of warm bodies to emit radiation. The emissivity of Styrofoam-brand foam is 0.6. Even though it is currently not possible for the IRIS team to estimate the emissivity of this foam at stratospheric temperatures, this value provides a good estimate of the radiation balance with its environment.

The Stefan-Boltzmann law for grey bodies can be used to estimate the radiation heat balance:

$$Q = \epsilon A \sigma (T_{in}^4 - T_{out}^4) \tag{14}$$

Where ϵ is the emissivity, σ is the Boltzmann constant, T_{in} is the temperature of the body emitting radiation within the body of interest, T_{out} is the temperature of the box and A is the area of the box.

For the sensor boxes, the radiation input is assumed to be zero: even though some emitted thermal radiation from the gondola will warm them, this is considered negligeable. The brain box within the gondola will be subject to emitted radiation inside the gondola, as shown on Fig. F.1.3.

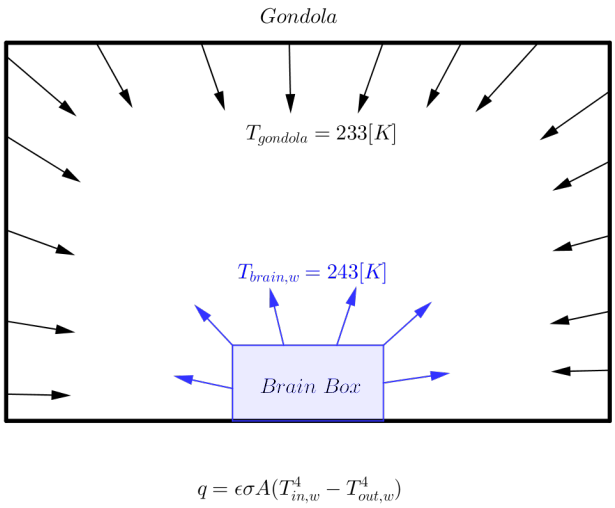

Figure F.1.3: Radiation field of the brain box inside the gondola.

Introducing the value $\sigma = 5.67 \times 10^{-8}\ \frac{W}{m^2K^4}$ and the emissivity of Styrofoam-brand foam, the following radiation losses are obtained:

- Sensor box: 17.26 W
- Brain box: 7.54 W
- RPi box: 1.95 W

F.2 Heat Inputs

F.2.1 Heat Power Dissipation

Without any kind of active thermal control, the electronic devices in each of the boxes are the only source of heat from inside. In order to estimate how much heat is being generated by each component, a 50% power efficiency is assumed for all of them, meaning that 50% of the electric power consumed by each component is being converted into heat. Notice that in the worst-case scenario all electronic devices are assumed to be not working, which means they would be producing no heat at all.

Therefore, calculating the heat power dissipation for each box is reduced to first identify which components are present on each box and how much electric power they consume; these values can be found on Tab. 4.6.1. After applying a 50% efficiency to the power consumption of every component, the resulting heat power dissipations are summed for the components present on each box. The result is the heat input in the form of heat power dissipation for each box:

- Sensor box: 0.9 W
- Brain box: 0.784 W

- RPi box: 1.5 W

F.2.2 Solar Radiation

The heat transfered to a surface by incident electromagnetic radiation can be calculated from the following equation:

$$Q = AIcos(\theta) \tag{15}$$

where Q $[W]$ is the absorbed heat, A $[m^2]$ is the exposed area, I $[Wm^{-2}]$ is the solar irradiance, and θ is the angle of incidence of the incoming photons on the surface and is equal to zero in the case of perpendicular incidence.

Solar irradiance has an approximate value of $I = 1362\ \frac{W}{m^2}$ at one astronomical unit from the Sun. As stated in Tab. F.0.1, only the sensor boxes are considered to be receiving solar radiation in all cases. For the middle-case in particular, solar radiation is assumed to hit three different surfaces of each sensor box at an average angle of $\theta = 45°$: this is intended to represent the possible rotations of the gondola during the flight.

By calculating the exposed area A for both sensor boxes -which is the same due to both having the same dimensions and being attached to the gondola in a very similar position- and making use of the aforementioned values of irradiance and incidence angle, equation 15 can be then used to obtain the heat input from the solar radiation, which has a value of $Q = 114.7$ W.

F.3 Heat Budget

Once both heat inputs and outputs are calculated as shown in the previous sections, the heat budget can be calculated by substracting the heat outputs to the heat inputs. The results for the middle-case scenario are shown on Tab. F.3.1.

	Conduction	Convection	Radiation	Power Dissipation	Solar Irradiance	**Total**
Sensor Box	10.418	24.278	17.26	0.9	114.68	63.63
Brain Box	2.835	3.385	7.54	0.784	0	-11.52
RPi Box	7.18	1.026	1.95	1.5	0	-4.312

Table F.3.1: Heat budget estimation for the middle case scenario. All values are given in Watts.