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README - ESOQ2 Algorithm

Guidance, Navigation and Controls Subsystem

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es_main_esoq2.m

Code Type: MATLAB - Script
Code author: Shashank Singh
Created on: 08/08/2020
Last modified: –/–/—-
Reviwed by: NOT YET REVIEWED!
Description:
This is the main script, which runs the ESOQ2 Algorithm. It also runs the sequential rotation function, in case the ESOQ2 fails in the given initial frame.
Formula & References:
Reference: **Chapter 5,** Fundamentals of Spacecraft Attitude Determination and Control Authors: Markley, F. Landis, Crassidis, John L.
Input parameters:
The input arguments to the function are read from the **Input** folder. Here **N** refers to the number of input stars.

1. **es_input.mat** : The contents of which are-
   - **op_bi** : ((N, 4) - Matrix) - The body-frame vectors - (X,Y,Z), of the matched stars
   - **op_ri** : ((N, 4) - Matrix) - The inertial-frame vectors - (X,Y,Z), of the corresponding matched stars
   - **N** : (Integer) - The number of stars matched by Star Matching
2. **es_epsilon.csv** : (Integer) - This is the the maximum value allowed for the for the characteristic equation. It would be used while doing iterations, using Newton Raphson method to find the maximum eigenvalue.

Output:
Writes the final estimated quaternion using ESOQ2 into **es_q_bi.csv** file in the **Output** folder.

es_esoq2_start.m

Code Type: MATLAB - Function
Code author: Shashank Singh
Created on: 08/08/2020

Last modified: –/–/—-
Reviwed by: NOT YET REVIEWED!
Description:
This is the first and common function for both the QuEST-1 and QuEST-2 Algorithms. This function calculates the **B matrix** , **z vector**, which are further used in finding the maximum eigenvalue of the K matrix. This function further calculates the **maximum eigenvalue of the K Matrix**, which is further used to calculate the final quaternion.
Formula & References:
Reference: **Chapter 5,** Fundamentals of Spacecraft Attitude Determination and Control Authors: Markley, F. Landis, Crassidis, John L.
Input parameters:
The input arguments to the function are read from the **Input** folder. Here **N** refers to the number of input stars.

1. **b_m** : ((N, 3) - Matrix) - The body-frame vectors - (X,Y,Z), of the matched stars
2. **m_r** : ((N, 3) - Matrix) - The inertial-frame vectors - (X,Y,Z), of the corresponding matched stars
3. **v_a** : ((N, 1) - Vector) - The weights of the corresponding matched stars
4. **es_epsilon.csv** : (Integer) - This is the the maximum value allowed for the for the characteristic equation. It would be used while doing iterations, using Newton Raphson method to find the maximum eigenvalue.

Output:

1. **m_B** : ((3,3) - Matrix) - The **B Matrix**
2. **v_z** : ((3,1) - Vector) - The **z vector**
3. **lam** : (Float) - The maximum eigenvalue of the K matrix.

es_esoq2_final.m

Code Type: MATLAB - Function
Code author: Shashank Singh
Created on: 08/08/2020
Last modified: –/–/—-
Reviwed by: NOT YET REVIEWED!
Description:
This is the final function for ESOQ2 Algorithm. This function calculates the **final estimated quaternion**. It also checks if **check_value** is close to zero. If **check_value** is smaller than the threshold value, then $q\_bi = [-1; -1; -1; -1]$ is returned, which indicates the main script that ESOQ2 has failed in this frame and then sequential rotation is used.
Formula & References:
Reference: **Chapter 5,** Fundamentals of Spacecraft Attitude Determination and Control Authors: Markley, F. Landis, Crassidis, John L.
Input parameters: Here **N** refers to the number of input stars.

1. **m_B** : ((3,3) - Matrix) - The **B Matrix**

2. **v_z** : ((3,1) - Vector) - The **z vector**

3. **lam** : (Float) - The maximum eigenvalue of the K matrix

4. **es_seq_error** : (Float) - The minimum allowed value of **check_value**. If **check_value** is less than this value, then sequential rotation is used.

Output:
q_bi : ((4,1) - Vector) - The final estimated quaternion, using ESOQ2.

es_esoq2_seq_rot.m

Code Type: MATLAB - Function
Code author: Shashank Singh
Created on: 08/08/2020
Last modified: –/–/—-
Reviwed by: NOT YET REVIEWED!
Description:
This function calculates the **final estimated quaternion**.This function first finds the preferred frame for sequential rotation and finds the estimated quaternion in the changed frame using ESOQ2. This quaternion is later converted to quaternion in the original initial frame. If **check_value** is again smaller than the threshold value, then a new preferred frame is found and sequential rotation is used in the new frame. This process continues for all the three frames(the three frames are, inertial frame rotated by 180 degrees about x,y,z axes) until the correct quaternion is found.
Formula & References:
Reference: **Chapter 5,** Fundamentals of Spacecraft Attitude Determination and Control Authors: Markley, F. Landis, Crassidis, John L.
Input parameters: Here **N** refers to the number of input stars.

1. **b_m** : ((N, 3) - Matrix) - The body-frame vectors - (X,Y,Z), of the matched stars

2. **m_r** : ((N, 3) - Matrix) - The inertial-frame vectors - (X,Y,Z), of the corresponding matched stars

3. **v_a** : ((N, 1) - Vector) - The weights of the corresponding matched stars

4. **epsilon** : (Float) - This is the the maximum value allowed for the for the characteristic equation. It would be used while doing iterations, using Newton Raphson method to find the maximum eigenvalue.

Output:
q_bi : ((4,1) - Vector) - The final estimated quaternion, using ESOQ2 after using sequential rotation.