SIMULATION VERIFICATION TECHNIQUES STUDY
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SUBSYSTEM SIMULATION VALIDATION TECHNIQUES
Task Report #5 (TR-5)

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30 December 1974  MDC E1201

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SECTION 1
SUMMARY

This report discusses techniques for validation of software modules which simulate spacecraft onboard systems. The results presented in this report represent a portion of Task 2 -- the performance verification task -- of the Simulation Validation Techniques Study (SVTS). Task 2 is concerned with simulation validity; i.e., fidelity of representation of the real world. The outputs of this study task will support validation of the next generation of training and procedures-development simulators at JSC. Specifically, these results will enable NASA/contractor personnel to:

- obtain the basic reference data which establishes standards of simulation performance
- develop the support software needed for check case generation and data formatting
- develop the support software needed for realtime performance data acquisition and subsequent processing.

Section 3 of this report defines the objectives of this study task. Section 3 also provides an overview of the simulation software hierarchy for a Shuttle mission simulator. The major categories of simulation software are environment, crew station, vehicle configuration, vehicle dynamics, and vehicle subsystems. Vehicle subsystems simulation modules are covered in this report; all other categories were covered in a previous report (Ref. 1).

Section 4 presents the technical results of Task 2. Section 4.1 presents a set of guidelines for the identification of subsystem/module performance...
parameters and "critical" performance parameters. Section 4.2 identifies various sources of reference data to serve as standards of performance for simulation validation.

Sections 4.3-4.6 very briefly discuss the environment, crew station, vehicle configuration, and vehicle dynamics simulation software, from the point of view of their interfaces with subsystem simulation software modules.

Section 4.7 provides a detailed presentation of our study results in the area of vehicle subsystems simulation modules. The vehicle subsystem hierarchy is expanded down to the lowest level modules of interest for performance verification. For each Vehicle Subsystem, we present a description of the subsystem, and a definition of the simulation software module for that subsystem (including a module interface diagram and a list of performance parameters). Sources of reference data for module validation are discussed, and a flowchart of a suitable reference module is provided. Finally, validation techniques appropriate to that module are identified, static and/or dynamic check case requirements are defined, and an estimate is made of the data base impact for module validation.

Section 5 presents our conclusions and recommendations. Section 6 is a list of references.
SECTION 2
INTRODUCTION

This report presents Subsystem simulation performance verification

techniques defined during the Simulation Verification Techniques Study (SVTS)
being conducted for NASA's Johnson Space Center under Contract NAS 9-13657.
This study is being performed by McDonnell Douglas Astronautics Company -
East at its Houston Operations facility. Keith L. Jordan, Simulation
Development Branch, FSD, is Technical Monitor of the contract for the NASA.

The Simulation Verification Techniques Study is one of a number of
studies being conducted by NASA-JSC in support of the development of training
and procedures-development simulators for the Space Shuttle Program. The
other studies were: Shuttle Vehicle Simulation Requirements, NAS 9-12836;
Space Shuttle Visual Simulation System Design Study, NAS 9-12651, performed
by McDonnell Douglas Electronics Company; Development of Simulation Computer
Complex, NAS 9-12882; Crew Procedures Development Techniques, NAS 9-13660;
and Advanced Crew Procedures Development Techniques, NAS 9-14354. The
latter three studies were performed by McDonnell Douglas Astronautics Company -
East at Houston Operations.

The present study is concerned with the development of self-test


techniques for simulation hardware, and the validation of simulation per-
formance. The report for the Hardware Verification Task (Ref. 2) has
already been published. A report describing all results of SVTS Task 2
will be published at the end of January 1975.
SECTION 3
STUDY OBJECTIVES AND SCOPE

This report covers a portion of the work done under WBS 2.0 of the Simulation Verification Techniques Study.

3.1 PURPOSE

The purpose of WBS 2.0 is to develop methods for verifying simulation fidelity with respect to the real world; i.e., to ensure that the simulator responses presented to the crew are indiscernible from those which will be experienced during actual flight. During simulator development, performance verification (validation) is performed on individual software modules, at various stages of integration, and finally for the all-up simulator system. In addition, revalidation will be necessary from time to time during the simulator's operational lifetime, as modifications are made to hardware and/or software.

The outputs of this study task will support validation of the next generation of training and procedures-development simulators at JSC. Specifically, these results will enable NASA/contractor personnel to:

- obtain the basic reference data which establishes standards of simulation performance
- develop and use the support software needed for check case generation and data formatting
- develop and use the support software needed for realtime performance data acquisition and subsequent processing.
WBS 2.0 is divided into three subtasks:

- **WBS 2.1, Definition of Performance Parameters:** Analyze each Shuttle subsystem and simulation module; define a set of parameters which completely describe each subsystem/module.

- **WBS 2.2, Establishing Standards of Performance:** Define methods to provide reference data to serve as standards of performance for module validation (e.g., batch programs, test data). Define data formats, determine data base impact.

- **WBS 2.3, Methods for Validating Performance:** Define methods for realtime performance data acquisition and comparison with reference data; define comparison criteria.

### 3.2 Scope of This Report

Each of these subtask efforts must be applied in the context of each subsystem/module, as well as in the context of integrated simulator system operation. Because of the considerable body of specialized information required, it is convenient to work on the performance parameter identification, reference data sources and validation methods peculiar to a module all at once, rather than dealing with different aspects of a particular module at three widely-separated times. For that reason, this report is organized on the basis of the simulation software module hierarchy, and includes module-oriented efforts which fall under all three WBS subtasks.

Figure 3-1 shows an overview of the simulation software module hierarchy developed for use in WBS 2.0. The software categories covered in our previous (Ref. 1) report -- Environment, Crew Station, Vehicle
FIGURE 3-1  SUBSYSTEM/MODULE CATEGORIES COVERED IN THIS REPORT.
Configuration, and Vehicle Dynamics -- are enclosed in the dotted lines. This report covers vehicle subsystems simulation modules.

For each module covered, this report provides a description of the module's functions and operational modes, its stored data and inputs, and its performance parameters (including "critical" performance parameters as defined below). Sources of reference (standards) data are identified, and performance-verification techniques and support software are briefly discussed. Validation data base impact for each module is defined.
SECTION 4
STUDY TECHNICAL RESULTS

The focus of this report is vehicle subsystems simulation module validation, discussed in considerable detail in Section 4.7. Sections 4.1-4.6 provide brief introductory material to define the context in which the subsystems simulation analyses were performed.

4.1 PERFORMANCE PARAMETER GUIDELINES

In performing an analysis of each onboard subsystem and simulation software module, we must extract from its basic defining information a list of performance parameters, which completely describe the performance of the subsystem/module. By this we mean that any error or inadequacy in the simulation must show up in one or more of the designated performance parameters. We envision such a complete performance parameter list to be useful primarily in the exhaustive initial validation of the simulator.

In addition, we have further examined the complete parameter list for each module, designating a subset thereof as "critical" performance parameters. The primary utility of the critical performance parameter list would be in revalidating simulation modules after modifications or updates; we assume that if a module's critical parameters provide acceptable fidelity, it will not be necessary to check the rest of the performance parameters. Criteria for identification of performance parameters and critical performance parameters are given below.
4.1.1 Performance Parameters

The performance parameters for any onboard subsystem simulation module or for the total vehicle system simulation must have the following properties:

a. They must be real-world variables (either continuous or discrete). Thus, synthetic variables which are defined for analysis and programming purposes -- e.g., auxiliary angles, counters, initialization flags -- cannot be performance parameters.

b. They must be time-variable quantities, not constants; e.g., aerodynamic-coefficient tables are not performance parameters.

c. All system "state variables" are performance parameters. (State variables may be defined as the dependent variables in the system differential equations, when the equations have been reduced to first order).

d. Some outputs of a module may not be performance parameters. Outputs unrelated to the module's designated functions (e.g., power consumed and heat dissipated by an IMU) are "incidental outputs", not performance parameters.

e. Some performance parameters of a module may not be outputs. Internal variables (either continuous or discrete) not normally output from a module will still be performance parameters, if they are real-world variables, and are essential to the representation of the performance parameters which are outputs.

f. Every variable available to a flight computer or telemetred for ground-controller use should be a performance parameter of some module.
g. Inputs to a module are never performance parameters for that module. (This rule prevents double-counting; thus no variable will ever be a performance parameter for more than one module.)

4.1.2 Critical Performance Parameters

Guidelines for selection of a subset of critical performance parameters from the set of performance parameters of a module are somewhat less clear-cut than those for initial selection of performance parameters. A performance parameter may be denoted as a critical performance parameter for one or more of the following reasons:

a. It is a particularly significant indicator of simulation validity for its associated module.

b. Its accuracy has a long-term or cumulative impact upon the simulation validity; e.g., orbital drag forces, consumables expenditure rates.

c. It is readily available to the crew (by permanent or callable display), and plays a key role in crew operational procedures.

d. It is communicated to the flight computer(s) and plays a key role in computer control of vehicle systems.
4.2 ALTERNATE REFERENCE-DATA SOURCES

The Standards of Performance sought in this task are sources of reference data representing the real world, against which the simulation fidelity is to be evaluated. Four basic classes of reference-data source are considered in this study:

- Closed-form solutions: exact or approximate formulas giving answers to be compared to the output of simulation routines.
- Independent math models: parallel software development for the explicit purpose of providing reference data for module validation.
- Existing analysis/simulation programs: established, previously-validated programs which can be exercised with check-case data to provide outputs directly comparable to simulation module outputs.
- Test data: vehicle and/or subsystem data from an actual laboratory or flight environment.

Table 4.2-1 briefly lists advantages and disadvantages of each of the four basic classes of reference-data source. These considerations will be discussed in greater detail in a later report.
## TABLE 4.2-1 ALTERNATE DATA SOURCES: PROS & CONS

<table>
<thead>
<tr>
<th>DATA SOURCE</th>
<th>ADVANTAGES</th>
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<tr>
<td>Closed-Form Solutions</td>
<td>Simplicity</td>
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<tr>
<td></td>
<td>Accuracy</td>
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<td>Workload</td>
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<td></td>
<td>Compatibility</td>
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<td>Existing Analysis/Simulation Programs</td>
<td>Scope</td>
<td>Availability</td>
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<td>Documentation</td>
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<tr>
<td></td>
<td></td>
<td>Incompatibility</td>
</tr>
<tr>
<td>Test Data</td>
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<td>Timeliness</td>
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<td>Incompatibility</td>
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<tr>
<td></td>
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<td>Documentation</td>
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</table>
4.3 ENVIRONMENT MODULES

Environmental conditions external to the Shuttle vehicle interface with and influence the performance of the vehicle and its subsystems. The total environment is considered in two basic divisions -- natural environment and artificial environment.

4.3.1 Natural Environment

The natural environmental factors influencing the Shuttle vehicle include the earth's atmosphere, winds, gravitational potential, sun/moon/star positions, and terrain elevation. The atmosphere and wind produce aerodynamic affects, generating forces and moments on the vehicle. Gravitational potential is another important source of forces and moments. The sun, moon and star positions provide guidance and navigation inputs. Finally, the terrain near the landing site reflects radar altimeter signals, used for altitude measurement during Orbiter approach and landing. Figure 4.3-1 shows the interfaces of the natural environment module with other simulation modules.

4.3.2 Artificial Environment

The artificial environment consists of external systems and equipments which provide the Orbiter with certain services -- data, power, fuel, cooling -- or request such services from the Orbiter. The three artificial environment modules discussed in this section are ground navigation/communications, payloads and rendezvous targets, and prelaunch/launch interface.

4.3.2.1 Ground Navigation/Communications

Ground-based navigation and communications equipment provides data and command inputs to the Orbiter through its communication and tracking subsystem.
FIGURE 4.3-1. NATURAL ENVIRONMENT MODULE, FUNCTIONAL ELEMENTS AND INTERFACES
The ground systems planned for use during Shuttle operations are:

- Dual-antenna S-band telemetry
- UHF voice
- STDN/TDRS (NASA systems)
- SGLS (DoD system)
- Aeroflight navaids: TACAN, MSBLS

Figure 4.3-2 shown the interfaces between the ground nav/comm simulation module and other simulation modules.

The ground nav/comm simulation module will simulate the transmitted signal strengths and received signal strengths of ground-to-orbiter and Orbiter-to-ground communication links, by use of antenna pointing and antenna gain-pattern computations.

4.3.2.2 Payloads and Rendezvous Targets

A wide variety of payloads and rendezvous targets will be deployed and retrieved by the Shuttle during its operational lifetime; for example:

- Cryo tug
- Agena high-energy payload
- Interim tug
- Large Space Telescope
- ESRQ space lab
- Earth observation satellites

In addition, Orbiter-to-orbiter rendezvous and docking maneuvers may be undertaken; e.g., for rescue purposes.
FIGURE 4.3-2 GROUND NAV/COMM MODULE FUNCTIONAL ELEMENTS, AND MODULE INTERFACES
The payload/target (P/T) simulation module must provide for maneuvers (if any) made by the P/T when free-flying (post-deployment or pre-retrieval), for onboard consumables usage affecting the P/T mass properties, and for command and data transfer between the Orbiter and the P/T. Figure 4.3-3 identifies the major functional elements of the P/T simulation module, and shows its interfaces with other modules.

4.3.2.3 Prelaunch/Launch Interface

In the final phase of the prelaunch countdown, ground-based systems are interfaced with the Shuttle vehicle for the following functions:

- Communications and instrumentation (RF and hardline)
- Electrical power
- Environmental control
- Hydraulic power
- Purge, vent and pressurization
- Mechanical hold-down until successful engine startup is verified

These functions are indicated on the module interface diagram, Fig. 4.3-4. We do not anticipate a very detailed implementation of prelaunch/launch functions on any upcoming JSC simulator.
TARGET MODEL DISPLAY

OPTICAL TRACKER

COMMUNICATIONS AND TRACKING MODULE

EQUATIONS OF MOTION MODULE

ON-BOARD SYSTEMS
- Attitude Control
- Maneuver Control
- Electrical Systems
- External Electrical Systems

PAYLOAD INTERROGATOR INTERFACE

S-BAND TRANSPONDERS INTERFACE

RENDEZVOUS RADAR INTERFACE

UMBILICAL INTERFACE

PAYLOAD/RENDZVOUS TARGET MODULE

Configuration and consumeables remaining

Mass Inertia

Relative attitudes range

state vectors

Forces, torques etc.

state vectors, attitudes, rates

on various Modules

Data, voice

from various sources

Commands voice, data

FIGURE 4.3-3 PAYLOAD/RENDZVOUS TARGET MODULE, FUNCTIONAL ELEMENTS AND INTERFACES
FIGURE: 4.3-1. PRELAUNCH/LAUNCH INTERFACE MODULE, FUNCTIONAL ELEMENTS AND INTERFACES.
4.4 CREW STATION MODULES

Visual and motion simulation are of crucial importance in the flight crew's subjective perception of the simulation fidelity. Highly specialized software and hardware are necessary to accomplish visual and motion simulation, particularly over the widely varying dynamical and operational regimes of Shuttle missions.

Figure 4.4-1 shows the interfaces involved in visual simulation. Different types of hardware will be required to provide the various visual-scene elements. Each hardware unit will require its own software driver module, with control provided by a visual-system control module, using inputs from the simulation software. Several distinct fields must be generated, to provide forward and aft out-the-window views as well as TV displays for the payload manipulator station.

Motion-base drive software is designed to create the most realistic possible perception of vehicle motions and accelerations within the constraints imposed by the motion-base hardware, without introducing spurious cues due to abruptly reaching actuator travel limits. The functions of the motion-base software, as indicated in the interface diagram of Figure 4.4-2, include transformation of vehicle motions into actuator displacements, compensation for hardware response, and travel-limiting functions such as look-ahead, washout, and bleed-back.
FIGURE 4.4-1: VISUAL SYSTEM SOFTWARE AND HARDWARE INTERFACES
FIGURE 4.4-2 MOTION-BASE SOFTWARE INTERFACES
4.5 VEHICLE CONFIGURATION MODULES

The Shuttle vehicle configuration, and hence its response to external influences and vehicle system operation, changes during the course of a mission. The modules falling in the vehicle configuration category are aerodynamics, aerothermodynamics, and mass properties.

4.5.1 Aerodynamics

Significant aerodynamic forces and moments occur act on the Shuttle during the ascent, entry, aeroflight, and approach & landing mission phases. The forces vary with atmospheric conditions, Shuttle velocity, and Shuttle vehicle configuration; the moments also vary with vehicle c. g. position.

The aerodynamics simulation module must access tabular data appropriate to the current vehicle configuration and dynamical regime, then use the tabular data to compute forces and moments in terms of an appropriate axis set. Major configuration changes occur as the SRB's and the ET are separated from the vehicle; minor configuration changes occur with landing gear and drag chute deployment. Aerosurface positions, ground effects and ET/SRB proximity also influence the vehicle aerodynamics. These interfaces are shown in Figure 4.5-1.

4.5.2 Aerothermodynamics

Aerodynamic heating during entry is a major constraint on the vehicle guidance. For maximum downrange travel, the Orbiter is operated near its maximum heat loading; therefore, bondline temperatures are closely monitored by the flight crew. Heat transfer through the TPS, the vehicle structure and the windows affects the temperatures of various internal compartments. This directly affects the heat dissipation required of the ECLSS, and indirectly...
MECHANICAL SUBSYSTEMS MODULES

ENVIRONMENT MODULE

MASS PROPERTIES MODULE

landing gear, drag chute deployment, \( \delta \) (aero surface)

angle of attack, sideslip;
dynamic pressure, Mach no.

center of mass

AERODYNAMICS MODULE

aerodynamic forces, moments

state vector

EQUATIONS OF MOTION MODULE

FIGURE 4.5-1 AERODYNAMICS MODULE INTERFACES
affects the performance of equipment, such as avionics, located in these compartments.

Aerothermodynamics simulation module interfaces are shown in Fig. 4.5-2.

4.5.3 Mass Properties

Shuttle vehicle mass properties -- mass, moments and products of inertia, and c. g. position -- are involved in aerodynamics and vehicle dynamics computations. The mass properties simulation module performs the bookkeeping and transformations necessary to update these parameters as propellants are consumed, SRB's and ET are separated, and payloads are stowed and unstowed. Similar, although simpler, computations are performed for certain payloads and rendezvous targets.

Mass properties simulation module interfaces are shown in Fig. 4.5-3.
ENVIRONMENT
MODULE

CREW DISPLAY
MODULE

angle of attack, sideslip, velocity, Mach no., density, dynamic pressure

bondline temperature crew request signal

AEROTHERMODYNAMICS
MODULE

compartment heating rates

ACTIVE THERMAL
CONTROL SUBSYSTEM
MODULE

FIGURE 4.5-2 AEROTHERMODYNAMICS MODULE INTERFACES
**PAYLOAD/TARGET MODULE**

payload/target mass properties

**MASS PROPERTIES MODULE**

mass remaining in propulsion system
vehicle mass, mass center, inertia tensor

**PROPULSION MODULE**

thrust

**EQUATIONS OF MOTION MODULE**

aero forces, moments
state vector

**AERODYNAMICS MODULE**

center of mass

**FIGURE 4.5-3. MASS PROPERTIES MODULE INTERFACES**
4.6 VEHICLE DYNAMICS MODULES

Vehicle dynamics simulation is the core of any spacecraft simulator. The dynamics simulation modules interface with or otherwise influence the results of most of the rest of the simulation; these interfaces and influences are indicated by Fig. 4.6-1. We are concerned with three categories of dynamical phenomena -- rigid-body equations of motion (EOM), mechanical-system dynamics, and bending and slosh dynamics -- and their corresponding simulation software modules.

Rigid-body EOM include translational (point-mass) dynamics of the Shuttle vehicle, rotational dynamics, and multiple-body dynamics. Translational dynamical computations are performed during all Shuttle mission phases; however, different computational methods may be used in the different dynamical regimes. Rotational dynamics are computed throughout the mission, using essentially the same computational method (direction cosines or quaternions), possibly varying the computational rate. Multiple-body dynamics are necessary only during discrete mission phases; e.g., separation of the Orbiter from a carrier aircraft, separation of SRB's and ET from the Orbiter, and post-deployment/pre-retrieval relative motions of a payload/target.

The internal dynamics of such mechanical subsystems as the landing gear, docking mechanism and PDRS are driven by the external dynamics of the Orbiter motion relative to the runway or an external object such as a payload or another Orbiter. In turn, these mechanical systems impose reaction forces and moments upon the Orbiter and the external object. These forces and moments depend upon the relative states and rates, masses and inertias of the objects.
FIGURE 4.6-1 OVERVIEW OF DYNAMICS MODULE INTERFACES. (DATA TRANSFER IS NORMALLY VIA COMMON STORAGE, WHETHER SHOWN DIRECT OR BUSSED ON THIS FIGURE.)
involved, the design parameters of the springs, dampers and actuators in the mechanical systems, and the location of the points of application of the mechanical-system forces.

Body bending and fuel slosh phenomena represent additional dynamical degrees of freedom of the vehicle. Rigid-body and non-rigid-body dynamics drive each other by a process of momentum interchange. In addition to their dynamical effects, body bending dynamics also contribute to the outputs of onboard inertial sensors -- gyros and accelerometers. The magnitude of these effects varies with sensor longitudinal position, being minimal at "nodes" and maximal at "antinodes" of the various normal modes of body bending.
4.7 VEHICLE SUBSYSTEMS MODULES

Vehicle subsystems simulation fidelity is particularly important, because it is these simulation modules which interface most directly with the flight crew and the flight computers. Subsystem simulations also tend to be rather complex, with a great number of parameters (both discrete and continuous) which must be accurately represented for configuration monitoring, malfunction simulation, and propagation of malfunction effects.

This section deals with all onboard subsystems in the following categories: Mechanical, Purge/Vent & Drain, Propulsion & Fuel, Power Generation, Avionics, and Environmental Control/Life Support.
4.7.1 Mechanical Subsystems

This section describes those subsystems involved in the transfer and application of mechanical power. This includes Landing/Deceleration, Docking Mechanisms, Separation Mechanisms, Actuation Mechanisms, the Payload Deployment and Retrieval System, Hydraulics, and Pyrotechnics. Pyrotechnics, however, are not treated as a separate category; rather, pyrotechnic components are treated under whatever system they form a part of.

A detailed discussion of the Landing/Deceleration Subsystem is presented. The remaining mechanical subsystems are described with less detail, because they have many components - springs, dampers, actuators, etc. - which are similar to components found in the Landing/Deceleration Subsystem.

4.7.1.1 Landing/Deceleration Subsystem (LDS)

The LDS functionally provides for extension and retraction of the nose (NLG) and main (MLG) landing gear, shock attenuation of landing impact, deceleration and directional control during landing rollout, and a stable rolling platform for all ground maneuvering and landing operations (Ref. 3).

LDS Description

The principle components of the LDS consist of (Ref. 4):
- main and nose gears, fairing doors, and actuating and locking mechanisms
- nose wheel steering
- wheels, tires, and brakes
- brake control and anti-skid system
- drag chute and deployment mechanism

Landing gear layout is a conventional tricycle configuration with twin wheels on both the nose and main gear. Gear extension is initiated by crew selection of the landing gear "down" switch which energizes the uplock release hydraulic actuators. The main gear is designed with two additional backup uplock release actuators, whereas the nose gear sequences a pyrotechnic uplock release backup (Ref. 5).

In ferry-flight and horizontal flight test configuration, inflight retraction of the gear is possible; however, for orbital missions the retraction hydraulic actuators are less powerful and not designed for inflight operation. They will function on the ground to facilitate ground turn-around operations. Figures 4.7-1
FIGURE 4.7-1. MAIN LANDING GEAR INSTALLATION
and 4.7-2 (Ref. C) illustrate the forward and up retraction of the main and nose gear into fully enclosed wheel wells. This arrangement enables freefall extension and downlock via airloads in flight.

Nose wheel steering is crew available upon touchdown. Steering "on" selection will normally occur when vehicle velocity is below a "rudder aero-effectiveness" limit. As depicted in Figure 4.7-3, (Ref. 5), steering control is transmitted electrically from the rudder pedals to the hydraulic steering actuator. The steering actuator also functions as a shimmy damper in steering "on" and "off" modes.

Primary deceleration of the Orbiter vehicle during landing rollout is accomplished through the use of the main gear brakes. For maximum efficiency, braking and skid control functions are integrated into a "brake by wire" system as described in Figure 4.7-4, (Ref. 5). Wheel spin-up activates the fully modulated braking/skid control system to prevent premature brake application. Individual wheel lockup is also prevented. This system ensures maximum tire adhesion during deceleration thereby maintaining the optimum braking force on all runway surfaces. Three hydraulic systems are utilized for the braking/skid control functions. Two systems function as backups as any one system is sufficient for braking/skid control operation.

Deceleration is also assisted by drag chute deployment. The drag chute system consists of the main and pilot canopies and risers, deployment mortar, actuation mechanisms, and crew controls. Figure 4.7-5, (Ref. 5) describes the crew activated deployment sequence.

Landing shock attenuation is provided by the landing gear pneumdraulic (oil and air/GN₂) shock struts and tires. The tires assist the shock struts in absorbing landing energy and decelerating the landing gear unsprung mass to zero vertical velocity. The shock struts complete Orbiter vehicle deceleration at the required rate.

Hydraulic actuators used in the LDS are supplied power from the Orbiter Hydraulic Power System (HPS) described in Section 4.7.1.6. The individual actuators will be discussed in Section 4.7.1.4.
FIGURE 4.7-2  NOSE GEAR INSTALLATION
FIGURE 4.7-3. LDS NOSE GEAR STEERING UNIT DESIGN
Figure 4.7-4. LDS MAIN GEAR BRAKE ANTI-SKID CONTROL
MAIN GEAR TOUCH DOWN
PILOT SELECT DEPLOY SWITCH
CLOSE RELEASE MECH
OPEN DOORS
FIRE PILOT CHUTE MORTAR

MAIN CHUTE EXTRACTED & INFLATED
PILOT CHUTE RELEASED
DECEL & NOSE GEAR
TOUCH DOWN

DECEL & MAIN CHUTE
JETTISON 20 KTS

FIGURE 4.7-5. CHUTE DEPLOYMENT SEQUENCE
LDS Simulation Module Description and Performance Parameters

LDS simulation will incorporate several methods to simulate each subsystem component function to an acceptable level for the training simulator.

The LDS simulation module will use Orbiter geometry, altitude, attitude, vehicle mass, center of mass, groundspeed, and vertical velocity, along with terrain inputs and operator commands, to determine:
- actuator commands
- drag chute and landing gear aerodynamic effects
- crew display signals
- landing (touchdown) forces and moments
- braking and steering forces and moments
- electrical and hydraulic power requirements

All command/response relationships will be simulated using sequential time delay functions based upon actuator response characteristics and electrical power available checks to provide the desired "talkback." This method will be employed for drag chute deployment and jettison, display indicators, and landing gear extension. Dynamics equations combined with control logic loops and spring/damper relationships will be implemented for simulation of the remaining LDS components and subsystems. Spring/damper relationships will be determined from actual test data (Ref. 6). Performance parameters associated with the LDS are shown in Table 4.7-1. Figure 4.7-6 depicts the LDS simulation module interfaces with other simulation modules.

LDS Reference Data Sources and Data Formats

Figure 4.7-7, (Ref. 7) describes a functional math flow which, when combined with a driver, would serve as an LDS reference module. This reference module would provide reference data for verification of the LDS simulation module. The math flow shown primarily simulates the LDS dynamical inputs to the EOM.

A suitable driver routine should be constructed to fully simulate the LDS. The driver would contain crew input response and time delay functions to model those components simulated with "talkback" such as landing gear and drag chute deployment, steering "on" response, etc. Actual hardware simulation results will provide tabular data and curve fits for air/GN2 spring and shock strut damper characteristics,
TABLE 4.7-1. LDS PERFORMANCE PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE^a</th>
</tr>
</thead>
<tbody>
<tr>
<td>NLG and MLG &quot;up/down&quot; command</td>
<td>I</td>
</tr>
<tr>
<td>NLG and MLG &quot;uplocked/downlocked&quot; indicator flags</td>
<td>P</td>
</tr>
<tr>
<td>NLG and MLG mass</td>
<td>DB</td>
</tr>
<tr>
<td>NLG and MLG &quot;up/down&quot; actuator response time</td>
<td>I</td>
</tr>
<tr>
<td>Landing gear &quot;down&quot; aerodynamic effects flag</td>
<td>P</td>
</tr>
<tr>
<td>NLG and MLG coordinates</td>
<td>DB</td>
</tr>
<tr>
<td>Braking forces and moments</td>
<td>CP</td>
</tr>
<tr>
<td>Brake pedal displacement and rate</td>
<td>I</td>
</tr>
<tr>
<td>Wheel RPM</td>
<td>CP</td>
</tr>
<tr>
<td>Brakes &quot;on/off&quot; indicator flag</td>
<td>CP</td>
</tr>
<tr>
<td>Tire-to-runway braking force coefficient</td>
<td>DB</td>
</tr>
<tr>
<td>Runway terrain function</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter landing attitude, attitude rates</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter vertical velocity</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter groundspeed</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter mass</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter mass center</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter altitude above runway</td>
<td>I</td>
</tr>
<tr>
<td>NLG and MLG strut displacement, rate</td>
<td>CP</td>
</tr>
<tr>
<td>NLG and MLG G^2 spring rate</td>
<td>DB</td>
</tr>
<tr>
<td>NLG and MLG damper constant</td>
<td>DB</td>
</tr>
<tr>
<td>NLG and MLG tire spring rate</td>
<td>DB</td>
</tr>
<tr>
<td>NLG and MLG tire displacement</td>
<td>P</td>
</tr>
<tr>
<td>Rudder aero-effectiveness velocity limit</td>
<td>DB</td>
</tr>
<tr>
<td>Rudder pedal position</td>
<td>I</td>
</tr>
<tr>
<td>NLG steering &quot;on&quot; command and indicator</td>
<td>I, P</td>
</tr>
<tr>
<td>NLG steering actuator command</td>
<td>I</td>
</tr>
<tr>
<td>NLG steering forces and moments</td>
<td>CP</td>
</tr>
<tr>
<td>NLG steering angle and angular rate</td>
<td>I</td>
</tr>
<tr>
<td>NLG steering actuator response time</td>
<td>I</td>
</tr>
<tr>
<td>Drag chute deploy/jettison command</td>
<td>I</td>
</tr>
<tr>
<td>Drag chute deploy/jettison response time</td>
<td>I</td>
</tr>
<tr>
<td>Drag chute aero-effects flag</td>
<td>P</td>
</tr>
</tbody>
</table>

^aP - Performance Parameter
CP - Critical Performance Parameter
I - Input
DB - Data Base Input
AVIONICS MODULE

ground speed

ENVIRONMENT MODULE

angle of attack, sideslip, terrain (runway) model

CONTROLS AND DISPLAYS MODULE

activation commands

mass, center of mass

MASS PROPERTIES MODULE

subsystem response signals

LANDING/DECELERATION SUBSYSTEM MODULE

electrical power required, available

electrical power system module

LANDING, STEERING, BRAKING FORCES, MOMENTS

AERODYNAMICS MODULE

aero forces, moments

EQUATIONS OF MOTION MODULE

HYDRAULIC POWER SYSTEM MODULE

drag chute, landing gear aero-effects flags

actuator commands, response

LANDING GEAR, STEERING, DRAG CHUTE ACTUATORS MODULE

hydraulic power available, required

FIGURE 4.7-6. LDS SIMULATION MODULE INTERFACES
DEFINITION OF MATRIX TRANSFORMATIONS

NORTH-EAST-DOWN TO BODY AXES

\[
\begin{bmatrix}
C_{x1} & C_{y1} & C_{z1} \\
C_{x2} & C_{y2} & C_{z2} \\
C_{x3} & C_{y3} & C_{z3}
\end{bmatrix}
\begin{bmatrix}
\cos(a) & \cos(b) & -\sin(a) \\
\sin(a) & \cos(b) & \cos(a)
\end{bmatrix}
\begin{bmatrix}
\cos(c) & -\sin(c) & 0 \\
\sin(c) & \cos(c) & 0
\end{bmatrix}
\begin{bmatrix}
\cos(\theta) & \sin(\theta) & 0 \\
-\sin(\theta) & \cos(\theta) & 0
\end{bmatrix}
\begin{bmatrix}
\cos(e) & \sin(e) & 0 \\
-\sin(e) & \cos(e) & 0
\end{bmatrix}
\begin{bmatrix}
x_1 \\
y_1 \\
z_1
\end{bmatrix}
\]

DEFINITION OF SYMBOLS

\( \times \) COMPARATOR OR SUMMATION
\( E \) ENABLE SIGNAL FLOW
\( O \) OFF PAGE CONNECTOR
\( \sqrt{ } \) SIGN OF VARIABLE

FIGURE 4.7-7. LDS REFERENCE MODULE MATH FLOW
FIGURE 4.7-7  (CONTINUED)
SPRING PRESSURE

SPRING FORCE

\[ F_s = P_s \cdot A_v - A_a \]

INS FULL STRUT DEFORMATION

VELOCITY-SQUARED DAMPING

\[ F_v = C_v \cdot V^2 \]

TOTAL FORCE

\[ F_t = F_s + F_w + F_r \]

VELOCITY-SQUARED DAMPING FORCE

\[ F_v = C_v \cdot V^2 \]

LINEAR DAMPING FORCE

\[ F_l = C_l \cdot \dot{V} \]

TOTAL FORCE

\[ F_t = F_s + F_w + F_r \]

FORCE NORMAL TO GROUND

\[ F_n = \frac{F_0}{\cos \theta} \]

Rudder Pedal Engagement

Engaged

Rudder Pedal

Engaged

Figure 4.7-7 (continued)
SIDE FORCE COEFFICIENT

USED AS 2nd VARIABLE IN TABLE LOOK-UP OF EACH COEFFICIENT ON THIS PAGE.

COMPUTE VELOCITY CONTACT POINT

COMPUTE SIDE ANGLE

VELOCITY CONTACT POINT

EFFECTIVE SIDE ANGLE

= 2, 3

WET DRY BRAKES

BRAKE COEFFICIENT

SIDE FORCE COEFFICIENT

FIGURE 4.7-7 (CONTINUED)
TOTAL FORCES ON STRUTS
\[ F_{xv}(2) = -C_{av} \cdot F_v(2) \cdot U \]
\[ F_{uv}(2) = -C_{uv} \cdot F_v(2) \cdot \sqrt{s} \cdot \alpha \]
\[ F_{rv}(2) = -F_r(2) \]

MAX BRAKE FORCE FOR ANTI-SKID
\[ J_{max}(2) = -C_{a}(2) \cdot F_s(2) \]

TOTAL BRAKE FORCE
\[ J_{br}(2) = J_{br}(2) \cdot C \]

LIMIT TO BRAKE FORCE
\[ J_{lim}(2) = 0 \cdot \text{PERCENTAGE DEFLECTION} \]

TOTAL FORCES ON STRUTS
\[ F_{xv}(2) = C_{av} \cdot F_v(2) \cdot U \]
\[ F_{uv}(2) = C_{uv} \cdot F_v(2) \cdot \sqrt{s} \cdot \alpha \]
\[ F_{rv}(2) = F_r(2) \]

TOTAL MOMENTS ON BODY
\[ M_x(2) = C_{mx} \cdot F_v(2) \]
\[ M_y(2) = C_{my} \cdot F_v(2) \]
\[ M_z(2) = C_{mz} \cdot F_v(2) \]

SUMMATION OF FORCES AND MOMENTS
\[ F_{sum} = \sum_{i=1}^{n} F_x(2) \]
\[ F_{y} = \sum_{i=1}^{n} F_y(2) \]
\[ F_{z} = \sum_{i=1}^{n} F_z(2) \]
\[ M_{x} = \sum_{i=1}^{n} M_x(2) \]
\[ M_{y} = \sum_{i=1}^{n} M_y(2) \]
\[ M_{z} = \sum_{i=1}^{n} M_z(2) \]

EOM

FIGURE 4.7-7 (CONTINUED)
LEGEND:

CGx  Orbiter center of gravity coordinates
CGy
CGz

XD(J)  Gear and tip coordinates with respect to datum
YD(J)
ZD(J)

XNED(J)  Gear and tip coordinates in North-East-Down system
YNED(J)
ZNED(J)

\[
[CXN(i)]  \quad \text{North-East-Down to body axes transformation matrix}
\]
\[
[CBH(i)]  \quad \text{Horizontal to body axes transformation matrix}
\]

L  Orbiter latitude
\lambda  Orbiter longitude
RE  Radius of the earth

LR  Runway localizer latitude
\lambda_R  Runway localizer longitude
RL  Local radius of the earth at localizer
\psi_R  Runway azimuth

XG(J)  Gear and tip coordinates from center of gravity
YG(J)
ZG(J)

NRWY  Components of distance from vehicle center of gravity to runway
ERWY

DN(J)  Gear and tip locations relative to runway
DE(J)

RX(J)  Gear and tip locations in runway coordinates
RY(J)

HREF(J)  Runway reference and reference change rate for gear and tips
HREF(J)

H  Vehicle altitude
DHT(J)  Distance from gear and tips to runway

\[
\theta G(J)  \quad \text{Gear deflection}
\]
\[
\dot{\theta} G(J)  \quad \text{deflection rate}
\]

FIGURE 4.7-7  (CONTINUED)
XCP  
YCP  
ZCP  
Gear contact points

P  
Q  
R  
Body rates about body axes

VGX  
VGY  
VGZ  
Orbiter groundspeed components

VXCP(J)  
VYCP(J)  
VZCP(J)  
Velocity components, gear contact points

VXCP(TOT)(J)  
VYCP(TOT)(J)  
VZCP(TOT)(J)  
Contact point total velocity components

VXCPB(J)  
VYCPB(J)  
VZCPB(J)  
Contact point total velocity components in body axes

VXAP(J)  
VYAP(J)  
VZAP(J)  
Attach point velocity components

VZAPB(J)  
Total vertical velocity at attach point in body axes

AP(J)  
Shock strut piston area

PS(J)  
Shock strut air/GN2 pressure

FS(J)  
Shock strut reaction force

CV2(J)  
Damper coefficient

FMAX(J)  
Linear damping force constants

GK  
W

M(J)  
Landing gear linear damping force

FL(J)  
Landing gear velocity squared damping force

FV(J)  
Landing gear total damping force

FG(J)  
Landing force normal to ground

\( \theta \)  
\( \phi \)  
\( \psi \)  
Orbiter attitude angles

FIGURE 4.7-7. (CONTINUED)
Steering command
Steering angle
Tire skid angle
Side force coefficient
Braking force coefficient
Rolling force coefficient
Orbiter velocity in the x-direction
Total force on struts (vertical)
Total force on struts (horizontal)
Maximum braking force for anti-skid
Braking force on each wheel
Total gear forces in body axes
Total gear moments on body
Total LDS forces output to EOM
Total LDS moments output to EOM

NOTE: Circled fractions with a letter over a number are cross reference linking equation elements on separate pages. For example, the output point A on Sheet 1 refers to the input point A on Sheet 2.

FIGURE 4.7-7. (CONTINUED)
tire skid angles, tire braking, rolling, and side force coefficients, and sequential time delay functions. Note that the nose wheel steering actuator is modeled within the math flow for the reference module. The math flow shown should also be modified to utilize a "flat earth" model for runway proximity/touchdown flight regimes.

LDS Validation Methods and Check Cases
Both static and dynamic check cases should be used for LDS validation data generation. Check cases may include static discrete points or consist of dynamic input functions and vehicle touchdown trajectories.

Static check cases would contain discrete inputs such as static loads on the landing gear spring shock strut. The static deflection can then be calculated. The output data would be plotted as in Figure 4.7-R (Ref. 7) and the air/GN₂ spring rate verified.

Dynamic inputs would consist of time-dependent functions input to the LDS simulation and reference modules. A step input to the shock strut could be used to validate air/GN₂ spring-hydraulic damper characteristics. Steering reaction forces and tire skid angle could be verified using quasi-steady relationships involving tire load, velocity, tire side force coefficient, and vehicle steering and yaw angle.

Touchdown trajectories and runway profiles could also be used in formulating check cases. For example, a special runway profile could be constructed and the vehicle "rolled" down a given reference trajectory. LDS response could then be evaluated and comparison plots generated for the desired variables.

LDS Data Base Impact
Data base requirements for verification of the LDS consist of an appropriate reference module, check cases, and tables as required for the various tabular lookups of coefficients. When sufficient hardware testing of the LDS has been completed, the maximum sizes for these tables will be determined. Some variation in storage requirements may result until testing is complete.
FIGURE 4.7-8. MAIN GEAR AIR SPRING CHARACTERISTICS
4.7.1.2 Docking Mechanism Subsystem (DMS)

DMS Description

The DMS provides an active or passive interface to effect a satisfactory Orbiter docking/undocking operation with other orbital vehicles. (A passive docking interface is capable of accepting an active docking system; the active docking mechanism can function in either the active or passive mode.) The DMS comprises the actual docking interface as well as the extendible tunnel in the docking module kit. In the event of a DMS failure which would preclude payload door closure, the DMS may be pyrotechnically jettisoned at a separation plane lying below the Orbiter mold line (Ref. 5).

Figure 4.7-0 (Ref. 9) depicts the principal assemblies and systems which compose a typical active and passive DMS. The primary DMS components and assemblies consist of:

- Guide ring assembly
- Capture latch assembly
- Body-mounted latch assembly
- Base and tunnel assembly
- Attenuator assembly
- Retract system
- Structural ring latch assembly
- Electrical components (not shown specifically in Figure 4.7-0)
- DMS jettison assembly (not shown)
- DMS extendible tunnel (not shown)

Initial contact limit conditions for docking are given in Table 4.7-2 (Ref. 8). After vehicle-to-vehicle alignment is attained (via RCS), secondary docking alignment is made using the guide system mounted on the guide rings of the active and passive vehicles. Capture is effected by a series of latches on the extended ring of the active DMS. Following capture and stabilization, the mated vehicles are drawn together by the guide ring extension/retraction system. Hard dock providing a sealed interface is accomplished using the structural latches mounted on the base and tunnel assembly. All extension, retraction and unlatching functions are crew controlled. Undocking is accomplished through sequential unlatching operations.
FIGURE 4.7-9. ACTIVE AND PASSIVE DMS
TABLE 4.7-2 . DMS INITIAL CONTACT LIMITS

<table>
<thead>
<tr>
<th>CONDITION</th>
<th>LIMIT</th>
</tr>
</thead>
<tbody>
<tr>
<td>Closing velocity</td>
<td>0.5 ft./sec.</td>
</tr>
<tr>
<td>Lateral velocity</td>
<td>0.1 ft./sec.</td>
</tr>
<tr>
<td>Rotational velocity</td>
<td>1.0 deg./sec.</td>
</tr>
<tr>
<td>Miss distance</td>
<td>0.5 ft.</td>
</tr>
<tr>
<td>Angular misalignment</td>
<td>5.0 deg.</td>
</tr>
</tbody>
</table>

DMS Simulation Module Description and Performance Parameters

The DMS software will simulate the operation of the Orbiter DMS during docking/undocking maneuvers. This software module will be executed 10 times per second in the docking/undocking mission phases.

Inputs to the DMS simulation module consist of (Ref. 11):
- Orbiter vehicle state
- Target vehicle state, relative state
- Crew commands for DMS deployment, jettison, and docking/undocking operations
- Electrical power available
- Orbiter and target mass properties

The DMS simulation module will use these inputs to calculate the docking/undocking reaction forces and moments on the Orbiter and target vehicle. Also output are crew response and status indicators for all docking and undocking operations including DMS deployment and jettison.

Vehicle states and relative states in conjunction with DMS specification will be used to calculate the reaction forces and moments on both vehicles due to the operation of the MDS guide rings, retraction system, and attenuators. DMS deployment, jettison and undocking will be simulated as talkback using time delay functions incorporating power available checks. Latching operations will also be simulated with talkback; however, vehicle alignment checks must be made to respond to latching inputs. The performance parameters associated with the DMS are shown.
in Table A.7-3. Figure A.7-10 depicts the DMS simulation module interfaces with other simulation modules.

**DMS Reference Data Sources and Data Formats**

Complex docking/undocking operations provide a dynamic environment for the DMS. This environment requires comprehensive reference data for validation of the DMS simulation module. High-fidelity, comprehensive reference data can best be generated by a reference software module similar in function to the Figure 4.7-11 functional flow diagram.

Reference 10 describes, in detail, a well-developed DMS simulation software program which can be implemented as a DMS reference module. The Ring-Finger Docking Dynamics (RFDD) digital program was developed as an engineering/analysis tool for use in determining the docking system loads and attendant vehicular motion resulting from docking two vehicles that have an androgynous, six-hydraulic-attenuator, guide ring, docking interface similar to that designed for the Apollo/Soyuz Test Project (ASTP). Presently the program will analyze either: (1) docking of the Apollo and Soyuz or (2) Shuttle Orbiter to another Orbiter. The RCS subroutine is modified to accommodate the appropriate combination (Ref. 10). It is conceivable that other docking combinations could be simulated with similar program changes (e.g. Soyuz-Orbiter, Space Lab-Orbiter, etc.).

The RFDD program treats the two vehicles and the docking ring as rigid bodies. Each rigid body is modeled with six degrees of freedom. A structurally compliant, hydraulically attenuated docking interface is simulated between the docking ring and the active vehicle. All docking operations except tunnel sealing, hard structural latching, and hard docking dynamics are mathematically simulated (Ref. 10).

Inputs to the RFDD program are defined as (Ref. 10):
- Vehicle (active and passive) mass properties
- Vehicle control systems (active and passive)
- Attenuator locations and design characteristics
- DMS design characteristics and constraints
- Run configuration indicators
- Integration interval controls

4.7-25
<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>PARAMETER</th>
<th>TYPEa</th>
</tr>
</thead>
<tbody>
<tr>
<td>$I_o$</td>
<td>Orbiter inertia tensor</td>
<td>I</td>
</tr>
<tr>
<td>$I_t$</td>
<td>Target inertia tensor</td>
<td>I</td>
</tr>
<tr>
<td>$M_o$</td>
<td>Orbiter mass</td>
<td>I</td>
</tr>
<tr>
<td>$M_t$</td>
<td>Target mass</td>
<td>I</td>
</tr>
<tr>
<td>$C_{M_o}$</td>
<td>Orbiter center of mass</td>
<td>I</td>
</tr>
<tr>
<td>$C_{M_t}$</td>
<td>Target center of mass</td>
<td>I</td>
</tr>
<tr>
<td>$\mathbf{r}, \mathbf{v}$</td>
<td>Orbiter position, velocity</td>
<td>I</td>
</tr>
<tr>
<td>$\mathbf{S}<em>{\mathbf{r}}, \mathbf{S}</em>{\mathbf{v}}$</td>
<td>Target relative position and velocity</td>
<td>I</td>
</tr>
<tr>
<td>$\phi_o, \phi_o, \phi_o$</td>
<td>Orbiter attitude and attitude rates</td>
<td>I</td>
</tr>
<tr>
<td>$\phi_o, \phi_o, \phi_o$</td>
<td>Target relative attitude and attitude rates</td>
<td>I</td>
</tr>
<tr>
<td>$\delta \mathbf{v}_c$</td>
<td>Orbiter-target closing velocity limit</td>
<td>DB</td>
</tr>
<tr>
<td>$\delta \mathbf{v}_l$</td>
<td>Orbiter-target lateral velocity limit</td>
<td>DB</td>
</tr>
<tr>
<td>$\delta \mathbf{v}_r$</td>
<td>Orbiter-target rotational velocity limit</td>
<td>DB</td>
</tr>
<tr>
<td>$S_{\mathbf{m}}$</td>
<td>Orbiter-target miss distance limit</td>
<td>DB</td>
</tr>
<tr>
<td>$S_{\mathbf{m}}$</td>
<td>Orbiter-target angular misalignment limit</td>
<td>DB</td>
</tr>
<tr>
<td>$S_{\mathbf{x}<em>d}, S</em>{\mathbf{x}<em>d}, S</em>{\mathbf{x}_d}$</td>
<td>Relative position of Orbiter DMS</td>
<td>DB</td>
</tr>
<tr>
<td>$S_{\mathbf{x}<em>d}, S</em>{\mathbf{x}<em>d}, S</em>{\mathbf{x}_d}$</td>
<td>Relative (to Orbiter) position of target DMS</td>
<td>CP</td>
</tr>
<tr>
<td>$C, R_{ddms}$</td>
<td>DMS deploy command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$C, R_{jddms}$</td>
<td>DMS jettison command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$C, R_{cdms}$</td>
<td>DMS capture latch-un latch command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$C, R_{rdms}$</td>
<td>DMS target retract-extend command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$C, R_{bdms}$</td>
<td>DMS body-mounted latch-un latch command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$C, R_{sdms}$</td>
<td>DMS structural ring latch-un latch command/response</td>
<td>I/P</td>
</tr>
<tr>
<td>$K_s C_{d_{l}}$</td>
<td>DMS attenuator characteristics (spring constant, damping coefficient, travel)</td>
<td>DB</td>
</tr>
<tr>
<td>$S F_{o, dms}$</td>
<td>Orbiter forces due to DMS</td>
<td>CP</td>
</tr>
<tr>
<td>$S F_{t, dms}$</td>
<td>Target forces due to DMS</td>
<td>CP</td>
</tr>
<tr>
<td>$S F_{o, dms}$</td>
<td>Orbiter moment due to DMS</td>
<td>CP</td>
</tr>
</tbody>
</table>

*TABLE 4.7-3. DMS SIMULATION MODULE PERFORMANCE PARAMETERS*
<p>|</p>
<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>PARAMETER</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>( S_{L_{t,dms}} )</td>
<td>Target moment due to DMS</td>
<td>CP</td>
</tr>
<tr>
<td>( P_{dms} )</td>
<td>Electrical power load due to DMS</td>
<td>P</td>
</tr>
</tbody>
</table>

<sup>a</sup><br> I - Input  
P - Performance Parameter  
CP - Critical Performance Parameter  
DB - Data Base Input  
<sup>b</sup> - Denotes 2 parameters - command and response
FIGURE 4.7-10 DMS SIMULATION MODULE INTERFACES
FIGURE 4.7-11. DMS REFERENCE MODULE FUNCTIONAL FLOW DIAGRAM

4.7-29

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
CALCULATE INITIAL RELATIVE DOCKING MECHANISM FORCES AND MOMENTS

CAPTURE

NO

YES

GUIDE RING RETRACT

NO

YES

CALCULATE RETRACT DMS RELATIVE FORCES AND MOMENTS

RETURN

FIGURE 4.7-11. (CONTINUED)
Print and plot output controls
RFDD program output consists of real-time print and optional time-history plots of DMS and vehicle loads and motions (Ref. 10).

The RFDD program, when used as a reference module, should be combined with a driver which would ensure DMS Simulation Module compatibility and incorporate time-delay talkback functions for DMS tunnel extension, jettison, and undocking operations.

DMS Validation Methods and Check Cases
Check cases for validation of DMS deployment, jettison, and undocking command/response functions can be composed of the required command sequences to verify the proper talkback indicators.

Docking operations should be verified with several check cases containing appropriate velocity and misalignment variations to exercise the docking dynamics reference and simulation modules for each docking target planned. A typical check case should start the two vehicles within the specified miss distance and misalignments, but separated by a relatively large axial distance. The two vehicles are then mathematically positioned axially at some predetermined closing rate. As contact occurs, load computations, vehicle dynamic calculations, and latching simulation continue through draw down. The printed and/or plotted output of both the simulation and reference modules is then analyzed manually or automatically -- as determined by the user.

DMS Data Base Impact
Once the DMS is defined and the appropriate reference module is selected, the primary DMS simulation verification impact upon the verification data base will be in the areas of resident reference data and check cases. Additions to these requirements must be included for each docking target considered.
4.7.1.3 Separation Mechanisms Subsystem

This section discusses those mechanical, pyrotechnic-assisted subsystems which provide for ET/SRB and Orbiter/ET separation during the ascent mission phase.

Separation Mechanisms Description

Shuttle vehicle Orbiter/ET and ET/SRB attach points, umbilical connections and corresponding separation mechanism locations are shown in Figure 4.7-12 (Ref. 12).

ET/SRB Separation - The ET/SRB separation mechanisms provide for efficient, reliable separation of the SRB's (SRB's indicates both solid rocket boosters) from the mated Orbiter/ET vehicle. Included in the ET/SRB separation mechanisms are the fore and aft SRB separation fittings and the SRB boost separation motors (BSM) as shown in Figures 4.7-13, 4.7-14, and 4.7-15 (Ref. 12).

ET/SRB separation commands are generated by Guidance, Navigation, and Control (GN&C) to a sequencer in the Electrical Power Distribution and Control Subsystem (EPDCS). At approximately 125 seconds from launch, pyrotechnic devices in the ET/SRB separation fittings (see Figures 4.7-13 and 4.7-14) are initiated to "guillotine" the SRB's from the ET. The BSM, along with SRM thrust tail-off, direct the SRB's away from the Orbiter/ET. Figure 4.7-16 depicts the nominal separation of an SRB (Ref. 13).

Orbiter/ET Separation - Orbiter/ET separation mechanisms ensure complete separation of the ET from the Orbiter prior to orbital insertion. Structural Orbiter/ET separation occurs at the single forward and 2 aft ET attach points shown in Figure 4.7-12. Figures 4.7-17 and 4.7-18 (Ref. 14) depict typical fore and aft Orbiter/ET separation fittings. Orbiter/ET umbilical disconnect fittings are also included in the separation mechanisms.

Separation sequencing commands from GN&C through the EPDCS, including pyrotechnic initiation, provide structural release of the ET from the Orbiter as shown the Figure 4.7-19 (Ref. 12) separation maneuver.

Separation Mechanisms Simulation Module Description and Performance Parameters

Simulation of both the ET/SRB and Orbiter/ET separation mechanisms will be accomplished using similar techniques involving sequential logic and mechanical

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-12. ORBITER/ET AND ET/SRB ATTACH POINTS
ET SUPPORT FRAME (INTER-TANK)

SRB THRUST LONGERON

ET M/L

SRB M/L

SRB

DETAIL A

ET FITTING

SRB FITTING

FRANGIBLE NUT

BOLT

SMSI INITIATOR

3 REQD

BOLT IN RETRACTED POSITION

THRUSTER INITIATOR SWITCH (POTENTIAL)

DETAIL B

FIGURE 4.7-13. TYPICAL FORWARD ET/SRB SEPARATION FITTING
FIGURE 4.7-14. TYPICAL AFT ET/SRB SEPARATION FITTING
DIMENSIONS
LENGTH........ 145.1 FT
DIAMETER....... 142.3 IN.

4 SEPARATION MOTORS
(23,030 LB THRUST) EACH
SRB-ET AFT ATTACH

NOZZLE & TVC
AFT SKIRT & LAUNCH SUPPORT

GROSS WT........ 1,163,500 LB
RECOVERY WT...... 154,250 LB
THRUST (SL) (INITIAL) 2.6M LB
NOZZLE EXPANSION RATIO 7:1
MEOP.............. 900 PSIA

FIGURE 4.7-15. SOLID ROCKET BOOSTER (NOTE SEPARATION MOTORS)
FIGURE 4.7-17. FORWARD ORBITER/ET SEPARATION FITTING
FIGURE 4.7-18. AFT ORBITER/ET SEPARATION FITTING
OMS THRUST VECTOR

OMS ORB INSERTION
- OMS ORBIT INSERTION BURN

RCS PITCH MANEUVR
- PITCH TO ANGLE FOR OMS BURN (2 FWD, 2 AFT THRUSTERS)

RCS TRANSLATION
- STRUCTURAL RELEASE
- CONSTANT ATT TRANSLATION (2 FWD THRUSTERS AFT MODULATED)

MEO
- SSME SHUTDOWN
- INITIATE FWD RCS DEPLOYMENT
- UMBILICAL DISC
- ISO VALVE CLOSURE VERIFICATION

FIGURE 4.7-19. ORBITER/ET NOMINAL SEPARATION MANEUVER
functions to effectively model the actual system (Ref. 11).

Figure 4.7-20 depicts the separation mechanisms subsystem simulation module interfaces. Table 4.7-4 is a listing of the module parameters.

**ET/SRB Separation Mechanisms Simulation** - The ET/SRB separation mechanisms simulation module will receive pyro-initiate and separation motor ignition commands from GN&C. Response to pyrotechnic SRB separation and BSM will be simulated via "talkback." As BSM burn time is approximately 0.75 seconds, BSM thrust will be simulated with the proper impulsive thrust vector for each rocket motor. SRB separation produces no appreciable forces or moments on the Orbiter/ET vehicle unless a separation failure occurs. Tracking of the separated SRB continues until SRB burnout.

Sequencing of SRB separation will set flags to load new data tables in the Aerodynamics and Mass Properties simulation modules, as shown in Figure 4.7-20.

**Orbiter/ET Separation Mechanisms Simulation** - Orbiter/ET separation simulation will use sequential time delay functions to provide the "talkback" response for the Orbiter/ET separation mechanism pyrotechnic devices and Orbiter/ET umbilical disconnects. Flags will also be set for aerodynamic and mass properties table re-initializations. Significant separation forces and moments are applied to the Orbiter due to the two rear ball and socket structural attachment designs.

The Orbiter reaction separation forces and moments for the ET rear ball and socket and forward attachments will be computed using simultaneous equation solutions incorporating mechanical functions to effectively model the structural attachment design. Computed forces and moments will be output to the Equations of Motion (EOM) simulation module as shown in Figure 4.7-20.

**Separation Mechanisms Subsystem Reference Data Sources and Data Formats**

Successful ET/SRB separation has little effect on Orbiter EOM; thus no reference software module is necessary. Verified response to the separation pyrotechnic commands and BSM ignition and corresponding burn time will assure successful simulated ET/SRB separation. Separated SRB relative-state tracking will provide post separation Orbiter/ET-SRB proximity relationships.
FIGURE 4.7-20. SEPARATION MECHANISMS SUBSYSTEM SIMULATION MODULE INTERFACES
### TABLE 4.7-4. SEPARATION MECHANISM SUBSYSTEM SIMULATION MODULE PERFORMANCE PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>SRB pyro-device separation command/response^b</td>
<td>I, CP</td>
</tr>
<tr>
<td>BSM ignition command/response</td>
<td>I, CP</td>
</tr>
<tr>
<td>BSM coordinates</td>
<td>DB</td>
</tr>
<tr>
<td>BSM thrust</td>
<td>DB</td>
</tr>
<tr>
<td>BSM burn time</td>
<td>DB</td>
</tr>
<tr>
<td>SRB tail-off thrust</td>
<td>DB</td>
</tr>
<tr>
<td>SRB mass properties</td>
<td>I</td>
</tr>
<tr>
<td>SRB relative state vector</td>
<td>I</td>
</tr>
<tr>
<td>ET umbilical pyro-disconnect command/response</td>
<td>I, CP</td>
</tr>
<tr>
<td>ET separation command/response</td>
<td>I, CP</td>
</tr>
<tr>
<td>ET separation forces on Orbiter</td>
<td>CP</td>
</tr>
<tr>
<td>ET separation moments on Orbiter</td>
<td>CP</td>
</tr>
<tr>
<td>ET mass properties</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter mass properties</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter/ET forward attach point coordinates</td>
<td>DB</td>
</tr>
<tr>
<td>Orbiter/ET forward attach point design constraints</td>
<td>DB</td>
</tr>
<tr>
<td>Orbiter/ET aft (2) attach point coordinates</td>
<td>DB</td>
</tr>
<tr>
<td>Orbiter/ET aft attachment ball function</td>
<td>DB</td>
</tr>
<tr>
<td>Orbiter/ET aft attachment socket function</td>
<td>DB</td>
</tr>
<tr>
<td>Ball/socket coefficient of friction</td>
<td>DB</td>
</tr>
<tr>
<td>Orbiter state vector</td>
<td>I</td>
</tr>
<tr>
<td>Orbiter attitude and attitude rates</td>
<td>I</td>
</tr>
<tr>
<td>ET relative state</td>
<td>I</td>
</tr>
<tr>
<td>ET relative attitude and attitude rates</td>
<td>I</td>
</tr>
</tbody>
</table>

^I - Input  
P - Performance Parameter  
CP - Critical Performance Parameter  
DB - Data Base Input  

^b Indicates 2 parameters (command and response)
A suitable reference data source for Orbiter/ET separation is described in Figure A.7-21 math flown. The subroutine shown, ABIND, is used in the SVDS simulation/analysis program. For verification purposes, ABIND would be incorporated into a special driver as described in Section 4.2.

Inputs to ABIND consist of:
- Position vectors to the Orbiter/ET attach points
- Relative position vectors for the Orbiter and ET
- Several transformation matrices (ECI to body coordinates, body coordinates to attach points, etc.)
- Vehicle attitude rates for the Orbiter and ET
- Relative vehicle attitude rates for the Orbiter and ET
- Orbiter and ET mass properties
- Radii of rear attach point ball and socket
- Spring constants, damping coefficients, and coefficients of friction for ball and socket
- A defined region about each socket

Orbiter reaction forces and moments from the separated ET are computed for output to vehicle EOM.

Separation Mechanisms Subsystem Validation Methods and Check Cases

Since ET/SRB and Orbiter/ET separations are dynamic events, dynamic check cases are required to accurately verify the Separation Mechanisms Subsystems simulation modules.

In the case of the ET/SRB separation mechanisms, verification includes the checkout of: (1) the proper sequencing of pyrotechnic devices and BSM ignition, (2) correct BSM burn time and thrust, (3) SRB tail-off thrust, and (4) tracking of the SRB after separation to monitor Orbiter/ET-SRB proximities. The above parameters can be monitored during an actual simulation run to validate successful SRB separation mechanisms simulation.

Two parameter types must be verified to accurately check proper Orbiter/ET separation mechanism simulation. The correct pyrotechnic sequencing can be...
SUBROUTINE ABIND

C COMPUTE TOTAL NUMBER OF NODES DEFINED ON ALL VEHICLES

JH1=JHODE(1)+JHODE(2)

C ZERO FORCES AND MOMENTS ON FAIRING VEHICLE IF NO NODES ARE DEFINED

DO 100 I=1,3
FBLL(I)=0.0

100 TBLL(I)=0.0

C START SECONDARY VEHICLE DO LOOP. ZERO FORCES ON SECONDARY VEHICLES

DO 300 JV=2,25
JV=JHAX+JV-1

DO 120 I=1,3
FBLL(JV+I)=0.0

120 TBLL(JV+I)=0.0

C TEST TO DETERMINE IF ANY NODES HAVE BEEN DEFINED ON VEHICLE JV

IF(JHODE(JV-1).EQ.0) THEN

CONT. ON FG 2

ABIND

FG 1 OF 17

FIGURE 4.7-21. ORBITER/ET AFT SEPARATION MECHANISM REFERENCE MODULE

4.7-45

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FIGURE 4.7-21. (CONTINUED)
CALL MULT(3,3,1,BJTP(IV+1,1),PB5(1,N),PBST)

CALL MULT(3,3,1,BJTP(XI790(IV+1),V21)

CALL CROSS(PQ4(IV-1),PB5(1,N),SAVE1)

CALL MULT(3,3,1,BJTP(IV+1,1),SAVE,V2)

CALL CROSS(PQ4,PB1(1,N),V1)

GO TO 140 I=1,3

DPN(I)=XAS(I)+PBST(I)-PB1(I,N)

DVN(I)=V2(I)+V1(I)-V1(I)

SBALL(3n-2+24+1-1)=DPN(I)

SBALL(3N-2+24+1-1)-DVN(I)

C TRANSFORM RELATIVE DISPLACEMENT AND VELOCITY INTO NODE COORDINATE SYST

CALL MULT(3,3,1,UP6,DPN,DPNT)

CALL MULT(3,3,1,UP6,DYN,DYNT)

GO TO 142 I=1,3

SBALL(3n-2+86+1-1)=DPNT(I)

SBALL(3N-2+120+1-1)=DYN(I)

CONT. ON PG 4

ABINGO

FIGURE 4.7-21. (CONTINUED)
 C TEST TO DETERMINE IF BALL IS SEATED IN SOCKET ENCLOSURE

IF(DPNT(3).LE.0)  
  T
  GO TO 144

C TEST TO DETERMINE IF BALL IS UNDER RECONTACT PLANE

ABS(DPNT(1)).LE.XPLANE(N)/2. .AND. ABS(DPNT(2)).LE.YPLANE(N)/2.)  
  T
  GO TO 238

CONT. ON PG 5

FIGURE 4.7-21. (CONTINUED)
C START COMPUTATIONS FOR BALL SEATED IN SOCKET

CONTINUE

C COMPUTE AMPLITUDE OF NODE DISPLACEMENT VECTOR AND UNIT VECTOR IN C DIRECTION OF DISPLACEMENT IN NODE COORDINATE SYSTEM.

CALL UYVEC(DPNT, UOPNT)

DPNT = VECDG(DPNT)

IF(RAD.1(N).GT.RADS(IN)+DPNT)

GO TO 260

C COMPUTE RELATIVE VELOCITY VECTOR OF POINTS IN CONTACT

CALL MULT(3,3,1,USB,POR,SAVE)

CALL MULT(3,3,1,USB,POR(IY+1),SAVE)

DO 149 I=1,3

SAVEP(I) = RADL(N)+UOPNT(I)

Saves(I) = RADS(N)+UOPNT(I)

CALL CROSS(SAVE1,SAVEP,VIN)

CONT. ON PG 6

FIGURE 4.7-21. (CONTINUED)
CALL CROSS(SAVE, SAVES, V2N)

DO 151 I=1,3

DVNTN(I)=DVNT(I)+V2N(I)-V1N(I)

CALL SALL(I*N-2+184+I-11)-DVNTN(I)

C COMPUTE MAGNITUDE OF COMPONENT OF BALL RELATIVE VELOCITY ALONG DPNI(I)
C VECTOR, AND COMPUTE STRUCTURAL DAMPING NORMAL FORCE

DVHAG=DOT(DVNTN, UDPTN)
FND=OVHAG*CKI(IN)

C COMPUTE STRUCTURAL INFRAINGEMENT ALONG WITH MAGNITUDE OF NORMAL AND
C FRICIONAL FORCES AT NODE

GSPG=ASS(6D03(IN)+DPNTM-RAOL(IN))
FN=GSPG*SKI(IN)+FND
FF=FL*UFI(N)
SALL(I*N+173)=FM
SALL(I*N+175)=FF

C COMPUTE UNIT VECTOR IN PLANE PERPENDICULAR TO DPNI(I) AND DIRECTED ALO
C PROJECTION OF VELOCITY VECTOR DVNTN(I) INTO THIS PLANE (PLANE IS
C APPROXIMATELY TANGENT TO ENCLOSURE AT PT. OF CONTACT)

CALL UNVEC(DVNTN, UDPTN)

CALL CROSS(UDVNTN, UDPTN, SAVE)

CALL CROSS(SAVE, UDVNTN, UVPROJ)

C COMPUTE NORMAL AND FRICTIONAL FORCE VECTORS FOR BOTH PRIMARY AND SECON
C VEHICLES AND TRANSFORM FORCES INTO RESPECTIVE VEHICLE REF. COORD. SIST

DO 150 I=1,3

FMP(I)=FM(I)-UDPTN(I))
FFP(I)=FF(I)-UVPROJ(I))

CONT. ON PG 7 ASIND

FG.R OF 17

FIGURE 4.7-27 (CONTINUED)

4.7-50

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FIGURE 4.7-21. (CONTINUED)
CALL CROSS(ARRAY1(I),ARRAY2(I),TP(I,N))

CALL CROSS(ARRAY1(I),ARRAY2(I),TP(I,N))

DO 162 I=1,3

DO 162 I=1,3

SBALL(3*N-272*I-11,TP(I,N))

C GO TO END OF NODE DO LOOP

GO TO 280

C START COMPUTATIONS FOR BALL IN CONTACT WITH EDGE OF SOCKET

CONTINUE

C COMPUTE UNIT VECTOR ALONG PROJECTION OF OPNT(I) INTO SOCKET SUPPORT PL

CONT. ON PG 9

FIGURE 4.7-21. (CONTINUED)
C COMPUTE VECTOR FROM CENTER OF BALL TO EDGE OF SOCKET IN A PLANE DEFINED BY CI(I) AND DPNT(I). COMPUTE MAGNITUDE OF VECTOR

DO 210 I=1,9

210      C3(I)=C1(I)-DPNT(I)
              CSH=VECMG(C3)
              CALL UHVEC(C3,UCS)

C TEST TO DETERMINE IF BALL IS IN CONTACT WITH EDGE OF SOCKET

IF(RADSIN.LT.CSH)
  T
    GO TO 260
  F

C COMPUTE RELATIVE VELOCITY VECTOR OF POINTS IN CONTACT

CALL MULT(S,S,1,UP8,POA,SAVE1)

CALL MULT(S,S,1,USB,POA(V+1),SAVE1)

DO 212 I=1,9

212      SAVEP(I)=RADL(N)XUQXY(I)

CALL CROSS(SAVE1,SAVEP,VNI)

CONT. ON PG 10

FIGURE 4.7-21. (CONTINUED)
CALL CROSS(SAVE, SAVES, V2N)

DO 214 I=1,3

DVNTN(I)=DVNT(I)+V2N(I)-V1N(I)

SBALL(N-2+16*+I-1)-DVNTN(I)

C COMPUTE MAGNITUDE OF COMPONENT OF BALL RELATIVE VELOCITY ALONG CS(I)
C VECTOR, AND COMPUTE STRUCTURAL DAMPING NORMAL FORCE

DVHAG=DOT(DVNTN, UC3)
FND=DVHAG*CKA(N)

C COMPUTE STRUCTURAL INFRINGEMENT AND MAGNITUDE OF NORMAL AND FRICTIONAL
C FORCES AT POINT OF CONTACT

DSPC=ROSS(RASS(N)-C3I)
FN=DSPG*SKA(N)+FND
FF=FN*UPR(N)
SEALL(N+16*I)-FN
SBALL(N+16*I)=FF

C COMPUTE UNIT VECTOR IN A PLANE PERPENDICULAR TO CS(I) VECTOR AND DIRECT
C ALONG THE PROJECTION OF VELOCITY VECTOR, DVNTN(I), INTO THIS PLANE

CALL UVEC(DVNTN, UDVNTN)

CALL CROSS(UDVNTN, UC3, SAVE)

CALL CROSS(SAVE, UDVNTN, UVPROJ)

C COMPUTE NORMAL AND FRICTIONAL FORCE VECTORS FOR BOTH PRIMARY AND SECOND
C VEHICLES AND TRANSFORM FORCES INTO RESPECTIVE VEHICLE REF. COORD. SYST

DO 220 I=1,9

FFP(I)=FF+FFP(UVPROJ(I))
FN3(I)=FN+FN3(UVPROJ(I))

CONT. ON PG 11

FIGURE 4.7-21. (CONTINUED)
FIGURE 4.7-21. (CONTINUED)
C START COMPUTATIONS FOR BALL IN CONTACT WITH SUPPORT PLANE

IF (DPNT(3).GE.RADSIN11) THEN
    C TEST TO DETERMINE IF BALL IS IN CONTACT WITH SUPPORTING PLANE
    IF (DPNT(3).GE.RADSIN11) THEN
        C COMPUTE MAGNITUDE OF COMPONENT OF BALL RELATIVE VELOCITY ALONG DPNT(3)
        SAVE(1)=0.0
        SAVE(2)=0.0
        SAVE(3)=DPNT(3)
        CALL UVVEC(SAVE,DPNT31)
        C COMPUTE RELATIVE VELOCITY VECTOR OF POINTS IN CONTACT
        CALL MULT(3,3,1,UPB,DPD,SAVE1)
    END IF
END IF
CALL HULL(3,3.1,USB,PGA(IV+1),SAVE)

SAVEP(1)=QPT(1)
SAVEP(2)=QPT(2)
SAVEP(3)=0.0

DO 235 I=1,3

SAVE(I)=AROS(IN)=QPT3(I)
CALL CROSS(SAVE1,SAVEP,VIN1)
CALL CROSS(SAVE1,SAVE1,V2N1)

DO 241 I=1,3

DVNT(I)=DVNT(I)+V2N(I)-VIN(I)

SBALL(3xN-2+104+I-1)=DVNT(I)

C COMPUTE STRUCTURAL DAMPING NORMAL FORCE

DYKA=DOT(DVNTN,UPNT3)
FND=DVHAG=EXP(IN)

C COMPUTE MAGNITUDE OF NORMAL AND FRICTIONAL FORCES

DPSC=ABS(DYKAS(N)-UPNT3(I))
FN=DPSC=SKP(IN)+FND
FF=FN=UPP(IN)
SBALL(N-168)=FN
SBALL(N-170)=FF

C COMPUTE UNIT VECTOR ALONG PROJECTION OF VELOCITY VECTOR (CENTER OF C BALL) INTO SUPPORTING PLANE

CALL UNVEC(DVNTN,UVHVTN)

CALL CROSS(UVHN,UVHVTN,SAVE)

CONT. ON PG 14

FIGURE 4.7-21. (CONTINUED)
CALL CROSS(3AVE, UDVNTH, UVPROJ)

C COMPUTE NORMAL AND FRICTIONAL FORCES ON BOTH PRIMARY AND SECONDARY VEH
C AND TRANSFORM FORCES INTO RESPECTIVE VEHICLE REF. COORD. SYSTEMS.

DO 240 I = 1, 3

FNP(I) = FNP(I) + UOPNT3(I)
FFP(I) = FFP(I) + UVPROJ(I)
FNS(I) = FNS(I) - UOPNT3(I)
FFS(I) = FFS(I) - UVPROJ(I)

CALL HTRAXMP(UBP(I, 1, N1), FNP, FNP)

DO 242 I = 1, 3

FP(I, N1) = FNP(I) + FFP(I)
FS(I, N1) = FNS(I) + FFS(I)

CALL HTRAXMP(UBS, FNS, FNS)
CALL HTRAXMP(UBS, FFS, FFS)

CALL HTRAXMP(UBP, FNS, FNS)

CONT. ON PG 15

FIGURE 4.7-21. (CONTINUED)
FIGURE 4.7-21. (CONTINUED)
FIGURE 4.7-21. (CONTINUED)
validated with a simple sequence check of the desired pyrotechnic parameter. After verifying the pyrotechnic sequencing, the actual Orbiter/ET separation forces and moments due to the aft attach points must be verified. These forces and moments can best be validated through the use of a reference module similar to the one previously discussed. A check case incorporating a specific reference trajectory should be developed and exercised with the simulation and reference modules. Analysis of comparison plots of the simulation data and reference data would provide sufficient verification of the simulation module.

Previous simulations of Orbiter/ET separation have shown approximate aft attach point maximum forces of:

- Right rear attach point; $Fx = -1092.0$ lbs.
  $Fy = -2.0$ lbs.
  $Fz = 200.0$ lbs
- Left rear attach point; $Fx = -713.0$ lbs.
  $Fy = -220.0$ lbs.
  $Fz = 40.0$ lbs.

(Note: ET coordinate system)

Separation Mechanisms Subsystem Data Base Impact

Separation Mechanisms Subsystem verification is expected to have a minimal impact upon the verification data base as only various pyrotechnic sequencing checks, a small reference module for the ET aft attachment separation forces and moments, and check cases incorporating resident reference trajectories are required.
4.7.1.4 Actuation Mechanisms Subsystem (AMS)

AMS Description

The Shuttle AMS provides for crew- or computer-initiated control of various mechanical devices. Actuators used on the Shuttle function as servomechanisms (i.e., power-amplifying feedback control systems) in which the controlled variable is mechanical position (Ref. 15). Both electromechanical and hydraulic actuators are included, along with their corresponding valves, switches, servomotors, and linkages.

Electromechanical actuators receive as inputs electronic control signals. A servomotor or electronic switch is then used, along with a feedback loop, to effect the commanded mechanical position. Figure 4.7-22 (Ref. 15) depicts a general block diagram of an electromechanical actuator. Electromechanical actuators are used on the Shuttle for control of:
- Payload bay doors and radiator positions
- The Payload Deployment and Retrieval System (see Section 4.7.1.5, PDRS)
- Docking tunnel extension and docking operations (see Section 4.7.1.2, DMS)
- OMS gimbal position
- Drag chute engagement
- Various other remotely operated doors and latches (star tracker door, ADS and RCS deployment, umbilical doors, etc.)

Hydraulic actuators generally act as mechanical linkages in controlling mechanical position. Hydraulic power from the Orbiter HPS (Section 4.7.1.6) is used in conjunction with servovalves, regulators, and power amplifiers (hydraulic cylinders) to provide the commanded mechanical position. As hydraulic actuators are servomechanisms, a control feedback loop is also used as shown in the Figure 4.7-23 block diagram (Ref. 15). Hydraulic actuators are employed for control of:
- Landing gear uplock release, extension, steering, and "1-G" retraction (see Section 4.7.1.1)
- Orbiter braking and antiskid functions (discussed in Section 4.7.1.1)
- Aero-surface positions (including body flap)
- Main engine gimbal position and shutoff valves
- SRB gimbal position (note: each SRB incorporates a self-contained HPS and therefore does not interface with the Orbiter HPS (Ref. 16))
**FIGURE 4.7-22. BLOCK DIAGRAM; ELECTROMECHANICAL ACTUATOR (TYP)**

**FIGURE 4.7-23. BLOCK DIAGRAM; HYDRAULIC ACTUATOR (TYP)**
AMS Simulation Module Description and Performance Parameters

Shuttle AMS simulation is discussed in this section as two submodules: Electromechanical and Hydraulic.

Electromechanical Actuation Simulation Module - Electromechanical actuator simulation will provide the necessary real-world actuator representation desired in a training simulator. Shuttle electromechanical actuators will be modeled using two fidelity-defining methods.

Several electromechanical actuators will be simulated using time-delay functions to effect "talkback" response. Inputs to this type of actuator consist of crew/computer device position signals, switch positions, and electrical power available (from Orbiter EPS). Output will represent the "talkback" response to indicate mechanical position and electrical power required for the desired operation. Actuator functions modeled with this technique consist of:

- Docking tunnel extension
- Drag chute engagement
- Operation (open and closure) of various remotely-operated doors and latches

The remaining electromechanical actuators will be simulated with a more complex technique. This technique will use specific transfer functions and control feedback loops similar to the Figure 4.7-24 diagram (Ref. 15). The exact transfer functions and control logic (determined from hardware tests) will simulate non-linear actuator characteristics involving friction, hysteresis, deadband zones, and combined electrical power load effects to model actuator lags, overshoots, and rise time variations (Ref. 11).

Inputs will be similar to those discussed in the "talkback" model; however, outputs will be a dynamic mechanical position, thrust vector, and/or crew/computer responses as indicated in the Figure 4.7-25 diagram of Electromechanical Actuator Mechanisms Simulation Module Interfaces. Performance Parameters associated with electromechanical actuator simulation are given in Table 4.7-5.

Hydraulic Actuation Mechanisms Simulation Module - Most Shuttle hydraulic actuators will be simulated in a manner similar to that used for complex electromechanical actuator simulation. Only the landing gear uplock release and extension retract
LEGEND:

R(s) = input command
E(s) = actuating signal
C(s) = output command
G(s) = direct transmission function
H(s) = feedback transfer function

FIGURE 4.7-24. FEEDBACK CONTROL SYSTEM BLOCK DIAGRAM
### TABLE 4.7-5. AMS SIMULATION MODULES PERFORMANCE PARAMETERS

<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DESCRIPTION</th>
<th>TYPE&lt;sup&gt;C&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>δ&lt;sub&gt;c&lt;/sub&gt;</td>
<td>Commanded mechanical position</td>
<td>I</td>
</tr>
<tr>
<td>δ&lt;sub&gt;rel&lt;/sub&gt;</td>
<td>Limitied commanded mechanical position</td>
<td>P</td>
</tr>
<tr>
<td>ε</td>
<td>Position error command</td>
<td>P</td>
</tr>
<tr>
<td>{δ, \dot{δ}, \ddot{δ}}</td>
<td>Mechanical position deflection, rate, and acceleration</td>
<td>CP</td>
</tr>
<tr>
<td>{δ&lt;sub&gt;lim&lt;/sub&gt;, \dot{δ}&lt;sub&gt;lim&lt;/sub&gt;, \ddot{δ}&lt;sub&gt;lim&lt;/sub&gt;}</td>
<td>Limitied mechanical position deflection, rate, and acceleration</td>
<td>P</td>
</tr>
<tr>
<td>{δ&lt;sub&gt;max&lt;/sub&gt;, \dot{δ}&lt;sub&gt;max&lt;/sub&gt;, \ddot{δ}&lt;sub&gt;max&lt;/sub&gt;}</td>
<td>Maximum mechanical position deflection, rate and acceleration</td>
<td>DB</td>
</tr>
<tr>
<td>E</td>
<td>Engine thrust</td>
<td>I</td>
</tr>
<tr>
<td>K</td>
<td>Output thrust vector (where applicable)</td>
<td>CP</td>
</tr>
<tr>
<td>K&lt;sub&gt;r&lt;/sub&gt;</td>
<td>Forward gain</td>
<td>DB</td>
</tr>
<tr>
<td>K&lt;sub&gt;p&lt;/sub&gt;</td>
<td>Rate feedback gain</td>
<td>DB</td>
</tr>
<tr>
<td>{f(s)}</td>
<td>Actuator transfer functions</td>
<td>DB</td>
</tr>
<tr>
<td>E&lt;sub&gt;a&lt;/sub&gt;</td>
<td>Electrical power available</td>
<td>I</td>
</tr>
<tr>
<td>E&lt;sub&gt;r&lt;/sub&gt;</td>
<td>Electrical power required</td>
<td>P</td>
</tr>
<tr>
<td>E&lt;sub&gt;f&lt;/sub&gt;</td>
<td>Electrical power factor</td>
<td>P</td>
</tr>
<tr>
<td>H&lt;sub&gt;P&lt;/sub&gt;&lt;sub&gt;a&lt;/sub&gt;</td>
<td>Hydraulic power available</td>
<td>I</td>
</tr>
<tr>
<td>H&lt;sub&gt;P&lt;/sub&gt;&lt;sub&gt;r&lt;/sub&gt;</td>
<td>Hydraulic power required</td>
<td>P</td>
</tr>
<tr>
<td>H&lt;sub&gt;P&lt;/sub&gt;&lt;sub&gt;f&lt;/sub&gt;</td>
<td>Hydraulic power factor</td>
<td>P</td>
</tr>
<tr>
<td>{X&lt;sub&gt;g&lt;/sub&gt;, Y&lt;sub&gt;g&lt;/sub&gt;, Z&lt;sub&gt;g&lt;/sub&gt;}</td>
<td>Actuator gimbal coordinates (where applicable)</td>
<td>DB</td>
</tr>
</tbody>
</table>

<sup>C</sup>I - Input  
DB - Data Base Input  
P - Performance Parameter  
CP - Critical Performance Parameter
hydraulic actuators will be simulated with a time-delay "talkback" response combined with a hydraulic power available/required check.

All other Shuttle hydraulic actuators will utilize transfer function - control feedback techniques to accurately model the desired actuator. Actuator transfer functions and control feedback loops will be determined from tests performed in the Flight Control Hydraulic Lab (FCHL). The transfer functions will compensate for actuator friction, hysteresis, and deadzones associated with mechanical linkages as well as hydraulic power load sharing (Ref. 5).

Inputs to the Hydraulic Actuator Mechanisms Simulation Module consist of:
- Crew/computer device position commands (discrete and combinations)
- Hydraulic power available
- Electrical power available

Outputs will include dynamic mechanical positions and rates (e.g., aero-surface deflections), crew/computer response signals and hydraulic power required. In the case of thrusting devices (SSME, SRB gimbals) body-axis thrust forces and moments will also be output. Hydraulic Actuator Mechanisms Simulation Module Interfaces are depicted in Figure 4.7-26. Corresponding module performance parameters are shown in Table 4.7-5.

AMS Reference Data Sources and Data Formats

Verification of electromechanical and hydraulic actuator mechanism simulation modules can be accomplished through the use of reference data generated with a generalized Actuator Simulation Reference Module as depicted by Figure 4.7-27. (Ref. 17). Only one reference module is necessary for the two types of actuator simulations, as the same general concept applies to both (i.e., both are servo-mechanisms employing transfer functions and control feedback loops). Overall command, acceleration, rate, and position limiting combined with the necessary integrations yield similar results in each case (mechanical position).

Differences will arise, however, in the actual transfer functions, gains and rate limiting curves applicable to each actuator type. These variations will also occur with respect to each individual actuator. Thus, a special driver must be constructed to direct the loading and initializing of tabular data defining each
FIGURE 4.7-26. HYDRAULIC ACTUATOR MECHANISMS SIMULATION MODULE INTERFACES
FIGURE 4.7-27. ACTUATOR REFERENCE MODULE FUNCTIONAL FLOW DIAGRAM
actuator. The tabular data will contain information regarding:
• Actuator type (electromechanical, or hydraulic)
• Individual actuator transfer functions, gains and limit curves
• Power required computations (electrical, hydraulic or a combination)

Also included in the driver would be the time delay functions required to simulate those actuators which require "talkback" response.

AMS Validation Methods and Check Cases

The AMS Simulation Module should be verified through the use of reference data generated with a suitable reference module, as previously described. In some instances, actual hardware tests might be used as a reference data source (e.g., aero-surface actuators evaluated in the FCHL); however, the use of reference software as a data source is generally more efficient than test data in verification processes (see Section 4.2).

Simple "talkback" response to actuator commands is easily verified using simple check cases involving both parameter sweeps and discretes to evaluate indicator flags, time-delays, and specific switch logic and sequencing.

More complex actuators must be evaluated using dynamic check cases, which provide the most accurate means of verifying simulated actuator response. Check cases for each actuator (electromechanical or hydraulic) should contain one or more command sequences which exercise the actuator throughout its nominal and maximum operating range. Table 4.7-6 (Ref. 17) describes one such sequence for the aero-surface actuators. Actuator response characteristics can then be plotted as shown in Figures 4.7-28 and 4.7-29 for the OMS engine gimbals (Ref. 17). Selected performance parameters can also be output for verification analysis. The above check case operations can be performed using the simulation module and the reference module, with time-histories of their corresponding performance parameters compared by either manual or automated techniques (see Section 5.3).

AMS Data Base Impact

Data base requirements for verification of the AMS Simulation Module consist of:
• A generalized actuator reference module
• Tabular information for each individual actuator (used in the reference module)
<table>
<thead>
<tr>
<th></th>
<th>(t)</th>
<th>0</th>
<th>5</th>
<th>10</th>
<th>15</th>
<th>20</th>
<th>25</th>
<th>30</th>
<th>35</th>
</tr>
</thead>
<tbody>
<tr>
<td>(\delta e_{RC})</td>
<td>20°</td>
<td>-50°</td>
<td>0°</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(\delta e_{LC})</td>
<td>20°</td>
<td>-50°</td>
<td>0°</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(\delta e_c)</td>
<td></td>
<td></td>
<td></td>
<td>10°</td>
<td>10°</td>
<td>-40°</td>
<td>-40°</td>
<td>0°</td>
<td></td>
</tr>
<tr>
<td>(\delta a_c)</td>
<td></td>
<td></td>
<td></td>
<td>10°</td>
<td>-10°</td>
<td>10°</td>
<td>-10°</td>
<td>0°</td>
<td></td>
</tr>
<tr>
<td>(\delta r_c)</td>
<td>30°</td>
<td>-30°</td>
<td>0°</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(\delta SB_c)</td>
<td>105°</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>-5°</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(\text{gear}_c)</td>
<td>1.0</td>
<td></td>
<td></td>
<td>0.0</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**LEGEND:**

- \(t\) = time of command issue
- \(\delta e_{RC}\) = right elevon position command
- \(\delta e_{LC}\) = left elevon position command
- \(\delta e_c\) = elevator position command
- \(\delta a_c\) = aileron position command
- \(\delta r_c\) = rudder position command
- \(\delta SB_c\) = speed brake position command
- \(\text{gear}_c\) = gear position command
Engine 3 commanded to -3° about its z-axis at 4.0 sec.

Engine 3 commanded to +3° about its z-axis at 8.0 sec. before the command deflection was reached.

Engine 3 commanded to the null position at 7.0 sec.

FIGURE 4.7-28. EXAMPLE: REFERENCE DATA OMS GIMBAL ACTUATOR RESPONSE
Engine hit stop (4°)

Engine 3 commanded to -3.8° about its y-axis at 4.0 sec.

Commanded deflection reached at 8.9 sec.

Engine 3 commanded to 3.8° about its y-axis at 1.0 sec.

Engine hit stop (-4°)

Engine 3 commanded to the null position at 7.0 sec.

FIGURE 4.7-29. EXAMPLE: REFERENCE DATA OMS GIMBAL ACTUATOR RESPONSE
- Suitable check cases for each actuator
- Reference data generated with the reference module

Overall impact on the verification data base is greatly dependent upon the storage requirements of the tabular information required for each actuator to be verified. After considerable hardware tests have been conducted, these storage areas should remain relatively constant in size. Some variations are expected to occur during Shuttle development and testing.
4.7.1.5 Payload Deployment and Retrieval System (PDRS)

This section describes the components, functions, parameters, and verification of the software module required to simulate the Orbiter Payload Deployment and Retrieval System (PDRS) used in the On-orbit mission phase.

**PDRS Description**

The PDRS comprises the Payload Retention Mechanism (PRM) and the Payload Deployment and Retrieval Mechanism (PDRM). Functions of the PDRS include payload/target (P/T) manipulation and support services, docking assistance, and inspection capability (Ref. 5).

The PRM consists of a system of guides, latches, and release mechanisms which provide the capabilities for easy and reliable payload installation, removal, or changeout (Ref. 18).

The PDRM is located in the payload bay and on the flight deck of the Orbiter. The components of the PDRM are listed as follows (Ref. 5):

- Manipulator Retention Latches (MRL)
- Manipulator Deployment Mechanism (MDM)
- Manipulator Jettison Subsystem (MJS)
- Shuttle Attached Manipulator Subsystem (SAMS)

The MRL is used to support and lock the manipulator arm in the stowed position. The manipulator arm assembly is deployed and retracted via the MDM. The MJS separates the manipulator and its retention latches from the Orbiter should a failure occur which would preclude the complete stowing of the manipulator assembly.

The SAMS controls and affects actual payload handling using the Control Servo Input (CSI) unit and the Follow Up Output (FUO) unit. The CSI controls the FUO, the manipulator arm assembly, using crew commands to and feedback information from the FUO. Control transfer is accomplished with an electronic interface between the CSI and the FUO containing a resolver.
Only one manipulator arm assembly with its associated MRL, MDM, MJS, and electronics is standard on the Orbiter; however one additional assembly is optional and payload chargeable (Ref. 19). Figure 4.7-30 depicts the mechanical components of the PDRM.

PDRS Simulation Module Description and Performance Parameters

The PDRS simulation software module will simulate those functions performed by each element of the actual Orbiter PDRS. Simulation fidelity of the PDRS elements are; (1) PRM - talkback, (2) MRL - talkback, (3) MDM - low, (4) MJS - talkback, (5) SAMS - high.

Inputs to the PDRS software module consist of:
- Payload bay geometric constraints
- P/T type and placement status
- SAMS operator/control logic commands
- Electrical power available
- Orbiter vehicle translational and rotational states and rates
- P/T translational and rotational states and rates
- Orbiter mass properties
- P/T mass properties

The PDRS software will then provide:
- Manipulator arm retention, deployment, jettison status
- Payload retention status
- Manipulator arm assembly dynamics
- P/T attachment status
- Light, camera, monitor operations signals
- Electrical power system (EPS) loadings
- P/T Orbiter collision status when attached

Simulation of PRM, MRL, MDM, and MJS activation will be accomplished through the use of the following sequence: (1) crew switch set to indicate desired operation; (2) power required/power available check performed; (3) appropriate time delay; (4) crew response indicator set.
FIGURE 4.7-30. PDRM MECHANICAL COMPONENTS
However, simulation of the SAMS will involve the simulation of the dynamics and interfaces of the manipulator arm assembly. The arm assembly dynamics will be simulated by solving the equations of motion associated with each manipulator arm joint in the Orbiter - manipulator arm - P/T system. Factors affecting the solution of these equations are:

- Manipulator arm instantaneous geometry
- CSI simulation input commands
- Simulated servo motor response to input commands
- Manipulator arm joint geometric limitations
- Reaction forces and torques at each manipulator arm joint due to Orbiter - P/T

A simplified description of one manipulator arm joint depicting the joint reactions is shown in Fig. 4.7-31. Solution of the equations for the Orbiter - manipulator arm - P/T system will enable the software module to determine:

- True manipulator arm joint positions and rates
- Joint potentiometer and tachometer outputs
- Power required for the operation performed
- End effector status (P/T attach/release)

The simulation of the manipulator arm associated visuals will be accomplished utilizing a Computer Generated Image (CGI) technique. The CGI software interface module will receive outputs from the SAMS simulation module describing manipulator arm positions and angles, as well as camera and light operation. Based upon these inputs, the CGI will generate the associated visuals using its data base as described in Section 4.4.1.

The performance parameters described in Table 4.7-7 were selected using the criteria developed in Section 4.1. The execution rate of the PDRS simulation module will be 10 times per second. This will provide an update rate compatible with the mass properties module during attachment/docking as described in Section 4.5.3. PDRS simulation module interfaces with other Orbiter simulation software modules are given in Fig. 4.7-32.
FIGURE 4.7-31. SIMPLIFIED FUO JOINT REACTIONS
### TABLE 4.7-7 PDRS PERFORMANCE PARAMETERS

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Parameter</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>$F_0$</td>
<td>Orbiter body forces</td>
<td>I</td>
</tr>
<tr>
<td>$F_{P/T}$</td>
<td>P/T body forces</td>
<td>I</td>
</tr>
<tr>
<td>$I_0$</td>
<td>Orbiter inertia tensor</td>
<td>I</td>
</tr>
<tr>
<td>$I_{P/T}$</td>
<td>P/T inertia tensor</td>
<td>I</td>
</tr>
<tr>
<td>$M_0$</td>
<td>Orbiter mass</td>
<td>I</td>
</tr>
<tr>
<td>$M_{P/T}$</td>
<td>P/T mass</td>
<td>I</td>
</tr>
<tr>
<td>$C_0$</td>
<td>Orbiter center of mass</td>
<td>I</td>
</tr>
<tr>
<td>$C_{P/T}$</td>
<td>P/T center of mass</td>
<td>I</td>
</tr>
<tr>
<td>$r, v$</td>
<td>Orbiter position, velocity</td>
<td>I</td>
</tr>
<tr>
<td>$S_r, S_v$</td>
<td>P/T relative position and velocity</td>
<td>I</td>
</tr>
<tr>
<td>$S_{\phi/P/T}, S_{\psi/P/T}$</td>
<td>P/T relative angular orientation</td>
<td>I</td>
</tr>
<tr>
<td>$T_{prm}$</td>
<td>PRM actuation response time</td>
<td>I</td>
</tr>
<tr>
<td>$T_{mrl}$</td>
<td>MRL actuation response time</td>
<td>I</td>
</tr>
<tr>
<td>$T_{mdm}$</td>
<td>MDM actuation response time</td>
<td>I</td>
</tr>
<tr>
<td>$T_{mjs}$</td>
<td>MJS actuation response time</td>
<td>I</td>
</tr>
<tr>
<td>$T_{ee}$</td>
<td>End effector grasp/release response time</td>
<td>I</td>
</tr>
<tr>
<td>$\Theta_{\text{min},i}$; $\Theta_{\text{max},i}$</td>
<td>FUO joint geometric limits</td>
<td>I</td>
</tr>
<tr>
<td>$\Theta_{\text{ee, max}}$</td>
<td>FUO end effector extension limit</td>
<td>I</td>
</tr>
<tr>
<td>$C_{prm}$</td>
<td>PRM command</td>
<td>I</td>
</tr>
<tr>
<td>$C_{mrl}$</td>
<td>MRL command</td>
<td>I</td>
</tr>
<tr>
<td>$C_{mdm}$</td>
<td>MDM command</td>
<td>I</td>
</tr>
<tr>
<td>$C_{mjs}$</td>
<td>MJS command</td>
<td>I</td>
</tr>
<tr>
<td>$C_c,i$</td>
<td>Camera operation command</td>
<td>I</td>
</tr>
<tr>
<td>$C_{l,i}$</td>
<td>Light operation command</td>
<td>I</td>
</tr>
<tr>
<td>$C_{\text{ee}}$</td>
<td>End effector grasp/release command</td>
<td>I</td>
</tr>
<tr>
<td>$S_{rc}$</td>
<td>FUO translational position command</td>
<td>I</td>
</tr>
<tr>
<td>$S_{rc}$</td>
<td>FUO translational rate command</td>
<td>I</td>
</tr>
<tr>
<td>Symbol</td>
<td>Parameter</td>
<td>Type</td>
</tr>
<tr>
<td>-------------------</td>
<td>-----------------------------------------------------</td>
<td>------</td>
</tr>
<tr>
<td>$S_{\phi_c}, S_{\psi_c}, S_{\omega_c}$</td>
<td>FUO end-point attitude command</td>
<td>I</td>
</tr>
<tr>
<td>$S_{\psi_c}$</td>
<td>FUO end-point attitude rate command</td>
<td>I</td>
</tr>
<tr>
<td>$S_{\phi_c}, S_{\psi_c}, S_{\omega_c}$</td>
<td>Camera operation status</td>
<td>P</td>
</tr>
<tr>
<td>$S_c$</td>
<td>Light operation status</td>
<td>P</td>
</tr>
<tr>
<td>$S_e$</td>
<td>End effector status (grasp/release)</td>
<td>CP</td>
</tr>
<tr>
<td>$S_{ee}$</td>
<td>FUO jettison status</td>
<td>P</td>
</tr>
<tr>
<td>$S_j$</td>
<td>FUO joint positions in orbiter axes</td>
<td>CP</td>
</tr>
<tr>
<td>$\delta_{fu0,i}$</td>
<td>FUO end effector position in orbiter axes</td>
<td>CP</td>
</tr>
<tr>
<td>$\dot{\delta}_{fu0,i}$</td>
<td>FUO joint rates and accelerations</td>
<td>P</td>
</tr>
<tr>
<td>$\delta_{fu0,i}$</td>
<td>FUO end effector extention, rate and acceleration</td>
<td>P</td>
</tr>
<tr>
<td>$A_i$</td>
<td>FUO joint orientation matrices</td>
<td>CP</td>
</tr>
<tr>
<td>$[V_{fu0,i}]$</td>
<td>FUO joint potentiometer outputs</td>
<td>P</td>
</tr>
<tr>
<td>$[W_{fu0,i}]$</td>
<td>FUO joint tachometer outputs</td>
<td>P</td>
</tr>
<tr>
<td>$[L_{fu0,i}]$</td>
<td>FUO joint torques</td>
<td>CP</td>
</tr>
<tr>
<td>$S_{F_{o,prm}}$</td>
<td>Orbiter forces due to PRM</td>
<td>P</td>
</tr>
<tr>
<td>$S_{F_{o,sams}}$</td>
<td>Orbiter forces due to SAMS</td>
<td>CP</td>
</tr>
<tr>
<td>$S_{F_{P/T,prm}}$</td>
<td>P/T forces due to PRM</td>
<td>P</td>
</tr>
<tr>
<td>$S_{F_{P/T,sams}}$</td>
<td>P/T forces due to SAMS</td>
<td>CP</td>
</tr>
<tr>
<td>$L_o$</td>
<td>Total moment on orbiter</td>
<td>CP</td>
</tr>
<tr>
<td>$L_{P/T}$</td>
<td>Total moment on P/T</td>
<td>CP</td>
</tr>
<tr>
<td>$L_{o,pdrs}$</td>
<td>Orbiter moment due to PDRS</td>
<td>CP</td>
</tr>
<tr>
<td>$L_{P/T,pdrs}$</td>
<td>P/T moment due to PDRS</td>
<td>CP</td>
</tr>
<tr>
<td>$P_{pdrs}$</td>
<td>Electrical power load due to PDRS</td>
<td>CP</td>
</tr>
</tbody>
</table>

**Legend**

- **I** - Input
- **P** - Performance Parameter
- **CP** - Critical Performance Parameter
- **a** - P/T denotes payload/target
- **b** - FUO denotes the manipulator arm
- **c** - 4.7-83
FIGURE 4.7-32 PAYLOAD DEPLOYMENT AND RETRIEVAL SYSTEM MODULE INTERFACES
PDRS Reference Data Sources and Data Formats

The numerous dynamic functions performed by the PDRS Simulation Module require verification reference data over a wide operational range. Test data would not be completely adequate as verification reference data due to actual test limitations. It is then necessary to use a reference software module for reference data generation.

Presently, no readily available math model exists which simulates the Orbiter PDRS. However, Figures 4.7-33a and 4.7-33b depict a conceptual, functional flow diagram of a math model which can be combined with a driver to form a suitable PDRS reference module. This reference module, when implemented and exercised with carefully designed check cases, will supply reference data for the validation of the simulated functions of the PRM, MJS, MDM, MRL, and SAMS.

The reference module driver will control module input/output and ensure PDRS Simulation Module compatibility. Reference module inputs and outputs consist essentially of the corresponding parameters and parameter groups listed in Table 4.7-7 and shown in Figure 4.7-32. Minor variations between simulation and reference module internal parameters may result due to formulation differences, but principal inputs and outputs will be compatible. Other input/output requirements unique to the reference module will be specifically related to the user-designated quantity and fidelity of the desired output verification reference data.

Reference module simulation of the MJS, MDM and MRL response uses a talkback technique. Eventually, as hardware is developed and test data becomes available, time-delay functions should be incorporated simulating the actual time-delay talkback response. The PRM talkback response is also simulated in this manner.

Complete PRM simulation involves a time-delay talkback response function coupled with the appropriate force and moment calculations. PRM reactions forces and moments are used by the Orbiter and P/T equations of motion and based upon:

- PRM design and location(s)
- P/T type
- P/T relative position, velocity, and orientation
- PRM operation commands
FIGURE 4.7-33a. PDRS REFERENCE MODULE FUNCTIONAL FLOW
FIGURE 4.7.33a. (CONTINUED)

4.7-87

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-33b PDRS REFERENCE MODULE FUNCTIONAL FLOW (SAMSF SUBROUTINE)
FIGURE 4.7-33b  PDRS REFERENCE MODULE FUNCTIONAL FLOW (SAMSF SUBROUTINE)
SAMS simulation verification is concerned chiefly with the dynamics of the FUO. Operator commands to the FUO require that the reference module SAMSF subroutine (Figure 4.7-33b) compute:

- FUO arm joint torques
- FUO position dynamics (SAMS reaction forces and moments)
- FUO-Orbiter-P/T collision constraints
- FUO potentiometer and tachometer outputs

Actual SAMSF formulations and electromechanical actuator transfer functions (see Section 4.7.1.4) will be derived from empirical data obtained from hardware tests of the SAMS, and may experience some modification as the SAMS design evolves. Additional automatic command sequences may also be implemented for standard FUO positioning (less P/T) as required for FUO stowing, deployment, or Shuttle vehicle inspection (Ref. 9).

PDRS Validation Methods and Check Cases

Check case design for verification operation of the MGM, MRL, and MJS should consist of simple discrete command sequences. In sequencing the various commands through the simulation and reference modules, the corresponding talkback response, sequence check flags, and time-delays can be evaluated and analyzed. Low-fidelity (talkback) response of the PRM can also be verified through similar check case design.

Complete verification of the PDRS requires that the PRM and SAMS be verified with dynamic check cases. For both the PRM and SAMS, one or more check cases must be designed for each P/T and/or FUO operation planned. Each check case should verify the complete command sequence and SAMS response for stowing, deployment, retrieval and other manipulations of payloads with appropriate masses and inertias. Other dynamic command sequences should be used to evaluate the response and positioning of the FUO without an attached P/T. Previously discussed command sequences should be similar to the aero-surface command sequence shown in Section 4.7.1.4, although much more complex.

PDRS Data Base Impact

Data base requirements for verification of the PDRS consist of:

- Reference module as described
Reference data generated with the reference module
- A variety of check cases which exercise all planned PDRS operations
- The necessary tables, tapes, and/or service routines required for PDRS

Simulation Module verification

During PDRS simulation development, changes in the PDRS portion of the verification data base will occur. Most of the impact will be minor, unless a significant hardware modification is made. Other changes in the PDRS data base may be required, if payload masses/inertias and operational sequences outside of the previously-validated range are added later in the program.
4.7.1.6 Hydraulic Power Subsystem (HPS)

HPS Description

The hydraulic power system provides power to actuate the aerodynamic flight control surfaces, main engine gimbals and engine controls, main and nose landing gear deployment, speed brakes, main landing gear brakes, and nose wheel steering. Figure 4.7-34 illustrates the functional configuration of the HPS (Ref. 20). The HPS consists of three main hydraulic pumps, each driven by an auxiliary power unit (APU), connected to the hydraulic system loads.

HPS Simulation Module Description and Performance Parameters

The HPS simulation module will be divided into four main groups of generally related engineering equations. These equations will simulate hydraulic load, stored, accumulator energy, pump-reservoir capability, and hydraulic fluid temperature and heat load.

Signals will also be provided to indicate crew display of hydraulic fluid temperature and quantity as well as caution and warning displays relating high or low fluid temperature and low fluid quantity or pressure (Ref. 11).

Figure 4.7-35 depicts the HPS simulation module interfaces with other simulation modules. An example of module interaction and influence is that of the continuous dynamic loads on the aerodynamic control surfaces affecting HPS pressure and reservoir level. Table 4.7-19 provides a list of the HPS performance parameters (Ref. 21). These parameters are also reflected in Figure 4.7-37.

HPS Reference Data Sources and Data Formats

HPS verification reference data should be generated with a reference module functionally equivalent to the functional HPS reference module flow shown in Figure 4.7-36. Reference 22 describes an existing program which could be effective as a reference data source. As described, the Space Shuttle Hydraulic POWER Program assumes that all design dependent data is available from the Orbiter contractor (Rockwell). User-supplied information consists of output options, mission dependent data, and operational data for each mode to be analyzed. Special care must be exercised in coordinating the specific mission and design-dependent data (Ref. 22).
FIGURE 4.7-34, HYDRAULIC POWER SUBSYSTEM (TYP)
### TABLE 4.7-8 HYDRAULIC POWER SUBSYSTEM PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE\textsuperscript{a}</th>
</tr>
</thead>
<tbody>
<tr>
<td>RESERVOIR FLUID TEMP</td>
<td>-75 to +300 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>RESERVOIR FLUID VOLUME</td>
<td>0 to +100 PCNT</td>
<td>P</td>
</tr>
<tr>
<td>RESERVOIR FLUID LVL LOW</td>
<td>NORM to LOW EVENT</td>
<td>CP</td>
</tr>
<tr>
<td>SUPPLY PRESS A</td>
<td>0 to +4000 PSIA</td>
<td>P</td>
</tr>
<tr>
<td>SUPPLY PRESS B</td>
<td>0 to +4000 PSIA</td>
<td>P</td>
</tr>
<tr>
<td>FWD DISTR PRESS LINE TEMP</td>
<td>-75 to +300 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>FLUID HEATER OUTLET TEMP</td>
<td>-75 to +300 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>AFT COMPT RTN LINE TEMP</td>
<td>-75 to +300 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>CIRCULATION PUMP PRESS</td>
<td>0 to +500 PSIA</td>
<td>P</td>
</tr>
<tr>
<td>CIRCULATION PUMP-ON</td>
<td>ON EVENT</td>
<td>I</td>
</tr>
<tr>
<td>BACK-UP CIRCULATION PUMP ON</td>
<td>ON EVENT</td>
<td>I</td>
</tr>
<tr>
<td>MAIN ENGINE SUPPLY VLV-CLOSE</td>
<td>ON EVENT</td>
<td>I</td>
</tr>
<tr>
<td>READY FOR APU START-ON</td>
<td>READY EVENT</td>
<td>I</td>
</tr>
<tr>
<td>BOILER WATER TEMP</td>
<td>0 to +250 DEG F</td>
<td>I</td>
</tr>
<tr>
<td>H\textsubscript{2}O BOILER FLUID VOLUME</td>
<td>0 to +100 PCNT</td>
<td>I</td>
</tr>
</tbody>
</table>

\textsuperscript{a} P - Performance Parameter  
CP - Critical Performance Parameter  
I - Input
FIGURE 4.7-35 HPS SIMULATION MODULE INTERFACES
HYDRAULIC POWER ACTUATORS IN OPERATION SYSTEMS OPERATING — AT TIME t

SUM ACTUATOR DEMANDS

COMPUTE FLOW TYPE I ACTUATOR GRADIENTS TYPE II

SUM LEAKAGE RATES FROM ACTUATORS

COMPUTE TOTAL HYDRAULIC FLOW $F_t = f$ (summed; leak rates, flow grad., individual actuator flows)

COMPUT HEAT OUTPUT $Q_o = f$ (actuator demands, total flow, pump, systems operating)

COMPUTE APU HORSEPOWER REQUIRED

$HP_r = f$ (systems, pump, total flow)

RETURN

FIGURE 4.7-36. HPS REFERENCE MODULE FUNCTIONAL FLOW DIAGRAM 4.7-95

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
The POWER program provides an analysis of the flow, power, and thermal characteristics of the Orbiter HPS. Program outputs consist of (Ref. 22):

- Input card images
- Type I actuator data (Type I actuators are variable rate)
- Actuator operational mode status
- Mission flow
- Power and thermal profiles
- Pump characteristics for the mission
- Individual actuator flow
- Individual actuator thermal profiles
- Total mission system power

**HPS Validation Methods and Check Cases**

Check case construction for verification of the Orbiter HPS should contain the correct inputs (system and module dependent) for both the simulation and reference modules which exercise the complete HPS for the mission phase and/or operating conditions of interest. The ascent and entry mission phase are most important, as the HPS is not used in the on-orbit phase. Either a partial or complete mission phase check case can be executed to generate plots similar to the APU load profile shown in Figure A.7-37 (Ref. 5). Load profile data -- power, thermal, and flow -- should be generated and output (print, plot, and/or mass storage) for verification analysis. A complete verification requires that HPS load profiles be generated for each Orbiter hydraulic actuator and actuator group as well as the entire HPS.

**Data Base Impact**

Data base impact for HPS Simulation Module verification will consist of:

- A suitable reference module
- Resident reference data and check cases
- Resident data required by the reference module

Impact to the verification should not expand unless significant changes are made to the HPS.
FIGURE 4.7-37. HYDRAULIC POWER SYSTEM #2 LOAD PROFILE (NOTE: ORBITER HPS HAVE BEEN REDUCED TO 3; 4 SHOWN IN THIS FIGURE)
Figure 4.7-37. Hydraulic Power System #2 Load Profile (Note: Orbiter HPS have been reduced to 3; 4 shown in this figure)
4.7.2 Purge and Vent (P & V) Subsystem

The Orbiter P & V subsystem is very simple in form and function, and little or no simulation requirements exist for this subsystem on any of the simulators of interest to this study. Therefore, this section provides only a brief description of the P & V subsystem and a possible simulation module; validation-oriented subsections are omitted.

4.7.2.1 P & V Subsystem Description

The P & V subsystem performs the following functions:

- Purging of various Orbiter cavities and lines using an inert gas (He or N₂)
- Venting of various Orbiter cavities to relieve differential pressures and eliminate outgassing products
- Detection of hazardous gases (e.g., from leaks in reactant storage systems)
- Provision and application of rain repellent for the Orbiter windshield

Figures 4.7-38 and 4.7-39, from Ref. 12, provide an overview of the P & V subsystem layout and its GSE interface. Additional layout detail, if needed, is provided by Ref. 23. Additional discussion of the GSE interface will be found in Section 4.3.2.3.

As indicated by Figure 4.7-38, the only purging capability self-contained within the orbiter is dry-nitrogen purging of the windshield cavity. This purging is initiated manually by the flight crew whenever necessary (e.g., if fog or ice appears between the windshield panes).

Venting of Orbiter cavities is necessary primarily during periods of rapid external pressure change; e.g., ascent and entry. Both "active" and "passive" vents are provided. Passive vents are simply fixed holes in the Orbiter skin. Active vents consist of valves or doors which are opened and closed at appropriate times -- either manually, cued by the flight crew timeline, or automatically by the onboard sequencing system.

Hazardous-gas detection is apparently a prelaunch function, since no detector outputs are shown by Ref. 21 (see below).
Figure 4.7-30. PURGE SUBSYSTEM FLOW DIAGRAM
Figure 4.7-3n. PURGE SUBSYSTEM FLOW DIAGRAM
Figure 4.7-100. ORBITER PURGE AND VENT SUBSYSTEM
Figure 4.7-31. ORBITER PURGE AND VENT SUBSYSTEM
4.3.2.2 P & V Simulation Module Description and Performance Parameters

Prelaunch purging operations (if simulated) will fall under the Prelaunch/Launch Interface Module, Section 4.3.2.3. The remaining P & V functions, if simulated at all, will probably be implemented only as talkback of manually- or automatically-initiated discretes. The potential performance parameters are listed in Table 4.7-9; no critical performance parameters are indicated.

Table 4.7-9. P & V Simulation Module Parameters

<table>
<thead>
<tr>
<th>PARAMETER</th>
</tr>
</thead>
<tbody>
<tr>
<td>Window cavity safety valves (#1,2,3,4,5) open/closed</td>
</tr>
<tr>
<td>Window rain repellent tank quality</td>
</tr>
<tr>
<td>Orbiter vent doors open/closed</td>
</tr>
<tr>
<td>Payload bay vent doors (left, right) open/closed</td>
</tr>
<tr>
<td>Forward thruster vent doors (left, right) open/closed</td>
</tr>
<tr>
<td>Left forward fuel vent door open/closed</td>
</tr>
<tr>
<td>Right forward oxidizer vent door open/closed</td>
</tr>
<tr>
<td>Fuselage vent doors (left, right/forward, mid, aft) open/closed</td>
</tr>
<tr>
<td>Aft wing vent doors (left, right) open/closed</td>
</tr>
<tr>
<td>Left OMS/RCS fuel vent door open/closed</td>
</tr>
<tr>
<td>Right OMS/RCS oxidizer vent door open/closed</td>
</tr>
<tr>
<td>Fin vent door open/closed</td>
</tr>
</tbody>
</table>
4.7.3 Propulsion and Fuel Systems

The Orbiter Propulsion and Fuel System comprises the Main Propulsion Subsystem (MPS) and External Tank (ET), the Solid Rocket Motors (SRM), the Orbital Maneuvering System (OMS), and the Reaction Control Subsystem (RCS). This section discusses the functions, simulation, and simulation verification of each of these systems and subsystems.

4.7.3.1 Main Propulsion Subsystem and External Tank (MPS/ET)

MPS/ET Subsystem Description

The Orbiter MPS and ET are composed of the three, clustered aft Orbiter main engines, the external propellant tank (which separates from the Orbiter prior to orbital insertion), the Main Engine Controller (MEC), the pneumatic control subsystem, and assorted valves, pumps, and components.

Thrust and gimbal commands are generated by the avionics system (although the Shuttle also has a manual throttling capability) in response to sensed accelerations, computed position and velocity, and intended orbit. The MPS then provides the actual thrust.

MPS thrust is controlled by the MEC. The MEC is an electronic device installed on each main engine which, along with engine sensors, valves, spark igniters, actuators, etc., provides the following SSME functions:

- Sensor excitation and valve/igniter control signals
- Closed-loop control of thrust and propellant mixture ratio
- Engine start and shutdown sequencing
- Engine-ready monitoring
- Engine limit detection
- On-board checkout
- Vehicle/engine interfaces for (1) receiving electrical power and memory data words, and (2) transmission of engine status, performance, and maintenance data.

The MEC provides continuously variable thrust between the Minimum Power Level (MPL) and the Emergency Power Level (EPL) - 50% and 109% of nominal, respectively - as commanded by the vehicle. The thrust control loop contains control logic.
to receive thrust level commands from the Orbiter General Purpose Computers (GPC) through the Engine Interface Unit (EIU). The pneumatic control assembly is then directed by the MEC to position the fuel preburner oxidizer valve and oxidizer preburner oxidizer valve to achieve the commanded thrust as indicated by the main combustion chamber combustion pressure measurements (Ref. 26).

Figure 4.7-40 depicts the MPS and ET, showing the separation disconnects as well as the ground servicing interface and the ET pressurization subsystems. Figure 4.7-41 illustrates the MPS and ET Helium subsystem which is utilized for MPS and ET pressurization and the propellant feed system. A more detailed illustration of the plumbing, valves, hydraulic and pneumatic control subsystem, and pressurant subsystem for one typical engine is shown in Figure 4.7-42.

Figure 4.7-43 is a sketch of the basic MPS and ET configuration. Figures 4.7-44 and 4.7-45 illustrate the basic onboard displays and controls for the subsystems, which provide the crew interface to the subsystems via the avionics interface (Ref. 20).

**MPS/ET Simulation Module Description and Performance Parameters**

The MPS and ET simulation module will provide the capability to simulate the MPS and ET and their separation interface throughout the nominal operating ranges of the subsystem, as well as reflecting the influence resulting from other systems and subsystems. (An example of the subsystems' interaction and influence is that of the propellant monitoring subsystem interface with the subsystems effecting the propellant usage.) The propellant monitoring subsystem, in conjunction with the MEC, controls the flow rates and mixture ratio of propellants to the engines to deliver the commanded thrust and maintain efficient combustion, while at the same time maintaining the ratio of propellants remaining in the tanks within the proper range.

The fuel and oxidizer volumes will be dynamically simulated for all missions with the associated sensors, control valves, and associated components. The simulation module capabilities will encompass the nominal operational limits, the blueline and redline limits, and the subsystem design limits. The dynamics of the propellant monitoring and control subsystem are also influenced by the burn mixture ratios of the three engines, the flow rates, initial fill quantities, topping characteristics, and the relief characteristics of the fuel and oxidizer valves,
FIGURE 4.7-40 MAIN PROPULSION SUBSYSTEM SCHEMATIC
FIGURE 4.7-41 MAIN PROPULSION HELIUM SYSTEM
FIGURE 4.7-41 MAIN PROPULSION HELIUM SYSTEM
FIGURE 4.7-42 SSME SCHEMATIC

A - HYDRAULIC DRAIN AND HELIUM VENT;
B - FUEL TURBINE SECONDARY DRAIN AND HELIUM AND NITROGEN VENT
C - OXIDIZER DRAIN AND HELIUM AND NITROGEN VENT (S)
D - TURBINE PRIMARY DRAIN (S)
FIGURE 4.7-42 SSME SCHEMATIC.
FIGURE 4.7-43 ORBITER MAIN PROPULSION SUBSYSTEM
FIGURE 4.7-43 ORBITER MAIN PROPULSION SUBSYSTEM
FIGURE 4.7-44  MAIN PROPULSION SUBSYSTEM DEDICATED DISPLAYS
<table>
<thead>
<tr>
<th>Component</th>
<th>LO₂</th>
<th>LH₂</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>Engine AC Power No. 1</td>
<td>ON</td>
<td>OFF</td>
<td>ON</td>
</tr>
<tr>
<td>Engine AC Power No. 2</td>
<td>ON</td>
<td>OFF</td>
<td>ON</td>
</tr>
<tr>
<td>Engine Heaters</td>
<td>ON</td>
<td>OFF</td>
<td>ON</td>
</tr>
<tr>
<td>All Eng Limit Control</td>
<td></td>
<td></td>
<td>INHIBIT, AUTO ENABLE</td>
</tr>
<tr>
<td>Engine Shutdown</td>
<td></td>
<td></td>
<td>GUARDED, 100% 109% Throttle</td>
</tr>
<tr>
<td>Manual Throttle Control</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Tank Vent Valves</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
<tr>
<td>Disconnect Valves</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
<tr>
<td>Fill Valves</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
<tr>
<td>Helium Isolation</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
<tr>
<td>Helium Crossover</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
<tr>
<td>Helium Blowdown</td>
<td>OPEN</td>
<td>AUTO</td>
<td></td>
</tr>
</tbody>
</table>

**Figure 4.7-45 Main Propulsion Subsystem Manual Controls**
as well as the burn characteristics of the engines within their design profile boxes and the associated valves, and plumbing configurations for the specific test conditions. Body bending and fuel slosh effects (simulated in the vehicle dynamics module) will be incorporated as appropriate into the MPS/ET simulation module.

The performance parameters associated with each subsystem are located on each illustration and listed in Tables 4.7-10 and 4.7-11. The performance parameters are located on only one engine in detail and are representative of all three. Table 4.7-11 reflects the onboard software parameters. These parameters are transmitted via the engine PCM system and recorded on the maintenance recorder as well as routed to the G\&N computer and downlinked via the digital downlink. Reference 21 was used as the prime source for the information in the tables. This system has a high proportion of "critical" performance parameters due to its short operating time, and the critical nature of its functions to vehicle/crew survival and mission success. Figure 4.7-46 depicts the MPS/ET simulation module interfaces with other systems simulation modules.

MPS/ET Reference Data Sources and Data Formats

Reference data from an external source must be generated to verify the MPS/ET simulation module. The specific verification conditions determine the level of reference data fidelity required. This section describes two reference data sources which can be used as reference modules. The first reference module presented is a high-fidelity simulation of the MPS/ET. The second is a lower fidelity representation which provides less detailed reference data. Both models have applications in simulation verification.

MPS/ET High-Fidelity Reference Module - Reference 24 describes a very detailed SSME math model developed by Rocketdyne and designated as the RL00001 model. This detailed model is provided for use as a baseline standard to verify other SSME simulation models in the regions of start, throttling, and cutoff operations. Both extended limits and off-nominal operating conditions for the SSME system are simulated. Also modeled in this simulation are SSME turbopump, valve, and propellant feed line dynamics along with MEC functions.
### TABLE 4.7-10 MPS/ET MODULE PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>FM'ERG SHUTDOWN INHIBIT CMD/RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>AC POWER NO 1 ON CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>HEATER POWER ON CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>CONTROLLER TEMP</td>
<td>-200 +400 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>LH2 PREVALVE OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>LH2 PREVALVE CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>LO2 PREVALVE OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>LO2 PREVALVE CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>HELIUM BOTTLE TEMP</td>
<td>-65 +500 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>HE ISLN VLV 1 OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>HE ISLN VLV 2 OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>MPS-LH2 INBD FILL VALVE OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 INBD FILL VALVE CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 OUTBD FILL VALVE OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 OUTBD FILL VALVE CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 RECIRC DISC VLV OPEN CMD /RESP</td>
<td>ON OFF EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 RECIRC DISC VLV CLOSED CMD /RESP</td>
<td>ON OFF EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 RECIRC DISC VLV OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 RECIRC DISC VLV CLOSED CMD /RESP</td>
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<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 FEED DISC VLV OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 FEED DISC VLV CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LH2 FLOW RATE</td>
<td>LB/SEC</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LH2 MANIF REPRES NO 1 OPEN CMD /RESP</td>
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<td>I/P</td>
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<tr>
<td>MPS-LH2 MANIF REPRES NO 2 OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>MPS-LH2 FDLN RELIEF SOL CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>MPS-LH2 TOPPING VLV OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/P</td>
</tr>
<tr>
<td>MPS-LH2 QUANTITY</td>
<td>LB</td>
<td>P</td>
</tr>
<tr>
<td>MPS-GH2 DISCONNECT PRESS</td>
<td>0 1000</td>
<td>PSIA CP</td>
</tr>
<tr>
<td>MPS-GH2 PPRESS DISC VLV OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-GH2 PPRESS DISC VLV CLOSE CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>MPS-LO2 INBOARD FILL VLV OPEN CMD /RESP</td>
<td>ON EVENT</td>
<td>I/CP</td>
</tr>
<tr>
<td>PARAMETER NOMENCLATURE</td>
<td>DATA RANGE</td>
<td>TYPE&lt;sup&gt;a&lt;/sup&gt;</td>
</tr>
<tr>
<td>------------------------</td>
<td>------------</td>
<td>------------------</td>
</tr>
<tr>
<td>&quot;PS-LO2 INBOARD FILL VLV CLOSE CMD/RESP</td>
<td>LOW</td>
<td>HIGH</td>
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<tr>
<td>&quot;PS-LO2 OUTBD FILL VLV CLOSE CMD/RESP</td>
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<td>EVENT</td>
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<td>EVENT</td>
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<td>&quot;PS-LO2 FEED DISC VLV CLOSE CMD/RESP</td>
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<td>&quot;PS-LO2 FLOW RATE</td>
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<td>&quot;PS-LO2 MANIF REPRES NO 1 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
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<tr>
<td>&quot;PS-LO2 MANIF REPRES NO 2 OPEN CMD/RESP</td>
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<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-LO2 FDLN RELIEF SOL CLOSE CMD/RESP</td>
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<td>EVENT</td>
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<tr>
<td>&quot;PS-LO2 QUANTITY</td>
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<tr>
<td>&quot;PS-G0X DISCONNECT PRESSURE</td>
<td>0</td>
<td>1000</td>
</tr>
<tr>
<td>&quot;PS-G0X PRESS DISC VLV CLOSE CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-G0X PRESS DISC VLV OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-PNEUMATIC VLV-HE SUPPLY PRESS</td>
<td>0</td>
<td>5000</td>
</tr>
<tr>
<td>&quot;PS-PNEUMATIC VLV-HE BOTTLE TEMP</td>
<td>-65</td>
<td>+500</td>
</tr>
<tr>
<td>&quot;PS-PNEU VLV HE RGLTR OUTLET PRESS</td>
<td>0</td>
<td>1000</td>
</tr>
<tr>
<td>&quot;PS-PNEU VLV HE ISLN NO 1 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-PNEU VLV HE ISLN NO 2 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-PNEU CROSSOVER NO 1 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-PNEU CROSSOVER NO 2 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-PNEU CROSSOVER NO 3 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-HF SUP BLOWDOWN NO 1 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>&quot;PS-HF SUP BLOWDOWN NO 2 OPEN CMD/RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LH2 ULLAGE PRESS NO 1</td>
<td>0</td>
<td>50</td>
</tr>
<tr>
<td>ET-LH2 ULLAGE PRESS NO 2</td>
<td>0</td>
<td>50</td>
</tr>
<tr>
<td>ET-LH2 ULLAGE PRESS NO 3</td>
<td>0</td>
<td>50</td>
</tr>
<tr>
<td>ET-LH2 VENT VLV NO 1 CLOSE CMD /RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LH2 VENT VLV NO 1 OPEN CMD /RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LH2 VENT VLV NO 2 CLOSE CMD /RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LH2 VENT VLV NO 2 OPEN CMD /RESP</td>
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<td>EVENT</td>
</tr>
<tr>
<td>ET-LOX ULLAGE PRESSURE NO 1</td>
<td>0</td>
<td>30</td>
</tr>
<tr>
<td>ET-LOX ULLAGE PRESSURE NO 2</td>
<td>0</td>
<td>30</td>
</tr>
<tr>
<td>ET-LOX ULLAGE PRESSURE NO 3</td>
<td>0</td>
<td>30</td>
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### TABLE 4.7-10 (CONTINUED)

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>LOW</td>
<td>HIGH</td>
</tr>
<tr>
<td>ET-LOX VENT VLV NO 1 CLOSE CMD / RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LOX VENT VLV NO 1 OPEN CMD / RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LOX VENT VLV NO 2 CLOSE CMD / RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>ET-LOX VENT VLV NO 2 OPEN CMD / RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>MPS-MANUAL THROTTLE ENABLED CMD / RESP</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>MPS-MANUAL THROTTLE POSITION</td>
<td>50</td>
<td>109</td>
</tr>
<tr>
<td>MPS CHAMBER PRESSURE</td>
<td></td>
<td></td>
</tr>
<tr>
<td>MPS THRUST</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<sup>a</sup> P - PERFORMANCE PARAMETER  
CP - CRITICAL PERFORMANCE PARAMETER  
I - INPUT  
<sup>b</sup> INDICATES 2 PARAMETERS (COMMAND AND RESPONSE)
## TABLE 4.7-11 MPS/ET ON BOARD PROCESSED PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>LOW</td>
<td>HIGH</td>
</tr>
<tr>
<td>FAILURE IDENT DATA WORD-6</td>
<td></td>
<td></td>
</tr>
<tr>
<td>TEST DATA WORD 6 DATA WORD-7</td>
<td></td>
<td></td>
</tr>
<tr>
<td>THRUST DN-5</td>
<td></td>
<td></td>
</tr>
<tr>
<td>XCC PRESS DN-9-10-11-12</td>
<td></td>
<td></td>
</tr>
<tr>
<td>OX TR PRESURNT PRESS DN-64-65</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPFTP SHAFT SPEED DW-43</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPFTP DISCH PRES DN19 THRU-22</td>
<td></td>
<td></td>
</tr>
<tr>
<td>LPFTP DISCH PRESS DW36 THRU-39</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPOTP SHAFT SPEED DW-57</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPOTP DISCH TEMP DW-54</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPOTP DISCH PRESS DW23 THRU-26</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPOTP TURBO DISCH TEMP DW-59</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HPOTP INTMD SL PGE PRES DW-75</td>
<td></td>
<td></td>
</tr>
<tr>
<td>LPOTP DISCH PRES DW48 THRU-51</td>
<td></td>
<td></td>
</tr>
<tr>
<td>ENGINE STATUS DW-3</td>
<td></td>
<td></td>
</tr>
<tr>
<td>LH2 INLET PRESS</td>
<td>0</td>
<td>200</td>
</tr>
<tr>
<td>LH2 INLET TEMP</td>
<td>-430</td>
<td>-379</td>
</tr>
<tr>
<td>LH2 PREVALVE OPEN</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>LOX INLET PRESS</td>
<td>0</td>
<td>400</td>
</tr>
<tr>
<td>LOX INLET TEMP</td>
<td>-320</td>
<td>-270</td>
</tr>
<tr>
<td>LOX PREVALVE OPEN</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>HE FLLTR OUTLET PRESS</td>
<td>0</td>
<td>1000</td>
</tr>
<tr>
<td>MPS-LH2 INBOARD FILL VLV CLOSED</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LH2 OUTBD FILL VLV CLOSED</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LH2 TANK DISC VLV OPEN</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LH2 FEED DISC VLV OPEN</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LH2 FNG MANIFOLD PRESSURE</td>
<td>0</td>
<td>200</td>
</tr>
<tr>
<td>MPS-LH2 TOPPING VLV CLOSED</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LOX INBD FILL VLV CLOSED</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LOX OUTBD FILL VLV CLOSED</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>MPS-LOX TANK PRESS DISC VLV OPEN</td>
<td>ON</td>
<td>OFF</td>
</tr>
<tr>
<td>LPFTP DISCH TEMP DW-40</td>
<td></td>
<td></td>
</tr>
<tr>
<td>PARAMETER NOMENCLATURE</td>
<td>DATA RANGE</td>
<td>TYPE</td>
</tr>
<tr>
<td>------------------------</td>
<td>------------</td>
<td>------</td>
</tr>
<tr>
<td>MPS-LOX FEED DISC VLV OPEN</td>
<td>ON OFF EVENT</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX ENGINE MANIFOLD PRESSURE</td>
<td>0 400 PSIA</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX FEEDLINE RELIEF SOV CLOSED</td>
<td>ON OFF EVENT</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX LOW LEVEL LIQUID SNSR NO 1</td>
<td>DRY WET EVENT</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX LOW LEVEL LIQUID SNSR NO 2</td>
<td>DRY WET EVENT</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX LOW LEVEL LIQUID SNSR NO 3</td>
<td>DRY WET EVENT</td>
<td>P</td>
</tr>
<tr>
<td>MPS-LOX LOW LEVEL LIQUID SNSR NO 4</td>
<td>DRY WET EVENT</td>
<td>P</td>
</tr>
<tr>
<td>ET-LH2 LOW LEVEL LIQ SENSOR NO 1</td>
<td>WET DRY EVENT</td>
<td>P</td>
</tr>
<tr>
<td>ET-LH2 LOW LEVEL LIQ SENSOR NO 2</td>
<td>WET DRY EVENT</td>
<td>P</td>
</tr>
<tr>
<td>ET-LH2 LOW LEVEL LIQ SENSOR NO 3</td>
<td>WET DRY EVENT</td>
<td>P</td>
</tr>
<tr>
<td>ET-LH2 LOW LEVEL LIQ SENSOR NO 4</td>
<td>WET DRY EVENT</td>
<td>P</td>
</tr>
</tbody>
</table>

P - PERFORMANCE PARAMETER
CP - CRITICAL PERFORMANCE PARAMETER
FIGURE 4.7-46 MPS/ET SIMULATION MODULE INTERFACES

GENERAL PURPOSE COMPUTERS (flight hardware)

CONTROLS AND DISPLAYS MODULE

MDM

gimbal commands

monitoring data

throttle commands

control commands

display signals

SSME GIMBAL MODULE

thrust

forces, moments

MEC/EIU

ccontrol logic

SPACE SHUTTLE MAIN ENGINES (SSME)

mass remaining

power required, available

MASS PROPERTIES MODULE

HYDRAULIC POWER SUBSYSTEM MODULE

EQUATIONS OF MOTION MODULE
Figure 4.7-43 depicts an "intra-module" functional flow diagram for the major subroutines as well as the primary component process elements used in each of the major subroutines. The main program calls all computational subroutines and controls the model input/output. The subroutine names and their functions are listed in Table 4.7-12. Reference 24 provides a program listing and the user information source.

Complete simulation of the MPS/ET with this digital model requires that the ET and helium supply functions be incorporated. These modifications would consist primarily of simple mass decrements from launch conditions based upon fuel and oxidizer flowrates computed in the RL00001 model. Helium supply for the pneumatic control assembly would be similarly decremented.

**MPS/ET Low-Fidelity Reference Modules -** Figure 4.7-49 (Ref. 25) describes a reference module which would provide low-detailed reference data. This level of fidelity and detail would be adequate for special simulation module verification phases. For example, it would be useful in integrating other simulation verification modules needing only its particular (functional) outputs. It might also be suitable for use with procedures simulators. The lower detailed module would be capable of generating reference data needed to verify corresponding simulation module output in a quick-look verification mode.

Inputs to this reference module consist of:
- throttling commands from guidance
- engine gimbal commands from the Thrust Vector Control System (TVCS)
- nominal vacuum thrust per engine
- atmospheric pressure
- nozzle exit area
- number of engines operating
- oxidizer/fuel mixture ratio

The outputs of this module include:
- the forces and moments acting on the Shuttle from the MPS
- amounts of fuel/oxidizer remaining
- amounts of fuel/oxidizer expended
- fuel mass flow rate
FIGURE 4.7-48. SSME REFERENCE MODULE SUBROUTINES AND ELEMENTS
## Table 4.7-12. SSME Digital Model Subroutines

<table>
<thead>
<tr>
<th>Subroutine</th>
<th>Functions</th>
</tr>
</thead>
<tbody>
<tr>
<td>CNTROL</td>
<td>Simulates digital controller and hydraulic actuation of engine control valves</td>
</tr>
<tr>
<td>DISPL</td>
<td>Generates CRT displays of computed output</td>
</tr>
<tr>
<td>EPRØP</td>
<td>Computes error between ideal gas behavior and real hydrogen property map</td>
</tr>
<tr>
<td>FGEN</td>
<td>General purpose function generator</td>
</tr>
<tr>
<td>FLØW</td>
<td>Computes incompressible fluid flow dynamics</td>
</tr>
<tr>
<td>FUELFL</td>
<td>Computes fuel feed system flow and pressure dynamics</td>
</tr>
<tr>
<td>GFLØW</td>
<td>Computes isentropic gas flow for choked and unchoked orifices</td>
</tr>
<tr>
<td>HØTGAS</td>
<td>Computes engine hot gas pressure and flow dynamics</td>
</tr>
<tr>
<td>HTF</td>
<td>Computes hot gas side heat transfer coefficient</td>
</tr>
<tr>
<td>H2DFPE</td>
<td>Computes hydrogen density as a function of pressure and enthalpy</td>
</tr>
<tr>
<td>H2GAMMA</td>
<td>Computes hydrogen specific heat ratio as a function of pressure and temperature</td>
</tr>
<tr>
<td>IGN</td>
<td>Simulates ignition system transients</td>
</tr>
<tr>
<td>ØXIDF</td>
<td>Computes oxidizer feed system flow and pressure dynamics</td>
</tr>
<tr>
<td>PRØP</td>
<td>Computes hydrogen pressure and temperature as a function of density and internal energy</td>
</tr>
<tr>
<td>TRBTRQ</td>
<td>Simulates hot gas turbine dynamics</td>
</tr>
<tr>
<td>DISPL2</td>
<td>Generates CRT displays of computed output</td>
</tr>
</tbody>
</table>
ENTER

Neng = \( \frac{1}{3} \)
Keng = 1.0

MODE

\( = 1 \)

\( \neq 1 \)

Neng = \( \frac{1}{2} \)
Keng = \( \frac{2}{3} \)

\[
T\text{me} = (T\text{vme} - P\text{a} \cdot P\text{exit}) \cdot \text{Keng} \cdot \text{THe}
\]

\[
W\text{me} = T\text{me} / I_{sp}
\]

\[
M\text{me} = -W\text{me} / g
\]

\[
(F_{me})_{exp} = (F_{me})_{exp} + W\text{me} \Delta t
\]

\[
(F_{me})_{exp} \leq (F_{me})_o
\]

\[
(F_{me})_{exp} > (F_{me})_o
\]

\[
(F_{me})_{rem} = (F_{me})_o - (F_{me})_{exp}
\]

FIGURE 4.7-49. MPS/ET REFERENCE MODULE FLOW DIAGRAM

4.7-120

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[(OX)_{\text{exp}} = (F_{\text{me}})_{\text{exp}} \cdot (OX)_{\text{F}}\]

\[\begin{align*}
(OX)_{\text{exp}} & \leq (OX)_{0} \\
(OX)_{\text{exp}} & > (OX)_{0}
\end{align*}\]

\[(OX)_{\text{rem}} = (OX)_{0} - (OX)_{\text{exp}}\]

\[i = 0\]

\[i = i + 1\]

\[\begin{align*}
\delta Y_i &= \delta Y_i + \delta \Theta Y_i \\
\delta P_i &= \delta P_i + \delta \Theta P_i
\end{align*}\]

\[\begin{align*}
\delta Y_i &= \delta Y_{\text{trim}} + \delta \Theta Y_i \\
\delta P_i &= \delta P_{\text{trim}} + \delta \Theta P_i
\end{align*}\]

\[(T_{\text{me}})_i = T_{\text{me}} \cdot N_{\text{eng}}\]

\[\begin{align*}
(F_{\text{me}})_{\text{x}})_i &= (T_{\text{me}})_i \cdot \cos (\delta P_i) \cdot \cos (\delta Y_i) \\
(F_{\text{me}})_{\text{y}})_i &= (T_{\text{me}})_i \cdot \cos (\delta P_i) \cdot \sin (\delta Y_i) \\
(F_{\text{me}})_{\text{z}})_i &= (T_{\text{me}})_i \cdot \sin (\delta P_i)
\end{align*}\]

FIGURE 4.7-49. (CONTINUED)
Compute trim main engines' thrust forces on body axes (per-engine)

Compute total actual thrust forces acting on body axes

Compute total trim thrust forces acting on body axes

Determine trim thrust vector angles with respect to body axes

Compute position of engine gimbal points with respect to C.G.
FIGURE 4.7-49. (CONTINUED)

\[ (M_X)_i = YEB(FZB_{me})_i - ZEB(FYB_{me})_i \]
\[ (M_Y)_i = ZEB(FXB_{me})_i - XEB(FZB_{me})_i \]
\[ (M_Z)_i = XEB(FYB_{me})_i - YEB(FXB_{me})_i \]

Compute moments on body from each engine

\[ (M_X)_t = (M_X)_1 + (M_X)_2 + (M_X)_3 \]
\[ (M_Y)_t = (M_Y)_1 + (M_Y)_2 + (M_Y)_3 \]
\[ (M_Z)_t = (M_Z)_1 + (M_Z)_2 + (M_Z)_3 \]

Compute total thrust moments acting on body

\[ PCT_F = 100 \cdot \left( \frac{F_{me,rem}}{F_s} \right) \]

Calculate percent main engine fuel remaining

\[ PCTOX = 100 \cdot \left( \frac{OX_{me,rem}}{OX_s} \right) \]

Calculate percent main engine oxidizer remaining

RETURN
<table>
<thead>
<tr>
<th>VARIABLE</th>
<th>FUNCTION</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>( \dot{\mathcal{M}}_{\text{me}} )</td>
<td>Main engines mass flow rate (slugs/sec)</td>
<td>0</td>
</tr>
<tr>
<td>( N_{\text{eng}} )</td>
<td>Internal constant (=1/3 of MODE # 1; = 1/2 if MODE = 1)</td>
<td>0</td>
</tr>
<tr>
<td>( P_a )</td>
<td>Ambient pressure (psf)</td>
<td>1</td>
</tr>
<tr>
<td>( TH_c )</td>
<td>Throttle command</td>
<td>1</td>
</tr>
<tr>
<td>( T_{\text{me}} )</td>
<td>Main engine thrust (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>((T_{\text{me}})_i)</td>
<td>Main engine thrust for engine i (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>( T_{\text{vme}} )</td>
<td>Main engine vacuum thrust (lbs)</td>
<td>DATA</td>
</tr>
<tr>
<td>( TX )</td>
<td>Total thrust forces on body axes (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>( TY )</td>
<td>Total trim thrust forces acting on body (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>( TZ )</td>
<td>Total trim thrust forces acting on body (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>( \dot{\mathcal{W}}_{\text{me}} )</td>
<td>Main engine fuel flow (lbs/sec)</td>
<td>1</td>
</tr>
<tr>
<td>( X_{\text{CG}} )</td>
<td>C.G. position in Orbiter data reference plane (ft)</td>
<td>1</td>
</tr>
<tr>
<td>( Y_{\text{CG}} )</td>
<td>C.G. position in Orbiter data reference plane (ft)</td>
<td>1</td>
</tr>
<tr>
<td>( Z_{\text{CG}} )</td>
<td>C.G. position in Orbiter data reference plane (ft)</td>
<td>1</td>
</tr>
<tr>
<td>( X_{\text{EB}} )</td>
<td>Position of engine gimbals with respect to C.G. in body axes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( Y_{\text{EB}} )</td>
<td>Position of engine gimbals with respect to C.G. in body axes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( Z_{\text{EB}} )</td>
<td>Position of engine gimbals with respect to C.G. in body axes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( X_{\text{Gi}} )</td>
<td>Gimbal position of engine i in Orbiter data reference planes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( Y_{\text{Gi}} )</td>
<td>Gimbal position of engine i in Orbiter data reference planes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( Z_{\text{Gi}} )</td>
<td>Gimbal position of engine i in Orbiter data reference planes (ft)</td>
<td>DATA</td>
</tr>
<tr>
<td>( \text{PCTF} )</td>
<td>Percent main engine fuel remaining</td>
<td>0</td>
</tr>
<tr>
<td>( \text{PCTOX} )</td>
<td>Percent main engine oxidizer remaining</td>
<td>0</td>
</tr>
<tr>
<td>( \Delta t )</td>
<td>Subroutine internal integration internal (sec)</td>
<td>1</td>
</tr>
<tr>
<td>( SP_i )</td>
<td>Pitch gimbal angle of engine i with respect to null (rad)</td>
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</tr>
<tr>
<td>( SPB_i )</td>
<td>Pitch gimbal angle of engine i with respect to body axis (rad)</td>
<td>1</td>
</tr>
<tr>
<td>( SPT_i )</td>
<td>Pitch gimbal trim angle of engine i with respect to body axis (rad)</td>
<td>1</td>
</tr>
<tr>
<td>( \dot{A}_{\text{exit}} )</td>
<td>Main engine nozzle exit area (ft²)</td>
<td>1</td>
</tr>
<tr>
<td>( (F_{\text{me}})_{\text{exp}} )</td>
<td>Main engine fuel expended (lbs)</td>
<td>0</td>
</tr>
<tr>
<td>( (F_{\text{me}})_{\text{rem}} )</td>
<td>Main engine fuel remaining (lbs)</td>
<td>1</td>
</tr>
<tr>
<td>( (F_{\text{me}})_{0} )</td>
<td>Main engine fuel onboard at time = 0 (lbs)</td>
<td>1</td>
</tr>
<tr>
<td>( F_s )</td>
<td>Main engine fuel onboard at launch (lbs)</td>
<td>1</td>
</tr>
<tr>
<td>VARIABLE</td>
<td>FUNCTION</td>
<td>TYPE^a</td>
</tr>
<tr>
<td>----------</td>
<td>----------</td>
<td>--------</td>
</tr>
<tr>
<td>(OX)_{exp}</td>
<td>Main engine oxidizer expended (lbs)</td>
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</tr>
<tr>
<td>(OX)_{rem}</td>
<td>Main engine oxidizer remaining (lbs)</td>
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<tr>
<td>(OX)_{o}</td>
<td>Main engine oxidizer onboard at time = 0 (lbs)</td>
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<td>Main engine oxidizer onboard at launch (lbs)</td>
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</tr>
<tr>
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<td>Main engine thrust forces on body axes for engine i (lbs)</td>
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</tr>
<tr>
<td>(FYB_{me})_{i}</td>
<td>Main engine trim thrust forces on body axes for engine i (lbs)</td>
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</tr>
<tr>
<td>(FZB_{me})_{i}</td>
<td></td>
<td></td>
</tr>
<tr>
<td>g</td>
<td>gravitational acceleration (ft/sec^2)</td>
<td>1</td>
</tr>
<tr>
<td>i</td>
<td>Main engine number</td>
<td>1</td>
</tr>
<tr>
<td>= 1-upper; = 2-lower left; = 3-lower right</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Isp</td>
<td>Specific impulse</td>
<td>1</td>
</tr>
<tr>
<td>K_{eng}</td>
<td>Ratio of number of main engines on to total</td>
<td>1</td>
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<tr>
<td>MODE</td>
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<tr>
<td>= 1-all operating</td>
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<tr>
<td>= 2-upper engine failed</td>
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<td>= 3-left engine failed</td>
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<td>= 4-right engine failed</td>
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<tr>
<td>(MXE)_{i}</td>
<td>Moments about body axes due to engine i (ft/lbs)</td>
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<tr>
<td>(MZE)_{i}</td>
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<tr>
<td>(MXE)_{s}</td>
<td>Total engine moments on body axes (ft/lbs)</td>
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<tr>
<td>(MZE)_{s}</td>
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<td>SPTRIM;</td>
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<tr>
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<td>Yaw gimbal angle of engine i with respect to null (rad)</td>
<td>I</td>
</tr>
<tr>
<td>SY_{B}</td>
<td>Yaw gimbal angle of engine i with respect to body axis (rad)</td>
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<td>SYTRIM;</td>
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<tr>
<td>(\Theta_P_{i})</td>
<td>Pitch null angle of engine i with respect to body axis (rad)</td>
<td>DATA</td>
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<tr>
<td>(\Theta_{TRIM})</td>
<td>Pitch angle of trim thrust vector with respect to body axes (rad)</td>
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**FIGURE 4.7-49. (CONTINUED)**
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<td>Yaw null angle of engine i with respect to body axis (rad)</td>
<td>DATA</td>
</tr>
<tr>
<td>$\psi_{TRIM}$</td>
<td>Yaw angle of trim thrust vector with respect to body axes (rad)</td>
<td>0</td>
</tr>
</tbody>
</table>

aI - Input
0 - Output
DATA - Data resident in program

FIGURE 4.7-49. (CONTINUED)
trim thrust vector angles with respect to body axes

In developing this model it was assumed that throttling commands are generated by guidance (no manual throttle capability), no engine internal dynamics are simulated (instantaneous throttle response), and no internal SSME subsystems simulation (plumbing and valve dynamics, turbopump dynamics, internal thermodynamics). Thrust is decayed instantaneously at SSME cutoff.

MPS/ET Validation Methods and Check Cases
Complete simulation module verification requires exercising the MPS/ET simulation software through the extremes of the various subsystem inputs to verify proper response to the influencing subsystem stimuli. Comparison of the reference module response to that of the simulation module will determine simulation module validity. Actual verification will be performed in an off-line or batch test mode using special check cases.

Check case design will incorporate functions to exercise the simulation and reference modules throughout the Minimum Power Level (MPL), the Nominal Power Level (NPL), and the Emergency Power Level (EPL). The level of detail employed in the reference module and the specific verification conditions will determine the type of check case used.

High-Fidelity Check Cases - High-fidelity, dynamic verification of the simulation module requires check cases which evaluate the MPS/ET simulation module in the regions of start, throttling, and engine cutoff operations. Through each of these regions, performance parameters for each subsystem would be output and compared with the reference module results. Subsystem transient behavior and steady-state values must be checked. Comparisons would be made using plot output similar to the Figure 4.7-50 description of the SSME high-pressure fuel turbine torque characteristics. This detailed plot represents internal SSME functions. Automated techniques, discussed in Section 5.3, can also be used in evaluating the check case results.

Low-Fidelity Check Cases - Low-level check cases, employed with the corresponding reference module, may also be required. Check cases composed of static conditions would be used. For example, discrete throttling levels evaluated with respect to 4.7-127
LEGEND:

$\tau_{FT2}$ = torque function (in-lbs); high pressure fuel turbine

$FT2S$ = fraction of pressure ratio available for fuel turbine power (dimensionless)

$P_{FI}$ = main fuel injector pressure

$P_{FP}$ = fuel preburner pressure

$\eta_{FT2}$ = high pressure fuel turbine speed parameter

FIGURE 4.7-50. HIGH-PRESSURE FUEL TURBINE TORQUE CHARACTERISTICS
thrust and consumables usage (fuel and oxidizer) would be needed to check simulation module outputs to Vehicle Dynamics and Mass Properties modules.

MPS/ET Data Base Impact

Data base requirements for verification of the MPS/ET simulation module consist of the reference module(s), the reference module generated data, check cases, and various service routines as necessary. A high-fidelity module verification will require a complex reference module and corresponding check cases. Impact upon the verification data base will increase in accordance with reference module complexity.
4.7.3.2 Reaction Control Subsystem (RCS)

RCS Description

The RCS provides maneuvering capabilities for the Orbiter during Insertion, On-orbit, and Entry phases. The RCS provides additional capabilities for attitude changes and small translational accelerations.

As defined in Reference 20, the RCS is composed of one forward and two aft RCS modules. The forward module consists of two thruster clusters, a left side and a right side cluster. Each cluster contains eight main thrusters and three vernier thrusters. The fuel and oxidizer propellant tankage is shared by the two clusters. The aft RCS consists of two modules, a left and a right module. Each aft module is independent, consisting of twelve main thrusters, fuel and oxidizer tanks with separate propellant pressurant systems and the associated plumbing and components. However, the fuel and oxidizer sources for each aft RCS module can be inter-shared, as well as with the sources for each of the two OMS pods and the OMS payload bay kit (when carried for extended mission capabilities).

Figure 4.7-51 (from Reference 20) depicts the plumbing and thruster system of a typical forward RCS module indicating the cluster grouping. A typical aft RCS module is depicted in Figure 4.7-52, including the OMS and other aft RCS module interconnects. Figure 4.7-53 provides a more comprehensive indication of the propellant sharing capability by the valves and interconnects between the aft RCS modules, the OMS pods, and the OMS payload bay kit forming the auxiliary propulsion subsystem.

RCS Simulation Module Description and Performance Parameters

The RCS simulation module provides the capability to simulate the RCS throughout the design operating ranges of the subsystem and interfacing systems.

An example of the subsystems interaction and influence is that of the propellant subsystem interface with the crossover plumbing subsystem to provide crossfeed or sharing of propellant sources between the appropriate auxiliary propulsion subsystems. Each individual propellant source will be simulated for a defined mission or mission phase. These capabilities will encompass the subsystems nominal operational limits, the blueline and redline limits, and the design limits.
FIGURE 4.7-52 RCS BIPROPellant AFT Module (LEFT SIDE)
FIGURE 4.7-53 AUXILIARY PROPULSION SUBSYSTEM SCHEMATIC INTERCONNECTED OMS & RCS POD SHOWN
to simulate the proper response and capability of the RCS simulation module. The
dynamics of the propellant sources usage are also influenced by the propellant
pressurant sources, pressurant depletion rates, pressurant fill pressures, tem-
perature, and volume, the propellant flow rates, the propellant initial fill
quantities, the insertion accuracy, OMS usage, and the plumbing and associated
valve configuration for the normal and crossfeed lines for the specific simulated
conditions.

RCS thruster firing signals interface with the avionics module with inputs
initiated by automated systems and hand controllers. The RCS simulation module
interfaces with other simulation modules are depicted in Figure 4.7-54. Tables
4.7-13 and 4.7-14 list the performance parameters for the respective forward and
aft RCS modules, in the RCS simulation module (Ref. 21).

**RCS Reference Data Sources and Data Formats**

Figure 4.7-55 (Ref. 27) describes a subroutine, RCSENG, from the SVDS
simulation/analysis program (Ref. 28). RCSENG can be combined with a driver to
form a reference module which would serve as an adequate data source for RCS
verification reference data.

RCSENG computes the thrust of up to 35 user specified RCS jets on the Orbiter.
Hardware on and off thruster firing delays are simulated using an "equivalent square
wave" technique. Within the integration interval in which the thrust is acting,
this square wave is averaged to produce a constant thrust over the entire interval
with the total impulse remaining unchanged. A jet status table enables simulation
of manual on-off control and jet system failures (Ref. 27). RCS forces and
torques in Orbiter body axis coordinates are computed—both individually (each jet)
and collectively (summed).

RCSENG inputs consist of (Ref. 28):
- Number and location of RCS jets simulated
- RCS thrust vectors (directions and magnitudes)
- Turn on-off time delays
- RCS jet minimum electrical on-time
- Manual on-off jet control flag.
FIGURE 4.7-54 RCS SIMULATION MODULE INTERFACES
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<th>DATA RANGE</th>
<th>TYPE</th>
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<td>CP</td>
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<tr>
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<td>0 +5000 PSIA</td>
<td>CP</td>
</tr>
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<td>CP</td>
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<td>CP</td>
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<td>I/P</td>
</tr>
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<td>I/P</td>
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<td>I/P</td>
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<td>I/P</td>
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<td>I/P</td>
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<tr>
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**TABLE 4.7-13 (CONTINUED)**

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a  P - Performance Parameter
   CP - Critical Performance Parameter
   I - Input

b indicates 2 parameters (command and response)
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<td>CP</td>
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<td>0 +5000 PSIA</td>
<td>CP</td>
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<td>Helium Fuel Tank Pressure</td>
<td>0 +5000 PSIA</td>
<td>CP</td>
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<td>CLOSE EVENT I/P</td>
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<td>CP</td>
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<td>CP</td>
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<td>Thruster Injector Temperature No. 39</td>
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<td>CP</td>
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<tr>
<td>Oxidizer Heater Primary CMD/RESP</td>
<td>ON EVENT I/P</td>
<td></td>
</tr>
</tbody>
</table>

- **P** - Performance Parameter
- **CP** - Critical Performance Parameter
- **I** - Input

*b* indicates 2 parameters (command and response)
SUBROUTINE RCSENG

C SET UP VEHICLE INDEX AND DETERMINE IF ROUTINE IS TO BE EVALUATED

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FIGURE 4.7-55. RCSENG SUBROUTINE FLOW CHART
The electrical time variable is computed and jet status table interrogation counter is set to zero,

\[ t_{\text{NEW}} = t_{\text{C}} + \Delta t_{\text{R}} \]

\[ \text{LCOUNT} = 0 \]

- If the jet status table is not used (IFALCO=0) the next test is performed on the status of the specific vehicle table, otherwise control is advanced to the jet status for manual on-off jet control computations.

- If the inputs are made to jet status tables (IFLGC=0) then control is advanced to compute jet on and off times for open loop steering, otherwise control continues.

- If the control frequency computation interval is less than or equal to zero (\( \Delta t_{\text{R}} \leq 0 \)), RCSENG is exited and control is returned to main program, otherwise control is advanced to storing the total body torques and forces.

- The jet status for manual on-off jet control is computed if the sum of the appropriate jet status table value and the tolerance on current time is less than the current time \( t_{\text{C}} \), otherwise control is returned back to the test of the jet status input flag.

- Indices used to locate proper ECS jet status flag is computed.

**FIGURE 4.7-55. (CONTINUED)**
A test node on the index value to ensure that a value is input in the jet status table that was specified by IPLOC. If no value is present, control advances to an error message print out, otherwise control continues.

The RCS jet status flag is set equal to the appropriate value of the manual on-off control of the RCS jet.

The subscript for the jet status table is set equal to the subscript for the jet status table which indicates the next location plus one.

If the difference in the manual on-off control of the RCS jet and the tolerance at current time is less than or equal to current time ($t_f$) then control is advanced to the update of the jet status table index and recycled back to the composition of the RCS jet indices, otherwise logic flow continues.

If the $i$th value of the manual on-off control is greater than or equal to the $i$th plus one value plus the tolerance on current time then the jet status flag is set to zero (IPLOC=0) indicating no inputs were made to the table for that vehicle. If the test is false, the jet status table index is updated and control recycled back to the test of the jet status input flag.
The jet status table index is updated by one.

A test is made to determine if the jet status table has been interrogated fifty times. If the fifty passes are made then an error message is printed which states that the "jet status table" flag (IPLCO) was input one and no values were input to the jet status table. Control is then returned to test the next table flag. If JCOUNT is less than fifty interrogation logic is recycled.

If open loop control is being used (CONFLOP) logic continues, otherwise control advances to the zeroing of the RCS force and moment.

Vehicle data index is computed.
- If a given jet fails (JFAIL=0), then the electrical on time ($t_{on}$) is set equal to the current time ($t_c$), and the electrical off time ($t_{off}$) is set equal to electrical time variable:

$$t_{on} = t_c$$
$$t_{off} = t_c$$

or if jet is not failed (JFAIL=1), then $t_{on}$ and $t_{off}$ are zeroed.

$$t_{on} = 0$$
$$t_{off} = 0$$

- The time at which the control system or jet status was evaluated is equal to current time.

$$t_{PP} = t_c$$

- Vehicle data index is computed.

- Vehicle RCS forces and moments are zeroed.

$$F_{S7} = 0$$
$$H_{T7} = 0$$

**Figure 4.7-55 (Continued)**
FIGURE 4.7-55. (CONTINUED)

- Vehicle data index is computed.

- If the time at which the thrust goes on \( t_{\text{JON}} \) is greater than the current time \( t_e \), logic advances to the test of \( t_{\text{JPP}} \), otherwise logic flow continues.

- The time at which the thrust goes on \( t_{\text{JON}} \), and the time at which the thrust goes off \( t_{\text{OFF}} \) are set equal to the square wave on and off times which were saved from the previous evaluation of the routine, in the event that the jet was issued an electrical on signal before \( t_{\text{JON}} \) or \( t_{\text{OFF}} \) had occurred. The previous times are then redefined.

\[
\begin{align*}
& t_{\text{JON}} = t'_{\text{JON}} \\
& t_{\text{OFF}} = t'_{\text{OFF}} \\
& t'_{\text{OFF}} = 0
\end{align*}
\]

- If \( t_{\text{JPP}} \) is less than the current time \( t_e \) the logic which computes the square wave on and off is bypassed (meaning no electrical on and off signals have been issued) and control is transferred to the computation of the thrust, otherwise logic continues.

- If the electrical off signal \( t_{\text{OFF}} \) is less than or equal to the current time, it is assumed that no electrical signal has been issued for the jet and the square wave logic is bypassed, however, if the test is false logic flow continues.

- If the save value of the electrical off time \( t'_{\text{OFF}} \) plus the tolerance on current time \( t_e \) is less than the electrical on time \( t_{\text{ON}} \) control is transferred to the computation of the next portion of the square wave. If the test is false, logic flow continues.
If the past value of the time at which the thrust goes off is less than or equal to the present value, the logic flow continues, otherwise control is advanced to the calculation of t_{OFF}.

- If t_{OFF} is greater than zero then it is updated by:

\[ t_{OFF} = t_{OFF} + t_{PP} - E_{ON} \]

Control is then advanced to the calculation of E_{OFF}.

- If t_{OFF} is less than or equal to zero then it is updated by:

\[ t_{OFF} = t_{OFF} + E_{OFF} - E_{ON} \]

Control is then advanced to the calculation of E_{OFF}.

The past time at which the thrust cuts off is updated as:

\[ t_{OFF} = t_{OFF} + E_{ON} \]

Control is then advanced to the calculation of E_{OFF}.

---

**FIGURE 4.7-55. (CONTINUED)**
If the thrust on time \( t_{ON} \) is greater than the current time, the new "square wave" on and off times must be solved because \( t_{ON} \) is still required in computing the current thrust, otherwise control is transferred to the calculation of \( t_{ON} \) and \( t_{OFF} \).

The new "square wave" times are computed:

\[
\begin{align*}
\hat{t}_{ON} &= t_{ON} + \Delta t_{ON} \\
\hat{t}_{OFF} &= t_{OFF} + \Delta t_{OFF}
\end{align*}
\]

If the thrust on time \( t_{ON} \) is less than past value of the thrust off time \( t_{OFF} \), control is advanced to the calculation of \( t_{OFF}' \). If the \( t_{ON} \) is false then \( t_{OFF} \) is updated.

\[
\hat{t}_{OFF} = t_{OFF} + \Delta t_{OFF}
\]

Control is then advanced to the calculation of \( t_{OFF}' \).

The thrust on and off times are computed for the new "square wave" with engine time delays:

\[
\begin{align*}
\hat{t}_{ON} &= t_{ON} + \Delta t_{ON} \\
\hat{t}_{OFF} &= t_{OFF} - \Delta t_{OFF}
\end{align*}
\]

If the thrust on time \( t_{ON} \) is less than the thrust off time \( t_{OFF} \), then control is advanced to the calculation of \( t_{OFF}' \). Otherwise \( t_{OFF} \) is recomputed as

\[
\hat{t}_{OFF} = t_{OFF} + \Delta t_{OFF}
\]

Figure 4.7-55. (continued)
- The past value of the electrical cut off time (t\text{Off}) is computed.

\[ t_{\text{Off}} = t_{\text{Off}} \]

- If the control frequency step size is less than or equal to zero (open loop steering option), control is advanced by bypassing the thrust on the "square wave," otherwise control continues.

\[ F(JETRI1) \rightarrow 190, 200, 108 \]

- If the jet fail flag is less than zero again control bypasses computing the thrust based on the square wave, if the flag is equal to zero (jet failed) the average thrust is set to zero, otherwise the jet does not fail (flag greater than zero) then the average thrust is set to zero.

\[ T_{\text{AVG}} = 0 \]

- If the control system is to be evaluated on the next integration step (the test is false) the electrical off time is not equal to the current time:

\[ t_{\text{Off}} = t \]

and the logic advances to the computation of the RCS forces and torques. Likewise if the test is true control also advances to the computation of RCS forces and torques.
- The average thrust is set equal to the thrust magnitude.
  \[ T_{AVG} = T_{THR} \]
- If the control system is to be evaluated at the next integration step (test is false), the post value of the electrical off time is set equal to the current time plus \( \Delta t_M \).
  \[ T_{OFF} = T_{RX} \]
- Entry into this point of logic denotes that there is no jet fail and the following logic computes the square wave to denote the thrust interval.
- If the jet on time is greater than or equal to current time plus \( \Delta t_M \), then the average thrust is zeroed;
  \[ T_{AVG} = 0.0 \]
  and control is advanced to further test to determine square wave configuration, however, if the test is true, logic flow continues.
- If the jet on time is greater than or equal to the current time logic flow is advanced to the test of jet off time with \( T_{ON} \), otherwise logic flow continues.

**Figure 4.7-55. (continued)**
- If the thrust off time is greater than or equal to the current time plus $\Delta t$, then average thrust is set equal to the thrust magnitude:

$$T_{AVG} = T_{MAG}$$

and logic flow is advanced to further test to determine the square wave configuration. However, if the test is true, logic flow continues.

- If the thrust off time is less than or equal to the current time, the average thrust is set equal to zero:

$$T_{AVG} = 0.0$$

and control is advanced to further test to determine the square wave configuration. However, if the test is true, the average thrust is set equal to:

$$T_{AVG} = \left( T_{OFF} - C_{B} \right) / C_{S}$$

then the flow advances to further test to determine the square wave configuration.
If the jet off time is less than the current time plus \( \Delta t_R \), the average thrust is defined as:

\[
\tau_{AVG} = \left( \tau_{JOFF} - \tau_{JON} / \Delta t_R \right) \tau_{HAG}
\]

otherwise the average thrust is defined as:

\[
\tau_{AVG} = \left( \tau_{JEX} - \tau_{JON} / \Delta t_R \right) \tau_{HAG}
\]

- At this point further tests are made to determine the square wave configuration.
- If the thrust on time is less than the current time or greater than or equal to current time plus \( \Delta t_R \), then proceed to compute the RCS forces. Otherwise, the logic continues.

If the thrust off time is less than the current time plus \( \Delta t_R \), then the average thrust is redefined as:

\[
\tau_{AVG} = \tau_{AVG} + \left( \tau_{OFF} - \tau_{JON} / \Delta t_R \right) \tau_{HAG}
\]

FIGURE 4.7-55. (CONTINUED)
If the previous test is true then the average thrust is

\[ T_{AVG} = T_{AVG} + \left( \frac{(c_{260} - t_{260})}{t_{260}} \right) T_{KAD} \]

At this point the computed thrust is used to calculate the forces and moments for each jet and sum overall jets. If the average thrust is zero the RCS jet logic is recycled, if it is not then the logic flow continues.

Vehicle dependent index to locate data in the RCSARC array is computed.

The force due to a particular jet is computed from the average thrust and the direction cosine between the RCS jets thrust vector and the vehicle's RCS axes.

\[ \overline{F} = T_{AVG} RCS_{i} \]

for each jet

The torque due the RCS jet is computed as:

\[ \overline{H} = RCS_{i} \times \overline{F} \]

The total torque is then

\[ \overline{H}_{T} = \sum_{i=1}^{n} \overline{H}_{i} \text{ for jet } i \]
The total force per vehicle is then
\[
F_T = \sum_{i=1}^{n} F_i
\]
- The RCS logic is recycled until all jets are evaluated.
- Control is returned to the main program.

**LEGEND:**

**RCSENG COMMON VARIABLE DESCRIPTION TABLE**

<table>
<thead>
<tr>
<th>CODE</th>
<th>MATH</th>
<th>USE</th>
<th>DIMENSION</th>
<th>COMMON ARRAY</th>
<th>DEFINITION OF VARIABLE</th>
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<tbody>
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<td>U</td>
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<td>DAP1 (1)</td>
<td>RCS/EVC DAP CONTROL SYSTEM MODEL, COMPUTATION INTERVAL (SEC)</td>
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<tr>
<td>DELTR</td>
<td>( \Delta T )</td>
<td>U</td>
<td>1</td>
<td>GNDAT1 (2)</td>
<td>RCS JET MINIMUM ELECTRICAL ON TIME</td>
</tr>
<tr>
<td>DTMIN</td>
<td>( \Delta T_{MIN} )</td>
<td>U</td>
<td>25</td>
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<td>RCS JET MINIMUM ELECTRICAL ON TIME</td>
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<td>TIME DELAY IN TURNING OFF EACH RCS JET</td>
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<td>DTON</td>
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<td>E ON</td>
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<td>EPS</td>
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<td>TOLERANCE ON CURRENT IF trim FOR EVALUATION OF JET STATUS TABLE (SEC)</td>
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<td>F J J T</td>
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<td>C/U</td>
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<td>F J U S</td>
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<td>U</td>
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<tr>
<td>J SS V</td>
<td>C/U</td>
<td>25</td>
<td>RJDAT1 (207)</td>
<td>INDEX FOR JET STATUS TABLE WHICH INDICATES NEXT LOCATION TO BE USED</td>
<td></td>
</tr>
</tbody>
</table>

**FIGURE 4.7-55. (CONTINUED)**
CODE    MATH     USE    DIMENSION    COMMON ARRAY
-------    -------    -------    ---------    ----------------------
NRCS     U         1        DAPI (35)  INTEGER NUMBER OF TVC SAMPLE PERIOD
PEDFF    E         0,25      RJDA11,331  CONTROL LOOP CYCLED
RCSANG   Rcs, Rcs, Rcs Y  3,25      RJDA11,71  SAVED VALUE OF EOFF FROM PREVIOUS CONTROL
RCSLOC   X, Y, Z    3,25      RJDA11,21  SYSTEM EVALUATION (SEC)
TIMEC    Tc         1        RJDA12,183  DIRECTION COSINES OF THRUST VECTOR
TPP      Tp         0,25      RJDA11,356  OF THE RCS JET
THG      Tmag       0,25      RJDA11,177  CURRENT TRAJECTORY TIME (SEC)
TORQJT   M          0,25      RJDA11,357  THUST MAGNITUDE OF EACH RCS JET (LBS)
JTEST    C         0,25      RJDA21,208  TOTRAJECTORY TIME THAT THE RCS DAP
          C         0,25      RJDA21,169  CONTROL SYSTEM WAS EVALUATED (SEC)
          C         0,25      RJDA21,174  THRUST MAGNITUDE OF EACH RCS JET (LBS)
          C         0,25      RJDA21,11  TOTAL MOMENT ABOUT VEHICLE CG IN VEHICLE
          C         0,25      RJDA21,11  RCS (FT-LBS)

RCSENG INTERNAL VARIABLE DESCRIPTION TABLE

CODE    MATH     DEFINITION OF VARIABLE
-------    -------    ----------------------
FBJ       F         RCS COMPONENTS OF THE FORCE VECTOR PRODUCED BY A SINGLE
              RCS JET (LBS)
IJCOUNT    IV        INTERNAL COUNTER
JV         IJ        VEHICLE INDEX
JSS        S         SUBSCRIPT FOR THE JET STATUS TABLE
JTFAIL    IJ        RCS JET STATUS FLAG
          0         NO MANUAL COMMAND TO JET
          -1        JET COMMANDED ON
          -2        JET COMMANDED OFF
N          IJ        NUMBER OF JETS
TJOFF     Toff      TIME AT WHICH JET IS ACTUALLY TURNED OFF. (SEC)
TJOFFS    Toff      SAVED VALUE OF TJOFF IN THE EVENT THAT EON IS ISSUED BEFORE
              TJOFF OCCURS. (SEC)
TJON      Toh       TIME AT WHICH RCS JET IS ACTUALLY TURNED ON. (SEC)
TJONS     Toh       SAVED VALUE OF TJON IN THE EVENT THAT EON IS ISSUED BEFORE
              TJON OCCURS. (SEC)
TNEXT     Tn        TEMPORARY VARIABLE EQUIVALENT TO CURRENT TIME PLUS THE
              ROTATIONAL INTEGRATION STEP SIZE. (SEC)
TORQJT    M         RCS COMPONENTS OF THE TORQUE VECTOR PRODUCED BY A SINGLE
              RCS JET. (FT-LBS)

FIGURE 4.7-55. (CONTINUED)
Outputs of RCSENG are the individual and summed RCS thrust forces and torques on the Orbiter. RCS mass properties information is not computed in RCSENG.

A driver must be constructed to ensure a complete RCS reference module. In addition to providing input/output simulation module compatibility, the RCS reference module driver must provide accurate simulation of: (1) fuel and oxidizer mass consumed during RCS activation (including turn on-off losses) and (2) RCS/OMS propellant sharing interface functions. These calculation and logic sequences should not be difficult to implement.

RCS Validation Methods and Check Cases

Check cases for RCS simulation module verification should consist of static and dynamic command sequences to exercise both the simulation and reference modules.

In the static check cases, each RCS jet could be fired and its effects on Orbiter body axis forces and moments analyzed. Individual jet thrust and consumables usage can be similarly evaluated. Static firing check cases for groups of RCS jets should be developed to check collective jet performance.

Dynamic check cases would be composed of integrated jet firing command sequences which simulate actual Orbiter maneuvers or manual and automatic control systems. Dynamic maneuvers include:

- Orbiter/ET separation
- Docking/payload handling
- Entry attitude control

Data Base Impact

RCS Simulation Module verification data base requirements consist of:

- RCS reference module
- Resident reference data and check cases
- Any additional routines, jet tables, etc. as needed for verification

The reference module, once developed, should not expand significantly; however, vehicle design changes involving the placement and thrust of individual and groups of RCS jets and various control system modifications will require the construction of additional check cases.
4.7.3.3 Orbital Maneuvering System (OMS)

OMS Description

The OMS provides maneuvering capabilities for the Orbiter during orbital insertion, on-orbit, and de-orbit mission phases. The OMS is contained in two semi-independent pods located on the aft portion of the Orbiter. The prime components of each OMS pod are the OMS engine, fuel tank, oxidizer tank, propellant pressurant system, and the associated plumbing and components. However, the fuel and oxidizer sources can be inter-shared between pods, as well as the sources for the aft RCS pods.

Figure 4.7-56 illustrates the propellant sharing capability, by use of manifolding tanks and isolation valves, between the two OMS pods and the aft RCS modules. Figures 4.7-57, 4.7-58, and 4.7-59 depict the tankage, engine, optional OMS payload bay kit, and respective associated hardware for one OMS pod (Ref. 20).

OMS Simulation Module Description and Performance Parameters

Simulation of the OMS will utilize a combination of logical, functional, and explicit engineering equations to calculate the required parameters. For simulation purposes, the OMS module will provide the OMS thrust as well as crew displays of fuel, oxidizer, helium, and engine chamber pressure, and for oxidizer and fuel quantities (Ref. 11).

Included in the simulation module will be subsystem simulation and interaction. An example of the subsystems interaction and influence is that of the propellant subsystem interface with the pressure subsystem which maintains proper propellant flow in a non-gravity environment. The dynamics of the pressurant subsystem are also influenced by the depletion, the flow rates, the burn mixture ratio, and initial fill quantities of the fuel and oxidizer as well as the burn characteristics of the engine within its design profile box and the associated valves, and plumbing configurations.

Figure 4.7-60 depicts the OMS simulation module interfaces with other simulation modules. The performance parameters associated with the OMS module are described in Table 4.7-15 (Ref. 21).
FIGURE 4.7-56 AUXILIARY PROPULSION SUBSYSTEM SCHEMATIC INTERCONNECTED OMS & RCS LEFT POD SHOWN
FIGURE 4.7-57 OMS LEFT POD OPERATIONAL INSTRUMENTATION MEASUREMENTS
FIGURE 4.7-58 OMS ENGINE OPERATIONAL INSTRUMENTATION MEASUREMENTS
FIGURE 4.7-59 OMS PAYLOAD BAY KIT OPERATIONAL INSTRUMENTATION MEASUREMENTS
FIGURE 4.7-60, OMS SIMULATION MODULE INTERFACES
### TABLE 4.7-15 OMS MODULE PARAMETER LIST

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>FIGURE 2, PROPELLANT SUBSYSTEMS</strong></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Engine Fuel Crossfeed Line Temperature</td>
<td>Low 0</td>
<td>High +200 Deg F P</td>
</tr>
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<td>Close Open Event P</td>
<td></td>
</tr>
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<td>Engine Fuel Crossfeed Valve No. 2 Position</td>
<td>Close Open Event P</td>
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</tr>
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<td><strong>FIGURE 2, PROPELLANT SUBSYSTEMS (continued)</strong></td>
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<td>Engine Oxidizer Feed/Dump Valve Position</td>
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<td><strong>FIGURE 3, ENGINE</strong></td>
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<td><strong>FIGURE 4, PAYLOAD BAY KIT</strong></td>
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</tr>
<tr>
<td>Vapor Isolation Valve No. 2 Position - Auxiliary</td>
<td>Close</td>
<td>Open</td>
</tr>
</tbody>
</table>

a P - Performance Parameter
CP - Critical Performance Parameter
I - Input
OMS Reference Data Sources and Data Formats

The Figure 4.7-61 math flow describes the subroutine THR2, from the SSFS simulation/analysis program (Ref. 17), which can be modified slightly and combined with a main program driver to form a reference module capable of generating OMS verification reference data.

THR2 models OMS thrust for a maximum of three equivalent thrust Orbiter OMS engine (currently there are only two). The model assumes that each engine is independently gimballed and that the engine deflections are input from an OMS actuator model. THR2 computes and outputs OMS thrust forces and torques in the Orbiter body axis coordinate system.

The direction of output thrust force, Q, depends upon engine location and deflection. Engine locations are initially specified in the Fabrication (F) frame. An engine coordinate system (E) and an actuator coordinate system (A) are also defined for each engine. Figure 4.7-62 depicts the various coordinate system relationships used in THR2.

Inputs to THR2 consist of:
- Location of vehicle mass center in body axis system
- Fabrication to vehicle body axis transformation matrix
- Engine actuator locations and mounting angles
- Engine thrust and gimbal deflections
- Fuel loss per OMS firing
- Specific impulse
- Number of OMS engines
- Thrust command on-off delays and minimum impulse time

Outputs are the computed OMS forces and torques in body axis coordinates along with fuel mass consumed.

To function adequately as a reference data source, THR2 must be modified to include calculation of OMS oxidizer consumed. Fuel and oxidizer consumption are then output. A main program (driver) should also be incorporated to control and maintain input/output compatibility with the simulation module. This includes the OMS/RCS propellant sharing interface and propellant pressurant calculations.
FIGURE 4.7-61. THR2 SUBROUTINE MATH FLOW
4.7-167

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ N_i = (R_{VA_i} - R_{VK}) \times Q_i \]

\[ Q = \sum_{i=1}^{NE} Q_i \]

\[ N = \sum_{i=1}^{NE} N_i \]

**Legend:**

- \( X_v, Y_v, Z_v \): Axes of the vehicle (V) body frame.
- \( X_F, Y_F, Z_F \): Axes of the fabrication (F) frame.
- \( X_{E_i}, Y_{E_i}, Z_{E_i} \): Axes of the \( i \)th engine (E) frame.
- \( X_{A_i}, Y_{A_i}, Z_{A_i} \): Axes of the \( i \)th actuator (A) frame.
- \( R_{FV} \): Position of the vehicle's (V) body frame in the fabrication (F) frame, meters.
- \( R_{FA_i} \): Position of the \( i \)th engine actuator (A) in the fabrication (F) frame, meters.
- \( R_{VA_i} \): Position of the \( i \)th engine actuator (A) in the vehicle (V) body frame, meters.
- \( [F_{MA_i}] \): Attitude matrix to go from the \( i \)th actuator (A) frame to the fabrication (F) frame.

**Figure 4.7-61 (Continued)**

4.7-163
\[
\begin{align*}
[V_{MF}] & \quad \text{Attitude matrix to go from the fabrication (F) frame to the vehicle (V) body frame.} \\
[V_{MA}]_i & \quad \text{Attitude matrix to go from the } i\text{th actuator (A) frame to the vehicle (V) body frame.} \\
T_{\text{mass}} & \quad \text{Thrust magnitude divided by the gravitational acceleration.} \\
I_{SP} & \quad \text{Specific impulse.} \\
DT & \quad \text{Delta time since last update.} \\
T & \quad \text{Present time.} \\
T_L & \quad \text{Time of the last THR2 update.} \\
T_{\text{ON}_i} & \quad \text{Time } i\text{th CMS engine has been on.} \\
M_{\text{LOSS}} & \quad \text{Fuel lost per CMS engine firing.} \\
I_{\text{FIRE}_i} & \quad \text{Number of times } i\text{th CMS engine has been fired.} \\
\dot{M}_{\text{FUEL}} & \quad \text{Mass flow rate.} \\
M_{\text{FUEL}_i} & \quad \text{Mass of the fuel used by the } i\text{th CMS engine.} \\
M_{\text{FUEL}} & \quad \text{Total fuel mass used by all the CMS engines.} \\
T_{\text{ON}} & \quad \text{Total on-time for all CMS engines.} \\
[A_{ME}] & \quad \text{Attitude matrix to go from the engine (E) frame to the actuator (A) frame.}
\end{align*}
\]

FIGURE 4.7-61. (CONTINUED)
Attitude matrix to go from the engine (E) frame to the vehicle (V) body frame.

$T_E$ Thrust vector for all the OMS engines.

$Q_i$ Force vector of the $i$th OMS engine.

$N_i$ Torque vector of the $i$th OMS engine.

$R_{vX}$ Position of the vehicle's center of mass (X) in the vehicle (V) body frame.

$Q$ Total force vector.

$N$ Total torque vector.

$NE$ Number of gimbalable engines.

FIGURE 4.7-61. (CONTINUED)
OMS Validation Methods and Check Cases

Check case design for OMS Simulation Module verification should consist of closed-loop command sequences to evaluate proper execution sequence and the calculated forces, torques, and mass properties information. A brief check case example is shown in Table 4.7-16 (Ref. 17). In this case, engines 1 and 3 were turned on with their engines in the null position. Both engines were then commanded to their indicated stops. The corresponding forces and moments are given in the figure. Check cases of this type should cover both the static design end-points (as shown) and intermediate values. Dynamic sequences should also be designed for OMS thrust transient effects analyses.

OMS Data Base Impact

Data base impact should be minimal for OMS Simulation Module verification, as the reference module and check cases can be simple in design and construction, thus reducing the overall OMS verification data base requirements.
<table>
<thead>
<tr>
<th>Engine</th>
<th>Engines in Null Position</th>
<th>Axes</th>
<th>Engines 1 &amp; 3 Commanded to Stops</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Forces</td>
<td>Torques</td>
<td>Forces</td>
</tr>
<tr>
<td>1</td>
<td>43244.537</td>
<td>1927.844</td>
<td>X 43620.685</td>
</tr>
<tr>
<td></td>
<td>-4263.431</td>
<td>20443.561</td>
<td>Y -7354.579</td>
</tr>
<tr>
<td></td>
<td>9507.928</td>
<td>398.718</td>
<td>Z 6411.012</td>
</tr>
<tr>
<td>2</td>
<td>0.0</td>
<td>0.0</td>
<td>X 0.0</td>
</tr>
<tr>
<td></td>
<td>0.0</td>
<td>0.0</td>
<td>Y 0.0</td>
</tr>
<tr>
<td></td>
<td>0.0</td>
<td>0.0</td>
<td>Z 0.0</td>
</tr>
<tr>
<td>3</td>
<td>43244.537</td>
<td>-1203.340</td>
<td>X 43620.685</td>
</tr>
<tr>
<td></td>
<td>4263.431</td>
<td>20443.561</td>
<td>Y 7354.579</td>
</tr>
<tr>
<td></td>
<td>9507.928</td>
<td>-3693.951</td>
<td>Z 6411.012</td>
</tr>
<tr>
<td>TOTALS</td>
<td>86489.074</td>
<td>724.504</td>
<td>X 87241.370</td>
</tr>
<tr>
<td></td>
<td>0.0</td>
<td>0.0</td>
<td>Y 0.0</td>
</tr>
<tr>
<td></td>
<td>19015.856</td>
<td>-3295.233</td>
<td>Z 12822.024</td>
</tr>
</tbody>
</table>
4.7.3.4 Solid Rocket Motors (SRM)

SRM System Description

The SRM represents the engine and propellant portion of the Solid Rocket Boosters (SRB's). One SRM and its associated propellant is contained in each SRB. Each SRB contains, in addition to the SRM subsystem, an avionics subsystem, a recovery subsystem, a thrust control (TVC) subsystem, and a structures subsystem.

In general, solid rocket propulsion depends on 1) the grain composition, geometry, and mean temperature at ignition, 2) the combustion chamber conditions, and 3) the nozzle characteristics. The grain geometry of the SRM propellant consists of a truncated cone for the first 75 percent followed by a star in the latter 25 percent. The mean grain temperature at ignition and combustion chamber are limited under normal operation. The nozzle characteristics are fixed by design. Each SRM has the same overall propulsion characteristics; however, minor deviations are expected due to variations in initial mean grain temperature and grain irregularities.

SRM Simulation Module Description and Performance Parameters

The simulation module is based upon the SRM as defined for the SRB's used on the Space shuttle vehicle. The SRM simulation module will utilize tabular data and table lookup techniques to calculate the SRM total thrust, the body axis thrust forces and moments, the propellant mass, and mass flow rate (Ref. 11).

SRM simulation module interfaces are shown in Figure 4.7-63. Table 4.7-17 lists the performance parameters associated with the SRM simulation module. These parameters were established using the criteria developed in Section 4.1.

SRM Reference Data Sources and Data Formats

A reference software module will provide reference data to be used to verify the SRM simulation module. Reference modeling is only to a detail necessary to provide reference data for normal operation of the SRM (i.e., no failure considerations are provided and the model does not provide for thrust termination other than the nominal burning to depletion). By normal operation it is meant that the operating status remains within the operational design specifications.
FIGURE 4.7-63. SRM SIMULATION MODULE INTERFACES
TABLE 4.7-17 SOLID ROCKET MOTOR MODULE PARAMETER LIST

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>DEFINITION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>DT</td>
<td>INTEGRATION TIME STEP</td>
<td>I</td>
</tr>
<tr>
<td>Po</td>
<td>ATMOSPHERIC PRESSURE</td>
<td>I</td>
</tr>
<tr>
<td>δP, δY</td>
<td>δP - PITCH GIMBAL ANGLE, δY - YAW GIMBAL ANGLE</td>
<td>I</td>
</tr>
<tr>
<td>T&lt;sub&gt;G&lt;/sub&gt;</td>
<td>MEAN GRAIN TEMPERATURE AT IGNITION</td>
<td>I</td>
</tr>
<tr>
<td>IFM</td>
<td>INDICATOR FLAG TO SPECIFY TRANSFORMATION OF THRUST INTO BODY-AXIS FORCES AND MOMENTS</td>
<td>I</td>
</tr>
<tr>
<td>i</td>
<td>SRM INDICATOR INDEX (SPECIFIES LEFT OR RIGHT SRM)</td>
<td>I</td>
</tr>
<tr>
<td>M</td>
<td>MASS OF THE GRAIN (USED INTERNALLY AND UPDATED FOR OUTPUT)</td>
<td>P</td>
</tr>
<tr>
<td>P&lt;sub&gt;c&lt;/sub&gt;, T&lt;sub&gt;c&lt;/sub&gt;</td>
<td>P&lt;sub&gt;c&lt;/sub&gt; - COMBUSTION CHAMBER PRESSURE, T&lt;sub&gt;c&lt;/sub&gt; - COMBUSTION CHAMBER TEMPERATURE</td>
<td>CP</td>
</tr>
<tr>
<td>m</td>
<td>MASS FLOW RATE</td>
<td>CP</td>
</tr>
<tr>
<td>TH&lt;sub&gt;v&lt;/sub&gt;</td>
<td>VACUUM THRUST</td>
<td>P</td>
</tr>
<tr>
<td>TH</td>
<td>ALTITUDE THRUST</td>
<td>CP</td>
</tr>
<tr>
<td>AE</td>
<td>EFFECTIVE EXHAUST AREA</td>
<td>DB</td>
</tr>
<tr>
<td>θ&lt;sub&gt;i&lt;/sub&gt;, Ψ&lt;sub&gt;i&lt;/sub&gt;</td>
<td>THE TWO ANGLES THAT DEFINE THE GIMBAL NULL POSITION WRT THE BODY AXES (ONE SET FOR EACH SRB)</td>
<td>DB</td>
</tr>
<tr>
<td>TX, TY, TZ</td>
<td>THRUST FORCES IN THE TIME INVARIANT BODY AXES</td>
<td>CP</td>
</tr>
<tr>
<td>LX, LY, LZ</td>
<td>THRUST MOMENTS IN THE TIME INVARIANT BODY AXES</td>
<td>CP</td>
</tr>
<tr>
<td>XG&lt;sub&gt;i&lt;/sub&gt;, YG&lt;sub&gt;i&lt;/sub&gt;, ZG&lt;sub&gt;i&lt;/sub&gt;</td>
<td>GIMBAL LOCATION IN THE TIME INVARIANT BODY AXES SYSTEM (ONE SET FOR EACH SRB)</td>
<td>DB</td>
</tr>
</tbody>
</table>

<sup>a</sup>

- P - PERFORMANCE PARAMETER
- CP - CRITICAL PERFORMANCE PARAMETER
- I - INPUT
- DB - DATA BASE INPUT
As described in the Figure 4.7-64 math flow, the reference module model consists primarily of the reference performance characteristics tabulated as a function of grain mass remaining (M) and mean grain temperature at ignition (T_G). Specifically, the combustion chamber pressure, the vacuum thrust, and the mass flow rate are stored as functions of M and T_G, and the combustion chamber temperature is stored as a function of M. (Chamber temperature is not characteristically highly dependent on chamber pressure variations or the initial grain temperature; however, if SRM performance data indicates the contrary, then it should be modeled accordingly.) For each time step during simulated burning, the mass flow rate is used to decrement the mass remaining.

Due to standardization, reference propulsion characteristics are the same for both SRM's being simulated, and a single model can represent the propulsion for both (separately). In the reference module, the only difference in the left and right SRM computations are associated changes in relative geometry (i.e., the gimbal location and the gimbal null angles). These changes are handled by the pick-up of the appropriate value through an associated input index (i).

The propulsion parameters are computed by table interpolations and are indicated by the functions f_1, f_2, f_3, and f_4 of Figure 4.7-64. The total altitude thrust is computed by correcting the vacuum thrust for the loss due to atmospheric pressure. If desired, the thrust is then resolved into the time invariant body axis components with the corresponding thrust moments.

The indicated operations for resolving the thrust into the body axis components are presented as two successive transformations. The inner transformation (f_6) represents the resolution of the total thrust (assumed to be along a single line of action represented by the first component of a triad axis system) into thrust along the gimbal null axes (representing a zero deflection of gimbal actuators). The outer transformation (f_5) represents the transformation of these null axis thrust components into thrust components along the time invariant body axes. The two functions, f_5 and f_6, are dependent on the appropriate coordinate system definitions as well as baseline vehicle characteristics.

The moment computations indicated are the standard moment equations in terms
- INTEGRATION
  TIME STEP (DT)
- ATMOSPHERIC
  PRESSURE (Po)
- GIMBAL PITCH
  AND YAW
  ANGLES (\(\theta_p, \psi_y\))
- INITIAL MEAN
  GRAIN TEMPERATURE
  (Tg)
- GRAIN MASS
  (M)
- SRM INDICATOR
  INDEX (i)
- INDICATOR FLAG
  FOR TRANSFORMATION
  OF THRUST
  INTO FORCES &
  MOMENTS (IFM)

CHECK POINT
INPUT

DATA BASE
INPUT

PROPELLION PARAMETERS
(TABLE. INTERPOLATIONS)

- \(PC = f_1 (M, Tg)\)
- \(TC = f_2 (M)\)
- \(M = f_3 (M, Tg)\)
- \(THV = f_4 (M, Tg)\)
- \(TH = THV - AE P_0\)

1
zero
IMIT
non zero

TRANSFORM TO THRUST FORCES AND
MOMENTS IN THE TIME INVARIANT
BODY AXES

\[
\begin{bmatrix}
TX \\
TY \\
TZ
\end{bmatrix}
= \begin{bmatrix}
TXG \\
TYG \\
TZG
\end{bmatrix}
\begin{bmatrix}
GIMBAL NULL AXES THRUST \ Components \\
GIMBAL NULL AXES MOMENTS
\end{bmatrix}
\begin{bmatrix}
TXG \\
TYG \\
TZG
\end{bmatrix}
\begin{bmatrix}
GIMBAL NULL AXES THRUST \ Components
\end{bmatrix}
\begin{bmatrix}
GIMBAL NULL AXES MOMENTS
\end{bmatrix}
\begin{bmatrix}
TH
\end{bmatrix}
\]

\[
\begin{align*}
LX &= YG \cdot TZ - ZG \cdot TY \\
LY &= ZG \cdot TX - XG \cdot TZ \\
LZ &= XG \cdot TY - YG \cdot TX
\end{align*}
\]

FIGURE 4.7-64 SRM REFERENCE MODULE MATH FLOW

4.7-177

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ M = M - \dot{M} \times DT \]

- BODY AXIS THRUST FORCES AND MOMENTS (TX, TY, TZ)(LX, LY, LZ)
- TOTAL THRUST (TH)
- VACUUM THRUST (THv)
- COMBUSTION CHAMBER PARAMETERS (Pc, Tc)
- MASS FLOW PARAMETERS (\dot{M}, \dot{H})

RETURN
of the forces (TX, TY, TZ) and the moment arms (XG, YG, ZG) with the appropriate
sign convention consistent with a right hand coordinate system definition. Per-
formance parameters are then output and a mass update is performed. Additional
outputs are also made as necessary for simulation module verification.

SRM Validation Methods and Check Cases

Validation methods used to verify the simulation module utilize the data
generated with the reference module for comparison purposes. That is, the refer-
ence module and simulation module would both be accessed by a driver routine
supplying check point data and the resulting performance parameters would be output
and stored for post-processing applicable to the verification task.

One check point should be established to reproduce the reference sea level
propulsion characteristics (i.e., M should be initialized to a reference value, T_G
should be assigned a reference temperature (e.g., 60°F), P_o should be sea level
atmospheric pressure, and DT as appropriate for the mass integration). (NOTE: that
when generating propulsion characteristics for the complete SRM action time, the
sequential check points use the mass (M) as updated in the previous check point.)

Additional check points should reproduce the propulsion characteristics for
non-reference initial mean grain temperatures (i.e., T_G ≠ 60°F, but within the
operational range of 40°F to 90°F).

The remaining check points should exercise the modules through the full range
of nominal use. These check points can be generated with off-line digital analysis
programs and can be representative of realistic states along typical trajectories
(including the gimbal deflections providing realistic TVC). These cases are
required to provide verification data for the altitude dependency of the thrust
and the calculations necessary to compute the thrust related forces and moments.

The actual verification can be made by direct comparison of output (plots and
single case situations) and by the use of the plotting techniques discussed in
Section 5.3.

In addition to the check point capability, the reference module is structured
so as to be easily driven by data generated in previous simulation runs. This provides the capability to verify the simulation for particular situations suspected of inaccuracies.

**SRM Data Base Impact**

The reference module and the associated verification technique as presented require certain data to be available for the reference module data base. The data base requirements are presented with an indication of the likely source in Table 4.7-13.

It should be noted that the tabular data represents the expected performance characteristics and not the design requirement characteristics. However, the design requirements may be used prior to availability of the SRM reference characteristics. In addition, some form of configuration control protection should be employed with respect to data base items for the reference module, since it is anticipated that changes will occur as the program progresses.
# TABLE 4.7-18 SRM REFERENCE MODULE DATA BASE REQUIREMENTS

<table>
<thead>
<tr>
<th>ITEM DESCRIPTION</th>
<th>SOURCE</th>
</tr>
</thead>
<tbody>
<tr>
<td>PROPULSION CHARACTERISTICS ((\rho_c, T_c, \dot{M}, THV)) AS APPROPRIATE FOR REDUCTION TO TABULAR FORM</td>
<td>SRM SUBSYSTEM CONTRACTOR</td>
</tr>
<tr>
<td>GIMBAL LOCATION ((XG_i, YG_i, ZG_i)) IN BODY AXES</td>
<td>VEHICLE CONTRACTOR</td>
</tr>
<tr>
<td>ANGLES DEFINING GIMBAL NULL AXES WRT THE BODY AXES ((\theta_i, \psi_i))</td>
<td>VEHICLE CONTRACTOR</td>
</tr>
<tr>
<td>EFFECTIVE EXHAUST AREA ((A_E))</td>
<td>VEHICLE CONTRACTOR</td>
</tr>
</tbody>
</table>
4.7.4 Power Generation Subsystems

This section discusses the Electrical Power Generation and Auxiliary Power Generation.

4.7.4.1 Electrical Power Generation

The Electrical Power Generation (EPG) portion of the Electrical Power System includes three H2/O2 fuel cells with associated water cooling loops; and the Power Reactant Storage and Distribution subsystem (PRSD). (The battery subsystem has been deleted.) The distribution and control of electrical power is accomplished by the Avionics Subsystem.

EPG System Description

Each of the three fuel cells contains subsystems which provide the following functions:

- Heating and pressure regulation of the H2 and O2.
- Coolant circulation and control for proper temperature control.
- H2/O2 circulation to remove product water from the fuel cell.

Reference 20 provided Figure 4.7-65, a schematic of the fuel cell interfaces with other systems. Figure 4.7-66 (also from Reference 20) illustrates the fuel cell internal operations and functions, which are discussed below.

Fuel Cell

The H2 and O2 from the PRSD are passed through pre-heaters (heat exchangers) which warm the gases prior to flow through coupled pressure regulators which maintain the proper operational gas pressures for purges and normal fuel power generation.

The fuel cell coolant loop circulates a cooling fluid through the fuel cell. This fluid transfers heat from the fuel cell to the active Thermal Control System. The system includes coolant pump, flow control valve, condenser (heat exchanger), startup heaters, fuel cell coldplates, O2/H2 pre-heaters (heat exchangers), and coolant accumulator.

The H2/O2 circulation is accomplished by a combination pump/H2O separator. The flow is through the fuel cell, condenser, and the water separator. The fuel
FIGURE 4.7-55 ELECTRICAL POWER GENERATION (EPG) DESCRIPTION
FCP SUBSYSTEM SCHEMATIC

*ADDITIONAL MEASUREMENTS SHOWN ON FCP SCHEMATIC
FIGURE 4.7-66, EPG DESCRIPTION, FUEL CELL POWER PLANT SCHEMATIC
cell product water is output to the ECLSS for storage and use.

**PRSD**

The Power Reactant Storage and Distribution (PRSD) subsystem comprises cryogenic storage tanks, control valves and distribution manifold. The Shuttle subsystem has two tank assemblies for O₂ and two tank assemblies for the H₂. However, provisions of the manifolds allow the addition of cryogenic O₂ and H₂ tank assemblies in the payload bay. Each tank assembly has two heaters, burst diaphragm and relief valve. The subsystem schematic from Reference 20 is shown in Figure 4.7-67.

**EPG Module Description and Performance Parameters**

The EPG module functions are to provide the calculations related to the fuel cell operations and the PRSD performance. Figure 4.7-68 is an illustration of the EPG module functional elements and their interfaces with other modules. The functions of each functional element are discussed in the following paragraphs. The module performance parameters for the fuel cell and PRSD are identified in Tables 4.7-19 and 4.7-20.

**Fuel Cell Pressure Control** - The following calculations are provided by this element:

- Electrode pressure - a function of temperature, gas quantity, gas volume.
- Gas Usage rates - a function of electrical load, inlet pressure, electrode pressure, temperature, purge mode selection, and electrode differential pressures.
- Electrode Gas Quantities - functions of regulator flow characteristics and gas usage rates.
- H₂O quantity - function of electrical load and electrode pressures.

**Fuel Cell Coolant Loop** - This element makes the following calculations:

- Pump flow rate - a function of loop configuration selection, fluid temperature, input voltage.
- Pump outlet temperature - a function of inlet temperature, flow rate, input electrical power, and output hydraulic power.
FIGURE 4.7-67 POWER REACTANT STORAGE AND DISTRIBUTION (PRSD) SUBSYSTEM SCHEMATIC
FIGURE 4.7-8. ELECTRICAL POWER GENERATION MODULE ELEMENTS AND INTERFACE WITH OTHER MODULES.
### TABLE 4.7-19  EPS FUEL CELL PARAMETERS (TYP 3)

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>H2 Regulator Pressure</td>
<td>0</td>
<td>+100 PSIA</td>
</tr>
<tr>
<td>Voltage</td>
<td>0</td>
<td>+40 VDC</td>
</tr>
<tr>
<td>Current</td>
<td>0</td>
<td>+500 AMP DC</td>
</tr>
<tr>
<td>Cell Current Low</td>
<td>LOW</td>
<td>EVENT</td>
</tr>
<tr>
<td>Ready</td>
<td>OFF</td>
<td>ON EVENT</td>
</tr>
<tr>
<td>Start Up Heater</td>
<td>OFF</td>
<td>ON EVENT</td>
</tr>
<tr>
<td>Startup Heater - OFF</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>Stack Cool Out Temperature</td>
<td>-50</td>
<td>+300 DEG F</td>
</tr>
<tr>
<td>Condenser Exit Temperature</td>
<td>0</td>
<td>+250 DEG F</td>
</tr>
<tr>
<td>O2 Flow</td>
<td>0</td>
<td>25 LB/HR</td>
</tr>
<tr>
<td>O2 Regulator Pressure</td>
<td>0</td>
<td>+100 PSIA</td>
</tr>
<tr>
<td>H2 Flow</td>
<td>0</td>
<td>4.5 LB/HR</td>
</tr>
<tr>
<td>O2 Purge Valve Automatic</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>H20 Condition</td>
<td>ON</td>
<td>OFF EVENT</td>
</tr>
<tr>
<td>H20 Outlet Valve Position</td>
<td>OPEN</td>
<td>CLOSE EVENT</td>
</tr>
<tr>
<td>Product H20 Line Temperature</td>
<td>0</td>
<td>+200 DEG F</td>
</tr>
<tr>
<td>H20 Line Heater Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>H20 Line Heater ON</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>O2 Pressure Over H20</td>
<td>0</td>
<td>+10 PSID</td>
</tr>
<tr>
<td>H2 Purge Valve OPEN</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>H2 Purge Valve - Automatic</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>O2 Purge Valve OPEN</td>
<td>ON</td>
<td>EVENT</td>
</tr>
</tbody>
</table>

<sup>a</sup> P - Performance Parameter  
CP - Critical Performance Parameter  
I - Input
### TABLE 4.7-20  EPS POWER REACTANT STORAGE AND DISTRIBUTION PARAMETERS (COMMON 3 FUEL CELLS)

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>H2 Circulation Isolation Valve 1A OPEN</td>
<td>CLOSE OPEN EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Isolation Valve 1B OPEN</td>
<td>CLOSE OPEN EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Pump 1A ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Pump 1B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Pump 1A Automatic</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Pump 1B Automatic</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Line Heater No. 1A-Active</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Circulation Line Heater No. 1B-Active</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Manifold 1 Pressure</td>
<td>0 +400 PSIA</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Manifold 1 Isolation Valve Closed</td>
<td>OPEN CLOSE EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Manifold 2 Pressure</td>
<td>0 +400 PSIA</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Manifold 2 Isolation Valve Closed</td>
<td>OPEN CLOSE EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 FCP 1 Supply Valve Closed</td>
<td>OPEN CLOSE EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 FCP 2 Supply Valve Closed</td>
<td>OPEN CLOSE EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 FCP 3 Supply Valve Closed</td>
<td>OPEN CLOSE EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Pressure</td>
<td>0 +400 PSIA</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Quantity</td>
<td>0 100 PCNT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Heater 1A ON</td>
<td>OFF ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Heater 1A Temperature</td>
<td>-425 +200 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Heater 1B ON</td>
<td>OFF ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Heater 1B Temperature</td>
<td>-425 +200 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Purge Vent Temperature</td>
<td>0 +250 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>H2 Relief Vent Heater 1 Active</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Relief Vent Heater 2 Active</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>H2 Relief Vent Heater 3 Active</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>O2 Pressure</td>
<td>0 +1500 PSIA</td>
<td>CP</td>
</tr>
<tr>
<td>O2 Quantity</td>
<td>0 100 PCNT</td>
<td>P</td>
</tr>
</tbody>
</table>
### TABLE 4.7-20 (CONTINUED)

<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>LOW</td>
<td>HIGH</td>
</tr>
<tr>
<td>02 Heater 1A ON</td>
<td>OFF</td>
<td>ON</td>
</tr>
<tr>
<td>02 Heater 1A Temperature</td>
<td>-325</td>
<td>+300</td>
</tr>
<tr>
<td>02 Heater 1B ON</td>
<td>OFF</td>
<td>ON</td>
</tr>
<tr>
<td>02 Heater 1B Temperature</td>
<td>-325</td>
<td>+300</td>
</tr>
<tr>
<td>02 Circulation Isolation Valve 1A OPEN</td>
<td>CLOSE</td>
<td>OPEN</td>
</tr>
<tr>
<td>02 Circulation Isolation Valve 1B OPEN</td>
<td>CLOSE</td>
<td>OPEN</td>
</tr>
<tr>
<td>02 Circulation Pump 1A ON</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Circulation Pump 1A Automatic</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Circulation Pump 1B ON</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Circulation Pump 1B Automatic</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Circulation Line Heater No. 1A-Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Circulation Line Heater No. 1B-Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Manifold 1 Pressure</td>
<td>0</td>
<td>+1500</td>
</tr>
<tr>
<td>02 Manifold 1 Isolation Valve Closed</td>
<td>OPEN</td>
<td>CLOSE</td>
</tr>
<tr>
<td>02 Manifold 2 Pressure</td>
<td>0</td>
<td>+1500</td>
</tr>
<tr>
<td>02 Manifold 2 Isolation Valve Close</td>
<td>OPEN</td>
<td>CLOSE</td>
</tr>
<tr>
<td>FC 1 02 Supply Valve Closed</td>
<td>OPEN</td>
<td>CLOSE</td>
</tr>
<tr>
<td>FC 2 02 Supply Valve Closed</td>
<td>OPEN</td>
<td>CLOSE</td>
</tr>
<tr>
<td>FC 3 02 Supply Valve Closed</td>
<td>OPEN</td>
<td>CLOSE</td>
</tr>
<tr>
<td>H2O Relief Vent Temperature</td>
<td>0</td>
<td>+250</td>
</tr>
<tr>
<td>FC H2O Relief Vent Heater 1 Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>FC H2O Relief Vent Heater 2 Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Purge Vent Temperature</td>
<td>0</td>
<td>+250</td>
</tr>
<tr>
<td>02 Relief Vent Heater 1 Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Relief Vent Heater 2 Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
<tr>
<td>02 Relief Vent Heater 3 Active</td>
<td>ON</td>
<td>EVENT</td>
</tr>
</tbody>
</table>

a P - Performance Parameter
CP - Critical Performance Parameter
I - Input
Coolant flow to ATCS - a function of condenser $\text{H}_2\text{O}/\text{H}_2$ outlet temperature, pump flow rate, startup heater inlet temperature, and condenser fluid outlet temperature.

Fluid temperature to ATCS - a function of pump outlet temperature.

Coolant flow to condenser - a function of coolant flow to ATCS, condenser $\text{H}_2\text{O}/\text{H}_2$ outlet temperature, startup heater inlet temperature, and condenser fluid outlet temperature.

Condenser fluid inlet temperature - a function of condenser fluid flow rate, pump outlet temperature, condenser $\text{H}_2\text{O}/\text{H}_2$ outlet temperature, ATCS fluid flow, and ATCS fluid return temperature.

Condenser fluid outlet temperature - a function of condenser fluid flow, $\text{H}_2\text{O}/\text{H}_2$ flow, $\text{H}_2\text{O}/\text{H}_2$ inlet temperature, and condenser fluid inlet temperature.

Startup heater inlet temperature - a function of stack inlet control valve characteristics, pump fluid outlet temperature, condenser fluid outlet temperature, condenser flow rate, and pump flow rate.

Startup heater temperature - functions of heater electrical power, inlet fluid temperature, and fluid flow rate.

Startup heater outlet temperature - a function of fluid flow, heater temperature, and inlet fluid temperature.

Fuel cell outlet temperature - a function of the fuel cell temperature, pump flow rate, and startup heater outlet temperature.

$\text{O}_2$ Pre-heater fluid outlet temperature - a function of inlet fluid temperature, inlet $\text{O}_2$ temperature, $\text{O}_2$ flow rate, pump flow rate.

$\text{O}_2$ Pre-heater outlet $\text{O}_2$ temperature - a function of inlet $\text{O}_2$ temperature, inlet fluid temperature, and $\text{O}_2$ and fluid flow rates.

$\text{H}_2$ Pre-heater outlet fluid temperature - a function of $\text{O}_2$ pre-heater fluid outlet temperature, $\text{H}_2$ inlet temperature, $\text{H}_2$ flow rate, and fluid flow rate.

$\text{H}_2$ Pre-heater outlet $\text{H}_2$ temperature - a function of $\text{O}_2$ Pre-heater fluid outlet temperature, $\text{H}_2$ inlet temperature, $\text{H}_2$ flow rate, and fluid flow rate.

Fuel cell temperature - a function of electrical load, end plate heater power, $\text{O}_2/\text{H}_2$ flow rates, coolant flow rate, $\text{H}_2/\text{H}_2\text{O}$ flow rate, coolant inlet temperature, and $\text{H}_2/\text{H}_2\text{O}$ inlet temperature.

$\text{H}_2/\text{H}_2\text{O}$ Circulation - This element calculates the following:

- $\text{H}_2/\text{H}_2\text{O}$ pump flow - a function of electrical input voltage, $\text{H}_2/\text{H}_2\text{O}$ temperature, pump flow rate, startup heater temperature, condenser fluid outlet temperature, and $\text{H}_2/\text{H}_2\text{O}$ flow rate.
rpm, and output power.

- Separator H$_2$O flow - a function of separator efficiency and H$_2$O quantity inlet.
- Separator H$_2$O pressure - a function of H$_2$O tank pressure, and H$_2$O flow.
- Separator outlet H$_2$O temperature - a function of inlet H$_2$/H$_2$O temperature, input electrical power, and output hydraulic power.
- H$_2$ pump outlet temperature - a function of the inlet H$_2$/H$_2$O temperature, input electrical power, and output hydraulic power.
- H$_2$ pump outlet pressure - a function of H$_2$ temperature, and pump flow rate.
- Condenser inlet H$_2$/H$_2$O temperature - a function of inlet H$_2$ temperature, inlet H$_2$ flow, H$_2$/H$_2$O pump flow, fuel cell outlet H$_2$/H$_2$O temperature, and H$_2$/H$_2$O pressure.

**Fuel Cell Electrical Output** - This element generates the following:
- Output voltage level - a function of reactant quantities at electrodes, output current, and fuel cell temperature.
- Output current - a function of load impedance, and fuel cell output voltage.

**PRSD** - The calculations performed by this element are:
- Reactant Quantities - functions of ECLSS usage, fuel cell usage, and relief venting.
- Tank temperatures - functions of input heater power, heat leakage, reactant flow rates, and pressures.
- Tank pressures - functions of reactant quantities, temperatures, and volumes.
- Burst diaphragm rupture (discrete) - a function of diaphragm characteristics and pressure.
- Relief flow rate - a function of tank pressure, ambient pressure, reactant temperature, and relief valve characteristics (only after burst diaphragm rupture).
- Manifold temperature - a function of inlet and outlet flow rates, and temperatures.
- Manifold pressure - a function of inlet flow, outlet flow, and manifold temperature.
- Manifold flow rates - functions of inlet pressure, inlet temperature, and outlet pressure.

EPG Reference Data Sources and Data Formats

Several sources of data exist for use for developing reference modules or making direct comparison with simulator results. The system and component design performance requirements, analysis/performance predictions, test results, and flight performance data are a few. Figure 4.7-69 is an overview flow chart of methods of using these sources in a direct comparison with the results of a simulator run. In brief, the method is to establish the design requirement, analysis, etc. as input conditions on the simulation module to be verified. The simulation module is allowed to reach a stabilized response and the resulting data output for manual comparison with the spec requirements, analysis results, etc. This method is discussed in Section 4.2.1.4. The method of section 5.1 can be used with the reference models for verification.

Fuel Cell

The fuel cell requirements are provided by Reference 30. The requirements, analysis and predictions can be determined from Reference 31, design or analysis groups, and MPAD. Many of the test results can be acquired from individual acceptance tests and integrated-systems checkout. Reference 29 discusses a computer program for simulation of the CSM fuel cells for the Skylab mission. The Shuttle fuel cell system is very similar to the one described by this reference; thus, the subject program should be easily converted for Shuttle simulation verification.

PRSD - The basic flow for the PRSD O\textsubscript{2} reference module is shown in Figure 4.7-70. This approach utilizes the basic flow charts shown in Figures 4.7-71 and 4.7-72. The approach for PRSD-H\textsubscript{2} parameters would be identical to the O\textsubscript{2} except for the fluid characteristics. Reference 32 can be used as a source of O\textsubscript{2} characteristics while Reference 33 provides the H\textsubscript{2} characteristics. Reference 31 provides many of the component characteristics of interest.

EPG Validation Methods and Check Cases

The reference module is utilized by the method of Section 5-1, while the systems performance data is used by the technique of Section 4.2 is validating the EPG simulation module. Drivers required to generate and maintain interfacing...

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY, EAST
FIGURE 4.7-69. BASIC EPG VERIFICATION DATA SOURCE FLOW CHART
PERFORM SIMULATOR RUN

OUTPUT SELECTED PERFORMANCE PARAMETERS FOR MANUAL COMPARISON

EXIT

FIGURE 4.7-69. (CONTINUED)
FIGURE 4.7-70. PRSD REFERENCE MODULE OVERALL MATH FLOW

4.7-196

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ \dot{m}_s = m_s \]
\[ \dot{m}_s = \dot{m}_{so} - \left( \dot{m}_{so} + \dot{m}_{se} \right) \Delta t \]
\[ \dot{m}_{se} = \kappa_2 \left( T_{sc} - T_e \right) + 3.41 \text{ W/m}^2 \]
\[ W_{so} = P_s \left( \dot{m}_{so} + \dot{m}_{se} \right) \Delta t \]
\[ T_e = \frac{\dot{m}_{so} - W_{so} + \kappa_2 m_s \dot{T}_s}{c_s m_s} \]
\[ P_s = f_{sa} \left( T_s, V_s, m_s \right) \]

LEGEND
- \( m_s \) = fluid mass in tank
- \( \dot{m}_{so} \) = fluid flow rate in outlet line
- \( \dot{m}_{se} \) = fluid flow rate via relief line
- \( T_s \) = tank fluid temperature
- \( P_s \) = tank fluid pressure
- \( P_{so} \) = fluid density
- \( c_s \) = fluid specific heat
- \( T_{sc} \) = tank compartment temperature
- \( W_{heater} \) = tank electrical heater power
- \( \dot{W}_{heat} \) = heat leak into tank
- \( W_{so} \) = work done by fluid in expansion
- \( \Delta t \) = time increment
- \( V_s \) = tank volume

FIGURE 4.7-71. PRSD SOURCE TANK REFERENCE MODULE MATH FLOW
\[ K_n = \left( \frac{2}{\gamma + 1} \right)^{\frac{1}{\gamma + 1}} \]

**FLUID Flow**

\[ P_o \leq K_n \]

**GAS Flow**

\[ \checkmark \]

**NO**

\[ M = \left\{ \left( \frac{P_o}{P_w} \right)^{\frac{1}{\gamma - 1}} \left( \frac{2}{\gamma - 1} \right) \right\}^{\frac{1}{2}} \]

\[ M = 1 \]

\[ \dot{m} = AN^\frac{3}{2} \left( P_0 - P_r \right) \]

\[ T_o = T_{in} \]

\[ u_0 = \left( \frac{2 \left( P_o - P_r \right)^{\frac{1}{2}}}{\rho} \right) \]

**RETURN**

**LEGEND:**
- \( \dot{m} \) = Mass flow rate
- \( T_o \) = Outlet flow temperature
- \( P_o \) = Outlet pressure
- \( P_r \) = Inlet pressure
- \( T_{in} \) = Inlet temperature
- \( K_n \) = Critical pressure ratio
- \( M \) = Mach number
- \( \gamma \) = Specific heat ratio
- \( A \) = Effective flow area
- \( \rho \) = Density

**FIGURE 4.7-72. MATH FLOW FOR FLUID FLOW CALCULATIONS**

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module input parameters include:

- Atmosphere Revitalization
- Active Thermal Control
- Avionics (Electrical Power distribution)
- H₂O Management
- Control Logic Inputs

The check cases should include minimum, intermediate, and maximum electrical power load requirements, transient power switching loads, and projected mission load profiles.

**EPG Data Base Impact**

The impact of the EPG validation on the simulator data base is in four forms. These forms are the reference module, required drivers, processing subroutines, and data files. The most significant impact is the reference module. The reference module includes the fuel cell and the power reactants systems. The drivers would have the next most significant impact. The drivers would be required for both the reference module method and the systems performance data method.

The processing subroutines would include the data output routines (tables, plots, etc.) and any comparisons or data manipulations. The output routines would be required for the reference module and the systems performance data methods. Most processing routines would be common to all modules validated, however.

Data files are required for the power load profiles, O₂/H₂ cryogenic tables, and output data tables.

**4.7.4.2 Auxiliary Power Generation (APG)**

The APG consists of three Auxiliary Power Units (APU's) which provide power to the hydraulic pumps in the three hydraulic power systems. The three APU's are identical with each driving only one hydraulic system. APU's are identical with each driving only one hydraulic system.

**APG System Description**

Figure 4.7-73 (taken from Reference 20) is a schematic of the APU used for the Shuttle Orbiter. The fuel (N₂H₄) is expelled from the fuel tank by a fixed quantity of nitrogen used as a pressurant. A turbine-driven fuel pump feeds the
FIGURE 4.7-73 APU SUBSYSTEM OPERATIONAL MEASUREMENTS (TYP-4)
fuel through control valves into the gas generator. The gas generator is a heated catalytic bed which causes decomposition of the fuel into a hot gas. The hot, high pressure gas is then used to drive the turbine and exhausted overboard. A gearbox provides torque and angular velocity transformation to drive the fuel pump, AC generator (if any), oil pump and hydraulic fluid pump. The oil pump circulates the gearbox lubricant through the gearbox and the water boiler for cooling. The lubricant in the gearbox is pressurized by a tank of GN₂ via a pressure regulator. An electronic APU controller provides fuel flow modulation to allow startup, shutdown, and maintain normal turbine run speed.

APG Module Description and Performance Parameters

Figure 4.7-74 is a schematic showing the APG module functional elements and their interfaces with other modules. Table 4.7-21 is a listing of the APU parameters. The functions performed by each element are discussed below:

Fuel Source
- N₂ pressure - function of temperature, Helium quantity, and N₂H₄ quantity remaining.
- Tank (fuel) temperature - function of heater power, input, and N₂H₄ usage.
- N₂H₄ quantity - function of initial quantity and fuel usage rate.

Fuel Pump
- Pump flow rate - function of turbine speed and fuel density.
- Pump bypass rate - function of fuel delivered to the gas generator, pump flow rate, and control mode.
- Fuel source flow rate - function of fuel delivered to the gas generator and control mode.
- Fuel pump torque - function of friction, speed, flow, differential pressure, and moment of inertia.

Gas Generator
- Pressure - function of temperature, fuel inlet flow, gas flow out, and gas quantity.
- Temperature - function of fuel decomposition rate, heater power, exhaust temperature, and turbine flow rate.
- Gas quantity - function of turbine flow, fuel inlet rates, and decomposition rate.
FIGURE 4.7-74. APU REFERENCE MODULE FUNCTIONAL ELEMENTS AND INTERFACES WITH OTHER MODULES
<table>
<thead>
<tr>
<th>PARAMETER NOMENCLATURE</th>
<th>DATA RANGE</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>Shutdown inhibit command</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Propellant tank pressure</td>
<td>0 600 PSIA</td>
<td>CP</td>
</tr>
<tr>
<td>Propellant tank temperature</td>
<td>0 +160 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>Tank heater-element A-B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Discharge line temperature</td>
<td>0 +160 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>Line heater-element A-B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Fuel pump discharge temperature</td>
<td>0 250 DEG F</td>
<td>P</td>
</tr>
<tr>
<td>Package heater-element A-B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Fuel isolation valve-open command</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Fuel isolation valve position</td>
<td>Open CLD EVENT</td>
<td>CP</td>
</tr>
<tr>
<td>Lube oil heater-element A-B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Thermal bed heater A ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Thermal bed heater B ON</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Gas generator bed temperature</td>
<td>0 2500 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>Controller power-on command</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Status light - ready</td>
<td>OFF ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Start command</td>
<td>ON EVENT</td>
<td>P</td>
</tr>
<tr>
<td>Turbine speed</td>
<td>0 100K RPM</td>
<td>CP</td>
</tr>
<tr>
<td>Gearbox lube oil temperature</td>
<td>0 400 DEG F</td>
<td>CP</td>
</tr>
<tr>
<td>Gearbox lube oil pressure</td>
<td>0 +100 PSIA</td>
<td>P</td>
</tr>
<tr>
<td>Gearbox bearing temperature no. 1</td>
<td>0 500 DEG F</td>
<td>CP</td>
</tr>
</tbody>
</table>

a P - Performance Parameter  
CP - Critical Performance Parameter  
I - Input
Turbine
- Turbine speed - function of turbine torque, gear box lubricant temperature, hydraulic pump load, system friction, system moments of inertia, fuel pump rate, and AC generator output power.
- Turbine input power - function of turbine polytropic efficiency, gas inlet temperature, gas inlet pressure, and gas outlet pressure.
- Discharge temperature - function of inlet temperature, turbine power.
- Turbine fuel flow - function of inlet pressure, temperature, outlet pressure, and effective turbine flow area.

Gearbox
- Oil pump pressure - function of pump speed, oil temperature, and line resistance.
- Oil pump flow rate - function of pump speed.
- Oil pump torque load - function of oil temperature, flow rate, and line resistance.
- Oil temperature - function of oil pump flow, return oil temperature, oil quantity.
- Rate heat input - a function of friction and rotation (rpm).

APU Control
- Valve control(s) - function of input commands, turbine speed, temperatures.

APG Reference Data Sources and Data Formats
The APG module can be verified by use of reference module(s) or system performance data. The reference module(s) should have incorporated the most accurate systems performance data in order to achieve a high degree of fidelity. The systems performance data would include design requirements, analysis results, test results, and vehicle flight data.

Figure 4.7-75 is a flow chart utilizing the reference data sources for verification. The sources of the systems performance data include:
- MC201-0001 (Reference 34.) - provides system and component design perfor-
FIGURE 4.7-75. FLOW CHART FOR APU VERIFICATION

4.7-205

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-75. (CONTINUED)
mance requirements.

- JSC-08934, Vol. I (Reference 31) - provides a compilation of design requirements, analysis results, test results, and performance predictions for various Shuttle systems.
- SAPUCM (Reference ---) - the Simplified Auxiliary Power Unit Consumables Model allows the conduct of full consumable analysis for comparison with the simulation module.

A reference module for the APU is shown in Figure 4.7-76.

APG Validation Methods and Check Cases

The method of Section 5.1 and the selected reference module on the technique presented in Section 4.2.1.4 with the system performance data can be used for verification of the APG module. When utilizing the reference module, the following interface module drivers are required:

- Hydraulic power - system functions, power load, and lubricating oil (Gearbox) cooling
- Electrical power bus voltages
- Control logic inputs

Check cases should include startup, shutdown, steady-state maximum hydraulic load, steady state minimum hydraulic load, mission hydraulic load profiles, and hydraulic load switching.

APG Data Base Impact

The impacts on the simulator data base are associated with the reference module, special drivers and check case data files. The selected APG reference module will have a large impact. The development of Figure 4.7-76 into a reference module (or the use of some detailed model) will be the bulk of the impact.

Special drivers will also be required for the simulation module and reference modules. These drivers would include the hydraulic power subsystem, electrical power system, and control logic inputs. The hydraulic power subsystem driver would provide hydraulic pump loads and cooling for the gearbox lubricating oil. The electrical power driver provides appropriate bus voltage levels for the heaters, control logic, and valve actuation. Switch positions, command inputs, and automatic inputs are provided by the control logic input driver.
(a) overview

FIGURE 4.7-76. APU REFERENCE MODULE MATH FLOW.
FIGURE 4.7-00. (CONTINUED)

4.7-00^ 76. (CONTINUED)

(b) detailed math
\[ v_{PF} = \frac{\Delta m_{PF}}{\Delta t} \]
\[ \mu = F(t) \]
\[ P_{E1} = \frac{\Delta m_{DEF}}{\Delta t} v_{E1} \]
\[ \beta = \frac{\Delta m_{LF1}}{\Delta t} v_{LF1} \]
\[ \Delta t = \frac{P_F - P_0 - \frac{P_F (v_{E1} - v_{RF})^2}{2} - \frac{\Delta m_{LF1} v_{E1}^2}{2}}{M_{LF1}} \]
\[ P_{F-01} = P_F + \frac{1}{2} \rho F v_{E1}^2 + \frac{\Delta m_{LF1} v_{E1}^2}{2} \]
\[ M_{LF} = M_{LF1} \]
\[ H_{FL} = (P_{F-01} - P_F) \nu_{RF} A_{E1} \]
\[ \Delta P_F = P_{F-01} - P_F \]

**Figure 4.7-76. (Continued)**

4.7-210

**McDonnell Douglas Astronautics Company - East**
\[ \nu_{\text{FL}} = \nu_{\text{F1}} \]
\[ \dot{m}_{\text{ST}} = 0 \]
\[ \nu_{\text{F1}} = \frac{\dot{m}_{\text{PF}}}{P_F A_{\text{F1}}} \]
\[ \mu_{\text{F1}} = F(T_F) \]
\[ \rho_{\text{F1}} = \frac{P_F D_{\text{F1}}}{A_{\text{F1}}} \]
\[ \rho_{\text{FL}} = F_F \left( \frac{\nu_{\text{F2}}}{D_{\text{F2}}} \right) \]
\[ \Delta P_{\text{F}} = \frac{M_{\text{FL}}}{A_{\text{F1}}} \left( \frac{\nu_{\text{F2}} - \nu_{\text{F1}}}{\Delta \nu} \right) + \frac{P_{\text{F2}}}{D_{\text{F2}}} \rho_{\text{F2}} \nu_{\text{F2}}^2 \]
\[ P_{\text{F0}} = \Delta P_{\text{F}} + P_F \]
\[ \dot{\nu}_{\text{FL}} = \frac{\dot{m}_{\text{PF}}}{P_F A_{\text{F1}}} \]
\[ \dot{m}_{\text{F-OUT}} = 0 \]
\[ \dot{\nu}_{\text{F-OUT}} = \frac{\dot{m}_{\text{PF}}}{P_F A_{\text{F1}}} \]
\[ \rho_{\text{F-OUT}} = \frac{P_F D_{\text{F1}}}{A_{\text{F1}}} \]
\[ \nu_{\text{FL}} = M_{\text{FL}} \]
\[ \dot{m}_{\text{F-OUT}} = 0 \]
\[ \nu_{\text{F-OUT}} = \frac{\dot{m}_{\text{PF}}}{P_F A_{\text{F1}}} \]
\[ \rho_{\text{F-OUT}} = \frac{P_F D_{\text{F1}}}{A_{\text{F1}}} \]

**FIGURE 4.7-76. (CONTINUED)**

4.7-211

**MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST**
\[ J_F = J_{FP} + \eta_{PF} k_{PF} M_{LF} \]
\[ J_F = \dot{J}_{FP} + \dot{J}_{LF} \]
\[ \dot{m}_{F1} = u_{F1} \rho_0 A_{E1} \]

\[ m_{P0} = \rho_0 k_{P0} \eta_{P0} w_0 \]
\[ T_{P0} = T_{0} + \frac{\dot{J}_{FP} w_0}{c_0 k_{P0} \eta_{P0}} \]
\[ v_{E1} = u_0 \]
\[ K_{al} = \frac{\rho_0 c_0}{T_0} \]
\[ \mu_0 = F(T_{G0}) \]
\[ \dot{v}_0 = \frac{\dot{m}_{P0}}{\rho_0} \]
\[ \dot{P}_{co} = \rho_0 \frac{\dot{v}_0}{\rho_0} \]
\[ \dot{F}_{co} = F(T_{co}, \frac{\dot{v}_0}{\rho_0}) \]
\[ \Delta P_0 = \frac{M_{al}}{A_{al}} \left( \frac{v_{E1} - v_{co}}{v_{E1} - v_{co}} \right) - \frac{\rho_0 c_0}{T_{G0}} \ln \frac{v_{E1}}{v_{co}} v_0^2 + \frac{1}{2} \rho_0 v_0^2 \]
\[ P_{in, out} = \Delta P_0 + \frac{\dot{m}_{P0}}{\rho_0} \]

\[ \dot{J}_0 = J_{FP} + K_{al} \dot{F}_{co} (k_{P0} \eta_{P0})^3 \left( \frac{v_{E1}}{A_{E0}} \right)^2 \]
\[ T_{al, out} = T_{E0} + \frac{K_{al} \dot{F}_{co} v_0^2}{c_0 \rho_0} \]
\[ H_{al} = \frac{1}{2} \rho_0 v_0^2 A_0 \]
\[ \dot{Q}_{GB, in} = \frac{f_{os} w_r^2}{2} + \frac{1}{2} m_{P0} v_0^2 \]
\[ \dot{Q}_{GB, out} = c_0 m_{P0} (T_{G0} - T_{al, out}) - C_{VWZ} v_0^2 (T_{G0} - T_{SN2}) \]
\[ T_{GB} = \frac{\dot{Q}_{GB, in} - \dot{Q}_{GB, out}}{c_0 m_{P0} + C_{VWZ} M_{SN2B} + L_{SN2}} + T_{G0} \]

**FIGURE 4.7-76. (CONTINUED)**

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\[ m_{SN2} = m_{SN2} - \dot{m}_{ORN2} \Delta t \]
\[ Q_{SN2} = k_2 (T_{SN2} - T_{CSN2}) \]
\[ \dot{Q}_{SN2-in} = k_1 (P_{SN2}) \]
\[ T_{SN2} = \frac{[\dot{Q}_{SN2-in} - \dot{Q}_{SN2-out} - P_{SN2} (m_{ORN2})] \Delta t}{C_{SN2} m_{SN2}} + T_{SN2} \]
\[ P_{SN2} = \frac{m_{SN2}}{V_{SN2}} R \Delta T_{SN2} \]
\[ \dot{m}_{ORN2} = F(P_{SN2}, P_{SN}, T_{SN2}) \]
\[ m_{ORN2} = m_{ORN2} + \dot{m}_{ORN2} (\Delta t) \]
\[ P_{SN} = \frac{m_{SN2}}{V_{ORN2}} R \Delta T_{SN} \]

\[ m_6 = \dot{m}_f \Delta t - \dot{m}_g \Delta t + m_6 \]
\[ \dot{Q}_w = 3.41 P_{TNE}_6 + 5 \dot{m}_f + \frac{1}{2} \dot{m}_f v_1^2 \]
\[ \dot{Q}_e = k (T_e - T_6) + C_{ve} \dot{m}_e T_6 \]
\[ T_6 = \frac{\dot{Q}_w \Delta t - \dot{Q}_e \Delta t}{C_{ve} \dot{m}_e + C_6 m_6} \]
\[ P_6 = \frac{m_6}{V_6} R_6 T_6 \]

**FIGURE 4.7-76. (CONTINUED)**
\( M = \left\{ \left[ \left( \frac{P_0}{P_0} \right)^{\frac{1}{m_0}} - 1 \right] \left( \frac{2}{m_0} \right) \right\} V_a \)

\( \dot{M}_{GT} = \frac{M A T P_0 \sqrt{V_a}}{\sqrt{R_a T_0}} \left( 1 + \frac{1}{(m_0 - 1) \gamma^2} \right)^{1/2} \)

\( H_T = \eta_T C_{p, T_{bg}} \left[ 1 - \left( \frac{P_0}{P} \right)^{\frac{1}{m_0}} \right] \dot{M}_{GT} \)

\( \frac{T_0}{T} = \frac{T_0}{T_{bg}} - \frac{H_T}{C_{p, T_{bg}}} \)

\( J_S = J_T + N_T^2 J_F + N_0^2 J_0 + N_H^2 J_H + J_{bg} \)

\( f_S = f_T + f_{bg} + N_T^2 f_F + N_0^2 f_0 + N_H^2 f_H \)

\( H_L = H_{FL} + H_{HL} + H_{0L} \)

\( \omega_{T_{bg}} = \omega_T \)

\( \omega_T = \left[ \left( \frac{H_T - H_L}{J_S} \right) + (\omega_T^2 - \frac{H_T - H_L}{J_S}) e^{-\frac{2f_{bg} t}{J_S}} \right] V_a \)

\( \omega_F = N_F \omega_T \)

\( \omega_H = N_H \omega_T \)

\( \omega_0 = N_0 \omega_T \)

**RETURN**

**FIGURE 4.7-76. (CONTINUED)**

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LEGEND:

- \( m_{GB} \) - Gear Box mass
- \( m_{SG} \) - Mass of Gas Generator
- \( m_{FA} \) - Fuel mass available
- \( m_{FR} \) - Residual fuel mass
- \( m_{TP} \) - Fuel tank \( N_2 \) mass
- \( m_{GKB} \) - \( N_2 \) mass in Gear Box pressure bellows
- \( m_{LR} \) - Gear Box - \( N_2 \) source tank \( N_2 \) mass
- \( m_{G} \) - Gas mass in Gas Generator
- \( m_{NP1} \) - Mass of fuel in fuel line 1 (Run)
- \( m_{NP2} \) - Mass of fuel in fuel line 2 (Bypass)
- \( m_{LP} \) - Mass of fuel in fuel pump line
- \( m_{LPD} \) - Mass of lubricant in oil base
- \( M \) - Mach number of turbine flow
- \( V_{NP} \) - Volume of \( N_2 \) in fuel tank
- \( V_T \) - Fuel tank volume
- \( V_{NP2} \) - Gear Box \( N_2 \) source tank volume
- \( V_{NKB} \) - Gear Box \( N_2 \) bellows volume
- \( V_G \) - Gas volume of Gas Generator

- \( T_F \) - Fuel tank and fuel temperature
- \( T_{EP} \) - Fuel tank compartment temperature
- \( T_{FP IN} \) - Fuel pump inlet fuel temperature
- \( T_{FP OUT} \) - Fuel pump outlet temperature
- \( T_{LI} \) - Gas Generator inlet fuel temperature
- \( T_{LO} \) - Lubricant pump outlet temperature
- \( T_{GB} \) - Gear Box lubricant temperature
- \( T_{GRO} \) - Gear Box lubricant return temperature
- \( T_{GB} \) - Lubricant temperature out of Hydraulic Boiler
- \( T_{N2} \) - Gear Box \( N_2 \) source tank temperature
- \( T_{G2} \) - Gear Box \( N_2 \) tank compartment temperature
- \( T_G \) - Gas Generator temperature
- \( T_C \) - Gas Generator compartment temperature
- \( T_T \) - Turbine outlet gas temperature

- \( \sigma \) - Fuel heat of formation

FIGURE 4.7-76. (CONTINUED)
\( \dot{m}_{F,\text{in}} \) - Mass flow rate of fuel from fuel tank

\( \dot{m}_{PF} \) - Fuel pump mass flow rate

\( \dot{m}_{St} \) - Fuel flow rate through startup line

\( \dot{m}_{F,B} \) - Bypass line fuel flow rate

\( \dot{m}_{Fo} \) - Lubricant pump mass flow rate

\( \dot{m}_{N2} \) - \( \text{N}_2 \) flow rate to Gear Box pressure bellows

\( \dot{m}_{GT} \) - Gas flow rate through turbine

\( \rho_F \) - Fuel density

\( \rho_o \) - Lubricant density

\( \Delta t \) - Time increment

\( c_F \) - Specific heat of fuel

\( (c_V)_{N2} \) - Specific heat at constant volume of \( \text{N}_2 \)

\( c_o \) - Specific heat of lubricant

\( c_{GB} \) - Specific heat of Gear Box

\( c_{VG} \) - Specific heat of fuel gases at constant volume

\( c_G \) - Specific heat of gas generator

\( c_{FG} \) - Specific heat of fuel gases at constant pressure

\( \gamma \) - Fuel gases specific heat ratio

\( R_{N2} \) - \( \text{N}_2 \) gas constant

\( R_G \) - Fuel gas constant

\( \eta_{PF} \) - Fuel pump volume displacement per cycle

\( \eta_{Po} \) - Lubricant pump volume displacement per cycle

\( \eta_{PF} \) - Fuel pump efficiency factor

\( \eta_{Po} \) - Lubricant pump efficiency factor

\( \omega_F \) - Fuel pump angular velocity

\( \omega_H \) - Hydraulic pump angular velocity

\( \omega_o \) - Lubrication pump angular velocity

\( \omega_T \) - Turbine angular velocity

\( N_F \) - Gear ratio of fuel pump to turbine

\( N_o \) - Gear ratio of oil pump to turbine

\( N_H \) - Gear ratio of hydraulic pump to turbine

FIGURE 4.7-76. (CONTINUED)
\[ f_s \] - System friction at turbine
\[ f_{oF} \] - Oil line friction factor
\[ f_{FPL} \] - Fuel delivery line friction factor
\[ f_{FBL} \] - Fuel bypass line friction factor
\[ f_{FDP} \] - Fuel friction due to line related to pump shaft
\[ f_{LOP} \] - Friction losses of oil pump
\[ f_{FPP} \] - Friction losses of fuel pump
\[ f_{HP} \] - Friction losses of hydraulic pump
\[ f_r \] - Oil pump and line friction losses
\[ f_f \] - Fuel pump and line friction losses
\[ J_{PP} \] - Fuel pump moment of inertia
\[ J_{OP} \] - Oil pump moment of inertia
\[ J_{HP} \] - Hydraulic pump moment of inertia
\[ J_r \] - Summation of pump and fuel inertias
\[ J_o \] - Summation of pump and oil inertia
\[ J_s \] - System moment of inertia at turbine
\[ J_{GB} \] - Gear Box moment of inertia at turbine
\[ H_{OL} \] - Oil pump hydraulic power load
\[ H_{FL} \] - Fuel pump hydraulic power load
\[ H_{HP} \] - Hydraulic pump hydraulic power load
\[ H_t \] - Turbine power
\[ H_c \] - Hydraulic power load for turbine
\[ \eta_t \] - Turbine efficiency
The use of analysis/test/design requirements reference data requires the use of special drivers. These drivers establish and maintain proper conditions in the module which correspond to the analysis/test/design requirements conditions. The plotting or outputting of the simulation data would also require special subroutines. However, the total impact of the analysis/test/design requirements is small.

The use of input/output files for special check case profiles may be required. The profiles would include hydraulic power profiles for launch and reentry-through-landing.
4.7.5 Avionics

Avionics subsystems are involved in sensing, communications, information handling, and control. The following subsections discuss avionics modules under the categories of Guidance, Navigation and Control; Communications and Tracking; Displays and Controls; Operational Instrumentation; and EPS Distribution and Control. Data Processing and Software functions are performed by flight hardware and software in the simulators of interest to this study.

4.7.5.1 Guidance, Navigation and Control

Guidance, Navigation and Control subsystems and components are used for sensing vehicle-related observables, using these sensor data to estimate vehicle state variables, and defining and executing desired vehicle maneuvers. The subsystems and components in this category include inertial measurement units, strapdown gyros and accelerometers, propulsion systems interfaces, optical trackers, and the aeroflight control system.
4.7.5.1.1 Inertial Measurement Unit (IMU) - The IMU is used to sense the inertial orientation and acceleration of the vehicle.

**IMU System Description**

Generally, three types of IMU's are employed in spacecraft:

- three-gimbal platform - as used in the Apollo Command Module.
- four-gimbal platform - as used in the Gemini spacecraft and currently baselined for Shuttle (see Refs. 20, 35).
- strap-down platform - similar to the backup attitude reference system on Apollo; considered as an alternate attitude reference system for Shuttle.

Regardless of the type, the IMU outputs directly perceivable by the crew consist of three angular readouts which describe the orientation of the spacecraft with respect to an inertial reference. In addition, accelerometer outputs are input to the onboard computer for processing. In the case of the four-gimbal platform, the output of a redundant inner roll gimbal is also input to the onboard computer. This gimbal provides the capability of preserving the stable member attitude reference during "gimbal lock" conditions. The output of this gimbal is used by the flight computer to prevent gimbal lock, but is not normally displayed to the crew.

The performance verification methods presented in this section are particularly suited to the four-gimbal arrangement, since this design has all-attitude capabilities under normal conditions of body rates. Additional development would be required to verify IMU simulation in and around the gimbal-lock regions characteristic of the other two types of IMU design.

**IMU Module Functions and Performance Parameters**

Figure 4.7-77 depicts the interfaces between the IMU module and the rest of the simulation. Inputs come from four basic sources:

- MDM (Multiplexer/Demultiplexer), which provides the "operate" discrete and the flight software torquing and slew commands.
FIGURE 4.7-77. IMU MODULE INTERFACES
Note on this table that the three primary gimbal angles (not the resolver sine and cosine outputs) have been chosen as critical performance parameters. The fourth gimbal is a redundant roll gimbal which is forced by the stabilization loop to remain at or near zero. It only has a non-zero value during the time that the platform is in the condition that would result in gimbal-lock in a three gimbal platform. Since the stabilization loop of the IMU is not expected to be part of the simulation software (Reference 11), the role of this redundant gimbal in the simulation is unknown. Some empirically-determined "kluge" simulation may be incorporated to provide a "wobble" in the FDAI during these conditions; however, verification of this implementation would be dependent on the manner of its simulation, and is therefore not addressed in this newsletter.

EPS (Electrical Power System), which provides the 28 Vdc operating power.
ECLS (Environment Control and Life Support) system, which provides the thermal control.
Environment, which provides the vehicle dynamics sensed by the platform: angular rotation and inertial acceleration.

Outputs of the IMU fall into four categories:

- Status discretes which are used by the flight software and the Caution and Warning (C & W) system.
- PMS (Performance Monitor System) Data, which are used by the flight software performance monitor system for its redundancy management function.
- Gimbal angle resolver data, which consists of sine and cosine data from the coarse (1X) and fine (8X) resolvers attached to the individual gimbals and is used by the flight software and the FDAI for determining the orientation of the vehicle with respect to the stable member of the platform.
- Accelerometer Data, which consists of the ΔV accumulator outputs and is used by the flight software to determine the total inertial acceleration acting on the vehicle.

Using the current Shuttle baselined four-gimbal platform as a reference, the performance parameters as defined in Ref. 20 are summarized in Table 4.7-22.

Note on this table that the three primary gimbal angles (not the resolver sine and cosine outputs) have been chosen as critical performance parameters. The fourth gimbal is a redundant roll gimbal which is forced by the stabilization loop to remain at or near zero. It only has a non-zero value during the time that the platform is in the condition that would result in gimbal-lock in a three gimbal platform. Since the stabilization loop of the IMU is not expected to be part of the simulation software (Reference 11), the role of this redundant gimbal in the simulation is unknown. Some empirically-determined "kluge" simulation may be incorporated to provide a "wobble" in the FDAI during these conditions; however, verification of this implementation would be dependent on the manner of its simulation, and is therefore not addressed in this newsletter.
### Table 4.7-22. IMU Module Parameters

<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DESCRIPTION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>&quot;Operate&quot; discrete</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Electrical power</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Avionics Bay temperature</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Gyro torquing and gimbal slew commands</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Body angular rate vector</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Body sensed acceleration vector</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Status discretees (IMU ready, operate mode, over-temperature, IMU fail)</td>
<td>O</td>
</tr>
<tr>
<td></td>
<td>PMS data (redundant sensed angular rate, oven temperature, IMU mode/BITE status)</td>
<td>O</td>
</tr>
<tr>
<td></td>
<td>Gimbal angle resolvers:</td>
<td></td>
</tr>
<tr>
<td></td>
<td>• outer roll (coarse/fine)</td>
<td>P</td>
</tr>
<tr>
<td></td>
<td>• pitch (coarse/fine)</td>
<td>P</td>
</tr>
<tr>
<td></td>
<td>• yaw (coarse/fine)</td>
<td>P</td>
</tr>
<tr>
<td></td>
<td>• inner roll (fine only)</td>
<td>P</td>
</tr>
<tr>
<td>φ, θ, ψ</td>
<td>Gimbal angles (roll, pitch, yaw)</td>
<td>CP</td>
</tr>
<tr>
<td>V&lt;sub&gt;x&lt;/sub&gt;, V&lt;sub&gt;y&lt;/sub&gt;, V&lt;sub&gt;z&lt;/sub&gt;</td>
<td>ΔV accumulator outputs</td>
<td>P</td>
</tr>
<tr>
<td>a&lt;sub&gt;imu&lt;/sub&gt;</td>
<td>Instantaneous accelerometer outputs</td>
<td>CP</td>
</tr>
</tbody>
</table>

**Legend:**

- **I** = input
- **O** = output
- **P** = performance parameter
- **CP** = critical performance parameter
IMU Reference Data Sources and Data Formats

Two methods are presented in this section to provide ideal (closed-form solution) IMU angular information in response to selected vehicle body rate inputs. The first method, the "constant rate input method", employs constant body rates or stable member drift rates as inputs, and computes the resultant gimbal angle time histories. The second method, the "closed-form gimbal angle input method", computes the body rate time history which must be input to produce a pre-selected gimbal angle time history.

These methods apply only to the nominal operation of an IMU. Failure modes, effects of off-nominal temperature or power conditions, and control logic are not considered. In the design of these IMU reference math models, only rate and acceleration inputs and gimbal angle and accelerometer outputs are considered. Generation of status discretes and PMS data would require a high-fidelity representation of actual hardware operational logic, which is best obtained from test data. Similarly, determination of IMU responses to input voltages and temperatures will require test results from the actual flight hardware. Generation of the IMU responses to slew commands and gyro torquing commands would involve a high fidelity simulation of the flight hardware stabilization loop. Approximate data for the response to gyro torquing commands can be generated by equating the torquing commands to the gyro drift rates in the reference module presented in this section.

Constant Rate Input Method - By holding the rate input to an IMU constant, the total angular displacement can be determined as a linear function of time. The corresponding IMU gimbal angles can be easily determined by first defining the total angular response in terms of quaternion elements. Once the time history of quaternion element variation is determined, the individual gimbal angles can be extracted from the body/IMU direction cosine matrix, which is a function of the quaternion elements.

Two types of rate inputs are considered:
- body rates \((p, q, r)\) - three components of angular velocity about the body axes.

- drift rates \((D_x, D_y, D_z)\) - three components of angular velocity about the stable member reference axes. (These rates can also be interpreted as gyro torquing commands from the flight software.)

Both types may be input in a single run. Other input data required are: the iteration rate \((\Delta t)\) at which the resultant gimbal angles are to be printed out; the initial gimbal angles \((\varphi_0, \Theta_0, \psi_0)\); the body-axis referenced accelerations \((A_x, A_y, A_z)\), to check the IMU accelerometer computations; and the time \((t_{\text{max}})\) at which the run is to stop.

Figure 4.7-18 presents a math flow of this technique. An initialization path is incorporated, to allow the capability to preset the gimbal angles to any value prior to initiating the input rates. Additional data is computed (including an initial direction-cosine matrix, \(C\)) concerning the orientation of the angular velocity vector with respect to the initial stable member orientation, which serves as the inertial reference for the remainder of the computations.

After the initialization pass, the gimbal angles at each time increment \((\Delta t)\) are computed. This computation progresses as follows:

1) Time is incremented by \(\Delta t\).

2) The total angular displacements of the body \((\Omega_r)\) and of the stable member \((\Omega_d)\) from their initial orientations are computed as linear functions of time.

3) The quaternion elements \((d_1, d_2, d_3, d_4)\) defining the angular displacement of the stable member are computed as a function of total drift angle \(\Omega_d\) and the orientation of the drift vector.

4) The direction cosine matrix \((D)\) defining the orientation of the stable member with respect to its initial position is computed.

5) The quaternion elements \((r_1, r_2, r_3, r_4)\) defining the angular displacement of the vehicle are computed as a function of the total displacement \(-\Omega r\), and the orientation of the rate vector.
BEGIN

YES

1st PASS

NO

READ INPUT DATA

PASS

body rates - p, q, r

drift rates - D_x, D_y, D_z

body accel. - A_x, A_y, A_z

initial angles - \theta_0, \phi_0, \psi_0

max. time - t_{max}

delta time - \Delta t

YES

NO

\begin{align*}
C_{11} &= \cos \theta_0 \cos \psi_0 \\
C_{12} &= \cos \theta_0 \sin \psi_0 \\
C_{13} &= \sin \theta_0 \\
C_{21} &= \sin \theta_0 \sin \theta_0 \cos \psi_0 - \cos \theta_0 \sin \psi_0 \\
C_{22} &= \sin \theta_0 \cos \theta_0 \\
C_{23} &= \cos \theta_0 \sin \theta_0 \cos \psi_0 + \sin \theta_0 \sin \psi_0 \\
C_{31} &= \cos \theta_0 \sin \theta_0 \sin \psi_0 - \sin \theta_0 \cos \psi_0 \\
C_{33} &= \cos \theta_0 \cos \theta_0 \\
\end{align*}

\begin{align*}
wr &= \left( p^2 + q^2 + r^2 \right)^{1/2} \\
wd &= \left( D_x^2 + D_y^2 + D_z^2 \right)^{1/2} \\
\end{align*}

\begin{align*}
\cos \alpha_r &= p/wr \\
\cos \alpha_d &= D_x/wd \\
\cos \beta_r &= q/wr \\
\cos \beta_d &= D_y/wd \\
\cos \gamma_r &= r/wr \\
\cos \gamma_d &= D_z/wd \\
\end{align*}

\begin{align*}
d_1 &= \cos (\alpha_d/2) \\
n_d &= \left( \frac{D_1^2 + D_2^2 + D_3^2 + D_4^2}{2} \right)^{1/2} \\
d_2 &= \cos (\beta_d) \sin (\alpha_d/2) \\
d_3 &= \cos (\gamma_d) \sin (\beta_d/2) \\
d_4 &= \cos (\gamma_d) \sin (\gamma_d/2) \\
\end{align*}

\begin{align*}
D_{11} &= d_1^2 - d_2^2 - d_3^2 - d_4^2 \\
D_{12} &= 2(d_1d_2 + d_3d_4) \\
D_{13} &= 2(d_1d_3 - d_2d_4) \\
D_{14} &= 2(d_1d_4 + d_2d_3) \\
D_{22} &= d_2^2 - d_1^2 + d_3^2 - d_4^2 \\
D_{23} &= 2(d_2d_3 + d_1d_4) \\
D_{24} &= 2(d_2d_4 - d_1d_3) \\
D_{33} &= d_3^2 + d_2^2 - d_1^2 - d_4^2 \\
D_{34} &= 2(d_3d_4 - d_2d_1) \\
D_{44} &= d_4^2 - d_3^2 - d_1^2 - d_2^2 \\
\end{align*}

FIGURE 4.7-78 CONSTANT RATE INPUT METHOD

REPRODUCIBILITY OF THE ORIGINAL PAGE IS POOR

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ R_1 = \cos(r_1 r_2) \]
\[ R_2 = \cos(r_1 \sin(r_2 r_3)) \]
\[ R_3 = \cos(r_4 \sin(r_2 r_3)) \]
\[ R_4 = \cos(r_4 \sin(r_2 r_3)) \]

\[ R_{11} = r_1 - r_1^2 - r_3^2 + r_4^2 \]
\[ R_{12} = 2(r_4 r_3 + r_2 r_1) \]
\[ R_{13} = 2(r_3 r_2 - r_4 r_1) \]
\[ R_{21} = 2(r_4 r_3 - r_2 r_1) \]
\[ R_{22} = r_1^2 - r_2^2 + r_3^2 - r_4^2 \]
\[ R_{23} = 2(r_3 r_2 + r_4 r_1) \]
\[ R_{31} = 2(r_4 r_3 + r_2 r_1) \]
\[ R_{32} = 2(r_3 r_2 - r_4 r_1) \]
\[ R_{33} = r_1^2 + r_2^2 - r_3^2 - r_4^2 \]

\[ [B] = [R] [C] [D]^{-1} \]

\[ \theta = \text{ARC SIN} \left( B_{13} \right) \]
\[ \psi = \text{ARC TAN} \left( \frac{B_{12}}{B_{11}} \right) \]
\[ \phi = \text{ARC TAN} \left( \frac{B_{23}}{B_{33}} \right) \]

FIGURE 4.7-78 (CONTINUED)
6) The direction cosine matrix (R) defining the orientation of the vehicle with respect to its initial position is computed from the quaternion elements.

7) The direction cosine matrix (B) defining the orientation of the vehicle with respect to the stable member is computed as a function of the three previously defined matrices.

8) The gimbal angles describing this orientation are extracted from the B matrix. The equations presented are valid for a gimbal sequence of yaw (ψ), pitch (Θ), roll (φ); other sequences can be treated in a similar manner.

9) The ideal IMU accelerometer outputs are computed using the B matrix and the input body-referenced accelerations.

10) The gimbal angles and accelerometer outputs are stored for comparison with simulation software outputs.

Closed Form Gimbal Angle Input Method - The previous method is primarily suited to verifying the IMU performance during orbital conditions, where the body rates tend to be constant for considerable periods of time. It is also necessary to verify the IMU performance for variable body rates such as encountered during entry conditions. The math flow shown in Figure 4.7-79 describes a method for establishing a closed-form relationship between variable body rates and IMU gimbal angles.

This reference module, given a desired IMU output time history, "inverts" the IMU transformation to generate the body-rate time history which must be input to the IMU. To do this, it is necessary to restrict the form of the input. Each gimbal angle time-history must be an analytic function of time; thus the time derivative of the function (i.e., gimbal angle rate) is precisely computable.

Three typical examples are:

\[ \varphi = A \sin w_1 t \quad \Rightarrow \quad \dot{\varphi} = A w_1 \cos w_1 t \]
\[ \Theta = \frac{B}{C} \tan^{-1} \left( \frac{t-D}{C} \right) \quad \Rightarrow \quad \dot{\Theta} = \frac{B}{C^2 + (t^2 - D^2)} \]
\[ \psi = E \left[ \cos w_2 t + (w_2^2 t) \sin w_2 t \right] \quad \Rightarrow \quad \dot{\psi} = E (w_2^2 t) \cos w_2 t \]

With the gimbal angle rates thus defined, the corresponding body rates are determined by standard Euler transformations. The body rate data is then written...
READ INPUT DATA:
$F_1(t), \dot{F}_1(t)$
$F_2(t), \dot{F}_2(t)$
$F_3(t), \dot{F}_3(t)$
$t_{\text{max}}, \Delta t$

$t = 0$

$\emptyset = F_1(t)$
$\dot{\emptyset} = \dot{F}_1(t)$
$\Theta = F_2(t)$
$\dot{\Theta} = \dot{F}_2(t)$
$\Psi = F_3(t)$
$\dot{\Psi} = \dot{F}_3(t)$

$p = \emptyset - \Psi \sin \Theta$
$q = \dot{\emptyset} \cos \emptyset + \dot{\Psi} \sin \emptyset \cos \Theta$
$r = \dot{\Psi} \cos \emptyset \cos \emptyset - \dot{\emptyset} \sin \emptyset$

STORE:
$\emptyset, \Theta, \Psi,$
$p, q, r,$
t

$t = t + \Delta t$

$\text{IF } t \geq t_{\text{max}} \text{ THEN } \text{YES ELSE NO}$

END

FIGURE 4.7-79 CLOSED FORM GIMBAL ANGLE METHOD
on an output tape for each computation interval required by the simulation software.

**IMU Data Base Impact**

Data base impact for initial IMU dynamical validation is very minor; only the above reference modules and a few mathematical subroutines are required. Revalidation of the basic IMU dynamics should be required rarely, if at all. Validation of subsidiary IMU outputs will require a certain amount of hardware test data.

**IMU Validation Methods and Check Cases**

Verification software structures employing the closed-form-solution reference modules previously described are shown in Figure 4.7-80.

To use the constant rate input method, Figure 4.7-80 (a), input constant body rates and/or drift rates to the IMU reference module and the IMU simulation module, thus obtaining comparable gimbal-angle time histories.

To use the closed-form gimbal angle input technique, Figure 4.7-80 (b), select analytic functions of time to be used as inputs (see preceding examples). These time-histories and their derivatives are input to the reference module, which generates body-rate time-histories to be input to the IMU simulation module. The outputs of the IMU simulation module should then match the original gimbal-angle time histories.

A set of check cases applying different combinations of magnitude and frequency inputs to the various IMU axes should be used for thorough validation of individual-axis responses and their interactions. Due to the analytical nature of the reference data, a highly-accurate match with simulation data should be demanded; e.g., one percent or better over time spans up to a hundred seconds.
Figure 4.7-80. IMU SIMULATION VERIFICATION TECHNIQUES

4.7-232

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
4.7.5.1.2 Strapdown Inertial Sensors - This section concerns those inertial sensors which are "strapped down"; i.e., rigidly mounted to the vehicle structure, rather than on a stable element.

SIS System Description
The SIS subsystem, as described in Refs. 20, 37, consists of five identical sensor packages - three at various locations in the Orbiter, and one in each SRB. Each package contains a normal and lateral accelerometer, and orthogonal rate gyros to sense body roll, pitch and yaw rates. These sensors provide data for use in the vehicle attitude control loops. The SIS has also been considered for use as a backup navigation data source in the event of multiple IMU failures. This application would require the addition of longitudinal accelerometers.

SIS Simulation Module Description and Performance Parameters
The input/output interfaces of the SIS module are shown in Fig. 4.7-81. Primary inputs are of course the body angular rates, the body-axis sensed accelerations of the center of mass, and the current c.g. position. The primary outputs are the simulated rate gyro and accelerometer outputs, which include the effects of sensor location, axis misalignment, and possibly hardware error characteristics. (Hardware error modelling may not be required, unless the SIS is used as a backup navigation reference.) Body bending and fuel slosh contributions to SIS outputs are discussed in Section 4.6. Subsidiary inputs and outputs include electrical power, avionics bay temperature, and various status and failure discretes. Table 4.7-23 provides a parameter list for the SIS simulation module.

SIS Reference Data Sources and Data Formats
Figure 4.7-82 provides the math flow for a reference module which provides data for nominal SIS operation only. Off-nominal operation due to failures and voltage variations and temperature variations is not considered in this study.

Two separate flow paths are shown on Figure 4.7-82: an error-free computation path, and a measurement-error path. On the error-free path, Equation (1) calculates sensed vehicle accelerations at the sensor-package location, in ideal
body-axis angular rates and sensed accelerations of the c.g.

current c.g. position

avionics bay temperature

electrical power

rate gyro and accelerometer outputs

status and failure discretes

FIGURE 4.7-81. STRAPDOWN INERTIAL SENSOR MODULE INTERFACES.
### 4.7-23. STRAPDOWN INERTIAL SENSOR MODULE PARAMETERS

<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DEFINITION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>x, y, z</td>
<td>Body coordinates of center of gravity</td>
<td>I</td>
</tr>
<tr>
<td>a</td>
<td>Vehicle sensed acceleration</td>
<td>I</td>
</tr>
<tr>
<td>p, q, r;</td>
<td>Vehicle angular rate and acceleration in body axes</td>
<td>I</td>
</tr>
<tr>
<td>( \Delta T )</td>
<td>Difference between operating temperature and calibration temperature of the SIS</td>
<td>I</td>
</tr>
<tr>
<td>( x'_i, y'_i, z'_i )</td>
<td>Typical sensor locations (in body coordinates)</td>
<td>DB</td>
</tr>
<tr>
<td>( \psi', \epsilon', \phi' )</td>
<td>Accelerometer/rate gyro misalignments ( (\psi' = \text{misalignment in X-Y plane, } \Theta' = \text{misalignment in X-Z plane, } \phi' = \text{misalignment in Y-Z plane}) )</td>
<td></td>
</tr>
<tr>
<td>D</td>
<td>Accelerometer dead zone</td>
<td>DB</td>
</tr>
<tr>
<td>( \epsilon a_y, \epsilon a_z )</td>
<td>Accelerometer measurement errors</td>
<td>DB</td>
</tr>
<tr>
<td>( \epsilon p_d, \epsilon q_d, \epsilon r_d )</td>
<td>Rate gyro measurement errors (roll, pitch, yaw drift rates respectively)</td>
<td>DB</td>
</tr>
<tr>
<td>( a_{ia} )</td>
<td>Accelerations at the accelerometer, in ideal axes</td>
<td>P</td>
</tr>
<tr>
<td>( a_{ma} )</td>
<td>Accelerations at the accelerometer, in misaligned axes</td>
<td>CP</td>
</tr>
<tr>
<td>( p_{ma}, q_{ma}, r_{ma} )</td>
<td>Vehicle angular rates, in misaligned axes</td>
<td>CP</td>
</tr>
</tbody>
</table>

<sup>a</sup>LEGEND:  
DB = data base input  
I = input  
P = performance parameter  
CP = critical performance parameter
FIGURE 4.7-82. STRAPDOWN INERTIAL SENSOR REFERENCE MODULE MATH FLOW.
sensor axes. Equations (2) and (3) then transform the ideal-axis accelerations and angular rates into true sensor-axis outputs, using small-angle relationships for axis misalignments. A single misalignment transformation is used for both accelerometer and gyro outputs, since the use of a typical misalignment provides all the generality required for a complete verification.

The measurement-error computations are provided on the assumption that some or all of the simulations of interest will require sensor error modelling. The measurement-error path is taken only when an input flag is set.

The accelerometer measurement error reference data is generated using Equations (4) and (5) of Fig. 4.7-82, where $D$ is from the data base and represents a typical dead zone or threshold below which no acceleration is sensed, and the functions $\epsilon_{AY}$ and $\epsilon_{AZ}$ are generalized representations of the measurement errors that would be added to the true axis accelerations. Equation (7) presents an expansion for the accelerometer error function $\epsilon_A$ of Equation (5), using a standard modelling algorithm for typical accelerometer measurement errors.

$$A_1 = B_a + C_1 A_1 + C_2 A_1^2 + ... + C_{12} A_2 + C_{13} A_3 + C_{14} T + ... \quad (7)$$

The parameters in Equation (7) are defined as follows:

- $B_a$ = accelerometer total bias (mean + random)
- $A_1, A_2, A_3$ = acceleration components along the input axis and the cross-axes, respectively
- $C_1$ = linear scale factor error
- $C_2$ = non-linearity error coefficient
- $C_{12}, C_{13}$ = cross-axis sensitivity error coefficients
- $\Delta T$ = difference between calibration temperature and operating temperature
- $C_{14}$ = linear temperature error coefficient
It may not be necessary to model all the terms shown in Equation (7), according to the fidelity required. In addition, Equation (7) does not represent the most general case; for example, we could include higher order non-linearity terms, error terms proportional to acceleration products, and non-linear temperature variations. The necessary terms in the error model can be determined using vendor-supplied design and test data for individual errors, the real-world sensor use, and the simulator's functional requirements. Typically, bias, linear scale factor, second order non-linearity and linear temperature error terms would be all that is required for sensors involved in a navigation function.

Equation (6) provides rate gyro measurement error reference data, where the functions $E_{PD}$, $E_{QD}$, and $E_{RD}$ are generalized representations of measurement errors based on sensor design and test data. The error values output would normally be added to the true rate outputs as drift rates. Equation (8) presents an expansion for gyro drift rate, using a standard modeling algorithm:

$$
E_D = B_g + K_iA_i + K_OA_o + K_SA_s + \ldots + K_i0A_i0 + K_0A_o0 + K_sA_s \\
+ K_{i1}A_iA_1 + K_{t\Delta T} + \ldots
$$

(8)

where the individual parameters are defined as follows:

- $B_g$ = gyro total bias drift (mean + random).
- $A_i, A_o, A_s$ = case accelerations along the input, output, and spin axes respectively.
- $K_i, K_o, K_s$ = anisoelectric drift coefficients
- $\Delta T$ = difference between calibration temperature and operating temperature
- $K_t$ = linear temperature coefficient

It may not be necessary to model all the terms of Equation (8), or it might be necessary to model additional terms; for example, drifts proportional to acceleration squared or possibly drift due to external magnetic fields. As with the accelerometer error modeling, gyro error model fidelity should be determined using vendor-supplied design and test data on individual errors, the real-world sensor use, and the simulator's functional requirements.
The gyro case accelerations shown as variables in the error functions of Equation (8) are the same as the body accelerations for the accelerometer error functions. The transformation of AX, AY, and AZ into gyro input, output, and spin axis accelerations depends on the individual gyro orientations. As a result the individual drift rate equations for $\dot{\varepsilon}_P$, $\dot{\varepsilon}_Q$, and $\dot{\varepsilon}_R$ will have different body acceleration components as the respective gyro axis accelerations. Since the error model is not affected by the preceding generalizations, there is no loss in the validity of the verification.

The data required for validation will normally be in hard-copy format. Basic information, such as sensor package locations and typical misalignments, should be found in Ref. 36. Hardware error coefficients may have to be obtained from test reports or other less-accessible sources.

**SIS Validation Methods and Check Cases**

In general, checkpoint data will be required for both error-free and measurement-error modes of operation of the SIS module. Although reference-trajectory segments may be used to provide input data, selected discrete checkpoints will be simpler to implement, and actually give better results.

For reference data not containing measurement errors, the inputs include sensor location in the body reference system, the center-of-mass accelerations, body angular rates and angular accelerations, and a zero value for the measurement-error flag. Only a relatively small number of independent input check points are required for a complete verification for this mode, since the equations involved are relatively simple. Sets of three widely-spaced linearly-independent vectors in linear acceleration, angular rate, angular acceleration and axis misalignments will provide a thorough validation exercise. Several sensor-package locations should be tested, including fore/aft, left/right, and up/down displacements relative to the c.g. Agreement between reference and simulation data should be close to machine accuracy (e.g., five to six significant figures).

When generating reference data for the error model verifications, the required inputs are the accelerations at the sensor in the sensor true axes (assumed the
for both accelerometers and rate gyros), the operating temperature variation from that for calibration, and a positive value for the measurement-error flag. Data can be generated by varying the inputs selectively to magnify effects of different error terms. Comparisons can then be made which are identifiable with individual error components. Agreement should be within a few percent.

When driving the simulator models to generate the corresponding data, we anticipate that some action will have to be taken to provide compatibility with the reference module execution mode. For example, contributions due to flexible body dynamics must be zeroed; simulation-module measurement-error models must be deactivated for non-measurement error check points. For the measurement error check points, sensor locations should be set to the center of gravity, with zeroed misalignments. Since the simulator software has not yet been developed, only the preceding generalizations are made with respect to interface initializations and input identifications required for the simulator module.

**SIS Validation Data Base Impact**

Data base impact for SIS module initial validation is very minor. The reference module is rather simple, and the use of discrete checkpoints obviates handling of large data files. Revalidation would only be required if significant changes were made in the measurement-error model.
4.7.5.1.3 Propulsion Systems Interface Units (PSIU's) - These units, which transfer data between the propulsion subsystems and flight computers and/or crew controls and displays, include the Main Engine Controller/Engine Interface Unit (MEC/EIU), the Solid Rocket Booster (SRB) interface, the Orbital Maneuvering System Thrust Vector Control (OMS TVC) interface, and the Reaction Control System (RCS) interface.

Except for the MEC/EIU, these are rather simple hardware units, and we assume that their functional simulation, data-word generation/interpretation capabilities and malfunction-insertion provisions will be "embedded" in the module which simulates the corresponding propulsion subsystem. Only the MEC/EIU will be described in any detail in this section; the other PSIU's perform the same general functions.

PSIU Subsystem Descriptions

The MEC hardware and functions are described by Ref. 26, the MEC software by Ref 38. The EIU is described by Ref. 39. Specifications for the other PSIU's have apparently not been issued yet.

The MEC and EIU together perform the following functions:
- Accept discrete (e.g., start, shutdown) and variable (e.g., thrust level) commands from the Orbiter avionics.
- Control SSME sequencing, thrust, and mixture ratio.
- Perform engine checkout and monitoring.
- Transmit SSME checkout/monitoring data back to the Orbiter avionics
- Perform self-test.

Figure 4.7-83 (after Ref. 26) shows the control and data interfaces of the MEC/EIU. The EIU's role in control/data interchange is simply code conversion and formatting. Other PSIU's perform similar functions, except for thrust variation.

PSIU Module Description and Performance Parameters

PSIU simulation has two aspects: functional simulation, and data-word generation/interpretation. From the functional viewpoint, we assume that each PSIU simulation is "embedded" in the module which simulates the associated
FIGURE 4.7-83. MEC/EIU HARDWARE INTERFACES
The overall command/response characteristics of each propulsion subsystem. Thus the overall command/response characteristics of each propulsion module will be a composite of (a) the internal processing of the PSIU and (b) the response of the propulsion hardware - pumps, valves, combustion chamber and nozzle. Startup/shutdown sequencing will probably be simulated as empirical time functions for thrust buildup/tailoff.

The other basic function of the PSIU modules is the handling of digital data-words, including interpretation of command words received from the flight computers, and generation and formatting of monitoring and status words for transmission to the flight computers. These functions must be implemented precisely to satisfy the flight software; however, they will be shared with or entirely absorbed by the Flight Hardware Interface Device (FHID), thus simplifying the simulation software.

Each PSIU module will also require some failure-insertion provisions; simulated failures may affect either the functional simulation, the data-word handling, or both.

No performance-parameter tables are provided for PSIU simulation modules. Since PSIU simulation is embedded in the propulsion subsystem simulation module, the performance parameters for each such module will include both functional-simulation parameters and avionics-related command and status words. For example, see Section 4.7.3.1 for the SSME/MEC/EIU parameter table and simulation-module interface diagram.

**PSIU Reference Data Sources and Data Formats**

The functional performance of each PSIU simulation will be implicitly validated by end-to-end command/response validation of the associated propulsion module. This will include static thrust levels, thrust buildup/tailoff, and (for the SSME only) throttle response.

The basic source of functional-simulation reference data will be engineering simulations of each propulsion subsystem. Later in the program, engineering data will be refined using static-firing data; these data will be corrected for atmospheric pressure in the case of the larger engines, but vacuum-chamber firing data will be available for the smaller engines. These considerations are discussed in Section 4.7.3.
Command/status data-word formats must be verified bit-by-bit for each nominal and off-nominal case, the basic source of reference data being the most current version of each PSIU specification.

Due to the complexity of the MEC/EIU, it may be necessary to verify this submodule in isolation, before integration with the basic SSME module. The hardware/software MEC simulation described by Ref. 40 may be a suitable source of reference data for such an exercise.

**PSIU Validation Methods and Check Cases**

Each composite PSIU/propulsion-subsystem module must be exercised over its overall operating range, including startup, constant thrust, and tailoff. Additional check cases will be necessary for the variable-thrust SSME. These will include static-thrust levels from MPL to EPL, as well as dynamic throttle response to both increase and decrease commands over the operational static-thrust range. For simulators which use functional simulation of the flight software, the command inputs will be in the normal internal floating-point format of the host computer.

For simulators using flight-computer hardware, inputs must be in the format in which they will be received from the flight computer/FHID. The set of check cases must then be sufficient to verify that each PSIU module properly interprets all valid flight-computer command words, and returns the correct status/monitoring words for all self-test modes, nominal and off-nominal operational modes.

**PSIU Validation Data Base Impact**

In the functional-simulation area, validation of the PSIU's contributes no data base impact, since PSIU functions are implicit in the end-to-end validation of the propulsion modules.

Validation of digital data-word handling will require a command/response data-word "dictionary" covering the operational regime of the simulator of interest. For the MEC/EIU, this dictionary will be fairly extensive (several hundred entries); for other PSIU's, the dictionaries will be short (perhaps a few dozen entries).
4.7.5.1.4 Star Tracker (ST) - Unlike previous manned space vehicles, the Orbiter provides fully automatic star/target tracking, without crew viewing of the tracker field. This section discusses the ST hardware and its flight-computer interface, as well as the functions and validation of the associated simulation module.

ST Subsystem Description

The ST is a strapdown, wide field-of-view (10 X 10°) image-dissector device. It provides automatic acquisition and tracking, under flight-computer control, of a selected star or sun-illuminated rendezvous target. While tracking, it outputs the apparent magnitude and position in the field of the object being tracked. Its sensitivity (acquisition threshold) is variable on command; the maximum sensitivity is sufficient to acquire and track the 153 brightest stars (S-20 magnitude), or a sunlit target whose apparent brightness is at least equivalent to an S-20 magnitude of +3 at a range of 300 nm.

Despite the stray-light protection afforded by its light shade (LS), the ST may fail to acquire, or lose track on, stars or targets which are in the vicinity of other bright objects; e.g., the sun, moon, earth, or a brighter star. To protect the tracker from damage due to excessive input brightness, it is provided with a shutter, activated by a separate bright source sensor. Field of view and response time of this subsystem are sufficient to prevent damage due to a bright object approaching at a rate of 10 deg/sec.

The physical arrangement of the three ST/LS assemblies, mounted on the nav base for maximum accuracy, is shown in Figure 4.7-84 (from Ref. 41); additional detail may be found in Ref. 42. Note that #1 and #2 star trackers provide overlapping coverage.

Star tracker operational modes, internal signal processing, and command/data interfaces are indicated by Figure 4.7-85. The modes of interest are:

- Open/close door
- Self test
- Search/acquire star or target
- Track star or target
- Break track
- Close shutter (bright source protection)
FIGURE 4.7-8A. STAR TRACKER PHYSICAL ARRANGEMENT
FIGURE 4.7-85. STAR TRACKER FUNCTIONAL BLOCK DIAGRAM (REFERENCE)
The star tracker door, in the left side of the Orbiter fuselage, is closed during ascent and entry, and opened on orbit. The self-test mode activates ST BITE, causing the ST to return a discrete indicating either operable or failed status.

In initiating a search, the flight computer sets the acquisition threshold, and may also provide horizontal and vertical position offset coordinates. In the absence of offset coordinates, the ST searches its entire field, locking onto either the first catalog star acquired, or to the brightest object in the field. If given an initial offset, it searches a reduced field centered on the offset point. In either case, a rectangular raster-scan search pattern is used, the search time will not exceed ten seconds, and the ST falls into the track mode.

The ST remains in the track mode until given a "break-track" command, the object passes out of the field of view, or it loses lock due to excessive vehicle rates or bright-source interference. Since the ST's are strapped-down, it may be necessary for Orbiter attitude maneuvers to be executed to maintain tracking. (Note that Ref. 41 does not presently define ST discretes for search failure or loss of target during track.)

ST Module Description and Performance Parameters

Star tracker functions will be simulated at varying levels of detail. Door opening and closing will be simulated as talkback, with time delay and allowance for malfunction insertion. Self-test operation can be simulated with a small command/response dictionary which allows for nominal status and a repertoire of inserted malfunctions.

To obtain realistic star selection and timing results, the search/acquire mode simulation will have to be rather detailed. For all stars which are not blocked by the sun, moon, or earth, and satisfy the magnitude criterion defined by the current threshold selection setting, coordinate transformation and gating operations will determine whether they fall in the range of the scan pattern. To determine the first star acquired, a "lexicographic ordering" operation (see Ref. 43) will be required to determine which of the candidate stars is "nearest" to the starting corner (shown as the bottom-left corner in Figure 4.7-86, in terms of scan-pattern coordinates. Hardware scan-rate parameters can then be used to compute the acquisition time.

4.7-243
projection of scan range on celestial sphere

stars satisfying magnitude criterion

ending point of raster scan

selected star (first star satisfying magnitude criterion, within the scan region, which is encountered by scan pattern)

starting point of raster scan

vertical

horizontal

FIGURE 4.7-86. TYPICAL SCAN-PATTERN RELATIONSHIPS
The scan computations per se will be simpler for target acquisition, or for the search mode in which the brightest object in the field is selected. However, computation of target brightness will require determination of terminator position, range to target, and target viewing aspect (e.g., broadside vs. end-on).

Simulation of tracking outputs requires only a simple coordinate transformation, plus logic for loss of tracking due to excessive vehicle rates, movement of the object out of the field, and inserted malfunctions. Hardware error sources (bias and random) and stellar aberration due to Orbiter inertial velocity will also be simulated.

Bright-source relative positions and closure rates must be simulated at all times that any star tracker is operational.

Star tracker simulation module parameters are listed in Table 4.7-24, and module interfaces are shown in Figure 4.7-87.

**ST Reference Data Sources and Data Formats**

Initial validation of the track mode is best supported using closed-form solutions, for several special orientations of the ST axes relative to the point targets used for testing.

For more complete validation (all operational modes, interface with environment and dynamics), a detailed reference module will be required. Two candidate reference modules have been identified. One of these was developed, checked out, and used for the study described in Ref. 44. However, we recommend the module now being developed and checked out for inclusion in SVDS, the math flow of which (Ref. 45) is presented in Figure 4.7-88. Note that the search-mode simulation in this module only simulates the brightest-object selection criterion. Modifications will be necessary if the first-object-acquired criterion of Ref. 41 is actually implemented in the flight system.

**ST Data Base Impact**

The reference module for ST simulation validation is quite detailed; it will be of the same order of size as the ST simulation module for the SMS, larger than the one for the SPS. In addition, a driver routine will be required to generate Orbiter and target states and rates. Initially, these should be just synthetic 4.7-250
<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DESCRIPTION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Door-open discrete</td>
<td>I</td>
<td></td>
</tr>
<tr>
<td>Search-mode command discrete</td>
<td>I</td>
<td></td>
</tr>
<tr>
<td>Initial search position commands (horizontal and vertical displacement)</td>
<td>I</td>
<td></td>
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<tr>
<td>Self-test mode command</td>
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<td>Threshold-set command</td>
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<tr>
<td>Break-track command</td>
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<td>Bus voltage</td>
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<td>r, v</td>
<td>Orbiter position &amp; velocity (ECI axes)</td>
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<tr>
<td>E&lt;sub&gt;r&lt;/sub&gt;</td>
<td>Target relative position (Orbital axes)</td>
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<td>ϕ, e, ψ</td>
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<tr>
<td>ω</td>
<td>Orbiter angular rate vector</td>
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<td>Star catalog (magnitudes, unit vectors in ECI)</td>
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<td>Sun &amp; moon positions (unit vectors in ECI)</td>
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<td>Earth horizon altitude</td>
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<td>Tracker alignment angles</td>
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<td>Horizontal &amp; vertical scan rates</td>
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<td>Tracker hardware errors (bias, scale factor, and random)</td>
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<td>Shutter-closed discrete</td>
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<tr>
<td>Self-test data</td>
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<td></td>
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<tr>
<td>Track-mode engaged discrete</td>
<td>P</td>
<td></td>
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<tr>
<td>Star/target tracking position (horizontal &amp; vertical displacement)</td>
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<td>Star/target apparent magnitude</td>
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</table>

<sup>a</sup> I = input  
DB = data base input  
P = performance parameter  
CP = critical performance parameter
VEHICLE DYNAMICS MODULE

Orbiter states & rates

TARGET RELATIVE POSITION

EARTH HORIZON ALTITUDE

SUN & MOON POSITIONS

STAR CATALOG: POSITIONS & MAGNITUDES

EPS MODULE

power demand & supply

COMMANDS

DISCRETES

DATA

MDM

FLIGHT COMPUTER

FIGURE 4.7-37. STAR TRACKER SIMULATION MODULE INTERFACES
### STAR TRACKER REFERENCE MODULE MATH FLOW

**Program ITVF**

**Purpose:** To generate simulated star tracker measurements from vehicle trajectory and attitude information.

**Inputs:**
- PHI(3,3) angular rotation vectors defining star tracker coordinate frames with respect to the shuttle body frame
- REL(3) angular factor to account for celestial body brightness
- RTL(3) average radii of the earth, sun, and moon
- XTH angular factor for the earth's atmosphere
- RE effective radius of the earth for sun occultation
- MRZV rendezvous tracking flag
- FOV star tracker raster field of view (one half of the side of the square)
- AFOV auto-optics field of view
- NSTAR number of stars in the star table
- CFOV half-angle of the circular field of view enclosing the star tracker square raster field
- BMAX maximum range for beacon tracking
- BMAG beacon visual magnitude
- TMAG sun-illuminated target visual magnitude
- T elapsed time since the clock epoch
- R(3) vehicle position vector
- RT(3) target vehicle position vector
- ITK(3) star tracker acceleration flags
- AUTOP(3) auto-optics flags
- MBCON(3) beacon tracking flags
- PSICOM(2,3) auto-optics angular commands
- TIB(3,3) ECI-to-body transformation matrix

**Outputs:**
- ITM(3) tracking flags
- PSI(2,3) ideal star tracker deflection angles
- PSIOB(2,3) simulated star tracker angles

**Outputs:**
- ITMK(3) tracking flags
- PSIK(3) ideal star tracker deflection angles
- PSI0B(3) simulated star tracker angles

- error option flags
- constant for computing tracker noise standard deviation
- tracker misalignment vectors
- tracker scale factor nonlinearities
- deflection output quantization level

**Figure 4.7-88.** STAR TRACKER REFERENCE MODULE MATH FLOW
READ PROGRAM CONSTANTS

CONVERT MAGNETIC UNITS TO RADIANS, LENGTH UNITS TO METERS, AS REQUIRED

COMPUTE VEHICLE BODY TO STAR TRACKER TRANSFORMATIONS:

\[
[\mathbf{T}_B(1)] = \begin{bmatrix}
\cos(3,1) & \sin(3,1) & 0 \\
\cos(2,1) & -\sin(2,1) & 0 \\
0 & 0 & 1
\end{bmatrix}
\]

\[
[\mathbf{C}_N(2,1)] = \begin{bmatrix}
\cos(1,1) & \sin(1,1) \\
-\sin(1,1) & \cos(1,1)
\end{bmatrix}
\]

\[
[\mathbf{C}_R(1,1)] = \begin{bmatrix}
1 & 0 & 0 \\
0 & 1 & 0 \\
0 & 0 & 1
\end{bmatrix}
\]

\[
\mathbf{STCL}(1) = \begin{bmatrix}
\theta_1 \\
\phi_1 \\
0
\end{bmatrix}
\]

READ T, R, RT, ITK, HNTOO, MICON, PSIOM, TIB

COMPUTE STAR TRACKER CENTER LINES:

\[
[\mathbf{STCL}(1)] = [\mathbf{T}_{IB}]^T \mathbf{STCL}(1)^T
\]

CALL WCULS(1, T, DFL, RO, KATH, RE, UV, T-HET, KE, KRE, IDAY)

CALL BLNLC (STCL(1,10), UV, THETA, ICVU, IDAY, 0, IDGCC)

CALL WECL-1, T, DEL, RO, KATH, RE, UV, T-HET, KE, KRE, IDAY)

PRINT: "IDth STAR TRACKER OCCULTED BY EARTH (IF IDGCC = 1), SUN (IF IDGCC = 2), MOON (IF IDGCC = 3)"

FIGURE 4.7-38. (CONTINUED)
FIGURE 4.7-5B. (CONTINUED)
FIGURE 4.7-RR. (CONTINUED)
Purpose: To compute the shift in the apparent line of sight to a star due to motion of the observing vehicle about the sun.

Inputs:
- $T$: elapsed time from the clock epoch
- $U(3)$: geometrical line of sight to star

Output:
- $USTAR(3)$: line-of-sight vector corrected for aberration

Figure 4.7-83. (Continued)
Subroutine EOC (V, LW, LFW, CFF, IDAY, IDCC, IDART, IDART) 1

Purpose: To test for interference by the earth, sun, or moon

Inputs:
- V(3) target line of sight or ST centerline
- LW(3,3) unit vectors from the vehicle to the earth, sun, or moon
- THETA(3) effective half-angles of the earth, sun, and moon subtended at the vehicle
- CFF half-cone angle of the circular field-of-view encompassing the ST search raster pattern
- IDAY orbital phase (day/night) flag
- IDART earth only flag

Output:
- IDCC identity of the occulting body
  - IDCC = 1: earth
  - IDCC = 2: sun
  - IDCC = 3: moon

*compute aberration correction vector:
\[ \text{TEMP} = \begin{bmatrix} \sin(\text{GAMMA}) & -\cos(\text{GAMMA}) & 0 \end{bmatrix} \]
\[ \text{A} = \text{CINV} \cdot \text{VVE} + \text{CA} + \text{TEMP}^\top \text{[TIEC]} \]

*compute line of sight adjusted for aberration:
\[ \text{USTAR} = \text{UNIT} (y + z) \]

RETURN

**FIGURE 4.7-88**: (CONTINUED)
FIGURE 4.7-88. (CONTINUED)
Subroutine OBSINF (S1, WAG, ITTRR, TSI, T, SIG, PS100)

Purpose: To compute simulated star tracker deflection angles

Inputs:

S1(3) geometrical line of sight to the target
WAG visual magnitude of target
ITTRR identity of tracker
TSI(3,3) star tracker-to-CSE transformation matrix
T elapsed time since the clock epoch
IABERR error option flag
IHOISE (Input via COMMON)
ISCALE (Input via COMMON)
ICNOIS constant for computing tracker noise standard deviation (via COMMON)
PHI(3,3) tracker misalignment vectors (via COMMON)
SF(3,2,3) tracker scale factor nonlinearities (via COMMON)
QUANT deflection output quantization level (via COMMON)

Outputs:

PSI(2) ideal star tracker deflection angles
PSI00(2) simulated star tracker angles

START

1 = ITTRR

COMPUTE IDEAL STAR TRACKER DEFLECTION ANGLES:

SR = [TSI] \cdot T

PSI(1) = \arctan \left( \frac{SR(1)}{SR(3)} \right)

PSI(2) = \arctan \left( \frac{SR(2)}{SR(3)} \right)

CORRECT FOR ABERRATION:

CALL ABERR (T, S1, SIG)

SR = [TSI] \cdot T

COMPUTE NOISE \sigma:

SIG = ICNOIS \cdot (2.5)^{\text{QUANT}}

ACCESS RANDOM NUMBER GENERATOR FOR 2 GAUSSIAN RANDOM NUMBERS, R1 AND R2

RNOIS(1) = R1 \cdot SIG

RNOIS(2) = R2 \cdot SIG

FIGURE 4.7-88. (CONTINUED)
FIGURE 4.7-88. (CONTINUED)
Subroutine SCREEN (STCL, CFOV, NSTAR, STDAT, NS)

Purpose: To sort out navigation stars which fall within the circular field of view encompassing the ST search raster pattern.

Inputs:
- STCL(3) : ST centerline in ECI coordinates
- CFOV : half-angle of the circular field of view encompassing the ST search raster pattern
- NSTAR : number of stars in the star table

Outputs:
- STDAT(10,4) : star data (unit vectors and magnitudes) of candidate stars
- NS : number of candidate stars

QUANTIZE PSI03:
TEMP = MOD(PSI03(1), QUANT)
PSI03(1) = PSI03(1) - TEMP
TEMP = MOD(PSI03(2), QUANT)
PSI03(2) = PSI03(2) - TEMP

FIGURE 4.7-03. (CONTINUED)
Subroutine SEARCH (STCL, CFOV, NSTAR, KE, MAUTOP, PSICOM, PSIMAX, TSI, UW, IDAY, FOV, TSTR, ITRAC)

Purpose: To detect a target star for tracking

Inputs:
- STCL(3): star tracker center line
- CFOV: half-angle of circular field of view enclosing the tracker search raster pattern
- NSTAR: number of stars in the star table
- KE: effective half-angle of the earth
- MAUTOP: auto-optics mode flag
- PSICOM(2): auto-optics deflection commands
- PSIMAX: raster limit
- TSI(3,3): ST-to-ECI transformation matrix
- UW(3,3): unit vectors from vehicle to the earth, sun, and moon
- IDAY: orbital phase (day/night) flag
- FOV: tracker search raster size

Outputs:
- TSTR(4): target star unit vector and magnitude
- ITTRAC: tracking flag
SEARCH STAR TABLE FOR CANDIDATE STARS:
CALL SCREEN (STC_, CFUV, NSTAR, STRAT, K)

A

SEARCH-2

SEARCH-1

TEST VISIBILITY OF J5th CANDIDATE STAR:
CALL VISID(STRAT(1,JS), KE, MAUTOP, PSL01, PS1OU1, T51, JO, IVAY, IDCC)

IDCC = 0 ? NO

YES

STORE VISIBLE STAR UNIT VECTOR AND MAGNITUDE:
VSTR(K,1) = STRAD(1,JS)
VSTR(K,2) = STRAD(2,JS)
VSTR(K,3) = STRAD(3,JS)
VSTR(K,4) = STRAD(4,JS)
NSTR = K
K = K + 1

SEARCH-1

FIGURE 4.7-88. (CONTINUED)
Subroutine SELECT (ST, NSTR, MIN)

Purpose: To select the brightest star in the ST field of view

Inputs:
- SNTG(NSTR) magnitudes of visible stars
- NSTR number of visible stars

Outputs:
- MIN index of the brightest star

FIGURE 4.7-88. (CONTINUED)
Subroutine TRACK (TSTR, STCL, CFOV, NSTAR, KE, MAUTOP, PSICOM, PSIMAX, TSI, UW, ITRAC)

Purpose: To test the visibility of the star being tracked and to search for a new target star if the visibility test is failed.

Inputs:
- TSTR(4): target star unit vector and magnitude
- STCL(3): star tracker centerline
- CFOV: half-angle of circular field of view enclosing the tracker search raster pattern
- NSTAR: number of stars in the star table
- KE: effective half-angle of the earth
- MAUTOP: auto-optics mode flag
- PSICOM(2): auto-optics deflection commands
- PSIMAX: raster limit
- TSI(3,3): ST-to-EC1 transformation matrix
- UW(3,3): unit vectors from vehicle to the earth, sun, and moon
- IDAY: orbital phase (day/night) flag
- FOV: tracker search raster size

Outputs:
- TSTR(4): target star unit vector and magnitude
- ITRAC: tracking flag

FIGURE 4.7-88. (CONTINUED)
Subroutine VECELB (R, T, DEL, RB, KATI, RE, UW, THETA, KE, KRE, IDAY)

Purpose: To compute vehicle-to-celestial body (the earth, sun, and moon) unit vectors, half-angles of celestial bodies, and orbital phase.

Inputs:
- R(3): vehicle position vector
- T: elapsed time from the clock epoch
- DEL(3): angular factors to account for celestial body brightness
- RB(3): average radii of the earth, sun, and moon
- KATI: angular factor for the earth's atmosphere
- RE: effective radius of the earth for sun occultation

Outputs:
- UW(3,3): vehicle-to-celestial body unit vectors
- THETA(3): effective half-angles of celestial bodies including glow
- KE: effective half-angles of the earth including the atmosphere
- KRE: effective half-angle of the earth for sun occultation
- IDAY: day phase flag

---

**FIGURE 4.7-38. (CONTINUED)**
Subroutine VISIS (V, KE, MAUTOP, PSICOM, PSIRAX, TSI, UW, IDAY, IDOCC)

Purpose: To test the visibility of a target within a specified raster area (source or auto-optics).

Inputs:
- V(3) target line of sight in ECI
- KE effective half-angle of the earth subtended at the vehicle
- MAUTOP auto-optics mode flag
- PSICOM(2) auto-optics angular commands
- PSIRAX raster limit
- TSI(3,3) ST-to-ECI transformation matrix
- UW(3,3) unit vectors from vehicle to the earth, sun, and moon
- IDAY orbital phase (day/night) flag

Outputs:
- IDOCC visibility flag
  - IDOCC = 0: target visible
  - 1: earth occultation
  - 4: target outside specified raster area

Diagram:
- A
  - J = J + 1
  - J > 3
    - YES
    - NO
      - DETERMINE ORBITAL PHASE (DAY/NIGHT)
      - TEMP = ARCCOS [(V(3) \cdot [M(1)]]
      - TEMP < KE? YES NO
      - -DAY = 1
      - IDAY = 0
      - RETURN
- RETURN
FIGURE 4.7-88. (CONCLUDED)
states and rates; later, realistic vehicle dynamics can be provided by an EOM module. Hardware data (error sources and scan-rate parameters) and a star catalog complete the ST validation data base requirements.
4.7.5.1.5 Aero-Flight Control System (FCS) - The FCS, which is used during approach and landing, TAEM, and part of entry, is described in Ref. 46. This is a "fly by wire" system, with data handling and control functions performed by the flight software resident in redundant digital computers. The backup FCS is another digital computer (with identical CPU hardware and simplified software).

Of the flight hardware involved in flight control, most modules -- e.g., IMU, rate gyros, TACAN receivers -- are covered in other sections of this report. The flight hardware modules which we have assigned exclusively to FCS are:
- Aerosurface Actuator Interface Units
- Air Data System

4.7.5.1.5.1 Aerosurface Actuator Interface Units (ASAIU's) - These are rather simple hardware units, with very limited simulation and validation requirements. Therefore, the discussion which follows is rather brief. Additional information relating to somewhat similar hardware units (PSIU's) may be found in Section 4.7.5.1.3.

ASAIU Description

Like the PSIU's described in Section 4.7.5.1.3, the ASAIU's provide interfacing between controlled hardware units (in this case, aerosurface actuators) and manual controls and flight computers, performing signal processing and checkout functions. When the control channels and aerosurface actuators are performing properly, the primary function of the ASAIU's is formatting and conversion of signals from and to the flight computers, to implement closed-loop vehicle control.

The ASAIU's also implement "voting" of redundant commands and feedback signals, enabling command equalization as well as malfunction detection, isolation, switch-out and annunciation. Switchout of a malfunctioning actuator can be overridden by crew command. In the case of the quad-redundant hydraulic actuators used on the fast-response surfaces -- elevons and rudder/speedbrake -- these monitoring functions are implemented with rather complex and as yet ill-defined algorithms involving position feedbacks and hydraulic pressures sensed at multiple ports. For the dual-redundant hydraulic actuators used on the body flap, the implementation is similar, albeit simpler.
Specifications and study reports defining command/response word formats, malfunction-handling algorithms, etc., have not yet been identified.

**ASAIU Module Description and Performance Parameters**

Again like the PSIU's, it seems reasonable to assume that the functions of the ASAIU's will be "embedded" in the associated actuator simulation modules. This is particularly true in view of the fact that the level of detail of actuator simulation will probably not be adequate to directly simulate the equalization and monitoring functions in high fidelity. That is, the actuators will be simulated basically as transfer functions with appropriate nonlinearities (see Section 4.7.1.4); thus the physical quantities used in the monitoring process will simply not exist in the simulation. It may be possible to translate these physical parameters into their equivalent transfer-function variables. More likely, however, the simulation module will simply talkback inserted malfunctions.
4.7.5.1.5.2 Air Data System (ADS) -- The air data system is used to sense the velocity and orientation of the Orbiter relative wind, providing data used for aeroflight control.

ADS System Description

Figure 4.7-89 shows an overview of the air data system and its hardware interfaces. The total system consists of: a set of dual-redundant probes, with associated deploy/retract mechanisms and heaters; dual/dual-redundant air data transducer assemblies (ADTA); and electronics interfaces. The probes are deployed during the transition phase of entry, and air data outputs are used from then until landing. (See Refs. 20, 48.)

Figure 4.7-90 is an expansion of an ADTA, identifying the individual transducers, calibration memories, and miscellaneous electronics. The ADTA has self-test and operate modes. Self-test data is evaluated by the GN&C computers to determine the status of each ADTA. In the operate mode, the ADTA responds to probe inputs to generate static pressure, total pressure, total temperature and differential pressure outputs. These are processed by the GN&C computer to compute airspeed, angles of attack, etc.

ADS Simulation Module Description and Performance Parameters

We assume that the ADS simulation module will provide a high-fidelity simulation of ADTA self-test and operate mode outputs and a time-delay simulation of probe deployment and retraction, will allow for various internal failure modes, and will respond properly to variations in simulated bus voltages.

Figure 4.7-91 is an overview of ADS simulation module interfaces. Table 4.7-25 provides an ADS module parameter list.

ADS Reference Data Sources and Data Formats

The ADS reference module discussed in this section provides a simulation of the nominal operation of the air data probes and the ADTA, and sets discretes for probe deploy/retract and heaters without any detail simulation. The individual hardware elements of the air data system are not modelled in this reference module.
FIGURE 4.7-89 AIR DATA SYSTEM FUNCTIONAL CONFIGURATION (ORBITER 103)

FIGURE 4.7-90 INTERNAL ADTA FUNCTIONAL CONFIGURATION
<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DEFINITION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>- -</td>
<td>Command for self-test mode or operation mode</td>
<td>I</td>
</tr>
<tr>
<td>T&lt;sub&gt;0&lt;/sub&gt;, P&lt;sub&gt;0&lt;/sub&gt;</td>
<td>Ambient air temperature and pressure</td>
<td>I</td>
</tr>
<tr>
<td>M</td>
<td>Mach number</td>
<td>I</td>
</tr>
<tr>
<td>α, β, V&lt;sub&gt;a&lt;/sub&gt;</td>
<td>Angle-of-attack angle-of-sideslip and airspeed</td>
<td>I</td>
</tr>
<tr>
<td>- -</td>
<td>ADTA self-test values for P&lt;sub&gt;si&lt;/sub&gt;, P&lt;sub&gt;ti&lt;/sub&gt;, T&lt;sub&gt;ti&lt;/sub&gt;, ΔP&lt;sub&gt;i&lt;/sub&gt;, and mode/status</td>
<td>DB</td>
</tr>
<tr>
<td>θ</td>
<td>Temperature sensor recovery factor</td>
<td>DB</td>
</tr>
<tr>
<td>✓</td>
<td>Specific heat ratio for air</td>
<td>DB</td>
</tr>
<tr>
<td>P&lt;sub&gt;so&lt;/sub&gt;, P&lt;sub&gt;to&lt;/sub&gt;, T&lt;sub&gt;to&lt;/sub&gt;</td>
<td>Ideal probe values of static pressure, total pressure and total temperature</td>
<td>P</td>
</tr>
<tr>
<td>ΔP</td>
<td>Ideal probe differential pressure (function of vehicle aerodynamics)</td>
<td>P</td>
</tr>
<tr>
<td>δP&lt;sub&gt;si&lt;/sub&gt;, δP&lt;sub&gt;ti&lt;/sub&gt;, δΔP&lt;sub&gt;i&lt;/sub&gt;</td>
<td>Changes in ideal probe values due to vehicle dynamics</td>
<td>P</td>
</tr>
<tr>
<td>εP&lt;sub&gt;si&lt;/sub&gt;, εP&lt;sub&gt;ti&lt;/sub&gt;, εT&lt;sub&gt;ti&lt;/sub&gt;, εΔP&lt;sub&gt;i&lt;/sub&gt;</td>
<td>ADTA hardware errors</td>
<td>P</td>
</tr>
<tr>
<td>P&lt;sub&gt;si&lt;/sub&gt;</td>
<td>Indicated static pressure (divided into most significant and least significant words)</td>
<td>CP</td>
</tr>
<tr>
<td>P&lt;sub&gt;ti&lt;/sub&gt;</td>
<td>Indicated total pressure</td>
<td>CP</td>
</tr>
<tr>
<td>T&lt;sub&gt;ti&lt;/sub&gt;</td>
<td>Indicated total temperature</td>
<td>CP</td>
</tr>
<tr>
<td>ΔP&lt;sub&gt;i&lt;/sub&gt;</td>
<td>Indicated pressure differential</td>
<td>CP</td>
</tr>
<tr>
<td>- -</td>
<td>ADTA Operational Mode and Status flag</td>
<td>O</td>
</tr>
<tr>
<td>- -</td>
<td>Power-on discrete from ADTA</td>
<td>O</td>
</tr>
<tr>
<td>- -</td>
<td>Probe heater status discrete</td>
<td>O</td>
</tr>
<tr>
<td>- -</td>
<td>Probe deploy/retract status discrete</td>
<td>O</td>
</tr>
</tbody>
</table>

<sup>a</sup>LEGEND:  
I = input  
DB = data base input  
O = output  
P = performance parameter  
CP = critical performance parameter
ENVIRONMENT MODULE

temperature, pressures, mach number, angles of attack and sideslip

ADS MODULE

electrical power

deploy/retract, self-test data and status
deploy/retract, self-test, and operate commands
self-test data and status
pressure, temperature and differential pressure data

MDM

GN&C COMPUTERS

FIGURE 4.7-91. ADS MODULE INTERFACES

REPRODUCIBILITY OF THE ORIGINAL PAGE IS POOR
solving of hardware errors is to be accomplished by means of "generalized solutions" (table lookups, polynomials, etc.), based upon hardware test data.

The math flow for module CKADS, as shown in Fig. 4.7-38, is initialized with constant parameters from the data base, and driven by checkpoint data provided either by an on-line driver routine or accessed from a predefined data file. It has two basic paths: one for the self-test mode, and one for the operate mode.

Self-Test Mode - The ADS reference module simulates the ADTA self-test mode, normally initiated by the GN&C computer. Generation of reference verification data for the self-test mode is accomplished by simply setting the ADTA output to the values expected by the GN&C computer for a nominal status.

Operate Mode - The operate mode simulates the functional situation in which dynamic sensor data is supplied to the GN&C computer for processing. Generation of the ADTA output during this mode is accomplished by exercising Equations (1) through (9) of Figure 4.7-92, discussed in the following paragraph.

Equations (10), (11), and (12) provide the ideal values for total temperature \( T_t \), static pressure \( P_s \), and total pressure \( P_t \), as measured by the air data probes. The equations presented are developed, using fundamental dynamics and thermodynamics of air, in Reference 47.

\[
T_t = T_0 (1.0 + \frac{\gamma-1}{2} \cdot \frac{T_0}{T_0+M^2}) \\
P_t = P_0 \\
P_s = P_0 \left[ (1.0+\frac{\gamma-1}{2} \cdot \frac{T_0}{T_0+M^2}) \right]^{\gamma-1} \\
P_t = P_0 \left[ (1.0+\frac{\gamma-1}{2} \cdot \frac{T_0}{T_0+M^2}) \right]^{\gamma-1} \times \left[ (10+\gamma) \cdot \frac{T_0}{T_0+M^2} \right]^{\gamma-1} \text{ for } M \leq 1 \\
P_t = P_0 \left[ (10+\gamma) \cdot \frac{T_0}{T_0+M^2} \right]^{\gamma-1} \times \left[ (10+\gamma) \cdot \frac{T_0}{T_0+M^2} \right]^{\gamma-1} \text{ for } M > 1
\]

Note that the probes are assumed to be located in the free stream ahead of any shock wave, and the temperature sensor is assumed to measure full adiabatic temperature increase within the recovery factor \( \eta \). Equations (10), (11), and (12) are for airflow axial along the probes, and will not provide the correct measurement when the incident flow is not axial. They are typical calibration equations; by addition of correction terms dependent on vehicle parameters such as angle of attack, angle of sideslip, and airspeed, representative ideal values for \( P_s \), \( P_t \), and \( T_t \) can be achieved for all vehicle states. The additive
FIGURE 4.7-92 AIR DATA SYSTEM REFERENCE DATA MODULE
functions indicated by $S$ in Equations (1), (2), and (3) of Figure 4.7-92 are derived from test data.

The differential pressure parameter ($\Delta P$), is a function of vehicle dynamics and airflow around the probe, with the functional form heavily dependent on probe design and location on the vehicle. For the reference module, the ideal $\Delta P$ is modeled using design and test data. (The flight software will contain an algorithm for converting $\Delta P_1$ into sensed angles of attack; this algorithm will be essentially the inverse of the reference module algorithm.)

The ideal inputs to the ADTA thus obtained are then degraded due to non-ideal operation of the hardware. Typically, hardware errors can be divided into two classes: those which are compensated for in the software accepting the data, and those not compensated for and thereby introduced into the system. Since the GN&C flight software will likely perform compensation for certain hardware characteristics, both types should be introduced to the ideal data. The reference module discussed here provides all hardware errors as additive terms ($E$) to the ideal values. The hardware error functions are determined using design and test data.

The final output performance parameter, the mode/status flag, is assigned the appropriate value for nominal system operation. Since operate and self-test values may differ, the parameter appears in both paths of Figure 4.7-92.

**ADS Module Validation Methods and Check Cases**

ADS module validation is performed by driving both the simulation module and the reference module with corresponding input data. Check-case data required by the reference module are as follows:

- **Power-off Data Check** - The power off checkpoint is to verify that the power-off condition for the ADTA results in proper power-off output data. This single check point need not be built in to the reference module.

4.7-279

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
- Self-Test Data Check - The self-test check point is to verify the ADTA output in response to self-test commands. The reference output for this check point will consist of stored test words identical to those existing in the GN&C computer for verification of the ADTA status. The reference module input needs only the mode parameter to specify the self-test condition.

- Operate Data Check - This check consists of a series of check points chosen to verify the system output over its normal range of use. The reference data for this check is generated by a parametric variation of the inputs \( P, T, \alpha, \beta \) etc. used in the calculation of the performance parameters. The appropriate parameter variations are selected based on performance specifications for the air data system and the vehicle.

The simulation module, being more directly hardware-oriented, will require additional input data (see Table 4.7-25) for proper operation.

In addition to the discrete check points, the appropriate input values to the reference module may be stored along with resulting simulation module outputs from a simulation run. The verification executor can then access the data to drive the reference module and generate data for comparison with the stored simulation data. However, care should be used in utilizing this option. Since the reference module does not simulate all the air data system hardware-related effects (e.g., malfunctions, voltage and temperature variations), the simulation data must be in the nominal operational regime to be directly comparable.

For nominal operation, reference/simulation data agreement should be within a few percent for moderate mach numbers and angles of attack, during steady flight. Discrepancies of ten percent or greater would not be unreasonable at high mach numbers or high angles of attack, during turbulence or high-g maneuvers.

**ADS Data Base Impact**

The parameters and functions indicated on Figure 4.7-92 as input through the data base must be available to the reference module from mass storage. Table 4.7-26 presents the individual data base items, with an indication of the data source and added comments on the type of data.
TABLE 4.7-26 REFERENCE MODULE DATA BASE SOURCE LIST

<table>
<thead>
<tr>
<th>ITEM</th>
<th>SOURCE</th>
<th>COMMENT</th>
</tr>
</thead>
<tbody>
<tr>
<td>self-test values</td>
<td>Air Data Subsystem Vendor</td>
<td>Nominal Values indicating a &quot;GO&quot; status</td>
</tr>
<tr>
<td>γ</td>
<td>Reference Simulation Standards</td>
<td>Assigned Reference Value (e.g., 1.40 for air)</td>
</tr>
<tr>
<td>η</td>
<td>Air Data Subsystem Vendor</td>
<td>From Design or Test Data</td>
</tr>
<tr>
<td>( \Delta P_s, \Delta P_t )</td>
<td>Air Data Subsystem Vendor</td>
<td>Predicted static error data from design studies</td>
</tr>
<tr>
<td>( \Delta P_s, \Delta P_t )</td>
<td>Vehicle Vendor</td>
<td>From Wind Tunnel or Flight Test Data</td>
</tr>
</tbody>
</table>

The complicated nature of the airflow functions \( \Delta P_s, \Delta P_t \), and \( \Delta P \) warrants the use of flight test data when available. Wind tunnel data or predicted values will in general provide only trend data, but should be used until flight test data becomes available. However initially obtained, the airflow functions should be updated upon the availability of flight test data to ensure a valid simulation.

For all test data items, it is important that configuration control procedures be utilized to maintain up-to-date data base information. Reference module data base updates would result from system modifications and from the availability of more reliable data through program advances. When such updates are incorporated into the reference module, a reverification of the simulator air date module would be undertaken. If it is found that the simulator module is no longer valid with respect to the updated data, simulator management would then be informed.
4.7.5.2 Communications and Tracking (C&T) Subsystem

The C&T subsystem provides capabilities for transmission of information and/or commands and determination of relative state variables between the Orbiter and (a) ground-based facilities (see Section 4.3.2.1) and (b) payloads and rendezvous targets (see Section 4.3.2.2). Orbiter/payload communication and tracking is performed during the on-orbit mission phase; Orbiter/ground communication and tracking may be performed during any mission phase - except for a short period of communications "blackout" during entry.

C&T Subsystem Description

The block diagram of Figure 4.7-93 (Ref. 36) provides an overview of the C&T subsystem. This subsystem includes several types of components:

- receivers, transmitters and transponders
- record/playback equipment
- data handling and distribution equipment (e.g., signal processors, coders, data interleavers, switching systems)
- antennas
- manual control and display interfaces
- flight computer interfaces

Component specifications (Refs. 49 through 58) provide detailed information relating to many of these components; specifications for other components have not yet been identified.

C&T Module Description and Performance Parameters

The C&T subsystem simulation module will consist of a number of submodules. Each such submodule will provide the operational modes and performance parameters of one of the basic hardware components of the C&T subsystem, model appropriate hardware errors, and allow for the insertion of simulated malfunctions.

Table 4.7-27 gives a list of performance parameters for the C&T simulation module.

Figure 4.7-94 shows the C&T module interfaces. Definition of the interface with the artificial environment module requires some assumptions about the software design. We have assumed that, for maximum module independence, each of these modules will require a minimum of information about the other. For example, the ground nav/comm module will compute the line-of-sight (LOS) to the Orbiter (as seen from the ground), in its own axis set, and use the ground-antenna gain pattern to compute its transmitted signal strength along that LOS. The onboard C&T
FIGURE 4.7-93 COMMUNICATIONS AND TRACKING SUBSYSTEM BLOCK DIAGRAM
**TABLE 4.7-27. COMMUNICATIONS AND TRACKING SIMULATION MODULE PARAMETERS**

<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DESCRIPTION</th>
<th>TYPEa</th>
</tr>
</thead>
<tbody>
<tr>
<td>$R_{SE}$</td>
<td>Ground station coordinates (earth-fixed axes)</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Ground station identification tags</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Ground station transmitting frequencies</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Line-of-sight contact flags</td>
<td>I</td>
</tr>
<tr>
<td>$r, v$</td>
<td>Orbiter position and velocity (ECI axes)</td>
<td>I</td>
</tr>
<tr>
<td>$\delta r, \delta v$</td>
<td>Target relative position and velocity (ECI or orbital axes)</td>
<td>I</td>
</tr>
<tr>
<td>$\phi, \theta, \psi$</td>
<td>Orbiter attitude, I</td>
<td>I</td>
</tr>
<tr>
<td>$h$</td>
<td>Orbiter altitude (above local terrain)</td>
<td>I</td>
</tr>
<tr>
<td>$r_s, \dot{r}_s$</td>
<td>Station range and range rate</td>
<td>I</td>
</tr>
<tr>
<td>$A_{ZS}, E_S$</td>
<td>Station azimuth, elevation</td>
<td>I</td>
</tr>
<tr>
<td>$r_T, \dot{r}_T$</td>
<td>Target range and range rate</td>
<td>I</td>
</tr>
<tr>
<td>$S_{ST}, S_{ST}$</td>
<td>Transmitted signal strength from ground station, target</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Incoming and outgoing data/command streams</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td>Onboard antenna gain patterns DB</td>
<td>DB</td>
</tr>
<tr>
<td>$u_s, u_T$</td>
<td>Line-of-sight to station, target (body axes)</td>
<td>P</td>
</tr>
<tr>
<td>$S_{SR}, S_{ST}$</td>
<td>Received signal strength from station, target</td>
<td>P</td>
</tr>
<tr>
<td>$S_T$</td>
<td>Transmitted signal strength to ground station or target</td>
<td>P</td>
</tr>
<tr>
<td>$D_c$</td>
<td>Measured doppler counts</td>
<td>CP</td>
</tr>
<tr>
<td>$h_{ra}$</td>
<td>Measured radar altitude</td>
<td>CP</td>
</tr>
<tr>
<td>$r_s, \dot{r}_s$</td>
<td>Measured range to station, target</td>
<td>CP</td>
</tr>
<tr>
<td>$A_{ZS}, E_S$</td>
<td>Measured station-referenced azimuth, elevation</td>
<td>CP</td>
</tr>
<tr>
<td>$\theta_T, \dot{\theta}_T$</td>
<td>Measured target angle and angular rate</td>
<td>CP</td>
</tr>
</tbody>
</table>

a**TYPE:**

- I = input
- DB = data base input
- P = performance parameter
- CP = critical performance parameter
FIGURE 4.7-94. COMMUNICATIONS & TRACKING MODULE INTERFACES
module will compute the LOS to the ground antenna (as seen from the Orbiter), in its body-axis set, and then use the onboard antenna gain pattern and the transmitted signal strength to compute its received signal strength along that LOS. Thus, each module will need to know its own antenna patterns, but neither module will need to know the other's antenna patterns. In addition, each module will need to output various flags and tags to inform the other which ground facilities are active and in view, which onboard subsystems are active, etc.

The Shuttle Mission Simulator, which is sometimes used in integrated operations with Mission Control, must provide the capability to provide a simulated telemetry stream -- realtime and/or recorder data-dump. This will require the C&T module to have telemetry simulation modes, in which properly-formatted mass-storage files are generated during simulator operations, then dumped over an appropriate communication channel upon commands received via the Mission Control communication link.

C&T Reference Data Sources and Data Formats

Figure 4.7-95 shows the math flow and variable definition for a module (CHKCMT) to generate reference data for validation of the C&T simulation module. The equations shown in this figure are derived in Ref. 59. Geometry calculations necessary to compute range, range rate, bearing, etc. are performed in terms of coordinate systems as shown in Figure 4.7-96; (see Ref. 60). In some cases, complete information required for equation development is not yet available, and computations are shown as generalized functions. These generalized functions may be implemented in computational form, or via table lookup, polynomial fit, etc., as the required data becomes available during the course of the Shuttle program. Status discretes and other secondary parameters are assumed set to their nominal operational values, and are not represented on the math flow.

Note that this reference module is designed for initial validation of the C&T module, and includes computations which will actually be performed by the artificial environment module. A simpler reference module will be appropriate for integrated validation of the C&T and artificial environment modules.

Command parameters (e.g., switching, data-dump) normally generated by manual controls, flight computers, or ground command must be provided by an external driver and/or manual data input to the reference module, in a format matching their
\[ r_{si} = \frac{a_e}{(1 - ee^2 \sin^2 \phi_{si})^{1/2}} \]

\[
RSE = \begin{bmatrix}
(r_{si} + h_{si}) \cos \phi_{si} \cos \lambda_{si} \\
(r_{si} + h_{si}) \cos \phi_{si} \sin \lambda_{si} \\
[(1 - ee^2) r_{si} + h_{si}] \sin \phi_{si}
\end{bmatrix}
\]

\[
T_1 = \begin{bmatrix}
-\sin \lambda_{si} - \sin \phi_{si} \cos \lambda_{si} \\
\cos \lambda_{si} - \sin \phi_{si} \sin \lambda_{si} \\
0 & \cos \phi_{si} & \sin \phi_{si}
\end{bmatrix}
\]

\[
T_2 = \begin{bmatrix}
\cos \omega t - \sin \omega t & 0 \\
\sin \omega t & \cos \omega t
\end{bmatrix}
\]

\[
T_3 = \begin{bmatrix}
\sin \omega t & \cos \omega t & 0 \\
-cos \omega t & \sin \omega t & 0 \\
0 & 0 & 1
\end{bmatrix}
\]

\[ R_{SI} = T_2 RSE \]

\[ R_{SI} = -\omega T_3 RSE \]
\[ RL = T_1^T [T_2^T R_V - R_{SE}] \]

\[ AZS = \tan^{-1} \frac{X_L}{Y_L} \]

\[ ES = \tan^{-1} \frac{Z_L}{\sqrt{X_L^2 - Y_L^2}} \]

\[ RS = \frac{(R_V - R_{SI}) \cdot (R_V - R_{SI})}{r_S} \]

\[ \dot{R}_S = \frac{R_V \cdot \dot{R}_V + R_{SI} \cdot \dot{R}_{SI} - R_V \cdot \dot{R}_{SI} - R_{SI} \cdot \dot{R}_V}{r_S} \]

\[ r_V = (R_V \cdot \dot{R}_V)^{1/2} \]

\[ \sin \psi = \frac{Z}{r_V} \]

\[ \cos \psi = \frac{(x^2 + y^2)^{1/2}}{r_V} \]

\[ r_e = \frac{a_e}{\sqrt{(1 + e^2 \sin^2 \psi)^{1/2} - e^2 \cos^2 \psi}} \]

\[ \delta = \frac{e e^2 \sin \psi \cos \psi}{1 - e^2 \cos^2 \psi} \]

\[ \xi = \frac{r_e \delta}{r_V} \]

\[ h = (r_V - r_e) \left( 1 - \frac{1}{26 \xi} \right) \]

**FIGURE 4.7-95: (CONTINUED)**
YES

RLB = B(RV-RSI)
SST = f1(RLB)
SSR = f2(RLB)

NO

YES

S-BAND GROUND STATION TRACKING

NO

YES

RADAR ALTIMETER

CALCULATE h USING TERRAIN MODEL

NO

RETURN

FIGURE 4.7-95 (CONTINUED)
YE
STDRS NO (DEZ!%IDUS)

\[
\begin{align*}
R LB &= B RV - RT \\
S SR &= B L B \\
S ST &= B L B
\end{align*}
\]

RETURN

FIGURE 4.7-95 (CONTINUED)

RETURN

TDRS

YES

\[
T = \frac{1}{\text{RV} \cdot \text{RV} - \dot{R} T \cdot \text{RT} \cdot \dot{R} T} \cdot \left( \text{RV} - \dot{R} T \right)
\]

NO (RENDVZOUS)

CALCULATE \( \dot{R} \)

FOR RENDEZVOUS RADAR

MCD E1201
30 December 1974

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
**LEGEND**

<table>
<thead>
<tr>
<th>SYMBOL</th>
<th>DEFINITION</th>
</tr>
</thead>
<tbody>
<tr>
<td>i</td>
<td>Pass number</td>
</tr>
<tr>
<td>$\phi_s$</td>
<td>Ground station latitude</td>
</tr>
<tr>
<td>$\lambda_s$</td>
<td>Ground station longitude</td>
</tr>
<tr>
<td>$h_s$</td>
<td>Ground station altitude</td>
</tr>
<tr>
<td>N</td>
<td>Number of Ground stations to be verified</td>
</tr>
<tr>
<td>ae</td>
<td>Earth semimajor axis</td>
</tr>
<tr>
<td>ee</td>
<td>Earth eccentricity</td>
</tr>
<tr>
<td>$\omega_t$</td>
<td>Angle between vernal equinox and Greenwich Meridian (Note: t depends on time of reference frame initialization)</td>
</tr>
<tr>
<td>$\omega$</td>
<td>Earth rotation rate</td>
</tr>
<tr>
<td>$f_1$</td>
<td>Function relating Doppler counts to range rate (Ground Transmission)</td>
</tr>
<tr>
<td>$f_2$</td>
<td>Function relating antenna transmitted signal strength to line of sight (vehicle to ground station)</td>
</tr>
<tr>
<td>$f_3$</td>
<td>Function relating antenna received signal strength to line of sight (ground station to vehicle)</td>
</tr>
<tr>
<td>$f_4$</td>
<td>Function relating antenna transmitted signal strength to line of sight (vehicle to TDRS)</td>
</tr>
<tr>
<td>$f_5$</td>
<td>Function relating antenna received signal strength to line of sight (TDRS to vehicle)</td>
</tr>
</tbody>
</table>

**FIGURE 4.7-95 (CONCLUDED).**
intended operational format in the eventual integrated-simulator environment. A pseudo-data stream should also be provided to verify proper transfer of telemetry data.

Note that, to simplify the reference module logic, values for azimuth, elevation, range and range rate are computed for all ground station types, even though not needed in every case; e.g., elevation angle and range rate are not used for TACAN stations.

C&T Validation Methods and Check Cases

In accordance with the basic validation software structure described in Section 5.1, Figure 4.7-97 provides the math flow for a checkpoint-generation routine to be used in C&T module validation. This routine will provide, in addition to discretes for selection of operational modes, ground stations and TDRS satellites, the following vehicle-dynamics-related data:

\[ \mathbf{X} = (X, Y, Z, \dot{X}, \dot{Y}, \dot{Z}) = \text{shuttle state vector} \]

\[ \mathbf{X}_t = (X_t, Y_t, Z_t, \dot{X}_t, \dot{Y}_t, \dot{Z}_t) = \text{rendezvous-target state vector} \]

\[ \mathbf{B} = 3 \times 3 \text{ coordinate transformation matrix} \]

\[ T = \text{universal time} \]

The logic of this driver routine provides for exercising the linkage between the Orbiter and every ground facility, as well as varying the relative position and velocity over the entire range of operational interest. For initial validation, synthetic state vectors will be used. Later, when a vehicle dynamics module becomes available, integrated validation will make use of realistic trajectories which pass into and through the regions of ground-station and payload contact.

C&T Validation Data Base Impact

The data base contributions for C&T module validation will include the reference module, the checkpoint-generation routine, ground-station tables, antenna-pattern functions or tables, and temporary files of checkpoint inputs and outputs.

The reference module and checkpoint-generation module are both fairly simple, and will impose little storage load. The ground-station table may be fairly extensive (dozens or hundreds of stations, depending upon Shuttle operational rules), but will be common to the simulator data base rather than in addition to 4.7-292.
XI - Through the Vernal Equinox of Reference
YZ - 90° East in the Equatorial plane
ZI - Through the North Pole
XE - Through the Greenwich Meridian
YE - 90° East in the Equatorial plane
ZE - Through the North Pole
XL - East through the station location in the Earth tangential plane
YL - North through the station location in the Earth tangential plane
ZL - Up through the station location along the geodetic vertical

4.7-293
MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-97 COMMUNICATIONS AND TRACKING CHECKPOINT-GENERATION MATH FLOW.
it. The antenna-pattern data, if maintained in tabular rather than functional form, will also be extensive, but should also be common to the simulator. The extent of the checkpoint files will vary with the resolution desired for comparison plots, and in any event, these files need not be maintained after initial validation is completed. Overall, the data base impact for C&T module validation should be minor.
4.7.5.3 Controls and Displays (C&D)

The controls and displays group includes subsystems and components involved in the presentation of information to the flight crew and flight crew control of the Shuttle vehicle and its various onboard systems. It also includes the Master Events Controller (MEC), which transfers discrete commands from the flight computer to various pyrotechnic devices.

Controls and displays will be discussed in four categories: timers (including the MEC), artificial feel system, miscellaneous display interfaces, and miscellaneous control interfaces. Flight-computer CRT/keyboard units are excluded from this discussion, on the assumption that they will be implemented using flight hardware on the simulators of interest.

This discussion will be brief, since C&D software requirements are minor, and much of their validation will be done in an integrated rather than isolated-module configuration:

C&D Subsystem Description

Timers and MEC - This category includes the Master Timing Unit (MTU), the event timer, and the MEC.

The MTU (Ref. 61), based on a crystal-controlled oscillator, provides (a) stable frequency outputs for use by various Orbiter subsystems and payloads, and (b) serial time code outputs for subsystems including computers, data acquisition systems, recorders, displays and attached payloads. It includes separate time accumulators for Greenwich Mean Time and Mission Elapsed Time, which can be set or updated by external control.

The Event Timer (Ref. 62) is used by the crew in execution of maneuvers and other onboard procedures. It accepts and counts timing pulses from the MTU (or a backup internal source), and generates a numeric display. Operational modes are count-up, count-down, reset, preset, and override.

The MEC (Ref. 63) recognizes two types of discrete commands output by the flight computer: critical and non-critical. Critical command words must be
transmitted by all four computers to be acted upon; non-critical words may be received from any individual flight computer. Command words are then decoded and addressed to the proper pyro initiator controller (PIC), to perform such actions as SRB initiation, SRB or ME separation, etc.

Artificial Feel System - The artificial feel used on Orbiter manual controls consists of simple spring resistance and no software input is required.

Miscellaneous Display Interfaces - The Orbiter crew station panels include a great number of displays, some of which are described in Refs. 64 - 66. These displays provide visual and/or aural information of a discrete (events, anomalies) or continuous nature (range, altitude, air-speed, etc.) to the crew. Some of this information comes directly from onboard sensors, some is generated by flight computers. In some cases, the display interface simply buffers and formats the raw data; in other cases, software compensation for sensor and display calibration is provided.

The caution and warning (C&W) status display incorporates crew-settable switches to select channels, change alarm limits, suppress alarm indications, etc.

Miscellaneous Control Interfaces - Orbiter crew station panels also incorporate a number of controls -- hand controllers, switches, circuit breakers, etc. These controls enable the crew to input discrete (e.g., arm drag chute) and continuous (e.g., aerosurface, thruster) commands to control the vehicle. The control interface hardware and software merely buffers and decodes these control inputs for use by the flight computer.

C&D Module Description and Performance Parameters

Timers and MEC - Timer functions will be simulated using the basic simulator central clock (either within the host computer or external hardware) as a timing source. The event timer will require a simple software module, which will accept mode-select commands from the crew panel. The MEC software module will just provide delayed-time talkback of non-critical discretes; its method of voting critical discretes will depend upon how flight-computer redundancy is implemented in the various simulators.
Miscellaneous Display Interfaces - The display interface software will perform simple buffering, formatting and scaling of signals from the host computer. Some meters may require compensation-curve processing, based upon periodic calibration data.

The caution and warning status display, if flight hardware, will interface directly with the flight computer. If implemented as simulator hardware, it will require flight-computer data conversion by means of software in the host and/or the FEID. An interface with the aural simulation hardware will also be required to generate tone, klaxon and siren outputs, used to indicate mission-critical anomalies.

Miscellaneous Control Interfaces - The control interface software will simply buffer, format and scale discrete and continuous control inputs for the host and/or FC/FEID.

Summary - Figure 4.7-98 depicts the C&D simulation module interfaces. Table 4.7-28 lists the C&D simulation module parameters.

C&D Reference Data Sources and Data Formats

The basic sources of reference data are the specifications of the onboard systems, and of the simulator hardware and software for the particular simulator of interest. The simple C&D software modules just perform a simulator-peculiar mapping of inputs to outputs -- e.g., discrete input #xxx is delayed for ttt seconds and becomes discrete output #yyy; so much controller motion maps into so many degrees of aerosurface deflection.

C&D Validation Methods and Check Cases

The bulk of the C&D validation is performed on the integrated simulator. Preliminary validation of discrete-data handling would be done by means of an external driver and a command/response "dictionary." Preliminary validation of continuous-data handling would be performed by providing sampled inputs over the specified range (e.g., the input to a particular meter), generating a data plot to be compared to the meter calibration curve.
FIGURE 4.7-98. CONTROLS AND DISPLAYS MODULE INTERFACES
<table>
<thead>
<tr>
<th>DESCRIPTION</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Hand-controller and rudder pedal deflections</td>
<td>I</td>
</tr>
<tr>
<td>Manual switch actions</td>
<td>I</td>
</tr>
<tr>
<td>Flight computer discretes</td>
<td>I</td>
</tr>
<tr>
<td>Flight computer continuous data</td>
<td>I</td>
</tr>
<tr>
<td>Avionics data: MSBLS, TACAN, IMU gimbals, etc.</td>
<td>I</td>
</tr>
<tr>
<td>Aerodynamic and runway velocities</td>
<td>I</td>
</tr>
<tr>
<td>Sensor and instrument scaling and calibration data</td>
<td>DB</td>
</tr>
<tr>
<td>Aerosurface deflection commands (manual)</td>
<td>P</td>
</tr>
<tr>
<td>Avionics mode and channel-select commands</td>
<td>P</td>
</tr>
<tr>
<td>Thrust commands (manual)</td>
<td>P</td>
</tr>
<tr>
<td>Displayed times: GMT, MET, event</td>
<td>P</td>
</tr>
<tr>
<td>Display discretes: C&amp;W, channel set, etc.</td>
<td>P</td>
</tr>
<tr>
<td>Instrument drive signals</td>
<td>P</td>
</tr>
<tr>
<td>C&amp;W panel settings: inhibits, limits, etc.</td>
<td>P</td>
</tr>
<tr>
<td>Discrete talkbacks</td>
<td>P</td>
</tr>
</tbody>
</table>

<sup>a</sup>TYPE - I = input

DB = data base input

P = performance parameter
C&D Validation Data Base Impact

Very little on-line storage is required for validation of the C&D module, which requires no reference module as such. The on-line data base will consist of some short command/response dictionaries, a few calibration curves, and a simple external driver module.
4.7.5.4 Operational Instrumentation (OI)

The OI subsystem provides the telemetry processing and caution and warning (C&W) functions on the Shuttle Orbiter. The telemetry processing function consists of data buffering, scaling and formatting, and control of onboard recording, recorder dumping, and real-time telemetry to the ground network. The caution and warning function consists of buffering, filtering and gating data, and generating display messages in response to detected anomalies.

These functions are all implemented in flight software in the Orbiter flight computers, and will thus require no simulation software in the simulators of interest, which will incorporate flight computer hardware. In the SMS, which simulates most onboard subsystems in high fidelity, OI implementation will require the subsystem simulations to provide realistic values for such performance-correlated variables as temperatures, voltages, and various operational discretes -- over and above a correct representation of subsystem functions. In the SPS and OAS, we expect little or no implementation of OI functions, and much-simplified representation of most onboard subsystems.

The telemetry and maintenance recorders are discussed under C&T (Section 4.7.5.2), and the C&W displays under Controls and Displays (Section 4.7.5.3).
4.7.5.5 Electrical Power Distribution and Control

The Electrical Power Distribution and Control (EPD&C) subsystem provides the means of conditioning and transfer of electrical energy from the fuel cells or ground support equipment (GSE) umbilicals to the various systems electrical equipment. In addition, the subsystem includes external vehicle illumination. This section provides a discussion of the subsystem components, module performance parameters, reference data sources, validation methods, and impact to the simulation data base.

EPD&C Subsystem Description

Figure 4.7-99 is a schematic of the EPD&C subsystem. The means of energy transfer is a network of bus bars which are connected by electrical cables, power relays, solid state power controllers, fuses, etc. This network of buses includes:
- 3 main buses
- 3 essential (critical) control buses
- 3 forward local buses
- 3 midsection local buses
- 3 aft section local buses
- 3 AC 3-phase buses (powered by 3 inverters)

The three main buses can be individually interconnected by a tie bar which also allows connection of the tie bar to GSE power via the nose-wheel umbilical. The three aft local buses can be individually connected to GSE power via the aft GSE power umbilical. The three aft local buses can also be connected together via a tie bar. The 3-phase AC buses can also be electrically connected by tie bars.

The illumination system block diagram is presented in Figure 4.7-100. The exterior lighting is controlled by manual switching. The lighting includes landing, navigational, anti-collision, rendezvous, docking, manipulator, payload and camera lights.

EPD&C Module Description and Performance Parameters

The Figure 4.7-101 schematic illustrates the EPD&C module interfaces with the other modules and shows the functional elements within the module. The performance parameters of the module are listed in Table 4.7-29. The module functional elements provide the following calculations:

4.7-303
FIGURE 4.7-99. ELECTRICAL POWER DISTRIBUTION AND CONTROL-SUBSYSTEM SCHEMATIC
FIGURE 4.7-100. ILLUMINATION SUBSYSTEM SCHEMATIC

- FLIGHT DECK PANELS INSTRUMENTS
- MID-DECK PANELS INSTRUMENTS
- FLIGHT DECK
- MID-DECK
- AIRLOCK/DOCK MOD
- LANDING
- MANIPULATOR
- PAYLOAD
- CAMERA SPOTLIGHT
- RENDEZVOUS
- DOCKING LIGHTS
- NAVIGATION
- ANTI-COLLISION
- FLIGHT-DECK
- MID-DECK
- AIRLOCK/DOCK MOD
- FLIGHT DECK
- MID-DECK
FIGURE 4.7-101. ELECTRICAL POWER DISTRIBUTION AND CONTROL MODULE ELEMENTS AND INTERFACES.
### TABLE 4.7-20. EPD&C PERFORMANCE PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Switch position, selections, etc.</td>
<td>I</td>
</tr>
<tr>
<td>Equipment operating modes, on/off</td>
<td>I</td>
</tr>
<tr>
<td>FC electrical outputs - (Norton's equivalent current, admittance)</td>
<td>I</td>
</tr>
<tr>
<td>GSE electrical outputs - (Norton's equivalent current, admittance)</td>
<td>I</td>
</tr>
<tr>
<td>Equipment temperatures</td>
<td>CP</td>
</tr>
<tr>
<td>Bus voltages</td>
<td>P</td>
</tr>
<tr>
<td>Load voltages</td>
<td>CP</td>
</tr>
<tr>
<td>Bus currents</td>
<td>P</td>
</tr>
<tr>
<td>Load currents</td>
<td>P</td>
</tr>
<tr>
<td>Bus distribution admittances</td>
<td>P</td>
</tr>
<tr>
<td>Load admittances</td>
<td>P</td>
</tr>
<tr>
<td>External illumination light operating modes</td>
<td>P</td>
</tr>
<tr>
<td>Power interruption devices - total current</td>
<td>CP</td>
</tr>
<tr>
<td>- overload trip time</td>
<td>P</td>
</tr>
<tr>
<td>- device open</td>
<td>P</td>
</tr>
</tbody>
</table>

<sup>a</sup> **TYPE:**

- CP = critical parameter
- P = performance parameter
- I = input
• Loads - determine the admittance values of each load as functions of operating mode, input voltage, and temperature.
• Control logic - determines enabling/disabling selection logic from the control inputs.
• AC inverter - calculates:
  -- Inverter AC load - determines inverter load-phase as functions of AC voltage, mode selected temperatures.
  -- Inverter efficiency - this is a function of inverter temperature, AC load, and input DC voltage.
  -- Equivalent DC load - a function of inverter efficiency and inverter AC load.
• Distribution resistances - calculates the bus network distribution resistances as functions of the control logic, and bus voltages.
• Distribution voltages and currents - calculates bus and load voltages and currents as functions of the fuel cell current/admittance, load admittances, and distribution network resistances.
• Power interruption - sums current through the power interruption devices, determines overload conditions, integrates overload time, and sets logic indicating power line open.
• External illumination - determines light operating mode and on/off condition from control logic and bus voltages.

EPD&C Reference Data Sources and Formats
The component design performance requirements, performance predictions, test results, and flight vehicle performance results can be used as reference data for direct comparison with simulation results. Reference 31 is specifically intended to provide data of this type. Component design requirements are defined in the following Rockwell International documents:

<table>
<thead>
<tr>
<th>COMPONENT</th>
<th>SPECIFICATION</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fuses</td>
<td>MC451-0010</td>
</tr>
<tr>
<td>Thermal circuit breakers</td>
<td>MC454-0026</td>
</tr>
<tr>
<td>Remote control circuit breakers</td>
<td>MC454-0027</td>
</tr>
<tr>
<td>Remote power controller</td>
<td>MC450-0017</td>
</tr>
<tr>
<td>AC inverters</td>
<td>MC495-0012</td>
</tr>
</tbody>
</table>
Various analysis computer programs are available for use in providing reference data. One such program is the Shuttle Electric Power System Analysis Computer Program (SEPS) developed by TRW for the consumables analysis section of the Mission Planning and Analysis Division (see Ref. 67). The subroutines used in the SEPS can be easily developed into an adequate reference module. The complete development of a suitable module would be a relatively simple and straightforward task. Figure 4.7-102 is a generalized overview of the module operations.

Figure 4.7-103 provides an equivalent DC circuit for the Shuttle EPD&C. It also shows the defining matrices for the circuit assuming the switches are all closed and the diodes are forward-biased. The defining matrix equation is:

\[
[I] = [G][E]
\]

where
- \([I]\) = column matrix for the node input current sources
- \([G]\) = square admittance matrix of the circuit
- \([E]\) = column matrix of the node voltages

The node voltages can be determined from the following equation:

\[
E_x = \frac{\Delta_x}{\Delta_o}
\]

- \(E_x\) = x-node voltage
- \(\Delta_o\) = value of the determinant of \([G]\)
- \(\Delta_x\) = value of the determinant of the matrix resulting by replacing the x column of the \([G]\) with \([I]\)

The analysis of the circuit with all switches open is similar with the resulting matrices being less complex.

**EPD&C Validation Methods and Checkcases**

The methods of Sections 5.1 and 4.2 can be used in validating the EPD&C simulation module. A comparison of the parameters listed in Table 4.7-29 and bus power, load power, fuel cell input power, fuel cell input watt hours, and ampere hours, should provide adequate checks. During the module runs, interface drivers will be required to provide the input parameters from the interfacing modules. It will also be necessary to provide drivers to initialize or hold static the intermodule parameters and conditions. Drivers required are:
- FC electrical outputs
- Equipment operating mode, etc.
Calculate individual AC loads and phase angles.
\[ y_{ac} = f(v_{ac}, \theta) \]

Sum AC loads on each inverter
\[ y_{ac} = \sum y_{ac} \]

calculate inverter efficiency based on AC loads
\[ \delta = f(y_{ac}, \epsilon_{in}, \ell) \]

calculate equivalent DC load representing inverter and its load
\[ G_{acs} = f(\delta, y_{acs}, \epsilon_{in}) \]

calculate individual DC load values
\[ R_m = f(V_m, \ell, T) \]
\[ G_L = \frac{1}{R_L + R_m} \]

Sum DC loads on each bus
\[ G_1 = \sum G_L \]

calculate bus interconnection admittances
\[ G_3 = f(\epsilon_i, \epsilon_k, \ell) \]

FIGURE 4.7-102 ELECTRIC POWER DISTRIBUTION AND CONTROL SUBSYSTEM REFERENCE MODULE MATH FLOW.

4.7-310

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
1. Calculate bus voltages
   \[ E_x = \frac{\Delta x}{\Delta o} \]

2. Bus volt converged

   YES
   - calculate Bus currents, load currents, load power
     \[ I = I_e E \]
     \[ P = I E \]
   - Sum currents thru power interruption devices for overload
     \[ I_{oe} = \sum I_e \]

   NO
   - \[ I_{oe} > I_1 \]

   YES
   - Integrate current overload time.
     \[ \sigma = \sum I_{oe} \Delta t \]
   - Determine device interrupt state.
     \[ B = f(\sigma^-) \]

RETURN

FIGURE 4.7-102 (CONTINUED)
LEGEND:

- $Y_{AC}$ = AC load admittance
- $V_{AC}$ = AC bus voltage
- $I_0$ = logic inputs
- $Y_{ACI}$ = Sum of AC loads on AC inverter
- $S_I$ = Inverter electrical efficiency
- $G_{ACI}$ = Equivalent DC load representing inverter and its AC loads
- $R_{m}$ = Individual DC load resistances
- $R_L$ = Line resistance from load to bus
- $G_I$ = Sum of bus load admittances
- $G_2$ = Bus interconnection admittance (DC)
- $E_x$ = Bus voltage
- $\Delta_x$ = Value of determinant of the admittance matrix with $x$-column replaced by current matrix
- $\Delta_0$ = Value of the determinant of the admittance matrix
- $i$ = Current
- $E$ = voltage
- $P$ = Power (electrical)
- $B$ = Interruption state of power interrupt devices (fuses, circuit breakers, etc.)
- $\Delta t$ = Time increment
- $T$ = Temperature

FIGURE 4.7-102 (CONTINUED)
\[ \mathbf{I} = [\mathbf{G}] \mathbf{E} \]

\[ \mathbf{I} = \begin{bmatrix} I_{FCA} \\ I_{FCB} \\ I_{FCC} \end{bmatrix} \]

\[ \mathbf{E} = \begin{bmatrix} E_{FA} \\ E_{HA} \\ E_{BB} \\ E_{EA} \\ E_{LA} \\ E_{LB} \\ E_{HA} \\ E_{BB} \\ E_{EA} \\ E_{LA} \\ E_{LB} \\ E_{EA} \\ E_{LA} \\ E_{LB} \\ E_{EA} \end{bmatrix} \]
\[
\begin{bmatrix}
G_{11} & -G_{GCA} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
-G_{GCA} & G_{22} & 0 & 0 & 0 & 0 & -G_{MA} & 0 & -G_{BA} & -G_{A} & 0 & -G_{LA} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & G_{33} & -G_{GB} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & -G_{GB} & G_{44} & 0 & 0 & -G_{MB} & 0 & -G_{BB} & 0 & -G_{BC} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & 0 & G_{55} & -G_{GB} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & 0 & -G_{GB} & G_{66} & G_{MC} & 0 & 0 & -G_{CA} & -G_{CC} & 0 & 0 & -G_{LAC} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
-G_{MA} & 0 & -G_{MB} & 0 & -G_{MC} & G_{77} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & 0 & 0 & 0 & G_{88} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
-G_{BA} & 0 & -G_{BB} & 0 & 0 & 0 & 0 & G_{99} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
-G_{A} & 0 & 0 & 0 & -G_{BC} & 0 & 0 & 0 & G_{0,10} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & -G_{GC} & 0 & -G_{CC} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
-G_{LA} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & -G_{TA} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & -G_{LAB} & 0 & 0 & 0 & 0 & -G_{TB} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & 0 & 0 & 0 & 0 & -G_{AC} & 0 & -G_{TC} & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\
\end{bmatrix}
\]

**NOTES:**

1. ALL MATRICES SHOWN ARE WITH ALL SWITCHES CLOSED.

2. \( G_{11} = G_{GCA} + G_{GCA} \)
\( G_{22} = G_{GCA} + G_{A} + G_{LAA} + G_{AB} + G_{A} + G_{TMA} \)
\( G_{33} = G_{GB} + G_{FGB} \)
\( G_{44} = G_{FGB} + G_{A} + G_{LAB} + G_{AB} + G_{BAC} + G_{TMB} \)
\( G_{55} = G_{GCC} + G_{FGBM} \)
\( G_{66} = G_{FGBM} + G_{C} + G_{LAC} + G_{CC} + G_{CA} + G_{TMC} \)
\( G_{77} = G_{TMA} + G_{TMA} + G_{TMC} \)
\( G_{88} = G_{TMA} + G_{TMA} + G_{TMC} \)
\( G_{99} = G_{BCC} + G_{BCC} + G_{BCC} \)
\( G_{10,10} = G_{CA} + G_{GA} + G_{MA} \)
\( G_{11,11} = G_{CC} + G_{CC} + G_{CC} \)
\( G_{12,12} = G_{LA} + G_{LTA} + G_{LAC} \)
\( G_{13,13} = G_{LAB} + G_{LTB} + G_{LBC} \)
\( G_{14,14} = G_{LAC} + G_{LTC} + G_{LCC} \)

**FIGURE 4.7-103.** (CONTINUED)
LEGEND:

$I_{FCA}$ = Norton's equivalent current sources representing the fuel cell A, B, C outputs.

$I_{FLB}$

$I_{FLC}$

$G_{FCA}$ = Norton's equivalent admittance for the fuel cells A, B, C.

$G_{FCB}$

$G_{FCC}$

$G_{FC(M)}$ = Admittances connecting fuel cell output to main buses.

$G_{A}$

$G_{B}$

$G_{C}$

$G_{LAA}$

$G_{LAB}$ = Admittance between main buses and AFT local buses A, B, C.

$G_{LAC}$

$G_{LA}$

$G_{LB}$ = Admittance loads on AFT local buses A, B, C.

$G_{LC}$

$G_{TA}$

$G_{TB}$ = Admittance between AFT local buses A, B, C and AFT Bus Tie.

$G_{TC}$

$G_{TMA}$

$G_{TMB}$ = Admittances between main buses A, B, C and main Bus Tie.

$G_{TMC}$

$G_{AA}$

$G_{CA}$ = Admittance between main buses A, C and essential bus A.

FIGURE 4.7-103. (CONTINUED)  

REPRODUCIBILITY OF THE ORIGINAL PAGE IS POOR
\[ G_{AB} \] = Admittances between main buses A, B and essential bus B.

\[ G_{BB} \]

\[ G_{BC} \] = Admittances between main buses A, B and essential bus C.

\[ G_{CC} \]

\[ G_{EA} \]

\[ G_{EB} \] = Admittance loads on essential buses A, B, C.

\[ G_{EC} \]

\[ E_{FCA} \]

\[ E_{FCB} \]

\[ E_{FCC} \]

\[ E_{FCA} \]

\[ E_{FCC} \]

\[ E_{MA} \]

\[ E_{MB} \] = Main buses A, B, C voltages.

\[ E_{MC} \]

\[ E_{MT} \]

\[ E_{LT} \]

\[ E_{EA} \]

\[ E_{EB} \]

\[ E_{EC} \]

\[ E_{LA} \]

\[ E_{LB} \]

\[ E_{LC} \]

\[ \Delta_o \] = Value of the determinant of the G-matrix ([G]).

\[ \Delta_x \] = Value of the determinant of the matrix resulting by replacing the x-column of the G-matrix with the I-matrix.

\[ Sw. \] = Switch.

FIGURE 4.7-103, (CONTINUED)

4.7-316

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
Equipment temperature
- Control logic (switch positions)
- Prelaunch/launch interface - GSE electrical inputs parameters

The check cases implemented should include step changes in loads, bus switching, maximum equipment powered, minimum equipment powered, and expected mission load profiles (equipment powered time-line). System checkout or test sequence results can be input as check cases with simulation results compared directly to the test results.

EPD&C Data Base Impact

The EPD&C reference module and drivers are of moderate impact to the simulation data base. The majority of the processing subroutines (data comparison, read, write, etc.) would be common to all modules requiring validation. The equipment power profiles (time-lines) would be required but represent a minor impact. Data files would also be required for the input and output data tables.
4.7.6 Environmental Control/Life Support System

This section includes the discussion of the Atmosphere Revitalization System; the Active Thermal Control System; and the Food, Water, and Waste Management System.

4.7.6.1 Atmosphere Revitalization System (ARS)

The ARS includes the Atmosphere Revitalization Pressure Control Subsystem (ARPCS), and the ARS Cabin Atmosphere Control Subsystem (ARS-CACS). These two subsystems are discussed in the following sections.
4.7.6.1.1 Atmosphere Revitalization Pressure Control System Description

The Atmosphere Revitalization Pressure Control Subsystem (ARPCS) provides three basic functions for the Shuttle Orbiter. The functions provided are:

1) N$_2$ and O$_2$ storage (gas)
2) distribution of gaseous O$_2$ and N$_2$, at proper pressures, to the user equipment, system, etc.
3) ensuring proper O$_2$ and N$_2$ mixture while controlling cabin (crew quarters) pressure.

These functions are accomplished via interconnecting manual valves, solenoid valves, pressure regulators, pressure sensors, electronic controls and relief valves. This interconnection was determined from schematic VL70-000214 (Reference 79), specification MC250-0002 (Reference '71), and a Preliminary Design Review (PDR) handout on the Power Reactant Storage and Distribution System. The resulting representative plumbing schematic is shown in Figure 4.7-104 and 4.7-105. Although these figures are not totally accurate, they should suffice for the current verification study purposes.

N$_2$ Supply and Distribution - The N$_2$ gas is stored in 3000 psi bottles containing approximately 50 pounds of N$_2$ in each. The primary source of N$_2$ is one (1) bottle, with the auxiliary source comprised of three (3) bottles. Additional bottles can be carried in the payload area and connected to the system if desired. Either the primary, auxiliary, or payload supply can be selected to deliver gas to either of the two N$_2$ distribution networks.

The N$_2$ distribution networks are each comprised of various control valves (manual and solenoid) and two (2) N$_2$ pressure regulators. A 175 psi outlet regulator provides the proper pressure level to the O$_2$/N$_2$ cabin pressure controller and to the potable H$_2$O bottle regulators. This 175 psi regulator also provides outlet pressure relief (at approximately 200 psi) to prevent over pressurizing the downstream distribution network. The pressure relief is vented overboard resulting in possible vehicle attitude and rate disturbance torques. Potable water bottle regulators maintain pressurization of the three (3) potable water tanks. Pressure is regulated 8 to 12 psi above the cabin pressure. This higher pressure ensures the expulsion of the water from the tanks. It should be noted that the N$_2$ side
FIGURE 4.7-105. ATMOSPHERE PRESSURE CONTROL, AIRLOCK SUPPORT SUBSYSTEM SCHEMATIC

FROM O2/N2 CONTROL ASSY

FIGURE 1 a.

PAYLOAD (VOLUME 1500 TO 4500 ft.³)

DOCKING MODULE OR EVA

CREW COMPARTMENT

AIRLOCK (VOLUME 150 ft³)
of the water tanks can be opened to the crew quarters atmosphere via a solenoid actuated valve. The potable water tanks pressure regulators also provide pressure relief for the water tanks. This relief is vented into the crew quarters and contributes to the total cabin pressure.

**O₂ Supply and Distribution** - The O₂ gas supply has three (3) sources. The primary and secondary supplies are from the Cryogenic O₂ Systems for the Power Reactants Storage and Distribution System (PRSD) which also provide O₂ to the fuel cells. The Cryogenic O₂ flows through restrictor/heat exchangers which provide flow control as well as increasing the gas temperature. Oxygen accumulators (surge tanks) act as pressure stabilizing and intermediate storage devices.

An auxiliary O₂ gas supply is also available. This is at an initial pressure of 3000 psi and must be regulated to approximately 450 psi to prevent overpressurizing the O₂ distribution network. The 450 psi regulator also provides a distribution system over pressure relief at approximately 1100 psi. This O₂ relief is vented overboard and may generate vehicle attitude and rate disturbance torques.

The O₂ distribution networks are each made up of manual valves, solenoid valves and a pressure regulator. The 100 psi O₂ regulator provides the proper O₂ supply pressure to the O₂/N₂ cabin pressure controller. High pressure O₂ is provided to the four (4) emergency O₂ outlets in the crew compartment mid section, to the four (4) outlets for portable O₂ bottle filling, and to the two (2) airlock support outlets.

**Mixture and Pressure Control** - The cabin O₂/N₂ mixture control and cabin pressure control are provided by cabin pressure regulators, pressure relief valves, O₂ partial pressure controller, manual valves, and solenoid valves.

O₂ or N₂ is selected for cabin make-up gas by the O₂/N₂ mixture controller. The partial pressure of oxygen is sensed by the partial pressure controller and electronically opens (for O₂ partial pressure 3.45 psia) the N₂ supply solenoid.
valve(s) which allows the 170 psi N\textsubscript{2} to flow to the cabin pressure regulator inlet. The N\textsubscript{2} pressure is greater than the 100 psi O\textsubscript{2} which feeds the regulator through a check valve. The higher pressure closes the check valve preventing O\textsubscript{2} from entering the regulator and N\textsubscript{2} only is supplied to the cabin. When the O\textsubscript{2} partial pressure is less than 2.95 psia, the N\textsubscript{2} solenoid valve is closed. This allows any cabin make-up gas flow to be O\textsubscript{2}. O\textsubscript{2} and N\textsubscript{2} flow sensors provide output to the caution and warning subsystem if flow is excessive. In addition, signals are provided to the caution and warning subsystem if the cabin O\textsubscript{2} partial pressure becomes too high or too low.

The cabin pressure control is provided by two (2) types of cabin pressure regulators, cabin relief pressure valves, and manual valves. The primary cabin pressure regulators maintain the cabin pressure at 14.7 psia under normal conditions. However, in the event of excess cabin leakage, additional cabin regulators operate to maintain the pressure at 8 psia.

Two cabin overpressure relief valves operate to limit the cabin high pressure at 15.5 to 16 psi above the vehicle external pressure. These relief valves can be electrically overridden if desired. Two reverse cabin pressure relief valves actuate to maintain a maximum 2 psid external pressure above the cabin pressure. These reverse pressure relief valves can be manually overridden when desired. The venting of these valves can cause body attitude and rate disturbance torques.

Manually actuated pressure equalization valves are used to pressurize and depressurize the airlock compartment. Each of the three (3) avionics bays is continually vented (at a low rate) to the spacecraft external ambient. This venting is required to prevent equipment outgassing products from entering the crew compartment. The inlet to each bay is open to the crew compartments via a relief valve. This valve maintains the bay pressure at 0 to 0.4 psi below the cabin pressure. In the event of a cabin rapid depressurization the same relief valve operates at 0.6 psi to prevent the bay over-pressurizing with respect to the crew compartment.

A cabin pressure decay rate detection provides signals to the caution and warning subsystem when the cabin pressure is decreasing at an excessive rate.
The continued venting of the three avionics bays, and pressurization/depressurization of the airlock may cause vehicle attitude and rates disturbance torques.
ARPCS Module Functions and Parameters

Figure 4.7-106 provides an overview of the ARPCS simulation module functional elements and interfaces with other modules. Basically there are four functions performed within the module. These functions are:

- Control logic
- O₂ and N₂ storage
- O₂ and N₂ pressure regulation and distribution
- Cabin pressure control

Table 4.7-30 provides a detailed listing of the parameters associated with the ARPCS module and designation of parameter type.

The following discussion identifies, in general, the functions performed in each element and the factors involved in the calculations.

Control Logic - The control logic functions are dependent on the position of manual valves, solenoid valves, switches, command inputs, bus voltages, etc. The logic outputs are used extensively in each of the other functional elements calculations. The valve logic can be determined from the plumbing schematic; however, the electrical logic is not presently known. The total logic will, of necessity, be highly dependent on the exact electrical design, and this study does not warrant accurate description of the logic. It is only necessary to recognize its existence, and the possibility of many combinations existing.

O₂ and N₂ Storage - The O₂ and N₂ storage functions are the calculation of remaining (or available) gas mass, source pressures, temperatures, inlet or outlet mass flow, etc. The parameters associated with these calculations are as follows:

A. O₂ Accumulator Calculations
   1. O₂ quantity as a function of initial quantity, inlet flow, outlet flow, time, etc.
   2. Pressure as a function of quantity, temperature, tank volume.
   3. Temperature is a function of initial temperature, inlet O₂ temperature, heat leak, etc.
   4. Mass flow inlet as a function of cryogenic O₂ pressure, accumulator pressure, and restrictor flow/pressure characteristics.
FIGURE 4.7-106 ARPCS MODULE FUNCTIONAL ELEMENTS AND MODULE INTERFACES

4.7-326

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>Primary O₂ Accumulator - inlet O₂ temperature</td>
<td>I</td>
</tr>
<tr>
<td>Primary O₂ Accumulator - cryo O₂ pressure</td>
<td>I</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - inlet O₂ temperature</td>
<td>I</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - cryo O₂ temperature</td>
<td>I</td>
</tr>
<tr>
<td>Primary O₂ Accumulator - O₂ mass</td>
<td>CP</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - O₂ mass</td>
<td>CP</td>
</tr>
<tr>
<td>Primary O₂ Accumulator - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Primary O₂ Accumulator - Temperature</td>
<td>P</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - Temperature</td>
<td>P</td>
</tr>
<tr>
<td>Primary O₂ Accumulator - O₂ inlet mass flow - cryo</td>
<td>P</td>
</tr>
<tr>
<td>Secondary O₂ Accumulator - O₂ inlet mass flow - cryo</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY O₂ ACCUMULATOR - O₂ mass outlet flow</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY O₂ ACCUMULATOR - O₂ mass outlet flow</td>
<td>CP</td>
</tr>
<tr>
<td>AUXILIARY O₂ TANK - O₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>AUXILIARY O₂ TANK - pressure</td>
<td>P</td>
</tr>
<tr>
<td>AUXILIARY O₂ TANK - Temperature</td>
<td>P</td>
</tr>
<tr>
<td>AUXILIARY O₂ TANK - O₂ mass outlet flow</td>
<td>P</td>
</tr>
<tr>
<td>AIRLOCK SUPPORT - O₂ pressure</td>
<td>P</td>
</tr>
<tr>
<td>AIRLOCK SUPPORT - O₂ mass flow</td>
<td>P</td>
</tr>
<tr>
<td>N₂ PRIMARY TANK - N₂ Mass</td>
<td>CP</td>
</tr>
<tr>
<td>N₂ AUXILIARY TANKS - N₂ mass</td>
<td>CP</td>
</tr>
<tr>
<td>N₂ PRIMARY TANK - pressure</td>
<td>P</td>
</tr>
<tr>
<td>N₂ SECONDARY TANKS - pressure</td>
<td>P</td>
</tr>
<tr>
<td>N₂ PRIMARY TANKS - temperature</td>
<td>P</td>
</tr>
<tr>
<td>N₂ SECONDARY TANKS - temperature</td>
<td>P</td>
</tr>
<tr>
<td>N₂ PRIMARY - N₂ mass flow outlet</td>
<td>P</td>
</tr>
<tr>
<td>N₂ SECONDARY - N₂ mass flow outlet</td>
<td>P</td>
</tr>
<tr>
<td>Numerous Control Logic Outputs/Inputs</td>
<td>P</td>
</tr>
<tr>
<td>Electrical Power System - Bus Voltages</td>
<td>I</td>
</tr>
<tr>
<td>Aux O₂ regulator - Output Pressure (include relief)</td>
<td>P</td>
</tr>
<tr>
<td>Aux O₂ regulator - Input Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Aux O₂ regulator - Relief vent mass flow rate</td>
<td>P</td>
</tr>
<tr>
<td>PARAMETER</td>
<td>TYPE</td>
</tr>
<tr>
<td>------------------------------------------------</td>
<td>------</td>
</tr>
<tr>
<td>MID SECTION EMERG O₂ flow 1 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>MID SECTION EMERG O₂ flow 2 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>MID SECTION EMERG O₂ flow 3 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>MID SECTION EMERG O₂ flow 4 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 1 - 1 bottle pressure</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 2 - 2 bottle pressure</td>
<td>P</td>
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<tr>
<td>PORTABLE O₂ bottle fill 3 - 3 bottle pressure</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 4 - 4 bottle pressure</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 1 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 2 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 3 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PORTABLE O₂ bottle fill 4 - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY O₂ - 100 PSI reg - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY O₂ - 100 PSI reg - outlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY O₂ - 100 PSI reg - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY O₂ - 100 PSI reg - relief vent mass flow</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY O₂ - 100 PSI reg - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY O₂ - 100 PSI reg - outlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY O₂ - 100 PSI reg - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY O₂ - 100 PSI reg - relief vent mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PAYLOAD N₂ tanks - mass</td>
<td>CP</td>
</tr>
<tr>
<td>PAYLOAD N₂ tanks - pressure</td>
<td>P</td>
</tr>
<tr>
<td>PAYLOAD N₂ tanks - temperature</td>
<td>P</td>
</tr>
<tr>
<td>PAYLOAD N₂ tanks - mass flow out</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY N₂ 175 PSI reg - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY N₂ 175 PSI reg - outlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY N₂ 175 PSI reg - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY N₂ 175 PSI reg - relief vent flow</td>
<td>P</td>
</tr>
<tr>
<td>PARAMETER</td>
<td>TYPE</td>
</tr>
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<td>-----------</td>
<td>------</td>
</tr>
<tr>
<td>SECONDARY N₂ 175 PSI reg - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY N₂ 175 PSI reg - outlet pressure</td>
<td>P</td>
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<tr>
<td>SECONDARY N₂ 175 PSI reg - mass flow</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY N₂ 175 PSI reg - relief vent mass flow</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY N₂ Check valve - outlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY N₂ Check valve - outlet pressure</td>
<td>P</td>
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<tr>
<td>PRIMARY POTABLE H₂O Bottle Regulator - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>Primary POTABLE H₂O Bottle Regulator - relief vent flow to cabin</td>
<td>P</td>
</tr>
<tr>
<td>PRIMARY POTABLE H₂O Bottle Regulator - flow rate</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY POTABLE H₂O Bottle Regulator - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY POTABLE H₂O Bottle Regulator - relief vent flow to cabin</td>
<td>P</td>
</tr>
<tr>
<td>SECONDARY POTABLE H₂O Bottle Regulator - flow rate</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - N₂ (gas) quantity</td>
<td>CP</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - Gas Pressure</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - temperature</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - Gas flow/bottles 1 &amp; 2</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - Gas volume,</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tank 3 - H₂O mass remaining</td>
<td>I</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - N₂ (Gas) mass</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - Gas pressure</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - temperature</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - Gas flow to cabin</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - Gas volume</td>
<td>P</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - H₂O mass remaining 1</td>
<td>I</td>
</tr>
<tr>
<td>POTABLE H₂O tanks 1 and 2 - H₂O mass remaining 2</td>
<td>I</td>
</tr>
</tbody>
</table>

Crew Compartment CO₂ Partial Pressure | P |
<p>| Pri N₂ to Cabin Pressure Controller - Pressure | P |
| Sec N₂ to Cabin Pressure Controller - Pressure | P |</p>
<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>Pri O₂ to Cabin Pressure Controller - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Sec O₂ to Cabin Pressure Controller - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Pri Cabin Pressure Regulator - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>Sec Cabin Pressure Regulator - inlet pressure</td>
<td>P</td>
</tr>
<tr>
<td>Pri O₂ mass flow to cabin</td>
<td>CP</td>
</tr>
<tr>
<td>Sec O₂ mass flow to cabin</td>
<td>CP</td>
</tr>
<tr>
<td>Pri N₂ mass flow to cabin</td>
<td>CP</td>
</tr>
<tr>
<td>Sec N₂ mass flow to cabin</td>
<td>CP</td>
</tr>
<tr>
<td>Pressurized Volume</td>
<td>P</td>
</tr>
<tr>
<td>Crew Compartment Pressure - total</td>
<td>P</td>
</tr>
<tr>
<td>Crew Compartment Pressure - O₂ Partial Pressure</td>
<td>CP</td>
</tr>
<tr>
<td>Crew Compartment Pressure - Decay rate</td>
<td>CP</td>
</tr>
<tr>
<td>Crew Compartment - O₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Crew Compartment - N₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Crew Compartment - temperature (gas)</td>
<td>I</td>
</tr>
<tr>
<td>Crew Compartment - O₂ leakage, loss</td>
<td>P</td>
</tr>
<tr>
<td>Crew Compartment - N₂ leakage, loss</td>
<td>P</td>
</tr>
<tr>
<td>Airlock Compartment - O₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Airlock Compartment - N₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Airlock Compartment - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Airlock Compartment - O₂ mass loss /gain</td>
<td>P</td>
</tr>
<tr>
<td>Airlock Compartment - N₂ mass loss /gain</td>
<td>P</td>
</tr>
<tr>
<td>Payload Compartment - O₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Payload Compartment - N₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Payload Compartment - Pressure</td>
<td>P</td>
</tr>
<tr>
<td>Payload Compartment - O₂ mass loss /gain</td>
<td>P</td>
</tr>
<tr>
<td>Payload Compartment - N₂ mass loss /gain</td>
<td>P</td>
</tr>
<tr>
<td>Avionics Bay 1 - O₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Avionics Bay 1 - N₂ mass</td>
<td>P</td>
</tr>
<tr>
<td>Avionics Bay 1 - Pressure</td>
<td>P</td>
</tr>
</tbody>
</table>
### Table 4.7-31. (COMPLETE)

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE(^a)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Avionics Bay 1 - (O_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 1 - (N_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 1 - Gas temperature</td>
<td>(I)</td>
</tr>
<tr>
<td>Avionics Bay 2 - (O_2) mass</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 2 - (N_2) mass</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 2 - pressure</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 2 - (O_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 2 - (N_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 2 - Gas temperature</td>
<td>(I)</td>
</tr>
<tr>
<td>Avionics Bay 3 - (O_2) mass</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 3 - (N_2) mass</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 3 - Pressure</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 3 - (O_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 3 - (N_2) mass loss/gain</td>
<td>(P)</td>
</tr>
<tr>
<td>Avionics Bay 3 - Gas temperature</td>
<td>(I)</td>
</tr>
</tbody>
</table>

\(^a\) \(P\) = Performance Parameter  
\(CP\) = Critical Performance Parameter  
\(I\) = Input parameter (from another module)
B. Auxiliary O₂ Calculations
1. O₂ quantity remained as a function of time, initial quantity, flow, etc.
2. O₂ source pressure as a function of quantity, temperature, tank volume.
3. Temperature as a function of initial temperature, heat leak, etc.

C. N₂ Source Calculations
1. Primary, auxiliary, and payload N₂ quantities as a function of initial quantities, outlet flow, etc.
2. Primary, auxiliary and payload temperature as a function of initial temperatures, heat leaks, etc.
3. Primary, auxiliary and payload source pressures as a function of temperature, tank volumes, quantity, etc.

D. Components characteristics needed to perform these calculations are:
2. O₂ accumulator volumes
3. O₂ and N₂ tank volumes

Pressure Regulation and Distribution - The O₂ and N₂ pressure regulation and distribution functions are the calculation of the pressures, temperatures, flow rates, etc. throughout the distribution networks. The parameters associated with the calculations are as follows:

A. O₂ Distribution Network Calculations
1. Gas temperatures as a function of source temperature and heat leaks.
2. Pressures as a function of regulator characteristics, inlet pressures, relief characteristics, line volumes, flow rates, etc.
3. Total system flow rate as a function of demand, leakage, etc.
4. O₂ delivery flow rates to the four Emergency O₂ outlets as a function of inlet/outlet pressures, valve/line flow characteristics.
5. O₂ delivery flow rates to the four portable O₂ fill outlets as a function of inlet/outlet pressures, fill tank volume, valve/line flow characteristics, etc.
C. The component characteristics needed to perform these calculations are:
1. Pressure regulators flow characteristics, relief pressure points, and regulation pressure points.
2. Line/equipment volumes.

Cabin Pressure Control - The cabin pressure control functions are the calculation of various compartment pressures, \( O_2 \) and \( N_2 \) gas quantities, gas flow rates into and out of the cabins, and pressure decay rates. The parameters associated with these calculations are as follows:

A. Flow Rates
1. \( O_2 \) flow rate to cabin as function of pressures, partial pressure controller characteristics, cabin pressure regulator characteristics, etc.
2. \( N_2 \) flow rate to cabin as function of pressures partial pressure controller characteristics, cabin pressure regulator characteristics.
3. \( O_2 \) and \( N_2 \) flow from cabin, as function of pressures, cabin leak rates, relief valves, depressurization valves, etc.

B. Gas Quantities
1. \( O_2 \) and \( N_2 \) quantities in cabin as a function of initial quantities, flow rates into and out of cabin, etc.
C. Cabin Pressure
   1. Caution and warning signals as functions of pressures.
   2. Cabin pressures as a function of various gas partial pressures.
   3. $O_2$ partial pressure as a function of $O_2$ quantity, cabin temperature, cabin volumes.
   4. $N_2$ partial pressure as a function of $N_2$ quantities, cabin temperature, cabin volumes.

D. Component characteristics required to perform these calculations are:
   1. Cabin pressure regulators flow/pressure characteristics, regulation points, etc.
   2. Cabin pressure relief valves flow/pressure characteristics, open and close points for solenoid valves.
   3. $O_2$ partial pressure controller operating voltage levels, open and close points for solenoid valves.
   4. Avionics bays vent orifice flow/pressure characteristics (effective flow area), etc.
   5. Airlock vent and equalization valve flow/pressure characteristics.
   6. Cabin or compartment gas volumes, leakage, etc.
Reference Data Sources and Formats

Reference modules for ARPCS module validation can be developed from routines described in Reference 69 and 70. The G189A (see Ref. 69) program was developed for JSC and provides a versatile analytical tool for support of environmental systems work. Reference 70 describes environmental analysis subroutine used for mission analysis and consumables studies.

Figure 4.7-107 is a flow chart for calculation of gas flow into or from a manifold or compartment from various source, as well as calculating the resulting pressure, temperature, etc. This routine is used in providing a reference module for cabin pressure control (see Figure 4.7-108) and N₂ distribution/source (Figure 4.7-109). The O₂ distribution network module can be developed in a similar way. It should be noted that the proper system control logic must be integrated into these modules.

The system and component design performance requirements, analysis, performance predictions, and test results provide data for direct comparison with the Shuttle simulation results. Reference 31 will provide these types of data as they become available. The design requirements can be determined from Reference 71.
FIGURE 4.7-107, MANIFOLD GAS REFERENCE MODULE MATH FLOW

4.7-336

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ \dot{m}_i = \frac{P_i A}{\sqrt{R_i} \text{Im}} \left( 1 + \frac{2}{\gamma} \left( \frac{2}{M_i^2 - 1} \right) \right)^{\gamma - 1} \frac{1}{2} \]

\[ T_{oi} = \frac{2 T_i}{2 + (\gamma - 1) M_i^2} \]

\[ v_{oi} = \frac{2 R_i \text{Im}}{1 + \frac{2}{\gamma} \left( \frac{2}{M_i^2 - 1} \right) v_i} \]

\[ K_3 > 0 \]

\[ m_{\text{In-1}} = +m_i \]
\[ T_{\text{m,m-1}} = T_{oi} \]
\[ T_i = T_{\text{Im-1}} \]
\[ E_i = C_{PI} T_{\text{Im}} m_{\text{In-1}} \]

\[ m_{\text{IIn-1}} = -m_i \]
\[ T_{\text{m,In-1}} = T_{\text{Im}} \]
\[ T_i = T_{oi} \]
\[ E_i = -C_{PI} T_{\text{m}} m_i \]

\[ I \geq N \]

\[ m_{\text{m}} = \frac{\dot{v}_i}{\text{Im}} m_{\text{Im-1}} \]
\[ T_{\text{m}} = \frac{c_{\text{Im}} m_{\text{m}} T_{\text{m}} + \dot{v}_i E_i \Delta t + \dot{Q}_m \Delta t}{c_{\text{Im}} (m_{\text{m}} + m_{\text{Im}} \Delta t)} \]
\[ m_{\text{m}} = m_{\text{m}} + m_{\text{Im}} \Delta t \]
\[ P_{\text{m}} = \frac{m_{\text{m}}}{v_{\text{m}}} R_{\text{Gm}} T_{\text{m}} \]

\text{RETURN}

\text{FIGURE 4.7-107. (CONTINUED)}
LEGEND:

- $P_m$ - Manifold pressure
- $P_{m,i}$ - Pressure of $i^{th}$ load/source
- $T_{m,i}$ - Temperature of $i^{th}$ load/source
- $m_{m,i}$ - Flow rate from $i^{th}$ load/source into manifold
- $T_{m,i}$ - Temperature into manifold from $i^{th}$ tank
- $T_i$ - Temperature delivered to $i^{th}$ load/source
- $v_{os}$ - Fluid velocity from $i^{th}$ tank into manifold
- $T_m$ - Fluid temperature in manifold
- $\rho$ - Fluid density
- $m_m$ - Fluid mass in manifold
- $c$ - Fluid specific heat
- $\Delta t$ - Time increment
- $A_{m,i}$ - Flow area from $i^{th}$ load/source into manifold
- $\kappa_c$ - Critical pressure ratio

FIGURE 4.7-107. (CONTINUED)
FIGURE 4.7-108. CABIN PRESSURE CONTROL REFERENCE MODULE MATH FLOW

4.7-339

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
\[ \dot{Q}_{B1} = \dot{Q}_{B1} - \dot{m}_{F1} c_v (T_{B1} - T_{B1-ECLLS}) - \dot{Q}_{L-ECLLS} \]
\[ \dot{Q}_{B2} = \dot{Q}_{B2} - \dot{m}_{F2} c_v (T_{B2} - T_{B2-ECLLS}) - \dot{Q}_{L-ECLLS} \]
\[ \dot{Q}_{B3} = \dot{Q}_{B3} - \dot{m}_{F3} c_v (T_{B3} - T_{B3-ECLLS}) - \dot{Q}_{L-ECLLS} \]
\[ \dot{Q}_C = \dot{Q}_C - \dot{m}_{F} c_v (T_C - T_{C-ECLLS}) - \dot{Q}_{L-ECLLS} \]
\[ \dot{Q}_L = \dot{Q}_L - \dot{Q}_{L-ECLLS} \]
\[ \dot{Q}_P = \dot{Q}_P - \dot{Q}_{P-ECLLS} - \dot{Q}_{L-ECLLS} \]

CALL MANIFOLD GAS

\[ \dot{m}_{BL-C} = \dot{m}_{N-1} \]
\[ \dot{m}_{BL-A0} = \dot{m}_{N-2} \]
\[ \dot{m}_{BLO} = \dot{m}_{m} \]
\[ P_{BLO} = P_{m} \]
\[ T_{BLO} = T_{m} \]

\[ L \geq 3 \]

FIGURE 4.7-108. (CONTINUED).
FIGURE 4.7-103. (CONTINUED)

PRODUCIBILITY OF THE
ORIGINAL PAGE IS POOR
FIGURE 4.7-108. (CONTINUED)

4.7-343

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY・EAST
FIGURE 4.7-10B. (CONTINUED)

4.7-344

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-108. (CONTINUED)
FIGURE 4.7-108, (CONTINUED)

\[
\begin{align*}
\Delta m(\text{CO}_2)_c &= m(\text{CO}_2)_c \Delta t - m(\text{CO}_2)_{\text{B1-2CO}} \Delta t - m(\text{CO}_2)_{\text{G2-CO}} \Delta t - m(\text{CO}_2)_{\text{B3-CO}} \Delta t \\
&+ m(\text{CO}_2)_{\text{ECS}} \Delta t + m(\text{CO}_2)_{\text{HET}} \Delta t - m(\text{CO}_2)_{\text{HET}} \Delta t \\
\Delta m(\text{N}_2)_c &= m(\text{N}_2)_c \Delta t - m(\text{N}_2)_{\text{B1-2CO}} \Delta t - m(\text{N}_2)_{\text{G2-CO}} \Delta t - m(\text{N}_2)_{\text{B3-CO}} \Delta t \\
&+ m(\text{N}_2)_{\text{ECS}} \Delta t + m(\text{N}_2)_{\text{HET}} \Delta t - m(\text{N}_2)_{\text{HET}} \Delta t \\
\Delta m(\text{CO})_c &= m(\text{CO})_c \Delta t - m(\text{CO})_{\text{B1-2CO}} \Delta t - m(\text{CO})_{\text{G2-CO}} \Delta t - m(\text{CO})_{\text{B3-CO}} \Delta t \\
&+ m(\text{CO})_{\text{ECS}} \Delta t + m(\text{CO})_{\text{HET}} \Delta t - m(\text{CO})_{\text{HET}} \Delta t \\
\Delta m(\text{H}_2\text{O})_c &= m(\text{H}_2\text{O})_c \Delta t - m(\text{H}_2\text{O})_{\text{B1-2CO}} \Delta t - m(\text{H}_2\text{O})_{\text{G2-CO}} \Delta t - m(\text{H}_2\text{O})_{\text{B3-CO}} \Delta t \\
&+ m(\text{H}_2\text{O})_{\text{ECS}} \Delta t + m(\text{H}_2\text{O})_{\text{HET}} \Delta t - m(\text{H}_2\text{O})_{\text{HET}} \Delta t \\
\Delta m_e &= \Delta m(\text{CO})_c + \Delta m(\text{N}_2)_c + \Delta m(\text{CO})_c + \Delta m(\text{H}_2\text{O})_c \\
&+ m(\text{N}_2)_c + \Delta m(\text{CO})_c \\
&+ m(\text{N}_2)_c + \Delta m(\text{N}_2)_c \\
&+ m(\text{CO})_c + \Delta m(\text{CO})_c \\
&+ m(\text{H}_2\text{O})_c + \Delta m(\text{H}_2\text{O})_c
\end{align*}
\]

4.7-346

MCDONNELL DOUGLAS AERONAUTICS COMPANY - EAST
\[
(C_p)_f = \frac{m(c_0)^2 c(c_0) + m(w_3)^2 c(w_3) + m(c_0)^2 c(w_0)^2 + m(h_0)^2 c(h_0)}{m_c + \Delta m_c}
\]

\[
(C_p)_c = \frac{m(c_0)^2 c(c_0) + m(w_3)^2 c(w_3) + m(c_0)^2 c(w_0)^2 + m(h_0)^2 c(h_0)}{m_c + \Delta m_c}
\]

\[
R_c = (C_p)_c - (C_v)_c
\]

\[
T_c = \frac{\Delta v}{(C_v)_c (m_c + \Delta m_c)}
\]

\[
m_c = m_c + \Delta m_c
\]

\[
P_c = \frac{m_c}{V_c} R_c T_c
\]

\[
m_{b1} = m_{b10}
\]

\[
m_{b2} = m_{b20}
\]

\[
m_{b3} = m_{b30}
\]

\[
m_{l} = m_{l0}
\]

\[
m_p = m_{p0}
\]

\[
T_{b1} = T_{b10}
\]

\[
T_{b2} = T_{b20}
\]

\[
T_{b3} = T_{b30}
\]

\[
T_L = T_{l0}
\]

\[
T_P = T_{p0}
\]

\[
P_{b1} = P_{b10}
\]

\[
P_{b2} = P_{b20}
\]

\[
P_{b3} = P_{b30}
\]

\[
P_L = P_{l0}
\]

\[
P_P = P_{p0}
\]

**FIGURE 4.7-168. (CONTINUED)**

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
LEGEND:

- Crew Compartment Pressure
- Lock Compartment Pressure
- Payload Compartment Pressure
- Avionics Bay 1 Pressure
- Avionics Bay 2 Pressure
- Avionics Bay 3 Pressure
- Ambient Pressure
- Ambient Temperature
- Compartment heat exchanger outlet temperature
- Crew Compartment Temperature
- Locl Compartment Temperature
- Payload Compartment Temperature
- Avionics Bay 1 Temperature
- Avionics Bay 2 Temperature
- Avionics Bay 3 Temperature
- Effective flow area of relief valves, lines, etc., between compartments
- Heat gain rate of crew compartment
- Heat gain rate of lock compartment
- Heat gain rate of Payload compartment
- Heat gain rate of Bay 1 compartment
- Heat gain rate of Bay 2 compartment
- Heat gain rate of Bay 3 compartment
- Electrical heat rate for compartment
- Heat leakage rate from compartment
- Metabolic heat rate
- Compartment volume
- Constant pressure specific heat of gas
- Constant volume specific heat of gas
- Gas Constant
- Specific heat ratio of gas
- Gas flow rate into compartment (x) from compartment y
- O2 gas flow rate into compartment y from compartment y.
- N2 gas flow rate into compartment y from compartment y.
- CO2 gas flow rate into compartment y from compartment y.
- H2O gas flow rate into compartment y from compartment y.

FIGURE 4.7-108. (CONTINUED)

4.7-340
\( m_{(o_2)}^X \) - X compartment \( O_2 \) gas quantity
\( m_{(n_2)}^X \) - X compartment \( N_2 \) gas quantity
\( m_{(co_2)}^X \) - X compartment \( CO_2 \) gas quantity
\( m_{(h_2o)}^X \) - X compartment \( H_2O \) gas quantity

FIGURE 4.7-108 (CONTINUED)
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\[ N_2 \text{ DIST-E} \]

\[ A_{\text{REG1}} = \frac{A_{\text{REG1}}(P_2, P_{\text{REG1}})}{\text{FLOW \ FLAG \ N2}} \]

1. \[ \text{NO} \quad \text{P}(x) > K_1 \quad \text{CLEAR} \]
2. \[ \text{YES} \quad \text{FLOW \ FLAG \ N2} \]

\[ \text{SET} \quad \text{P}(x) > K_1 \quad \text{NO} \]

\[ \text{CLEAR \ REG1 \ FLOW \ FLAG \ N2.} \]

\[ P_{\text{N2}} = P_{\text{REGI}}, \quad P_{\text{IN-1}} = P_2, \]
\[ P_{\text{IN-2}} = P_{\text{IN-1}}, \quad T_{\text{IN-1}} = T_2, \]
\[ T_{\text{IN-2}} = T_{\text{IN-1}}, \quad V_{\text{IN}} = V_{\text{REG1}}, \]
\[ A_{\text{IN1}} = A_{\text{REG1}}, \quad A_{\text{IN2}} = A_{\text{CV}}, \]
\[ R_{\text{G1}} = R_{\text{REG1}}, \quad V_{\text{m}} = V_{\text{REG1}}, \]
\[ \dot{Q}_{\text{m}} = Q_{\text{REG1}}(T_{\text{REG1}}), \quad \dot{C}_{\text{V1}} = C_{\text{REG1}}, \]
\[ \dot{C}_{\text{V1}} = C_{\text{CV REG1}}, \quad \dot{C}_{\text{V2}} = C_{\text{CV REG1}}. \]

\[ \text{CALL MANIFOLD GAS} \]

\[ \dot{m}(x) = \dot{m}_{\text{IN-2}}, \quad \dot{m}(x) = 0 \]

\[ \dot{m}(x) = \overline{m}_{\text{IN-2}}, \quad \dot{m}(x) = 0 \]

\[ \dot{m}_{\text{REG1}} = \frac{\dot{m}_{\text{IN-1}} - \dot{m}_{\text{REG1}}}{m_{\text{REG1}}}, \quad \dot{m}_{\text{REG1}} = \frac{\dot{m}_{\text{IN-1}} - \dot{m}_{\text{REG1}}}{m_{\text{REG1}}} \]

**FIGURE 4.7-109, N₂ SOURCE/DISTRIBUTION NETWORK REFERENCE MODULE MATH FLOW**

4.7-350

**MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST**
\( m_{\text{H}_2\text{O}-1} = m_{\text{H}_2\text{O}-1} \)
\( m_{\text{H}_2\text{O}-1} = m_{\text{m}} \)

\[
J_0 = Q_{\text{in}} \Delta t + (c_T)_{\text{H}_2\text{O}} m_{\text{H}_2\text{O}-1} \Delta T_{\text{H}_2\text{O}} + c_{\text{H}_2\text{O}} \left[ m_{\text{H}_2\text{O}} \Delta T_{\text{H}_2\text{O}} - m_{\text{H}_2\text{O}-0} \Delta T_{\text{H}_2\text{O}} + \dot{m}_{\text{H}_2\text{O}-1} \Delta T_{\text{H}_2\text{O}-1}\right] + \rho_{\text{H}_2\text{O}} \frac{\dot{m}_{\text{H}_2\text{O}}}{\Delta t} - \rho_{\text{H}_2\text{O}} \frac{\dot{m}_{\text{H}_2\text{O}-0}}{\Delta t} + \frac{\Delta}{2} C_2 \Delta t
\]

\[
T_{\text{H}_2\text{O}-1} = \frac{J_0}{(c_T)_{\text{H}_2\text{O}} (m_{\text{H}_2\text{O}-1})} + c_{\text{H}_2\text{O}} (m_{\text{H}_2\text{O}} + \dot{m}_{\text{H}_2\text{O}-1} \Delta t - \dot{m}_{\text{H}_2\text{O}-0} \Delta t)
\]

\[
V_{\text{H}_2\text{O}} = V_T + \frac{m_{\text{H}_2\text{O}} + \dot{m}_{\text{H}_2\text{O}-1} \Delta t - \dot{m}_{\text{H}_2\text{O}-0} \Delta t}{\rho_{\text{H}_2\text{O}}}
\]

\[
P_{\text{H}_2\text{O}-1} = \frac{m_{\text{H}_2\text{O}-1}}{V_{\text{H}_2\text{O}}} R_{\text{H}_2} T_{\text{H}_2\text{O}-1}
\]

\text{FIGURE 4.7-109. (CONTINUED)}

\text{4.7-352}

\text{MCDONNELL DOUGLAS AERONAUTICS COMPANY - EAST}
\[ A_{N2-17} = f(P_{N2-17}, P_{N2-51}) \]
\[ \dot{A}_{N2-17} = K_{N2-17} (T_e - T_{N2-17}) \]
\[ P_0 = P_{N2-17} \]
\[ \rho_0 = \rho_{N2-51} \]
\[ v = 1.4 \]
\[ R_0 = R_{0(u2)} \]
\[ T_{in} = T_{N2-51} \]

SET GAS FLOW FLAG.

CALL SUBROUTINE:
FLUID FLOW

\[ \dot{m}_{N2-17} = \frac{\dot{m}_{N2-17}}{V_{N2-17}} - \dot{m}_{N2-17} \]
\[ \dot{m}_{nu} = \dot{m}_{N2-17} - \dot{m}_{N2-17} \]
\[ T_{N2-17} = \frac{c_{V(u2)} m_{N2-17} T_{N2-17} + \dot{m}_{N2-17} \Delta t + c_{V(u2)} \dot{m}_{N2-17} \Delta t}{c_{V(u2)} [\dot{m}_{N2-17} + \dot{m}_{nu} \Delta t]} \]
\[ m_{N2-17} = m_{N2-17} + \dot{m}_{N2-17} \Delta t \]
\[ P_{N2-17} = \frac{m_{N2-17}}{V_{N2-17}} R_{0(u2)} T_{N2-17} \]

\[ \dot{A}_{N2-51} = K_{N2-51} (T_e - T_{N2-51}) \]
\[ T_{N2-51} = \frac{c_{V(u2)} m_{N2-51} T_{N2-51} + \dot{A}_{N2-51} \Delta t - \dot{m}_{N2-17} T_{N2-17} c_{P(u2)}}{c_{V(u2)} [\dot{m}_{N2-51} - \dot{m}_{N2-17} \Delta t]} \]
\[ m_{N2-51} = m_{N2-51} - \dot{m}_{N2-17} \Delta t \]
\[ P_{N2-51} = \frac{m_{N2-51}}{V_{N2-51}} R_{0(u2)} T_{N2-51} \]
LEGEND:

- $P_{\text{Reg}}$ - Cabin Pressure Regulator inlet pressure
- $P$ - Cabin Pressure (Crew Compartment)
- $P_{\text{O}_2-1}$ - $O_2$ Regulator (100 psi) outlet pressure
- $P_{\text{N}_2-1.7}$ - $N_2$ 170 psi Regulator outlet pressure
- $P_{\text{H}_2O-1}$ - $H_2O$ tank regulated pressure
- $P_{\text{N}_2-51}$ - $N_2$ 170 psi Regulator inlet pressure
- $T_c$ - Cabin temperature
- $T_{\text{Reg}}$ - Cabin pressure regulator inlet temperature
- $T_{\text{N}_2-1.7}$ - $N_2$ 170 psi pressure regulator inlet temperature
- $T_{\text{H}_2O-1}$ - $H_2O$ tank gas temperature
- $T_{\text{N}_2-51}$ - $N_2$ 170 psi regulator inlet temperature
- $V_{\text{Reg}}$ - Cabin pressure regulator inlet manifold volume
- $V_{\text{H}_2O-1}$ - Volume of $H_2O$ in $H_2O$ tank
- $V_T$ - Volume of $H_2O$ tank
- $V_{\text{N}_2-51}$ - Volume of manifold inlet to $N_2$ pressure regulator
- $V_{\text{N}_2-1.7}$ - $N_2$ 170 psi regulator outlet volume
- $A_{\text{Reg}}$ - Effective flow area of cabin pressure regulator
- $A_{\text{Reg}-\text{H}_2O}$ - Effective flow area of $H_2O$ tank pressure regulator
- $C_p$ - Specific heat at constant pressure
- $C_v$ - Specific heat at constant volume
- $C_{H_2O}$ - Specific heat of liquid water

- $m_{\text{O}_2}$ - $O_2$ flow rate into cabin
- $m_{\text{N}_2}$ - $N_2$ flow rate into cabin
- $m_{\text{N}_2-1.7}$ - Flow rate of $N_2$ 170 psi regulator
- $m_{\text{H}_2O-1}$ - $H_2O$ flow rate into $H_2O$ tank
- $m_{\text{H}_2O-0}$ - $H_2O$ flow rate out of $H_2O$ tank
- $m_{\text{N}_2}$ - $N_2$ quantity in $H_2O$ tank
- $m_{\text{O}_2-\text{Reg}}$ - Cabin pressure regulator inlet line $O_2$ mass quantity
- $m_{\text{N}_2-\text{Reg}}$ - Cabin pressure regulator inlet line $N_2$ mass quantity
- $m_{\text{H}_2O-1}$ - $H_2O$ tank gas quantity
- $m_{\text{N}_2-51}$ - $N_2$ 170 psi regulator inlet quantity

FIGURE 4.7-109 (CONTINUED)

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\( \gamma \) - Specific heat ratio (CP/CV)

\( \kappa \) - Gas constant
FIGURE 4.7-110  N₂ SOURCE FLOW CHART

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
LEGEND:

- $P_s$ - Tank pressure
- $P_{atm}$ - Ambient pressure
- $A_{ev}$ - Effective flow area of relief line/valve
- $T_s$ - Temperature of tank
- $T_{sc}$ - Tank compartment temperature
- $m_{se}$ - Flow rate through relief line
- $m_{so}$ - Flow rate to distribution system
- $m_s$ - Quantity of gas in source tank
- $P_{so}$ - Gas density in tank
- $W_{heater}$ - Tank electrical heater power
- $Q_{in}$ - Heat leak into tank
- $C_s$ - Gas specific heat
- $V_s$ - Tank volume

FIGURE 4.7-110, (CONTINUED)
**FLUID FLOW**

\[ K_n = \left( \frac{\gamma+1}{2} \right)^{\frac{1}{\gamma-1}} \]

\[ \frac{P_o}{P_{in}} \leq K_n \]

\[ M = \left\{ \left[ \left( \frac{P_o}{P_{in}} \right)^{\frac{1}{\gamma-1}} - 1 \right] \left( \frac{2}{\gamma-1} \right) \right\}^{\frac{1}{2}} \]

\[ M = 1 \]

\[ V_n = A \sqrt{2 \rho \left( \frac{P_{in}-P_{out}}{P_{in}} \right)} \]

\[ T_o = T_{in} \]

\[ V_o = \left[ \frac{2 \left( P_{in}-P_{out} \right)}{\rho} \right]^{\frac{1}{2}} \]

**LEGEND:**

- \( \dot{m} \) = Mass flow rate.
- \( T_o \) = Outlet flow temperature.
- \( P_o \) = Outlet pressure.
- \( T_{in} \) = Inlet temperature.
- \( P_{in} \) = Inlet pressure.
- \( R_g \) = Gas constant.
- \( \gamma \) = Specific heat ratio.
- \( A \) = Effective flow area.
- \( \rho \) = Density.

**FIGURE 4.7-111. FLUID FLOW SUBROUTINE FLOW CHART**

4.7-358

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Validation Methods and Check Cases

The verification approach for the ARPCS simulation module utilizes and expands upon the technique presented in Section 5.1. The use of this flow chart allows the comparison of the simulation module with various types of checkcases (test, analysis, software model, etc.). Figure 4.7-112 presents the flowchart for checkpoint generation subroutine in Figure 5.1-1. Figure 4.7-113 is the subroutine shown in Figure 4.7-112 as "COMBCHK" and generates the "all checkpoints sequenced flag".

Some liberty was taken in the notation for variables in these flow charts. With the exceptions of time (t), initialization time (to), computation time (Δt), and COMBCHK variables, the variables used represent a group or "set" of parameters rather than a single variable. Each parameter set is associated with a particular driver, function or logic. For example, the variable PAOS (JAOS) represents a set of parameters including pressure, O₂ quantity, etc. associated with the auxiliary O₂ supply. The identification of the actual parameters is dependent on exact system design and simulation fidelity desired.

This verification technique provides the following capabilities:
- Initialization of parameters
- Interfacing module drivers
- ARPCS functional element drivers
- Time-dependent evaluations
- Multiple evaluations in a single run.

Initialization - At the start of each checkcase the ARPCS module and driver parameters, logic, and conditions are set to pre-determined values. The values may change as the checkcase is allowed to continue.

External Module Drivers - The parameters normally provided by interfacing modules are provided by module drivers. These drivers supply parameter values which can be held constant or allowed to vary according to calculations performed within the driver. The following module drivers were identified:
FIGURE 4.7-112. CHECK POINT DRIVER, ATMOSPHERE REVITALIZATION PRESSURE CONTROL SUBSYSTEM (ARPCS) FLOWCHART
<table>
<thead>
<tr>
<th>Component</th>
<th>Initial Conditions</th>
</tr>
</thead>
<tbody>
<tr>
<td>Cryo2 Source</td>
<td>CRYIC (JCRY)</td>
</tr>
<tr>
<td>Active Thermal Control</td>
<td>ATCIC (JATC)</td>
</tr>
<tr>
<td>H2O Coolant</td>
<td>CLNTIC (JCLNT)</td>
</tr>
<tr>
<td>Potable H2O</td>
<td>H2OIC (JH2O)</td>
</tr>
<tr>
<td>Electric Power</td>
<td>ELPIC (JLTRC)</td>
</tr>
<tr>
<td>Fire Suppression</td>
<td>FSIC (JFIR)</td>
</tr>
<tr>
<td>Aux O2 Source</td>
<td>AOIC (JAOS)</td>
</tr>
<tr>
<td>N2 Source</td>
<td>N2SIC (JN2S)</td>
</tr>
<tr>
<td>Cabin Pressure Control</td>
<td>CPIC (JCBNP)</td>
</tr>
<tr>
<td>N2 Control Logic</td>
<td>CN2L (JN2L)</td>
</tr>
<tr>
<td>O2 Control Logic</td>
<td>CO2L (J02L)</td>
</tr>
<tr>
<td>Cabin Pressure Control Logic</td>
<td>CPCL (JCBNL)</td>
</tr>
<tr>
<td>O2 Distribution Network</td>
<td>DO2IC (J02N)</td>
</tr>
<tr>
<td>N2 Distribution Network</td>
<td>DN2IC (JN2N)</td>
</tr>
<tr>
<td>Active Thermal Control Parameters</td>
<td>PATC (JATC)</td>
</tr>
<tr>
<td>Cryo2 Parameters</td>
<td>PCRY (JCRY)</td>
</tr>
<tr>
<td>H2O Coolant Parameters</td>
<td>PCLNT (JCLNT)</td>
</tr>
<tr>
<td>Potable H2O Parameters</td>
<td>PH2O (JH2O)</td>
</tr>
<tr>
<td>Electric Power Parameters</td>
<td>PLTRC (JLTRC)</td>
</tr>
<tr>
<td>Fire Suppression Parameters</td>
<td>PFIR (JFIR)</td>
</tr>
<tr>
<td>Aux O2 Source Parameters</td>
<td>PAOS (JAOS)</td>
</tr>
<tr>
<td>N2 Source Parameters</td>
<td>PN2S (JN2S)</td>
</tr>
<tr>
<td>Cabin Pressure Control Parameters</td>
<td>PCBNP (JCBNP)</td>
</tr>
</tbody>
</table>

FIGURE 4.7-112 (CONTINUED)
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FIGURE 4.7-112 (continued)

4.7-352
MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-112 (CONTINUED)

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
4.7-363
FIGURE 4.7-112 (CONTINUED)
LEGEND:

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$t_0$</td>
<td>Universal time at initialization</td>
</tr>
<tr>
<td>$\Delta t$</td>
<td>Computation time</td>
</tr>
<tr>
<td>tCMIT</td>
<td>Limit on time</td>
</tr>
<tr>
<td>CMIT</td>
<td>Limit</td>
</tr>
<tr>
<td>CRY</td>
<td>Cryogenic element</td>
</tr>
<tr>
<td>ATC</td>
<td>Active Thermal Control Element</td>
</tr>
<tr>
<td>CLNT</td>
<td>Coolant element</td>
</tr>
<tr>
<td>H2O</td>
<td>$\text{H}_2\text{O}$ element</td>
</tr>
<tr>
<td>LTRC</td>
<td>Electric element</td>
</tr>
<tr>
<td>FIR</td>
<td>Fire Suppression element</td>
</tr>
<tr>
<td>AOS</td>
<td>Auxiliary $\text{O}_2$ element</td>
</tr>
<tr>
<td>N2S</td>
<td>$\text{N}_2$ source element</td>
</tr>
<tr>
<td>CBNP</td>
<td>Cabin Pressure element</td>
</tr>
<tr>
<td>N2L</td>
<td>$\text{N}_2$ logic element</td>
</tr>
<tr>
<td>O2L</td>
<td>$\text{O}_2$ logic element</td>
</tr>
<tr>
<td>CBNL</td>
<td>Cabin Logic element</td>
</tr>
<tr>
<td>O2N</td>
<td>$\text{O}_2$ network element</td>
</tr>
<tr>
<td>N2N</td>
<td>$\text{N}_2$ network element</td>
</tr>
<tr>
<td>J___</td>
<td>Indexing variable for indicated parameters</td>
</tr>
<tr>
<td>____IC</td>
<td>Indicated parameter initial conditions</td>
</tr>
<tr>
<td>P___</td>
<td>Parameters for indicated element</td>
</tr>
</tbody>
</table>

FIGURE 4.7-112 (COMPLETE)
FIGURE 4.7-113, FLOWCHART FOR ARPCS CHECKPOINT SEQUENCE

MCDONNELL DOUGLAS AEROSPACE CORPORATION
4.7-366
• Prsd Cryogenic O₂ supply - provides O₂ supply pressure temperature, quantity, etc.
• Active Thermal Control - provided cryogenic O₂ feed temperature, etc.
• ARS-H₂O Coolant - provides cabin temperature, CO₂ quantity, humidity, etc.
• Potable H₂O Management - provides quantity H₂O remaining (each tank), temperature, etc. for N₂ pressure quantity, etc. calculations.
• Electrical Power Distribution - provides bus voltages for logic, etc.
• Fire Suppression - provides freon quantity release rate into cabin for cabin pressure calculations, etc.

Functional Element Drivers - Certain intramodule parameters provide logic changes, etc. which require thorough verification. Drivers are included to provide ease in this verification. Those drivers identified were:

- Auxiliary O₂ source - parameters include tank pressure, quantity, etc.
- N₂ source - parameters include tank pressures, quantities, etc.
- Cabin pressure control - parameters include cabin total pressure, pressure decay rate, O₂ partial pressure, etc.

Multiple Evaluations - The sub-subroutine "COMBCHK" (Figure 4.7-113) generates the values of indexing variables controlling the checkcase conditions and determines when all check points have been sequenced (CHKPSEQ). Since the number of checkcases performed during a single run is the product of the number of parameter sets (LMT JCRY, etc.), care must be taken to prevent a large number of unnecessary checkcases being performed. Effort must be made to complete the module verification with a minimum number of checkcases. This may be best accomplished by restricting certain parameter sets to nominal values, while cycling through the more significant parameter sets. The run could then be repeated for different parameter sets.
ARPCS Data Base Impact

The major impact to the ARPCS data base is the impact of the reference module (Figures 4.7-107, 4.7-108, and 4.7-109) and the functional element/module drivers of Figure 4.7-112. Most processing subroutines (data input/output routines) would be common to all modules being validated. Data files are required for storage of the output data tables. The use of analysis/test/design requirements as reference data requires the use of special drivers. These drivers establish and maintain the conditions within and interfacing with the module which correspond to the analysis/test/design conditions. The plotting or formatting of the simulation results would require a few utility subroutines of small data base impact.
4.7.6.1.2 ARS-CACS Subsystem Description

The ARS Cabin Atmosphere Control Subsystem provides the circulation of the atmosphere, temperature and humidity control, and CO₂ and odor control. Figure 4.7-114 provides a simple schematic of the interfaces with other ECLSS modules.

Atmosphere Circulation - This subsystem provides atmosphere circulation for the crew quarters, and avionics bays. A simple schematic of the crew quarters circulation is shown in Figure 4.7-115 and the avionics bay schematic is shown in Figure 4.7-116.

Temperature Control - This element provides cooling and heating of the cabin atmosphere. Thermal transport is accomplished by means of two water loops, as shown in Figure 4.7-116. The primary and secondary loops are identical, except that the secondary loop has one water pump vice two as in the primary loop.

Heat rejection from the water loops to the ATCS is accomplished at the cabin interchanger through which both water loops and both ATCS freon loops flow. Two water sublimators receiving water from the potable water system provide an active heat sink during launch and orbital periods when the payload bay doors, housing the space radiator system on the underside, are closed. The sublimators are active during entry to an altitude of 100K feet. Between 100K feet and 20K feet there is no active heat rejection from the Orbiter, and temperatures are governed by the bulk thermal capacitance of the vehicle. Below 20K feet through landing, ammonia evaporators in the ATCS are activated for heat rejection.

Figure 4.7-115 from Reference 12 shows the Orbiter cabin atmosphere thermal and purification system. Three fans circulate cabin air through an aerosol filter, through lithium hydroxide canisters for CO₂ removal, then on through a condensing (cooling) heat exchanger for temperature and humidity control. Condensate is removed to the waste management system. The condensing heat exchanger is part of the water coolant loop system shown as the "cabin HX" in Figure 4.7-114. The cabin temperature is maintained by controlling the airflow through the cabin heat exchanger by means of a controller regulating bypass flow around the heat exchanger. The controller is regulated by a temperature selector. If cabin heat input is required the controller activates electric heaters in the bypass loop.
FIGURE 4.7-114 ENVIRONMENT CONTROL AND LIFE SUPPORT SUBSYSTEM (ECLSS) SCHEMATIC
FIGURE 4.7-115 ECLSS CABIN TEMPERATURE, HUMIDITY AND CO₂ CONTROL SCHEMATIC
FIGURE 4.7-116. PRIMARY WATER COOLANT LOOP SCHEMATIC
ARS-CACS Module Functions and Parameters

Figure 4.7-117 provides an overview of the ARS-CACS simulation module functional elements and interfaces with other modules. There are five basic functions performed within the module: air circulation, CO₂/H₂O control, H₂O coolant flow, thermal control, and control logic. Tables 4.7-31, 4.7-32, and 4.7-13 provide a listing of the atmosphere control module parameters. The following discussion is related to the calculations performed within each of the module elements.

Air Circulation - Air circulation calculations are provided for each of the three avionics bays and the crew quarters.
- Fan/Duct flow rates - These are functions of input voltages, air density, duct pressure drop and fan efficiency.
- Duct pressure drop - a function of air velocity, density, and duct configuration or branches.
- Condensate line inlet pressure - a function of pump outlet pressure and duct pressure drop.
- Duct air temperature - functions of cabin temperature, duct velocity, fan power, heat exchanger outlet temperature, air cooled equipment electrical power, and electrical heaters electrical power.

CO₂ Control - This control is provided for the crew quarters.
- CO₂ removal rate - a function of cabin CO₂ pressure, air flow rate through LiOH canisters, and air temperature.

H₂O Coolant Loop Flow - Calculates H₂O coolant loop flow rates and pressures.
- Pump flow rate - a function of input voltage, pump pressure rise, and inlet pressure.
- Loop pressure drop - a function of H₂O pump flow rate, H₂O temperature, and branch flow rates.
- Branch flow rates - functions of pump flow rates and cabin heat exchanger outlet H₂O temperature.
- Accumulator H₂O Quantity - a function of H₂O temperature.
- Accumulator Pressure - a function of H₂O quantity and temperature.
FIGURE 4.7-17 ATMOSPHERE REVITALIZATION SYSTEM, CABIN ATMOSPHERE CONTROL SUBSYSTEM, MODULE FUNCTIONAL ELEMENTS AND INTERFACES
### TABLE 4.7-31 WATER COOLANT LOOP MODEL INPUT DATA

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPEa</th>
</tr>
</thead>
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<tr>
<td>SPECIFIC HEATS</td>
<td>DB</td>
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<tr>
<td>HEAT TRANSFER COEFFICIENTS</td>
<td>DB</td>
</tr>
<tr>
<td>SOURCE HEAT CAPACITIES</td>
<td>DB</td>
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<tr>
<td>SOURCE TEMPERATURES</td>
<td>DB</td>
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<tr>
<td>LOOP TEMPERATURES</td>
<td>DB</td>
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<tr>
<td>INTERNAL HEAT LOADS</td>
<td>DB</td>
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<tr>
<td>TRAJECTORY AND ATTITUDE HEAT LOAD TABLES</td>
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<td>TRAJECTORY AND ATTITUDE</td>
<td>I</td>
</tr>
<tr>
<td>MISSION PHASE FLAGS</td>
<td>I</td>
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<tr>
<td>WATER PUMP/LOOP FLOW CHARACTERISTICS</td>
<td>DB</td>
</tr>
<tr>
<td>INTERFACING MODULE PARAMETERS</td>
<td>I</td>
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<td>WATER PUMP POWER</td>
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<tr>
<td>AVIONICS EQUIPMENT POWER</td>
<td>DB</td>
</tr>
<tr>
<td>AVIONICS BAY FAN/AIR FLOWRATE CHARACTERISTICS</td>
<td>DB</td>
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<td>AVIONICS BAY FAN POWER</td>
<td>DB</td>
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<td>WATER PUMP AND AVIONICS BAY FAN ON-OFF DISCRETES</td>
<td>I</td>
</tr>
<tr>
<td>AVIONICS EQUIPMENT ON-OFF DISCRETES</td>
<td>I</td>
</tr>
<tr>
<td>PORTABLE WATER USAGE</td>
<td>I</td>
</tr>
<tr>
<td>SUBLIMATOR OPERATING CHARACTERISTICS</td>
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</tr>
<tr>
<td>LIQUID COOLED GARMENT HEAT LOADS</td>
<td>DB</td>
</tr>
</tbody>
</table>

---

a DB - from Data Base  
I - Input
### Table 4.7-32 Water Coolant Loop Model Output Data

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Typea</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\text{H}_2\text{O}$ Accumulator Quantity - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>AVIONICS BAY 1 AIR FLOW</td>
<td>P</td>
</tr>
<tr>
<td>AVIONICS BAY 2 AIR FLOW</td>
<td>P</td>
</tr>
<tr>
<td>AVIONICS BAY 3 AIR FLOW</td>
<td>P</td>
</tr>
<tr>
<td>Sublimator Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
<tr>
<td>$\text{H}_2\text{O}$ Coolant Flow Rate - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>Sublimator 1 Vapor Vent Temp</td>
<td>P</td>
</tr>
<tr>
<td>Sublimator 2 Vapor Vent Temp</td>
<td>P</td>
</tr>
<tr>
<td>$\text{H}_2\text{O}$ Pump Outlet Pressure - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>AVIONICS BAY 1 Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
<tr>
<td>AVIONICS BAY 2 Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
<tr>
<td>AVIONICS BAY 3 Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
<tr>
<td>Cabin Interchanger Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
<tr>
<td>Source Temperatures (All Capacitive Loads)</td>
<td>P</td>
</tr>
<tr>
<td>Loop Temperatures (Non-Telemetered) - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>Flow Rates (Non-Telemetered) - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>Heat Transfer Rates (Non-Telemetered) - PCL &amp; SCL</td>
<td>P</td>
</tr>
<tr>
<td>$\text{H}_2\text{O}$ Pump Outlet Temp - PCL &amp; SCL</td>
<td>CP</td>
</tr>
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</table>

a  P - Performance Parameter  
CP - Critical Performance Parameter
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Type</th>
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</thead>
<tbody>
<tr>
<td>&quot;METABOLIC HEAT, CO₂ AND WATER PRODUCTION&quot;</td>
<td>DB</td>
</tr>
<tr>
<td>CABIN EQUIPMENT HEATING RATES</td>
<td>I</td>
</tr>
<tr>
<td>TRAJECTORY/ATTITUDE CABIN HEATING RATES</td>
<td>I</td>
</tr>
<tr>
<td>CABIN FAN PERFORMANCE DATA</td>
<td>DB</td>
</tr>
<tr>
<td>CABIN FAN ON-OFF DISCRETES</td>
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</tr>
<tr>
<td>LiOH CANISTER ON-LINE TIME</td>
<td>P</td>
</tr>
<tr>
<td>LiOH CANISTER PERFORMANCE CHARACTERISTICS</td>
<td>DB</td>
</tr>
<tr>
<td>TEMPERATURE SELECTOR SETTING</td>
<td>P</td>
</tr>
<tr>
<td>BULK CABIN THERMAL CAPACITANCE</td>
<td>DB</td>
</tr>
<tr>
<td>CONDENSING HEAT EXCHANGER CHARACTERISTICS</td>
<td>DB</td>
</tr>
<tr>
<td>CONTROLLER/BYPASS THROTTLE CHARACTERISTICS</td>
<td>DB</td>
</tr>
<tr>
<td>CABIN TEMPERATURE</td>
<td>CP</td>
</tr>
<tr>
<td>CABIN HUMIDITY</td>
<td>CP</td>
</tr>
<tr>
<td>CABIN CO₂ PARTIAL PRESSURE</td>
<td>CP</td>
</tr>
<tr>
<td>CABIN AIR FLOW RATE</td>
<td>CP</td>
</tr>
<tr>
<td>OUTLET HUMIDITY</td>
<td>P</td>
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<tr>
<td>OUTLET CO₂ PARTIAL PRESSURE</td>
<td>P</td>
</tr>
<tr>
<td>OUTLET TEMPERATURE</td>
<td>CP</td>
</tr>
<tr>
<td>CONDENSING Hx AIR FLOW RATE</td>
<td>P</td>
</tr>
<tr>
<td>CONDENSING Hx OUTLET AIR TEMPERATURE</td>
<td>P</td>
</tr>
</tbody>
</table>

a  P - Performance Parameter  
CP - Critical Performance Parameter  
I - Input
Thermal Control - Temperature calculations are provided for the H₂O coolant loops and interfacing module.

- Pump outlet temperature - a function of H₂O flow, pump inlet temperature, pump pressure rise, and pump input electrical power.
- Coldplate equipment temperature - functions of electrical power, inlet H₂O temperature, equipment temperature, and H₂O flow rate.
- Heat exchanger outlet H₂O temperatures - functions of inlet H₂O temperature, H₂O flow rate, interchange fluid inlet temperatures, and interchange fluid flow rate.
- Heat exchanger outlet interchange fluid temperatures - functions of interchange fluid inlet temperature and flow rate and the H₂O inlet temperature and flow rate.
- Accumulator H₂O inlet temperature - a function of cabin heat exchanger outlet H₂O temperature/flow rate, bypass temperature and flow rate.
- Pump inlet temperature - a function of the accumulator inlet temperature, accumulator temperature and H₂O flow rate.

ARS-CACS Reference Data Sources and Data Format

Various reference data sources exist for the ARS-CACS. Data concerning component and system performance requirements, predictions, and tests are available from References 31 and 72. In addition, several computer programs are available for development into a reference model or performing analyses. References 69 and 70 described component subroutines which can be combined to provide a system simulation reference module. Reference 73 is an ARS/ATCS performance routine designed for use with the Wang 700-series programmable calculator system. The use of this type of equipment allows an average runs time of five minutes per case, as opposed to hours or days turnaround with a regular computer facility. References 74 and 75 provide data for Orbiter heat exchanger calculations. The following discussion pertains to the development of an independent reference module.
Final performance evaluation of the simulator subsystems modules is best accomplished by evaluating the dynamic response of all crew station displayed and telemetered parameters pertaining to that subsystem, in a full-up simulation (all interfaces operating) of a mission phase or a transition from one mission phase to another. Certain parametric data, other than displayed data, is required to verify proper interfacing and coupling with other subsystem modules, e.g., the heat load from the H₂O coolant loops transferred to the ATCS.

Static check cases can be run with simpler verification models, however, the validation of simulator response to combinations of off-nominal operating conditions, insertion of malfunctions, etc., is not readily performed using simple check case models. The subject thermal and atmospheric control models are presented as examples of what a verification model involves in terms of input data and interface requirements. Maximum use should be made of existing hardware sizing and subsystem analysis programs with their data packages in developing an integrated verification module, e.g., Reference 69.

Primary and Secondary H₂O Coolant Loop Model - The math flow for the H₂O coolant loops model (COOLP) is shown in Figure 4.7-118. This model is applicable for generating static or programmed parametric variation check case data from a given set of input data, as well as generating performance data from a dynamic simulation run (whereby the simulator supplies the systems configuration and trajectory data). Basically COOLP calculates the outlet temperature of each heat transfer device in the order of the device position in the loop. Appropriate mixing calculations are performed at device output convergence points. Reference is made to three subroutines for calculating outlet temperatures for three types of heat transfer devices: a) coldplate, b) heat exchanger, and c) a direct heat load such as structural cooling, windows, etc.

COOLP uses an incremental time base for the computations. Typically the time increment would correspond to the computation cycle of the simulator module being checked. The device inlet temperature is related to the preceding device outlet temperature and assumed constant during the integration time period.
The PRI and SEC H$_2$O loops are identical except for flow rate, i.e., all heat transfer devices are serviced by both loops. The model combines the flow in both loops, and the calculated loop temperatures are applicable for both loops. Parameters for a non-operating loop could be set to some predetermined value based on the temperatures maintained by the operating loop.

The comp cycle begins at the outlet of the H$_2$O pumps and proceeds around the loop as shown in Figure 4.7-118 using internally calculated flow rates and heat loads as applicable. Not all the coolant loop flow paths are represented for the sake of simplicity, e.g., the avionics bay cold plates really consist of a series/parallel arrangement of cold plates for each piece of equipment. Some unidentified functions are those of the cabin interchanger bypass flow which is controlled by the cabin HX outlet temperature, and the sublimator operation.

Table 4.7-31 is a representative set of input data required to operate COOLP. A complete set of starting conditions is required including load source and loop temperatures. Data pertaining to vehicle and subsystem configuration is contained in a configuration array of discretes which is continuously updated during the course of a run. These data are used to internally compute flow rates and heat loads from tabular type input data. A number of scripted malfunctions can be handled by inputs to the configuration array.

Operational data such as heat capacities, heat transfer coefficients, etc., will probably not be available until late in the subsystem design/test stage; however, high fidelity data of this type is not required for accurate equilibrium solutions. Starting conditions (namely initial loop temperatures, bypass flow rates, etc.) can be determined and trimmed by running the model until it reaches equilibrium for given static heat loads and vehicle configuration.

The output parameters for directly evaluating the performance of the H$_2$O coolant loop module are listed in Table 4.7-32. All the telemetered parameters are available for display on any of four crew station CRT's via keyboard callup. Other parameters (such as avionics equipment case temperatures) can be checked.
using this model; however, they are not identified here. The output from COOLP can be used to provide checks on such things as equipment overtemp condition sensing and proper alarm response. Parameters such accumulator quantities are scripted unless a malfunction such as a leak is input, whereby internal computations would be made prior to outputting the data.

Cabin Atmosphere Control - The math flow for the cabin atmosphere control model (CABAIR) is shown in Figure 4.7-119. As with COOLP this model is capable of running prescribed check cases or evaluating a simulator run. The output from this model consists primarily of cabin temperatures, humidity, and CO₂ partial pressure profiles for given starting conditions and dynamic load conditions. The air flow into the system is based on the running status and performance characteristics of the three cabin fans. Flow rates through each of the LIOH canisters and the cabin HX are determined in order to calculate the CO₂ and water removal rates and heat transfer to the H₂O coolant loops or heat input to the cabin as required.

CO₂ Level

CO₂ is removed by passing cabin air over LIOH beds contained in a canister. The reaction (2 LIOH + CO₂ → Li₂CO₃ + H₂O) results in heat production as well as water which is removed by the subsystem. The efficiency of the LIOH canisters in removing CO₂ is a function of bed geometry and on-line time. The cabin CO₂ level is determined by the time integral of the net of the removal and metabolic production rates.

Cabin Temperature

Cabin air temperature is determined by calculating the net cabin heat production (or loss) and using appropriate starting conditions and thermal capacitance. Heat production sources include metabolic, cabin equipment, LIOH canister operation, and wall heating. The heat removal is governed by the cabin temp selector which controls the air flow through the cabin heat exchanger. The cabin heat exchanger heat removal rate in turn is a function of the running condition of the H₂O coolant loops and the ATCS.
FIGURE 4.7-119 REFERENCE MODULE, ARS CABIN ATMOSPHERE FLOWCHART
Cabin Humidity

The cabin humidity is determined by calculating the net cabin water production. Water sources include metabolic, food and waste management, LiOH canister operation, etc. The removal is a function of the cabin heat exchanger air flow rate, air inlet dew point and outlet air temperature. The calculated water removal rate is required by the condensate and urine storage model.

ARS-ACS Validation Methods and Check Cases

The methods of Sections 5.1 and 4.2 can be used to verify the ARS-ACS simulation module. These methods require the use of interface drivers (to provide interfacing module functions) and the module functional element drivers to establish and maintain desired conditions for each check case. Drivers are required for the following:

- ARS-ARPCS module
- Electrical Power Generation
- Electrical Power Distribution
- Active Thermal Control module
- Food, Water and Waste Management module

These drivers should provide capabilities for parameter initialization, transient response, steady state response, static inputs, and multiple check case execution during a single simulation run.

The check cases implemented should include step inputs with a comparison of the transient and steady-state responses. Initial check cases should also provide a thorough exercise of the module internal responses, as outlined in the design requirements documents. Latter check cases should implement refinements due to actual component and system design/tests. Actual systems/component test conditions can be input as a check case with simulation results compared directly to the test results. Other check cases should include the maximum, minimum, and nominal load conditions for each subsystem.

ARS-ACS Data Base Impact

The ARS-ACS reference module and the module drivers previously discussed represent a large impact to the simulation data base. Most of the processing subroutines (data input/output; data comparison) would be common to all modules being validated. Data files are required for input and output data tables.

4.7-335

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
4.7.6.2 Active Thermal Control System

The Active Thermal Control System (ATCS) provides the positive means of preventing orbiter equipment and fluids from exceeding permissible temperature extremes. This section describes the current system design, the expected simulation module's functions, identifies parameters associated with the module, and discusses techniques of verification of the module performance.

**ATCS Description**

The ATCS transfers heat from "heat sources" to "heat sinks" via a circulating fluid and interconnecting valves and tubing. The heat sources include coldplate mounted equipment, warmer fluids flowing through heat exchangers, and pumps. The heat sinks include fluid evaporators, colder fluids in heat exchangers, and the radiator. The heat sources and sinks are connected by controlling valves, tubing and fluid accumulators. The Orbiter uses two coolant loops which are identical, except that the primary loop has two pumps and accumulators, while the secondary loop has only one pump and accumulator. Figure 4.7-120 (see Refs. 75 and 78) is a schematic of the ATCS. A brief description of the major components and their pertinent performance characteristics follows.

**Fluid** - The circulating cooling liquid used in the Orbiter ATCS is Freon 21. The primary characteristics of interest are the density and specific heat, both of which vary with the fluid temperature. The consideration of these temperature variations in the simulation is dependent on the required fidelity.

**Pump(s)** - The role of the fluid pump is to provide the energy (pressure rise) necessary for circulation of the fluid through the loop components. The pump flow rate produced will vary with its input voltage and the system's resistance to fluid flow (pressure drop). Voltage regulation can be used to reduce the effects of the voltage variations. The system resistance (pressure drop) will vary with the selection of flow paths.

**Fluid Accumulators** - The purpose of the accumulator is to provide adequate system fluid volume for thermal expansion, slow leakage, and to provide adequate fluid pressure ranges throughout the expected temperature range. The major performance characteristics are the fluid volume and the pressure exerted on the fluid. The pressure is maintained by a sealed bellows.
FIGURE 4.7-120 ACTIVE THERMAL CONTROL SYSTEM (ATCS) SCHEMATIC
Heat Exchangers - Heat exchangers provide the means of transfer of heat from one fluid to another flowing fluid. The major performance characteristic of interest is the "overall heat transfer coefficient (UA)," which varies with the flow rates and inlet temperatures of the fluids. A second characteristic is the fluid's pressure drop as functions of the fluid flow rates. These pressure drop characteristics are used in determining the total system pressure drop and corresponding loop fluid flow rates.

Evaporators - The H$_2$O evaporator and NH$_3$ Boiler are essentially heat exchangers with one of the flowing fluids being allowed to vaporize within the exchanger. The energy required for the fluid's vaporization is absorbed from the fluid being cooled. This vaporizing fluid is operated "open-cycle" being vented overboard. The amount of cooling is dependent on the flow rate and the specific heat of vaporization of the fluid being evaporated. The effective heat transfer is therefore dependent on the cooled fluid inlet temperature and flow rate and the quantity rate of fluid evaporated.

The H$_2$O evaporator uses water from the H$_2$O management subsystem as the evaporating fluid. The NH$_3$ Boiler uses ammonia from three storage tanks for the evaporating fluid. The H$_2$O evaporator is used on-orbit when the payload bay door is closed. The NH$_3$ Boiler is used after entry, below 100K feet.

Coldplates - The coldplates provide heat transfer from the mounted equipment to the cooling fluid circulating through the coldplates. The primary performance characteristic is the effective thermal conductance. This characteristic varies according to the cooling fluid inlet temperature, flow rate and the mounted equipment temperature.

Radiator - The radiator cools the Freon 21 by radiating the heat into space. The heat rejection is dependent on the fluid inlet temperature, fluid flow rate, surface emissivity, surface absorptivity, and the surface area exposed to sunlight, earth, and space.
Control Logic - The exact switching logic is not currently known. The logic, however, represents the control inputs for pump operation, valve positioning, loop selection, etc. These inputs can be manual controls, radio frequency commands, or automatic equipment commands. The functions of the logic are normally dependent on the voltage level, pressure level, temperatures, etc.

ATCS Module Functions and Parameters

The functions provided by the ATCS module include calculations and performance determination pertaining to control logic, coldplates, heat exchangers, evaporators, radiator, and pumps. Figure 4.7-121 is a block diagram which illustrates the module functional elements and interfaces with other modules. Table 4.7-34 provides a listing of the parameters associated with the ATCS module. The following paragraphs describe the functions performed by each element.

Control Logic - This element provides logic determination of loop selection, pump enabling, valve positioning, etc., allowing control of the freon fluid flow rates, interfaces, temperatures, etc. Inputs would include manual switch and valve positions, radio frequency command, automatic commands, and computer commands. Most of these controls are dependent on electrical bus voltage levels to actuate relays, valves, or other circuits. The logic would also include the following:

- Bypass Valve Position controller: a function of the bus voltage(s) and \( H_2O \) evaporator outlet freon temperature, etc.
- Radiator Bypass Valve Position Control: a function of the bus voltage(s) and the radiator outlet freon temperature, etc.
- Radiator Flow Direction Valve Position: a function of the payload door position, etc.

Coldplates - This element provides the calculations of the thermal conditions of the coldplate mounted equipment and the effect on the coolant fluids. The coldplates cooled are the mid-fuselage, aft-fuselage, and DFI coldplates. The following calculations should be provided for each coldplate or group of coldplates:

- Equipment temperatures: functions of equipment mass, equipment specific heat, previous temperature, heat dissipation, coldplate freon inlet temperature, freon flow rate, freon specific heat, heat transfer of the coldplates, heat conduction to walls, etc.
FIGURE 4.7-121 ACTIVE THERMAL CONTROL MODULE FUNCTIONAL ELEMENTS AND INTERFACES
### TABLE 4.7-34. ACTIVE THERMAL CONTROL PARAMETERS

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>Electrical power bus voltages</td>
<td>I</td>
</tr>
<tr>
<td>Switches/control selections</td>
<td>I</td>
</tr>
<tr>
<td>Coldplate equipment heat loads or power</td>
<td>I</td>
</tr>
<tr>
<td>(DFI, AFT fuselage, MID fuselage)</td>
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</tr>
<tr>
<td>Heat exchangers (H₂O payload, Cryo 0₂, fuel cell, hydraulics 1/2,</td>
<td>I</td>
</tr>
<tr>
<td>fluid inlet temps./specific heats/flow rates</td>
<td></td>
</tr>
<tr>
<td>Heat exchanger UoA (overall heat transfer conductance)</td>
<td>I</td>
</tr>
<tr>
<td>Sun angle</td>
<td>I</td>
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<tr>
<td>Shuttle attitude</td>
<td>I</td>
</tr>
<tr>
<td>GSE heat exchanger freon outlet temp.</td>
<td>I</td>
</tr>
<tr>
<td>H₂O evaporator, H₂O inlet temp./pressure/flow rate</td>
<td>I</td>
</tr>
<tr>
<td>Freon pumps on - (primary: 1, 2; secondary)</td>
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<tr>
<td>Freon system, branch flow rates</td>
<td>P</td>
</tr>
<tr>
<td>Freon pump outlet pressure, pressure rise</td>
<td>CP</td>
</tr>
<tr>
<td>Freon accumulator position (quantity)</td>
<td>P</td>
</tr>
<tr>
<td>Freon temperature (into and out of coldplates, heat exchangers,</td>
<td>CP</td>
</tr>
<tr>
<td>radiator, evaporators)</td>
<td></td>
</tr>
<tr>
<td>Coldplate equipment temperatures (DFI, AFT &amp; MID fuselage)</td>
<td>CP</td>
</tr>
<tr>
<td>Heat exchangers - 2nd fluid outlet temperature</td>
<td>CP</td>
</tr>
<tr>
<td>(H₂O, payload, Cryo 0₂, fuel cell, hydraulics 1/2)</td>
<td></td>
</tr>
<tr>
<td>Evaporators - evaporation fluid outlet temperature/vapor pressure (NH₃, H₂O)</td>
<td>CP</td>
</tr>
<tr>
<td>Specific heats (freon, fluids, equipment)</td>
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<tr>
<td>Controlled valve positions</td>
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<td>(Diverter, flow proportioning, bypass, radiator bypass,</td>
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<tr>
<td>radiator flow direction, NH₃ evaporator valves, H₂O evaporator</td>
<td></td>
</tr>
<tr>
<td>valves, accumulator control valves)</td>
<td>P</td>
</tr>
<tr>
<td>NH₃ flow rate/quantity remaining/pressure</td>
<td>CP</td>
</tr>
<tr>
<td>Radiator temperatures</td>
<td>P</td>
</tr>
</tbody>
</table>

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CP = Critical Performance Parameter
P = Performance Parameter
I = Input
Heat Exchangers - This element provides the interface relationships and functions defining the thermal interchange with other modules. This interchange includes PRSD, Cryogenic O₂ heating for the ARPCS, fuel cell heat dissipation from the power generation circulation system, H₂O coolant loop heat transfer for the ARS, hydraulic fluid warming for the hydraulics systems, heat transfer from payload coolant loops and heat dissipation to the ground cooling loop of the prelaunch/launch module. The calculation of the fluid outlet temperatures are provided for each interface.

Outlet temperatures: functions of inlet fluid temperatures, fluid flow rates, heat conductance of the heat exchanger, and fluid specific heats.

Evaporators - This element provides the calculations associated with the NH₃ boiler subsystem and control of the H₂O evaporator as follows:

A. NH₃ Boiler
   1. Quantity NH₃ remaining: function of flow rate, flow time, leakage, vent rate, starting quantity for each of three tanks.
   2. Tank pressure: function of NH₃ quantity remaining, temperature, for each of three tanks.
   3. Tank vent flow: function of tank pressure, density.
   4. Evaporator NH₃ valve position: function of electrical bus voltage, evaporator outlet freon temperature.
   5. NH₃ evaporator flow rates: function of NH₃ tank pressure, valve position, and density.
   6. Freon outlet temperature: function of the inlet freon temperature, freon flow rate, specific heat, NH₃ flow rate, NH₃ inlet temperature, NH₃ specific heat, NH₃ heat of vaporization.
B. H₂O Evaporator

1. H₂O flow control valve position: function of bus voltage level, outlet freon temperature.
2. Outlet freon temperature: a function of H₂O flow rate, inlet freon temperature, freon flow rate, inlet H₂O temperature, specific heat of fluids, water heat of vaporization.

Radiator - This element determines thermal results and conditions for heat rejection.

- Radiator temperatures: function of the inlet freon temperature, freon flow rate, heat rejection, mass, specific heat, freon flow direction (payload door position).
- Radiator heat rejection: a function of the radiator temperature, vehicle attitude, vehicle state vector, beta angle, payload door position, freon flow direction.
- Radiator outlet freon temperature: a function of freon flow rate, inlet freon temperature, heat rejection, freon flow direction, radiator bypass valve position, specific heat, etc.

Freon Flow/Pressure/Temperatures - This element determines the freon system/branch flow rates, pressures, and integrated temperatures.

- System/Branch flow rates: functions of the system configuration, pump selection/enabling, freon temperatures, pump and equipment flow/pressure characteristics, bus voltage level.
- System pressures: functions of the flow rates, temperatures, accumulator quantities, flow/pressure characteristics, system configuration, bus voltage level.
- Integrated freon temperatures: function of mixing freon flow rates/temperatures, system configuration.
- Accumulator freon quantity: function of the freon leakage, flow rate, temperature.
ATCS Reference Data Sources and Formats

ATCS System and component design performance requirements, analysis, predictions, and tests provide data for direct comparison with the Shuttle simulation results. Figure 4.7-122 is an overview flow chart of a method of reference source selection and comparison. Reference 31 (updated at intervals) is a source of component and systems performance data regarding design requirements analysis, tests, and actual flight. Design requirements are available from Reference 76. The analysis and test results should be available from Shuttle design and evaluation groups.

In addition, several computer programs are available which can be used to develop suitable reference modules or to use in performing analysis of the system. References 69 and 70 provide descriptions of system component subroutines which can be combined to provide a reference module for the ATCS. The G189A program of Reference 69 was developed for JSC and is a versatile analytical tool for support of environmental systems work. Reference 73 describes an ARS/ATCS performance subroutine designed for use with the Wang 700 series programmable calculator. This subroutine allows an average run time of five minutes per case as opposed to hours or days turnaround when using the regular computer facilities. Figure 4.7-123 provides a overview flow chart of an ATCS reference module.

ATCS Validation Methods and Check Cases

The ATCS module can be verified by the techniques described in Sections 4.2 and 5.1. During the verification the following drivers are required to provide the necessary range of inputs and conditions for establishing each checkpoint.

- Electrical Power Generation
- PRS and D
- ARPCS
- ARS
- Payload thermal control loop
- Prelaunch/launch GSE cooling
- Hydraulic subsystem heating
- Food, H₂O, waste management
- Equations of motion
- Intra module functional elements

4.7-394
FIGURE 4.7-122 ACTIVE THERMAL CONTROL SYSTEM VERIFICATION OVERVIEW

4.7-395

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
FIGURE 4.7-122 (CONTINUED)

PERFORM SIMULATOR RUN

OUTPUT SELECTED PERFORMANCE PARAMETERS FOR MANUAL COMPARISON

EXIT
ATCS - R

(PUMP OPERATION)
\[ \dot{m}_p = f (\Delta P_D, E_b, \rho_f) \]
\[ T_{P-o} = f (T_{P-I}, W_p, \Delta P_D, \rho_f, \dot{m}_p) \]

(DUCT PERFORMANCE)
\[ \Delta P_D = f (\dot{m}_p, L_0, \mu_f, D_0, T_e) \]
\[ \dot{m}_b = f (\dot{m}_p, L_0, \mu_f, D_0, T_e) \]

(HEAT EXCHANGER PERFORMANCE)
\[ T_{F-OE} = f (\dot{m}_b, \dot{m}_i, T_{F-I}, T_{E-I}) \]
\[ T_{E-OE} = f (\dot{m}_b, \dot{m}_i, T_{F-I}, T_{E-I}) \]

(HEAT EXCHANGER COMPLETED)

(EVAPORATOR PERFORMANCE)
\[ A_v = f (\bar{T}_{F-OE}) \]
\[ \dot{m}_{EF} = f (P_E, P_E, A_v, T_e) \]
\[ \dot{m}_{EF} = f (\dot{m}_{EF}, \delta T) \]
\[ T_E = f (\dot{m}_{EF}, P_E, T_E, \dot{m}_{EF}) \]
\[ P_E = f (\dot{m}_{EF}, T_e) \]
\[ T_{E-OE} = f (\dot{m}_b, \dot{m}_{EF}, T_{E-I}, T_{E-I}) \]
\[ T_{E-OE} = f (\dot{m}_b, \dot{m}_{EF}, T_{E-I}, T_{E-I}) \]
\[ P_E = f (T_{E-OE}, \dot{m}_{EF}, P_{amg}) \]

ALL EVAPORATORS COMPLETED

FIGURE 4.7-123 ATCS REFERENCE MODULE OVERVIEW MATH FLOW

4.7-307

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
(RADIATOR PANELS)

\[ T_{F-OR} = f_1(\frac{T_{F-IR}}{T_{F-IR}}, \gamma, \dot{m}_{F-R}, \xi) \]

\[ T_{RS} = f_2(\frac{T_{F-IR}}{T_{F-IR}}, \gamma, \dot{m}_{F-R}, \xi) \]

---

FIGURE 4.7-123 (CONTINUED)
LEGEND:

- \( A_v \) - Effective flow area of control valves
- \( m_{ev} \) - Evaporator fluid quantity
- \( \dot{m}_p \) - Pump freon flow rate
- \( \dot{m}_b \) - Freon loop branch flow rate
- \( \dot{m}_{ji} \) - Heat exchanger Interfaces circuit flow rate
- \( \dot{m}_{ep} \) - Evaporator fluid flow rate
- \( \dot{m}_{fr} \) - Freon flow rate through radiator
- \( \gamma \) - Sun rays incidence angle with radiator panel
- \( \alpha \) - Earth view angle with radiator panels

- \( T_a \) - Freon average temperature
- \( T_b \) - Branch freon temperature
- \( T_{oh} \) - Heat exchanger freon outlet temperature
- \( T_{ohf} \) - Heat exchanger interface circuit outlet temperature
- \( T_{in} \) - Heat exchanger freon inlet temperature
- \( T_{inh} \) - Heat exchanger Interface circuit inlet temperature
- \( T_{of} \) - Evaporator outlet freon temperature
- \( T_g \) - Evaporator fluid tank temperature
- \( T_{of} \) - Evaporator outlet evaporation fluid temperature
- \( T_{in} \) - Evaporator freon inlet temperature
- \( T_{in} \) - Evaporator inlet evaporation fluid temperature
- \( T_{inr} \) - Radiator inlet freon temperature
- \( T_{or} \) - Radiator outlet freon temperature
- \( T_{rs} \) - Temperature of radiator surface

- \( \Delta P \) - Freon loop pressure drop
- \( L_P \) - Freon loop effective length
- \( L_B \) - Effective branch length
- \( D_P \) - Freon loop flow diameter
- \( D_B \) - Branch flow diameter
- \( \mu \) - Freon viscosity
- \( \varepsilon \) - Freon loop effective roughness

- \( P_E \) - Evaporator storage tank pressure
- \( P_r \) - Evaporator pressure on evaporation fluid circuit
- \( P_{amb} \) - Ambient pressure

FIGURE 4.7-123 (CONTINUED)
The system design requirements (see Ref. 76) provide component and system maximum/minimum acceptable performance levels. These requirements should provide the initial check case conditions. The results of various contractor- and NASA-performed analysis, studies, and evaluations can provide higher fidelity verification check cases. Later, data from actual systems and component tests as well as actual flight performance can be used to establish the more severe verification check cases for both the module and the individual functional elements.

The check cases should include the exercise of each individual functional element and of the module functioning as a unit. The approach for individual functional element verification is to nullify or isolate all interaction with other elements and allow the calculation of selected outputs for controlled input parameters.

**ATCS Data Base Impact**

The ATCS reference module and the ATCS module drivers as previously discussed will have a large impact on the simulator data base. The processing subroutines (such as data input/output and data comparison) are of small impact, and most of them will be common to all the modules being validated.

**4.7.6.3 Food, Water and Waste Management (FWWM)**

This system provides control, storage and utilization of food, water and waste. The simplified schematic of the water subsystem (from Ref. 78) is shown in Figure 4.7-124. Figure 4.7-125 is a schematic of the waste management subsystem (also from Ref. 78).

**FWWM System Description**

**Food Management** - This subsystem provides for the storage and preparation of crew meals.

**Water Management** - The water management subsystem provides for the collection of fuel cell product water, storage in the three potable water bottles, and subsequent delivery to water sublimators, overboard dumps, airlock, and food management subsystem.

**Waste Management** - This subsystem provides for the collection, storage, and disposal of condensate (from the ARS subsystem) and human waste.
FIGURE 4.7-124 ECLSS WATER MANAGEMENT SUBSYSTEM
FIGURE 4.7-125 ECLSS WASTE MANAGEMENT SUBSYSTEM
FWWM Module Functions and Parameters

The food management system is a lower-deck function, and thus will not be dynamically simulated. The waste management system only requires the condensate collection (flow rate) to be dynamically simulated. The water management subsystem, however, interfaces dynamically with the fuel cell and ARS-water coolant loop (water sublimators). The module performance parameters are identified in Table 4.7-35.

Water Management - This functional element provides the following calculations.
- Water flow rates to using outlets - functions of the tank pressures, outlet pressures, and effective flow areas.
- Tank H₂O quantities - functions of initial quantity, flow rates, and time.

Waste Management - This functional element provides the calculation of the condensate flow rate from the condensing heat exchanger to the urine storage tank or vacuum dump. The flow rate is a function of the heat exchangers inlet pressure, condensate quantity and tank pressure.

FWWM Reference Data Sources and Formats

FWWM subsystem design requirements, analysis, and test results can be used for module verification. In addition, certain math models described in previous portions of Section 4.7.6 can be utilized for this module. Figure 4.7-126 to calculate the liquid flow rates, can be developed into a suitable reference module. Those portions that are not dynamically simulated can be functionally provided by a performance profile (i.e., a tabular function of time). Reference 31, 77, and 12 are sources of component and subsystem performance requirements and data.

FWWM Validation Methods and Check Cases

This module can be verified by the techniques described in Section 4.2 and 5.1. Module drivers are required to provide the fuel cell inlet water flow rates, water sublimator pressure, water tank pressure/temperature, and condensing heat exchanger inlet pressure. Check cases can be developed utilizing component and systems maximum and minimum performance design requirements, analysis, and system evaluations.
### TABLE 4.7-36  FOOD, WATER AND WASTE MANAGEMENT PARAMETERS

<table>
<thead>
<tr>
<th>PARAMETER</th>
<th>TYPE&lt;sup&gt;a&lt;/sup&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Condensate heat exchanger H&lt;sub&gt;2&lt;/sub&gt;O quantity/pressure</td>
<td>I</td>
</tr>
<tr>
<td>Ambient pressure</td>
<td>I</td>
</tr>
<tr>
<td>Fuel cell water flow rates/temperatures</td>
<td>I</td>
</tr>
<tr>
<td>Water chiller and heater flow rates</td>
<td>I</td>
</tr>
<tr>
<td>Water sublimator pressure</td>
<td>I</td>
</tr>
<tr>
<td>Water container pressure/temperature</td>
<td>I</td>
</tr>
<tr>
<td>Water sublimator pressure regulator flow areas</td>
<td>P</td>
</tr>
<tr>
<td>Water container water quantities</td>
<td>CP</td>
</tr>
<tr>
<td>Fan/Separator flow rates</td>
<td>P</td>
</tr>
<tr>
<td>Urine tank quantities/pressures</td>
<td>P</td>
</tr>
</tbody>
</table>

<sup>a</sup> P = Performance Parameter  
CP = Critical Performance Parameter  
I = Input Parameter
FIGURE 4.7-126 POTABLE WATER MANAGEMENT FLOW CHART

4.7-405

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\[ \Delta m_{\text{in}} = \sum_{i=1}^{N} \Delta m_{\text{in},i} - N \cdot m_{\text{in}}^{0} + \Delta m_{\text{n}} \]

\[ T_i = c \cdot m_{\text{m}} \cdot T_{\text{m}} + \sum_{j=1}^{N} \Delta m_{\text{n},j} \Delta t \left[ c \cdot T_{\text{m},j} + \frac{1}{2} v_{\text{n},j}^2 + \frac{1}{\chi} (P_{\text{n},j} - P_{\text{a},j}) \right] \]

\[ T_2 = \sum_{j=1}^{N} \Delta m_{\text{n},j} \Delta t \left[ c \cdot T_{\text{m},j} + \frac{1}{2} v_{\text{n},j}^2 + \frac{1}{\chi} (P_{\text{n},j} - P_{\text{a},j}) \right] \]

\[ T_{\text{m}} = \frac{T_i - T_2}{c \cdot m_{\text{m}}} \]

\[ I = I + 1 \]

\[ \Delta \rho_{\text{m}} = \rho_{\text{m}} - \rho_{\text{m}}^{0} \]

\[ \rho_{\text{m}} = \frac{\rho_{\text{m}}^{0}}{1 - \varepsilon_{\text{m}}} \]

\[ \varepsilon_{\text{m}} = \frac{\Delta \rho_{\text{m}}}{\rho_{\text{m}}^{0}} \]

\[ I \geq N \]

RETURN

FIGURE 4.7-126 (CONTINUED)

4.7-406

MCDONNELL DOUGLAS ASTRONAUTICS COMPANY - EAST
LEGEND:

\( P_{t} \) — Pressure of \( j^{th} \) load

\( P_{m} \) — Manifold pressure

\( P_{s,i} \) — Source pressure of \( i^{th} \) tank

\( T_{w,i} \) — Source temperature of \( i^{th} \) tank fluid

\( \dot{m}_{i,m} \) — Liquid flow rate from \( i^{th} \) tank into manifold

\( \dot{m}_{o,j} \) — Liquid flow rate from manifold to \( j^{th} \) load

\( T_{m,i} \) — Liquid temperature into manifold from \( i^{th} \) tank

\( T_{o,j} \) — Fluid temperature delivered to \( j^{th} \) load

\( v_{i,m} \) — Fluid velocity from \( i^{th} \) tank into manifold

\( v_{h,o,j} \) — Fluid velocity from manifold to \( j^{th} \) load

\( T_{m} \) — Fluid temperature in manifold

\( \rho \) — Fluid density

\( m_{m} \) — Fluid mass in manifold

\( m_{i,o} \) — \( i^{th} \) tank fluid quantity

\( c \) — Fluid specific heat

\( \Delta t \) — Time increment

\( A_{m,i} \) — Flow area from \( i^{th} \) tank into manifold

\( A_{o,j} \) — Flow area from manifold to \( j^{th} \) load

\( V_{i,o} \) — Volume of fluid in \( i^{th} \) tank

FIGURE 4.7-126 (CONTINUED)
FWWM Data Base Impact

Impact to the simulation data base is small. The reference module should be relatively simple. Few drivers are required, and the comparison/processing subroutines would be common to other simulation modules.
SECTION 5
METHODS FOR VALIDATING PERFORMANCE

The process of simulation validation consists of exercising a simulation with properly-chosen inputs, gathering the output performance parameter data it generates in response to these inputs, and comparing these data to reference data representing the real world which the simulation is intended to represent. Support software required to efficiently perform these operations is briefly discussed below. Additional detail will be provided in a later report.

5.1 VALIDATION SOFTWARE STRUCTURE

Figure 5-1 depicts a support-software organization suitable for the generation, handling, comparison and display of simulation and reference data required to perform simulation software validation. A complete validation software system will consist of a basic "driver" or executive (denoted SOFCHK in the figure) and a set of service routines, briefly identified in Table 5-1.

These routines will, of course, vary in degree of generality. Routines GENPT, SIMMOD, and CHKMOD must be completely "customized" for each simulator module being validated. Routine DREAD will be a data-driven input routine, designed to be compatible with the basic data-output structure of the simulator being validated. Finally, routines DWRITE and DSPLAY should be highly independent of the characteristics of the module being validated. The greater the degree of generality designed into the support software, of course, the less specialized coding and setup required to validate each individual module.
CALL GENPT (GENERATE A CHECK POINT)  

EXTERNAL DATA RUN  
YES

CALL READ (SELECT ONE RECORD OF SIMULATOR DATA)  

HAVE ALL CHECK POINTS BEEN SEQUENCED  
YES

CALL SIMMOD (GENERATE ONE RECORD OF SIMULATOR DATA)  

WRITE END OF FILE ON DATA FILE  
YES

WAS END OF FILE ENCOUNTERED  
NO

CALL CHKMOD (GENERATE CHECK DATA CORRESPONDING TO SIM.-DATA)  

CALL DWRITE (WRITE SIMULATOR & CHECK DATA ON DATA FILE)  

END

CALL DISPLAY (PROCESS DATA FILE & OUTPUT DATA LISTINGS & PLOTS)  

REPRODUCIBILITY OF THE ORIGINAL PAGE IS POOR

FIGURE 5-1. VALIDATION SOFTWARE OVERALL FLOW
### TABLE 5-1. VALIDATION SUBROUTINES\(^a\)

<table>
<thead>
<tr>
<th>SUBROUTINE</th>
<th>PURPOSE</th>
</tr>
</thead>
<tbody>
<tr>
<td>DREAD</td>
<td>Reads records from a data tape or disc file generated during a simulator performance run; selects data for the appropriate module and places it into a data array.</td>
</tr>
<tr>
<td>GENPT</td>
<td>Generates a checkpoint which includes all data required for input into the module to be verified.</td>
</tr>
<tr>
<td>SIMMOD</td>
<td>Interfaces with the simulation software module and places the input and output data into a data array.</td>
</tr>
<tr>
<td>CHKMOD</td>
<td>Interfaces the &quot;reference&quot; software module and places the input and output data into a data array compatible with the simulation software data array.</td>
</tr>
<tr>
<td>DWRITE</td>
<td>Writes the data from the simulator software module and the reference module onto a data file to be used for comparison processing.</td>
</tr>
<tr>
<td>DSPLAY</td>
<td>Processes the data file written by DWRITE. Performs automated comparisons of simulation and reference data, and/or generates listings and plots for manual comparison of data. Incorporates a variety of differencing techniques and comparison criteria.</td>
</tr>
</tbody>
</table>

\(^a\)Math flows and comprehensive discussions of these routines will be provided in a later report.
5.2 DATA ACQUISITION AND FORMATTING

For efficient manual or automatic comparison of the reference and simulation performance-parameter data, it is necessary that these data be put into compatible formats.

The means for manual comparison will almost always be a time-history plot of the system module's response to its inputs. If both the reference and simulation data are in machine-readable form, service routines may be used to overplot them on the same set of axes, in any convenient scale. In many cases, however, the reference data will be in the form of external hard-copy, previously plotted. It is then necessary that the service routines used for plotting the simulation performance-parameter data allow full control of scaling, to force the simulation data plot to be exactly comparable to the reference data plot. Then manual comparison can be accomplished by simply overlaying the two plots.

For automatic comparison, the reference and simulation data will have to be put out on temporary files, which are compatible with respect to units, axes, machine code (BCD/EBCDIC, 7-track/9-track, etc.), and time spacing. Generally, the process of ensuring compatibility will be undertaken by the module drivers. In some cases, however, it will be necessary to reprocess an existing data-file; e.g., machine-code conversion, time interpolation.

5.3 COMPARISON METHODS AND CRITERIA

As previously mentioned, manual comparison will normally be performed by overplotting data available to the machine, or by overlaying a newly-generated data plot on an existing plot. The comparison criteria in manual
comparison will generally be more or less subjective, based upon the validator's experience with similar simulation programs, knowledge of the overall fidelity standard of the particular simulator, known inaccuracies in the basic data (e.g., aerodynamic coefficients), and the importance of the particular performance parameter to the validity of training or procedures development to be done on that simulator.

To accomplish automatic validation, it is necessary that such subjective criteria be translated into objective terms, and then into some machine algorithm (maximum error, average percent error, integral of squared error, etc.) which assigns a numerical value to the degree of mismatch between the reference and simulation data time-histories. Finally, this mismatch value must be compared to a numerical acceptance value, beyond which the fidelity is considered unacceptable. The choice of mismatch algorithms and acceptance values will require considerable judgement and experience. In practice, the validator will often use these computed mismatch values as a guide in perturbing the values of simulation parameters (gains, time constants, etc.), attempting to secure the best possible match.
SECTION 6
CONCLUSIONS AND RECOMMENDATIONS

1. Attention should be concentrated upon the "critical" performance parameters of each simulation module in performing simulation validation.

2. There are four general classes of reference data sources for simulation validation: closed-form solutions, independent math models, existing analysis/simulation programs, and test data. Each has particular advantages and disadvantages.

3. The SUDS and SSFS subroutine libraries offer many potential reference modules for simulation validation. However, modifications will be necessary in many cases.

4. Driver routines will be needed for module validation exercises -- both to provide the inputs representing interfacing modules, and to ensure format compatibility between the reference and simulation modules.

5. Service routines will be required for printout, plotting, data comparison, and data base management.

6. Most simulation modules will require both static and dynamic check cases for thorough validation.

7. Modules must be validated in isolation, as well as at various stages of simulation integration.
SECTION 7
REFERENCES


   APU, SD72-SH-104-2, Volume 4-2.
   Docking Mechanism Subsystem, SD72-SH-0102-2, Volume 2-3.
   Hydraulics, SD72-SH-106-2, Volume 2-6.
   Landing/Deceleration Subsystem, SD72-SH-0102-1.


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