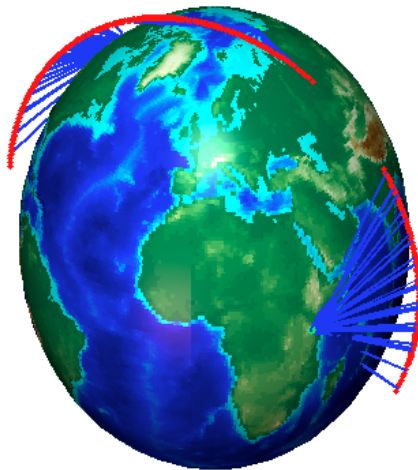


ASEN 5010 Course Project

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The essence of attitude determination is the estimation of a body's pointing relative to a known frame, given one or more observations taken in different frames. This paper will discuss the development and theoretical testing of attitude estimation algorithms for a satellite two such sensors. Numerical simulations will simulate measurements taken in various frames, and from them determine the spacecraft's attitude relative to the inertial frame. Various parameters such as measurement noise, and orbit characteristics will be examined in order to quantify their impact on performance on the attitude estimation algorithms.



Nomenclature

i	Orbit Inclination Angle
Ω	Longitude of the Ascending Node
θ	Orbit Position Angle
r	Orbit Radius
r_E	Mean Radius of the Earth
μ	Gravitational Constant
n	Mean Orbit Rate
$[XY]$	DCM Mapping Y to X Frames
$^X x$	x expressed in X frame components
<i>Left Superscript</i>	
N	Inertial Frame
B	Body Frame
T	Topographical {n,e,d} Frame

I. Introduction

The spacecraft in question for this examination is equipped only with sun and magnetic field direction sensors. Numerical simulations of measurements taken from both of these devices in the B frame, as well as the N frame. Relating measurements between frames, and ultimately providing a measure of the spacecraft's attitude, will be done with the Optimal Linear Attitude Estimation (OLAE) method. Through this numerical simulation, the affect of sensor noise, errors in the orbit parameters, and other sources of error will be examined and quantified.

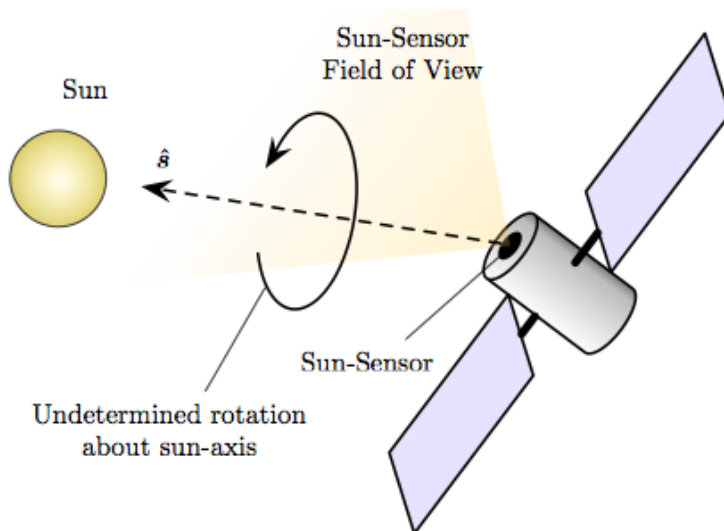


Figure 1. Satellite Sun Sensor Visual

The spacecraft itself is orbiting the Earth in a pure circular orbit, and is tumbling free of any active attitude control. The inertial frame position of the satellite is given by:

$$^N r = \begin{pmatrix} \cos \Omega \cos \theta - \sin \Omega \sin \theta \cos i \\ \sin \Omega \cos \theta + \cos \Omega \sin \theta \cos i \\ \sin \theta \sin i \end{pmatrix} \quad (1)$$

where

$$\Omega = 2^\circ$$

$$i = 75^\circ$$

For this simulation, the longitude of the ascending node is Ω , the orbit inclination is i , and θ is the orbit position angle relative to the equatorial crossing point. As the orbit is circular, its governing equation is:

$$\theta(t) = \theta_0 + nt \quad (2)$$

where n is the mean orbit rate, r is the constant orbit radius, and μ is the Earth's gravitational constant.

$$n = \sqrt{\frac{\mu}{r^3}}$$

$$r = 6878\text{km}$$

$$\mu = 398600\text{km}^3/\text{s}^2$$

The spacecraft is axially symmetric, and has the inertia tensor given in body frame components:

$${}^B I = \begin{bmatrix} 25 & 2.5 & 0.5 \\ 2.5 & 20 & 0 \\ 0.5 & 0 & 15 \end{bmatrix} \text{ kg m}^2$$

The spacecraft also is experiencing no external torques, and has initial 3-2-1 Euler angles and initial angular rates defined as:

$$\begin{bmatrix} \psi_0 \\ \theta_0 \\ \phi_0 \end{bmatrix} = \begin{bmatrix} 5^\circ \\ 10^\circ \\ -5^\circ \end{bmatrix} \quad \left| \quad {}^B \omega_0 = \begin{bmatrix} 0.4 \\ 0.3 \\ 0.2 \end{bmatrix} \text{ deg/s} \right.$$

II. Results

In this section, the development, testing, and simulation of various subprocess in the attitude determination process will be discussed. Unless otherwise mentioned, all numerical calculations, simulations, and visualizations were all performed in Matlab, and all code can be found in ??.

II.A. Part A

The first step in setting up a numerical simulation of the satellite was to obtain its position in orbit for an arbitrary time. Using EQ ??, solutions for the satellite positions were found over a ten minute period. Figure ?? shows the result of this simulation.

II.B. Part B

Next, a routine was written to take a body orientation as a set of MRPs $\sigma_{\mathbf{B}/\mathbf{N}}$, and with the known inertial sun direction vector ${}^N \hat{s} = (0, -1, 0)^T$, compute the simulated sun direction measurement in body coordinates.

This problem essentially boils down to rotating a measurement in one frame into another frame. In general, this is done by multiplying one observation by the appropriate rotation matrix.

$${}^X a = [XY]^Y x$$

Where in this case, the two frames are the body B and inertial N frames, and the vector quantity being rotated is the measured sun direction vector \hat{s} .

$${}^B \hat{s} = [BN]{}^N \hat{s}$$

In the above equation, $[BN]$ is the 3x3 rotation matrix, or DCM, which describes the three dimensional rotation between the B and N frames. In this case, this rotation is given as a set of MRPs. From lecture notes, the 3x3 DCM can be extracted from a set of MRPs through the relationship in EQ ??.

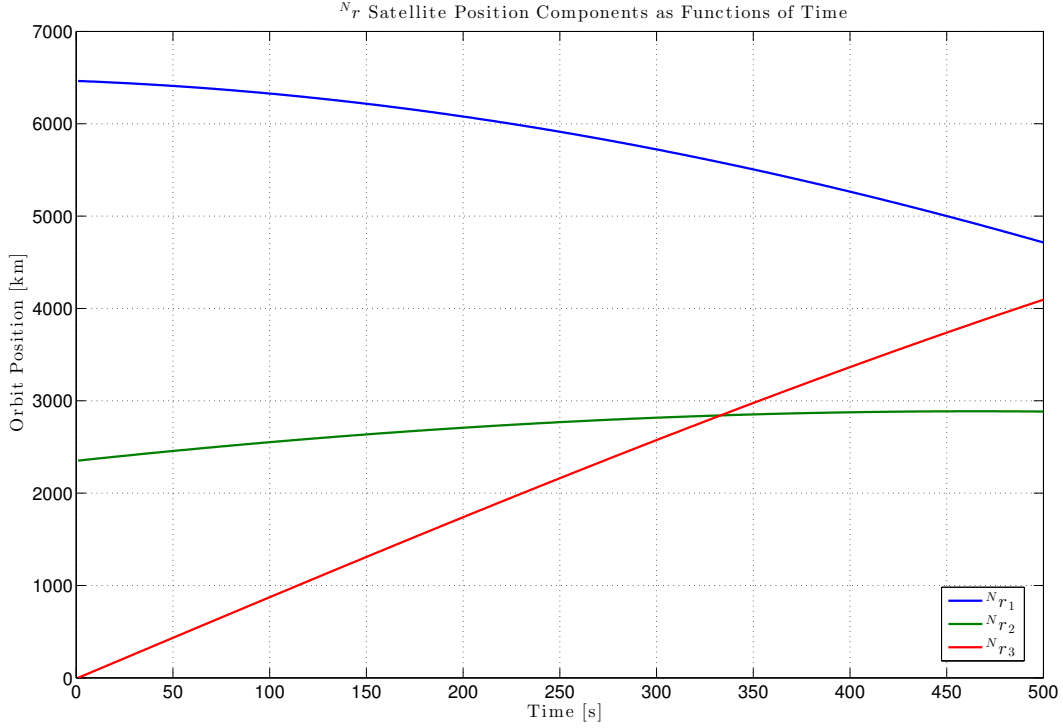


Figure 2. Orbit Position in Time

$$[BN] = [I_{3 \times 3}] + \frac{8[\tilde{\sigma}]^2 - 4(1 - \sigma^2)[\tilde{\sigma}]}{(1 + \sigma^2)^2} \quad (3)$$

This conversion was provided with the course's computational toolbox, and was implemented in Matlab here. The code for this routine is found in Appendix ??.

II.C. Part C

The frame for the satellite to be used in this simulation is a North-East-Down (NED) topographic frame τ . Another main frame of interest is the Earth-fixed frame ϵ .

$$\tau : \{\hat{n}, \hat{e}, \hat{d}\}$$

$$\epsilon : \{\hat{e}_1, \hat{e}_2, \hat{e}_3\}$$

This frame is illustrated in

In order to describe the arbitrary rotation between the two frames, a DCM was constructed. Starting at the ϵ frame, I first rotated λ about the third axis, $\hat{e}_3 = \hat{n}_3$.

$$[M_3(\lambda)] = \begin{bmatrix} \cos \lambda & \sin \lambda & 0 \\ -\sin \lambda & \cos \lambda & 0 \\ 0 & 0 & 1 \end{bmatrix} \quad (4)$$

Now, $\hat{e}'_2 = \hat{e}$. The next rotation is about \hat{e} needs to be a negative rotation of magnitude θ . However, this rotation produces a frame in which $\hat{e}''_3 = \hat{n}$. By adding another $\pi/2$ rotation to the previous, all three axes of the ϵ'' frame align with the new NED τ frame.

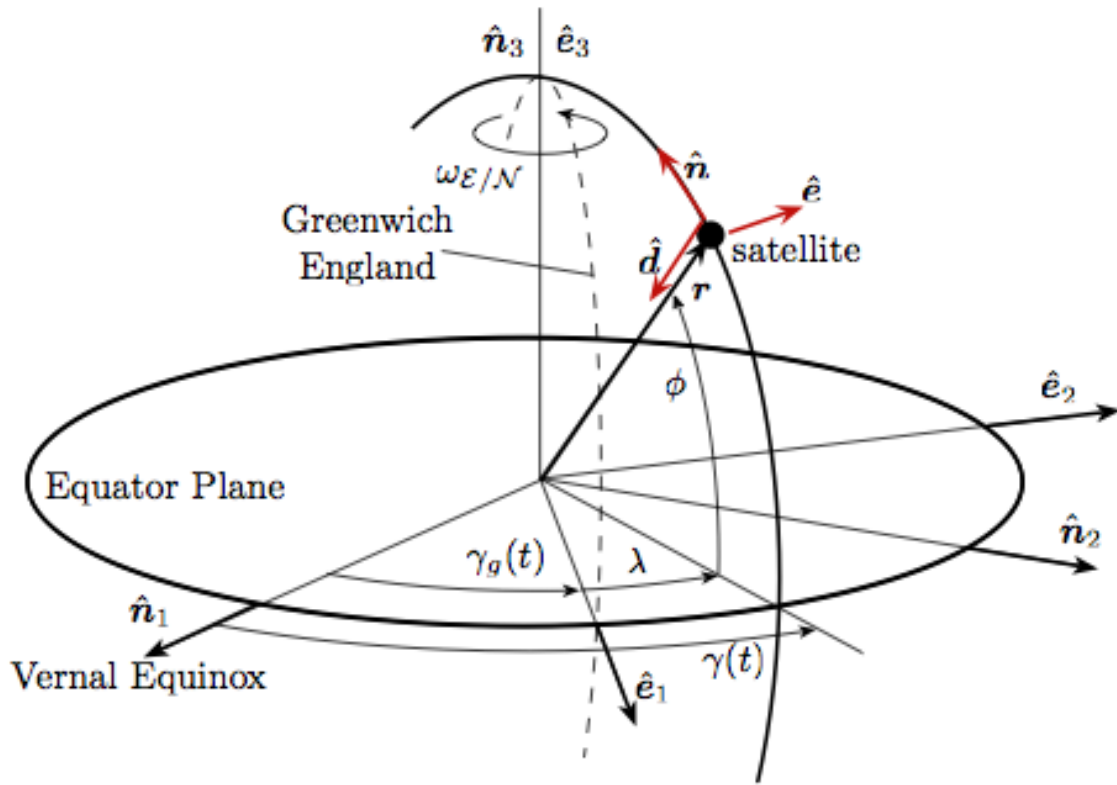


Figure 3. North East Down Frame

$$[M_2(-\phi\pi/2)] = \begin{bmatrix} \cos(-\phi\pi/2) & 0 & -\sin(-\phi\pi/2) \\ 0 & 1 & 0 \\ \sin(-\phi - \pi/2) & 0 & \cos(-\phi\pi/2) \end{bmatrix} \quad (5)$$

With no orbit inclination, these two orbit inclinations are all that are necessary to rotate the τ frame into the ϵ frame. The resulting DCM is computed by multiplying EQ ?? by EQ ??.

$$[TE] = [M_2][M_3] \quad (6)$$

II.D. Part D

Like in the previous section, another frame of interest is the earth-centered-inertial (ECI) frame. For the purpose of this exercise, the ECI frame differs from the ECEF frame by the angle γ , the Greenwich local sidereal time.

Sometimes writing meaningless text can be quiet easy, but other times one is hard pressed to keep the words flowing.^a Meanwhile back in the other world, table ?? shows a nifty comparison.

III. Conclusion

After much typing, the paper can now conclude. Four rocks were next to the channel. This caused a few standing waves during the rip that one could ride on the way in or jump on the way out.

^aAnd sometimes things get carried away in endless detail.

Table 1. Variable and Fixed Coefficient Runge-Kutta Schemes as a Function of Reynolds Number

Re	Vary	Fixed
1	868	4,271
10	422	2,736
25	252	1,374
50	151	736
100	110	387
500	85	136
1,000	77	117
5,000	81	98
10,000	82	99

IV. Appendix

IV.A. Appendix A: Code for part A

```
function r_N = computeR.N(t)
%>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>>
%                                     computeR.N.m
% Author:    Zach Dischner
% Date:      April 1, 2013
%
% Usage:
%   r_N = computeR.N(t)
%
% Description: Computes orbit position vector in inertial frame components
%              for ASEN 5010 project circular orbit
%
% Inputs: t ==> Time value array [s]. Either row or column vector
%
% Outputs: r_N ==> Orbit position in N frame components
%           | r1(t1)    r2(t1)    r3(t1) |
%           | r1(t2)    r2(t2)    r3(t2) |
%           | r1(t3)    r2(t3)    r3(t3) |
%           ...
%<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<<
%
% Orbit Parameters
Omega = deg2rad(20); % RAAN? [rad]
i     = deg2rad(75); % Orbit Inclination Angle [rad]
mu    = 398600;       % Gravatational Parameter [km^3/s^2]
r     = 6878;         % Circular Orbit Radius [km]
n     = sqrt(mu/r^3); % Mean Orbit Rate [s]
theta_0 = 0;          % Initial Angle [rad]

%% Compute r_N(t)
if ~iscolumn(t)
    t=t';
end

theta = theta_0 + n*t;

r_N = r*[ cos(Omega).*cos(theta)-sin(Omega).*sin(theta).*cos(i) , ...
        sin(Omega).*cos(theta)+cos(Omega).*sin(theta).*cos(i) , ...
        sin(theta).*sin(i)];
```

IV.B. Appendix B: Code for part B

```
function s_B = computeSunVec_B(sigma_BN)
```

An appendix, if needed, should appear before the acknowledgments. Use the 'starred' version of the `\section` commands to avoid section numbering.