

Index

- acquisition of docking axis, 22, 121–3, 154, 165, 169
- angular momentum, 35, 185, 428
- apogee raise manoeuvre, 12, 15, 37, 38
- Apollo Project, 1, 297–9
- Apollo–Soyuz Test Project, 2, 294, 299–301
- approach corridor, 4, 7, 19, 21, 23, 56, 106, 107, 142–4, 150, 154, 157, 160, 162, 167, 169, 195, 212
- Approach Ellipsoid, 17, 143–7, 149, 343
- approach recovery, 150, 151, 153, 155
- approach rules by target, 114
- approach strategy, 78, 112, 114, 116, 137, 141, 145, 146, 155, 164, 165, 223, 442
 - for Soyuz/Progress, 446
 - for Space Shuttle, 442
- approach velocity, 24, 105, 116, 140, 155, 161, 183, 352, 358, 380, 396
- atmospheric density, 81
- atmospheric drag, 64, 79–81, 83, 84, 88, 89, 105, 106, 121, 195
- attenuation device
 - closed loop controlled, 303, 321
 - concepts, 316, 318
 - eddy current damper, 319
 - friction damper, 302, 320
 - including friction, 315
 - viscous damper, 318, 319
- attenuation function
 - friction only, 310, 313
 - principle, 283, 285, 308, 312, 316
 - spring only, 309, 313
 - V-latch, 296
 - velocity proportional, 310, 314
- attenuation system
 - berthing mechanism, 291
 - central mechanism, 297, 298, 317
 - compliance, 285, 323
 - force on capture latch, 332
 - modelling, 397, 402
 - peripheral mechanism, 294, 317
 - preliminary design, 316
 - relation with contact conditions, 329
 - size, 291, 327
- attitude dynamics
 - linear, 440
 - non-linear, 438
- attitude kinematics
 - linear, 440
 - non-linear, 439
- ATV, 2, 145, 298, 455, 466
- ballistic coefficient, 81, 83–5, 88, 104, 106, 153
- bandwidth, 177, 185, 187–90, 192–5, 227, 229, 270, 280–2
- berthing, 3, 21–25, 144, 283, 452, 453
- berthing box, 7, 23, 24, 98, 109, 116, 118, 120, 144, 155, 156, 160–162, 286, 287, 290, 322
 - location, 28, 59, 105, 116, 119, 144, 455, 469

- berthing mechanism, 118, 290–2, 294, 296, 302, 304, 325–7, 469
- berthing port, 3, 120, 284, 288, 455
 - location, 28, 120
- C/A code, 255–6, 260
- CAM, *see* collision avoidance manoeuvre
- capture, 4, 24–5, 283, 306
 - by manipulator, 22, 25, 119, 286, 287, 290, 291, 322
- capture conditions
 - for berthing, 21
 - for docking, 21
- capture cone, 293
- capture function, 289, 290
- capture interfaces
 - alignment, 285, 322, 323
 - berthing, 25, 284, 287, 290, 291
 - docking, 3, 25, 284, 317
 - location, 112, 116
- capture latch, 21, 22, 24, 285, 286
 - active, 302, 318, 321, 323–5, 329
 - electro-magnetic, 303, 324
 - modelling, 397, 402
 - opening for departure, 332
 - operation, 285
 - passive, 301, 318, 321–4
 - V-latch, 296
- capture location berthing, 116, 118, 144, 160, 289, 290
- capture mechanism
 - berthing, 303, 322, 326, 327
 - central, 293, 298, 299, 322, 323
 - docking, 322
 - peripheral, 293, 300–2, 323, 324
- capture range, 285, 288
 - berthing, 120, 291, 325
 - docking, 323, 329
- capture strategy, 302, 315, 321–3, 327, 329
 - initiation of, 287
 - relation with GNC, 226, 289
 - relation with illumination, 127, 132
 - time constraints
 - berthing, 226, 287, 303
 - docking, 290, 308, 314, 315
 - velocity after capture, 307
- catastrophic failure, 77
- CC, *see* ground control centre
- central force, 424
- central gravity field, 424
- clock bias, 257
- Clohessy-Wiltshire equations, 178, 370, 430
- collision avoidance manoeuvre, 4, 23, 27, 79, 98, 107
 - berthing box, 162
 - during Hohmann transfer, 102, 150, 160
 - inertially pointing target, 123, 168, 170
 - initiation of, 100
 - all parties, 341
 - by ground, 339, 341, 345, 349
 - onboard, 208
 - by target crew, 19, 351, 352
 - open loop CAM, 111
 - R-bar, 108, 109, 162–3
 - recovery after, 137, 160, 163, 343
 - during tangential transfer, 163
 - target pointing chaser, 166, 167
 - trajectory corridor, V-bar, 108, 155
- collision free trajectory, 78, 98, 101, 108
- communication links, 5, 19, 145, 148–50, 211, 264, 266, 267, 336, 339, 343, 346, 350, 353
 - availability, 354, 356, 357
 - between chaser and target, 211, 338, 351, 353
 - capacity, 354, 357, 358, 360
 - constraints, 354
 - failure, 341, 354

- communication links (*cont.*)
 - ground, 340, 353
 - interruption, 351, 354
 - reliability, 354
- communication window, 5, 104, 113, 126, 133–5, 354
- communications
 - between chaser and target, 18, 124, 145, 146, 264, 267
 - delay, 113, 353, 356, 357
 - range, 146, 147
 - with ground, 19, 133, 135, 136, 203
- Consultative Committee for Space Data Systems, CCSDS, 359
- contact, point of, 98, 317, 323
- contact conditions, 22, 76, 289, 291, 296, 309, 317
- contact ring, 300–2, 305, 318, 320–2, 324–5, 335
- contact velocity, 315, 321, 323
- contingency modes, 181, 204–6, 208
- contingency operations, 136, 137, 143, 212
- contingency situation, 5, 20, 111, 112, 127, 179
- contingency strategy, 204
- continuous targeting, 99
- control authority, 141, 340, 343
- control centre, *see* ground control centre
- control error, 79, 80, 99, 187–90, 192, 197, 200
- control hierarchy, 172, 338, 340, 343
- control zone, 142–44
 - Approach Ellipsoid, 143, 144
 - Keep-Out Zone, 143, 144
- controlled trajectories, 42, 47, 99, 149, 168, 170, 180, 181, 225
- convergence of navigation filter, 145, 147, 148, 156, 178, 209
- coordinate frames
 - body frame, 32, 178, 180
 - Earth-centred equatorial frame, 13, 30, 129
 - ecliptic frame, 129, 130
 - LVLH frame, 32, 121, 128, 164, 166, 167
 - orbital plane frame, 13, 20, 29
 - reference frames, 29
 - spacecraft attitude frame, 32, 164
 - spacecraft geometric frames, 33
 - spacecraft local orbital frame, 13, 31, 123, 128, 129, 131, 145, 427
- crew schedule, 114, 136, 137, 145, 343
- CW equations, *see* Clohessy–Wiltshire equations
- data relay satellites, 135
- demonstration in orbit, 411, 412, 414, 416–421
- departure corridor, 27, 28, 142, 144
- development life cycle, 365, 367, 368
- differential drag, 80, 84–86, 99, 103, 104, 106, 139, 140, 147, 149, 153, 159, 181
- dilution of precision, 258
- direction cosine matrix, 438, 440
- discrete control, 200, 435
- discrete time systems, 434
- docking, 3, 21, 24, 25, 144, 283, 452
- docking port, 221, 282, 328
 - location, 453, 455, 459
- docking reception range, 284, 328
 - angular range
 - entrance of interfaces, 285, 315, 322, 329
 - error allocation, 226, 227, 324
 - GNC requirements, 220, 221, 226, 282, 289, 328
 - leaving, after contact, 313, 315
- docking system
 - androgynous, 295, 296, 299, 301, 323, 331, 335

- central, 293, 297, 298, 316, 322, 323, 329, 459, 464, 466, 467
- peripheral, 293, 294, 296, 299, 301–3, 317, 318, 323–5, 331, 459, 461
- pressurised, 284, 286, 291, 292
- testing, 409, 410
- unpressurised, 284, 291, 294, 296, 297
- Doppler radar, 236, 237
- Doppler shift, 230, 234, 235, 237, 245, 258
- ecliptic, 128–30
- entry gate, 12, 16
- EPOS, 406, 407
- equations of motion, 185, 193
 - in local orbital frame, 40
 - in orbital plane frame, 34
- equinoctial points, 10
- ETS-VII, 418–20
- Euler angles, 438–39
- Euler equations, 185, 193
- failure tolerance, 77, 78
- FDIR, 171, 172, 206–8, 370
- finite pulse, 65, 68, 97
- fly-around, 19, 20, 53, 56, 70, 123, 449
- geopotential anomaly, 85
- GLONASS, 124, 251–3, 256
- GNC mode, 173–4, 179, 180, 204, 206–7, 346, 382–3, 423
- GPS, 124, 252, 256, 372, 373, 387, 395, 405, 413, 415
 - absolute, 17, 124, 126, 146, 150, 179, 218
 - differential, 251, 260–2, 415–17
 - raw data, 338, 415
 - receiver, 388, 415–17, 419
 - receiver stimulation, 164, 262, 265, 376, 377
 - relative, RGPS, 17, 19, 146, 148, 156, 160, 211, 218, 220, 251, 455
 - flight demonstration, 413, 414, 416–18, 421
 - functional principle, 260, 263
 - modelling, 373, 415
 - navigation filter, 145, 262, 264, 378, 414, 417
 - operating range, 147, 151, 264
 - testing, 376–8
 - selective availability, 124, 126
- grapple fixture, 25, 160, 286, 287, 291, 326
- grappling, 284, 286, 287, 303, 322, 325
- ground control centre, 115, 141, 142, 144, 171, 337–44, 346, 348, 350, 353, 357, 382, 384, 385
- ground station, 113, 126, 133–5
- guidance law, 181, 183, 213
- H-bar, 13, 31, 32, 43, 118, 140
- H-bar docking port, 118
- Hermes, 2, 302
- Hill equations, 40, 185, 193, 391, 393
- Hohmann transfer, 15, 16, 38, 52, 102, 145, 147, 148
- hold point, 4, 15, 18, 73, 75, 101, 116, 136–41, 145, 147–50, 155, 157, 160, 165, 166, 168
- HTV, 3, 155, 455, 468
- human operator, 5, 107, 111, 121, 126, 172, 211, 213, 214, 216
- impulsive manoeuvres
 - radial thrust manoeuvre, 20, 53, 55, 56, 104
 - tangential thrust manoeuvre, 20, 37, 38, 49, 51, 53, 65, 102, 104, 149, 165
- initial aim point, 12, 15, 16, 146–49, 155, 442, 443, 447
- Integrated Doppler count, 259

- International Space Station (ISS)
 - Programme, 2, 77, 451
- International Telecommunication
 - Union, ITU, 359
- ionospheric delay, 257
- J_2 -effect, 86, 112, 252, 390, 391, 393
- Jacobian matrix, 426
- joysticks, 215, 216, 352
- Kalman filter, 174–7, 208
- Keep-Out Zone, 143, 150, 154
- Kepler's laws, 34
- Kurs, 243, 245–50, 447, 459, 464, 466
- Laplace transformation, 186, 429
- launch window, 8, 10
- man-in-the-loop, 215
- man-machine interface, MMI, 346
- manipulator, 3, 21, 22, 142, 155
 - end-effector, 120, 160, 286, 287, 289, 322, 325, 326, 370
 - motion after capture, 120
 - operations, 137, 370
- manipulator arm, 24, 25, 45, 46,
 - 118–21, 284, 286–91, 322, 325–7, 329, 335
- manual control, 172, 197, 214, 215
- manual state update, 214, 215
- mating, 24, 112, 113, 115, 121, 144
- measurement errors, 221, 223, 256, 257
- mid-course manoeuvre, 99, 181, 182, 195, 225, 228
- MIMO control, 174, 197
- minimum impulse bit, 182, 200, 201
- mission and vehicle management,
 - MVM, 7, 171, 179, 203, 206, 208, 360, 370
- mission time-line, 206
- monitoring
 - of capture process, 128, 339
 - communication constraints, 5, 135, 136, 211, 353
 - by control centre, 5, 338
 - of final approach and mating, 113, 126, 132, 133
 - of mating process, 4, 340
 - of mission progress, 340
 - of onboard controlled manoeuvres, 149, 158, 339
 - of onboard systems, 339
 - by remote operators, 7, 113, 172, 211, 337, 344
 - by target crew operator, 136, 142, 211, 340–1, 350–1
 - of trajectory boundaries, 99–101
 - of vehicle state vector, 78, 100, 340
 - visual, constraints on ISS, 159
 - visual/video monitoring, 4, 113, 126, 127, 136, 142, 154, 217, 357
- monitoring tools, 346
 - for crew operator, 351, 352
 - for ground operator, 346–8
- multi-path, 124, 151, 242, 243, 257, 264–6, 281
- navigation errors, 79, 90, 219–21, 223, 226, 229
 - angular rate measurement, 93
 - attitude measurement, 93
 - position measurement, 91, 146, 147, 221, 222
 - velocity measurement, 92, 146, 147, 222
- navigation filter, 147, 174, 175, 178–80, 185, 194, 208–9, 214–5, 262, 264, 378, 413, 415–7, 421
- Navstar, 251–2
- Newton's law of gravitation, 34, 424
- nodes, 10, 31, 39, 86, 252
 - ascending, 10, 39

- descending, 10, 39
 - drift of, 39, 80, 86–7, 112, 114–5, 128–9, 131, 134, 252
- open loop manoeuvres, 16, 42, 90, 181
- operator display, 249, 346–8, 350–2
- orbit
 - circular, 37
 - elliptic, 35
- orbit corrections, 37
- orbit parameter
 - apogee, 10–16, 35, 37, 38, 102, 103, 160, 164–6
 - eccentricity, 16, 35, 38, 39, 53, 87, 88, 137
 - inclination, 10, 12, 16, 19, 31, 39, 57, 87, 88, 115, 128, 129, 131, 252, 253
 - perigee, 10–14, 16, 35, 37, 38, 102–4, 164–5
 - RAAN, 10, 12, 16, 19, 31, 39, 57, 80, 86, 115, 129, 131, 252
 - true anomaly, 10, 35
- orbital disturbances, 79
 - atmospheric drag, 81
 - differential drag, 81, 85
 - geopotential anomaly, 85
 - solar pressure, 87
 - thruster plume interaction, 89
- orbital plane, 9, 11, 252
 - corrections, 12, 39, 56
- out-of-plane errors, 19, 56, 149
- packet telemetry, 355–57, 360
- perigee raise manoeuvre, 11, 12, 15, 37, 38
- phase angle, 12
- phase/mode management, 203–6
- phasing strategy, 14
- Principal axis, 439
- PRN code, 252, 255, 256
- Progress, 215, 216, 298, 320, 331, 332, 352, 446, 455, 459, 464
- project phases, 367, 368
 - definition phase, 367, 370, 387, 399
 - design phase, 367, 371, 372
 - development phase, 363, 367, 369, 375, 381
 - manufacturing phase, 367, 385, 386
 - operational phase, 364, 367–9
- pseudo-range, 254, 256
- pulse width modulation, 182, 200
- R-bar, 13, 32
 - acquisition, 20
 - approach, 61, 62, 116, 119, 155, 181, 444–6, 449
 - departure strategy, 28
- radar, 17, 232–34, 236, 238
- relative attitude, 21, 121
 - choice of sensor type, 281, 282
 - control of, 170, 197
 - by manual state update, 215
 - GNC mode for relative attitude, 145
 - large angles, 122
 - measurement, 179
 - accuracy, 229
 - by camera sensor, 272–3, 276–7, 281
 - by human operator, 217
 - by Kurs system, 245–50
 - by laser range finder, 270, 271, 280
 - principles of, 230
 - by RF-sensors, 238, 240–2, 244
 - need for data on, 23, 122, 220
- relative dynamics
 - discrete time state space, 434
 - homogeneous solution, 430, 431
 - linear, 428, 429
 - non-linear, 426
 - particular solution, 431, 434
 - transition matrix, 431
 - travelling ellipse, 435
 - state space formulation, 431

- relative navigation, 17, 40, 144, 146, 178, 179, 204, 218, 219, 227, 251, 260, 261, 264, 266, 267, 353
- relative position vector, 424
- relay satellite
 - Luch, 135
 - TDRS, 135, 418
- remote control, 212, 341
- remote operator, 107, 111, 113, 172, 213, 216, 336, 337, 340, 344, 346, 353
- rendezvous control software, 369, 371, 372, 375, 379, 383, 384, 386, 394, 395, 404, 407, 419
- rendezvous orbit
 - GEO, 80
 - LEO, 80
- rendezvous sensors, 173, 179, 195, 208, 214
 - camera type, 144, 164, 168, 169, 267, 272, 274–8, 280–2, 467
 - field of view, 125, 169, 269–6, 278, 280, 281
 - Kurs, 243, 245, 459, 464, 466
 - laser range finder, 267–71, 278–82, 467, 470
 - measurement environment, 173, 185, 187, 191, 219, 242, 259, 264, 277, 379
 - modelling, 372, 373, 376, 377, 387, 389, 393, 395, 401, 403
 - stimulation, 375, 376, 378, 403, 406
- operational range, 124
- optical, 121, 124–6, 144, 244, 267, 272, 277, 279, 281, 461
- radar, 124, 144, 243, 461
- relative GPS, 124, 126, 144, 151, 156, 211, 218, 260, 262–4, 467, 470
- sensor modelling, 372, 393–5
 - target pattern, 269–72, 274–82, 455
- retreat to hold point, 141
- role of target in RVD process, 114
- rotation of line of apsides, 87
- RVD phases, 9
 - close range rendezvous, 19, 115, 126, 141, 165, 211, 218, 219, 343
 - closing, 19
 - departure, 26
 - far range rendezvous, 17, 87, 126, 141, 146, 218, 219
 - final approach, 21, 126, 150
 - homing, 17
 - mating, 24
 - phasing, 12, 13, 87, 126, 146
 - ranges of approach phases, 126
- safe trajectory, 98, 153
 - safety ellipse, 139
- safety of human life, 77
- safety zone, 4, 114
- sampling time, 434
- satellite navigation, 218, 244, 250
 - Galileo, 253
 - GLONASS, 251
 - GPS, 251
 - ground segment, 253
 - measurement environment, 257, 259, 264
 - modelling of, 393
 - navigation satellites, 254
 - constellation, 251–53
 - new constellations, 253
 - position finding principle, 257
 - user segment, 254
- sensitivity function, 190, 191
- simulation
 - of communication links, 384
 - of contact/capture dynamics, 371
 - ‘all-software’, 381
 - modelling, 396

- non-real time, 374
- test facility, 380
- distributed interactive, 384, 385
- of GNC system
 - algorithms, 371
 - 'all-software', 372, 373, 377, 379
 - environment, 371, 381, 388, 398
 - Monte Carlo runs, 379, 384
 - navigation hardware in the loop, 377, 378
 - non-real time, 372, 384
 - with onboard computer, 375, 376, 383, 384, 386
 - real time, 381–4, 386
 - test facility, GNC, 404, 405, 407
- of GPS satellite constellation, 378
- of sensor measurement environment, 401
- of trajectory dynamics, 370
- SISO control, 173
- soft failures, 210, 211
- solar pressure, 79, 87
- Soyuz, 1, 3, 144, 215, 298, 320, 331, 332, 351, 446, 455, 459, 462
- Space Frequency Coordination Group, SFCG, 359
- Space Shuttle, 2, 144, 243, 325, 416, 443, 455, 459–61
- space station, 46, 77, 83, 142, 144, 338, 340, 341, 350
 - ISS, 2, 77, 114, 143–5, 265, 343, 344, 350–2, 355, 451–3
- Mir, 1, 123, 135, 265, 288, 298, 301, 351, 355, 416, 442, 449, 451, 457–60
- MTFF, Columbus Free Flyer, 2, 302
- Salyut, 1, 135, 298
- Skylab, 1
- space station scenario, 338
- spacecraft security, 77
- state vector, 78, 79, 90, 99, 100, 107, 142, 171, 174–81, 184, 197, 261
- station keeping, 62, 63
- stimulation
 - docking mechanism, 380, 402, 404, 408–10
 - GPS receiver, 378, 406
 - sensor, 377–79, 401, 403, 406, 407,
- structural latch, 286, 289, 298, 300–3, 329–33
- Sun illumination, 113, 124, 126, 127, 132, 154, 448
 - β -angle, 128, 129, 131, 132
 - illumination angles, 127
- Sun pointing target, 123
- supervisory control, 344, 345
- synchronisation
 - of arrival times, 115
 - of communication windows, 5, 113
 - of crew work cycles, 4, 114, 136
 - of monitoring needs, 126
 - of Sun illumination, 4, 113, 127
- Taylor series, 426
- thrust inhibit, 47–8, 116–18, 120, 153, 160–2, 351, 352
- thrust vector errors, 79, 80, 93, 146, 147, 152, 156, 159, 173, 204
 - position error factor, 94
 - thrust direction, 93, 96
 - thrust duration, 93, 94
 - velocity error factor, 95
- thruster failures, 80, 97, 203, 204, 208
 - thruster-closed, 97, 101
 - thruster-open, 96–7, 101
- thruster management, 180, 200, 214
- thruster plume effects, 23, 79, 80, 89
- time-flexible elements, 18, 20, 115, 137, 138
- torque equilibrium attitude, TEA, 123, 168
- trajectories, 73

- continuous thrust
 - circular fly-around, 70
 - straight line R-bar, 61, 105
 - straight line V-bar, 59, 105, 145, 154
 - x -thrust transfer, 64, 66
 - z -thrust transfer, 67, 69
- free drift, 41, 42
- impulsive manoeuvre, 41, 48
- parallel to target orbit, 43
- passive safety, 104
- radial boost
 - fly-around, 56
 - V-bar transfer, 55, 145, 152, 153, 158, 165, 167
- release trajectory
 - at different velocities, 47
 - release at y -distance, 45
 - release at z -distance, 44
- station keeping, 62
- tangential boost
 - fly-around, 53
 - to different altitude, 52
 - V-bar transfer, 49, 150, 152, 159
- transfer to arbitrary points, Lambert transfer, 57
- trajectory gate, 12, 16
- trajectory safety, 76, 78, 149, 151, 153–4
 - active protection, 98
 - long term, 106
 - passive protection, 98, 101
 - passive safety, 101, 105
 - safety ellipse, 138, 139
 - short term, 153
- transfer function, 184, 186–92
- transition matrix, 175, 178
 - definition, 431
- unmanned transport vehicles
 - ATV, 3, 145, 455, 466
 - HTV, 3, 155, 455, 468
 - Progress, 1, 3, 144, 446, 455, 459, 464
- utility transfer, 292
- V-bar, 13, 31
- V-bar approach, 19, 59, 60, 101, 116, 117, 119, 145, 181, 444–6, 448
 - +V-bar, 116, 449
 - V-bar, 116, 449
- V-bar departure strategy, 27
- validation, 5
 - definition, 362
 - of mathematical modelling, 398, 402
 - of measurement environment modelling, 373, 412
 - of tools, 398, 403
- velocity profile, 59–62, 154, 160, 161, 180, 183
- verification, 5
 - of contact/capture process, 366, 369, 371, 373, 379, 386
 - definition of, 362
 - of GNC/MVM functions, 366, 369, 371, 375, 386
 - methods of, 365, 366, 369, 382, 384
 - objectives of, 364, 367, 370–72, 374–5, 379
 - of operations, 381, 384
 - of operator tools, 381–3
 - in orbit, 363
 - by physical testing, 362, 363
 - by simulation, 362, 363, 370
 - in thermal vacuum, 381
 - of trajectory strategy, 370
 - using mathematical modelling, 387–93, 396
- verification facility, 404–6, 410
- verification tools, 363, 369
 - contact/capture, 371, 374, 380, 386
 - GNC, 370, 372, 375, 376, 384, 386

- vernal equinox, 10, 130
- video camera, 23, 27, 113, 132, 165,
166, 214, 351
 - for navigation, 164
- video images, 4, 113, 136, 142, 143,
214–6, 348, 351, 357
 - for navigation, 164
- video transmission, 126, 132, 136, 348,
358, 359
- virtual target plane, 11, 115
- visual target pattern, 197, 216,
217
- Z-transformation, 199, 434