Appendix A.

Final Source Listing of Fuzzy Learning Modules for Shuttle Translational Controller
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: V Bar Approach

TIME (sec)

0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:53:45 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: V Bar Approach

MODULE: ORBITER_lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER_im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: V Bar Approach

MODULE: ORBITER
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: V Bar Approach

\[
\begin{array}{c}
0.501 \\
0.5 \\
0.499 \\
\hline
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\end{array}
\]

TIME (sec)

MODULE: ORBITER.linear
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]
RUN: V Bar Approach

\[ x[1] \]

TIME (sec)

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: V Bar Approach

<table>
<thead>
<tr>
<th>TIME (sec)</th>
<th>0</th>
<th>200</th>
<th>400</th>
<th>600</th>
<th>800</th>
<th>1000</th>
<th>1200</th>
<th>1400</th>
<th>1600</th>
<th>1800</th>
</tr>
</thead>
<tbody>
<tr>
<td>P</td>
<td>1.00199</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P</td>
<td>0.999993</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MODULE: ORBITER lm _range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[8] \text{ vs TIME} \]
RUN: V Bar Approach

MODULE: ORBITER\_im\_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[12] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[25] \text{ vs TIME} \]
\[ \text{RUN: R Bar Approach} \]

\[ 0.973244 \]
\[ 0.969358 \]
\[ 0.9631301 \]

TIME (sec)

MODULE: ORBITER.Im_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
d[36] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[37] \text{ vs TIME} \]
RUN: R Bar Approach

\[
\begin{array}{c}
\text{TIME (sec)} \\
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800
\end{array}
\]

MODULE: ORBITER lm range
DATA SAMPLING FREQUENCY: 0.200 Hz
d[48] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[49] \text{ vs TIME} \]
RUN: R Bar Approach

\begin{center}
\begin{tabular}{c}
\text{TIME (sec)} \\
\hline
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\hline
\end{tabular}
\end{center}

MODULE: ORBITERlm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: R Bar Approach
SIMULATION APPLICATION: ARIC Translational Controller Simulation

sfuel vs TIME
RUN: R Bar Approach

MODULE: ORBITER, primary
DATA SAMPLING FREQUENCY: 0.200 Hz
B3. Fly-Around from V-bar to R-bar vector in 30 minutes
TARGET CENTERED ROTATING CURVILINEAR LVLH X POS vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER
TARGET VEHICLE: SOLMAX
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y POS vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z POS vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR  3                   Fri Nov 20 1992 02:23:36 PM
TARGET CENTERED ROTATING CURVILINEAR LVLH X VEL vs TIME
RUN: Fly Around - V Bar To - R Bar

VEHICLE: ORBITER\textunderscore state
TARGET VEHICLE: SOLMAX\textunderscore state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y VEL vs TIME

RUN: Fly Around - V Bar To - R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z VEL vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y POS vs X POS

RUN: Fly Around - V Bar To - R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z POS vs X POS
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER state
TARGET VEHICLE: SOLMAX state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR

Fri Nov 20 1992 02:23:36 PM
TARGET CENTERED ROTATING CURVILINEAR LVLH Y VEL vs X VEL

RUN: Fly Around - V Bar To - R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Z VEL vs X VEL
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH EULER PYR ROLL vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH EULER PYR PITCH vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR

Fri Nov 20 1992 02:23:55 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH EULER PYR YAW vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY ROLL RATE vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY PITCH RATE vs TIME
RUN: Fly Around - V Bar To -R Bar

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY YAW RATE vs TIME
RUN: Fly Around - V Bar To - R Bar

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

sfuel vs TIME
RUN: Fly Around - V Bar To -R Bar

 MODULE: ORBITER.primary
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 1  Fri Nov 20 1992 02:24:10 PM
Phi vs TIME

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
push vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: Fly Around - V Bar To - R Bar

TIME (sec)

0.0002
0.00018
0.00016
0.00014
0.00012
0.0001
8e-05
6e-05
4e-05
2e-05
0
0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\[
\begin{array}{cccccccc}
0 & 0.5 & 0.525 & 0.55 & 0.575 & 0.6 & 0.625 & 0.65 & 0.675 & 0.7
\end{array}
\]

\[
\begin{array}{cccccccc}
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800
\end{array}
\]

TIME (sec)

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.Im.elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

$f[3]$ vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITERIm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[4] vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**f(5) vs TIME**

**RUN**: Fly Around - V Bar To -R Bar

**MODULE**: ORBITER.lm.elev

**DATA SAMPLING FREQUENCY**: 0.200 Hz

**ORBITAL OPERATIONS SIMULATOR**

12

Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[8] vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER
DATA SAMPLING FREQUENCY: 0.200 Hz

TIME (sec)
**SIMULATION APPLICATION: ARIC Translational Controller Simulation**

**f[9] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

<table>
<thead>
<tr>
<th>TIME (sec)</th>
<th>0</th>
<th>200</th>
<th>400</th>
<th>600</th>
<th>800</th>
<th>1000</th>
<th>1200</th>
<th>1400</th>
<th>1600</th>
<th>1800</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.913998</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0.91035</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**MODULE:** ORBITER.im.elev

**DATA SAMPLING FREQUENCY:** 0.200 Hz

**ORBITAL OPERATIONS SIMULATOR**

Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[10] vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[13] vs TIME
RUN: Fly Around - V Bar To -R Bar

0.952856
0.950954
0.949052

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[14] vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[15] \text{ vs } \text{TIME} \]
RUN: Fly Around - V Bar To -R Bar

\[
\begin{array}{c}
0.975426 \\
0.971532 \\
\end{array}
\]

\[
\begin{array}{cccccccccc}
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\end{array}
\]

TIME (sec)

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
d[9] vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[10] \text{ vs TIME} \]
\[ \text{RUN: Fly Around - V Bar To -R Bar} \]

\[ \begin{array}{c|cccccccccc}
\hline
0.942954 & 0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\hline
0.93919 & & & & & & & & & & \\
\hline
\end{array} \]

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[12] \text{ vs TIME} \]

RUN: Fly Around - V Bar To - R Bar

\begin{center}
\begin{tabular}{c}
\textbf{TIME (sec)}
\end{tabular}
\end{center}

\begin{center}
\begin{tabular}{c}
0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800
\end{tabular}
\end{center}

\begin{center}
\begin{tabular}{c}
0.96006 \quad 0.956228 \quad \text{\textit{144}}
\end{tabular}
\end{center}

\textbf{MODULE: ORBITER.IM._elev}

\textbf{DATA SAMPLING FREQUENCY: 0.200 Hz}

\textbf{ORBITAL OPERATIONS SIMULATOR}
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[13] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[15] vs TIME**
RUN: Fly Around - V Bar To -R Bar

<table>
<thead>
<tr>
<th>TIME (sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
</tr>
<tr>
<td>200</td>
</tr>
<tr>
<td>400</td>
</tr>
<tr>
<td>600</td>
</tr>
<tr>
<td>800</td>
</tr>
<tr>
<td>1000</td>
</tr>
<tr>
<td>1200</td>
</tr>
<tr>
<td>1400</td>
</tr>
<tr>
<td>1600</td>
</tr>
<tr>
<td>1800</td>
</tr>
</tbody>
</table>

MODULE: ORBITER.lm.elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[16] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\[ 0.945091 \]

\[ 0.941319 \]

\[ 0.940205 \]

TIME (sec)

MODULE: ORBITER_im_clev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[24] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\begin{align*}
\text{TIME (sec)} & \\
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
0.985022 & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad \\
0.983056 & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad \\
0.98109 & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad & \quad
\end{align*}

MODULE: ORBITER.\text{Im}_\text{elev}

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[25] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

<table>
<thead>
<tr>
<th>TIME (sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
</tr>
<tr>
<td>200</td>
</tr>
<tr>
<td>400</td>
</tr>
<tr>
<td>600</td>
</tr>
<tr>
<td>800</td>
</tr>
<tr>
<td>1000</td>
</tr>
<tr>
<td>1200</td>
</tr>
<tr>
<td>1400</td>
</tr>
<tr>
<td>1600</td>
</tr>
<tr>
<td>1800</td>
</tr>
</tbody>
</table>

**MODULE:** ORBITER.Im_elev

**DATA SAMPLING FREQUENCY:** 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
d[27] vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER improv
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[28] vs TIME
RUN: Fly Around - V Bar To -R Bar

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 28
Fri Nov 20 1992 02:25:02 PM
d[30] vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[31] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

**MODULE:** ORBITER.im_elev

**DATA SAMPLING FREQUENCY:** 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 30

Fri Nov 20 1992 02:25:02 PM
d[39] vs TIME

RUN: Fly Around - V Bar To -R Bar

TIME (sec)

0.945364

0.94159

0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.im.elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[40] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\begin{center}
\begin{tikzpicture}
\begin{axis}[
    width=\textwidth,
    height=0.8\textwidth,
    xlabel={TIME (sec)},
    ylabel={},
    xmin=0, xmax=1800,
    ymin=0.907158, ymax=0.910794,
    xtick={0,200,400,600,800,1000,1200,1400,1600,1800},
    ytick={0.907158,0.910794},
]
\end{axis}
\end{tikzpicture}
\end{center}

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[42] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\begin{align*}
0.981451 \\
0.977533
\end{align*}

\begin{align*}
0.792492 \\
0.792492
\end{align*}

\begin{align*}
0.77533 \\
0.77533
\end{align*}

\begin{align*}
0 & \ 200 & \ 400 & \ 600 & \ 800 & \ 1000 & \ 1200 & \ 1400 & \ 1600 & \ 1800 \\
\text{TIME (sec)}
\end{align*}

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 33
Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[43] vs TIME**

RUN: Fly Around - V Bar To - R Bar

**Module:** ORBITER.lm_elev

**Data Sampling Frequency:** 0.200 Hz

Orbital Operations Simulator

Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[45] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_elev

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 35

Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[46] vs TIME**
RUN: Fly Around - V Bar To -R Bar

```
0.979338

0.975428

0.975428

0 200 400 600 800 1000 1200 1400 1600 1800

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 36
Fri Nov 20 1992 02:25:02 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: Fly Around - V Bar To -R Bar

MODCLUDE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: Fly Around - V Bar To -R Bar

0.08
0.06
0.04
0.02
-0.02
-0.04
-0.06
-0.08

6.93889e-18
push

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.Im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\begin{center}
\begin{tikzpicture}
\begin{axis}[
    width=\textwidth,
    height=\textwidth,
    xlabel={TIME (sec)},
    ylabel={x[0]},
    xmin=0, xmax=1800,
    ymin=0.4, ymax=0.625,
    grid=both,
    grid style={line width=0.5pt, draw=gray!30},
    major grid style={line width=1pt, draw=gray!50},
    minor tick num=1
]
\addplot [black, line width=1pt] table [x expr=
\thisrow{TIME}, y expr=\thisrow{x[0]}] {data.csv};
\end{axis}
\end{tikzpicture}
\end{center}

MODULE: ORBITER.IM_RANGE
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\[ x[\_498] \]

\[ \begin{array}{cccc}
0.51 & 0.507 & 0.504 & 0.501 \\
0.495 & 0.492 & 0.489 & 0.486 \\
\end{array} \]

\[ \begin{array}{cccc}
0 & 200 & 400 & 600 \\
800 & 1000 & 1200 & 1400 \\
1600 & 1800 \\
\end{array} \]

TIME (sec)

MODULE: ORBITER

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER:Im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(8) \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\[ 0.967399 \]

\[ 0.963537 \]

\[ 0.8468 \]

TIME (sec)

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[12] vs TIME

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[16] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\[ 0.929462 \]
\[ 0.925752 \]

\[ 0.927607 \]

\[ 0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \]
TIME (sec)

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[24] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

Module: ORBITER.im_range

Data Sampling Frequency: 0.200 Hz

---

ORBITAL OPERATIONS SIMULATOR

12

Fri Nov 20 1992 02:25:11 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[25] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

**MODULE:** ORBITER:Im_range

DATA SAMPLING FREQUENCY: 0.200 Hz

TIME (sec)
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\( d[36] \) vs TIME

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz

Fri Nov 20 1992 02:25:11 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[37] vs TIME**
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.Ira_hinge
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[48] vs TIME**
RUN: Fly Around - V Bar To -R Bar

<table>
<thead>
<tr>
<th>Time (sec)</th>
<th>0</th>
<th>200</th>
<th>400</th>
<th>600</th>
<th>800</th>
<th>1000</th>
<th>1200</th>
<th>1400</th>
<th>1600</th>
<th>1800</th>
</tr>
</thead>
<tbody>
<tr>
<td>Value 1</td>
<td>0.977111</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Value 2</td>
<td>0.973211</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 16
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[49] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\[ 0.982156 \]

\[ 0.978236 \]

\[ 0.980196 \]

\[ 0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \] TIME (sec)

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: Fly Around - V Bar To - R Bar

unusualness -0.06
5e-06
4e-06
3e-06
2e-06
1e-06
0
TIME (sec)
0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER_lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBrrER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Fri Nov 20 1992 02:24:23 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: Fly Around - V Bar To -R Bar

TIME (sec)

0.0015
0.0012
0.0009
0.0006
0.0003
-0.0003
-0.0006
-0.0009
-0.0012
-1.0842e-19

Phi_dot

0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Fri Nov 20 1992 02:24:23 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

Fri Nov 20 1992 02:24:23 PM
unusualness vs TIME

RUN: Fly Around - V Bar To - R Bar

unusualness

0.0005
0.00045
0.0004
0.00035
0.0003
0.00025
0.0002
0.00015
0.0001
5e-05
0

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER Im_zim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: Fly Around - V Bar To - R Bar

0.5019

0.50085

0.500085

0.4998

0.49875

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.lm_zazim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\begin{align*}
\text{TIME (sec)}
\end{align*}

0.500944

0.49994

\begin{align*}
x[1]
\end{align*}

MODULE: ORBITER.Im_xzim

DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.lm_a_u
DATA
SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
v vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f(3) vs TIME
RUN: Fly Around - V Bar To -R Bar

TIME (sec)

MODULE: ORBITER.lm_azi
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[7] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\[ \text{TIME (sec)} \]

\[ 0.95388 \]
\[ 0.950072 \]
\[ 0.951976 \]

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[8] vs TIME
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_xzim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[9] vs TIME
RUN: Fly Around - V Bar To R Bar

MODULE: ORBITER.im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[13] \text{ vs TIME} \]

RUN: Fly Around - V Bar To - R Bar

\[ 0.923106 \]

\[ 0.91942 \]

TIME (sec)

MODULE: ORBITER.im_\text{azim}

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 14

Fri Nov 20 1992 02:24:23 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[9] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\begin{center}
\begin{tikzpicture}
\begin{axis}[
    title={Flownum\#000}
    ,width=\textwidth
    ,height=\textwidth
    ,xlabel={TIME (sec)}
    ,ylabel={\text{Value}}
    ,xmin=0
    ,xmax=1800
    ,ymin=0.944947
    ,ymax=0.941175
    ,axis x line=middle
    ,axis y line=middle
    ,axis x line=bottom
    ,axis y line=left
    ,grid=major
\end{axis}
\end{tikzpicture}
\end{center}

MODULE: ORBITER.im\_stim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[10] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[21] vs TIME**

**RUN:** Fly Around - V Bar To -R Bar

---

**MODULE:** ORBITER. Imzimzim

**DATA SAMPLING FREQUENCY:** 0.200 Hz
宗SIMULATION APPLICATION: ARIC Translational Controller Simulation

宗d[22] vs TIME
宗RUN: Fly Around - V Bar To - R Bar

TIME (sec)

MODUKE: ORBITER lm azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[24] \text{ vs TIME} \]

RUN: Fly Around - V Bar To -R Bar

\[ 0.961342 \]

\[ 0.9575041 \]

\[ 0.9529423 \]

\[ \text{TIME (sec)} \]

\[ 0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \]

MODULE: ORBITER lm_azi

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[25] vs TIME**
RUN: Fly Around - V Bar To -R Bar

MODULE: ORBITER.im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
Fri Nov 20 1992 02:24:23 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[27] \text{ vs TIME} \]
RUN: Fly Around - V Bar To -R Bar

\begin{center}
\begin{tikzpicture}
\begin{axis}[
width=\textwidth,
height=0.8\textwidth,
axis x line=bottom,
axis y line=left,
axis line style={-},
xtick={0,200,400,600,800,1000,1200,1400,1600,1800},
xticklabels={0, 200, 400, 600, 800, 1000, 1200, 1400, 1600, 1800},
ytick={0.972399, 0.968517, 0.9570458},
yticklabels={0.972399, 0.968517, 0.9570458},
]
\end{axis}
\end{tikzpicture}
\end{center}

TIME (sec)

MODULE: ORBITER.lm_ezim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[28] vs TIME
RUN: Fly Around - V Bar To - R Bar

TIME (sec)

0.998276
0.99429
0.99283

0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\( d[39] \) vs TIME
RUN: Fly Around - V Bar To - R Bar

MODULE: ORBITER.Lm_axism
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[40] vs TIME**

RUN: Fly Around - V Bar To -R Bar

<table>
<thead>
<tr>
<th>0.939683</th>
<th>0</th>
<th>200</th>
<th>400</th>
<th>600</th>
<th>800</th>
<th>1000</th>
<th>1200</th>
<th>1400</th>
<th>1600</th>
<th>1800</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.935931</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**TIME (sec)**

**MODULE:** ORBITER.lm_azim

**DATA SAMPLING FREQUENCY:** 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 24

Fri Nov 20 1992 02:24:23 PM
B4. Station-Keeping for 30 minutes at 50 feet distance on V-bar
TARGET CENTERED ROTATING CURVILINEAR LVLH X POS vs TIME

RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y POS vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z POS vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR 3 Sat Nov 21 1992 04:22:37 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH X VEL vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y VEL vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z VEL vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Y POS vs X POS
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

TARGET CENTERED ROTATING CURVILINEAR LVLH Z POS vs X POS
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Y VEL vs X VEL
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
TARGET CENTERED ROTATING CURVILINEAR LVLH Z VEL vs X VEL

RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
TARGET VEHICLE: SOLMAX.state
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH EULER PYR ROLL vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH EULER PYR PITCH vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
LVLH EULER PYR YAW vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY ROLL RATE vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY PITCH RATE vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER.state
DATA SAMPLING FREQUENCY: 0.521 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

LVLH BIASED BODY YAW RATE vs TIME
RUN: Station Keep At 200 Feet

VEHICLE: ORBITER
DATA SAMPLING FREQUENCY: 0.521 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

sfuel vs TIME
RUN: Station Keep At 200 Feet

MODULE: ORBITER.primary
DATA SAMPLING FREQUENCY: 0.200 Hz

Sat Nov 21 1992 04:22:53 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:52 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Range ARIC Learning Parameters - Learning Confidence

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:52 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Range ARIC Learning Parameters - Scaled Inputs

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:52 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Elevation ARIC Learning Parameters - Inputs

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:35 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Elevation ARIC Learning Parameters - General Parameters

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:35 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Elevation ARIC Learning Parameters - Learning Confidence

Time (sec)

\[ p \] (confidence)

\[ v \] (delta confidence)

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:35 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Elevation ARIC Learning Parameters - Scaled Inputs

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:35 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Azimuth ARIC Learning Parameters - Inputs

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:11 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Azimuth ARIC Learning Parameters - General Parameters

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:11 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Azimuth ARIC Learning Parameters - Learning Confidence

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:11 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
Azimuth ARIC Learning Parameters - Scaled Inputs

SIMULATION APPLICATION: ARIC Translational Controller Simulation
RUN IDENTIFICATION: Station Keep At 200 Feet
MODEL: ORBITER
DATE: Sat Nov 21 1992 04:20:11 PM
NUMBER OF DATA POINTS: 361
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[16] vs TIME
RUN: V Bar Approach

MODULE: ORBITER lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[24] vs TIME**

**RUN: V Bar Approach**

**TIME (sec)**

**MODULE: ORBITER_im_range**

DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARJC Translational Controller Simulation

$d[25]$ vs TIME
RUN: V Bar Approach

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[36] vs TIME
RUN: V Bar Approach

MODULE: ORB1T&dm_mnge
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 14
Tue Nov 17 1992 02:53:45 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[37] vs TIME
RUN: V Bar Approach

MODULE: ORBITER_in_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:53:45 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[48] \text{ vs TIME} \]
RUN: V Bar Approach

\[ 0.977111 \]
\[ 0.973211 \]

MODULE: ORBITER\_im\_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[49] \text{ vs TIME} \]

RUN: V Bar Approach

\begin{center}
\begin{tikzpicture}
\begin{axis}[
    xlabel={TIME (sec)},
    ylabel={},
    xtick={0,200,400,600,800,1000,1200,1400,1600,1800},
    ytick={0.982156,0.978236},
]
\addplot[""] coordinates { (0,0.982156) (1800,0.982156) };
\addplot[""] coordinates { (0,0.978236) (1800,0.978236) };
\end{axis}
\end{tikzpicture}
\end{center}

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: V Bar Approach
SIMULATION APPLICATION: ARIC Translational Controller Simulation

sfuel vs TIME
RUN: V Bar Approach

MODULE: ORBITER primary
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
B2. Shuttle R-bar Approach from 400 feet to 50 feet
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:05:42 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.Im_axim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
push vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.Im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: R Bar Approach

TIME (sec)

0.0005
0.00045
0.0004
0.00035
0.0003
0.00025
0.0002
0.00015
0.0001
0.00005
0.00005
0

unusualness vs TIME
RUN: R Bar Approach

TIME (sec)

0.0005
0.00045
0.0004
0.00035
0.0003
0.00025
0.0002
0.00015
0.0001
0.00005
0.00005
0

MODULE: ORBITER.Em_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: R Bar Approach

MODULE: ORBITER.Lm_zsim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

$x[0]$ vs TIME
RUN: R Bar Approach

TIME (sec)

0.5009
0.4998

MODULE: ORBITER.lm_axim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

x[1] vs TIME
RUN: R Bar Approach

MODULE: ORBITER lm_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_ezim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.lm_asim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[3] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[7] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_szim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f(8) vs TIME
RUN: R Bar Approach

MODULE: ORB1TERAm_a_m
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:05:42 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[9] \text{ vs } \text{TIME} \]
RUN: R Bar Approach

\[
\begin{array}{cccccccccccccccc}
& & & & & & & & & & & & & & & & \\
& & & & & & & & & & & & & & & & \\
0.988627 & & & & & & & & & & & & & & & & \\
& & & & & & & & & & & & & & & & \\
0.984681 & & & & & & & & & & & & & & & & \\
& & & & & & & & & & & & & & & & \\
0.986654 & & & & & & & & & & & & & & & & \\
& & & & & & & & & & & & & & & & \\
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 & \\
\end{array}
\]

TIME (sec)

MODULE: ORBITER.im_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[13] vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.Im_azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[9] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lmazel
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[10] \text{ vs TIME} \]

RUN: R Bar Approach

\[ \text{TIME (sec)} \]

MODULE: ORBITERlm_azim

DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[21] \text{ vs TIME} \]
RUN: R Bar Approach

\begin{center}
\begin{tabular}{c}
\hline
0.981931 \\
\hline
0.978011 \\
\hline
\end{tabular}
\end{center}

\begin{center}
\begin{tabular}{c}
\hline
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\hline
\end{tabular}
\end{center}

\begin{center}
TIME (sec)
\end{center}

MODULE: ORBITER_lm_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[22] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.Im_aziim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[24] vs TIME**

RUN: R Bar Approach

MODULE: ORBITER lm_azim

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[25] \text{ vs TIME} \]
RUN: R Bar Approach

\[
\begin{array}{c}
0.916164 \\
0.912506 \\
0.8754335
\end{array}
\]

TIME (sec)

MODULE: ORBITER_In_zer
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d_{27} \text{ vs TIME} \]
RUN: R Bar Approach

\[ 0.972399 \]
\[ 0.968517 \]

TIME (sec)

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[28] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_axim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:05:42 PM
d[39] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.hm_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[40] \text{ vs TIME} \]

RUN: R Bar Approach

<table>
<thead>
<tr>
<th>TIME (sec)</th>
<th>0.939683</th>
<th>0.935931</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td></td>
<td></td>
</tr>
<tr>
<td>200</td>
<td></td>
<td></td>
</tr>
<tr>
<td>400</td>
<td></td>
<td></td>
</tr>
<tr>
<td>600</td>
<td></td>
<td></td>
</tr>
<tr>
<td>800</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1000</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1200</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1400</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1600</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1800</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MODULE: ORBITER.Im_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:20 PM
Module: ORBITER.im_elev
Data Sampling Frequency: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: R Bar Approach

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
FAILURE vs TIME
RUN: R Bar Approach

failure 0

TIME (sec)

MODULE: ORBITER.Ira
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: R Bar Approach

[Graph showing time series data with a linear trend line and oscillations.]

MODULE: ORBITER:im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

$x[1]$ vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_e1ev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
v vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[3] \text{ vs TIME} \]
RUN: R Bar Approach

TIME (sec)

MODULE: ORBTRER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[4] \text{ vs TIME} \]

RUN: R Bar Approach

 MODULE: ORBITER.im_elev
 DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 11
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[5] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[8] vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[9] \text{ vs TIME} \]
RUN: R Bar Approach

\[ 0.914 \]
\[ 0.910352 \]
\[ 0.912176 \]

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[10] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_slew
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(13) \text{ vs TIME} \]

RUN: R Bar Approach

\[ 0.95 \Rightarrow 0.85 \]

\[ 0.949052 \]

\[ 0.952856 \]

\[ 0.949052 \]

\[ 0.952856 \]

MODULE: ORBTER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[14] \text{ vs TIME} \]
RUN: R Bar Approach

\[ 0.990062 \]

\[ 0.98611 \]

\[ 0.98611 \]

\[ 0.990062 \]

\[ 0.200 \text{ Hz} \]

\[ \text{DATA SAMPLING FREQUENCY: 0.200 Hz} \]

MODULE: ORBITER.im_elev

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[15] vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[9] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.In_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[12] vs TIME
RUN: R Bar Approach

MODULE: ORB_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[13] vs TIME
RUN: R Bar Approach

MODULE: ORBITER_im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[15] vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER_lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[16] \text{ vs TIME} \]
RUN: R Bar Approach

\[
\begin{array}{c|cccccccc}
\text{TIME (sec)} & 0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 \\
\hline
0.945091 & & & & & & & & & \\
0.941319 & & & & & & & & & \\
0 & & & & & & & & & \\
\end{array}
\]

MODULE: ORBITER lm.elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[24] \text{ vs TIME} \]
RUN: R Bar Approach

MODULE: ORBITER_im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

$\text{d[25] vs TIME}$
RUN: R Bar Approach

MODULE: ORBITER.Irn_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
d[27] vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.im.elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[28] vs TIME
RUN: R Bar Approach

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[30] \text{ vs } \text{TIME} \]
RUN: R Bar Approach

MODULE: ORBITER.im_clev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 29 Tue Nov 17 1992 03:06:20 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[39] \text{ vs TIME} \]
RUN: R Bar Approach

\(
\begin{array}{cc}
0.945364 & \\
0.94159 & \\
\end{array}
\)

\( \text{TIME (sec)} \)

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[42] vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:20 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[43] vs TIME**

**RUN: R Bar Approach**

**TIME (sec)**

**MODULE:** ORBITER lm_elev

**DATA SAMPLING FREQUENCY:** 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 34

Tue Nov 17 1992 03:06:20 PI
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[45] \text{ vs TIME} \]
RUN: R Bar Approach

\begin{align*}
0.947011 & \quad 0.943231 \\
0.943231 & \quad 0.943121 \\
\end{align*}

\begin{align*}
\text{TIME (sec)} & \\
0 & \quad 200 & \quad 400 & \quad 600 & \quad 800 & \quad 1000 & \quad 1200 & \quad 1400 & \quad 1600 & \quad 1800 \\
\end{align*}

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:20 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[46] \text{ vs TIME} \]

RUN: R Bar Approach

\[
\begin{array}{c}
0.979338 \\
0.975425 \\
0.975428 \\
\end{array}
\]

\[
\begin{array}{c}
0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \\
\end{array}
\]

\[
\begin{array}{c}
\text{TIME (sec)} \\
\end{array}
\]

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: R Bar Approach

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

$x(0)$ vs TIME
RUN: R Bar Approach

0.501

0.5

0.499

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:49 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]
RUN: R Bar Approach

\[
\begin{align*}
0.5 & \\
0.4 & \\
0.3 & \\
0.2 & \\
0.1 & \\
0.0 & \\
2.77556e-17 & \\
-0.1 & \\
-0.2 & \\
-0.3 & \\
\end{align*}
\]

TIME (sec)

MODULE: ORBITER_lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: R Bar Approach

MODULE: ORBITER.im_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: R Bar Approach

TIME (sec)

MODULE: ORBITER.lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[8] vs TIME
RUN: R Bar Approach

0.967399
0.963537

0.963468

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.Jm_range
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(12) \text{ vs TIME} \]
RUN: R Bar Approach

MODULE: ORBITER
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:49 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\( f[16] \) vs TIME
RUN: R Bar Approach

0.929462

0.925752

0.929462

0.925752

TIME (sec)

MODULE: ORBITERlm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:49 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[24] \text{ vs TIME} \]
RUN: R Bar Approach

0.901925

0.898325

0.898325

TIME (sec)

MODULE: ORBITER_lm_range
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 03:06:49 PM
RICIS Preface

This research was conducted under auspices of the Research Institute for Computing and Information Systems by Dr. Yashvant Jani of the Technology Systems Division of Togai InfraLogic, Inc. Dr. Kwok-bun Yue served as the RICIS research coordinator.

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The views and conclusions contained in this report are those of the author and should not be interpreted as representative of the official policies, either express or implied, of UHCL, RICIS, NASA or the United States Government.
Research Activity AR.06

APPLICATION OF FUZZY LOGIC-NEURAL NETWORK BASED REINFORCEMENT LEARNING TO PROXIMITY AND DOCKING OPERATIONS

Deliverable D3
Report on the Shuttle Translational Control Results
submitted to
The Research Institute for Computing and Information Systems
University of Houston-Clear Lake
Houston, Texas 77058-1096

Prepared by
Yashvant Jani
Technology Systems Division
Togai InfraLogic Inc.
Houston, Texas 77058

November 15, 1992
APPLICATION OF FUZZY LOGIC-NEURAL NETWORK BASED REINFORCEMENT LEARNING TO PROXIMITY AND DOCKING OPERATIONS

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Houston, Texas 77058

November 15, 1992
Table of Contents

1.0 Introduction .................................................. 1
2.0 Fuzzy Learning System Baseline Configuration ............... 1
3.0 Fuzzy Logic based Shuttle Translational Control .......... 6
4.0 Description of Test Cases ..................................... 13
5.0 Results and Conclusions ..................................... 16
6.0 Future Plans and Summary .................................. 16

Appendix A. Source Code Listing of Fuzzy Learning Modules for Translational Control ........................................ 17
Appendix B. Plots of Selected Parameters for Translation Testcases ..................................................... 54

List of Figures

1. Attitude Controller membership Functions - Overlapping Rate Error MBF's. ........................................ 4
2. Definition of Relative Trajectory Control. ..................... 7
3. Membership Functions for Elevation Control. ................ 8
4. Membership Functions for Azimuth Control. ................ 10
5. Membership Functions for Range Control. .................... 11
6. Definition of v-bar and r-bar Approach Testcases. .......... 14
7. Definition of Fly-Around Testcase. ............................ 15

List of Tables

I. Rulebase for Attitude Control. ............................... 5
II. Rulebase for Elevation Control. ............................. 9
III. Rulebase for Azimuth Control. .............................. 9
IV. Rulebase for Range Control. ................................. 12
1.0 Introduction:

As part of the RICIS project # AR.06 activity, the reinforcement learning techniques developed at Ames Research Center are being applied to proximity and docking operations using the Shuttle and Solar Maximum Mission (SMM) satellite simulation. In utilizing these fuzzy learning techniques, we also use the Approximate Reasoning based Intelligent Control (ARIC) architecture, and so we use two terms interchangeable to imply the same. This activity is carried out in the Software Technology Laboratory utilizing the Orbital Operations Simulator (OOS).

This report is the deliverable D3 in our project activity and provides the test results of the fuzzy learning translational controller. This report is organized in six sections. Based on our experience and analysis with the attitude controller, we have modified the basic configuration of the reinforcement learning algorithm in ARIC as described in section 2. The shuttle translational controller and its implementation in fuzzy learning architecture is described in section 3. Two test cases that we have performed are described in section 4. Our results and conclusions are discussed in section 5, and section 6 provides future plans and summary for the project.

2.0 Fuzzy Learning System Configuration

In this section, we have described the changes/modifications we have made in the fuzzy learning algorithms within the ARIC framework. These changes were determined necessary based on our study so far to properly utilize the fuzzy learning techniques for space operations. The ARIC algorithm with these changes provides us a baseline that we will use for all translational modules - range, azimuth and elevation control.

a. Remove bias from all inputs and rules.

We have learned from the attitude controller performance that the bias term really limits the fuzzy controller's ability to perform, especially when the bias term is kept constant at 0.5 value throughout the learning cycle. The bias was zeroed out in several test cases and results showed good improvements, particularly in learning the environment. Therefore, we have decided to remove bias from our future implementations. We have also discussed this issue with Dr. Berenji at Ames and he also agrees that if we do not need bias, then, it would be better for the learning system.

b. Updates of d's and f's both depend on the belief value of premise as well as consequent part of the rule.

In our earlier experiments, we observed that the variations in all d's and all f's were the same, meaning that if d(1) changes by an amount, then d(2) will change by the same amount, even though, the initial values of d(1) and d(2) are different. This behavior is not acceptable in the sense that the coefficients d's and f's should have different variations based on which rules fire. We examined the formulas that update these weights, and concluded that the best way to incorporate effects of rule firing is to include the strength in the update of coefficient f. Similarly, the d's should be updated using the belief value from the fuzzification of the premise side of the rule. Both of these changes were discussed in detail with Dr. Berenji, Dr. Lea and our team. It is very appropriate to utilize these changes in the algorithm, and therefore, we implemented these modifications.
c. Crisp failure with protection.

Our current implementation uses what we call crisp failure, e.g. 0 or -1, at 1.4 DB, but we must protect the weight updating from too much punishing. Since failure is based on a parameter value, it can continue to be a failure for many cycles. If the weights are updated for few cycles with a large punishment, the controller goes unstable and can not recover at any time during the mission. This is not allowed and will not be allowed for space operations. So we need to protect against too much punishing that can result in total catastrophe.

d. Action changed to no action rather than reverse action.

In the earlier version of ARIC, the Stochastic Action Modifier (SAM) changed the 'push' from one way to the other way, if the random probability exceeded the measure of confidence p calculated using the Action Selection Network coefficients. This means that the controller requires a positive torque, but the random probability at that time is larger than the measure of confidence p (output of Action Selection network), then SAM changed the positive torque to negative torque. { 'push' is changed to '-push' }. This process for space operations is not acceptable because the negative torque in such case will perturb the state too much and the controller may not be able to recover from such an action.

In space operations, typically, an action is taken or no action is taken. It is seldom the case that an action is changed to its reverse. We also understand that such a process is desired in learning process, because the fuzzy learning technique is exploring all possible solution space. However, if we want to implement these learning techniques on a spacecraft so that it learns real time, this process must be changed to lower the risks. Therefore, we suggest to use the following procedure.

If the random probability is larger than the measure of confidence p, then SAM should change the action to no action, meaning that the push value is set to zero, and not to its negative. We accomplish several benefits from this type of process.

First, the controller will still learn from the search of solution. Now it is learning if the action recommended by the controller is really working or not. It really learns what happens when the action is not taken. Second, the controller will not be punished too much and thus it will be possible to maintain the performance rather than degrade it. Third, the solution will be slowly discarded rather than catastrophic failure. The weight updates during this time may result in a better solution. Fourth, process like this one is acceptable for space operations without increasing the risk of failure. Operationally, it is never acceptable to change an action to its reverse until there is a very high confidence that the reverse action is really needed. In our technique, since we have low confidence in an action, it should not be interpreted as high confidence in reverse action. Thus, logically it also makes sense for caring out operations.

e. No changes to computations for measure of confidence.

The measure of confidence 'p' is computed as originally proposed rather than normalizing using the number of rules. During the analysis of attitude controller performance we suggested that the measure of confidence p should be normalized per rule so that it will not continue to saturate during the learning process. We performed several attitude controller tests with this normalization, and had observed good learning rate for the neural network. However, now our main concern stems from the fact that the decision to fire jets was not arrived at by firing just one rule. Entire rulebase was utilized in the process, so for that reason we should not normalize the p-value. One can also argue that all rules were not used in deriving the controller action. We should properly scale the p-value using the number of rules fired. If we know that only four rules are responsible for the decision, then, we can normalize using these four rules. However,
it is not possible to find out which four rules are responsible. Thus, it is best not to normalize the measure of confidence. Furthermore, the d's and f's are being updated using the firing strength from the left hand side and right hand side of the rules anyway. Thus, the calculation of 'p' will include effect of long term behavior.

f. Input parameters normalized between 0.0 and 1.0.

We were first normalizing the input parameters phi error and phi_dot error between -1.0 and +1.0. The reinforcement learning algorithms at this time require that the input parameters be normalized between 0.0 and +1.0. We have changed the attitude controller to reflect this change. In our opinion, there are no guidelines in neural network algorithms how to normalize input and output parameters. It is a research area to generate guidelines which parameters should scaled between 0.0 and 1.0, and which one should be scaled between -1.0 and +1.0. For example, range has no negative values, and there is what so ever no interpretation when a sensor measure negative range except that the sensor is failed. Similarly, mass of an object is never negative.

g. Overlapping Membership Functions.

During the analysis of attitude control performance, we discovered that the fuzzy learning technique uses a lot more fuel compared to fuzzy controller alone. Our results showed that the fuzzy learning or ARIC used three to eight times the fuel used by fuzzy only control. Further analysis showed that the defuzzification by Tsukomoto's method does not allow to use triangular membership functions for output. As a result we had to use only one side of the triangle. When we used only one side of the triangle, it resulted in a large hysteresis in the jet firing command sequence. Once the jets are turned on to provide torque in a desired direction, they are not turned off as soon as the rate error is corrected. The jets remain on for additional three to four cycles providing increased rate in the reverse direction. The angle error then hits the other side of the deadband. The control system then fires jets to reduce the angle error that was really caused by the previous unnecessary jet firing. Net effect is larger fuel usage and more angular activity.

We further analyzed the rate error membership functions, and decided to overlap them (as shown in Fig. 1) to reduce the net hysteresis. We performed several tests to find a proper overlap, and now we have reduced the hysteresis to no hysteresis. We have decided to use this attitude controller in all our future tests. The rulebase for the attitude controller is shown in Table I for completeness. The translational controller uses this new attitude controller with overlap in rate membership functions. However, we will not utilize such overlap in rate errors for translational controller because we need to analyze the performance without such overlap. At this time we do not know if a hysteresis exists in the translational control.
**Fig. 1** Attitude Controller Membership functions - Overlapping Rate Error MBF's

**KEY:**
- NB - Negative Big
- NM - Negative Medium
- NS - Negative Small
- ZO - Zero
- PS - Positive Small
- PM - Positive Medium
- PB - Positive Big
Table I. Fuzzy Rulebase for Attitude control

<table>
<thead>
<tr>
<th>Rate Error</th>
<th>Angle Error</th>
<th>NB</th>
<th>NM</th>
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KEY:
NB - Negative Big, NM - Negative Medium, NS - Negative Small, ZO - Zero, PS - Positive Small, PM - Positive Medium, PB - Positive Big
3.0 Fuzzy Logic based Shuttle Translational Controller

We have implemented the shuttle translational controller using TILShell and fuzzy-C compiler in the software technology laboratory. Development of this translational controller and its performance was reported at the AIAA Guidance, Navigation, and Control Conference in 1991. We plan to utilize the same controller with minimum changes in the ARIC architecture.

The control tasks during the proximity operations are: 1) maintain desired range by controlling the thrust along the line of sight, 2) keep the elevation angle close to zero with respect to line of sight, and 3) keep the azimuth angle close to zero with respect to line of sight. It is expected that the attitude controller is performing with desired accuracy in maintaining the desired angle and rate. This assumption is necessary because the translational controller is slaved after the attitude controller in the shuttle manual operations.

The input parameters to the translational controller are range, range rate, elevation angle, azimuth angle, elevation rate, and azimuth rate as shown in Fig. 2. In reality only three parameters are measured and their rates are derived using differencing method at regular intervals. The output parameters are the translational hand controller commands (Fig. 2) that fire the jets in a given direction. There are three hand controller commands known as THC-X, THC-Y, and THC-Z used in jet select logic to fire the jets for thrust in x, y and z directions with respect to the shuttle. Typically range and range rates are used to generate the approach thrust, and the elevation and azimuth angles are used to generate side thrusts to maintain the line of sight. The THC axes are transformed into appropriate direction by transformation matrix that involves the attitude of the shuttle in the local horizontal local vertical coordinate frame. The software for this transformation is already a part of the flight software in OOS.

We have designed the membership functions for all input and output parameters using the baseline earlier developed. Membership functions for elevation error, elevation rate error and its corresponding commanded delta-v are shown in Fig. 3, and its rulebase is shown in Table II. Since the elevation error membership functions are designed specially for the Shuttle operations, they are very asymmetric with respect to the positive and negative values in their Universe of Discourse. This asymmetry is required because the shuttle's center of mass is very far away from the radar location from where the parameters are measured. Since the ARIC architecture can not use triangular membership functions in the output set, we have used only one side of the triangle as shown in Fig. 3. This is very similar to the attitude control output membership functions shown in Fig. 1. Membership functions for azimuth control are shown in Fig. 4, where the azimuth error and its rate error are input and the commanded delta-v is output. The rulebase is shown in Table III. The range error, range rate error and commanded delta-v membership functions for the relative distance control are shown in Fig. 5, and the rulebase that generates these commanded delta-v's using range error and range rate error as two inputs is shown in Table IV. Please note that the output parameter membership functions are one sided triangles because the way ARIC defuzzification method is implemented.
Fig. 2 Definition of Relative Trajectory Control
Fig. 3 Membership Functions for Elevation Control
Table III. Rulebase for azimuth control

<table>
<thead>
<tr>
<th>AZIMUTH RATE ERROR</th>
<th>NM</th>
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Table II. Rulebase for elevation control

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KEY:
NB - Negative Big, NM - Negative Medium, NS - Negative Small, ZO - Zero, PS - Positive Small, PM - Positive Medium, PB - Positive Big
Fig. 4 Membership Functions for Azimuth Control
Fig. 5 Membership Functions for Range Control
**Table IV. Rulebase for range control**

<table>
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<tr>
<th>RANGE RATE ERROR</th>
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**KEY:**

NB - Negative Big, NM - Negative Medium, NS - Negative Small, ZO - Zero, PS - Positive Small, PM - Positive Medium, PB - Positive Big
4.0 Description of Test Cases

For our translational controller we have performed four testcases. These testcases were also performed for the fuzzy logic based 6 DOF controller and we have the man-in-the-loop simulation data that provides us insight as to how the Shuttle crew is trained for performing these proximity operations.

The first test case is the v-bar approach where the shuttle is initialized at 400 feet distance in the front of the satellite. The pitch attitude of the Shuttle is 90 degrees (as shown in Fig. 6) so that a crew member can see the satellite from the window or the Crew Optical Alignment System (COAS) for measuring the angles of the satellite relative to the line of sight. In our case we are using a radar like sensor placed at its proper location for measurements. The Shuttle has a closing rate of 0.4 feet per second. Its mission time-line calls for maintaining certain closing rate as a function of distance. As it approaches 50 feet distance, the mode changes to Station-keeping during which this distance is maintained. It approximately takes 1400 seconds for the Shuttle to complete this transition from 400 feet to 50 feet. The second test case known as r-bar approach is similar to the first one. Instead of v-bar it approaches along r-bar. The Shuttle is initialized at 400 feet on r-bar which is the z-axis of the LVLH frame as shown in Fig. 6. The pitch attitude of the Shuttle is zero degrees, and it sees the satellite from the window or COAS or radar. The trajectory is as shown in Fig. 6.

The third test case is the Fly-Around test case. The Shuttle is initialized at 200 feet on v-bar with pitch attitude of 90 degrees very similar to the v-bar case. However, its pitch rate is initialized at 0.05 deg per sec, and thus it will rotate to increase the pitch angle. As the Shuttle rotates, the elevation angle will change and the range rate may also change. The elevation control rulebase will see this change in the elevation angle and fire the jets to move the Shuttle upward. As a results, the Shuttle will translate upward of v-bar. As the pitch rate continues to be non-zero, the elevation angle will continue to change, and the elevation control will keep the Shuttle pushing upward. When the Shuttle moves sufficiently upward, its range will increase, and then, the range control will initiate the range rate to reduce the range to 200 feet. Thus, the Shuttle will traverse a circular path as shown in Fig. 7, and will reach the negative r-bar in a certain given time. Actually, the initial pitch rate of 0.05 will set the arrival time of 1800 seconds. If the 90 Fly-around is desired in 900 seconds, then, the initial pitch rate should be 0.1 deg per sec. The mission time-line is typically set using this type of calculations.

The fourth testcase is the station-keeping testcase, where the Shuttle is initialized at 200 feet distance on v-bar with 90 deg pitch angle and zero pitch rate. The range must be maintained within the range deadband as the mission time increases. Also, the elevation and azimuth angles must be maintained near zero. This activity is very simple and very boring for the Shuttle crew. There is not much jet firing activity and the drift in range is very slow, so the Shuttle is not moving relatively fast. However, this station-keeping is an important activity because it allows the Shuttle crew to check out sensors and other systems. We have set up this activity for 1800 seconds to be consistent with all other testcases.
Fig. 6 Definition of Proximity Operations v-bar and r-bar Approaches
Fig. 7 Definition of Proximity Operations fly-around Segment
5.0 Results and Conclusions

In all four testcases, the translational controller in ARIC architecture works; it achieves the desired position at the end of the proximity operations segment. This behavior is expected because the translational controller derived in ARIC is from the fuzzy logic based controller which has given very good results. In all testcases, we observed that the fuel usage is comparatively large. Since we have not tried to optimize the membership functions, particularly the rate membership functions, to achieve any fuel efficiency or any performance improvement, this behavior is again expected for this controller.

The Action Evaluation Network and Action Selection Networks do not learn much because of short mission duration time. Each of the testcase is only 1800 seconds long. In our attitude controller testcase, these two networks learned the environment over 50,000 seconds training time. Coefficients d's and f's were stabilized after this long training. We suggest that we use the station-keeping testcase for 100,000 seconds to train these two networks and see what happens. Any other testcase is not feasible to use because it will require to set up initial conditions again and again.

Coefficients d's and f's are being updated properly and the networks seem to handle these updates favorably. The Fly-Around trajectory is not that good in comparison to what an experienced crew member will fly. However, this is expected because the networks are in training. Trajectories in other testcases seem to be expectable. The scaling of input parameters is based on full Universe of Discourse resulting in a small variation of inputs within 0.0 and 1.0 range. Typically, we expect that x(0) and x(1) should vary between 0.2 and 0.8 for proper learning. In current testcases, it varies between 0.45 and 0.55 or even less. This is really not good for network training.

6.0 Future Plans and Summary

First of all we plan to change the scaling properly so that the input parameter variations are within 0.2 to 0.8 range. To achieve such scaling, we will have to change the source code of all three modules and re-compile them. We will perform all testcases again and generate all plots for detail analysis. Next we plan to overlap the rate membership functions and try to optimize the fuel usage. Based on the results, we expect that there is a hysteresis within the rate membership functions and we should remove it by modifying the rate membership functions as we did for the attitude controller.

We then plan to set up a test case that will simulate the shuttle docking operations. In this test case, the shuttle will approach the solar max satellite from 50 feet to 2 feet and hold the relative orientation for a specified time at the final distance so that the grappling task can be performed. We will analyze the performance of ARIC and learning modules for this test case and provide a presentation and proper documentation for the results.
A1. Source code for range control
#include <stdio.h>
#include <math.h>
#include <sys/types.h>

/* EXTERNAL DATA STRUCTURE DEFINITION */
#include "../orb_fuzzy/learn_cycle.h"
#define max(x,y) ( (x > y) ? x : y )
#define min(x,y) ( (x < y) ? x : y )
#define Gamma 0.9
#define Beta 0.2
#define Beta_h 0.05
#define Rho 1.0

extern double sgn();
extern double exp();
extern double rnd();
extern double sim_time();

learn_range(L)
LEARN_CYCLE * L;
/*IN : */
{
    int i,il, j, k;
    double range_match(), range_calculate_z_array();
    double temp;

    L->x[0] = (L->Phi+10)/20 ;
    L->x[1] = (L->Phi_dot + 5)/10.0 ;

    /* CC 6 November, 1992 */
    /* CC Turn off learning when there is a failure */
    /* CC until there has been no failure for 4 pass */
    L->fourth_pass_failure = L->third_pass_failure ;
    L->third_pass_failure = L->second_pass_failure ;
    L->second_pass_failure = L->first_pass_failure ;
    L->first_pass_failure = 0 ;
    if(L->failure == -1) {
        L->first_pass_failure = 1 ;
    } /* end if */

    /* If No Failure in the last 4 passes then turn learning on */
    if( !L->fourth_pass_failure &&
/* If Failure first pass, but not second pass, let the learn flag stay on, so that the failure is processed. On the next pass (where there is a failure second pass, but not third pass) then turn learning off until there are no failures for four passes */
if( L->second_pass_failure && !(L->third_pass_failure) ) {
    L->learn_flag = 0;
} /* end if */

/* output: state evaluation */
for (i = 0; i < 25; i++) {
    L->sum = 0.0;
    for(j = 0; j < 3; j++) {
        L->sum += L->a[i*3+j] * L->x_old[j];
    }
    L->y[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum = 0.0;
for(i = 0; i < 25; i++) {
    L->sum += L->c[i] * L->y[i];
}
L->suml = 0.0;
for ( j = 0; j < 3; j++) {
    L->suml += L->b[j] * L->x_old[j];
}
L->v = L->sum + L->suml;

/* output: action */
for(i = 0; i < 25; i++) {
    il=i;
    L->w[i] = range_match(il,L);
    L->zl[i] = range_calculate_z_array(il,L);
}
L->numl = 0.0;
L->denom = 0.0;
for(i = 0; i < 25; i++) {
    L->numl += L->w[i] * L->zl[i] * L->f[i] ;
    L->denom += L->w[i]*L->f[i] ;
}

/* JUNE 9, 1992 - CORRECTION !!! */
/* Add test for denom very small compared to suml - no rule firing zone */
/* L->push = (1000.0*fabs(L->denom)<fabs(L->suml))?0.0:L->suml/L->denom;*/
if(fabs(L->numl)<0.01 || fabs(L->denom)<0.01) {
    L->push = 0.0;
} else {
    L->push = L->numl/L->denom ;
} /* end if */
/* output: action computations completed */
for(i = 0; i < 25; i++)
{
    L->sum = 0.0;
    for (j = 0; j < 3; j++)
        L->sum += L->d[i*3+j] * L->x_old[j];
    L->z[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum2 = 0.0;
L->sum3 = 0.0;
for(i = 0; i < 3; i++)
    L->sum2 += L->e[i] * L->x_old[i];
for (i = 0; i < 25; i++)
    L->sum3 += L->f[i] * L->z[i];
L->sum4 = L->sum3 + L->sum2 / 3.0;
L->p = 1.0 / (1.0 + exp(-1.0 * L->sum4));

/* 15 April 1992 - Use temp variable - not push */
/* 28 Sept 1992 - Change definition of unusualness to correspond with Hamid's notes. */
if (rand() <= ((L->p+1.0)/2.0)) {
    L->unusualness = 1.0 - L->p;
} else {
    L->push = 0.0;
    L->unusualness = -L->p;
} /* end if */
L->sum += L->a[i*3+j] * L->x[j];
}
L->y_new[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum = 0.0;
L->sum1 = 0.0;
L->sum2 = 0.0;

for(j = 0; j < 3; j++)
    L->sum1 += L->b[j] * L->x[j];
for(i = 0; i < 25; i++)
    L->sum2 += L->c[i] * L->y_new[i];
L->sum = L->sum1 + L->sum2;
L->v_new = L->sum;

/*CCC*/
/* 17 September, 1992 */
/* This logic depends upon a "crisp" (two valued) failure */
/* It has been replaced by "fuzzy" failures */
/* action evaluation */
    if (L->failure)
        L->r_hat = L->failure - L->v;
    else
        L->r_hat = L->failure + Gamma * L->v_new - L->v;
/*CCC*/
/* L->r_hat = -1.0 * L->failure */
/* (1.0 - L->failure ) * Gamma * L->v_new - L->v ; */

/* modification and update to parameters */
for(i = 0; i < 25; i++)
    { 
        L->factor1 = Beta_h * L->r_hat * L->y[i] * (1.0 - L->y[i]) * sgn(L->c[i]);
        L->c[i] += Beta * L->r_hat * L->y[i];
        for(j = 0; j < 3; j++)
            { 
                L->a[i*3+j] += L->factor1 * L->x_old[j];
            }
    }

for(i = 0; i < 3; i++)
    L->b[i] += Beta * L->r_hat * L->x_old[i];
for(i = 0; i < 25; i++)
    { 
        L->factor2 = Rho_h * L->r_hat * L->z[i] * (1.0 - L->z[i]) * sgn(L->f[i])*L->unsualness;
        for(j = 0; j < 3; j++)
            { 
                if( L->learn_flag )
                    { 
                        L->d[i*3+j] += L->factor2 * L->x_old[j] * L->d_weights[i*3+j];
                    }
            } /* end if */
    } /* end for */
}
for(i = 0; i < 25; i++)
{
    if( L->learn_flag ) {
        L->f[i] += Rho * L->r_hat * L->unusualness * L->z[i] * L->w[i];
    } /* end if */
}

L->e[i] += Rho * L->r_hat * L->unusualness * L->x_old[i];

L->x_old[0] = L->x[0];
L->x_old[1] = L->x[1];
L->x_old[2] = L->x[2];

double sgn(x)
double x;
{
    if( x < 0.0)
        return (-1.0);
    else if (x > 0.0)
        return (1.0);
    else
        return (0.0);
}

double zero_one(x)
double x;
{
    if (x < 0) return (0.0);
    else if (x > 1) return (1.0);
    else return (x);
}

double range_nbl(x)
double x;
{
    return(min( max((-4-x)/4 , 0.0 ) , 1.0 ));
}

double range_nml(x)
double x;
{
    if (x < -4.0) return (min( max((x+8)/4 , 0.0 ) , 1.0 ));
    else return (min( max(( -x-2)/2 , 0.0 ) , 1.0 ));
}

double range_ns1(x)
double x;
{
    if (x <= -2.0) return (min( max((x+4.0)/2, 0.0), 1.0));
    else return (min( max((-x/2), 0.0), 1.0));
}

double range_zol(x)
double x;
{
    if (x <= 0) return (min( max((x+2)/2, 0.0), 1.0));
    else return (min( max((-x+2)/2, 0.0), 1.0));
}

double range_psl(x)
double x;
{
    if (x <= 2) return (min( max((x)/2, 0.0), 1.0));
    else return (min( max((-x+4)/2, 0.0), 1.0));
}

double range_pml(x)
double x;
{
    if (x <= 4) return (min( max((x-2)/2, 0.0), 1.0));
    else return (min( max((-x+8)/4, 0.0), 1.0));
}

double range_pbl(x)
double x;
{
    return(rain( max((x-4)/4, 0.0), 1.0));
}

/*******************
Range-Rate Membership Functions *****************************/
double range_nb2(x)
double x;
{
    return (min(( max((-0.5-x)/.5, 0.0), 1.0)));
}

double range_nm2(x)
double x;
{
    if (x <= -.5) return (min( max((x+1.0)/.5, 0.0), 1.0));
    else return (min( max((x-.15)/.35, 0.0), 1.0));
}

double range_ns2(x)
double x;
{
    if (x <= -.15) return (min( max((x+.5)/.35, 0.0), 1.0));
    else return (min( max((-x/.15), 0.0), 1.0));
}

double range_zo2(x)
double x;
{
    if (x <= 0) return (min( max((x+.15)/.15, 0.0), 1.0));
    else return (min( max((-x+.15)/.15, 0.0), 1.0));
}

double range_ps2(x)
double x;
{
    /* Modified from x/.1 to put gap between ns2 and ps2 */
    /* 29 Sept 1992 */
    if (x <= .15) return (min( max(x/.15, 0.0), 1.0));
    else return (min( max((-x+.5)/.35, 0.0), 1.0));
}

double range_pm2(x)
double x;


```c
double range_pb2(x)
double x;
{
    return(min( max(( x-.5)/.5 , 0.0 ), 1.0 ));
}

double range_pb3(x)
double x;
{
    return(0.2 + 0.3*x);
}

//******************** Defuzzification Process with Delta-V Membership Functions ********************/

double range_nb3(x)
double x;
{
    return(-0.2 - 0.3*x);
}

double range_nm3(x)
double x;
{
    return(-0.1 - 0.1*x);
}

double range_ns3 (x)
double x;
{
    return (-0.1*x);
}

double range_zo3 (x)
double x;
{
    return (0.0);
}

double range_ps3 (x)
double x;
{
    return (0.1 + 0.1*x);
}

double range_pro3 (x)
double x;
{
    return(0.1 + 0.1*x);
}

double range_match(i,L)
int i;
LEARN_CYCLE *L ;  /IN ： */
{
    double temp;
    switch (i) {  
        case 0:
```
L->d_weights[i*3+0] = zero_one(range_nbl(L->Phi)*L->d[i*3+0]) ;
L->d_weights[i*3+1] = zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nbl(L->Phi)*L->d[i*3+0]), zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 1 :
    L->d_weights[i*3+0] = zero_one(range_nbl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nbl(L->Phi)*L->d[i*3+0]), zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 2 :
    L->d_weights[i*3+0] = zero_one(range_nbl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nbl(L->Phi)*L->d[i*3+0]), zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 3 :
    L->d_weights[i*3+0] = zero_one(range_nbl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nbl(L->Phi)*L->d[i*3+0]), zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 4 :
    L->d_weights[i*3+0] = zero_one(range_nml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nml(L->Phi)*L->d[i*3+0]), zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 5 :
    L->d_weights[i*3+0] = zero_one(range_nml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nml(L->Phi)*L->d[i*3+0]), zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 6 :
    L->d_weights[i*3+0] = zero_one(range_nml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nml(L->Phi)*L->d[i*3+0]), zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 7 :
    L->d_weights[i*3+0] = zero_one(range_nml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nml(L->Phi)*L->d[i*3+0]), zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 8 :
    L->d_weights[i*3+0] = zero_one(range_nsl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nsl(L->Phi)*L->d[i*3+0]), zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 9 :
    L->d_weights[i*3+0] = zero_one(range_nsl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nsl(L->Phi)*L->d[i*3+0]), zero_one(range_ns2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);

case 10:
    L->d_weights[i*3+0] = zero_one(range_nsl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nsl(L->Phi)*L->d[i*3+0]), zero_one(range_nm2(L->Phi_dot)*L->d[i*3+1]));
    return(temp);
```c
return (temp);

case 11:
    L->d_weights[i*3+0] = zero_one(range_nsl(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_nsl(L->Phi)*L->d[i*3+0]), zero_one(range_nb2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 12:
    L->d_weights[i*3+0] = zero_one(range_zol(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_zol(L->Phi)*L->d[i*3+0]), zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 13:
    L->d_weights[i*3+0] = zero_one(range_ps1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_ps1(L->Phi)*L->d[i*3+0]), zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 14:
    L->d_weights[i*3+0] = zero_one(range_ps1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_ps1(L->Phi)*L->d[i*3+0]), zero_one(range_pm2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 15:
    L->d_weights[i*3+0] = zero_one(range_ps1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_ps2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_ps1(L->Phi)*L->d[i*3+0]), zero_one(range_ps2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 16:
    L->d_weights[i*3+0] = zero_one(range_pml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_pml(L->Phi)*L->d[i*3+0]), zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 17:
    L->d_weights[i*3+0] = zero_one(range_pml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_pml(L->Phi)*L->d[i*3+0]), zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 18:
    L->d_weights[i*3+0] = zero_one(range_pml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_pml(L->Phi)*L->d[i*3+0]), zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 19:
    L->d_weights[i*3+0] = zero_one(range_pml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_ps2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_pml(L->Phi)*L->d[i*3+0]), zero_one(range_ps2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 20:
    L->d_weights[i*3+0] = zero_one(range_pml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(range_pml(L->Phi)*L->d[i*3+0]), zero_one(range_zo2(L->Phi_dot)*L->d[i*3+1]) ) ;
    return (temp);

case 21:
    L->d_weights[i*3+0] = zero_one(range_pb1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(range_pb2(L->Phi_dot)*L->d[i*3+1]) ;
```
```c
double range_calculate_z_array(i, L)
int i;
LEARN_CYCLE * L;    /*IN : */
{
    switch (i) {
    case 0:
        return(range_pm3(L->w[0]));
    case 1:
        return(range_pb3(L->w[1]));
    case 2:
        return(range_pb3(L->w[2]));
    case 3:
        return(range_pb3(L->w[3]));
    case 4:
        return(range_pb3(L->w[4]));
    case 5:
        return(range_pm3(L->w[5]));
    case 6:
        return(range_pb3(L->w[6]));
    case 7:
        return(range_pb3(L->w[7]));
    case 8:
        return(range_pb3(L->w[8]));
    case 9:
        return(range_pb3(L->w[9]));
    case 10:
        return(range_pm3(L->w[10]));
    case 11:
        return(range_pb3(L->w[11]));
    case 12:
        return(range_pb3(L->w[12]));
    case 13:
        return(range_pb3(L->w[13]));
    case 14:
        return(range_pb3(L->w[14]));
    case 15:
        return(range_pb3(L->w[15]));
    case 16:
        return(range_pb3(L->w[16]));
    case 17:
        return(range_pb3(L->w[17]));
    }
```
return (range_nb3 (L->w[17]));
case 18:
    return (range_nb3 (L->w[18]));
case 19:
    return (range_nm3 (L->w[19]));
case 20:
    return (range_ns3 (L->w[20]));
case 21:
    return (range_nb3 (L->w[21]));
case 22:
    return (range_nb3 (L->w[22]));
case 23:
    return (range_nb3 (L->w[23]));
case 24:
    return (range_nm3 (L->w[24]));
A2. Source code for elevation control
#include <stdio.h>
#include <math.h>
#include <sys/types.h>

/* EXTERNAL DATA STRUCTURE DEFINITION */
#include "../orb_fuzzy/learn_cycle.h"
#define max(x,y) ( (x >- y) ? x : y )
#define min(x,y) ( (x < y) ? x : y )
#define Gamma 0.9
#define Beta 0.2
#define Beta_h 0.05
#define Rho 1.0
#define Rho_h 0.8
#define Rho_h1 0.4
extern double sgn();
extern double exp();
extern double rnd();
extern double sim_time();

learn_elev(L)
LEARN_CYCLE * L; /*IN : */
{
    int i,il, j, k;
    double elev_match(), elev_calculate_z_array();
    double temp;

    L->x[0] = (L->Phi+40)/80 ;
    L->x[1] = (L->Phi_dot+10)/20 ;

    /* 1 July 92 Change Rho_h from 0.2 to 0.8 */
    L->x[2] = 0.0 ;
    L->failure = 0;

    /* Set up and evaluate the failure criteria */
    if ( (fabs(L->Phi) > 40) || (fabs(L->Phi_dot) > 10) ) {
        L->failure = -1.;
        if( L->learn_flag ) {
            fprintf(stderr,"learn_elev: Failure at %f\n",sim_time());
        } /* end if */
    } /* end if */

    /* CC 6 November, 1992 CC */
    /* CC Turn off learning when there is a failure CC */
    /* CC until there has been no failure for 4 pass CC */
    L->fourth_pass_failure = L->third_pass_failure ;
    L->third_pass_failure = L->second_pass_failure ;
    L->second_pass_failure = L->first_pass_failure ;
    L->first_pass_failure = 0 ;

    if(L->failure == -1) {
        L->first_pass_failure = 1 ;
    } /* end if */

    /* If No Failure in the last 4 passes then turn learning on */
if( !L->fourth_pass_failure && 
    !L->third_pass_failure && 
    !L->second_pass_failure && 
    !L->first_pass_failure ) { 
    L->learn_flag = 1;
} /* end if */

/* If failure first pass, but not second pass, let the learn flag stay on, so that the failure is processed. On the next pass (where there is a failure second pass, but not third pass) then turn learning off until there are no failures for four passes */
if( L->second_pass_failure && !(L->third_pass_failure) ) {
    L->learn_flag = 0;
} /* end if */

/* output: state evaluation */
for (i = 0; i < 31; i++)
{
    L->sum = 0.0;
    for(j = 0; j < 3; j++)
    {
        L->sum += L->a[i*3+j]*L->x_old[j];
    }
    //CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC
    L->y[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
    //CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC
}
L->sum = 0.0;
for(i = 0; i < 31; i++)
{
    L->suml += L->c[i] * L->y[i];
}
L->suml = 0.0;
for( j = 0; j < 3; j++)
{
    L->suml += L->b[j] * L->x_old[j];
}
L->v = L->sum + L->suml;

/* output: action */
for(i = 0; i < 31; i++)
{
    il=i;
    L->w[i] = elev_match(il,L);
    L->zl[i] = elev_calculate_z_array(il,L);
}
L->numl = 0.0;
L->denom = 0.0;
for(i = 0; i < 31; i++)
{
    L->numl += L->w[i] * L->zl[i] * L->f[i];
    L->denom += L->w[i]*L->f[i];
}
/* JUNE 9, 1992 - CORRECTION !!! */
/* Add test for denom very small compared to suml - no rule firing zone */
/* L->push = (1000.0*fabs(L->denom)<fabs(L->suml))?0.0:L->suml/L->denom;*/
if(fabs(L->numl)<0.01 || fabs(L->denom)<0.01) {
    L->push = 0.0 ;
} else {
    L->push = L->numl/L->denom ;
} /* end if */
/* output: action computations completed */
for(i = 0; i < 31; i++)
{
    L->sum = 0.0;
    for (j = 0; j < 3; j++)
        L->sum += L->d[i*3+j] * L->x_old[j];
}
L->sum2 = 0.0;
L->sum3 = 0.0;
for(i = 0; i < 3; i++)
    L->sum2 += L->e[i] * L->x_old[i];
for (i=0;i < 31; i++)
    L->sum3 += L->f[i] * L->z[i];

L->sum4 = L->sum3 + L->sum2 / 3.0 ;

L->p = 1.0 / (1.0 + exp(-1.0 * L->sum4));
L->unusualness = (L->push > 0) ? 1.0 - L->p : -L->p ;
/* 15 April 1992 - Use temp variable - not push */
/* L->push = (rnd() <= L->p) ? L->push : -L->push; */
/* 28 Sept 1992 - Set stochastic action to zero out cmd */
28 Sept 1992 - Change definition of unusualness to correspond with Hamid's notes.
L->push = ( rnd() <= ((L->p+1.0)/2.0) ) ? L->push : -L->push;

if ( rnd() <= ((L->p+1.0)/2.0) ) {
    L->unusualness = 1.0 - L->p;
} else {
    L->push = 0.0;
    L->unusualness = -L->p;
} /* end if */

/* using new input values and unmodified weights. */
/* Use y_new and v_new so not to destroy y and v. */
for(i = 0; i < 31; i++)
{
    L->sum = 0.0;
    for(j = 0; j < 3; j++)
    {
        L->sum += L->a[i*3+j] * L->x[j];
    }
    L->y_new[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->v_new = L->sum;

/* modification and update to parameters */
for(i = 0; i < 31; i++)
{
    L->factor1 = Beta_h * L->r_hat * L->y[i] * (1.0 - L->y[i]) * sgn(L->c[i]);
    L->c[i] += Beta * L->r_hat * L->y[i];

    for(j = 0; j < 3; j++)
    {
        L->a[i*3+j] += L->factor1 * L->x_old[j];
    }
}

for(i = 0; i < 3; i++)
    L->b[i] += Beta * L->r_hat * L->x_old[i];

for(i = 0; i < 3; i++)
{
    L->factor2 = Rho_h * L->r_hat * L->z[i] * (1.0 - L->z[i]) * sgn(L->f[i]) * L->unusualness;

    for(j = 0; j < 3; j++)
    {
        if( L->learn_flag )
            L->d[i*3+j] += L->factor2 * L->x_old[j] * L->d_weights[i*3+j];
    }
}

for(i = 0; i < 31; i++)
{
    for(j = 0; j < 3; j++)
    {
        if( L->learn_flag )
            L->f[i] += Rho * L->r_hat * L->unusualness * L->z[i] * L->w[i];
    }
}

for(i = 0; i < 3; i++)
{
    L->e[i] += Rho * L->r_hat * L->unusualness * L->x_old[i];
}

L->x_old[0] = L->x[0];
L->x_old[1] = L->x[1];
L->x_old[2] = L->x[2];

/***************************************************************

double sgn(double x)
{
    double x;
    if (x < 0.0)
        return (-1.0);
    else if (x > 0.0)
        return (1.0);
    else
        return (0.0);
/* zero_one function returns 0 for negative numbers 
   1 for values > 1 
   x for values between 0 and 1 */

double zero_one(x)
    double x;
    { if (x < 0) return (0.0);
      else if (x > 1) return (1.0);
      else return (x);
    }

/*********** Membership Function for Elev_Angle **********************/

double elev_nml(x)
    double x;
    { return (min( max(( -x-1)/7 , 0.0 ), 1.0 ));
    }
double elev_nsl(x)
    double x;
    { if (x <= -1.0) return (min( max( (x+8.0)/7 , 0.0 ), 1.0 ));
      else return (min( max( -x/1 , 0.0 ), 1.0 ));
    }
double elev_zol(x)
    double x;
    { if (x <= 0) return (min( max( x+1/1 , 0.0 ), 1.0 ));
      else return (min( max( (-x+16)/16 , 0.0 ), 1.0 ));
    }
double elev_psl(x)
    double x;
    { if (x <= 16) return (min( max( x/16 , 0.0 ), 1.0 ));
      else return (m/n( max(( -x+32)/16 , 0.0 ), 1.0 ));
    }
double elev_pml(x)
    double x;
    { return (m/n( max(( x-16)/16 , 0.0 ), 1.0 ));
    }

/*************** Elev_Rate Membership Functions *********************/

double elev_nm2(x)
    double x;
    { return (min( max(( -x-.5)/.5 , 0.0 ), 1.0 ));
    }
double elev_ns2(x)
    double x;
    { if (x <= -.5) return (min( max( (x+1)/.5 , 0.0 ), 1.0 ));
      else return (min( max( (-x/.5) , 0.0 ), 1.0 ));
    }
double elev_zo2(x)
    double x;
    { if (x <= 0) return (min( max(( x+.5)/.5 , 0.0 ), 1.0 ));
      else return (min( max( (-x+.5)/.5 , 0.0 ), 1.0 ));
double elev_ps2(x)
    double x;
    {
        if (x <= .5) return (min( max(x/.5 , 0.0 ) , 1.0 ));
        else return (min( max(( -x+1)/.5 , 0.0 ) , 1.0 ));
    }

double elev_pm2(x)
    double x;
    { return (min( max(( x-.5)/1.5 , 0.0 ) , 1.0 ));
    }

/***************** Defuzzification Process with Accel Membership Functions *****************/

double elev_nm3(x)
    double x;
    { return(-0.1 - 0.1*x); }

double elev_ns3 (x)
    double x;
    { return (-0.1*x); }

double elev_zo3 (x)
    double x;
    { return (0.0); }

double elev_ps3 (x)
    double x;
    { return (0.1 + 0.1*x); }

double elev_match(i,L)
    int i;
    LEARN_CYCLE *L; /*IN : */
    {
        double temp;
        switch (i) {
            case 0:
                L->d_weights[i*3+0] = zero_one(elev_nm1(L->Phi)*L->d[i*3+0]) ;
                L->d_weights[i*3+1] = zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]) ;
                temp=min( zero_one(elev_nm1(L->Phi)*L->d[i*3+0]), zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]));
                return(temp);
            case 1:
                L->d_weights[i*3+0] = zero_one(elev_nm1(L->Phi)*L->d[i*3+0]) ;
                L->d_weights[i*3+1] = zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]) ;
                temp=min( zero_one(elev_nm1(L->Phi)*L->d[i*3+0]), zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]));
                return(temp);
        }
    }
return (temp);

case 2:
    L->d_weights[i*3+0] = zero_one(elev_nml(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_nml(L->Phi)*L->d[i*3+0]), zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 3:
    L->d_weights[i*3+0] = zero_one(elev_ns1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_ps2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_ns1(L->Phi)*L->d[i*3+0]), zero_one(elev_ps2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 4:
    L->d_weights[i*3+0] = zero_one(elev_ns1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_ns1(L->Phi)*L->d[i*3+0]), zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 5:
    L->d_weights[i*3+0] = zero_one(elev_ns1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_ns1(L->Phi)*L->d[i*3+0]), zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 6:
    L->d_weights[i*3+0] = zero_one(elev_ns1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_ns1(L->Phi)*L->d[i*3+0]), zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 7:
    L->d_weights[i*3+0] = zero_one(elev_zo1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_pm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_zo1(L->Phi)*L->d[i*3+0]), zero_one(elev_pm2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 8:
    L->d_weights[i*3+0] = zero_one(elev_zo1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_ps2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_zo1(L->Phi)*L->d[i*3+0]), zero_one(elev_ps2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 9:
    L->d_weights[i*3+0] = zero_one(elev_zo1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_zo1(L->Phi)*L->d[i*3+0]), zero_one(elev_zo2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 10:
    L->d_weights[i*3+0] = zero_one(elev_zo1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_zo1(L->Phi)*L->d[i*3+0]), zero_one(elev_ns2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 11:
    L->d_weights[i*3+0] = zero_one(elev_zo1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]) ;
    temp = min( zero_one(elev_zo1(L->Phi)*L->d[i*3+0]), zero_one(elev_nm2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);

case 12:
    L->d_weights[i*3+0] = zero_one(elev_pm1(L->Phi)*L->d[i*3+0]) ;
    L->d_weights[i*3+1] = zero_one(elev_pm2(L->Phi_dot)*L->d[i*3+1]) ;
double elev_calculate_z_array(int i, LEARN_CYCLE * L)
{
    int j;
    double elev_pm3(L->w[0]);
    double elev_pm3(L->w[1]);
    double elev_pm3(L->w[2]);
    double elev_pm3(L->w[3]);
    double elev_pm3(L->w[4]);
    double elev_pm3(L->w[5]);
    double elev_pm3(L->w[6]);
    double elev_pm3(L->w[7]);
    double elev_pm3(L->w[8]);
    double elev_pm3(L->w[9]);
    double elev_pm3(L->w[10]);
    double elev_pm3(L->w[11]);
    double elev_pm3(L->w[12]);
    double elev_pm3(L->w[13]);
    double elev_pm3(L->w[14]);
    double elev_pm3(L->w[15]);
    double elev_pm3(L->w[16]);
    double elev_pm3(L->w[17]);
    double elev_pm3(L->w[18]);
    double elev_pm3(L->w[19]);
    double elev_pm3(L->w[20]);
    double elev_pm3(L->w[21]);
    double elev_pm3(L->w[22]);
    double elev_pm3(L->w[23]);
    double elev_pm3(L->w[24]);
    double elev_pm3(L->w[25]);
    double elev_pm3(L->w[26]);
    double elev_pm3(L->w[27]);
    double elev_pm3(L->w[28]);
    double elev_pm3(L->w[29]);
    double elev_pm3(L->w[30]);
    double elev_pm3(L->w[31]);
    double elev_pm3(L->w[32]);
    double elev_pm3(L->w[33]);
    double elev_pm3(L->w[34]);
    double elev_pm3(L->w[35]);
    double elev_pm3(L->w[36]);
    double elev_pm3(L->w[37]);
    double elev_pm3(L->w[38]);
    double elev_pm3(L->w[39]);
    double elev_pm3(L->w[40]);
    double elev_pm3(L->w[41]);
    double elev_pm3(L->w[42]);
    double elev_pm3(L->w[43]);
    double elev_pm3(L->w[44]);
    double elev_pm3(L->w[45]);
    double elev_pm3(L->w[46]);
    double elev_pm3(L->w[47]);
    double elev_pm3(L->w[48]);
    double elev_pm3(L->w[49]);
    double elev_pm3(L->w[50]);
    double elev_pm3(L->w[51]);
    double elev_pm3(L->w[52]);
    double elev_pm3(L->w[53]);
    double elev_pm3(L->w[54]);
    double elev_pm3(L->w[55]);
    double elev_pm3(L->w[56]);
    double elev_pm3(L->w[57]);
    double elev_pm3(L->w[58]);
    double elev_pm3(L->w[59]);
    double elev_pm3(L->w[60]);
    double elev_pm3(L->w[61]);
    double elev_pm3(L->w[62]);
    double elev_pm3(L->w[63]);
    double elev_pm3(L->w[64]);
    double elev_pm3(L->w[65]);
    double elev_pm3(L->w[66]);
    double elev_pm3(L->w[67]);
    double elev_pm3(L->w[68]);
    double elev_pm3(L->w[69]);
    double elev_pm3(L->w[70]);
    double elev_pm3(L->w[71]);
    double elev_pm3(L->w[72]);
    double elev_pm3(L->w[73]);
    double elev_pm3(L->w[74]);
    double elev_pm3(L->w[75]);
    double elev_pm3(L->w[76]);
    double elev_pm3(L->w[77]);
    double elev_pm3(L->w[78]);
    double elev_pm3(L->w[79]);
    double elev_pm3(L->w[80]);
    double elev_pm3(L->w[81]);
    double elev_pm3(L->w[82]);
    double elev_pm3(L->w[83]);
    double elev_pm3(L->w[84]);
    double elev_pm3(L->w[85]);
    double elev_pm3(L->w[86]);
    double elev_pm3(L->w[87]);
    double elev_pm3(L->w[88]);
    double elev_pm3(L->w[89]);
    double elev_pm3(L->w[90]);
    double elev_pm3(L->w[91]);
    double elev_pm3(L->w[92]);
    double elev_pm3(L->w[93]);
    double elev_pm3(L->w[94]);
    double elev_pm3(L->w[95]);
    double elev_pm3(L->w[96]);
    double elev_pm3(L->w[97]);
    double elev_pm3(L->w[98]);
    double elev_pm3(L->w[99]);
    return (temp);
    }


return(elev_ns3(L->w[8]));
    case 9:
        return(elev_zo3(L->w[9]));
    case 10:
        return(elev_ps3(L->w[10]));
    case 11:
        return(elev_pm3(L->w[11]));
    case 12:
        return(elev_nm3(L->w[12]));
    case 13:
        return(elev_ns3(L->w[13]));
    case 14:
        return(elev_ns3(L->w[14]));
    case 15:
        return(elev_zo3(L->w[15]));
    case 16:
        return(elev_nm3(L->w[16]));
    case 17:
        return(elev_nm3(L->w[17]));
    case 18:
        return(elev_ns3(L->w[18]));
A3. Source code for azimuth control
```c
#include <stdio.h>
#include <math.h>
#include <sys/types.h>

#define max(x,y)  ((x >= y) ? x : y)
#define min(x,y)  ((x < y) ? x : y)
#define Gamma 0.9
#define Beta 0.2
#define Beta_h 0.05
#define Rho 1.0

/* 1 July 92 Change Rho_h from 0.2 to 0.8 */
#define Rho_h 0.8
#define Rho_l 2.0
#define Rho_h1 0.4

extern double sgn();
extern double exp();
extern double rnd();
extern double sim_time();

learn_azim(L)
LEARN_CYCLE * L; /*IN : */
{
  int i, il, j, k;
  double azim_match(), azim_calculate_z_array();

  double temp;

  /* 11 March 1992 - Alter scaling */
  /* 08 April 1992 - Alter scaling */
  /* 08 April 1992 - Alter Bias */
  /* 15 April 1992 - Alter Bias to 0.5 */
  /* 1 July 1992 - Alter Bias to 0.0 */
  L->x[0] = (L->Phi + 40)/80.0;
  L->x[1] = (L->Phi_dot + 10)/20.0;

  /* 12 August, 1992 */
  /* CC Change failure criteria from 0.7 & 0.07 */
  /* CC to be 0.5 and 0.05 */
  L->failure = 0;

  /* CC 31 August, 1992 */
  /* CC Change back to 0.7 & 0.07 */
}
```
/* CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC */
/* Set up and evaluate the failure criteria */
if ((fabs(L->Phi) > 2.0) || (fabs(L->Phi_dot) > 0.5)) {
    L->failure = -1;
    if (L->learn_flag) {
        fprintf(stderr,"learn_azim: Failure at %f, \n", sim_time());
    } /* end if */
    } /* end if */

/* CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC */
/* CC 6 November, 1992 CC */
/* CC Turn off learning when there is a failure CC */
/* CC until there has been no failure for 4 pass CC */
/* CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC */
L->fourth_pass_failure = L->third_pass_failure;
L->third_pass_failure = L->second_pass_failure;
L->second_pass_failure = L->first_pass_failure;
L->first_pass_failure = 0;
if (L->failure == -1) {
    L->first_pass_failure = 1;
} /* end if */

/* If No Failure in the last 4 passes then turn learning on */
if (!L->fourth_pass_failure && !L->third_pass_failure && !L->second_pass_failure && !L->first_pass_failure) {
    L->learn_flag = 1;
} /* end if */

/* If Failure first pass, but not second pass, let the learn flag stay on, so that the failure is processed. On the next pass (where there is a failure second pass, but not third pass) then turn learning off until there are no failures for four passes */
if (L->second_pass_failure && !L->third_pass_failure) {
    L->learn_flag = 0;
} /* end if */

/* output: state evaluation */
for (i = 0; i < 16; i++) {
    L->sum = 0.0;
    for (j = 0; j < 3; j++) {
        L->sum += L->a[i*3+j] * L->x_old[j];
    }
    L->y[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum = 0.0;
for (i = 0; i < 16; i++) {
    L->sum += L->c[i] * L->y[i];
}
L->suml = 0.0;
for (j = 0; j < 3; j++) {
    L->suml += L->b[j] * L->x_old[j];
}
L->v = L->sum + L->suml;
/* output: action */
for(i = 0; i < 16; i++)
{
    il = i;

    L->w[i] = azim_match(il, L);
    L->z[i] = azim_calculate_z_array(il, L);
}
L->num = 0.0;
L->denom = 0.0;
for(i = 0; i < 16; i++)
{
    L->num += L->w[i] * L->z[i] * L->f[i];
    L->denom += L->w[i] * L->f[i];
}

/* JUNE 9, 1992 - CORRECTION !!! */
/* Add test for denom very small compared to sum - no rule firing zone */
/* L->push = (1000.0*fabs(L->denom)<fabs(L->sum))?0.0:L->sum1/L->denom; */
if(fabs(L->num) <= 0.01 || fabs(L->denom) <= 0.01) {
    L->push = 0.0;
} else {
    L->push = L->num1/L->denom;
} /* end if */

/* output: action computations completed */
for(i = 0; i < 16; i++)
{
    L->sum = 0.0;

    for (j = 0; j < 3; j++)
        L->sum += L->d[i*3+j] * L->x_old[j];

    L->z[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum2 = 0.0;
L->sum3 = 0.0;

for(i = 0; i < 3; i++)
    L->sum2 += L->e[i] * L->x_old[i];
for (i = 0; i < 16; i++)
    L->sum3 += L->f[i] * L->z[i];
/* 15 April 1992 - Use temp variable - not push */
/* L->push = (rnd() <= L->p) ? L->push : -L->push; */
/* L->unusualness = (L->push > 0) ? 1.0 - L->p : -L->p; */

/* 28 Sept 1992 - Set stochastic action to zero out cmd */
/* L->push = (rnd() <= ((L->p+1.0)/2.0) ) ? L->push : -L->push; */

28 Sept 1992 - Change definition of unusualness to correspond with Hamid's notes.
L->push = (rnd() <= ((L->p+1.0)/2.0) ) ? L->push : 0.0 ;
L->unusualness = (L->push > 0) ? 1.0 - L->p : -L->p;
*/
if(rnd() <= ((L->p+1.0)/2.0)) {
  L->unusualness = 1.0 - L->p ;
} else {
  L->push = 0.0 ;
  L->unusualness = -L->p ;
} /* end if */

/* using new input values and unmodified weights. */
/* Use y_new and v_new so not to destroy y and v. */
for(i = 0; i < 16; i++)
{
  L->sum = 0.0;
  for(j = 0; j < 3; j++)
  {
    L->sum += L->a[i*3+j] * L->x[j];
  }
  L->y_new[i] = 1.0 / (1.0 + exp(-1.0 * L->sum));
}
L->sum = 0.0;
L->sum1 = 0.0;
L->sum2 = 0.0;
for(j = 0; j < 3; j++)
  L->sum1 += L->b[j] * L->x[j];
for(i = 0; i < 16; i++)
  L->sum2 += L->c[i] * L->y_new[i];
L->sum = L->sum1 + L->sum2;
L->v_new = L->sum;

/* 17 September, 1992 */
/* This logic depends upon a "crisp" (two valued) failure */
/* It has been replaced by "fuzzy" failures */
/* action evaluation */
if (L->failure)
  L->r_hat = L->failure - L->v;
else
  L->r_hat = L->failure + Gamma * L->v_new - L->v;
/* modification and update to parameters */
for(i = 0; i < 16; i++)
{
    L->factor1 = Beta_h * L->r_hat * L->y[i] * (1.0 - L->y[i]) * sgn(L->c[i]);
    L->c[i] += Beta * L->r_hat * L->y[i];

    for(j = 0; j < 3; j++)
    {
        L->a[i*3+j] += L->factor1 * L->x_old[j];
    }
}

for(i = 0; i < 3; i++)
    L->b[i] += Beta * L->r_hat * L->x_old[i];

for(i = 0; i < 16; i++)
{
    L->factor2 = Rho_h * L->r_hat * L->z[i] * (1.0 - L->z[i]) * sgn(L->f[i]) * L->unusualness;

    for(j = 0; j < 3; j++)
    {
        if( L->learn_flag ) {
            L->d[i*3+j] += L->factor2 * L->x_old[j] * L->d_weights[i*3+j];
        } /* end if */
    } /* end for */
}

for(i = 0; i < 3; i++)
{
    L->e[i] += Rho * L->r_hat * L->unusualness * L->x_old[i];
}

L->x_old[0] = L->x[0];
L->x_old[1] = L->x[1];
L->x_old[2] = L->x[2];

double sgn(x)
    double x;
{
    if (x < 0.0)
        return (-1.0);
    else if (x > 0.0)
        return (1.0);
    else
        return (0.0);
}
/* zero_one function returns 0 for negative numbers
1 for values > 1
x for values between 0 and 1 */

double zero_one(x)
{
    double x;
    if (x < 0) return (0.0);
    else if (x > 1) return (1.0);
    else return (x);
}

/************ Membership Function for Azim ***********************/

double azim_nm1(x)
{
    double x;
    return(min(max(( -x-2)/2, 0.0), 1.0));
}

double azim_ns1(x)
{
    double x;
    if (x <= -2.0) return (min(max(( x+4.0)/2.0 , 0.0 ), 1.0 ));
    else return (min( max( -x/2, 0.0 ), 1.0 ));
}

double azim_zol1(x)
{
    double x;
    if (x <= 0) return (min(max(( x+2)/2 , 0.0 ), 1.0 ));
    else return (min( max( -x/2, 0.0 ), 1.0 ));
}

double azim_pml1(x)
{
    return (min( max( (-x-2)/2 , 0.0 ), 1.0 ));
}

/************ Azim_Rate Membership Functions **********************/

double azim_nm2(x)
{
    return (min(max(( -x-0.5)/0.5 , 0.0 ), 1.0 ));
}

double azim_ns2(x)
{
    if (x <= -.5) return (min(max(( x+1)/.5 , 0.0 ), 1.0 ));
    else return (min( max( -x/.5 , 0.0 ), 1.0 ));
}

double azim_zo2(x)
{
    if (x <= 0) return (min(max(( x+.5)/.5 , 0.0 ), 1.0 ));
}
double azim_ps2(x)
double x;
{
    if (x <= .5) return (min( max(x/.5 , 0.0 ) , 1.0 ));
    else return (min( max((-x+1)/.5 , 0.0 ) , 1.0 ));
}

double azim_pm2(x)
double x;
{
    return (min( max(( x-.5)/1.5 , 0.0 ) , 1.0 ));
}

/************************** Defuzzification Process with Accel Membership Functions *****************/
double azim_nm3(x)
double x;
{
    return(-0.1 - 0.1 * x);
}
double azim_ns3(x)
double x;
{
    return (-0.1*x);
}
double azim_zo3(x)
double x;
{
    return (0.0);
}
double azim_ps3(x)
double x;
{
    return (0.1*x);
}
double azim_pm3(x)
double x;
{
    return (0.1 + 0.1*x);
}

double azim_match(i,L)
int i;
LEARN_CYCLE *L; /*IN : */
{
    double temp;
    switch (i) {
        case 0:
            L->d_weights[i*3+0] = zero_one(azim_nml(L->Phi)*L->d[i*3+0]) ;
            L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot)*L->d[i*3+1]) ;
            temp=min( zero_one(azim_nml(L->Phi)*L->d[i*3+0]) , zero_one(azim_zo2(L->Phi_dot)*L->d[i*3+1]) ) ;
            return(temp);
        case 1:
            L->d_weights[i*3+0] = zero_one(azim_nml(L->Phi)*L->d[i*3+0]) ;
            L->d_weights[i*3+1] = zero_one(azim_ns2(L->Phi_dot)*L->d[i*3+1]) ;
            temp=min( zero_one(azim_nml(L->Phi)*L->d[i*3+0]) , zero_one(azim_ns2(L->Phi_dot)*L->d[i*3+1]) ) ;
            return(temp);
        default:
            return(0.0);
    }
}
case 2:
L->d_weights[i*3+0] = zero_one(azim_nm1(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_nm2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_nm1(L->Phi) * L->d[i*3+0]), zero_one(azim_nm2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 3:
L->d_weights[i*3+0] = zero_one(azim_zo1(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zo1(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 4:
L->d_weights[i*3+0] = zero_one(azim_ns1(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_ns2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_ns1(L->Phi) * L->d[i*3+0]), zero_one(azim_ns2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 5:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 6:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 7:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 8:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 9:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 10:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 11:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
L->d_weights[i*3+1] = zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1])
temp = min( zero_one(azim_zol(L->Phi) * L->d[i*3+0]), zero_one(azim_zo2(L->Phi_dot) * L->d[i*3+1]));
return (temp);
case 12:
L->d_weights[i*3+0] = zero_one(azim_zol(L->Phi) * L->d[i*3+0])
return (temp);
double azim_calculate_z_array(int i, LEARN_CYCLE * L)
{
    switch (i) {
    case 0:
        return (azim_pm3(L->w[0]));
    case 1:
        return (azim_pm3(L->w[1]));
    case 2:
        return (azim_pm3(L->w[2]));
    case 3:
        return (azim_ps3(L->w[3]));
    case 4:
        return (azim_ps3(L->w[4]));
    case 5:
        return (azim_pm3(L->w[5]));
    case 6:
        return (azim_nm3(L->w[6]));
    case 7:
        return (azim_ns3(L->w[7]));
    case 8:
        return (azim_oz3(L->w[8]));
    case 9:
        return (azim_ps3(L->w[9]));
    case 10:
        return (azim_pm3(L->w[10]));
    case 11:
        return (azim_nm3(L->w[11]));
    case 12:
        return (azim_ns3(L->w[12]));
    case 13:
        return (azim_ns3(L->w[13]));
    }
}

L->d_weights[i*3+0] = zero_one(azim_ps2(L->Phi)*L->d[i*3+0]);
temp=min( zero_one(azim_ps1(L->Phi)*L->d[i*3+0]), zero_one(azim_ps2(L->Phi)*L->d[i*3+1]));
return (temp);
case 13:
    L->d_weights[i*3+0] = zero_one(azim_ps1(L->Phi)*L->d[i*3+0]);
    L->d_weights[i*3+1] = zero_one(azim_oz2(L->Phi_dot)*L->d[i*3+1]);
temp=min( zero_one(azim_ps1(L->Phi)*L->d[i*3+0]), zero_one(azim_oz2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);
case 14:
    L->d_weights[i*3+0] = zero_one(azim_pml(L->Phi)*L->d[i*3+0]);
    L->d_weights[i*3+1] = zero_one(azim_pm2(L->Phi_dot)*L->d[i*3+1]);
temp=min( zero_one(azim_pml(L->Phi)*L->d[i*3+0]), zero_one(azim_pm2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);
case 15:
    L->d_weights[i*3+0] = zero_one(azim_pml(L->Phi)*L->d[i*3+0]);
    L->d_weights[i*3+1] = zero_one(azim_ps2(L->Phi_dot)*L->d[i*3+1]);
temp=min( zero_one(azim_pml(L->Phi)*L->d[i*3+0]), zero_one(azim_ps2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);
case 16:
    L->d_weights[i*3+0] = zero_one(azim_pml(L->Phi)*L->d[i*3+0]);
    L->d_weights[i*3+1] = zero_one(azim_oz2(L->Phi_dot)*L->d[i*3+1]);
temp=min( zero_one(azim_pml(L->Phi)*L->d[i*3+0]), zero_one(azim_oz2(L->Phi_dot)*L->d[i*3+1]));
    return (temp);
case 14:
    return(azim_nm3(L->w[14]));
case 15:
    return(azim_nm3(L->w[15]));
case 16:
    return(azim_nm3(L->w[16]));
Appendix B.

Plots of Selected Parameters for Shuttle Translational Control
B1. Shuttle V-bar Approach from 400 feet to 50 feet
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: V Bar Approach

MODULe: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: V Bar Approach

0.09
0.075
0.06
0.045
0.03
0.015
0
-0.015
-0.03
-0.045
-0.06

0 200 400 600 800 1000 1200 1400 1600 1800
TIME (sec)

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

unusualness vs TIME
RUN: V Bar Approach

Module: ORBITER:im_elev
Data Sampling Frequency: 0.200 Hz

Orbital Operations Simulator 4  Tue Nov 17 1992 02:06:07 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: V Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[1] \text{ vs TIME} \]

RUN: V Bar Approach

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: V Bar Approach

MODULE: ORBITER Lehr_clev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

v vs TIME
RUN: V Bar Approach

6.93889e-18
-0.02
-0.04
-0.06
-0.08
-0.1
-0.12
-0.14
-0.16
-0.18
0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[3] \text{ vs TIME} \]
RUN: V Bar Approach

\[ q_{13} = 0.937 \]
\[ q_{3513} = 0.93326 \]

TIME (sec)

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[4] \text{ vs TIME} \]
RUN: V Bar Approach

\[
\begin{array}{c}
0.921581 \\
0.917903 \\
0.945742 \\
0.917903 \\
\end{array}
\]

TIME (sec)

0 200 400 600 800 1000 1200 1400 1600 1800

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[5] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.lms_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[8] vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[9] \text{ vs TIME} \]
RUN: V Bar Approach

<table>
<thead>
<tr>
<th>TIME (sec)</th>
<th>0</th>
<th>200</th>
<th>400</th>
<th>600</th>
<th>800</th>
<th>1000</th>
<th>1200</th>
<th>1400</th>
<th>1600</th>
<th>1800</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.913998</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0.91035</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>ORBITAL OPERATIONS SIMULATOR</td>
<td>14</td>
<td>The Nov 17 1992 02:06:07 PM</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[10] vs TIME
RUN: V Bar Approach

0.997687

0.993705

TIME (sec)

MODULE: ORBITER.lrm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[13] vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER_lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[14] \text{ vs TIME} \]

RUN: V Bar Approach

\begin{array}{c}
\text{TIME (sec)}
\end{array}

\begin{array}{c}
0.990064 \\
0.986112
\end{array}

MODULE: ORBITER.im_elev

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:06:07 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[15] vs TIME
RUN: V Bar Approach

MODULE: ORBITER_lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[9] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[10] \text{ vs TIME} \]
RUN: V Bar Approach

MODULE: ORBITER.lsr_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[12] \text{ vs TIME} \]
RUN: V Bar Approach

\[ 0.96006 \]
\[ 0.956228 \]
\[ 0.9522144 \]
\[ 0.9502228 \]

TIME (sec)

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:06:07 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[13] \text{ vs TIME} \]
RUN: V Bar Approach

\[ 0.948002 \]
\[ 0.944218 \]

0 200 400 600 800 1000 1200 1400 1600 1800
TIME (sec)

MODULE: ORBITER_lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ \text{d[15]} \text{ vs TIME} \]
RUN: V Bar Approach

\begin{figure}
\centering
\begin{tikzpicture}
\begin{axis}[
    title={d[15] vs TIME},
    xlabel={TIME (sec)},
    ylabel style={align=center},
    ymin=0.899077, ymax=0.902681,
    xmin=0, xmax=1800,
    ytick={0.899077, 0.902681},
    xtick={0, 200, 400, 600, 800, 1000, 1200, 1400, 1600, 1800},
    xmajorgrids=true,
    ymajorgrids=true,
    grid style=dashed,
]
\end{axis}
\end{tikzpicture}
\end{figure}

MODULE: ORBITER Lim_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[16] vs TIME
RUN: V Bar Approach

TIME (sec)

0.945091
0.941319

ORBITAL OPERATIONS SIMULATOR

The Nov 17 1992 02:06:07 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[24] \text{ vs TIME} \]
RUN: V Bar Approach

\[ \begin{array}{c}
0.985022 \\
0.98109 \\
0.980056 \\
0.98109
\end{array} \]

TIME (sec)

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[25] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[27] vs TIME
RUN: V Bar Approach

MODULE: ORBITER lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 27 Tue Nov 17 1992 02:06:07 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d(28) vs TIME
RUN: V Bar Approach

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[30] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 29 Tue Nov 17 1992 02:06:07 PM
d[31] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.Im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[39] \text{ vs TIME} \]
\[ \text{RUN: V Bar Approach} \]

MODULE: ORBITER.lm_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 31
Tue Nov 17 1992 02:06:07 PM
d[40] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.irs.elev
DATA SAMPLING FREQUENCY: 0.200 Hz
d[42] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[43] \text{ vs TIME} \]
RUN: V Bar Approach

Module: ORBITER.im_elev
Data Sampling Frequency: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[45] vs TIME**
RUN: V Bar Approach

MODULE: ORBITER.im_elev
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 35
Tue Nov 17 1992 02:06:07 PM
d[46] vs TIME
RUN: V Bar Approach

MODULE: ORBIT.1m_elev
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER.1m_auim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

Phi_dot vs TIME
RUN: V Bar Approach

TIME (sec)

0.000225
0.00018
0.000135
9e-05
-4.5e-05
-9e-05
-0.000135

0 200 400 600 800 1000 1200 1400 1600 1800

MODuLe: ORBITer.lm_azim
DATA SAmPLING FReQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

push vs TIME
RUN: V Bar Approach

MODULE: ORBITER.im_axim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 3
Tue Nov 17 1992 02:05:33 PM
unusualness vs TIME
RUN: V Bar Approach

SIMULATION APPLICATION: ARIC Translational Controller Simulation

MODULE: ORBITER.lm.exim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

failure vs TIME
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER_hm_simulation
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ x[0] \text{ vs TIME} \]
RUN: V Bar Approach

\[ \begin{array}{c}
0.5003 \\
0.4993 \\
\end{array} \]
\[ \begin{array}{c}
x[0] \\
\end{array} \]

\[ 0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \]

TIME (sec)

MODULE: ORBITER_in_azi
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\( x[1] \) vs TIME
RUN: V Bar Approach

MODULE: ORBITER
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:05:33 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

p vs TIME
RUN: V Bar Approach

MODULE: ORBITER.ims_azelim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

V vs TIME
RUN: V Bar Approach

MODULE: ORBITER.Iso_axim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f[3] \text{ vs TIME} \]
RUN: V Bar Approach

TIME (sec)

MODULE: ORBITER.in
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(7) \text{ vs } \text{TIME} \]
RUN: V Bar Approach

0.95388

0.950072

0.9531976

0.950072

TIME (sec)

MODULE: ORBITER lm szim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(8) \] vs TIME
RUN: V Bar Approach

MODULE: ORBITER

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

f[9] vs TIME
RUN: V Bar Approach

0.988627

0.984681

0.984681

0 200 400 600 800 1000 1200 1400 1600 1800

TIME (sec)

MODULE: ORBITER.fm_znm
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ f(13) \text{ vs TIME} \]
RUN: V Bar Approach

MODULE: ORBITE.R.im_axism
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[9] \text{ vs TIME} \]
RUN: V Bar Approach

\[
\begin{align*}
\text{TIME (sec)} & \\
0 & 200 400 600 800 1000 1200 1400 1600 1800
\end{align*}
\]

MODULE: ORBITER.lm_azim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[10] vs TIME
RUN: V Bar Approach

MODULE: ORBITER lm azim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 16
Tue Nov 17 1992 02:05:33 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[21] \text{ vs TIME} \]

RUN: V Bar Approach

\begin{center}
\begin{tabular}{c|c|c|c|c|c|c|c|c|c|c|c|c}
0.981931 & 0.978011 & & & & & & & & & & \\
\hline
0 & 200 & 400 & 600 & 800 & 1000 & 1200 & 1400 & 1600 & 1800 & \\
\end{tabular}
\end{center}

TIME (sec)

MODULE: ORBITER.lm_azure

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR

Tue Nov 17 1992 02:05:33 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[22] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.nlm
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

**d[24] vs TIME**

**RUN: V Bar Approach**

**MODULE:** ORBITER.Im_sim

**DATA SAMPLING FREQUENCY:** 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[25] \text{ vs TIME} \]
RUN: V Bar Approach

\[
\begin{array}{c}
0.916164 \\
0.912506 \\
0.912535 \\
0.912506 \\
\end{array}
\]

\[
\begin{array}{c}
0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \\
\end{array}
\]

TIME (sec)

MODULE: ORBITER.im_atim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR 20

Tue Nov 17 1992 02:05:33 PM
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\( d[27] \) vs TIME
RUN: V Bar Approach

\[ \begin{align*}
0.972399 \\
0.968517
\end{align*} \]

\[ \begin{align*}
0.972399 & \quad 0 \quad 200 \quad 400 \quad 600 \quad 800 \quad 1000 \quad 1200 \quad 1400 \quad 1600 \quad 1800 \\
0.968517 & \\
\end{align*} \]

MODULE: ORBITER_lm_azelim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d(28) \text{ vs } \text{TIME} \]
RUN: V Bar Approach

MODULE: ORBITER.im_axim
DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR
SIMULATION APPLICATION: ARIC Translational Controller Simulation

d[39] vs TIME
RUN: V Bar Approach

MODULE: ORBITER.lm_4stim
DATA SAMPLING FREQUENCY: 0.200 Hz
SIMULATION APPLICATION: ARIC Translational Controller Simulation

\[ d[40] \text{ vs TIME} \]

RUN: V Bar Approach

\[ 0.939683 \]

\[ 0.935931 \]

0 \( \text{ vs TIME} \)

\[ \text{TIME (sec)} \]

MODULE: ORBITER.im_axim

DATA SAMPLING FREQUENCY: 0.200 Hz

ORBITAL OPERATIONS SIMULATOR