

COE CST Eleventh Annual Technical Meeting

399-UCF

Efficient Uncertainty Quantification, Probability of Collision and Benchmarking

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Agenda

- Team Members
- Task Description
- Schedule
- Goals
- Results
- Conclusions and Future Work

Team Members

- People

Principal Investigator



Tarek A. Elgohary

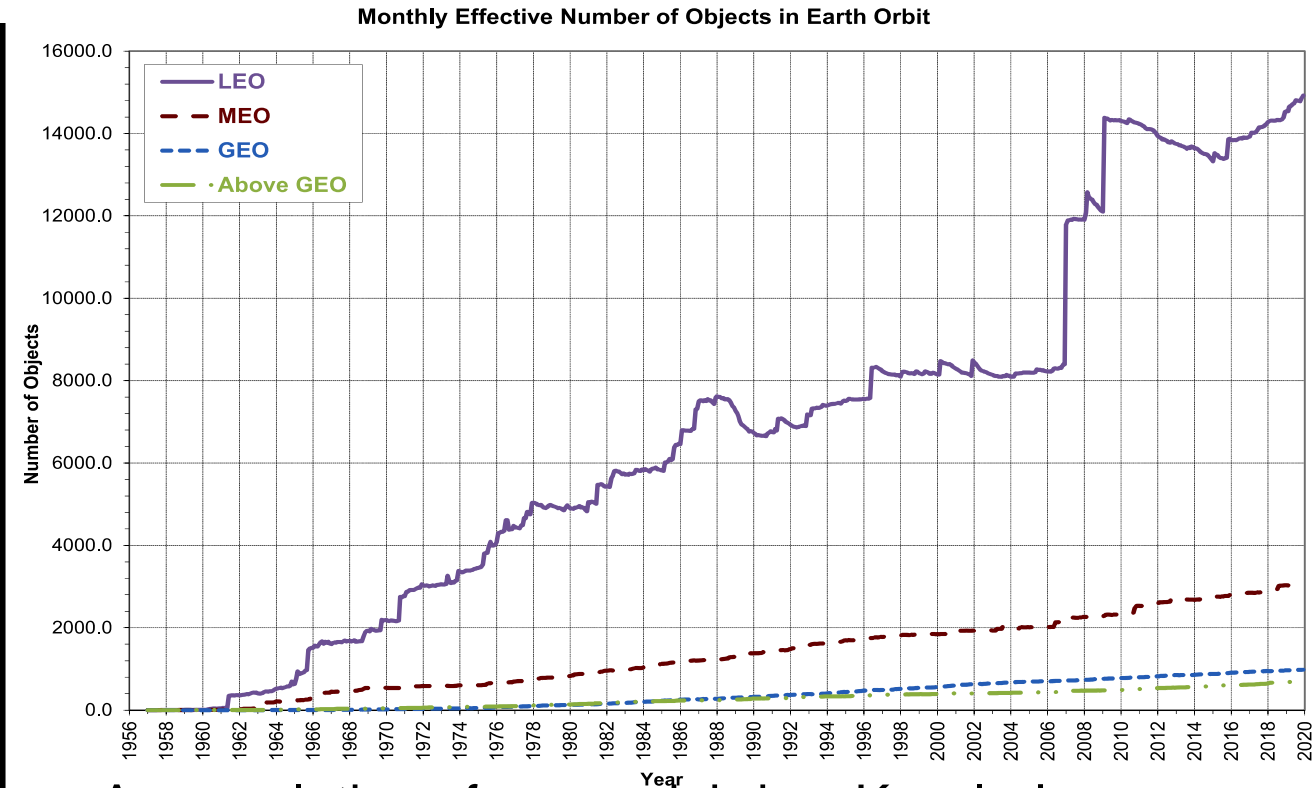
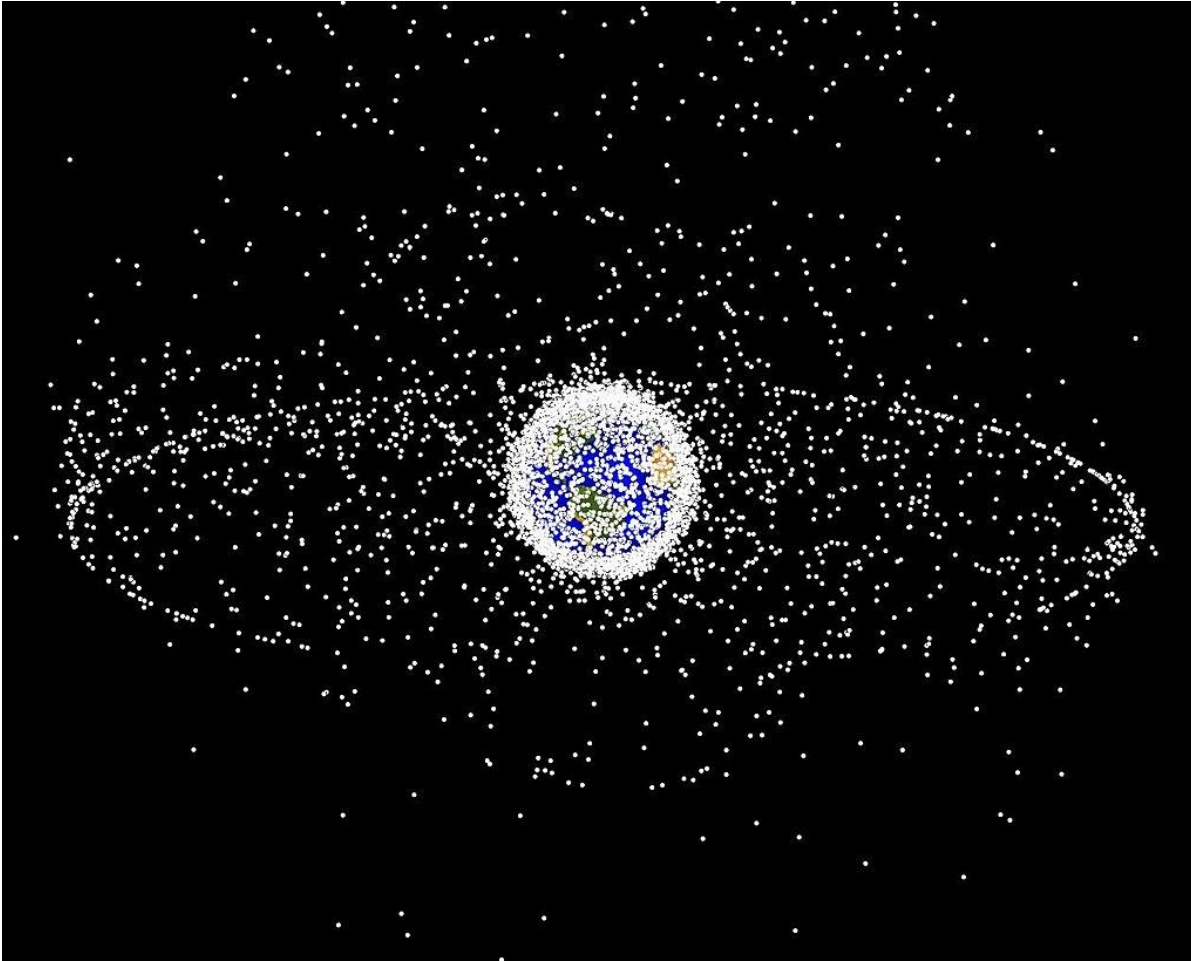
Ph.D. Student



Tahsinul Haque Tasif



Task Description



- Accumulation of space debris – Kessler’s Syndrome – Sustainability of the space environment
- More and more constellations in Earth orbit – SpaceX, OneWeb, India, China, etc.

Our Approaches for UQ

- **Probability Density Function (PDF) via Higher Order State Transition Tensors**

- Evolution of uncertainties

$$\delta x = \phi_1 \delta x_0 + \phi_2 \delta x_0 \delta x_0 + \dots$$

- Knowing the probability distribution of δx_0 , the posterior PDF is given by,

$$P_{\delta x}(\delta x) = P_{\delta x_0}(\delta x_0) \left| \det \left(\frac{\partial g^{-1}(\delta x)}{\partial (\delta x)} \right) \right|$$

- Where, $g^{-1}(\delta x)$ is the Taylor series reversion.

$$\delta x_0 = \Psi_1 \delta x + \frac{1}{2} \Psi_2 \delta x \delta x + \frac{1}{3!} \Psi_3 \delta x \delta x \delta x + \dots$$

$$\delta x'_0 = \Psi_1 + \frac{1}{2} \Psi_2 \delta x + \frac{1}{3!} \Psi_3 \delta x \delta x + \dots$$

$$P_{\delta x}(\delta x) = P_{\delta x_0}(\delta x_0) |\det (\delta x'_0)|$$

Analytic Continuation Technique

- Analytic Continuation is an integration method applied to solve fundamental problems in Astrodynamics.
- This method has been proven to be highly precise and computationally efficient in orbit propagation.
- The full spherical harmonics gravity model and atmospheric drag model were also incorporated with Analytic Continuation method.

$$f = \mathbf{r} \cdot \mathbf{r} \text{ and } g_p = f^{-\frac{p}{2}}$$
$$\mathbf{r}_0^{(2)} = -\mu \frac{\mathbf{r}_0}{(\mathbf{r}_0 \cdot \mathbf{r}_0)^{3/2}} = -\mu \mathbf{r}_0 f^{-\frac{3}{2}} = -\mu \mathbf{r}_0 g_3$$

Analytic Continuation - State Variables

- Taylor series expansion to obtain position and velocity:

$$\mathbf{r}(t_0 + dT) = \mathbf{r}_0 + \sum_{m=1}^n \mathbf{r}_0^{(m)} \frac{dT^{(m)}}{m!}$$

$$\mathbf{r}^{(1)}(t_0 + dT) = \mathbf{r}_0^{(1)} + \sum_{m=2}^n \mathbf{r}_0^{(m)} \frac{dT^{(m-1)}}{(m-1)!}$$

- The recursive equations to calculate $\mathbf{r}_0^{(n)}$, $f^{(n)}$ and $g_p^{(n)}$:

$$\mathbf{r}_0^{(n+2)} = -\mu \sum_{m=0}^n \binom{n}{m} \mathbf{r}_0^{(m)} g_3^{(n-m)} \text{ and } f^{(n)} = \sum_{m=0}^n \binom{n}{m} \mathbf{r}_0^{(m)} \cdot \mathbf{r}_0^{(n-m)}$$

$$g_p^{(n+1)} = -\frac{1}{f} \left\{ \frac{p}{2} f^{(1)} g_p^{(n)} + \sum_{m=1}^n \binom{n}{m} \left(\frac{p}{2} f^{(m+1)} g_p^{(n-m)} + f^{(m)} g_p^{(n-m+1)} \right) \right\}$$

Analytic Continuation – State Transition Tensors

- Index based First and Second order State Transition Tensors:

$$\Phi_{ij}^1 = \frac{\partial \chi_i}{\partial \chi_{0j}} \text{ and } \Phi_{ijk}^2 = \frac{\partial^2 \chi_i}{\partial \chi_{0j} \partial \chi_{0k}}$$

where, χ_i is the i -th element of the state vector, $\chi = [x, y, z, \dot{x}, \dot{y}, \dot{z}]^T$.

- Taylor series expansion of the terms of the State Transition Tensors:

$$\Phi_{i=1,\dots,3,jk}^2(t + dT, t) = \frac{\partial^2 \chi_i(t+dT)}{\partial \chi_j(t) \partial \chi_k(t)} = \frac{\partial^2 \chi_i(t)}{\partial \chi_j(t) \partial \chi_k(t)} + \sum_{m=1}^n \frac{\partial^2 \chi_i^{(m)}(t)}{\partial \chi_j(t) \partial \chi_k(t)} \frac{dT^{(m)}}{(m)!}$$
$$\Phi_{i=4,\dots,6,jk}^2(t + dT, t) = \frac{\partial^2 \chi_i(t+dT)}{\partial \chi_j(t) \partial \chi_k(t)} = \frac{\partial^2 \chi_i(t)}{\partial \chi_j(t) \partial \chi_k(t)} + \sum_{m=2}^n \frac{\partial^2 \chi_i^{(m)}(t)}{\partial \chi_j(t) \partial \chi_k(t)} \frac{dT^{(m-1)}}{(m-1)!}$$

Schedule

| Task | Time Frame |
|---|--------------------|
| Develop Analytic Continuation for arbitrary order perturbed state transition tensors for accurate error propagation | Fall 2020 |
| Develop estimation framework for space-based surveillance and tracking utilizing the perturbed STM/STT. | Fall 2021 |
| Computing Probability of collisions of RSOs via two approaches + Benchmarking problems | Spring/Summer 2022 |

Goals

- Accurate and efficient approaches to quantify uncertainty and compute probability of collision for RSOs
- Benchmarking platform for other methods to provide synthetic or real cases and compare results
- Sustainability of the space environment
- Tools to predict space debris trajectories and potential hazardous events to various operators
- Accurate orbit prediction for newly deployed constellations and their potential collisions with debris and/or other RSOs.

Results

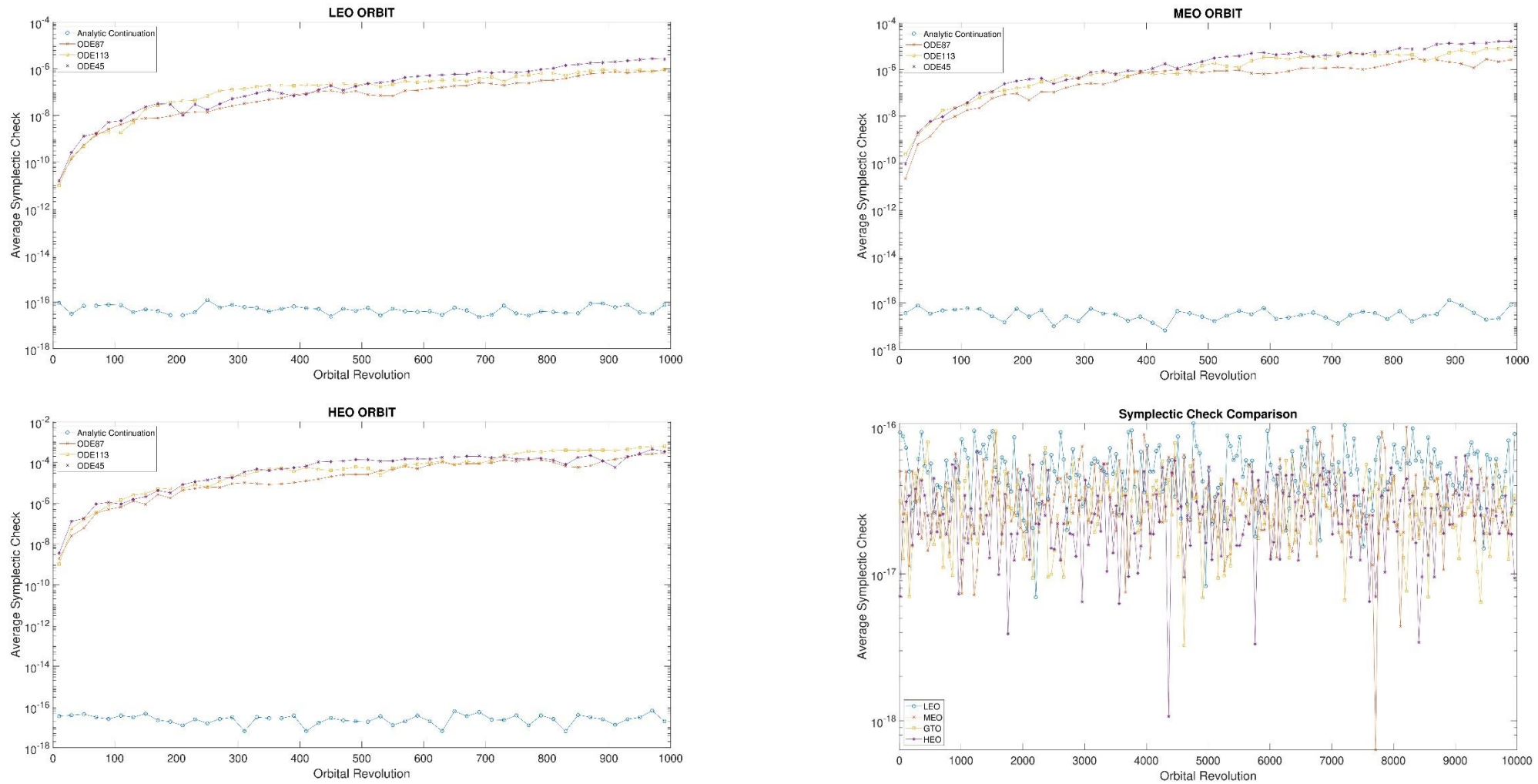


Fig: Symplectic Error in $J_2 - J_6$ gravity perturbed orbits and comparison with MATLAB ODE suite

Results (continued)

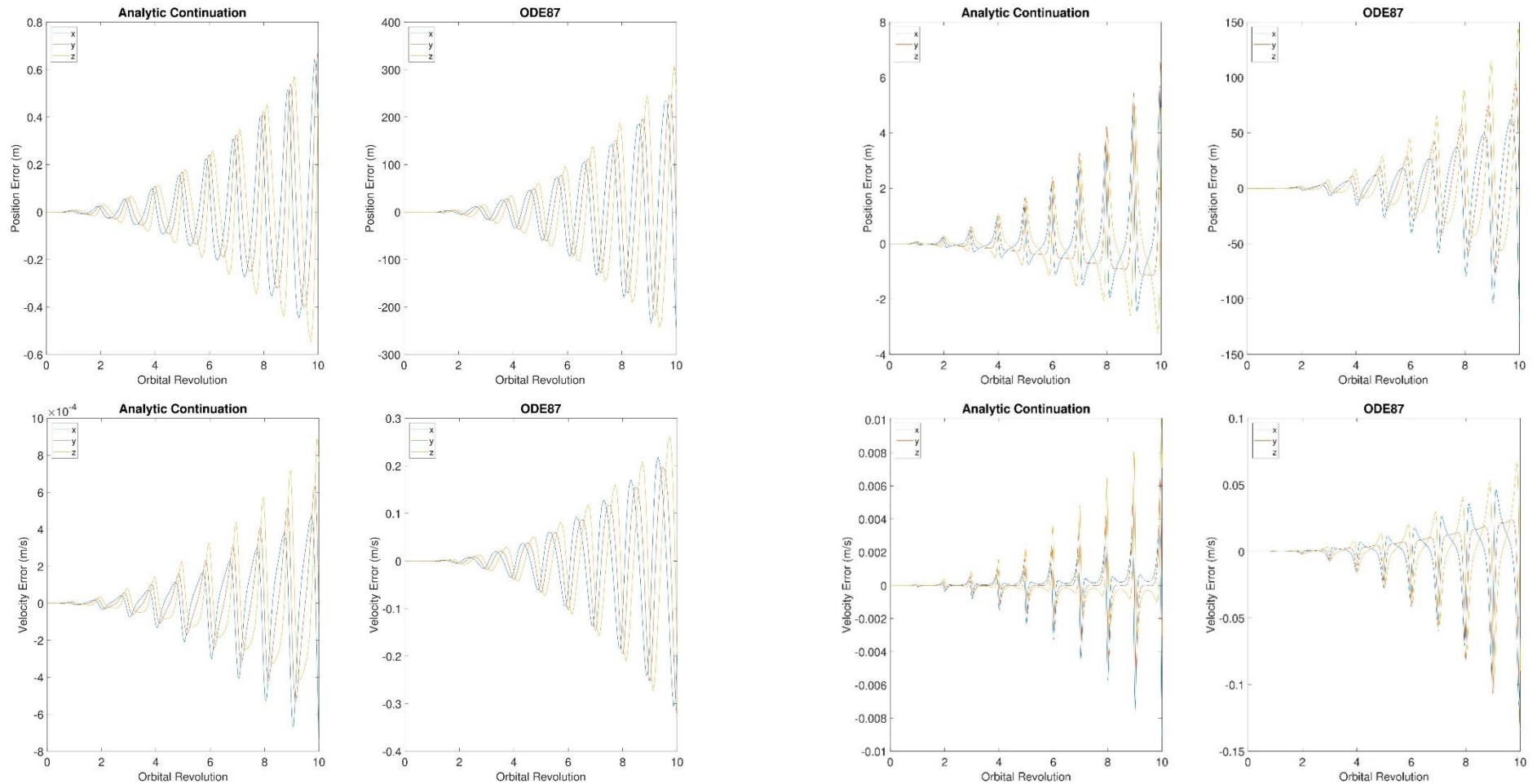


Fig: Linear prediction error of states of $J_2 - J_6$ gravity and drag perturbed LEO and MEO orbit using Analytic Continuation and comparison with ODE87

Results (continued)

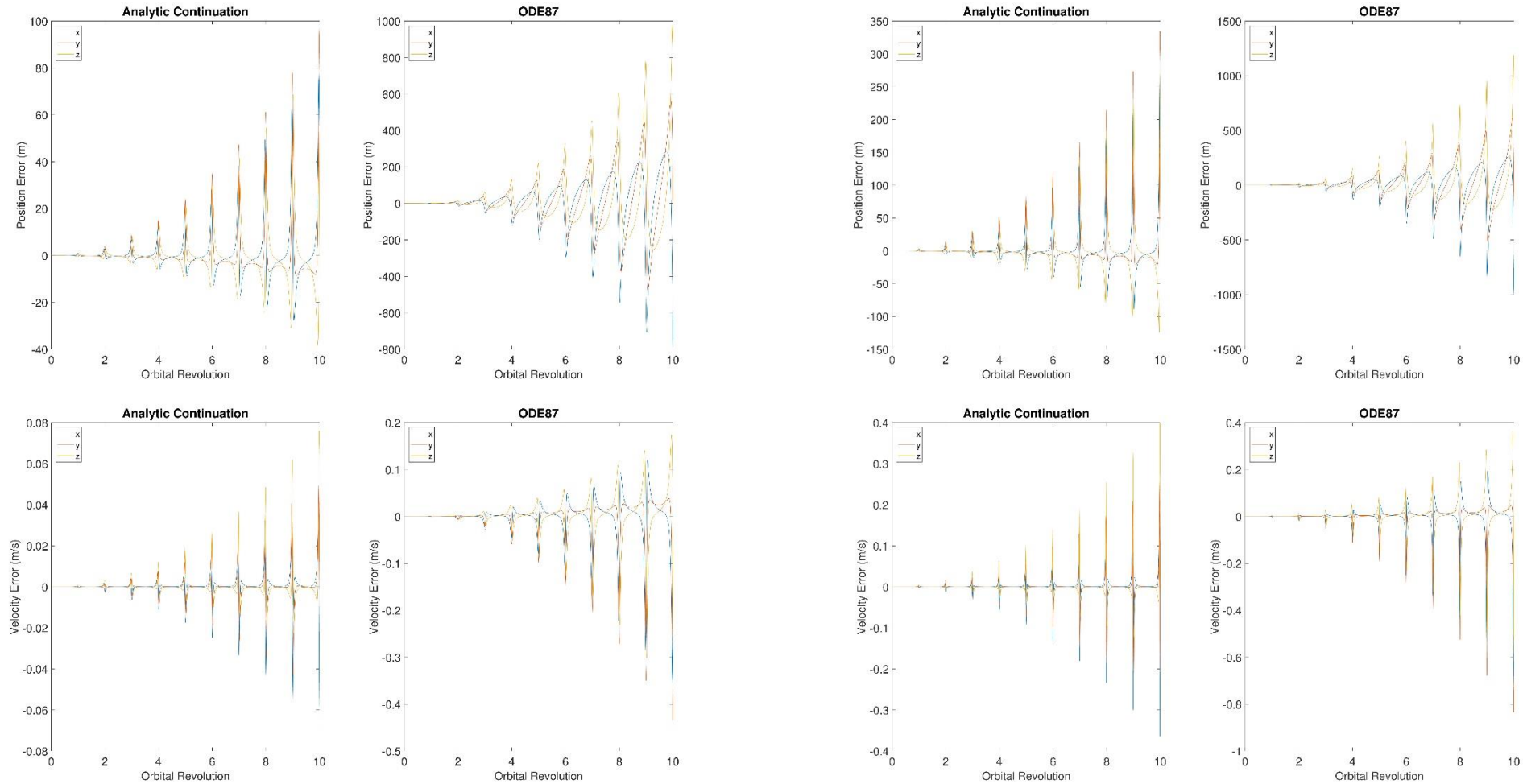


Fig: Linear prediction error of states of $J_2 - J_6$ gravity and drag perturbed GTO and HEO orbit using Analytic Continuation and comparison with ODE87

Results (continued)

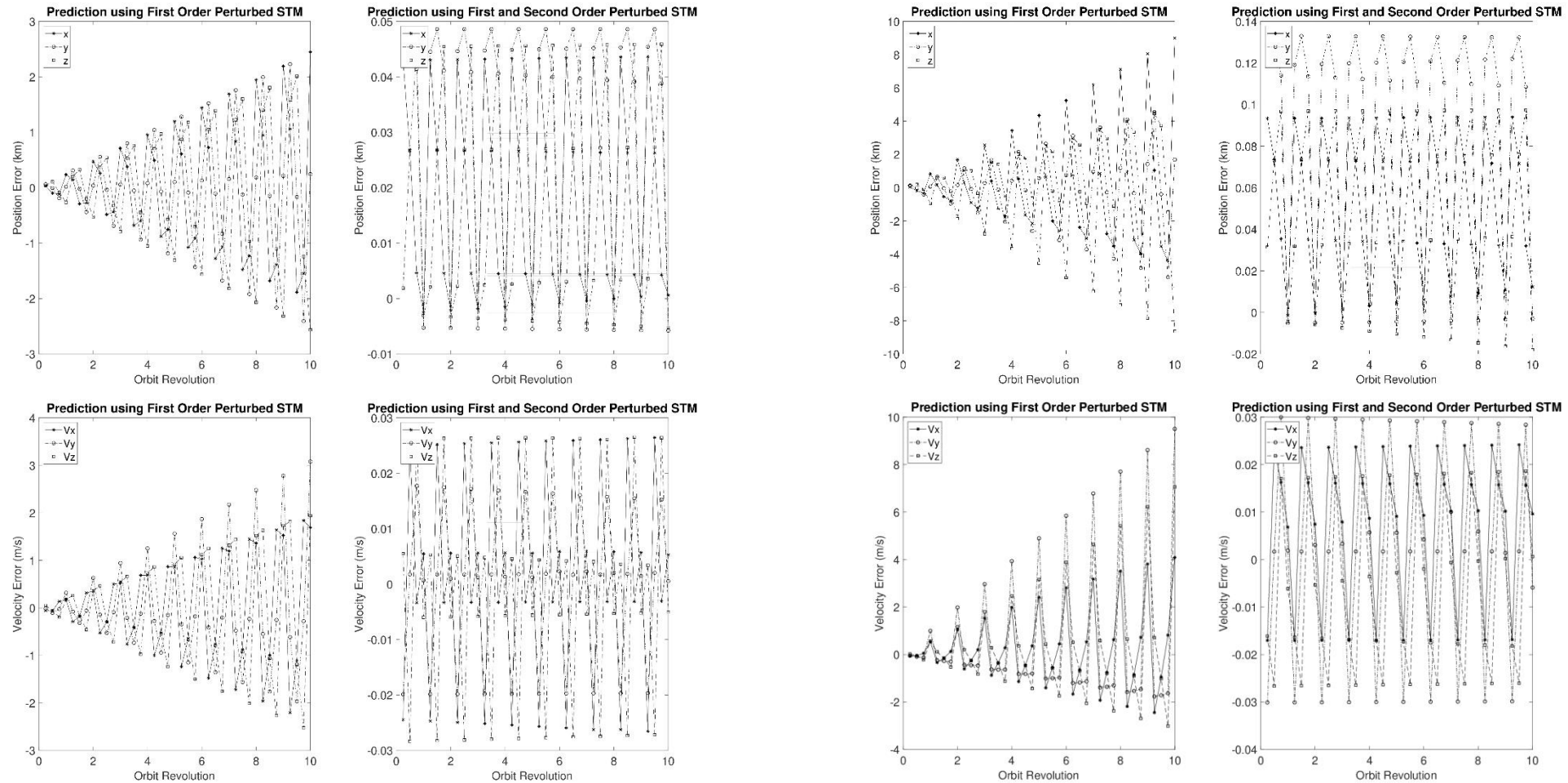


Fig: 2nd order prediction error improvement of states of J_2 perturbed LEO and MEO orbit using Second Order State Transition Tensor derived using Analytic Continuation technique

Results (continued)

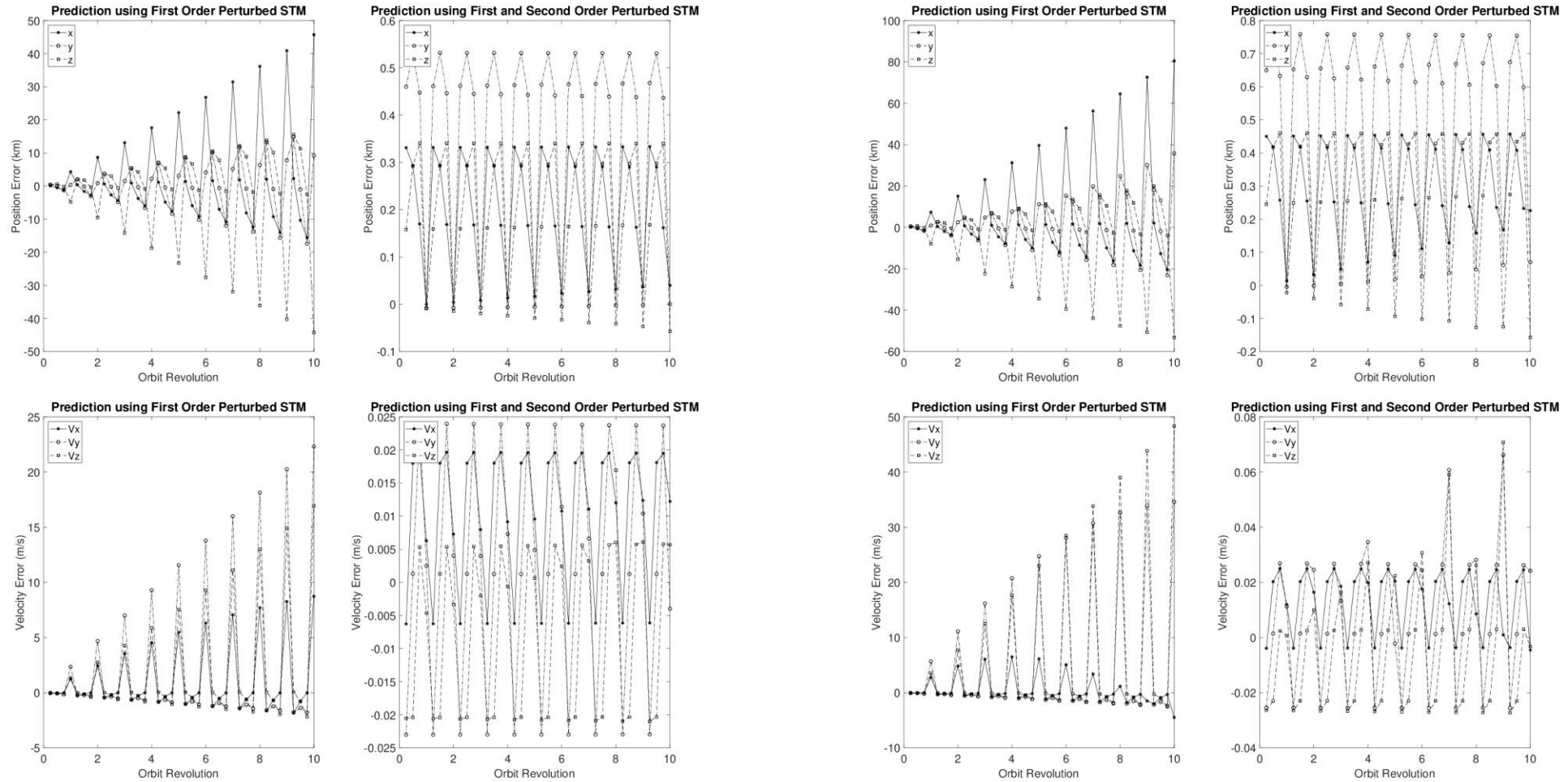
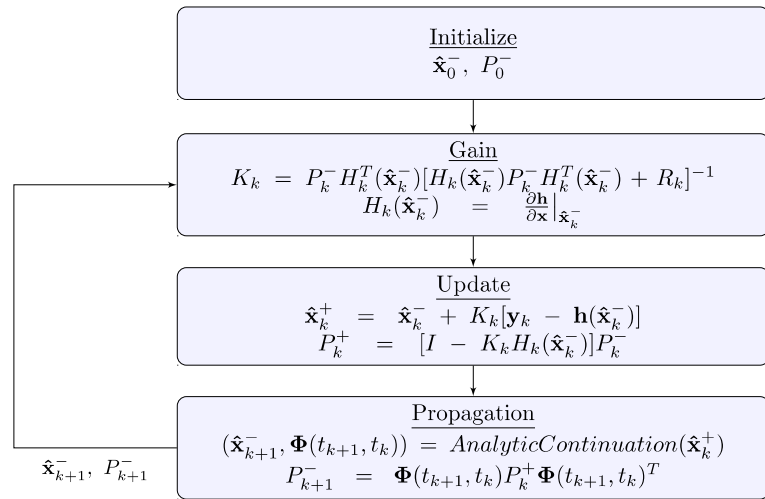


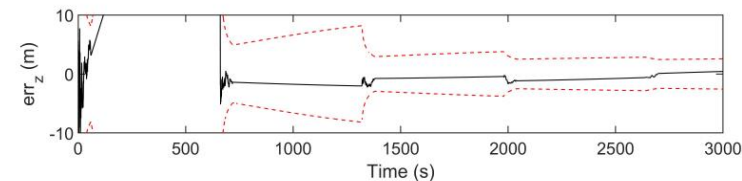
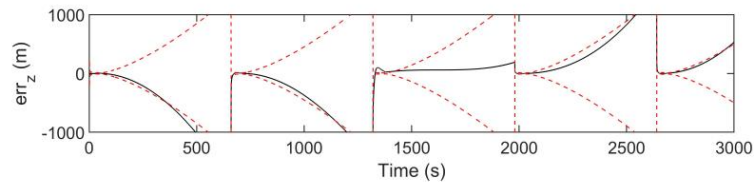
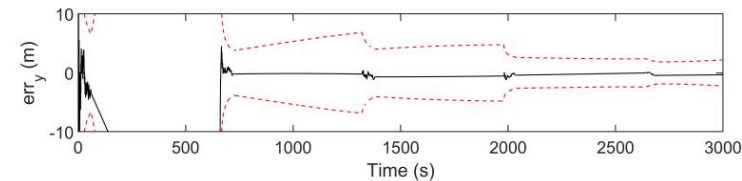
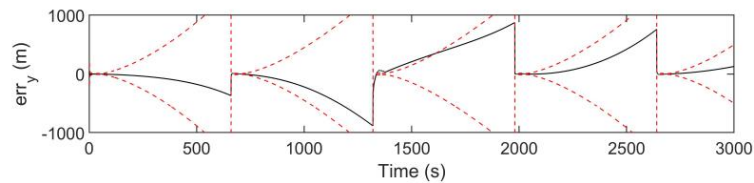
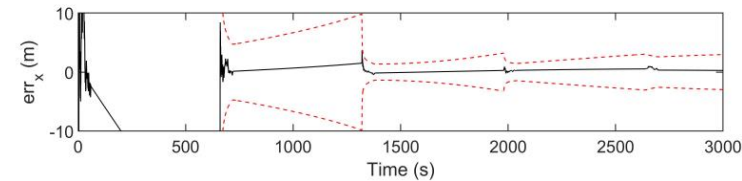
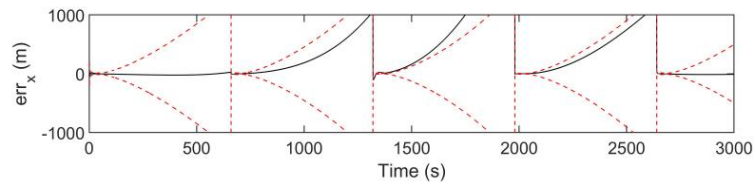
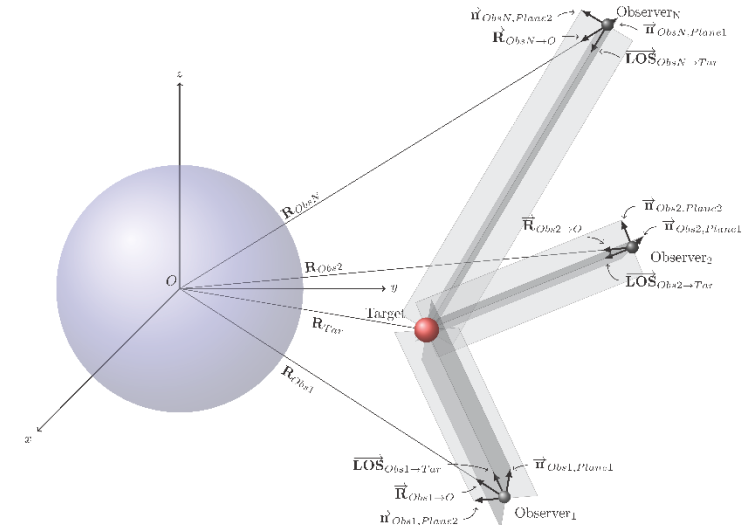
Fig: 2nd order prediction error improvement of states of J_2 perturbed GTO and HEO orbit using Second Order State Transition Tensor derived using Analytic Continuation technique

Application – Accurate Orbit Estimation with Sparse Measurements for Space-Based Surveillance & Tracking (SBSST)

- Analytic Continuation Extended Kalman Filter (AC-EKF)



$$H(\hat{\mathbf{X}}_{Tar_k}) = \left. \frac{\partial \mathbf{h}}{\partial \mathbf{x}} \right|_{\hat{\mathbf{x}}_{Tar_k}} = \begin{bmatrix} \frac{1}{(z_{Obs1_k} - \hat{z}_{Tar_k})} & 0 & \frac{(\hat{x}_{Tar_k} - x_{Obs1_k})}{(z_{Obs1_k} - \hat{z}_{Tar_k})^2} & 0 & 0 & 0 \\ 0 & \frac{1}{(z_{Obs1_k} - \hat{z}_{Tar_k})} & \frac{(\hat{y}_{Tar_k} - y_{Obs1_k})}{(z_{Obs1_k} - \hat{z}_{Tar_k})^2} & 0 & 0 & 0 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ \frac{1}{(z_{ObsN_k} - \hat{z}_{Tar_k})} & 0 & \frac{(\hat{x}_{Tar_k} - x_{ObsN_k})}{(z_{ObsN_k} - \hat{z}_{Tar_k})^2} & 0 & 0 & 0 \\ 0 & \frac{1}{(z_{ObsN_k} - \hat{z}_{Tar_k})} & \frac{(\hat{y}_{Tar_k} - y_{ObsN_k})}{(z_{ObsN_k} - \hat{z}_{Tar_k})^2} & 0 & 0 & 0 \end{bmatrix}$$



AC-EKF Accuracy & Efficiency Comparison

A Small Formation Performing SBSST

| | Pos. RMSE (m) | Vel. RMSE (m/s) | Condition Number |
|--|---------------|-----------------|------------------------|
| Keplerian Two-Body Motion | | | |
| Two-body Assumption w/o P.N. | 1.785 | 0.888 | 5.920×10^{11} |
| <i>AC-EKF</i> | 1.792 | 0.888 | 5.931×10^{11} |
| Two-Body Motion Gravity Perturbed | | | |
| Two-body Assumption w/o P.N. | | <i>Diverges</i> | |
| Two-body Assumption w/ P.N. | 5.680 | 1.672 | 6.395×10^{11} |
| <i>AC-EKF</i> | 1.646 | 1.348 | 6.592×10^{11} |
| Two-Body Motion Gravity and Drag Perturbed | | | |
| Two-body Assumption w/o P.N. | | <i>Diverges</i> | |
| Two-body Assumption w/ P.N. | 5.644 | 0.926 | 5.480×10^{11} |
| <i>AC-EKF</i> | 1.542 | 0.916 | 5.602×10^{11} |
| Two-Body Higher Order Gravity and Drag Perturbed | | | |
| Two-body Assumption w/o P.N. | | <i>Diverges</i> | |
| Two-body Assumption w/ P.N. | 9.470 | 0.547 | 6.896×10^{11} |
| <i>Analytic Continuation w/o P.N.</i> | | <i>Diverges</i> | |
| <i>Analytic Continuation w/ P.N.</i> | 4.592 | 0.518 | 6.916×10^{11} |

Computational Efficiency

| | Relative Time | Num. Steps | Pos. RMSE (m) | Vel. RMSE (m/s) |
|--------------------------|---------------|------------|---------------|-----------------|
| $\Delta t = 0.5$ s | | | | |
| <i>F&G-EKF</i> | 0.402 | 1 | 5.995 | 1.042 |
| <i>ODE45-EKF w/ P.N.</i> | 7.679 | 12 | 5.953 | 0.967 |
| <i>RK4-EKF</i> | 1.000 | 2 | 1.542 | 0.916 |
| <i>ODE45D-EKF</i> | 11.102 | 10 | 1.542 | 0.916 |
| <i>ODE45-EKF</i> | 11.409 | 10 | 1.542 | 0.916 |
| <i>AC-EKF</i> | 2.822 | 1 | 1.542 | 0.916 |
| $\Delta t = 200.0$ s | | | | |
| <i>F&G-EKF</i> | 0.073 | 1 | 928.977 | 4.114 |
| <i>ODE45-EKF w/ P.N.</i> | 2.692 | 100 | 922.227 | 4.109 |
| <i>RK4-EKF</i> | 1.000 | 40 | 25.827 | 0.106 |
| <i>ODE45D-EKF</i> | 1.703 | 13 | 25.827 | 0.106 |
| <i>ODE45-EKF</i> | 3.018 | 39 | 25.827 | 0.106 |
| <i>AC-EKF</i> | 0.158 | 1 | 25.827 | 0.106 |

Publications

- Tasif, T.H., Elgohary, T.A.: A high order analytic continuation technique for the perturbed two-body problem state transition matrix, Advances in Astronautical Sciences: **AAS/AIAA Space Flight Mechanics Meeting** (2019)
- Tasif, T.H., Elgohary, T.A.: An adaptive analytic continuation technique for the computation of the higher order state transition tensors for the perturbed two-body problem, **AIAA Scitech 2020** Forum, p. 0958 (2020)
- Tasif, T.H., Elgohary, T.A.: An adaptive analytic continuation method for computing the perturbed two-body problem state transition matrix, **The Journal of the Astronautical Sciences** (2020).
- Tasif, Tahasinul H.; Hippelheuser, James; and Elgohary, Tarek A., “Analytic Continuation Extended Kalman Filter Framework for Space-Based Inertial Orbit Estimation via a Network of Observers”, **IAA Space Traffic Management Conference**, January 26 – 27, 2021.
- Tasif, Tahsinul Haque; and Elgohary, Tarek A., “A Computation Process for the Higher Order State Transition Tensors of the Gravity and Drag Perturbed Two-Body Problem using Adaptive Analytic Continuation Technique”, **The International Conference on Computational and Experimental Engineering and Sciences (ICCES 2022)**, January 2022.
- Tasif, Tahsinul H.; Hippelheuser, James; and Elgohary, Tarek A., “An Analytic Continuation Extended Kalman Filter Framework for Perturbed Orbit Estimation Using a Network of Space-Based Observers with Angles-Only Measurements”, **Astrodynamics** (2022). **In Press.**

Conclusions and Future Work

- Implementation of Spherical Harmonics Gravity and drag perturbations for State Transition Matrix and Higher Order State Transition Tensors.
- A robust estimation framework for multi-observer space-based surveillance and tracking in the absence of continuous measurements.
- The results of the current research work will be extended to solve uncertainty quantification of states over time and perturbed Multi Revolution Lambert's Problem.