CONTACT DYNAMICS MATH MODEL
INTERIM REPORT
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1.0 Introduction

The Space Station Mechanism Test Bed consists of a hydraulically driven, computer controlled six degree of freedom (DOF) motion system with which docking, berthing, and other mechanisms can be evaluated. Shown in Figure 1, the Test Bed facility simulates the docking of two orbiting vehicles, a target and chaser. The chase vehicle docking mechanism is attached to the six DOF motion system, while the target's mechanism is fixed to the ceiling of the facility. A force and moment sensor is mounted in the ceiling above the target docking fixture. Contact forces and moments due to hardware mechanism operation are measured in six degrees of freedom and provided to the simulation host computer to enable representation of orbital contact dynamics. The old contact dynamics simulation model in use represented a restricted case in which one body was considered much larger than the second and therefore unaffected by the docking forces and moments.

The purpose of this report is to describe the development of a generalized math model to eliminate the restrictive assumptions of the old model. This new model represents the relative motion between two rigid orbiting vehicles. These vehicles are acted on by forces and moments from vehicle contact, attitude control systems, and gravity. The resulting model allows motion in six degrees of freedom for each body, with no vehicle size limitation. The new computer simulation is modular to facilitate the addition or deletion of various parts of the model.

This report derives the translational and rotational equations of motion for the vehicles in the model. The method used to transform the forces and moments from the sensor location to the vehicles' centers of mass is also explained. The interface between the dynamics math model and the overall
simulation consists of the relative position, velocity, and orientation between the vehicles, and the contact forces and moments. This interface is thoroughly discussed. Two math models of docking mechanisms, a simple translational spring and the RMS end effector, are presented along with simulation results. The translational spring model is used in an attempt to verify the simulation with compensated hardware in the loop results. Finally, recommendations are made at the end of the report to upgrade and improve the simulation.
2.0 Equations of Motion

Figure 2 depicts two rigid vehicles undergoing small deviations from a nominal circular orbit. The target vehicle is denoted by the number one and the chaser is labeled number two. The following coordinate frames and points are used by the simulation. Coordinate frame E is an inertial frame fixed at the center of the earth. In this frame, the X and Z axes are fixed in the equatorial plane with Z pointing at the vernal equinox. Y points to the North Pole. The local vertical frame, L, rotates on a circular path of radius Ro at a constant angular rate of \( \omega_L \). The Z axis of the local vertical frame lies along \( \mathbf{R}_0 \), the position of the local vertical frame with respect to the inertial frame. The X axis lies in the plane of the orbit and is tangent to the orbit path, while Y is the orbit normal. The orientation of the L frame with respect to the E frame is defined through a 2-3-2 Euler angle sequence of the following angles. The first two angles, the ascending node angle and the angle of inclination, are constant. The third angle, the orbit angle, is equal to its initial value plus the product of \( \omega_L \) and time. The \( V_1 \) and \( V_2 \) frames are fixed at the centers of mass of the target and chase vehicles, respectively, and located with respect to the local vertical by the position vectors \( \mathbf{R}_1 \) and \( \mathbf{R}_2 \). The D1 and D2 frames are docking port frames located at arbitrary positions with respect to the vehicles' centers of mass by the vectors \( \mathbf{R}_{D1V1} \) and \( \mathbf{R}_{D2V2} \). A sensor coordinate frame, \( S_1 \), is located arbitrarily on the target vehicle with respect to \( V_1 \) by the vector \( \mathbf{R}_{S1V1} \).

The inertial angular velocities of the target and chase vehicles are labeled \( \omega_1 \) and \( \omega_2 \). \( m_1 \) and \( m_2 \) are the masses of the target and chase vehicles, respectively, while \( I_1 \) and \( I_2 \) are the inertia dyadics about the centers of mass.
The translational equations of motion will now be derived for the target vehicle. Those of the chase vehicle will be identical. All forces, except gravity, such as vehicle contact and control forces, are included in the vector $f$. Referring to Figure 3, the coordinate frame $U$ lies in the plane of the orbit such that the $U_3$ axis is parallel to the $Y$ axis of the local vertical frame. The position vector $R_0$ is therefore defined by equation (1).

$$R_0 = R_0 \cos \omega_L t \, U_1 + R_0 \sin \omega_L t \, U_2$$

(1)

$t =$ time

The constant angular rate of the local vertical frame, $\omega_L$, is given by equation (2)

$$\omega_L = \left(\frac{GM}{R_0^3}\right)^{1/2}$$

(2)

$G =$ Universal Constant of Gravitation

$M =$ Mass of the Earth

Differentiating equation (1) twice with respect to time leads to equation (3).

$$\ddot{R}_0 = -R_0 \omega_L^2 \left( \cos \omega_L t \, U_1 + \sin \omega_L t \, U_2 \right)$$

(3)

$R_1$ is the position vector of the target vehicle center of mass with respect to the local vertical. From Newton's third law, the sum of the forces acting on the vehicle must equal the time rate of change of the linear momentum.

$$m \left( \dot{R}_0 + \dot{R}_1 \right) = F_g + f$$

(4)
The force due to gravity is defined in equation (5)

\[ F_g = \frac{-GMm_1}{(R_0 + R_1)^3}(R_0 + R_1) \]  

(5)

If it is assumed that \( |R_1| \ll |R_0| \) then using the Binomial theorem and keeping only first order terms in \( R_1 \), the gravitational force can be written as

\[ F_g = -GMm_1(R_0 + R_1)(\frac{1}{R_0^3})\left[1 - \frac{3R_1 \cdot R_0}{R_0^2}\right] \]  

(6)

Using equation (2), equation (6) can be written as in (7).

\[ F_g = -m_1 \omega_L^2(R_0 + R_1)(1 - \frac{3R_1 \cdot R_0}{R_0^2}) \]  

(7)

Substituting (7) into (4) yields equation (8).

\[ \ddot{R}_1 = -\omega_L^2 R_1(1 - \frac{3R_1 \cdot R_0}{R_0^2}) + \omega_L^2 R_0\left(\frac{3R_1 \cdot R_0}{R_0^2}\right) + \frac{f}{m_1} \]  

(8)

In order to express the components of (8) in the rotating local vertical frame, the following notation is now defined.

\[ \dot{\bar{R}} = \ddot{R} + \omega_L \times \bar{R} \]  

(9)

\( \dot{\bar{R}} \) is the time derivative of \( \bar{R} \) as seen by an observer fixed in inertial space. \( \ddot{\bar{R}} \) is the time derivative of \( \bar{R} \) as seen by an observer in the local vertical frame. Since \( \omega_L \) is constant, (9) can be differentiated with respect to time to produce (10).
Using equations (8) and (10), and ignoring second order effects, the following equations are generated to govern translational motion of the vehicle.

\[
\ddot{X}_1 = -2 \omega_L \dot{Z}_1 + f_x/m_1 \\
\dot{Y}_1 = -\omega_L^2 Y_1 + f_y/m_1 \\
\ddot{Z}_1 = 2 \omega_L \dot{X}_1 + 3 \omega_L^2 Z_1 + f_z/m_1
\]

In these equations, \(X_1, Y_1,\) and \(Z_1\) define the components of \(\mathbf{R}_1\) with respect to the local vertical frame. This formulation avoids the numerical problems of referencing the vehicle position from the center of the earth. This is especially useful for contact dynamics simulations which require the relative position between the vehicles.

The rotational equations of motion for the target and chase vehicles are the well known Newton - Euler equations shown in (14).

\[
\mathbf{I} \cdot \dot{\mathbf{\omega}} = -\mathbf{\omega} \times \mathbf{I} \cdot \mathbf{\omega} + \mathbf{T}
\]

\(\mathbf{\omega} = \text{Angular Velocity of Vehicle}\)
\(\mathbf{I} = \text{Inertia Dyadic about Vehicle Center of Mass}\)
\(\mathbf{T} = \text{Torques Acting about Vehicle Center of Mass}\)
The torque vector consists of gravity gradient, contact, and attitude control system torques. Equation (14) is expressed in a vehicle fixed frame so that the inertia dyadic will remain constant. This equation does not limit the body axes to align with the principal moment of inertia axes. In other words, the inertia matrix does not have to be diagonal. The gravity gradient torque acting on the body is expressed in equation (15).

\[ T_g = \mathbf{3} \omega_l^2 \frac{\mathbf{R}_o}{\mathbf{R}_o} \times \mathbf{I} \cdot \frac{\mathbf{R}_o}{\mathbf{R}_o} \]  

(15)

The Newton–Euler equations are not restricted to small angle rotations of the vehicle.
3.0 Force/Moment Transformation

The math model assumes that a force/moment sensor is located at some arbitrary position on the target vehicle which corresponds to its position on the ceiling fixture of the 6 DOF facility. However, since the sensor location is not at the center of mass of either vehicle, the measured values must be transferred to these points.

The sensor will measure the resultant forces and torques acting on the target vehicle due to hardware contact. If contact occurs at more than one point, the force vector measured will be the sum of these contact forces. The moment measured will be the resultant torque acting on the target vehicle about the sensor location due to the multiple contact forces and moments. The force and moment transformation method presented here is independent of the number of contact points.

It is assumed that the inertial forces acting on the moving parts of the docking mechanism are negligible. This assumption is valid when the moving mass of the docking mechanism is small compared to the mass of the vehicle. If this assumption is not violated, then the contact forces and moments are equal and opposite between the target and chase vehicles.

Referring to Figure 2, \( \overline{RS_1V_1} \) and \( \overline{RS_2V_2} \) are the position vectors from the target and chase vehicle centers of mass to the sensor. \( \overline{F_s} \) and \( \overline{M_s} \) are now defined as the force and moment values from the sensor. \( \overline{F_t}, \overline{M_t}, \overline{F_c} \) and \( \overline{M_c} \) are defined as the forces and moments acting at the target and chase vehicles' centers of mass. The forces and moments from the sensor can now be transferred to the vehicles' centers of mass through the following equations.

\[
\overline{F_t} = \overline{F_s} \quad (16)
\]
\[ F_c = -F_S \]  

\[ M_t = M_s + RS1V1 \times F_S \]  

\[ M_c = -M_s - RS1V2 \times F_S \]
4.0 Relative Vehicle Motion

The purpose of the math model is to generate the relative motion between the target and chase vehicles when acted on by contact, gravity, and control system forces and torques. This data will be used to generate the commands for the six DOF motion system.

As seen in Figure 2, RD2D1 is the position of the chase docking port with respect to the target docking port. It is calculated through equation (20).

\[
RD2D1 = R2 + RD2V2 - R1 - RD1V1
\]  

(20)

The relative vehicle velocity is defined as the velocity of the chaser docking port as seen by an observer on the target docking port. Equation (21) defines the relationship between the time derivative of a vector as seen by observers fixed in rotating coordinate frames.

\[
\dot{A} = \dot{\dot{A}} + \omega_{CB} \times \dot{A}
\]  

(21)

\( \dot{A} \) = Time derivative of \( A \) with respect to B frame.

\( \dot{\dot{A}} \) = Time derivative of \( \dot{A} \) with respect to C frame.

\( \omega_{CB} \) = Angular velocity of C frame with respect to B frame.

Equation (20) is differentiated with respect to time to produce (22).

\[
RD2D1 = \dot{R}2 + \dot{RD}2V2 - \dot{R}1 - \dot{RD}1V1
\]  

(22)
Using (21), the following relations are now presented.

\[ \mathbf{R}_{D2V1} = \mathbf{R}_{D2V1} + \mathbf{\omega}_1 \times \mathbf{R}_{D2V1} \]  

(23)

\[ \mathbf{R}_{D2V2} = \mathbf{R}_{D2V2} + \mathbf{\omega}_2 \times \mathbf{R}_{D2V2} \]  

(24)

\[ \mathbf{R}_1 = \mathbf{R}_1 + \mathbf{\omega}_1 \times \mathbf{R}_1 \]  

(25)

\[ \mathbf{R}_2 = \mathbf{R}_2 + \mathbf{\omega}_2 \times \mathbf{R}_2 \]  

(26)

\[ \mathbf{R}_1 = \mathbf{R}_1 + (\mathbf{\omega}_2 - \mathbf{\omega}_1) \times \mathbf{R}_2 \]  

(27)

Substituting (23) through (27) into (22) produces the desired result shown in equation (28).

\[ \mathbf{R}_{D2V1} = \mathbf{R}_{D2V1} + (\mathbf{\omega}_2 - \mathbf{\omega}_1) \times \mathbf{R}_2 + 
\]

\[ (\mathbf{\omega}_2 - \mathbf{\omega}_1) \times \mathbf{R}_{D2V2} - \mathbf{R}_1 - \mathbf{\omega}_1 \times \mathbf{R}_1 \]  

(28)
The angular velocity of the chase vehicle with respect to the target vehicle is given in equation (29)

\[
(\omega)_{21} = (\omega)_2 - (\omega)_1
\]
5.0 Simulation Description

The computer code of the dynamics math model is written entirely in FORTRAN 77 and is modular in form. There is a driver routine called by the host simulation which controls the math model and acts as the interface to the host simulation.

Figure 4 depicts the program flow as directed by the driver in the dynamic loop. The first pass through the program initializes the necessary variables. The program input consists of raw force and moment sensor data and OMV control system stick commands. The force and moment sensor data is filtered and transferred to the vehicles’ centers of mass. The stick commands are used to generate control forces and torques acting on the chase vehicle. These forces and moments are used in the equations of motion which are solved numerically for the relative position and velocity between the vehicles.

The following nomenclature used throughout the code is now presented. Position and translational velocity vectors begin with the letter \( \mathbf{R} \). The position vector \( \mathbf{R}_{ABC} \) is defined as the vector from point \( B \) to point \( A \) expressed in \( C \) frame coordinates. \( \mathbf{R}_{ABCD} \) is the time derivative of \( \mathbf{R}_{ABC} \). Angular velocity vectors begin with the letters \( \mathbf{OM} \). \( \mathbf{OM}_{ABC} \) is defined as the angular velocity of \( A \) with respect to \( B \) in \( C \) frame coordinates. The transformation matrix \( [AB] \) transforms vectors from the \( B \) frame to \( A \) frame as shown in equation (30)

\[
\mathbf{R}^A = [AB] \mathbf{R}^B
\]  

(30)

The labels used to describe the vehicles and geometry of Figures 2 and 3 are the same as those in the code.
FORCE SENSOR → FMTRAN → CNTRLC → CHASE → TARGET → INTEGRATE → INTFAC
RELATIVE MOTION

RETURN

Figure 4
The program common blocks and subroutines will now be discussed. A
detailed list of definitions of the global variables is included in Appendix
1. However, most variable definitions are given in comments throughout the
code. A program listing of the math model is in Appendix 2.

There are four files which contain the common blocks and global vari-
ables used throughout the code. These files are simply included in the
necessary subroutines of the program.

The file labeled cmmnbb.f is composed of all variables needed to inter-
face the dynamics routine with the host simulation. The common block PASS
consists of the variable JPASS, a program counter used in the OMV control
system. The variable JPASS counts the number of passes through the dynamic
loop. Common block INT1 contains the variable NNN. NNN may have four dif-
ferent integer values from -1 to 2. A value of -1 is used for the first ini-
tialization of the program, while a value of 0 is for program initialization
between runs. In the dynamic loop, this variable has the value of 1, and a
value of 2 is used for an end of run print of thruster on times. JPASS and
NNN are generated in the host simulation to be used in the dynamic math
model.

The common block CADIN is composed of the seven element array KDAT. The
first 6 elements are X, Y, Z translation and roll, pitch, yaw rotation stick
commands for the OMV control system. The seventh element is an attitude rate
hold switch. The common block sensor consists of the ten element array KIN
and the integer flags NOUSE, IFREEZ, IFLAG, and IPOT. The first 6 elements
of KIN are X, Y, Z, and roll, yaw, pitch signals from the force and moment
sensor. Element 7 is the freeze flag and element 8 is used to reset the
offset forces. Element 9 is the IPOT flag. The dynamic model uses the KIN
array to calculate the contact forces and moments, and to generate the four integer flags. Common block TIME is composed of the variables T, DT, DT2, and TD. T is time. DT and DT2 are the simulation cycle and half cycle times. TD is a time delay used in the OMV control system. All of these variables are set in the host simulation to be used by the dynamics routine. The common block RELATIVE contains the output of the dynamics math model. The vector RD2DlD1 is the position vector from the target docking port to the chase docking port, in target docking port coordinates. RD2DlDlD is the velocity of the chaser docking port with respect to the target docking port, in target docking port coordinates. OMV2VlV2 is the angular velocity of the chase vehicle with respect to the target vehicle, in chase vehicle coordinates. D1D2 is the transformation matrix from the chaser docking port frame to the target docking port frame.

The common blocks of the file cmmn.f, STAT, EARTH, and TRANS, define the size of the state vectors and necessary orbital parameters. In particular, OMO is the constant angular velocity of the local vertical frame, and XLE is the transformation matrix from the E to L frame.

The files cmmn1.f and cmmn2.f contain the variables pertaining to the target and chase vehicles, respectively. Appendix 1 should be consulted for a listing of the variable definitions of these files. The equivalence statements in these files should be noted. Y1, Y2, YD1, and YD2 are defined as the state and state dot vectors for the target and chase vehicles. The state vectors are composed of the vehicle angular momentum vectors, quaternions, and translational velocity and position vectors.

The file cmmncon.f contains the variables associated with the NASA OMV control system.
The file dyn.f is the subroutine DYNAMIC. This subroutine is the driver for the math model as shown in Figure 4. This subroutine will be called at time T by the host simulation, with no argument list, in order to obtain the relative vehicle motion data at time T + DT. The subroutine uses the 3-1 integration scheme, with the previous state dot values stored in the arrays YD01 and YD02. The first pass through DYNAMIC initializes the state and state dot vectors, vehicle mass properties and geometry, control system parameters, and the force and moment sensor scaling factors. After this first pass, the routine begins at the top of the dynamic loop with the force and moment transformation routine. The state and state dot vectors are then calculated and integrated. The vehicle relative motion data contained in the common block RELATIVE is generated and returned to the host simulation.

The subroutines CHASE and TARGET are located in the files chase.f and target.f. These routines calculate the state dot vectors for both vehicles. The first three elements of the state dot vector are components of the time derivative of the angular momentum vector. This vector is generated using equation (14) with the chase vehicle having additional torques due to the control system. The next four elements of the state dot vector are the result of the quaternion differential equations in (31) and (32).

\[
\dot{q} = \frac{1}{2} \left( q \cdot \omega + q \times \omega \right) \tag{31}
\]

\[
\dot{q}_4 = -\frac{3}{2} \omega \cdot q \tag{32}
\]

\(q\) = Vector Part of Quaternion  
\(q_4\) = Scalar Part of Quaternion  
\(\omega\) = Vehicle Angular Velocity Vector
The quaternions of the state vectors relate the vehicle fixed frames to inertial space. The next three terms of the state dot vectors are the vehicle accelerations with respect to the local vertical frame. These accelerations are calculated through equations (11) through (13). The force terms for the chase vehicle contain contributions from the OMV control system as well as the contact forces. The remaining terms of the state dot vector are the vehicle center of mass velocities with respect to the local vertical frame.

The file cntrlc.f contains the subroutines CNTRLC, QLIM1, and LOGIC which comprise the NASA OMV control system. Control system stick commands are input to the routines through the array KDAT. The resultant forces and moments about the chase vehicle center of mass are output in the V2 frame. These forces and moments are labeled FJX, FJY, FJZ, MX, MY, and MZ.

Subroutine FMTRAN, located in the file fmtran.f, takes in raw data from the force and moment sensor through the integer array KIN. This data is then scaled and filtered to produce the contact forces and moments acting on the target vehicle at the sensor location. From these values, the forces and moments acting at the target center of mass are calculated using equations (16) and (18), and those acting at the chase vehicle center of mass through (17) and (19).

File intfac.f contains the subroutine INTFAC. This subroutine generates the relative vehicle position, velocity, angular velocity, and orientation. This subroutine also calculates other transformation matrices used throughout the model. The relative vehicle position and velocity, RD2D1D1 and RD2D1D10, are generated through equations (20) and (28). The relative angular velocity of the chase vehicle with respect to the target vehicle, OMV2Y1V2, is computed using equation (29) with the resulting vector in the V2 frame.
The file libjg.f consists of various math library subroutines. Many of these routines handle routine matrix vector operations. There is a matrix inverse routine for 3 x 3 matrices and also routines which generate direction cosine matrices from quaternions and vice versa.

Subroutine STARTT of the file start.f defines the vehicles' mass properties and geometry. The orbital parameters and initial transformation matrices are also input. The effects of gravity can be nullified by setting the variable GMEK to zero. This variable is the product of the universal gravitational constant and the mass of the earth. This will fix the local vertical frame in space. The control system parameters are also set at the end of this subroutine.
6.0 Simulation Verification

Before integration of the math model with the host simulation, the dynamic model must be verified. The entire contact dynamics simulation must be validated upon integration before any confidence can be placed in the hardware tests.

The math model was checked out by two means. First, simple forces and moments were applied to the vehicles in each axis with the results verified by hand. The OMV control system was exercised by commanding translational accelerations and angular rates for the different axes and tracking the response of the chaser. More complex runs were then made to verify Hill's equations, orbital effects, and the Newton-Euler equations. These runs were verified through other contact dynamics simulations at Control Dynamics.

The math model has been successfully transferred to the VAX computer and again checked out. The necessary changes have been made to interface it with the host simulation. The integrated simulation can now be validated by using simple springs as the docking mechanism. After the compensation tests are completed, real time results can be generated for various initial condition runs.

An analytic model of the spring system will be used to duplicate the real time results. For the case presented here, a linear translational spring is attached to the chase vehicle shown in Figure 5. The unit vector along the 1 axis of D2, \( \mathbf{U}_1 \), coincides with the spring. \( \mathbf{R}_{rel} \) is the position vector of the D1 frame with respect to D2. Contact between the target vehicle and the spring is checked by comparing the equilibrium spring length to the component of \( \mathbf{R}_{rel} \) along \( \mathbf{U}_1 \). If contact is made, equal and opposite forces proportional to the spring compression are applied to the vehicles.
The equations governing these contact forces are (33) and (34).

\[
\begin{align*}
|R_{\text{rel}} \cdot U_1| &> L_{\text{eq}}, \quad F_c = 0 \\ (33) \\
|R_{\text{rel}} \cdot U_1| &< L_{\text{eq}}, \quad F_c = -K_s(L_{\text{eq}} - R_{\text{rel}} \cdot U_1)U_1 \\
(34)
\end{align*}
\]

Leq = Spring Equilibrium Length
Ks = Spring Constant
Fc = Contact Force Acting on Chase Vehicle

Figure 6 depicts the run scenario used to generate the results of Figures 7 and 8. The target vehicle is fixed in space with the chase vehicle approaching it at a rate of 0.5 inches per second. The effects of gravity have been neglected; therefore, the local vertical frame is fixed in space. The chase vehicle has a mass of 326.23 slugs, and the spring constant is 50 pounds per inch. The simulation cycle time or integration step size is 35 milliseconds. Since damping has been neglected in the model, the vehicle exit velocity should be 0.5 inches per second. Figure 7 shows the vehicle velocity versus time. When the velocity is zero, the spring compression, and force, is a maximum. This is seen in Figure 8. The velocity is presented in the local vertical frame, while the forces are plotted in the S1 or sensor frame. These results would compare favorably with the real time results for a perfect system with no time lag or numerical problems.
Figure 6
CHASE VEHICLE

VELOCITY ft / sec

TIME sec

Figure 7
7.0 **RMS End Effects Math Model**

In section 6, an analytical model of the translational spring was used to generate contact forces in place of the actual hardware. These forces were fed into the dynamic math model in place of those measured by the sensor in order to generate the vehicles' responses. This section describes the analytic model of the RMS end effector based on the method of soft constraints. To apply this method, a set of constraint equations describing the end effector are derived. Small violations of these constraints are permitted, but forces proportional to the violation are applied normal to the constraining surfaces.

There are three possible points of contact, shown in Figure 9, for which constraint equations are derived. First, there is probe to snare cable contact. Second, the shoulders at the base of the probe can hit the grooves in the collar of the end effector. And third, the shoulders may strike the flat of the collar and miss the grooves. It is assumed that there is no contact between the probe and the inner walls of the end effector. Damping is also neglected.

Figure 10 depicts two orbiting vehicles with the relative position between the two docking ports denoted by $r_F$. The $D1$ coordinate frame of the target vehicle is fixed to the tip of the probe or grapple fixture. The $D2$ frame is at the center of the top of the end effector.

Figure 11 shows the grapple fixture and the snare cables in an arbitrary position. With the grapple fixture inside of the end effector and snared by the cables, then the constraint equations governing the probe position are (35) and (36).

\[ \tilde{d} \geq 0 \] (35)

29
POSSIBLE POINTS OF CONTACT

- PROBE TO CABLE
- SHOULDER TO GROOVE
- SHOULDER TO COLLAR

Figure 9
Figure 10
Figure 11
\( \delta = 0 \)  \hspace{1cm} (36)

Equation (35) simply states that once the probe is snared, it may not leave the cylinder of the end effector. Equation (36) implies that the probe should remain in the center of the triangle formed by the three snare cables. If these equations are violated, then the forces of equations (37) and (38) are applied to the probe.

\[
\vec{F} = K \vec{d} \hspace{1cm} (37)
\]

\[
\vec{F} = K \vec{\delta} \hspace{1cm} (38)
\]

\( K = \text{Snare Cable Stiffness} \)

Figure 12 depicts the relative positions of the shoulders of the grapple fixture and the collar of the end effector. \( \vec{S} \) is the position vector from the tip of the probe to the outer edge of a shoulder. \( \vec{G} \) is the position of the center of a groove with respect to the origin. The width of each groove is \( W \). \( \vec{g} \) is the position vector from a given groove to a given shoulder. \( \vec{e} \) is calculated from equation (39) for each shoulder and groove combination.

\[
\vec{e} = \vec{S} - \vec{r} - \vec{G} \hspace{1cm} (39)
\]

The constraint equation governing the shoulder position is given by equation (40)
Figure 12
\[ \mathbf{e} \cdot \mathbf{n}_2 \geq 0 \]  

(40)

This equation simply states that the shoulder may not pass through the collar. However, if equation (40) is violated, then there is either shoulder to groove or shoulder to collar contact. If there is shoulder to groove contact, then the component of \( \mathbf{e} \) along \( \mathbf{n}_1 \) will be less than half the groove width. For shoulder to groove contact, the force of equation (41) is applied to the shoulder.

\[ |\mathbf{e} \cdot \mathbf{n}_1| \leq \frac{w}{2}, \quad F_S = -K\mathbf{e} \]  

(41)

\( K \) = Collar Material Stiffness

The collar stiffness is generally of the order of ten thousand pounds per foot. If the component of \( \mathbf{e} \) along \( \mathbf{n}_1 \) is larger than the groove half width, then there is shoulder to collar contact. The shoulder force is given by equation (42).

\[ |\mathbf{e} \cdot \mathbf{n}_1| > \frac{w}{2}, \quad F_S = K|\mathbf{e} \cdot \mathbf{n}_2| \mathbf{n}_2 \]  

(42)

This force is applied to the shoulder in the direction normal to the collar.

The analytic contact force model of the RMS end effector has been implemented into the simulation and exercised. In order to use this model to verify real time results of tests using the end effector, the carriage motor speed and material stiffness should be investigated to learn more accurate values.
8.0 Conclusions and Recommendations

In fulfillment of the contract objective, a generalized math model has been developed to represent the relative motion between two rigid six degree of freedom orbiting vehicles. The model has no restrictions on vehicle size and is modular in form. The NASA OMV control system has been integrated into the model. The dynamics math model is coded in FORTRAN 77 and is currently working on the VAX 11-750 of the docking facility. The interface has been defined to merge the math model with the host simulation and verify with actual real time tests.

In the future, the math model will be examined in an effort to reduce the simulation cycle time. The math model will be modified to streamline the leg length calculations. Control Dynamics will also support the three point contact study through structural analysis and continued improvement of the math model.
AE - Transformation from E Frame to Orbit Plane
AIV1 - Inertia of Target Vehicle about Center of Mass in V1 frame
AIV1I - Inverse of AIV1
AIV2 - Inertia of Chase Vehicle about Center of Mass in V2 Coordinates
AIV2I - Inverse of AIV2
DT - Cycle Time
DT2 - Half Cycle Time
D1D2 - Transformation from D2 to D1 Coordinates
D1L - Transformation from L to D1 Coordinates
D1V1 - Transformation from V1 to D1 Coordinates
D2L - Transformation from L to D2 Coordinates
D2V2 - Transformation from V2 to D2 Coordinates
F1CL - Contact Force Acting on Target Vehicle in L Coordinates
F1CS1 - Contact Force from Sensor in S1 Coordinates
F2CL - Contact Force Acting on Chase Vehicle in L Coordinates
F2CS1 - Contact Force Acting on Chase Vehicle in S1 Coordinates
FJX, FJY, FJZ - OMV Control System Forces in V2 Frame
HTV1 - Angular Momentum of Target Vehicle
HTV2 - Angular Momentum of Chase Vehicle
IFLAG - Flag Used in Sensor Offset Forces
IFREEZ - Freeze Flag Set by KIN
JPASS - Counter of Dynamic Loop Passes
JPOT - Flag Set by KIN
KDAT - Array of Joystick Commands for OMV Control System
KIN - Array of Force and Moment Sensor Values and Flags
MASS1 - Mass of Target Vehicle
MASS2 - Mass of Chase Vehicle
MX, MY, MZ - OMV Control System Torques about Chase Vehicle Center of Mass in V2 Coordinates
NNN - Initialization Variable
NST - Dimension of State Vector
OMO - Angular Velocity of L Frame
OMOSQ - OMO Squared
OMV1 - Angular Velocity of Target Vehicle in V1 Coordinates
OMV2 - Angular Velocity of Chase Vehicle in V2 Coordinates
OMV2V1V2 - Angular Velocity of Chaser with Respect to Target in V2 Coordinates
QV1E - Target Vehicle Quaternions Relating V1 and E Frames
QV2E - Chase Vehicle Quaternions Relating V2 and E Frames
RD1V1V1 - Position Vector of Target Docking Port with Respect to V1 in V1 Coordinates
RD2D1D1 - Position Vector of Chaser Docking Port with Respect to Target Docking Port in D1 coordinates
RD2D1D - Time Derivative of RD2D1D1
RD2V2V2 - Position Vector of Chase Docking Port with Respect to V2 in V2 Coordinates
RNU2 - Current Orbit Angle
RNU20 - Initial Orbit Angle
RS1V1V1 - Position Vector of Sensor with Respect to V1 in V1 Coordinates
RS1V1S1 - Position Vector of Sensor with Respect to V1 in S1 Coordinates
RS1V2S1 - Position Vector of Sensor with Respect to V2 in S1 Coordinates
RIL - Position Vector Target Vehicle with Respect to L Frame
RILD - Velocity Vector of Target Vehicle with Respect to L Frame
R2L - Position Vector of Chase Vehicle with Respect to L Frame
R2LD - Velocity Vector of Chase Vehicle with Respect to L Frame
S1L - Transformation from L to S1 Coordinates
S1V1 - Transformation from V1 to S1 Coordinates
S1V2 - Transformation from V2 to S1 Coordinates
T - Time
TD - OMV Control System Time Delay
T1CGV1 - Contact Torque Acting at Target Center of Mass in V1 Coordinates
T1CGS1 - Contact Torque Acting at Target Center of Mass in S1 Coordinates
T1CS1 - Contact Torque at Sensor in S1 Coordinates
T1G - Target Vehicle Gravity Gradient Torque in V1 Coordinates
T2CGS1 - Contact Torque Acting about Chase Vehicle Center of Mass in S1 Coordinates
T2CGV2 - Contact Torque Acting about Chase Vehicle Center of Mass in V2 Coordinates
T2G - Gravity Gradient Torque Acting on Chase Vehicle in V2 Coordinates
V1L - Transformation from L to V1 Coordinates
V1E - Transformation from E to V1 Coordinates
V2E - Transformation from E to V2 Coordinates
V2L - Transformation from L to V2 Coordinates
XLE - Transformation from E to L coordinates
Y1 - Target Vehicle State Vehicle
YD1 - Target Vehicle State DOT Vector
YD01 - Previous Value of YD1
Y2 - Chase Vehicle State Vector
YD2 - Chase Vehicle State Dot Vector
YD02 - Previous Value of YD2
APPENDIX 2

PROGRAM LISTING
THIS FILE CONTAINS THE NECESSARY COMMON BLOCKS TO INTERFACE
THE NASA DOCKING SIMULATION WITH THE CONTROL DYNAMICS DOCKING
DYNAMICS SUBROUTINE

INTEGER*2 KIN(10), KDAT(7)
INTEGER IFREEZ, NOUSE, IPOT, IFLAG, JPASS, NNN

REAL T, DT, DT2, TD
REAL RD2D1D1(3), RD2D1D1D(3), OMV2V1V2(3), D1D2(3,3)

COMMON /PASS/ JPASS
COMMON /INT1/ NNN
COMMON /CADIN/ KDAT
COMMON /SENSOR/ KIN, NOUSE, IFREEZ, IFLAG, IPOT
COMMON /TIME/ T, DT, DT2, TD
COMMON /RELATIVE/ RD2D1D1, RD2D1D1D, OMV2V1V2, D1D2

T IS TIME
DT IS THE CYCLE TIME
DT2 IS HALF OF THE CYCLE TIME
TD IS TIME DELAY FOR THE OMV CONTROL SYSTEM

JPASS IS A PROGRAM PASS COUNTER FOR THE OMV CONTROL SYSTEM

NNN IS INITIALIZATION VARIABLE

KDAT IS A 7 ELEMENT VECTOR FROM THE JOY STICK OF THE OMV
CONTROL SYSTEM. THE FIRST 6 ELEMENTS ARE X, Y, Z TRANSLATION
AND ROLL, PITCH, AND YAW. ELEMENT 7 IS FOR THE ATTITUDE RATE
HOLD SWITCH.

KIN IS A 10 ELEMENT VECTOR FROM THE FORCE/MOMENT SENSOR.
THE FIRST 6 ELEMENTS ARE X, Y, Z, AND ROLL, YAW, PITCH IN
SENSOR COORDINATES. ELEMENT 8 IS USED TO RESET THE OFFSET
FORCES. THE FREEZE FLAG IS SET EQUAL TO ELEMENT 7.
IPOT IS SET EQUAL TO ELEMENT 9.

RD2D1D1 IS THE POSITION VECTOR FROM THE TARGET DOCKING
PORT TO THE CHASE DOCKING PORT IN TARGET DOCKING PORT
COORDINATES.

RD2D1D1D IS THE VELOCITY VECTOR OF THE CHASE DOCKING PORT
WITH RESPECT TO THE TARGET DOCKING PORT IN TARGET DOCKING
PORT COORDINATES.

OMV2V1V2 IS THE ANGULAR VELOCITY VECTOR OF THE CHASE VEHICLE
WITH RESPECT TO THE TARGET VEHICLE IN CHASE VEHICLE COORDINATES.
D1D2 is the transformation matrix from the chase docking port to the target docking port.
THIS FILE CONTAINS THE COMMON BLOCKS FOR THE ORBITAL PARAMETERS
OF THE EQUATIONS OF MOTION AND ALSO THE SIZE OF THE PLANT
STATE VECTORS.

REAL OMOSQ, OMO, RNU2, RNU20
REAL XLE(3,3), AE(3,3)
INTEGER NST

COMMON /STAT/ NST
COMMON /EARTH/ RNU20, RNU2, OMOSQ, OMO
COMMON /TRANS/ AE, XLE
THIS FILE CONTAINS THE COMMON BLOCKS AND DIMENSIONS FOR THE DATA PERTAINING TO BODY 1 OR THE TARGET VEHICLE.

REAL Y1(13),YD1(13),AIV1(3,3),AIV1I(3,3)
REAL OMV1(3),S1V1(3,3),RS1V1V1(3),R1LD(3),R1L(3)
REAL HTV1(3),QV1E(4),MASS1,V1L(3,3),YD01(13)
REAL S1L(3,3),V1E(3,3),RS1V1S1(3)
REAL F1CS1(3),T1CGS1(3),T1G(3),T1CS1(3)
REAL T1CGV1(3),F1CL(3)
REAL RD1V1V1(3),D1V1(3,3),D1L(3,3)

EQUIVALENCE (HTV1(1),Y1(1)),
1 (QV1E(1),Y1(4)),
2 (R1LD(1),Y1(8)),
3 (R1L(1),Y1(11))

COMMON /STATE1/ Y1,YD1,YD01
COMMON /MAS1/ MASS1,AIV1,AIV1I,RS1V1V1,RS1V1S1,RD1V1V1
COMMON /BODY1/ OMV1,T1G
COMMON /TRANS1/ V1L,S1V1,V1E,S1L,D1V1,D1L
COMMON /CONT1/ T1CGV1,F1CL,F1CS1,T1CGS1,T1CS1
THIS FILE CONTAINS THE COMMON BLOCKS AND DIMENSIONS FOR THE DATA PERTAINING TO BODY 2 OR THE CHASE VEHICLE.

REAL Y2(13),YD2(13),AIV2(3,3),AIV2I(3,3)
REAL OMV2(3),D2V2(3,3),RD2V2V2(3),R2LD(3),R2L(3)
REAL HTV2(3),QV2E(4),MASS2,V2L(3,3),YD02(13)
REAL V2E(3,3),RS1V2S1(3)
REAL F2CS1(3),T2CGS1(3),T2G(3)
REAL T2CGV2(3),F2CL(3),S1V2(3,3),D2L(3,3)

EQUIVALENCE (HTV2(1),Y2(1)),
1  (QV2E(1),Y2(4)),
2  (R2LD(1),Y2(8)),
3  (R2L(1),Y2(11))

COMMON /STATE2/ Y2,YD2,YD02
COMMON /MAS2/ MASS2,AIV2,AIV2I,RD2V2V2,RS1V2S1
COMMON /BODY2/ OMV2,T2G
COMMON /TRANS2/ V2L,D2V2,V2E,S1V2,D2L
COMMON /CONTC2/ F2CS1,T2CGS1,T2CGV2,F2CL
THIS FILE CONTAINS THE NECESSARY COMMON BLOCKS FOR THE NASA
OMV CONTROL SYSTEM.

INTEGER*4 EAX, EAY, EAZ, EMX, EMY, EMZ, NAD, NDCI, NDC, IAUTOP, ISTBSL
INTEGER*4 MPASS, ISAMP, IJONS(3), IJOFS(3), IS
REAL SSIN(7), YIN, RTD, DTR, SCX, SCY, SCZ, AFUEL
REAL P31, P32, P33, P34, PD31, PD32, PD33, PD34, P31M1, P32M1, P33M1
REAL P34M1, PD31M1, PD32M1, PD33M1, PD34M1, DELAY(80, 6)
REAL WVX2A, WYY2A, WVZ2A, NOISE1, NOISE2, NOISQ
REAL MX, MY, MZ, FJX, FJY, FJZ

COMMON /ADIN/ SSIN, YIN, NDC, NAD, NDCI
COMMON /DEG/ RTD, DTR
COMMON /MSB/ ISTBSL
COMMON /SAMP/ MPASS, ISAMP
COMMON /LOG/ EAIX, EAY, EAIZ, EMX, EMY, EMZ, IJONS, IJOFS
COMMON /MOMV/ AFUEL, WVX2A, WYY2A, WVZ2A
COMMON /CONFOR/ MX, MY, MZ, FJX, FJY, FJZ
COMMON /SCALE/ SCX, SCY, SCZ
COMMON /NOIS/ NOISE1, NOISE2, NOISQ
COMMON /LAG/ DELAY, IS
COMMON /ERROR1/ P31, P32, P33, P34, P31M1, P32M1, P33M1, P34M1
COMMON /ERROR2/ PD31, PD32, PD33, PD34, PD31M1, PD32M1, PD33M1, PD34M1
DO 100 I=1,NST
   YD02(I)=YD2(I)
100 CONTINUE

C COMPUTE THE TOTAL GRAVITY GRADIENT TORQUES

DO 1500 I=1,3
   VTEM(I)=0.0
   DO 1500 J=1,3
      VTEM(I)=VTEM(I)+AIV2(I,J)*V2L(J,3)
1500 CONTINUE

T2G(1)=3.0*OMOSQ*(V2L(2,3)*VTEM(3)-V2L(3,3)*VTEM(2))
T2G(2)=3.0*OMOSQ*(V2L(3,3)*VTEM(1)-V2L(1,3)*VTEM(3))
T2G(3) = 3.0*OMOSQ*(V2L(1,3)*VTEM(2)-V2L(2,3)*VTEM(1))

C---
C CALCULATE THE ACCELERATION OF THE VEHICLE CENTER OF
C MASS WITH RESPECT TO THE L FRAME IN THE L FRAME COORDINATES.
C---

C  YD2(1) = MX + T2G(1) + T2CGV2(1) - OMV2(2)*HTV2(3) + OMV2(3)*HTV2(2)
C  YD2(2) = MY + T2G(2) + T2CGV2(2) - OMV2(3)*HTV2(1) + OMV2(1)*HTV2(3)
C  YD2(3) = MZ + T2G(3) + T2CGV2(3) - OMV2(1)*HTV2(2) + OMV2(2)*HTV2(1)

C---
C CALCULATE THE DERIVATIVE OF THE QUATERNION
C---

C  YD2(4) = .5*(OMV2(3)*QV2E(2)
C  -OMV2(2)*QV2E(3) + OMV2(1)*QV2E(4) )
C  YD2(5) = .5*(-OMV2(3)*QV2E(1)
C  + OMV2(1)*QV2E(3) + OMV2(2)*QV2E(4) )
C  YD2(6) = .5*(OMV2(2)*QV2E(1)
C  - OMV2(1)*QV2E(2) + OMV2(3)*QV2E(4) )
C  YD2(7) = -.5*(OMV2(1)*QV2E(1)
C  + OMV2(2)*QV2E(2) + OMV2(3)*QV2E(3) )

C---
C TRANSFORM FORCES OF CONTROL SYSTEM FROM V2 FRAME TO L FRAME
C---

C  FXL = FJX*V2L(1,1) + FJY*V2L(2,1) + FJZ*V2L(3,1)
C  FYL = FJX*V2L(1,2) + FJY*V2L(2,2) + FJZ*V2L(3,2)
C  FZL = FJX*V2L(1,3) + FJY*V2L(2,3) + FJZ*V2L(3,3)

C---
C CALCULATE THE ACCELERATION OF THE VEHICLE CENTER OF
C MASS WITH RESPECT TO THE L FRAME IN THE L FRAME COORDINATES.
C---

C  YD2(8) = (FXL+FZL(1))/MASS-2.*OMO*R2LD(3)
C  YD2(9) = (FYL+FZL(2))/MASS-OMOSQ*R2L(2)
C  YD2(10) = (FZL+FZL(3))/MASS+3.*OMOSQ*R2L(3)+2.*OMO*R2LD(1)
C  YD2(11) = Y2(8)
C  YD2(12) = Y2(9)
C  YD2(13) = Y2(10)

C---
RETURN
END
SUBROUTINE CNTRLC IS THE NASA RCS THRUSTER CONTROL SYSTEM FOR THE OMV.

THE INPUT TO THIS ROUTINE REQUIRES THE CHASE VEHICLE INERTIAL ANGULAR RATES IN THE BODY FIXED FRAME AND THE ANGULAR VELOCITY OF THE LOCAL VERTICAL FRAME. IT ALSO REQUIRES THE INPUT FROM THE JOY STICK IN THE KDAT VECTOR.

THE ROUTINE RETURNS THE CONTROL FORCES AND TORQUES IN THE BODY FIXED FRAME.

SUBROUTINE CNTRLC

INCLUDE 'cmmn.f'
INCLUDE 'cmnncon.f'
INCLUDE 'cmnn2.f'
INCLUDE 'cmnnbb.f'

INTEGER*4 IU,I
REAL XIN(7),XDAT(7),PHIE2X,PHIE2Y,PHIE2Z,EX,EY,EZ
REAL PD31M2,PD32M2,PD33M2,PD34M2,DW13,DW23,DW33
REAL SW13,SW23,SW33,P3NORM,ROLIN,PITIN,YAWIN
REAL ROLL,PITCH,YAW,RSQ,PSQ,RSQ1,PSQ1,YSQ1
REAL RSQ2,PSQ2,RSQ3,PSQ3,YSQ3,EAXIN,EAYIN,EAZIN
REAL EAXA,EAYA,EAZA,WVX,WVY,WVZ,WCVX2,WCVY2,WCVZ2
REAL WVX2,WWY2,WWZ
REAL QLIM1
LOGICAL SW,COMR,COMY,COMP,COM

SET INERTIAL CHASE VEHICLE ANGULAR RATES FOR CONTROL SYSTEM

WVX2A=OMV2(1)
WWY2A=OMV2(2)
WVZ2A=OMV2(3)
WVX2=WVX2A-OMO*VZL(1,2)
WWY2=WWY2A-OMO*VZL(2,2)
WVZ2=WVZ2A-OMO*VZL(3,2)

KDAT IS THE ANALOG INPUT FROM THE STICK

DO 1001 I=1,NAD,1
    XDAT(I)=FLOAT(KDAT(I))
    XIN(I)=XDAT(I)*YIN
1001 CONTINUE
ROLIN = XIN(4)*SSIN(4)
PITIN = XIN(5)*SSIN(5)
YAWIN = XIN(6)*SSIN(6)
**DELAY IS AN ARRAY TO DELAY XIN(I) FROM HAND CONTR.**

```fortran
C
C IF(IS .GE. NDC+1)IS = 0
   IS = IS + 1
C
IU = IS - NDC
IF(IU .LE. 0) IU = IS + 1
C
DELAY(IS,4) = ROLIN
DELAY(IS,5) = PITIN
DELAY(IS,6) = YAWIN
C
ROLL = DELAY(IU,4)
PITCH = DELAY(IU,5)
YAW = DELAY(IU,6)
C
IF(ROLL .LT. NOISE1 .AND. ROLL .GT. (-NOISE1))ROLL=0.0
IF(PITCH .LT. NOISE1 .AND. PITCH .GT. (-NOISE1))PITCH=0.0
IF(YAW .LT. NOISE1 .AND. YAW .GT. (-NOISE1))YAW=0.0
IF(XIN(7)*SSIN(7) .LT. -.5)GO TO 36
SW=.FALSE.
GO TO 37
36 SW=.TRUE.
37 IF(ROLL .GE. NOISE1 .OR. ROLL .LE. -NOISE1)GO TO 30
COMR=.FALSE.
ROLL=0.0
GO TO 31
30 COMR=.TRUE.
31 IF(PITCH .GE. NOISE1 .OR. PITCH .LE. -NOISE1)GO TO 32
COMP=.FALSE.
PITCH=0.0
GO TO 33
32 COMP=.TRUE.
33 IF(YAW .GE. NOISE1 .OR. YAW .LE. -NOISE1)GO TO 34
COMY=.FALSE.
YAW=0.0
GO TO 35
34 COMY=.TRUE.
35 COM=COMR .OR. COMP .OR. COMY
RSQ=ROLL*ABS(ROLL)
PSQ=PITCH*ABS(PITCH)
YSQ=YAW*ABS(YAW)
IF(SW .AND. COM)GO TO 38
RSQ1=RSQ+RSQ2
PSQ1=PSQ+PSQ2
YSQ1=YSQ+YSQ2
RSQ3=SCX*RSQ1
PSQ3=SCY*PSQ1
```

---

This code snippet appears to be a part of a program that handles delays and control inputs, possibly for a control system involving roll, pitch, and yaw. The code includes conditionals for checking if certain values exceed noise thresholds and assigns default values if so. It also performs calculations involving absolute values and compares them against noise levels.
YSQ3 = SCZ * YSQ1

GO TO 39
38 RSQ2 = RSQ1
   PSQ2 = PSQ1
   YSQ2 = YSQ1
39 WCVX2 = RSQ3 * DTR
   WCVY2 = PSQ3 * DTR
   WCVZ2 = YSQ3 * DTR

C DEFINE THE ERROR ANGLES FROM THE QUATERNION P3
C
IF (IAUTOP .EQ. 0) GO TO 4
P31 = 0.0
P32 = 0.0
P33 = 0.0
P34 = 1.0
PD31M1 = 0.0
PD32M1 = 0.0
PD33M1 = 0.0
PD34M1 = 0.0
PD31 = 0.0
PD32 = 0.0
PD33 = 0.0
PD34 = 0.0
GO TO 15
4 CONTINUE
PD31M2 = PD31M1
PD32M2 = PD32M1
PD33M2 = PD33M1
PD34M2 = PD34M1
PD31M1 = PD31
PD32M1 = PD32
PD33M1 = PD33
PD34M1 = PD34
DW13 = 0.5 * (WVX2 - WCVX2)
SW13 = 0.5 * (WVX2 + WCVX2)
DW23 = 0.5 * (WVY2 - WCVY2)
SW23 = 0.5 * (WVY2 + WCVY2)
DW33 = 0.5 * (WVZ2 - WCVZ2)
SW33 = 0.5 * (WVZ2 + WCVZ2)
P31 = PD31 * DW13 - P33 * SW23 + P32 * SW33
PD32 = P33 * SW13 + P34 * DW23 - P31 * SW33
PD33 = - P32 * SW13 + P31 * SW23 + P34 * DW33
PD34 = - P31 * DW13 - P32 * DW23 - P33 * DW33
P31M1 = P31
P32M1 = P32
P33M1 = P33
P34M1 = P34
P31 = P31M1 + DT2 * (3.0 * PD31M1 - PD31M2)
P32 = P32M1 + DT2 * (3.0 * PD32M1 - PD32M2)
P33 = P33M1 + DT2 * (3.0 * PD33M1 - PD33M2)
P34 = P34M1 + DT2 * (3.0 * PD34M1 - PD34M2)
P3NORM=$\sqrt{P31^2+P32^2+P33^2+P34^2}$

$P31 = \frac{P31}{P3NORM}$

$P32 = \frac{P32}{P3NORM}$

$P33 = \frac{P33}{P3NORM}$

$P34 = \frac{P34}{P3NORM}$

15 CONTINUE

PHIE2X = -2.0*RTD*P31

PHIE2Y = -2.0*RTD*P32

PHIE2Z = -2.0*RTD*P33

PHIE2X=QLIM1(-5.,PHIE2X,5.)

PHIE2Y=QLIM1(-5.,PHIE2Y,5.)

PHIE2Z=QLIM1(-5.,PHIE2Z,5.)

C

EAXIN =-XIN( 1)*SSIN( 1)

EAYIN =-XIN( 2)*SSIN( 2)

EAZIN =+XIN( 3)*SSIN( 3)

C

DELAY(IS,1) = EAXIN

DELAY(IS,2) = EAYIN

DELAY(IS,3) = EAZIN

C

EAXA = DELAY(IU,1)

EAYA = DELAY(IU,2)

EAZA = DELAY(IU,3)

C

WVX=RTD*WVX2A

WVY=RTD*WVY2A

WVZ=RTD*WVZ2A

EX=67.5*PHIE2X-169.5*(WVX-RSQ3)

EY=45.*PHIE2Y-110.625*(WVY-PSQ3)

EZ=45.*PHIE2Z-110.625*(WVZ-YSQ3)

C

MPASS=MOD(JPASS,ISAMP)

C

ACCEPT HAND CONTROLLER INPUTS ONLY EVERY ISAMP TIMES

IF(MPASS .NE. 0) GO TO 16

EAX=0

EAY=0

EAZ=0

EMX=0

EMY=0

EMZ=0

IF(EAXA .GT. NOISE2) EAX=1

IF(EAXA .LT. -NOISE2) EAX=-1

IF(EAYA .GT. NOISE2) EAY=1

IF(EAYA .LT. -NOISE2) EAY=-1

IF(EAZA .GT. NOISE2) EAZ=1

IF(EAZA .LT. -NOISE2) EAZ=-1

IF(IAUTOP .NE. 0) GO TO 160

IF(EX .GE. 17.) EMX=1

IF(EX .LE. -17.) EMX=-1

IF(EY .GE. 22.) EMY=1

IF(EY .LE. -22.) EMY=-1

IF(EZ .GE. 22.) EMZ=1
IF(EZ .LE. -22.) EMZ=-1
GO TO 16
C EXECUTE AT 160 IF IAUTOP .NE. 0
160 IF(RSQ1 .GT. NOISQ)EMX=1
IF(RSQ1 .LT. -NOISQ)EMX=-1
IF(PSQ1 .GT. NOISQ)EMY=1
IF(PSQ1 .LT. -NOISQ)EMY=-1
IF(YSQ1 .GT. NOISQ)EMZ=1
IF(YSQ1 .LT. -NOISQ)EMZ=-1
16 CONTINUE
CALL LOGIC
RETURN
END
FUNCTION QLIM1(BL,V,TL)
C
C THIS FUNCTION LIMITS V TO BL OR TL
C BL IS BOTTOM LIMIT
C TL IS TOP LIMIT
REAL BL,TL,V,QLIM1
QLIM1 = V
IF(V .LT. BL) QLIM1 = BL
IF(V .GT. TL) QLIM1 = TL
RETURN
END
SUBROUTINE LOGIC
SAVE
INCLUDE 'cmmncon.f'
INCLUDE 'cmmnbb.f'
REAL AX1,AY1,AY2,RO,FTR
REAL A21,A22,CX,CY,CZ,FM,FTRX,RTIME,STIME,SSUMRT,SUMRT
REAL SUMF,SUMFX,SUMRTL,WXDB,WYDB,WZDB
INTEGER ID,IDS,IFLAG1,II,IFX,IFY,IFZ,IROTRY,IROTRZ,ISIDEA
INTEGER ISDA,ISDB,ISIDEB,JETN,JETC,JET,JTIME,M,NCOUNT
INTEGER I2(3)
DIMENSION JETN(24),JETC(24)
DIMENSION FM(24,6),JET(24),IJETON(3),IJETOF(3)
DIMENSION ISIDEA(12),ISIDEB(12)
DIMENSION I2(3)
DIMENSION JTIME(24),RTIME(24),ID(24),STIME(24)
DIMENSION SUMRT(24),SUMRTL(24),IDS(24)
DIMENSION SSUMRT(24)
DATA *IJETON/0,0,0/,
*IJETOF/0,0,0/
DATA ISIDEA/1,2,3,7,8,9,13,14,15,19,20,21/
DATA ISIDEB/4,5,6,10,11,12,16,17,18,22,23,24/
DATA ISDA,ISDB/0,0/
DATA WXDB,WYDB,WZDB/.1,.1,.1/
DATA NFP/0/
C CONSF = FTR/SPECIFIC IMPULSE(SET AT 220 SEC)=0.031818
IF(NNN)18,18,30
18 FTR=10.0
FTRX=10.0
AX1=16.523/12.
AY1=28.529/12.
AY2=35.096/12.
AZ1=66.402/12.
AZ2=72.97/12.
DO 20 I=1,24
    DO 431 J=1,6
20 FM(I,J)=0.0
DO 431 I = 1,24
    JETN(I) = 0
    JETC(I) = 0
    SUMRT(I) = 0
431 CONTINUE
I2(1) = 0
I2(2) = 0
I2(3) = 0
NCOUNT = 0
C FM(I,J) ARE COEFFICIENTS FOR FORCES AND MOMENTS
C WHERE I IS THRUSTER NO.
C THE SIGN IS FROM BOTH FORCE AND ARM.
C X FORCES
FM(1,1)=1.0
FM(2,1)=1.0
FM(3,1)=1.0
FM(4,1)=1.0
C -X FORCES
FM(5,1)=-1.0
FM(6,1)=-1.0
FM(7,1)=-1.0
FM(8,1)=-1.0
C Y FORCES
FM(9,2)=1.0
FM(10,2)=1.0
FM(11,2)=1.0
FM(12,2)=1.0
C -Y FORCES
FM(13,2)=-1.0
FM(14,2)=-1.0
FM(15,2)=-1.0
FM(16,2)=-1.0
C Z FORCES
FM(17,3)=1.0
FM(18,3)=1.0
FM(19,3)=1.0
FM(20,3)=1.0
C -Z FORCES
FM(21,3)=-1.0
FM(22,3)=-1.0
FM(23,3)=-1.0
FM(24,3)=-1.0
C X MOMENT(ROLL)
FM(9,4)=AZ1
FM(10,4)=AZ1
FM(15,4)=AZ1
FM(16,4)=AZ1
FM(18,4)=AY1
FM(19,4)=AY1
FM(22,4)=AY1
FM(23,4)=AY1
C -X MOMENT(-ROLL)
FM(11,4)=-AZ1
FM(12,4)=-AZ1
FM(13,4)=-AZ1
FM(14,4)=-AZ1
FM(17,4)=-AY1
FM(20,4)=-AY1
FM(21,4)=-AY1
FM(24,4)=-AY1
C Y MOMENT(PITCH)
FM(17,5)=AX1
FM(18,5)=AX1
FM(23,5)=AX1
FM(24,5)=AX1
C -Y MOMENT(-PITCH)
FM(19,5)=-AX1
FM(20,5)=-AX1
FM(21,5)=-AX1
FM(22,5)=-AX1
C Z MOMENT(YAW)
FM(10,6)=AX1
FM(11,6)=AX1
FM(14,6)=AX1
FM(16,6)=AX1
C -Z MOMENT(-YAW)
FM(9,6)=-AX1
FM(12,6)=-AX1
FM(13,6)=-AX1
FM(15,6)=-AX1
RETURN
30 CONTINUE
IF(NNN .EQ. 2)GO TO 1050
FX = 0.
FY=0.0
FZ=0.0
MX=0.0
MY=0.0
MZ=0.0
C FTR =ACOF*(PLBS-AFUEL)+BCOF
DO 40 I=1,24
   JET(I)=0
40 CONTINUE
IF(ISTBSL.NE.0) GO TO 5000
IF(EAX) 210,230,220
210 JET( 5) = 1
    JET( 6) = 1
    JET( 7) = 1
    JET( 8) = 1
    GO TO 230
220 JET(1) = 1
    JET(2) = 1
    JET(3) = 1
    JET(4) = 1
230 CONTINUE
    IROTRY = EMX
    IROTRZ = 0
    IFLAG1 = 0
    IF(EMX) 240,300,240
240 IF(EMZ) 250,270,250
250 IF(EMY) 260,290,260
260 IF(EAY) 285,300,285
270 IF(EAY) 280,300,280
280 IF(EMY) 300,290,300
285 IFLAG1 = 1
290 IROTRZ = EMX
    IROTRY = 0
300 CONTINUE
    IF(IROTRY) 320,305,310
305 IF(IROTRZ) 340,350,330
310 JET(9) = 1
    JET(10) = 1
    JET(11) = 1
    GO TO 350
320 JET(12) = 1
    JET(14) = 1
    JET(13) = 1
    JET(11) = 1
    GO TO 350
330 JET(18) = 1
    JET(19) = 1
    JET(22) = 1
    JET(23) = 1
    GO TO 350
340 JET(17) = 1
    JET(20) = 1
    JET(21) = 1
    JET(24) = 1
350 CONTINUE
    IF(EMY) 370,380,360
360 JET(17) = 1
    JET(18) = 1
    JET(23) = 1
    JET(24) = 1
    GO TO 380
CONTINUE
IF(EMZ) 400,410,390
JET(10) = 1
JET(11) = 1
JET(14) = 1
JET(16) = 1
GO TO 410
JET(9) = 1
JET(12) = 1
JET(13) = 1
JET(15) = 1
CONTINUE
IF(EAY) 430,440,420
JET(9) = 1
JET(10) = 1
JET(11) = 1
JET(12) = 1
GO TO 440
JET(13) = 1
JET(14) = 1
JET(15) = 1
JET(16) = 1
CONTINUE
IF(EAZ) 460,470,450
JET(17) = 1
JET(18) = 1
JET(19) = 1
JET(20) = 1
GO TO 470
JET(21) = 1
JET(22) = 1
JET(23) = 1
JET(24) = 1
IF(JET(14)) 475,475,471
IF(JET(9)) 475,475,472
JET(14) = 0
JET(9) = 0
IF(JET(10)) 480,480,476
IF(JET(13)) 480,480,477
JET(10) = 0
JET(13) = 0
IF(JET(12)) 485,485,481
IF(JET(16)) 485,485,482
JET(12) = 0
JET(16) = 0
IF(JET(11)) 490,490,486
IF(JET(15)) 490,490,487
JET(11) = 0
JET(15) = 0
490 IF(JET(17)) 495,495,491
491 IF(JET(22)) 495,495,492
492 JET(17) = 0
  JET(22) = 0
495 IF(JET(18)) 500,500,496
496 IF(JET(21)) 500,500,497
497 JET(18) = 0
  JET(21) = 0
500 IF(JET(19)) 505,505,501
501 IF(JET(24)) 505,505,502
502 JET(19) = 0
  JET(24) = 0
505 IF(JET(20)) 510,510,506
506 IF(JET(23)) 510,510,507
507 JET(20) = 0
  JET(23) = 0
510 CONTINUE
  IF(IFLAG1) 560,560,511
511 IF(EAZ) 515,560,515
515 IF(JET(17)) 520,520,516
516 JET(24) = 1
  JET(20) = 1
  JET(18) = 1
  GO TO 560
520 IF(JET(18)) 525,525,521
521 JET(17) = 1
  JET(19) = 1
  JET(23) = 1
  GO TO 560
525 IF(JET(19)) 530,530,526
526 JET(18) = 1
  JET(20) = 1
  JET(22) = 1
  GO TO 560
530 IF(JET(20)) 535,535,531
531 JET(17) = 1
  JET(19) = 1
  JET(21) = 1
  GO TO 560
535 IF(JET(21)) 540,540,536
536 JET(20) = 1
  JET(22) = 1
  JET(24) = 1
  GO TO 560
540 IF(JET(22)) 545,545,541
541 JET(19) = 1
  JET(21) = 1
  JET(23) = 1
  GO TO 560
545 IF(JET(23)) 550,550,546
546 JET(24) = 1
  JET(22) = 1
  JET(18) = 1
GO TO 560
550 IF(JET(24)) 560,560,551
551 JET(17) = 1
JET(21) = 1
JET(23) = 1
GO TO 560
560 CONTINUE
IF(I2(1)) 600,600,565
565 IF(IROTRY) 590,570,590
570 IF(IROTRZ) 575,600,575
575 IF(EAZ) 600,580,600
580 IF(EMY) 600,581,600
581 JET(18) = 0
JET(20) = 0
JET(21) = 0
JET(23) = 0
GO TO 600
590 IF(EAY) 600,595,600
595 IF(EMZ) 600,596,600
596 JET(11) = 0
JET(10) = 0
JET(13) = 0
JET(15) = 0
600 CONTINUE
IF(I2(2)) 630,630,605
605 IF(EMY) 610,630,610
610 IF(EAZ) 630,615,630
615 IF(IROTRZ) 630,620,630
620 JET(17) = 0
JET(20) = 0
JET(22) = 0
JET(23) = 0
630 CONTINUE
IF(I2(3)) 700,700,635
635 IF(EMZ) 640,700,640
640 IF(EAY) 700,645,700
645 IF(IROTRY) 700,650,700
650 JET(11) = 0
JET(12) = 0
JET(15) = 0
JET(16) = 0
700 CONTINUE
GO TO 900
C
5000 CX = WX2A*RTD
  CY = WY2A*RTD
  CZ = WZ2A*RTD
  EMX = 0
  IF(CX.GT.WXDB) EMX = -1
  IF(CX.LT.(-WXDB)) EMX = 1
  EAZ = 0
  IF(CY.GT.WYDB) EAZ = -1
  IF(CY.LT.(-WYDB)) EAZ = 1
EAY = 0
IF(CZ.GT.WZDB) EAY = 1
IF(CZ.LT.(-WXDB)) EAY = -1
IFX = 1 + EMX
IFZ = 1 + EAZ
IFY = 1 + EAY
J = 1 + 9*IFX + 3*IFZ + IFY
GO TO J,(5001,5002,5003,5004,5005,5006,5007,5008,5009,5010,
*5011,5012,5013,5014,5015,5016,5017,5018,5019,5020,5021,5022,
*5023,5024,5025,5026,5027)
5001 CONTINUE
JET(2) = 1
JET(6) = 1
JET(15) = 1
JET(21) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5002 CONTINUE
JET(2) = 1
JET(6) = 1
JET(21) = 1
JET(8) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5003 CONTINUE
JET(6) = 1
JET(8) = 1
JET(15) = 1
JET(21) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5004 CONTINUE
JET(2) = 1
JET(23) = 1
JET(15) = 1
JET(21) = 1
JET(6) = 1
JET(12) = 1
GO TO 900
5005 CONTINUE
JET(15) = 1
JET(21) = 1
JET(6) = 1
JET(12) = 1
GO TO 900
5006 CONTINUE
JET(8) = 1
JET(17) = 1
JET(15) = 1
JET(21) = 1
JET(6) = 1
JET(12) = 1
GO TO 900
5007 CONTINUE
JET(12) = 1
JET(2) = 1
JET(15) = 1
JET(21) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5008 CONTINUE
JET(12) = 1
JET(15) = 1
JET(2) = 1
JET(8) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5009 CONTINUE
JET(12) = 1
JET(8) = 1
JET(15) = 1
JET(21) = 1
JET(17) = 1
JET(23) = 1
GO TO 900
5010 CONTINUE
JET(9) = 1
JET(21) = 1
JET(2) = 1
JET(20) = 1
GO TO 900
5011 CONTINUE
JET(9) = 1
JET(21) = 1
GO TO 900
5012 CONTINUE
JET(9) = 1
JET(21) = 1
JET(11) = 1
JET(17) = 1
GO TO 900
5013 CONTINUE
JET(2) = 1
JET(20) = 1
GO TO 900
5014 CONTINUE
GO TO 900
5015 CONTINUE
JET(17) = 1
JET(11) = 1
GO TO 900
5016 CONTINUE
  JET(3) = 1
  JET(15) = 1
  JET(2) = 1
  JET(20) = 1
  GO TO 900
5017 CONTINUE
  JET(3) = 1
  JET(15) = 1
  GO TO 900
5018 CONTINUE
  JET(3) = 1
  JET(15) = 1
  JET(11) = 1
  JET(17) = 1
  GO TO 900
5019 CONTINUE
  JET(9) = 1
  JET(5) = 1
  JET(14) = 1
  JET(20) = 1
  JET(18) = 1
  JET(24) = 1
  GO TO 900
5020 CONTINUE
  JET(9) = 1
  JET(18) = 1
  JET(11) = 1
  JET(14) = 1
  JET(5) = 1
  JET(20) = 1
  GO TO 900
5021 CONTINUE
  JET(9) = 1
  JET(11) = 1
  JET(14) = 1
  JET(20) = 1
  JET(18) = 1
  JET(24) = 1
  GO TO 900
5022 CONTINUE
  JET(5) = 1
  JET(20) = 1
  JET(9) = 1
  JET(18) = 1
  JET(3) = 1
  JET(24) = 1
  GO TO 900
5023 CONTINUE
  JET(9) = 1
  JET(18) = 1
  JET(3) = 1
  JET(24) = 1
GO TO 900
5024 CONTINUE
  JET(11) = 1
  JET(14) = 1
  JET(9) = 1
  JET(18) = 1
  JET(3) = 1
  JET(24) = 1
GO TO 900
5025 CONTINUE
  JET(3) = 1
  JET(5) = 1
  JET(14) = 1
  JET(20) = 1
  JET(18) = 1
  JET(24) = 1
GO TO 900
5026 CONTINUE
  JET(3) = 1
  JET(24) = 1
  JET(11) = 1
  JET(14) = 1
  JET(5) = 1
  JET(20) = 1
GO TO 900
5027 CONTINUE
  JET(3) = 1
  JET(11) = 1
  JET(14) = 1
  JET(20) = 1
  JET(18) = 1
  JET(24) = 1
900 CONTINUE
  IF(ISDA.EQ.0) GO TO 902
  DO 901 I = 1,12
      II = ISIDEA(I)
  901 JET(II) = 0
  GO TO 912
902 IF(ISDB.EQ.0) GO TO 904
  DO 903 I = 1,12
      II = ISIDEB(I)
  903 JET(II) = 0
  GO TO 912
904 CONTINUE
C
C FAILED JETS AND EFFECTS
C
  DO 910 I = 1,3
      IF(IJONS(I) .EQ. 0) GO TO 908
      IF(IJETON(I) .EQ. 0) GO TO 908
      II = IJETON(I)
      JET(II) = 1
  908 IF(IJOFS(I) .EQ. 0) GO TO 910

C
IF(IJETOF(I) .EQ. 0) GO TO 910
I I =IJETOF(I)
JET(I)=0
910 CONTINUE
912 CONTINUE

CALCULATE FORCES AND MOMENTS

SUMF =0.0
SUMFX=0.0
NCOUNT = NCOUNT + 1
DO 920 I=1,24
IF JET IS JUST NOW TURNED ON COUNT AS A FIRING STARTED.
IF(JET(I) .LE. JETN(I)) GO TO 101
JETC(I)=JETC(I)+1
JETC(I)=COUNT OF NO.OF FIRINGS STARTED FOR JET(I),
FOR THIS RUN.
101 CONTINUE
C IF THRUSTER STAYED OFF FROM LAST PASS, GO TO 920
IF(JETN(I) .EQ. 1)GO TO 918
RTIME(I)=0.
IF(JET(I) .EQ. 0) GO TO 920
JTIME(I)=0
C INCREMENT NO. OF FIRINGS THIS DATA PERIOD
NFP=NFP+1
C INCREMENT NO. OF FIRINGS THIS RUN.
NFT=NFT+1
JETN(I)=JET(I)
GO TO 919
918 JTIME(I)=JTIME(I)+1
IF(JET(I) .LE. 1) GO TO 919
C CALCULATE ON TIME AND TOTAL ON TIME
RTIME(I)=JTIME(I)*DT
SUMRT(I)=SUMRT(I)+RTIME(I)
JETN(I) = JET(I)
GO TO 920
C IF JET IS ON,ADD ITS THRUST LEVEL(FTR)TO FORCES & MOMENTS.
919 CONTINUE
IF(I .LE. 8)GO TO 913
SUMF =SUMF+1.0
GO TO 914
913 SUMFX=SUMFX+1
914 FJX =FJX+FTRX*FM(I,1)
FJY =FJY+FTRX*FM(I,2)
FJZ =FJZ+FTRX*FM(I,3)
MX =MX+FTRX*FM(I,4)
MY =MY+FTRX*FM(I,5)
MZ =MZ+FTRX*FM(I,6)
920 CONTINUE
AFUEL=AFUEL+(DT/220.)*(FTRX*SUMFX+FTR*SUMF)
C THE NEXT TWO STATEMENTS ARE USED TO MAKE A FILE OF DATA
C POINTS TO USE IN THE PLOT PROGRAM
WRITE(4,5100)NFT,AFUEL,RO,TIME
5100 FORMAT(1X,I4,2(1X,F6.2),1X,E12.5)
2000 CONTINUE
C IF DATA PERIOD NOT OVER, SKIP CALCULATION OF DURATION TIME.
C MPASS=MOD(JPASS,ISAMP)
C JPASS=NO. PROGRAM PASSES
C ISAMP=SAMPLING RATE ON HAND CONTROL INPUTS
IF(MPASS .NE. 0) GO TO 927
J=1
L=1
DO 921 I=1,24
C NO ID SHOULD BE PRINTED IF IT IS EQUAL TO 99.
IF(RTIME(I) .EQ. 0.)GO TO 922
C PACK ID AND DURATION TIMES
ID(J)=I
STIME(J)=RTIME(I)
J=J+1
922 CONTINUE
IF(SUMRT(I) .EQ. SUMRTL(I))GO TO 921
C IF TOTAL ON TIME HAS CHANGED REPACK ID AND TOTAL TIME
IDS(L)=I
SSUMRT(L)=SUMRT(I)
C SET TOTAL ON TIME LAST=TOTAL ON TIME
SUMRTL(I)=SUMRT(I)
L=L+1
921 CONTINUE
IF(J .NE. 1)GO TO 924
IF(NFP .EQ. 0.)GO TO 926
C WRITE(6,1000)NCOUNT,NFP,NFT,AFUEL,RO
GO TO 925
924 CONTINUE
103 FORMAT(1H ,2X, 15)
K=J-1
C WRITE(7,103) K
IF(K .GT. 10)GO TO 811
GO TO 925
C GO TO (801,802,803,804,805,806,807,808,809,810) ,K
801 WRITE(6,1001)NCOUNT,NFP,NFT,AFUEL,RO
GO TO 925
802 WRITE(6,1002)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,2)
GO TO 925
803 WRITE(6,1003)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,3)
GO TO 925
804 WRITE(6,1004)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,4)
GO TO 925
805 WRITE(6,1005)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,5)
GO TO 925
806 WRITE(6,1006)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,6)
GO TO 925
807 WRITE(6,1007)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,7)
GO TO 925
808 WRITE(6,1008)NCOUNT,NFP,NFT,AFUEL,RO,(ID(I),STIME(I),I=1,8)
GO TO 925
C NCOUNT IS THE CURRENT PROGRAM CYCLE IN THIS RUN.
C NFP IS NO. OF THRUSTER FIRINGS PER DATA PERIOD
C NFT IS TOTAL NO. OF THRUSTER FIRINGS FOR THIS RUN
C JETS CAN GO ON OR OFF ONLY EVERY ISAMP PROGRAM PASS BECAUSE
C HAND CONTROLLER INPUTS ARE ACCEPTED THEN ONLY.IN MAIN
C ISAMP IS THE MAX. NO. OF PROGRAM CYCLES PER DATA PERIOD.
C JETN(I)= VALUE OF JET(I) AT LAST PROGRAM CYCLE.
811 PAUSE 'K2LARGE'
925 CONTINUE
   NFP=0
926 CONTINUE
   IF(L .EQ. 1)GO TO 927
      M=L-1
   C WRITE(7,103)M
   IF(M .GT. 10)GO TO 928
   GO TO 927
   C GO TO (821,822,823,824,825,826,827,828,829,830),M
928 PAUSE 'M2LARGE'
   GO TO 927
821 WRITE(5,1021)NCOUNT,RO,IDS(1),SSUMRT(1)
C WRITE(4,1040)SSUMRT(1),RO
   GO TO 927
822 WRITE(5,1022)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,2)
   GO TO 927
823 WRITE(5,1023)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,3)
   GO TO 927
824 WRITE(5,1024)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,4)
   GO TO 927
825 WRITE(5,1025)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,5)
   GO TO 927
826 WRITE(5,1026)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,6)
   GO TO 927
827 WRITE(5,1027)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,7)
   GO TO 927
828 WRITE(5,1028)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,8)
   GO TO 927
829 WRITE(5,1029)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,9)
   GO TO 927
830 WRITE(5,1030)NCOUNT,RO,(IDS(I),SSUMRT(I),I=1,10)
927 CONTINUE
   RETURN
1050 DO 1041 I=1,24
C WRITE(5,1042)I,SSUMRT(I)
1042 FORMAT(1H ,13,2X,F6.2)
1041 CONTINUE
   RETURN
1000 FORMAT(1H ,I5,1X,I2,1X,I4,2(I1X,F6.2))
1001 FORMAT(1H ,I5,1X,I2,1X,I4,2(I1X,F6.2),1(1X, *
   * '('1X,I2,':-',F5.2,'')'))
1002 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),2(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1003 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),3(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1004 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),4(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1005 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),5(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1006 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),6(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1007 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),7(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1008 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),8(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1009 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),9(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1010 FORMAT(1H ,I5,1X,I2,1X,I4,2(1X,F6.2),10(1X, 
     *, '(',1X,I2,'-',F5.2,')'))
1011 FORMAT(1H ,I5,F6.2,1(1X,('(',1X,I2,'-',F5.2,')'))
1012 FORMAT(1H ,I5,F6.2,2(1X,('(',1X,I2,'-',F5.2,')'))
1013 FORMAT(1H ,I5,F6.2,3(1X,('(',1X,I2,'-',F5.2,')'))
1014 FORMAT(1H ,I5,F6.2,4(1X,('(',1X,I2,'-',F5.2,')'))
1015 FORMAT(1H ,I5,F6.2,5(1X,('(',1X,I2,'-',F5.2,')'))
1016 FORMAT(1H ,I5,F6.2,6(1X,('(',1X,I2,'-',F5.2,')'))
1017 FORMAT(1H ,I5,F6.2,7(1X,('(',1X,I2,'-',F5.2,')'))
1018 FORMAT(1H ,I5,F6.2,8(1X,('(',1X,I2,'-',F5.2,')'))
1019 FORMAT(1H ,I5,F6.2,9(1X,('(',1X,I2,'-',F5.2,')'))
1020 FORMAT(1H ,I5,F6.2,10(1X,('(',1X,I2,'-',F5.2,')'))
1021 FORMAT(2(2X,F6.2))
END
TBA DOCKING DYNAMICS SIMULATION

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THIS SUBROUTINE IS THE DRIVER FOR THE CONTROL DYNAMICS
DOCKING DYNAMICS SUBROUTINE. THE INPUT CONSISTS OF THE
CONTROL SYSTEM JOY STICK DATA AND SENSOR OUTPUT VECTOR
KIN AT TIME T. THE SUBROUTINE PRODUCES THE RELATIVE POSITION
VECTOR AND TRANSFORMATION MATRIX BETWEEN THE CHASE AND
TARGET VEHICLES AT TIME + DT.

SUBROUTINE DYNAMIC

INCLUDE 'cmmn.f'
INCLUDE 'cmnn1.f'
INCLUDE 'cmnn2.f'
INCLUDE 'cmnncon.f'
INCLUDE 'cmnnbb.f'

INTEGER I

5 CONTINUE
CALL STARTT
CALL INTFAC
CALL FMTRAN
CALL CNTRLC
CALL CHASE
CALL TARGET
RETURN

10 CONTINUE
CALL FMTRAN
CALL CNTRLC
CALL CHASE
CALL TARGET
IF (T.EQ.0.0) THEN
DO 1500 I=1,NST
YD01(I)=YD1(I)
YD02(I)=YD2(I)
1500 CONTINUE
ENDIF
DO 1000 I=1,NST
Y1(I)=Y1(I)+DT*(3.*YD1(I)-YD01(I))
Y2(I)=Y2(I)+DT*(3.*YD2(I)-YD02(I))
1000 CONTINUE

COMPUTE INTERFACE INFORMATION
CALL INTFAC

CALCULATE NEW OMEGA VECTORS

CALL MVMUL(OMV1,AIV1I,HTV1)
CALL MVMUL(OMV2,AIV2I,HTV2)

NORMALIZE QUATERNIONS

CALL NORMAL (QV1E)
CALL NORMAL (QV2E)

RETURN
END
THIS SUBROUTINE CALCULATES THE CONTACT FORCES AND MOMENTS
ABOUT THE CENTERS OF MASS OF THE TARGET AND CHASE VEHICLES.

THE INPUT IS THE KIN VECTOR FROM THE SENSOR

THE OUTPUT CONSISTS OF THE VALUES OF IPOT, IFREEZE, IFLAG, AND
NOUSE.

SUBROUTINE FMTRAN

SAVE

INCLUDE 'cmmn1.f'
INCLUDE 'cmmn2.f'
INCLUDE 'cmmnbb.f'

INTEGER*2 THRESH(6),KOFF(8)
INTEGER I
REAL RSlVZL(3),FKM(3),MTKM(3),FSC(3),MTSC(3),AIN(6)
REAL RSIVIL(3),WMAX,WMAXI

DATA THRESH /100,100,200,100,100,100/
DATA WMAX /32768./
DATA FKM /1000.,1000.,1000./
DATA MTKM /1000.,1000.,1000./

KOFF IS THE OFFSET FROM FORCES COMING IN
THRESH IS THRESHOLD LIMIT ON FORCES
ORDER IS X,Y,Z,ROLL,YAW,PITCH

THE MAXIMUM WORD IS 32768 (16 BITS)
FKM AND MTKM ARE MAXIMUM OUTPUTS OF THE FORCE TABLE AS SCALED
IN AMPS. ORDER IS X,Y,Z,ROLL,YAW,PITCH

ALL FORCE AND MOMENT DATA RETURNING FROM THE SENSOR
ARE IN S1 OR SENSOR FRAME COORDINATES

T1CS1 IS THE TORQUE ACTING AT THE SENSOR IN SENSOR COORDINATES
T1CGS1 IS THE TORQUE ACTING ON THE TARGET VEHICLE CENTER OF MASS
IN SENSOR COORDINATES.
T2CGS1 IS THE TORQUE ACTING ON THE CHASE VEHICLE CENTER OF MASS
IN SENSOR COORDINATES.
F1CS1 IS THE FORCE AT THE SENSOR IN SENSOR COORDINATES

RS1V1S1 IS THE VECTOR FROM THE TARGET VEHICLE CENTER OF MASS TO THE SENSOR IN SENSOR COORDINATES

RS1V2S1 IS THE VECTOR FROM THE CHASE VEHICLE CENTER OF MASS TO THE SENSOR IN SENSOR COORDINATES

IF (NNN) 5,5,15

COMPUTE SCALE FACTORS FOR FORCE TABLE INPUTS

CONTINUE
WMAXI=1./WMAX

DO 3 I=1,3
FSC(I)=FKM(I)*WMAXI
MTSC(I)=MTKM(I)*WMAXI

CONTINUE

15 CONTINUE

I POT= KIN(9)

IF(KIN(8) .EQ. 0) GO TO 7

NULL FORCE TABLE OFFSETS TO 0
ICFORCE=I2=KIN(8)

DO 9 I=1,6
KOFF(I)=KIN(I)
IFLAG=1

9 CONTINUE

IFLAG .NE. 0)KIN(I)=0
AIN(I)=FLOAT(KIN(I))

CONTINUE

FSC IS SCALE FACTOR ON INPUTS ( X,Y,Z,ROLL,YAW,PITCH)

F1CS1(1)=AIN(1)*FSC(1)
F1CS1(2)=AIN(2)*FSC(2)
F1CS1(3)=AIN(3)*FSC(3)
T1CS1(1)=AIN(4)*MTSC(1)
T1CS1(2)=AIN(6)*MTSC(3)
T1CS1(3)=AIN(5)*MTSC(2)

IFREEZ=KIN(7)
NOUSE=KIN(8)
C COMPUTE CONTACT TORQUES ON TARGET VEHICLE ABOUT ITS CENTER OF MASS
T1CGS1(1)=TICS1(1)+RS1V1S1(2)*F1CS1(3)-RS1V1S1(3)*F1CS1(2)
T1CGS1(2)=TICS1(2)+RS1V1S1(3)*F1CS1(1)-RS1V1S1(1)*F1CS1(3)
T1CGS1(3)=TICS1(3)+RS1V1S1(1)*F1CS1(2)-RS1V1S1(2)*F1CS1(1)
C-------------------------------
C TRANSFORM TARGET CONTACT TORQUES TO TARGET VEHICLE FRAME FROM SENSOR FRAME
C TRANSFORM TARGET CONTACT FORCES TO LOCAL VERTICAL FRAME FROM SENSOR FRAME
CALL VMMUL(T1CGV1,T1CGS1,S1V1)
CALL VMMUL(F1CL,F1CS1,S1L)
C-------------------------------
C COMPUTE MOMENT ARM FROM CHASE VEHICLE CENTER OF MASS TO THE SENSOR IN LOCAL VERTICAL COORDINATES.
CALL VMMUL(RS1V1L,RS1V1V1,V1L)
DO 10 I=1,3
   RS1V2L(I)=R1L(I)+RS1V1L(I)-R2L(I)
10 CONTINUE
C TRANSFORM MOMENT ARM TO SENSOR COORDINATES FROM TARGET VEHICLE COORDINATES.
CALL VMMUL(RS1V2S1,S1L,RS1V2L)
C-------------------------------
C ASSUME EQUAL AND OPPOSITE CONTACT FORCES
DO 20 I=1,3
   F2CS1(I)=-F1CS1(I)
20 CONTINUE
C-------------------------------
C COMPUTE CONTACT TORQUES ABOUT CENTER OF MASS OF CHASE VEHICLE IN SENSOR COORDINATES.
T2CGS1(1)=-TICS1(1)+RS1V2S1(2)*F2CS1(3)-RS1V2S1(3)*F2CS1(2)
T2CGS1(2)=-TICS1(2)+RS1V2S1(3)*F2CS1(1)-RS1V2S1(1)*F2CS1(3)
T2CGS1(3)=-TICS1(3)+RS1V2S1(1)*F2CS1(2)-RS1V2S1(2)*F2CS1(1)
C-------------------------------
C TRANSFORM CHASE CONTACT TORQUES TO CHASE VEHICLE FRAME FROM SENSOR FRAME
C TRANSFORM CHASE CONTACT FORCES TO LOCAL VERTICAL FRAME FROM SENSOR FRAME
CALL VMMUL(T2CGV2,T2CGS1,S1V2)
CALL VMMUL(F2CL,F2CS1,S1L)
C----------------------------------
        RETURN
        END
THIS SUBROUTINE CALCULATES THE NECESSARY TRANSFORMATION
MATRICES USED IN THE DYNAMICS.

IT OUTPUTS THE POSITION VECTOR FROM THE TARGET DOCKING
PORT TO THE CHASE DOCKING PORT IN TARGET DOCKING PORT
COORDINATES.

IT OUTPUTS THE VELOCITY OF THE CHASE DOCKING PORT WITH
RESPECT TO THE TARGET DOCKING PORT IN TARGET DOCKING
PORT COORDINATES.

IT OUTPUTS THE ANGULAR VELOCITY OF THE CHASE VEHICLE
WITH RESPECT TO THE TARGET VEHICLE IN CHASE VEHICLE
COORDINATES.

IT ALSO OUTPUTS THE TRANSFORMATION MATRIX FROM THE CHASE
DOCKING PORT TO THE TARGET DOCKING PORT COORDINATE FRAMES.

SUBROUTINE INTFAC

INCLUDE 'cmmn.f'
INCLUDE 'cmmn1.f'
INCLUDE 'cmmn2.f'
INCLUDE 'cmmnbb.f'

REAL RD1V1L(3), RD2V2L(3), RD2D1L(3), RD2D1LD(3), OMV1L(3)
REAL OMV2L(3), OMV1RL(3), OMV2V1L(3), WRXRD2(3)
REAL WRLXR2(3), WRLXRI(3)
INTEGER I, J, K

CONSTRUCT COORDINATE TRANSFORMATIONS

V1E
CALL AFQ(V1E, QV1E)

V2E
CALL AFQ(V2E, QV2E)

XLE IS THE TRANSFORMATION FROM THE INERTIAL E FRAME TO THE
LOCAL VERTICAL L FRAME

RNU2 IS THE CURRENT ORBIT ANGLE
RNU2=RNU20+OMO*T

CALL EUL2(XLE,RNU2)
CALL MMUL33(XLE,AE)

V1L=V1E*(XLE)T. V2L=V2E*(XLE)T.

C CALCULATE TRANSFORMATIONS FROM THE LOCAL VERTICAL TO THE CHASE
C AND TARGET VEHICLE FRAMES.

DO 900 I=1,3
DO 900 J=1,3
V1L(I,J) = 0.0
V2L(I,J) = 0.0
DO 900 K=1,3
V1L(I,J) = V1L(I,J) + V1E(I,K)*XLE(J,K)
V2L(I,J) = V2L(I,J) + V2E(I,K)*XLE(J,K)
900 CONTINUE

C COMPUTE TRANSFORMATION MATRIX FROM LOCAL VERTICAL FRAME
C TO THE TARGET DOCKING PORT FRAME

CALL MMUL3(D1L,D1V1,V1L)

C COMPUTE TRANSFORMATION MATRIX FROM LOCAL VERTICAL FRAME
C TO THE CHASE DOCKING PORT FRAME

CALL MMUL3(D2L,D2V2,V2L)

C COMPUTE TRANSFORMATION MATRIX FROM LOCAL VERTICAL FRAME
C TO THE SENSOR FRAME

CALL MMUL3(S1L,S1V1,V1L)

C CALCULATE TRANSFORMATION FROM CHASE VEHICLE TO TARGET VEHICLE
C DOCKING PORT COORDINATES.

DO 1540 I=1,3
DO 1540 J=1,3
D1D2(I,J) = 0.0
DO 1540 K=1,3
D1D2(I,J) = D1D2(I,J) + D1L(I,K)*D2L(J,K)
1540 CONTINUE

C CALCULATE TRANSFORMATION FROM CHASE VEHICLE TO SENSOR COORDINATES

DO 1550 I=1,3
DO 1550 J=1,3
S1V2(I,J)=0.
DO 1550 K=1,3
S1V2(I,J)=S1V2(I,J)+S1L(I,K)*V2L(J,K)
1550 CONTINUE

C-----------------------------------------------------------------------
C CALCULATE POSITION AND VELOCITY OF CHASE VEHICLE DOCKING PORT
C WITH RESPECT TO THE TARGET VEHICLE DOCKING PORT
C-----------------------------------------------------------------------

CALL VMMUL (RD1IV1L,RD1IV1V1,V1L)
CALL VMMUL (RD2V2L,RD2V2V2,V2L)

RD2D1L IS THE POSITION OF THE CHASE DOCKING PORT WITH RESPECT
TO THE TARGET DOCKING PORT IN LOCAL VERTICAL COORDINATES

DO 10 I=1,3
   RD2D1L(I)=R2L(I)+RD2V2L(I)-R1L(I)-RD1V1L(I)
10 CONTINUE

OMV1L AND OMV2L ARE THE ANGULAR VELOCITIES OF THE TARGET AND CHASE
VEHICLES, RESPECTIVELY, IN LOCAL VERTICAL COORDINATES

CALL VMMUL (OMV1L,OMV1,V1L)
CALL VMMUL (OMV2L,OMV2,V2L)

OMV2V1L IS THE ANGULAR VELOCITY OF THE CHASE VEHICLE WITH
RESPECT TO THE TARGET VEHICLE IN LOCAL VERTICAL COORDINATES

DO 20 I=1,3
   OMV1RL(I)=OMV1L(I)
   OMV2V1L(I)=OMV2L(I)-OMV1L(I)
20 CONTINUE

OMV1RL IS THE ANGULAR VELOCITY OF THE TARGET
VEHICLE WITH RESPECT TO THE LOCAL VERTICAL
ORBITAL RATE, IN LOCAL VERTICAL COORDINATES.

OMV1RL(2)=OMV1RL(2)-OMO

CALL CROSS (WRXRD2,OMV2V1L,RD2V2L)
CALL CROSS (WRLXR1,OMV1RL,R1L)
CALL CROSS (WRLXR2,OMV1RL,R2L)

DO 30 I=1,3
   RD2D1LD(I)=R2LD(I)-WRLXR2(I)+WRXRD2(I)-R1LD(I)+WRLXR1(I)
30 CONTINUE

C-----------------------------------------------------------------------
C TRANSFORM ALL RELATIVE DOCKING PORT DATA FROM THE L FRAME TO
C THE D1 FRAME.
C
CALL MVMUL(RD2D1D1,D1L,RD2D1L)
CALL MVMUL(RD2D1D1D,D1L,RD2D1LD)
CALL MVMUL(OMV2V1V2,V2L,OMV2V1L)

RETURN
END
SUBROUTINE EUL3(A, EA)
REAL A(3,3), EA
A(2,2) = 1.0
A(2,3) = 0.
A(2,1) = 0.
A(1,2) = 0.
A(3,2) = 0.
A(1,1) = COS(EA)
A(3,3) = A(1,1)
A(3,1) = SIN(EA)
A(1,3) = -A(3,1)
RETURN
END

C---------------------------------------------------------------------
C MATRIX PRODUCT
C OF 3x3 MATRICES WITH RESULT IN LEFT FACTOR
C---------------------------------------------------------------------

SUBROUTINE MMUL33(A, B)
REAL A(3,3), B(3,3), C(3,3)
INTEGER I, J, K
DO 10 I = 1, 3
DO 10 J = 1, 3
C(I, J) = 0.
DO 10 K = 1, 3
C(I, J) = C(I, J) + A(I, K) * B(K, J)
10 CONTINUE
DO 20 I = 1, 3
DO 20 J = 1, 3
A(I, J) = C(I, J)
20 CONTINUE
RETURN
END
C SUBROUTINE TO COMPUTE DIRECTION COSINE MATRIX FROM QUATERNION
C-----------------------------------------------------------------------
SUBROUTINE AFQ(A,Q)
REAL A(3,3),Q(4),Q1SQ,Q2SQ,Q3SQ,Q4SQ
REAL Q112,Q113,Q114,Q123,Q124,Q134
Q1SQ=Q(1)**2
Q2SQ=Q(2)**2
Q3SQ=Q(3)**2
Q4SQ=Q(4)**2
Q112=2.0*Q(1)*Q(2)
Q113=2.0*Q(1)*Q(3)
Q114=2.0*Q(1)*Q(4)
C-------------------
SUBROUTINE TO COMPUTE QUATERNIONS FROM DIRECTION COSINES
C-------------------

SUBROUTINE QFA(Q,A)
REAL S(4,4),SP(4,4),A(3,3),Q(4),TR,SPMAX,SPJ,SGN
INTEGER I,J
E!!
DO 10 I=1,3
DO 10 J=1,3
S(I,J)=A(I,J)
10 CONTINUE
S(1,4)=A(2,3)
S(2,4)=A(3,1)
S(3,4)=A(1,2)
TR=A(1,1)+A(2,2)+A(3,3)
S(4,4)=TR
S(4,1)=-A(3,2)
S(4,2)=-A(1,3)
S(4,3)=-A(2,1)
DO 20 I=1,4
DO 20 J=1,4
SP(I,J)=S(I,J)+S(J,I)
20 CONTINUE
TR=1.0-TR
DO 30 I=1,4
SP(I,I)=SP(I,I)+TR
30 CONTINUE
I=1
SPMAX=ABS(SP(1,1))
DO 40 J=2,4
SPJ=ABS(SP(J,J))
IF (SPJ.LT.SPMAX) GOTO 35
I=J
SPMAX=ABS(SP(J,J))
35 CONTINUE
40 CONTINUE
SPMAX=SORT(SPMAX)
DO 50 J=1,4
Q(J)=.5*SP(I,J)/SPMAX
50 CONTINUE

RETURN
END
SGN=1.0
IF (0(4).LT.0.) SGN=-1.0
DO 60 I=1,4
Q(I)=Q(I)*SGN
60 CONTINUE
RETURN
END

C-----------------------------------------------
SUBROUTINE AINV (A,B)
REAL A(3,3),B(3,3),COFA(3,3),DETA
INTEGER I,J
COFA(1,1)=A(2,2)*A(3,3)-A(2,3)*A(3,2)
COFA(1,2)=A(2,3)*A(3,1)-A(2,1)*A(3,2)
COFA(1,3)=A(2,1)*A(3,3)-A(2,2)*A(3,1)
COFA(2,1)=A(1,3)*A(3,2)-A(1,2)*A(3,3)
COFA(2,2)=A(1,1)*A(3,3)-A(1,3)*A(3,1)
COFA(2,3)=A(1,2)*A(3,1)-A(1,1)*A(3,3)
COFA(3,1)=A(1,2)*A(2,3)-A(1,3)*A(2,1)
COFA(3,2)=A(1,1)*A(2,2)-A(1,2)*A(2,1)
DETA=A(1,1)*COFA(1,1)+A(1,2)*COFA(1,2)
DO 126 I=1,3
DO 126 J=1,3
B(I,J)=COFA(J,I)/DETA
126 CONTINUE
RETURN
END

C-----------------------------------------------
SUBROUTINE TO CALCULATE THE INVERSE OF 3X3 MATRIX

C-----------------------------------------------
SUBROUTINE AINV (A,B)
REAL A(3,3),B(3,3),COFA(3,3),DETA
INTEGER I,J
COFA(1,1)=A(2,2)*A(3,3)-A(2,3)*A(3,2)
COFA(1,2)=A(2,3)*A(3,1)-A(2,1)*A(3,2)
COFA(1,3)=A(2,1)*A(3,3)-A(2,2)*A(3,1)
COFA(2,1)=A(1,3)*A(3,2)-A(1,2)*A(3,3)
COFA(2,2)=A(1,1)*A(3,3)-A(1,3)*A(3,1)
COFA(2,3)=A(1,2)*A(3,1)-A(1,1)*A(3,3)
COFA(3,1)=A(1,2)*A(2,3)-A(1,3)*A(2,1)
COFA(3,2)=A(1,1)*A(2,2)-A(1,2)*A(2,1)
DETA=A(1,1)*COFA(1,1)+A(1,2)*COFA(1,2)
$+A(1,3)*COFA(1,3)
DO 126 I=1,3
DO 126 J=1,3
B(I,J)=COFA(J,I)/DETA
126 CONTINUE
RETURN
END

C-----------------------------------------------
SUBROUTINE TO NORMALIZE QUATERNIONS

C-----------------------------------------------
SUBROUTINE NORMAL (O)
REAL Q(4),ON
INTEGER I
ON = 0.0
DO 10 I=1,4
QN = QN + Q(I)**2
10 CONTINUE
QN=1.5-.5*QN
DO 20 I=1,4
Q(I)=Q(I)*QN
20 CONTINUE
RETURN
END

C-----------------------------------------------
SUBROUTINE TO CALCULATE QUATERNION FROM EULER ANGLE SEQUENCE

C-----------------------------------------------
SUBROUTINE OINT(AA1,AA2,AA3,0)
REAL AA1,AA2,AA3,O(4),DTR
REAL AA1R,AA2R,AA3R,CC1,CC2,CC3,SS1,SS2,SS3
DTR=.0174532
AA1R =AA1*DTR*.5
AA2R =AA2*DTR*.5
AA3R =AA3*DTR*.5
CC1 =COS(AA1R)
SS1 =SIN(AA1R)
CC2 =COS(AA2R)
SS2 =SIN(AA2R)
CC3 =COS(AA3R)
SS3 =SIN(AA3R)
Q(1) =CC2*CC3*SS1+SS2*SS3*CC1
Q(2) =SS2*CC3*CC1-CC2*SS3*SS1
Q(3) =CC2*SS3*CC1+SS2*CC3*SS1
Q(4) =CC2*CC3*CC1-SS2*SS3*SS1
RETURN
END

SUBROUTINE TO CALCULATE CROSS PRODUCT C = A X B

SUBROUTINE CROSS (C,A,B)
REAL C(3),A(3),B(3)
C(1)=A(2)*B(3)-A(3)*B(2)
C(2)=A(3)*B(1)-A(1)*B(3)
C(3)=A(1)*B(2)-A(2)*B(1)
RETURN
END
C---------------------------------------------
C INITIALIZATION SECTION
C
C THIS SUBROUTINE DEFINES THE MASS PROPERTIES AND GEOMETRY
C OF THE CHASE AND TARGET VEHICLES.
C IT ALSO DEFINES THE INITIAL VEHICLE CONDITIONS, ORBITAL
C PARAMETERS, AND THE CONTROL SYSTEM VARIABLES.
C---------------------------------------------

SUBROUTINE STARTTT

INCLUDE 'cmmn.f'
INCLUDE 'cmmn1.f'
INCLUDE 'cmmn2.f'
INCLUDE 'cmmncon.f'
INCLUDE 'cmmnbb.f'

REAL QDUM(4),RORBK,GMEK,ALTK,REAK,RLA2K,RLA3K
REAL PI,TEM2(3,3),RFD,XKFM
INTEGER I,J

PI=3.1415926
RFD=PI/180.

C DIMENSION OF THE STATE VECTOR
NST=13

C THE ORIGIN OF THE VEHICLE FIXED FRAME, V, IS AT THE CENTER OF MASS

C TARGET VEHICLE MASS
MASSI=118.11

C THE VEHICLE MOMENT OF INERTIA MATRIX IS IN THE VEHICLE FIXED FRAME
C AND IS ABOUT THE VEHICLE CENTER OF MASS.
C
C AIV IS THE INERTIA MATRIX
C AIV1 IS INVERSE THE OF INERTIA MATRIX
C
C TARGET VEHICLE MOMENT OF INERTIA MATRIX BY ROWS
DO 10 I=1,3
  DO 10 J=1,3
    AIV1(I,J)=0.0
10 CONTINUE
AIV1(1,1)=723.41
AIV1(2,2)=2290.8
AIV1(3,3)=2290.8
CALL AINV (AIV1,AIVII)
THE INITIAL VEHICLE POSITION AND VELOCITY VECTORS ARE WITH RESPECT TO THE LOCAL VERTICAL, L, FRAME AND EXPRESSED IN THE LOCAL VERTICAL FRAME COORDINATES.

INITIAL TARGET VEHICLE LINEAR POSITION AND RATE
DO 20 I=1,3
   R1L(I)=0.0
   R1LD(I)=0.0
20 CONTINUE

THE VEHICLE ANGULAR RATES ARE WITH RESPECT TO THE INERTIAL, E, FRAME AND EXPRESSED IN THE VEHICLE FRAMES.

INITIAL TARGET VEHICLE INERTIAL ANGULAR RATES
IN DEGREES / SECOND
OMV1(1)=0.0
OMV1(2)=0.0
OMV1(3)=0.0
DO 5 I=1,3
   OMV1(I)=OMV1(I)*RFD
5 CONTINUE

EULER ANGLES, IN DEGREES, FOR TYPE 1,2,3 SYSTEM TO DEFINE TRANSFORMATION FROM LOCAL VERTICAL TO TARGET FRAME DEFINES TRANSFORMATION V1L

CALL QINT (0.,0.,0.,ODUM)
CALL AFO (V1L,ODUM)

CHASE VEHICLE MASS
MASS2=326.23

CHASE VEHICLE MOMENT OF INERTIA MATRIX BY ROWS
DO 25 I=1,3
   DO 25 J=1,3
      AIV2(I,J)=0.0
25 CONTINUE
AIV2(1,1)=6221.
AIV2(2,2)=3216.
AIV2(3,3)=3394.
CALL AINV (AIV2,AIV2I)

INITIAL CHASE VEHICLE LINEAR POSITION AND RATE WITH RESPECT TO LOCAL VERTICAL IN LOCAL VERTICAL COORD
DO 30 I=1,3
   R2L(I)=0.0
   R2LD(I)=0.0
30 CONTINUE
C INITIAL CHASE VEHICLE INERTIAL ANGULAR RATES
C IN DEGREES / SECOND

OMV2(1)=0.0
OMV2(2)=0.0
OMV2(3)=0.0

DO 15 I=1,3
   OMV2(I)=OMV2(I)*RFD
15 CONTINUE

C EULER ANGLES, IN DEGREES, FOR TYPE 1,2,3 SYSTEM TO DEFINE
C TRANSFORMATION FROM LOCAL VERTICAL TO CHASE FRAME
C DEFINES TRANSFORMATION V2L

C----------------------------------------------------------------------
CALL QINT (180.,0.,180.,ODUM)
CALL AFQ (VZL,QDUM)
C----------------------------------------------------------------------

C INPUT DOCKING/BERTHING PORT DEFINITION DATA

C THE DOCKING PORT LOCATION VECTOR IS FROM THE VEHICLE CENTER OF MASS
C TO THE ORIGIN OF THE DOCKING PORT FRAME. IT IS EXPRESSED IN
C THE COORDINATES OF THE VEHICLE FIXED FRAME.

S1 IS THE TARGET VEHICLE SENSOR COORDINATE FRAME

D1 IS THE DOCKING PORT COORDINATE FRAME ON THE TARGET VEHICLE

D2 IS THE CHASE VEHICLE DOCKING PORT COORDINATE FRAME

S1V1 IS THE TRANSFORMATION MATRIX FROM TARGET VEHICLE COORDINATES
C TO SENSOR COORDINATES.

D1V1 IS THE TRANSFORMATION MATRIX FROM TARGET VEHICLE COORDINATES
C TO DOCKING PORT COORDINATES

D2V2 IS THE TRANSFORMATION MATRIX FROM CHASE VEHICLE COORDINATES TO
C DOCKING PORT COORDINATES OF THE CHASE VEHICLE

RS1V1V1 IS THE POSITION VECTOR OF THE SENSOR IN TARGET VEHICLE COORDINATES
C WITH RESPECT TO THE TARGET CENTER OF MASS.

RD2V2V2 IS THE POSITION VECTOR OF THE CHASE DOCKING PORT IN CHASE
C VEHICLE COORDINATES WITH RESPECT TO THE CHASE CENTER OF MASS.

RD1V1V1 IS THE POSITION VECTOR OF THE DOCKING PORT IN TARGET
C VEHICLE COORDINATES WITH RESPECT TO THE TARGET CENTER OF MASS.

C----------------------------------------------------------------------
S1V1 TRANSFORMATION BY ROWS
DO 45 I=1,3
   DO 45 J=1,3
      S1V1(I,J)=0.0
45 CONTINUE
S1V1(1,3)=1.
S1V1(2,2)=1.
S1V1(3,1)=-1.

C C D2V2 TRANSFORMATION BY ROWS
DO 40 I=1,3
   DO 40 J=1,3
      D2V2(I,J)=0.0
40 CONTINUE
D2V2(1,1)=1.
D2V2(2,2)=1.
D2V2(3,3)=1.

C C D1V1 TRANSFORMATION BY ROWS
DO 50 I=1,3
   DO 50 J=1,3
      D1V1(I,J)=0.0
50 CONTINUE
D1V1(1,1)=-1.
D1V1(2,2)=1.
D1V1(3,3)=-1.

C C INPUT SENSOR LOCATION VECTOR
ON TARGET VEHICLE
RSlVlVl(1)=1.91667
RSlVlVl(2)=0.0
RSlVlVl(3)=0.0

C C INPUT DOCKING PORT LOCATION VECTOR
ON CHASE VEHICLE
RD2V2V2(1)=3.78125
RD2V2V2(2)=0.0
RD2V2V2(3)=0.0

C C INPUT DOCKING PORT LOCATION VECTOR ON TARGET VEHICLE
RD1VlVl(1)=4.0
RD1VlVl(2)=0.0
RD1VlVl(3)=0.0

C C TRANSFORM SENSOR POSITION VECTOR FROM TARGET VEHICLE COORDINATES
TO SENSOR COORDINATES.
C
CALL MVMUL(RS1V1S1,S1V1,RSlVlVl)

C C INITIAL ORBIT ANGLE NU20 IN DEGREES
RNU20=0.
RNU20=RNU20*RFD

C C NOMINAL ORBIT ALTITUDE IN NAUTICAL MILES
ALTK=260.

C C ASCENDING NODE ANGLE IN DEGREES
CALL EUL2 (TEM2, RLA2K)
CALL EUL3 (AE, RLA3K)
CALL MMUL33 (AE, TEM2)
CALL EUL2 (XLE, RNU20)
CALL MMUL33 (XLE, AE)
CALL MMUL3 (V1E, V1L, XLE)
CALL MMUL3 (V2E, V2L, XLE)

C---------------------------------------------
C INCLINATION ANGLE IN DEGREES
C---------------------------------------------
RLA3K=0.
RLA3K = RLA3K * RFD

C---------------------------------------------
C XKF=12.0*6076.0/39.37E3
C---------------------------------------------
C ALTK=ALTK*XXFM
C---------------------------------------------
C GMEK=3.9886E5
    !KM**3-S**-2
C---------------------------------------------
C
C CALCULATE THE RADIUS AND FREQUENCY OF THE NOMINAL CIRCULAR ORBIT
C REAK IS THE RADIUS OF THE EARTH IN KILOMETERS.
C---------------------------------------------
C REAK=6371.2
RORBK=REAK+ALTK
OMOSO=GMEK/RORBK**3

C---------------------------------------------
C OMO IS THE FREQUENCY OF THE NOMINAL CIRCULAR ORBIT
C OMO=SQRTO(OMOSO)
C---------------------------------------------
C
C CALCULATE THE INITIAL ANGULAR MOMENTUM VECTOR FOR EACH VEHICLE.
C THESE ARE EXPRESSED IN THE VEHICLE FIXED FRAMES.
C---------------------------------------------
C CALL MMUL(HTV1,AIV1,OMV1)
CALL MMUL(HTV2,AIV2,OMV2)
C---------------------------------------------
C DO 140 I=1,NST
    YD1(I)=0.0
    YD2(I)=0.0
140 CONTINUE

C---------------------------------------------
C CALCULATE THE INITIAL TRANSFORMATIONS FROM THE INERTIAL
C FRAME TO THE VEHICLE FIXED FRAMES.
C---------------------------------------------
C CALL EUL2(TEM2,RLA2K)
CALL EUL3(AE,RLA3K)
CALL MMUL33(AE,TEM2)
CALL EUL2(XLE,RNU20)
CALL MMUL33(XLE,AE)
CALL MMUL3(V1E,V1L,XLE)
CALL MMUL3(V2E,V2L,XLE)
CALL QFA(QV1E,V1E)
CALL QFA(QV2E,V2E)

C---------------------------------------
C                                      
C   INPUT INITIAL DATA FOR OMV CONTROL SYSTEM
C                                      
C---------------------------------------

RTD=57.29578
DTR=.0174532
IS=0

C

NDC=TD/DT
NDCI=NDC+1
DO 180 I=1,NDCI
  DO 180 J=1,6
    DELAY(I,J)=0.0
CONTINUE

180

C

CURRENT NUMBER OF A-D SIGNALS IN THE CONTROL VECTOR KDAT IS 7

C

NAD=7
AFUEL=0.0
DO 190 I=1,3
  IJONS(I)=0.0
  IJOFFS(I)=0.0
CONTINUE

190

C

IAUTOP=0
MPASS=0
ISTBSL=0
NOISE1=.05
NOISE2=.05
NOISO=NOISE1**2
ISAMP=1

C

SET SCALE FACTORS FOR A-D

C

SCX=2.
SCY=2.
SCZ=2.
DO 220 I=1,7
  SSIN(I)=1.
CONTINUE

220

C

SSIN(4)=10./6.7
SSIN(5)=10./3.8
SSIN(6)=10./7.9
YIN=1./2047.

C

SET INITIAL ERROR ANGLES TO ZERO

C

CALL QINT(0.,0.,0.,ODUM)
P31=ODUM(1)
P32=ODUM(2)
P33=ODUM(3)
P34=QDUM(4)
P31M1=P31
P32M1=P32
P33M1=P33
P34M1=P34
PD31=0.0
PD32=0.0
PD33=0.0
PD34=0.0
PD31M1=PD31
PD32M1=PD32
PD33M1=PD33
PD34M1=PD34

RETURN
END
PHYSICAL SYSTEM (PLANT) SUBROUTINE FOR TARGET VEHICLE

THE TARGET VEHICLE IS DENOTED BY THE NUMBER 1.

THIS SUBROUTINE CALCULATES THE TIME DERIVATIVE OF THE
TARGET VEHICLE STATE VECTOR. IT USES NEWTON-EULER AND
HILL'S EQUATIONS.

THE INPUT TORQUES ARE FROM THE VEHICLE CONTACT AND GRAVITY
GRADIENT.

THE INPUT FORCES ARE FROM THE VEHICLE CONTACT.

SUBROUTINE TARGET

INCLUDE 'cmmn.f'
INCLUDE 'cmmn1.f'

REAL VTEM(3)
INTEGER I,J

EXTRACT THE PHYSICAL PARAMETERS OUT OF THE STATE VECTOR Y.

ASSUME THAT THE STATE VECTOR IS CONSTRUCTED AS FOLLOWS:

Y=(HTV1,OV1E,R1LD,R1L)

HTV1 IS THE ANGULAR MOMENTUM VECTOR OF THE TARGET VEHICLE.
OV1E IS THE QUATERNION FOR THE TRANSFORMATION FROM THE
INERTIAL, E, FRAME TO THE TARGET VEHICLE FIXED FRAME.
R1LD IS THE VELOCITY OF THE TARGET VEHICLE CENTER OF MASS
WITH RESPECT TO THE L FRAME AND IN L FRAME COORDINATES.
R1L IS THE POSITION OF THE TARGET VEHICLE CENTER OF MASS
WITH RESPECT TO THE L FRAME AND IN L FRAME COORDINATES.

DO 100 I=1,NST
   YD01(I)=YD1(I)
100   CONTINUE

COMPUTE THE TOTAL GRAVITY GRADIENT TORQUES

DO 1500 I=1,3
   VTEM(I)=0.0
   DO 1500 J=1,3
      VTEM(I)=VTEM(I)+AIV1(I,J)*V1L(J,3)
   1500 CONTINUE
   T1G(1)=3.0*OMOSO*(V1L(2,3)*VTEM(3)-V1L(3,3)*VTEM(2))
   T1G(2)=3.0*OMOSO*(V1L(3,3)*VTEM(1)-V1L(1,3)*VTEM(3))
T1G(3)=3.0*OMOSQ*(V1L(1,3)*VTEM(2)-V1L(2,3)*VTEM(1))

C CALCULATE THE DERIVATIVE OF THE ANGULAR MOMENTUM VECTOR USING NEWTON-EULER EQUATION.

C

YD1(1)=T1G(1)+T1CGV1(1)-OMV1(2)*HTV1(3)+OMV1(3)*HTV1(2)
YD1(2)=T1G(2)+T1CGV1(2)-OMV1(3)*HTV1(1)+OMV1(1)*HTV1(3)
YD1(3)=T1G(3)+T1CGV1(3)-OMV1(1)*HTV1(2)+OMV1(2)*HTV1(1)

C CALCULATE THE DERIVATIVE OF THE QUATERNION

C

YD1(4)=.5*(OMV1(3)*QV1E(2)
  $-OMV1(2)*QV1E(3)+OMV1(1)*QV1E(4))$
YD1(5)=.5*(-OMV1(3)*QV1E(1)
  $+OMV1(1)*QV1E(3)+OMV1(2)*QV1E(4))$
YD1(6)=.5*(OMV1(2)*QV1E(1)
  $-OMV1(1)*QV1E(2)+OMV1(3)*QV1E(4))$
YD1(7)=-.5*(OMV1(1)*QV1E(1)
  $+OMV1(2)*QV1E(2)+OMV1(3)*QV1E(3))$

C CALCULATE THE ACCELERATION OF THE VEHICLE CENTER OF MASS WITH RESPECT TO THE L FRAME IN THE L FRAME COORDINATES.

C

YD1(8)=F1CL(1)/MASS1-2.*OMO*R1LD(3)
YD1(9)=F1CL(2)/MASS1-OMOSQ*R1L(2)
YD1(10)=F1CL(3)/MASS1+3.*OMOSQ*R1L(3)+2.*OMO*R1LD(1)
YD1(11)=Y1(8)
YD1(12)=Y1(9)
YD1(13)=Y1(10)

C RETURN
END