

Digital Radio Projects

IP400 Radio Node for Phase 1 and 2

Document Number: TBD

Revision: 0.4b

Status: Pre-release

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- [2] ST Microelectronics, "STM32WL33CC: Sub-GHz Wireless Microcontrollers.," ST Microelectronics, [Online]. Available: <https://www.st.com/en/microcontrollers-microprocessors/stm32wl33cc.html>. [Accessed 28 1 2025].
- [3] ST Microelectronics, "STM32 Nucleo-64 development board with STM32WL33CC MCU," [Online]. Available: <https://www.st.com/en/evaluation-tools/nucleo-wl33cc2.html>. [Accessed 26 01 2025].
- [4] ST Microelectronics, "Integrated Development Environment for STM32," [Online]. Available: <https://www.st.com/en/development-tools/stm32cubeide.html>. [Accessed 26 1 2025].
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Revision Status

Revision	Date	Description
0.1	January 26 th , 2025	Initial draft
0.2	February 2 nd , 2025	Added release notes for V0.3
0.3	February 6 th , 2025	Added release notes for V0.4, added Pi HAT description
0.4a	February 7 th , 2025	Added release notes for V0.4a, updated GPS section
0.4b	February 9 th , 2025	Added BW table and fixed missing pictures, and GPS fix

Table 1 Revision status

Reference Documents

Author	Issue Date	Description
M. Alcock	Jan 2025	IP400 Protocol Specification

Table 2 Reference Documents

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Introduction

The IP400 project was launched to experiment with digital mesh networking on the 400 MHz band, using commercial devices designed to run in this band.

To get the project rolling, code has been developed for an STM32WL33 microcontroller [2], using an off the shelf evaluation board called a 'nucleo' [3]. This will be superseded with other platforms for the Raspberry Pi and Arduino form factors, and eventually new devices that will include signal processing for higher orders of modulation, and RF components for other bands.

Operation of the node is segmented into a physical layer that runs on the microcontroller, and other layers that run on different host processors. The lower layer code contains the bare minimum to send and receive frames, repeating frames and building a mesh table, and contains a simple application.

The application code includes a simple setup menu, and the ability to change and store station and radio parameters, as well as a simple chat application to demonstrate the capabilities. It periodically sends a 'beacon' frame to build the mesh tables, which contains information about the station, including latitude, longitude and grid square. Provision has also been made to connect to a GPS receiver to update the position information dynamically.

Roadmap

Figure 1 illustrates the roadmap for the IP400 node development.

IP400 Node Development Roadmap

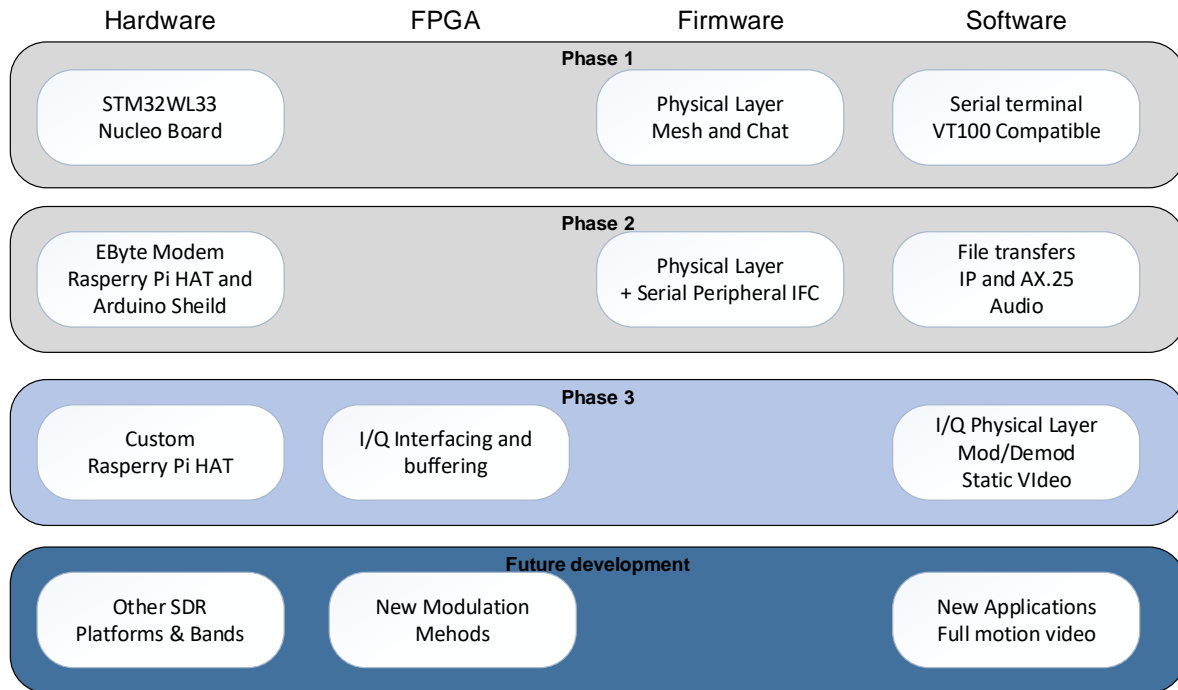


Figure 1 IP400 Node Development Roadmap

There are four phases of development for the IP400 node:

- Phase 1 is the initial evaluation phase using the Nucleo board and a simple chat application and is purely a firmware exercise. Using the PuTTY application, a connection can be made to the USART on the board. The software will implement a basic frame transmitter and receiver and be able to build a mesh table and repeat frames. The firmware can only be loaded using the ST integrated development environment (IDE) [4] and an integrated STLINK Debugger.
- Phase 2 utilizes an off the shelf module to support an integrated HAT for the raspberry Pi platform, or an Arduino shield. The firmware will be upgraded to include a high speed SPI, plus a downloader will be developed to alleviate the absolute requirement for the IDE, but support for an external STLINK debugger has been provided, so the IDE can also be utilized as an option. New applications on the Pi can be developed for audio, file transfers, AX.25 and encapsulated IP.
- Phase 3 will introduce new custom hardware and FPGA-based signal processing for higher modulation methods and add new applications, to be determined.
- The final phase will migrate to other bands and platforms.

Phase 1 ST Micro NUCLEO WL33CC2



Figure 2 Phase 1 Nucleo board

The module consists of two PCB's, once contains the STM32WL33 microcontroller, the second an STLink debugger with a type 'C' USB connection. To install the firmware, the STM32CubeIDE must be used. Download the zip file and source code from the Github site, unzip the project, import it into the IDE, and add the source files from the IP400 directory. Compile the code and run it using the IDE downloader.

Start a PuTTY session in serial mode to the first COM port on the debugger, set it to 115200 bits/sec and DEC VT100 emulation mode. This can remain in place, even when the code is restarted or the reset key on the board is hit.

The basic functionality includes a menu selection to set station or radio parameters, a mesh table builder, packet repeater, and a simple chat application.

Connecting a GPS receiver

A GPS receiver may be connected to the Nucleo using the Arduino connectors. The recommended module is the 'Ultimate GPS logging shield' from Adafruit industries [5]. The connection requires a small board modification as shown in Figure 3.

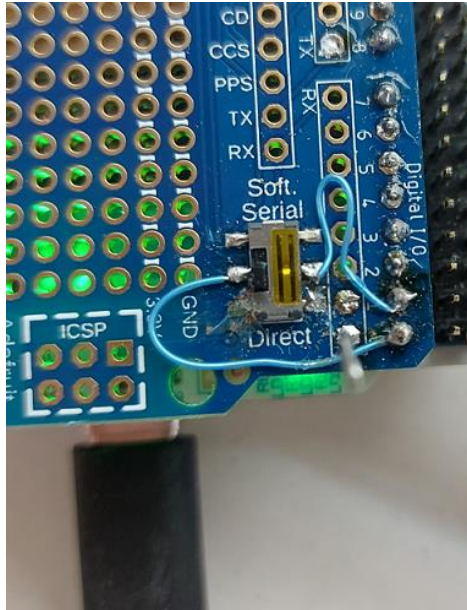


Figure 3 Adafruit GPS setup

The modification is as follows:

1. Using some soldering braid and an Exacto knife, remove the solder from both pins at the lower left hand and right hand side of the slide switch, then lift the pin or remove it completely.
2. With an ohmmeter, check there is no continuity between the left pin on the switch and the I/O pin labelled '1', and the right pin and the I/O pin labelled '0'.
3. Solder a piece of #30 Kynar wire to the centre pin on the left side, then to the pin labelled '0' on the connector, and a second wire from the right hand side to the pin labelled '1' on the connector.
4. Check continuity with an ohmmeter between the slide switch and the new pin locations.
5. Ensure that the switch is in the 'Direct' (towards the removed pins) position.

Phase 2 Raspberry Pi HAT

Figure 4 illustrates the Pi HAT in the Zero form factor.

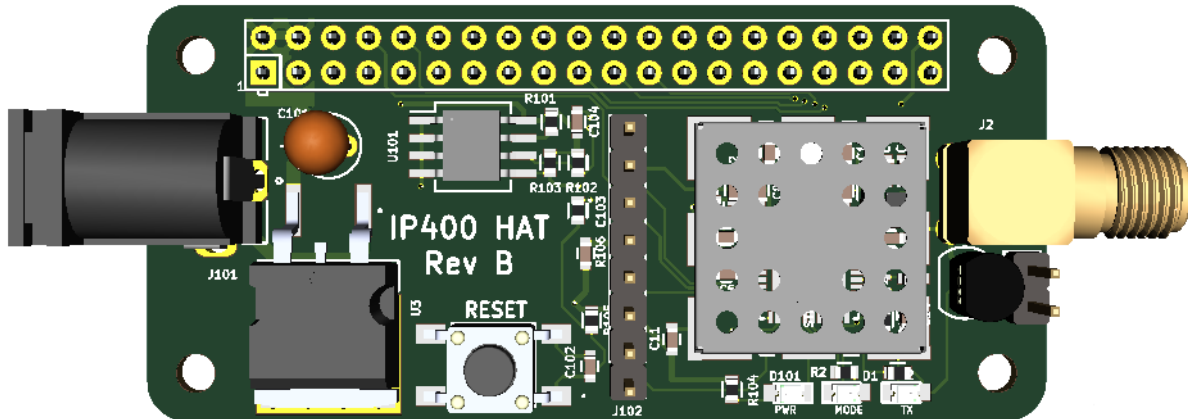


Figure 4 Raspberry Pi HAT (Zero form factor)

The Pi HAT features an EByte module that contains the same processor as the Nucleo board, but in a module form. Its basic feature set includes:

- EEPROM for Pi HAT standard identification
- STMWL33 processor with 400 MHz coupler
- PA control for external amplifier
- Switching power supply from 7-33V to power the Pi
- Reset Switch
- 3 LED's: one power, one bi-colour, and one red.
- ST Link connector with VCOM port (LPUART)
- Support for external GPS receiver
- TTYama0 connection to USART1
- SPI connection for high speed data
- Reset/Boot from the Pi.

The application code can be installed in one of two ways: using the IDE can be used with an external STLINK debugger in the same manner or copy the files to the target platform and use the makefile and bootloader to install the code.

Note: Connecting a GPS module requires Revision B or later of this module.

Connecting an ST Link Debugger or a GPS Unit

Table 3 illustrates the connections for the debugger.

Pin	Function	Debugger	GPS Receiver
1	VCP_TX	Transmit data from the LPUART	GPS receive data
2	VCP_RX	Receive data to the LPUART	GPS transmit data
3	VCC	3.3V supply	3.3V supply
4	SWCLK	Debugger serial clock	NC
5	GND	Ground	Ground
6	SWDIO	Debugger serial data	NC
7	NRST	Reset input	NC
8	NC	No connection	NC

Table 3 Connecting the STLink debugger or a GPS unit

Connecting a power amplifier

The Pi module supports a connection to a power amplifier that is buffered with an FET transistor. The signal can also be found on CN3 on the Nucleo board, but an external buffer is required. The buffered signal is grounded when active, the morpho connector is at 3.3V. Connections are shown in Table 4.

Signal	WL33 Pin	GPIO	Morpho CN3	Buffered RPi
PA Enable	PB14	21	11	J201-1
Ground		-		J201-2

Table 4 External PA connection

Migrating from Nucleo to the Pi

The same code runs on the module as on the Nucleo board, the only difference is the SPI high speed data connection. However, a Nucleo board can be connected to a RPi to offer the same functionality as the HAT board.

The connection is made using cable jumpers from CN4 on the Nucleo board's morpho connector, to the HAT connector on the raspberry Pi. The table below lists the signal name, it origin on the WL33 chip, the GPIO designation, and the pin where it can be found on the morpho, plus the corresponding pin on the Raspberry Pi HAT connector.

Signal	WL33 Pin	GPIO	Morpho CN4	RPi
SPI_MOSI	PB8	33	11	25
SPI_MOSI	PB9	34	13	19
SPI_SS	PB10	37	17	24
SPI_SCK	PB11	31	15	23

Table 5 SPI connections from Nucleo to RPi

Accessing the Menu

If you are not using the supplied image, there are three steps that need to be carried out to be able to connect to the application menu:

1. Run the configuration program 'raspi-config', and choose Interface Options, then Serial Port (I6). Turn off the login shell by answering 'no' to the first question. Enable the serial port by answering 'Yes' to the second question. Then re-boot the Pi.
2. Download and install minicom if you do not have it, with 'sudo apt-get install minicom'.
3. Launch minicom with the command 'minicom -b 115200 -D /dev/ttyAM0'.

You may also want to enable SSH access if you have an ethernet connection to the Pi and PuTTY on a remote machine.

Installing the software on the HAT

If you are not using a debugger, you can flash the code using the following method:

Starting in the home directory:

```
cd STM32Flash
make
make install
cd ..

cd IP400
./flash.sh Debug/WL_33_rPi.elf
```

Compiling the Code

Conditional Compilation

Globally used variables for conditional compilation for the are all contained in the include file config.h, Table 6 lists them and their effect on compilation.

Conditional	Value	Effect
_BOARD_TYPE	PI_BOARD	Compiles code for the raspberry pi board
	NUCLEO_BOARD	Compiles code for the Nucleo board
__ENABLE_GPS	0	Omits GPS code
	1	Includes GPS code for LPUART

Table 6 Conditional Compilation

Other modules may contain conditionals for debug purposes, which are local to that module only.

Compiling using Cube IDE

Import the correct project for your hardware platform and then add the most recent code to it. The steps are shown below.

1. Step 1: Go to the File->Import menu, then choose General->File System, then click next.
2. Step2: Using the browse button, navigate to the IP400 directory that you downloaded from GitHub. Click on the 'Src' directory.
3. Step 3: Click the box in the left pane, and make sure the "Into Folder" is pointing to your project folder, then IP400/Src.
4. Step 4: Click Finish.
5. Step5: Repeat steps 2-4 for the 'Inc' directory.

Then use the 'build project' to build it.

Compiling on the Raspberry Pi

Clone the IP400 directory from Github to ensure that you have the latest code:

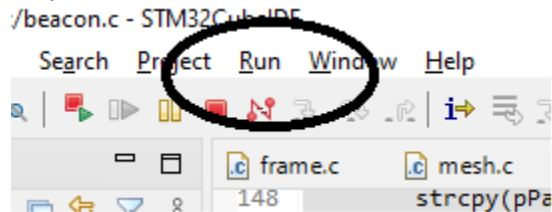
```
git clone https://github.com/adrcs/ip400/code/ip400.git
```

Then change to the main directory, and type 'make'.

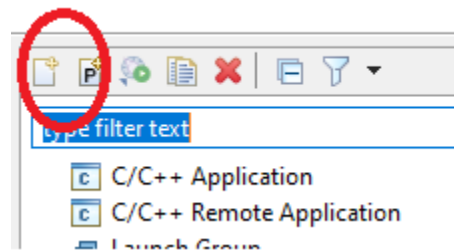
Running from the Cube IDE

There are seven steps involved in running from the IDE:

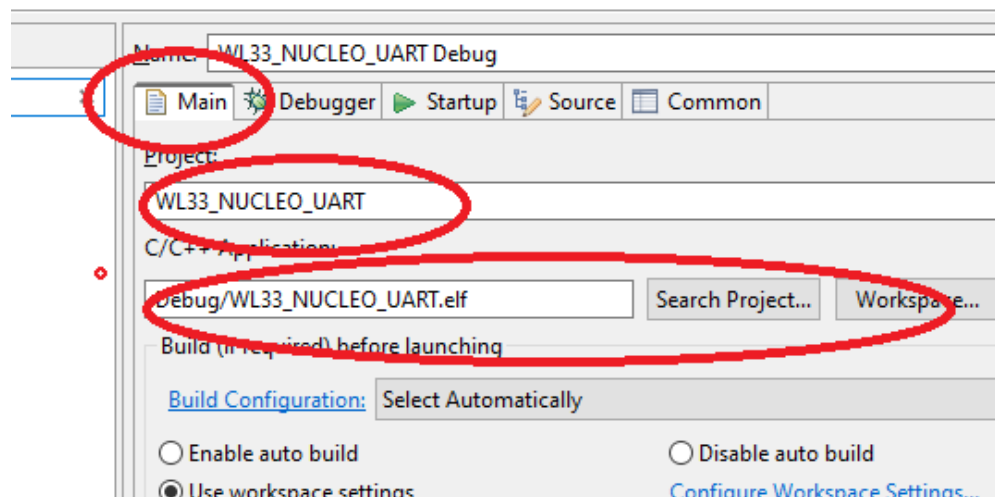
Step 1: Choose the RUN menu item, the Debug Configurations:



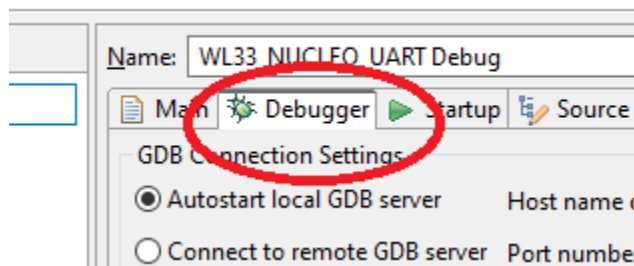
Step 2: A dialog box will launch. Click the 'new configuration' icon:



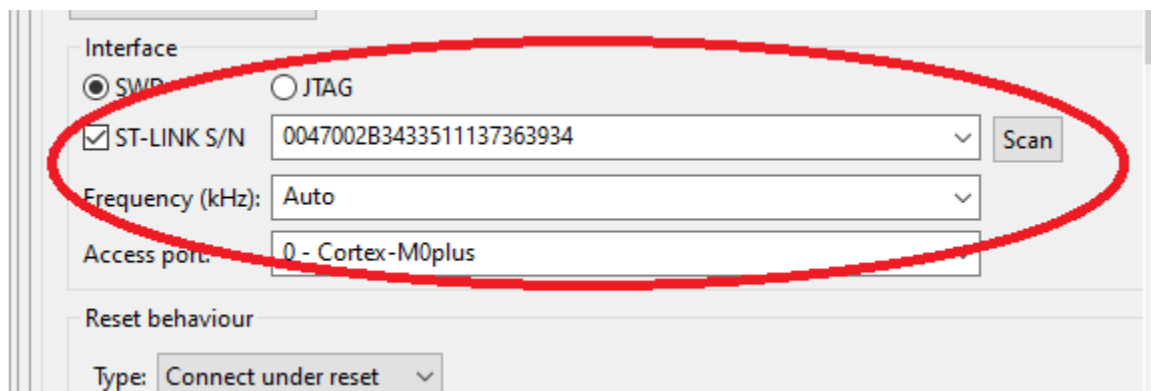
Step 3: on the Main tab, select your project and the .elf object file:



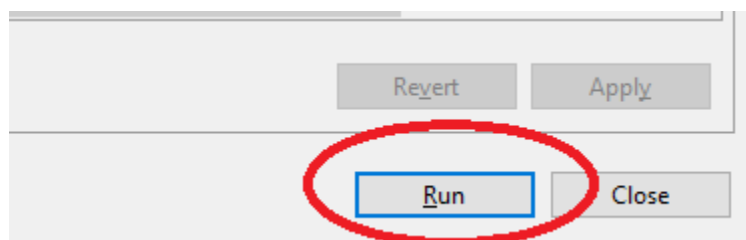
Step 4: Ensure your Nucleo is connected to your PC, then click the 'Debugger' tab.



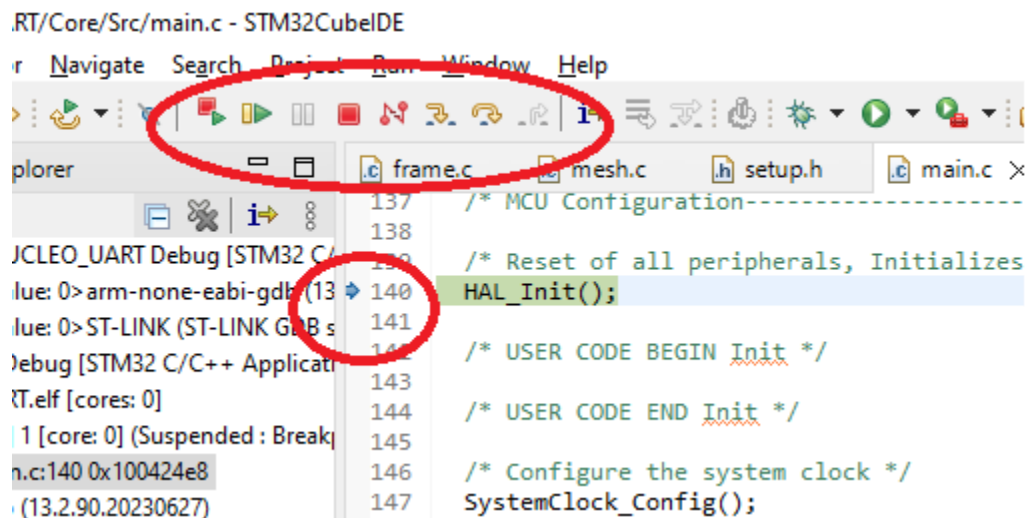
Step 5: Select the debugger tab, click the ST-LINK check box, and scan. Then the serial number of your Debugger.



Step 6: Click the 'Run' button.



Step 7: An editor will open and there will be an arrow next to the first line of executable code.



Click the green arrow to run it. The Red square will terminate it, and the combination. Will reload the code. Under the run menu you will find a restart that issues a reset to the device.

Operating the software

Main Menu

The main menu is enabled after a restart. It is shown Figure 5.

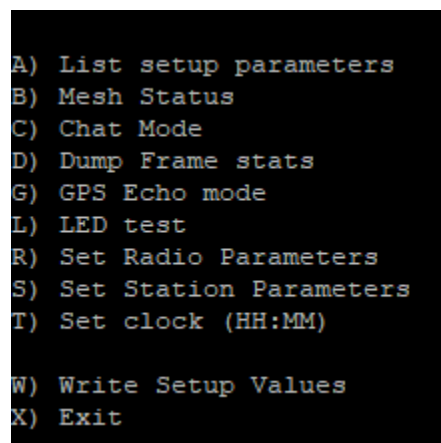


Figure 5 Main Menu

The menu items are described in Table 7.

Menu Item	Function
A	Lists the current setup parameters, including clock, station and radio
B	Displays the mesh table contents
C	Enters chat mode
D	Dumps the frame statistics
G	Dumps the NMEA sentences received from the GPS receiver ¹
L	Runs an LED test
R	Sets the radio parameters
S	Sets the station parameters
T	Sets the time of day clock
W	Writes the setup data to the flash
X	Exits the menu and puts the node in silent mode

Table 7 Main Menu Items

Most are self-explanatory, however further explanation is required.

Not

¹ Only shown when compiled with GPS code enabled

Setup Parameters

Figure 6 illustrates the setup parameters. Menu Items 'S' and 'T' set the station and radio parameters; menu item 'T' sets the time of day clock. Table 8 explains them.

```
System time is 00:02:00
Station Callsign->VE6VH
Latitude->51.08
Longitude->-114.10
Grid Square->DO21vd
Capabilities->FSK
Repeat mode on by default
Beacon Interval->5 mins

RF Frequency->445.750 MHz
Modulation method->4FSK
Data Rate->100.0 Kbps
Peak Deviation->25.0 KHz
Channel Filter Bandwidth->200.0 KHz
Output Power->14 dBm
PA Mode->TX_HP 20dBm Max
Rx Squelch->-60

Hit enter to continue->
```

Figure 6 Setup Parameters

Item	Purpose	Format
Time	Time of day clock with 10 second resolution	HH:MM
Callsign	Station callsign	Up to 6 characters ²
Latitude	Latitude, positive for N, negative for S	±xxx.xxx ³
Longitude	Longitude, positive for E, negative for W	±xxx.xxx
Grid Square	Home grid square	XXNNxx
Capabilities	Lists station operating modes	FSK or OFDM
Repeat Mode	Set the repeat flag in sent frames	On or Off
Beacon Interval	Interval between beacons, normally 5 mins	xx minutes
RF Frequency	RF operating frequency from 420 to 450 MHz	XXX.XXX or NNNNNNNNNN
Modulation	Modulation method, usually 4FSK	2FSK or 4FSK
Data Rate	Data rate 1.2 to 600Kb/s	xx.xx KHz or NNNNNN
Peak Deviation	Peak FM deviation	xx.xx KHz or NNNNNN
Channel Filter BW	BW of the receiver	xx.xx KHz or NNNNNN
Output power	Sets the transmitter power	0 to +20 dBm
Rx Squelch	Sets the receiver threshold	-30 to -130 dBm

Table 8 Setup parameters

² An extended method has been designed but not yet implemented

³ Used in beacon frames, unless a GPS receiver is connected

Channel Bandwidth Settings

The bandwidth values must be one of those listed in Table 9.

Permissible Bandwidth values (KHz)							
1600	666	266	100	41.6	16.6	6.1	2.6
1510	622	244	94.4	38.9	15.3	5.9	2.4
1422	577	222	88.9	36.1	13.9	5.5	2.2
1332	533	200	83.3	33.3	12.5	5.2	2.1
1244	488	188	77.8	30.5	11.8	4.8	1.9
1154	444	178	72.2	27.8	11.1	4.5	1.7
1066	400	166	66.7	25.0	10.4	4.1	2.6
976	377	155	61.1	23.6	9.7	3.8	
888	355	144	55.6	22.2	9.0	3.5	
800	333	133	50.0	20.8	8.3	3.1	
755	311	122	47.2	19.4	7.6	2.9	
711	288	111	44.4	18.1	6.9	2.7	

Table 9 Permissible Bandwidth Values (KHz)

Mesh Table

Figure 7 illustrates the mesh table contents, and Table 10 explains them.

```
Stations Heard: 1
Call(Port)      RSSI    Next Seq      Last Heard    Hops    Capabilities
VE6VH (1)       -12     0004         00:03:30     0       FSK_100K RPT 14 dBm
```

Figure 7 Mesh Status Table

Item	Explanation
Call(port)	Callsign of the transmitting station, and port number heard
RSSI	Receive signal strength when SYNC received (in dBm)
Next Seq	Next anticipated sequence number
Last Heard	TOD clock reading when last heard
Hops	Number of repeat hops, 0 indicates a direct signal
Capabilities	Data rate, repeat capabilities and transmitted signal strength

Table 10 Mesh Table explanation

Chat Mode

There are several control keys in the chat mode that are interpreted, as shown in Table 11.

Key	Purpose
ESC	Enables entering a new destination address, normally broadcast.
CTRL+'R'	Toggles repeat mode
CTRL+'D'	Toggles dump mode
CTRL+'Z'	Exits chat and returns to the main menu
ENTER	Sends the current frame
BACKSPACE	Deletes the last character entered, or more if repeated

Table 11 Chat mode control keys

If the 'ESC' key is hit a second time in the destination address entry, it will be reset back to a broadcast address.

Chat frames are displayed as follows:

Originating callsign(source port)>Destination Callsign(dest port)[number of repeats]:text message...
NOCALL(17)>BROADCAST(1085)[0]:hello to you...

The chat port number is always 17.

LED Test

The LED test will cycle through the patterns shown in the following table:

Test	Nucleo Board	PI HAT
1	RED Led	Bi Color Red
2	GREEN Led	Bi Color Green
3	All off	All off
4	Blue On	Tx LED On
5	All off	Tx LED Off

Table 12 LED Test Cycling

GPS Echo Mode

The NMEA sentences from the GPS receiver are dumped to the screen as shown below:

```

GNVTG,160.14,T,,M,0.23,N,0.42,K,A*
GNGGA,040907.000,5108.6054,N,11410.5759,W,1,07,1.53,1275.4,M,-17.5,M,,*
GLGSA,A,3,86,85,71,,,,,,,,,1.83,1.53,0.99*
GPGSV,4,1,14,18,73,294,36,29,50,156,22,23,42,220,26,15,40,130,29*
GPGSV,4,3,14,27,07,315,,20,05,057,,10,03,225,16,07,02,007,15*
GLGSV,3,1,11,86,75,007,33,70,53,059,,71,50,151,26,87,34,305,18*
GLGSV,3,2,11,85,32,101,22,77,21,285,,78,14,344,,72,09,183,*
GNRMC,040907.000,A,5108.6054,N,11410.5759,W,0.20,160.14,070225,,,A*
GPGSA,A,3,13,18,29,05,15,,,,,,,,,1.74,1.42,0.99*
GNRMC,040903.000,A,5108.6057,N,11410.5757,W,0.35,160.14,070225,,,A*
GNVTG,160.14,T,,M,0.35,N,0.65,K,A*
GLGSA,A,3,86,85,71,,,,,,,,,1.83,1.53,0.99*
GPGSV,4,1,14,18,73,294,36,29,50,156,22,23,42,220,26,15,40,130,29*
GPGSV,4,4,14,30,01,038,,45,,,*
GLGSV,3,1,11,86,75,007,33,70,53,059,,71,50,151,26,87,34,305,18*
GLGSV,3,3,11,76,07,243,,68,04,020,,69,01,019,*
GNRMC,040907.000,A,5108.6054,N,11410.5759,W,0.20,160.14,070225,,,A*
GPGSA,A,3,18,29,05,15,,,,,,,,,1.90,1.62,1.00*
GNRMC,040908.000,A,5108.6053,N,11410.5759,W,0.26,160.14,070225,,,A*
GNVTG,160.14,T,,M,0.20,N,0.36,K,A*
GLGSA,A,3,86,85,71,,,,,,,,,1.74,1.42,0.99*
GNVTG,160.14,T,,M,0.35,N,0.65,K,A*

```

Figure 8 GPS NMEA sentences

While this mode is active, two keys are processed:

1. Pressing the 'ESC' key will pause and prompt for the enter key to be hit before returning to the main menu. The data remains on the screen.
2. Pressing the ENTER key will clear the screen and return to the main menu.

Frame Statistics

The statistics for each frame are shown in Table 13.

Item	Meaning
Transmitted Frames	The number of frames transmitted
Good Rx Frames	The number of frames with a good CRC
CRC Errors	The number of frames with CRC errors
Rx Timouts	The number of times the receiver timed out

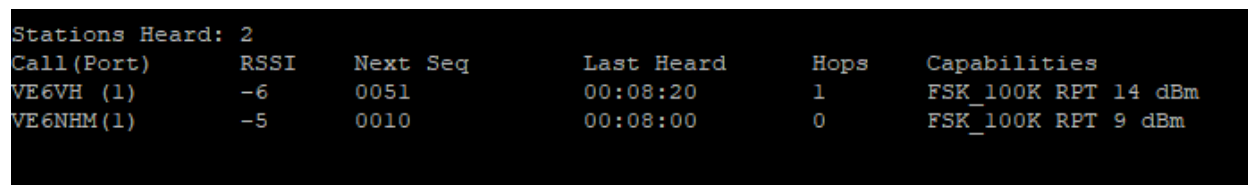
Table 13 Frame statistics

Setting the clock

The time of day is entered as HH: MM. The clock has a granularity of 10 seconds and uses 24 hour format, and knows nothing about time zones, as it considers you are in your home zone.

Mesh Table

The mesh table is built by receiving a frame from any source. If it has not previously been heard, it is added to the mesh table. The mesh table can be view from menu item B. Each entry in the mesh table is displayed as shown in Figure 9.



```
Stations Heard: 2
Call (Port)      RSSI    Next Seq      Last Heard     Hops    Capabilities
VE6VH (1)        -6      0051          00:08:20       1      FSK_100K RPT 14 dBm
VE6NHM(1)        -5      0010          00:08:00       0      FSK_100K RPT 9 dBm
```

Figure 9 Mesh Table Display

The table contents are listed in Table 14.

Field	Explanation
Call (Port)	Callsign of sending station, and port number where frame was heard
RSSI	Signal strength when sync was detected in dBm
Next Seq	Next expected sequence number from this station
Last Heard	Timestamp from the system clock when the last frame was heard
Hops	Number of times the frame was repeated, zero is direct
Capabilities	The capabilities of the station and its transmit power (into the antenna)

Table 14 Mesh table contents

The station capabilities can only be populated upon receipt of a beacon frame. If a non-beacon is received from a new station, it is added to the table without this field. If a beacon is heard subsequently, all the fields are updated. See Table 15 for details of these.

Bit	Capability	Meaning
0	FSK	Station can send 2 or 4 FSK
1	OFDM	Station is capable of OFDM transmissions
2	AREDN	Station is an AREDN node or has a path to one
3	REPEAT	Default setting of the repeat flag
4	EXT	Callsign is greater than 6 characters and has an extension
5	RATE	Maximum speed capability of the station ⁴

Table 15 Capabilities field

⁴ An explanation of these can be found in the frame layer documentation

Beacon Frames

Each station periodically sends a beacon frame that contains its capabilities and location, which is determined in the setup parameters. The beacon frame contains a series of comma-delimited fields as illustrated in

Field	Contents
Capabilities	A bitwise field containing the station capabilities
Tx Power	Transmit power in dBm
Location Source	Source for location data: FIX – fixed station data, GPS – from a GPS receiver
Latitude	Latitude in GPS format, DDD.MMM N/S
Longitude	Longitude in GPD format, DDD.MMM E/W
Fix Time	Time of fix if GPS receiver connected, otherwise omitted.
Timestamp	GPS time of fix if equipped, location data from setup otherwise
Grid Square	Home grid square from setup location data
Version number	Software version number in two ASCII characters: M.N

Table 16 Beacon Frame contents

The two types of beacon frames are shown in Figure 10.

```
VE6VH (1)>BROADCAST(0) [14:-001]:iFXD,5104.80000N,11406.00000W,000000,DO2  
VE6VH (1)>BROADCAST(0) [0:0001]:iGPS,5108.6102N,11410.5755W,164721.000,000010,DO2
```

Figure 10 Sample Beacon frames

Release Notes

V0.3b

Minor change made to the radio parameters display and entry. The frequency is now displayed as xxx.yyy and can be entered the same way. The old method of specifying it with all the digits is still supported.

Added the ability to set the clock. Format is HH:MM, 24 hours, time zone agnostic.
Granularity is 10 seconds. Current time added to setup display.

Chat mode was not changed, a reminder on how it works:

In the chat mode, to send a line of text just key it in and hit enter. Backspace removes one key at time.
CTRL+R changes the repeat flag. This flag tells a receiving station to repeat the frame. Defaults to setup.
CTRL+D: sets dump mode. When enabled, the frame header will be dumped instead of interpreted.
ESC key (only at the beginning of a line) enables entry of a destination callsign. Defaults to broadcast.
CTRL+Z. Exits chat mode and returns to the main menu.

The received frames are interpreted as:

Originating callsign(source port)>Destination Callsign(dest port)[number of repeats]:text message...
NOCALL(17)>BROADCAST(1085)[0]:hello to you...

The number of repeats is the number of times the frame has been repeated.

Beacon frames can be dumped to the console, by enabling `__DUMP_BEACON` in `frame.c`. If enabled, ensure that the receiving station is in receive mode to avoid running out of heap space.

Limited support has been added for a GPS receiver using the LPUART. It uses the DMA mode to receive a message and parses a GGA message for lat/long and a timestamp. These fields are used in the beacon frame. It is enabled by `__ENABLE_GPS` in `beacon.c`

BUGS FIXED

The beacon mode is now fully implemented. See the protocol spec for a description. Frequency is in the station setup, it can be overwritten by enabling `__SPEED_DAEMON` in `beacon.c`.

The mesh table is built using beacon frames. It lists the callsign, capabilities and last heard time.

The setup parameters can now be changed and stored in the internal flash.

NEW BUGS

The repeat mode has not yet been implemented.

A facility to set the clock needs to be added to the main menu.

The GPS code has yet to be fully tested.

V0.4

The receive frame processing was overhauled to make it consistent with the transmitter. Both now work in units of IP400_FRAMES.

The mesh table is now operational, and now contains an RSSI reading, timestamp, hop count, and capabilities of each station heard.

The repeat mode has been implemented. An inbound frame with the repeat flag set and hop count less than the maximum is repeated, providing it was not sourced by the receiving station.

The frame now contains a sequence number which is stored in the mesh table. If a frame is received with a previously known sequence, it is dropped.

The transmitted power is sent in the beacon frame to enable calculation of the path loss.

An LED manager has been added to control the LED's and provide better error indications. See the description in the documentation.

Menu changes

The current firmware and time of day clock have been moved to the list setup parameters menu item. The mesh status now lists the receive RSSI, next expected sequence number, a timestamp, number of hops, and capabilities.

The frame status now reports how frames were processed, as beacons, repeated, duplicated and dropped. It also shows the current radio errors, if any, and the current radio FSM state.

An LED test has been added, as well as a set time of day clock.

BUGS FIXED

Repeat has been implemented.

NEW BUGS

GPS code is still pending.

V0.4a

GPS code is operational, an echo mode has been added.

BUGS FIXED

A bug was found in the callsign compare, it failed on callsigns less than 6 characters.

NEW BUGS

SPI mode has not yet to been implemented, pending arrival of a working Pi board.

V0.4b

The GPS issues were fixed, and a return message has been sent back to reduce the number of messages to only a fix message.

A second escape key hit in the destination callsign field will reset it to a broadcast address.

A fix was made in the packet length to ensure that the DMA worked correctly, by rounding up to a multiple of 4 bytes.