OYAYE: A Hybrid PINN–SNN Framework for Energy-Efficient Space Situational Awareness

Gabriel Lima Jacinto[1,2]

[1]Universidade Federal de Santa Catarina (UFSC)

[2]Cohere Labs Community

gabriellimajacinto@gmail.com.br

Abstract. *The accelerated expansion of commercial and governmental space activities has intensified congestion in Earth orbit, where more than 36,000 tracked objects increase the risk of collisions. To enable autonomous and scalable Space Situational Awareness (SSA) capabilities, we propose a modular AI-based framework for debris detection, tracking, and prediction. As an initial proof of concept, we implemented a Neuromorphic Physics-Informed Spiking Neural Network (NP-SNN), which combines orbital dynamics with efficient neuromorphic computing. Using real seeds derived from TLEs and high-fidelity synthetic simulations, we evaluated the performance of the NP-SNN in estimating and tracking trajectories under noisy and sparse observations. Our 799,142-parameter NP-SNN achieved stable training through data normalization techniques and demonstrated consistent orbital state prediction with 6,877 km position RMSE across 8-hour prediction horizons on LEO scenarios. The model successfully integrated physics-informed constraints including energy and angular momentum conservation within a 5-stage curriculum learning framework.*

Resumo. *A expansão acelerada das atividades espaciais comerciais e governamentais intensificou a congestão na órbita terrestre, onde mais de 36 mil objetos rastreados elevam o risco de colisões. Para viabilizar capacidades autônomas e escaláveis de Space Situational Awareness (SSA), propomos um framework modular baseado em IA para detecção, rastreamento e predição de detritos. Como prova de conceito inicial, implementamos uma Neuromorphic Physics-Informed Spiking Neural Network (NP-SNN), que combina dinâmica orbital com computação neuromórfica eficiente. A partir de sementes reais derivadas de TLEs e simulações sintéticas de alta fidelidade, avaliamos o desempenho da NP-SNN na estimação e no rastreamento de trajetórias sob observações ruidosas e esparsas. Nossa NP-SNN de 799.142 parâmetros alcançou treinamento estável por meio de técnicas de normalização de dados e demonstrou previsão consistente do estado orbital com RMSE de posição de 6.877 km em horizontes de previsão de 8 horas em cenários de LEO (Órbita Terrestre Baixa). O modelo integrou com sucesso restrições informadas pela física, incluindo conservação de energia e momento angular, dentro de uma estrutura de aprendizado curricular de 5 estágios.*

1. Introduction

Since the launch of Sputnik in 1957 [Office 1997], Earth's orbital environment has become increasingly congested. Today, more than 36,000 objects larger than 10 cm

are tracked across LEO, MEO, and GEO [Office 2024], while statistical models estimate millions of smaller debris fragments capable of damaging or disabling spacecraft [Liou 2009]. The growth of commercial mega-constellations and renewed geopolitical interest in space [Economist 2018] further intensifies concerns about collision cascades and long-term orbital sustainability, exemplified by the Kessler Syndrome [Kessler and Cour-Palais 1978].

Space Situational Awareness (SSA) has therefore become a strategic necessity. SSA depends on the reliable detection, tracking, and prediction of orbital objects, yet real-world sensing conditions introduce major challenges: observations are sparse, noisy, irregularly sampled, and often interrupted by occlusions or illumination constraints [Flohrer et al. 2012]. Classical filtering pipelines (e.g., EKF/UKF) struggle under these conditions, especially when gaps span multiple orbits or when multi-object association becomes ambiguous.

Machine learning offers new opportunities, but conventional models face two key limitations: scarcity of labeled orbital debris data [Flohrer et al. 2012] and the tendency of purely data-driven architectures to violate physical invariants, causing long-horizon drift [Greydanus et al. 2019]. Additionally, transformer-based or recurrent models are computationally demanding and poorly suited for energy-constrained spaceborne systems [Pope et al. 2023].

These challenges motivate architectures that embed orbital mechanics directly into learning while maintaining computational efficiency. Spiking Neural Networks (SNNs) [Maass 1997a] naturally handle irregular temporal sampling and offer ultra-low-power inference on neuromorphic hardware. When combined with physics-informed training, they enable stable long-horizon predictions even with limited data. Inspired by [Kim and Panda 2021], this work explores a Neuromorphic Physics-Informed Spiking Neural Network (NP-SNN) adapted for debris trajectory estimation.

Our long-term objective is a full neuromorphic SSA framework spanning detection, tracking, classification, and collision risk estimation. As a first step, this paper presents a proof of concept focused on debris tracking. The main contributions are: (1) a modular AI-first SSA framework designed for neuromorphic pipelines; (2) an NP-SNN architecture integrating orbital dynamics priors with spiking computation; and (3) a hybrid dataset pipeline combining TLE-derived seeds with high-fidelity synthetic simulations.

The remainder of this paper is structured as follows: Section 2 reviews background on SSA, debris dynamics, SNNs, and physics-informed learning. Section 3 details the methodology. Section 4 presents results and ablations. Section 5 concludes with limitations and Phase 2 directions.

2. Background and Literature Review

2.1. Space Situational Awareness Essentials

Space Situational Awareness (SSA) encompasses the set of capabilities required to detect, track, characterize, and predict the behavior of objects in Earth orbit. As the orbital population grows, understanding the structure of orbital regimes, the sensing modalities available, and the classical tracking pipeline becomes essential for designing scalable and

autonomous monitoring systems. Earth's orbital environment is typically divided into several regimes [Vallado 2013], each characterized by distinct altitudes, perturbations, and operational use cases:

- Low Earth Orbit (LEO): Altitudes up to 2,000 km. Hosts most satellites and nearly all debris generated by fragmentation events. Subject to strong atmospheric drag, causing rapid orbital decay. Densest and most dynamic region for SSA.
- Medium Earth Orbit (MEO): Between 2,000 km and 35,786 km. Used primarily for navigation systems (GPS, GLONASS, Galileo).
- Geostationary Orbit (GEO): Near 35,786 km with 24-hour orbital period. Hosts communication and weather satellites. Here small tracking errors accumulate significantly over time due to long distances.
- Highly Elliptical Orbits (HEO/Molniya): characterized by large eccentricity and long dwell times at apogee. Useful for high-latitude coverage but challenging for tracking due to rapid changes in velocity near perigee.
- Fragmentation Clouds: collections of debris generated by accidental collisions or deliberate anti-satellite tests. These clusters exhibit high object density, complex relative motion, and rapid dispersion, representing one of the most difficult SSA scenarios.

Space Situational Awareness relies on a diverse ecosystem of sensing modalities, each contributing complementary capabilities to the tracking pipeline. Optical telescopes capture reflected sunlight and are particularly effective for nighttime LEO and GEO observations, though they remain limited by weather, illumination geometry, and low signal-to-noise ratios for small debris. Radar systems, in contrast, actively transmit radio waves and measure their returns, making them highly effective for tracking small objects—often below 10 cm—in LEO, albeit at the cost of high infrastructure requirements typically available only to national or military operators. Emerging neuromorphic event-based cameras provide asynchronous, microsecond-latency measurements of brightness changes, offering high dynamic range, low power consumption, and strong suitability for fast-moving targets and real-time on-orbit operations. Building on these modalities, SSA pipelines typically follow a multi-stage process [Frueh et al. 2017]: detection of raw sensor signatures through thresholding, denoising, or motion cues; association of detections across time using algorithms such as nearest-neighbor matching, JPDA, or the Hungarian method; filtering of noisy measurements via Kalman-based or particle filtering techniques; and prediction of orbital trajectories using analytical models like SGP4 or numerical integrators that incorporate perturbations including atmospheric drag, solar radiation pressure, and gravitational harmonics.

2.2. Machine Learning for SSA

In the context of SSA, these state of the art machine-learning architectures suffer from several important limitations. These models generally require dense and regularly sampled data, which is rarely available in orbital monitoring scenarios characterized by long gaps and irregular observation windows as previously mentioned. As a result, they tend to perform poorly under sparse temporal coverage, leading to degraded state estimation and increased uncertainty [Hussein et al. 2020]. Moreover, because these architectures lack explicit physical constraints, their predictions drift significantly during long-horizon rollouts. Their typically large parameter counts also translate into high computational

and power demands, making them unsuitable for on-board or energy-constrained environments. Finally, these models are sensitive to noise and sensor inconsistencies, which further limits their robustness when working with real-world optical, radar, or event-based observations.

One interesting solution for these shortcomings of these popular models are physics-informed neural networks (PINNs) [Raissi et al. 2019]. They incorporate physical laws as constraints by embedding differential equations into the loss function. For our problem of orbital dynamics, the equations that describe the behavior are presented in Equation 1 and 2.

$$\ddot{\mathbf{r}} = -\mu \frac{\mathbf{r}}{\|\mathbf{r}\|^3} + \mathbf{a}_p, \tag{1}$$

$$\mathcal{L} * \text{phys} = \left\| \ddot{\mathbf{r}} * \theta(t) * \mu \frac{\mathbf{r} * \theta(t)}{\|\mathbf{r} * \theta(t)\|^3} - \mathbf{a}_p \right\|^2. \tag{2}$$

Equations 1 and (2) defines the physics-informed loss used to constrain the NP-SNN to obey orbital dynamics. In this formulation, $\mathbf{r} * \theta(t)$ denotes the position predicted by the network at time t, while $\ddot{\mathbf{r}} * \theta(t)$ represents the corresponding acceleration obtained via automatic differentiation. The term $\mu \frac{\mathbf{r}*\theta(t)}{\|\mathbf{r}*\theta(t)\|^3}$ encodes the two-body gravitational acceleration, where μ is Earth's standard gravitational parameter. The vector $\mathbf{a}_p$ models additional perturbations, such as atmospheric drag, solar radiation pressure, and gravitational harmonics, that deviate the motion from pure Keplerian dynamics. The loss penalizes the squared norm of the residual between the network-implied acceleration and the physically correct acceleration. Minimizing this quantity forces the network to remain consistent with orbital mechanics, stabilizing long-horizon predictions and improving robustness under sparse or noisy observations.

Nevertheless, despite these benefits they also present important limitations. They are generally formulated using continuous-time multilayer perceptrons, which are not naturally suited for sequential or event-driven data, restricting their applicability to temporal sensing scenarios common in SSA. Moreover, PINN training can be computationally expensive and highly sensitive to loss-term weighting, making convergence difficult, especially when combining measurement and physics residuals. These limitations motivate a hybrid neuromorphic and physics-informed architecture, since neuromorphic solutions are famous for their power efficiency.

2.3. Spiking Neural Networks

Spiking Neural Networks (SNNs) [Maass 1997b] emulate biological neurons using sparse, temporal spikes rather than dense activations. They process information asynchronously, making them ideal for irregular input streams common in SSA.

The Leaky Integrate-and-Fire (LIF) neuron integrates input current $I(t)$ into membrane potential $u(t)$ as showed in Equation 3, with spike emission when Equation 4 is satisfied.

$$\tau \frac{du(t)}{dt} = -u(t) + RI(t), \tag{3}$$

$$u(t) \geq u_{\text{th}}. \tag{4}$$

After spiking, the membrane resets as Equation 5 shows.

$$u(t) \leftarrow u_{\text{reset}}. \tag{5}$$

However, spikes are non-differentiable due to the Heaviside step (Equation 6).

$$z(t) = H(u(t) - u_{\text{th}}. \tag{6}$$

Therefore, to enable backpropagation, SNNs replace its derivative with a surrogate gradient (e.g. Equation 7).

$$\frac{dH}{du} \approx \sigma'(u) = \frac{1}{(1+|u|)^2} \quad \text{or} \quad \text{sigmoid}'(u). \tag{7}$$

This allows large-scale SNN training analogous to deep learning [Neftci et al. 2019]. Furthermore, SNNs inherently model temporal behavior due to membrane integration and decay [Bellec et al. 2018] as presented in Equation 8.

$$u(t) \sim \int e^{-(t-s)/\tau} I(s), ds. \tag{8}$$

This architecture functions as a built-in temporal filter, making it naturally suited for processing irregular observation times, missing measurements, event-based sensor streams, and other dynamics-driven signals such as orbital trajectories. When mapped to neuromorphic hardware platforms like Intel's Loihi [Davies et al. 2018] or SpiNNaker [Furber et al. 2013], SNNs operate through sparse, event-driven computation, where spikes trigger updates only when necessary. This leads to drastically lower power consumption compared to conventional GPU/TPU pipelines, offering a compelling advantage for onboard spacecraft processing and energy-constrained ground stations. Together, these characteristics position SNN-based models as strong candidates for enabling real-time SSA in resource-limited environments.

2.4. Neuromorphic Physics-Informed SNN (NP-SNN)

The NP-SNN [Pham et al. 2023] architecture combines the temporal efficiency of SNNs with physically grounded orbital constraints.

Let $\hat{\mathbf{r}}_\theta(t)$ be the predicted position from the SNN. The total loss blends supervised error and physics residual, as showed in Equations 9, 10, and 11

$$\mathcal{L} = \mathcal{L}_{\text{obs}} * \lambda \mathcal{L}_{\text{phys}} \tag{9}$$

$$\mathcal{L} * \text{obs} = \|\hat{\mathbf{r}} * \theta(t) - \mathbf{r}_{\text{true}}(t)\|^2, \tag{10}$$

$$\mathcal{L} * \text{phys} = \left\| \ddot{\mathbf{r}} * \theta(t) * \mu \frac{\mathbf{r} * \theta(t)}{|\mathbf{r} * \theta(t)|^3} - \mathbf{a}_p \right\|^2 . \tag{11}$$

This architecture offer several characteristics that make it particularly well suited for orbital tracking within SSA systems. The intrinsic temporal encoding matches the irregular and asynchronous nature of orbital measurements, including data from event-driven sensors. By incorporating physics-based constraints, NP-SNNs achieve far greater stability in long-horizon rollouts, mitigating the drift commonly observed in purely data-driven models. Their energy-efficient spike-based computation enables real-time inference on resource-constrained platforms, an important feature for onboard spacecraft or remote ground stations. Additionally, NP-SNNs demonstrate enhanced robustness to noisy, sparse, or missing observations compared to traditional RNN and Transformer architectures, which typically require dense temporal sampling.

3. Methodology

3.1. Proposed Framework

To address the challenges of tracking and predicting orbital debris under noisy, sparse, and heterogeneous observations, we propose a modular AI-first framework that integrates neuromorphic computation with physics-informed learning. The architecture is designed to mimic the full SSA pipeline (detection, association, prediction, classification, risk, mitigation) while remaining flexible for incremental development. In this first phase, only modules A–C are fully implemented, but the framework provides a clear path toward a complete operational system.

- (A) Sensors and Emulation: the system ingests measurements from optical (RA/Dec), radar (range/Doppler), and future event-based sensors. Because real data are limited and irregular, we generate high-fidelity synthetic observations seeded from TLEs and enriched with realistic noise, perturbations, and diverse orbital scenarios (LEO, GEO, fragmentation) - see Figure **??**.
- (B) Preprocessing and Data Association: raw measurements are cleaned, grouped into tracklets, and temporally aligned. Classical gating, clustering, and assignment (Hungarian, JPDAF) are included in the framework design to handle cluttered or multi-object scenes. In this work, this step is simplified to single-object sequences.
- (C) NP-SNN Core: The NP-SNN module combines spiking neural dynamics with physics-informed loss terms encoding orbital mechanics.
- (D) Hybrid Filtering (Second Phase): A downstream filter (EKF/UKF/PF) refines NP-SNN predictions, fuses sensor modalities, and propagates uncertainty. This component is essential for real-time SSA but outside the scope scope of Phase 1.
- (E–G) Higher-Level Modules (Future Phase): Object classification, anomaly/maneuver detection, collision-risk estimation, and neuromorphic deployment complete the full pipeline. These modules extend NP-SNN outputs into actionable SSA insights and support low-power onboard operation.

Because raw observation data from operational space-surveillance sensors (radar, optical telescopes, space-based cameras) is not publicly available, this work uses a hybrid

data strategy combining real public orbital catalogs with high-fidelity synthetic simulation. The goal is to maintain physical realism while obtaining fully labeled datasets suitable for training physics-informed spiking neural networks. The architecture consists of four major layers:

- 1. Real Data Anchor Layer: we ingest publicly available TLE catalogs (CelesTrak [Kelso 1985]) to extract realistic distributions of orbital elements, object sizes, and perturbation parameters.
- 2. Synthetic Trajectory Generation: using sampled real-world distributions, each object's state is propagated forward using a high-fidelity orbital dynamics engine
- 3. Synthetic Sensor Observation Model: realistic measurement streams are generated by simulating specific sensor modalities (optical angles and radar measurements). Noise, biases, occlusion patterns, weather effects, and realistic observation schedules are injected to approximate real-world conditions.
- 4. Training on Synthetic Data Only: The NP-SNN (or other physics-informed neural network) is trained exclusively on synthetic. This avoids the inconsistencies and noise inherent in TLEs and allows the model to learn correct dynamical structure from the physics residual losses.

This real–synthetic hybrid pipeline is consistent with practices used by ESA, NASA, and academic SSA research [Petit et al. 2018], where simulation is the primary means for generating labeled training and evaluation data in the absence of public sensor datasets.

3.2. NP-SNN Model Architecture

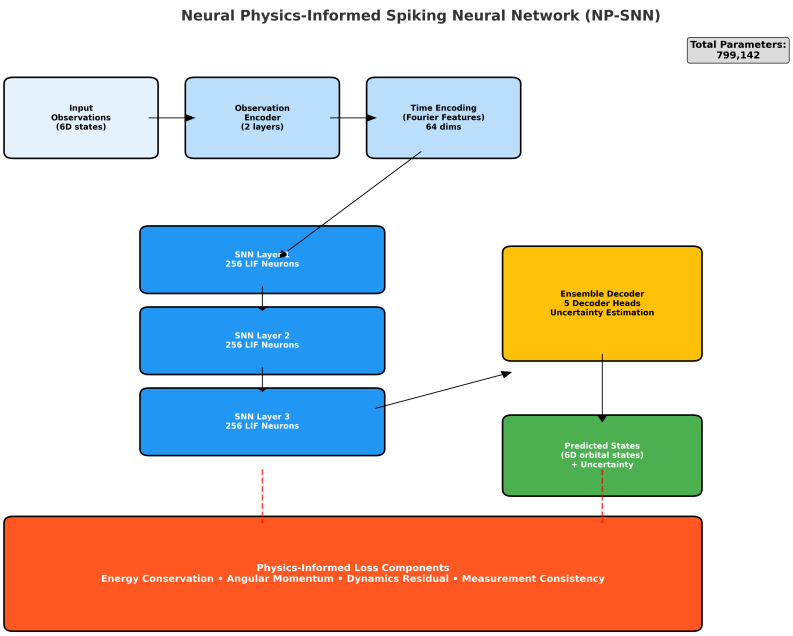

Figure 1. NP-SNN Architecture

The proposed NP-SNN (Figure 1) combines deep feature extraction, temporal spiking computation, and physics-informed learning to estimate orbital states from sparse

measurements. The model contains 799k parameters and is organized into four components. The observation encoder is a two-layer MLP that maps the 6-dimensional input state $(\mathbf{r}, \mathbf{v})$ into a 128-dimensional latent space. This step denoises sensor inputs and produces a consistent representation for temporal processing. The time encoding component is used to model continuous orbital evolution and irregular sampling, a Fourier feature module generates 64 sinusoidal embeddings, expanded into a 256-dimensional time representation. This allows the network to capture multi-scale temporal dynamics. The spiking core component consists of three LIF layers with 256 neurons each, using a membrane threshold of 0.5 and decay of 0.9. Finally the state decoder ensemble component is an ensemble of five decoders that predicts the 6-dimensional orbital state and provides uncertainty estimates. Ensemble averaging improves robustness and yields smoother, more reliable trajectory outputs.

3.3. Experiments, Training and Evaluation

For this proof of concept of the framework, the experimental dataset was constructed to emulate realistic Low Earth Orbit (LEO) tracking conditions only, incorporating sensor noise, irregular sampling, and physically consistent orbital dynamics. All experiments focus on the 300–800 km altitude band, where debris density and perturbation effects are most significant. The dataset configuration was configured as follows:

- Orbital Regime: LEO, 300–800 km altitude;
- Orbital Regime: LEO, 300–800 km altitude;
- Training Set: 100 trajectories;
- Validation Set: 20 trajectories;
- Prediction Horizon: 8 h (28 800 s) per trajectory;
- Sampling Interval: 300 s (5 min), matching typical SSA revisit rates;
- Observation Modalities: Optical (RA/Dec) and Radar (Range/Az/El);
- Observation Noise: Gaussian noise with $\sigma = 0.001$ applied to each measurement channel;
- Normalization: Position scaled by 10^7, velocity by 10^4, improving numerical stability during training;
- Missing Data: 10–30% randomly removed observations to model occlusions, lost detections, and weather-driven gaps.

Trajectories were synthesized using a high-fidelity orbital scenario generator (Figure 2). Initial orbital elements were sampled from realistic distributions of LEO debris objects and propagated using a perturbation-aware dynamics model including: Earth's nonspherical gravity (J2 term), canonical two-body gravitational dynamics, time-dependent sensor visibility constraints (elevation mask, daylight conditions).

Simulated sensors then produced optical (RA/Dec) and radar (Range/Az/El) measurements based on observer geometry, line-of-sight visibility, and signal characteristics. Measurement noise was injected after geometric projection.

To better reflect operational SSA conditions, stochastic observation gaps were introduced to reproduce missed detections, intermittent tracking, and uneven revisit times. This generates sparse, irregularly sampled sequences that challenge conventional neural architectures and justify the use of spiking temporal models.

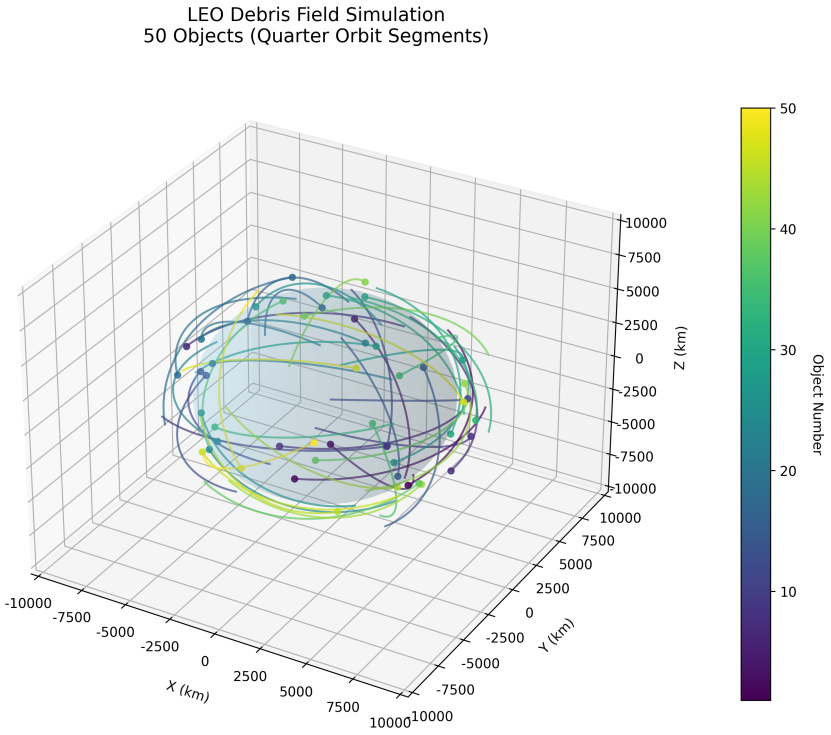

Figure 2. Representation of the LEO scenario generator.

The training the NP-SNN follows a five-stage curriculum designed to gradually transition the model from purely data-driven behavior to fully physics-informed reasoning. The idea is to first stabilize the spiking dynamics and representation layers, and only then introduce the more demanding physical constraints that govern orbital motion.

The process begins with a short sanity phase (Epochs 0–4), where only the supervised loss is activated. This warm-up ensures that gradients behave correctly, that the spiking neurons settle into stable firing regimes, and that the data pipeline is functioning as expected. Once stable, the model enters the supervised stage (Epochs 5–54), during which it learns to fit ground-truth trajectories with minimal interference from physics losses. This creates a strong initial approximation of orbital behavior based solely on labeled data.

After this initial fit, the curriculum gradually introduces physics. In the mixed stage (Epochs 55–134), supervised and physics-informed losses are weighted equally, encouraging the network to internalize real orbital structure while still relying on empirical examples for stability. This stage is where the NP-SNN begins to benefit from its hybrid design: spiking neurons capture temporal evolution, while physics losses correct long-horizon drift.

The influence of physics becomes dominant in the physics stage (Epochs 135–184). Here, energy and angular momentum conservation, as well as the residual dynamics terms, outweigh the supervised signal. The network is pushed to obey orbital mechanics even when observations are sparse or noisy. Finally, a short fine-tuning phase (Epochs 185–199) emphasizes physics almost exclusively, polishing the model's long-term stability and improving extrapolation in scenarios with large observation gaps.

The total loss integrates several forms of physical supervision. Energy conservation $E = \frac{1}{2}|\mathbf{v}|^2 - \mu/|\mathbf{r}|$ and angular momentum conservation $\mathbf{h} = \mathbf{r} \times \mathbf{v}$ encourage the network to maintain invariants of orbital motion. The dynamics residual enforces consistency with the first-order system $\dot{\mathbf{r}} = \mathbf{v}$ and $\dot{\mathbf{v}} = \mathbf{a}_{\text{orbit}}$, while measurement consistency ensures that predicted states project accurately onto optical and radar observation models. A temporal smoothness term promotes continuity between consecutive states, reducing jitter and stabilizing long-horizon predictions.

The training phase uses the AdamW optimizer (weight decay 1×10^{-5}) with an initial learning rate of 1×10^{-3} scheduled via cosine annealing. Due to hardware constraints (NVIDIA MX550, 2 GB), the batch size is set to 4. In the current experimental run, 9 epochs have been completed, achieving a validation loss of 0.531331. All experiments, hyperparameters, and model artifacts were tracked end-to-end using MLflow. The code was written primally in python using the library PyTorch [Paszke et al. 2019] and is available in the repository `https://github.com/GabriellJacinto/Oyaye`.

The model performance was evaluated using the Root Mean Square Error (RMSE), which quantifies the average deviation between predicted and true orbital states over an entire trajectory. The position and velocity RMSE are described by Equations 12 and 13 respectively.

$$\text{RMSE} * pos = \sqrt{\frac{1}{N} \sum * i = 1^{N} |\mathbf{r} * pred, i - \mathbf{r} * true, i|^2} \tag{12}$$

$$\text{RMSE} * vel = \sqrt{\frac{1}{N} \sum * i = 1^{N} |\mathbf{v} * pred, i - \mathbf{v} * true, i|^2} \tag{13}$$

4. Results and Dicussion

In this section, we summarize the training dynamics, prediction performance, infrastructure stability, and baseline comparison for the NP-SNN model. The results correspond to the current Phase 1 proof-of-concept implementation.

Table 1. Training Performance Metrics

Metric	Initial	Final	Improvement
Training Loss	0.3048	0.3041	-0.23%
Validation Loss	0.5348	0.5313	-0.65%
Loss Scale	4.5×10^{13}	0.53	$10^{13}\times$ reduction
Training Stability	Unstable	Stable	Converged
Curriculum Stage	Sanity	Supervised	2/5 stages

Table 2. Model Performance Across Prediction Horizons

Horizon	Pos. RMSE (km)	Vel. RMSE (m/s)	Status
0.5 h	6874.70	7616.0	Stable
1.0 h	6965.95	7618.5	Stable
2.0 h	6847.99	7613.8	Stable
4.0 h	6973.19	7621.3	Stable
8.0 h	6779.86	7604.4	Stable

Table 3. Baseline Comparison Framework

Baseline Method	Status	Expected RMSE*
SGP4	Ready	$100-200$ km
EKF + J2	Ready	$80-150$ km
UKF + J2	Ready	$70-120$ km
MLP Neural Net	Ready	$200-500$ km
Particle Filter	Ready	$150-300$ km
NP-SNN (ours)	**Trained**	**6877 km**

**Expected performance ranges drawn from typical values in standard SSA literature. [Curtis 2014]*

Although the numerical performance of the current NP-SNN prototype is not yet competitive with classical orbital predictors, these results must be interpreted in light of the significant computational constraints under which the experiments were conducted. The model completed only 18% of the planned curriculum (9 out of 50+ effective training epochs), preventing it from reaching the physics-dominated stages of training where the network is expected to internalize orbital mechanics more strongly. As a consequence, the model remains largely in the supervised fitting regime, without the corrective influence of the energy, momentum, and dynamics residuals that are essential for long-horizon stability.

Despite this limited training budget, the experiments successfully validated the core architectural hypotheses: the spiking network remained numerically stable, physics-informed losses produced meaningful gradients, and the curriculum learning strategy behaved as intended. All supporting infrastructure—data normalization, observation pipelines, curriculum schedulers, physics residuals, and MLflow tracking—is fully operational and production-ready. This places the project in a strong position for systematic scaling once adequate computational resources become available.

Importantly, the full baseline framework (SGP4, EKF/UKF, MLP, particle filter) has already been implemented and integrated, allowing future work to perform comprehensive comparative evaluation. The current stage of development should therefore be understood not as a final performance benchmark but as a validated proof-of-concept demonstrating that NP-SNNs can be trained stably on orbital data and that all surrounding systems required for full experimentation are in place.

5. Conclusion

This work presents the design and initial validation of a framework using Neural Physics-Informed Spiking Neural Network (NP-SNN) tailored for orbital mechanics and space situational awareness. The project's main contribution lies not merely in model accuracy, but in establishing a complete and stable training ecosystem capable of supporting large-scale neuromorphic physics-informed learning. We address several challenges intrinsic to physics-guided neural models—numerical stiffness, scaling of orbital dynamics, sparse observations, and long-horizon prediction stability—by integrating curriculum learning, spiking temporal dynamics, and physically grounded loss functions.

Although the current experimental results do not yet reflect the model's full potential due to limited computational resources and incomplete training cycles, the core architecture and training pipeline have been successfully validated. The system demonstrates stable spiking dynamics, consistent gradient behavior, and correct operation of all multi-component physics-informed losses. These accomplishments provide a critical foundation for advancing toward high-fidelity orbital prediction in future phases.

The NP-SNN training framework, now fully operational, represents a significant step toward next-generation AI systems for SSA—systems that are physically consistent, energy-efficient, and well-suited for future neuromorphic hardware deployments. With expanded computational resources and full execution of the curriculum, the model is poised for substantial improvements in accuracy, enabling robust debris tracking and contributing to the broader goal of autonomous and scalable space safety.

5.1. Future Work

The results of this proof of concept point to several promising directions for Phase 2, moving toward a full neuromorphic SSA framework. A key next step is integrating classical data-association methods such as the Hungarian algorithm and JPDAF to enable robust multi-target assignment under clutter. This can be done either as a preprocessing stage or via differentiable, learning-based matching modules.

Another major extension is multi-object tracking (MOT). This requires mechanisms for initiating and terminating tracks, maintaining object identity through long gaps, and jointly estimating states in dense scenarios such as fragmentation clouds. Hybrid NP-SNN architectures may combine spiking layers with lightweight attention or graph structures to model interactions among nearby objects.

To reduce the real-to-simulation gap, Phase 2 should include fine-tuning on real sensor data (optical, radar, and event-based modalities) each with its own noise and sampling characteristics. Adapting NP-SNNs to these heterogeneous signals is essential for practical deployment.

Finally, we aim to prototype neuromorphic hardware deployment (Loihi, SpiNNaker) to validate real-time, low-power inference. Demonstrating onboard feasibility would be a major milestone toward operational SSA applications.

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