Reference Equations of Motion for Automatic Rendezvous and Capture

David M. Henderson
TRW Systems Services Company, Inc.
Houston, Texas
(TRW Report Number 91:J431.1-182)

Prepared for
Lyndon B. Johnson Space Flight Center
under contract NAS9-17900

1992
Reference Equations of Motion for Automatic Rendezvous and Capture

David M. Henderson

Contract NAS9-17900

April 1992
# TABLE OF CONTENTS

1.0 INTRODUCTION ........................................................................................................ 1

2.0 TRANSLATION DYNAMICS - MOTION OF THE CENTER OF MASS ................................ 3

3.0 ROTATIONAL DYNAMICS - VEHICLE ANGULAR MOTION ABOUT THE CENTER OF MASS .................................................. 9

4.0 SIX DEGREES OF FREEDOM EQUATIONS OF MOTION ..................................... 11

5.0 TRANSLATION CONTROL PARAMETERS .............................................................. 14

6.0 ROTATION CONTROL PARAMETERS ................................................................ 21

7.0 CONCLUSIONS AND RECOMMENDATIONS ............................................................. 25

8.0 REFERENCES ............................................................................................................. 26

APPENDIX A SUGGESTED INTEGRABLE PARAMETER LIST .......................................... 27

APPENDIX B GRAVITATIONAL ACCELERATION .............................................................. 29

APPENDIX C PARTIAL DERIVATIVES OF THE GRAVITATIONAL ACCELERATION VECTOR ......................... 32
REFERENCES EQUATIONS OF MOTION FOR
AUTOMATIC RENDEZVOUS AND CAPTURE

David M. Henderson
TRW/Houston

1.0 INTRODUCTION

The analysis presented in this paper defines the reference coordinate frames and control parameters necessary to model the relative motion and attitude of spacecraft in close proximity with another space system during the Automatic Rendezvous and Capture phase of an on-orbit operation. Translation motion equations relative to the geodesic LVLH frame are developed yielding the Clohessy-Wiltshire differential equations of motion. Perturbations of the gravity partial derivative matrix due to a 4x4 gravity model show the expected deviations from the Clohessy-Wiltshire approximation. For the docking case, however, as the relative separation distances become small, both relative gravitational and inertial accelerations can be omitted from the translation equations of motion.

Euler's equation for the rotational rate accelerations of a rigid body are developed with expected torque effects indicated. The actual torque computations are problematic and these specific models are not developed as part of this work.

The relative docking port target position vector and the attitude control matrix are defined based upon an arbitrary spacecraft design. These translation and rotation control parameters could be used to drive the error signal input to the vehicle flight control system. Measurements for these control parameters would become the bases for an autopilot or FCS design for a specific spacecraft.

Cartesian analysis is used throughout the paper for the clarity and compactness in representing component equations. The use of Cartesian tensor notation makes the task of repeated differentiation of transformation equations considerably easier and more understandable. For instance, the position vector in inertial space is given by

\[ x = a \hat{x} + X \]  \hspace{1cm} (1.1)

where \( a \hat{x} \) is a transformation matrix times the vector \( \hat{x} \). Equation 1.1 defines both rotation and translation in the inertial frame. Differentiating Equation 1.1 for velocity is simply,
\[ v = a \vec{v} + V \quad (1.2) \]

where

\[ \vec{v} = \vec{W} \vec{x} + \vec{v} \quad (1.3) \]

and \( \vec{W} \) is the skew-symmetry angular velocity matrix. The vector \( \vec{v} \) is recognized from vector analysis [see Reference 4.0, Page 208] as the operator,

\[
\begin{pmatrix}
\vec{\omega} \times + \frac{d}{dt}
\end{pmatrix} \vec{x} \quad (1.4)
\]

However, in Equation 1.2 the inertial coordinates are preserved and no ambiguities arise as to which coordinate system the vectors components are represented.
2.0 TRANSLATIONAL DYNAMIC MOTION OF CENTER OF MASS

Let (o) be the origin of an imaginary coordinate frame attached to a mass in orbital motion about the planet's center. Further assume that there is no contact force acting upon this mass so that it moves along the geodesic arc in the inertial frame whose origin coincides with the center of mass of the planet. Also attached to the origin (o) is the Local-Vertical-Local-Horizontal (LVLH) coordinate reference frame. For circular orbital motion the LVLH system rotates downward about its y-axis at the orbital rate.

The Cartesian equation,

\[ x_{on} = a_o x_{on} + x_o \]  \hspace{1cm} (2.1)

Represents the components of the inertial vector to any coordinate center located at (n) as seen from (o), where \( a_o \) is the transformation matrix LVLH to inertial and
\[ x_n = a_n x_{on} + x_o \]  \hspace{1cm} (2.2)

represents vectors to the center of mass \( m_n \) at \( (n) \) or

\[ a_n x_{on} = x_n - x_o. \]  \hspace{1cm} (2.3)

This is their relative position relationship at any time \( t \).

Differentiating Equation 2.3 for velocity

\[ a_n v_{on} = v_n - v_o. \]  \hspace{1cm} (2.4)

where

\[ v_{on} = \bar{W} x_{on} + \varphi_{on} \]

and

\[
\bar{W} = \begin{pmatrix}
0 & -\hat{o}_3 & \hat{o}_2 \\
\hat{o}_3 & 0 & -\hat{o}_1 \\
-\hat{o}_2 & \hat{o}_1 & 0
\end{pmatrix}
\]

is the skew-symmetric angular velocity matrix. Solving for relative velocity in the LVLH frame,

\[ \varphi_{on} = (a_n)^T (v_n - v_o) - \bar{W} x_{on}. \]
Differentiating Equation 2.4 for acceleration

\[ a_o \dot{a}_{on} = \dot{V}_n - \dot{V}_o \]  

(2.5)

where

\[ a_{on} = (\overline{WW} + \overline{W}) \dot{x}_{on} + \overline{2W} v_{on} + \ddot{v}_{on} \]

and the relative LVLH acceleration vector as seen from (o) is

\[ \dot{v}_{on} = (a_o)^T (V_n - V_o) - (\overline{WW} + \overline{W}) \dot{v}_{on} - \overline{2W} v_{on}. \]  

(2.6)

The acceleration vectors are

\[ \dot{V}_n = G(X_n) + A_n \quad \text{and} \quad \dot{V}_o = G(X_o) + A_o \]  

(2.7)

But \( A_o = 0 \), since we have defined (o) to be an inertial frame moving along the geodesic arc about the planet center. Therefore,

\[ \dot{V}_n - \dot{V}_o = G(X_n) - G(X_o) + A_n \]  

(2.8)

and Equation 2.5 becomes

\[ a_o \dot{a}_{on} = G(X_n) - G(X_o) + A_n. \]  

(2.9)

If \( X_n \) and \( X_o \) are very close to one another. The difference in gravitation accelerations is simply a linear variation in acceleration about the origin (o),
\[ \delta G(X_o) = G(X_n) - G(X_o) \]

and

\[ \delta G(X_o) = \frac{\delta G}{\delta X_o} \delta X_o = \frac{\delta G}{\delta X_o} (X_n - X_o) = P_X (X_n - X_o), \quad (2.10) \]

therefore, Equation 2.9 becomes

\[ a_o a_{on} = P_X (X_n - X_o) + A_n. \quad (2.11) \]

From Equation 2.3 we have

\[ a_o a_{on} = P_X (a_o x_{on}) + A_n \quad (2.12) \]

and solving for the acceleration in the LVLH frame,

\[ a_{on} = [(a_o)^T P_X a_o] x_{on} + (a_o)^T A_n \quad (2.13) \]

\[ a_{on} = \overline{P}_X x_{on} + \overline{A}_n \quad (2.14) \]

where

\[ \overline{A}_n = (a_o)^T A_n \quad \text{and} \quad \overline{P}_X = [(a_o)^T P_X a_o]. \]
The $\mathbf{P}_x$ matrix is defined from the similarity transformation for matrices as described in Reference 5.0, Pages, 317 and 318, then Equation 2.14 becomes,

$$\dot{\mathbf{v}}_{on} = (\mathbf{P}_x - \mathbf{W} - \mathbf{W}) \mathbf{a}_{on} - 2 \mathbf{w} \cdot \mathbf{v}_{on} + \mathbf{A}_n. \quad (2.15)$$

Equation 2.15 is the equation for motion for mass $m$ in the LVLH coordinates system attached to the geodesic point $(\phi)$ in Figure 1.0. The $\mathbf{P}_x$ matrices are used here for simplicity and also contribute to understanding in the analysis, however, it should be pointed out that the $\mathbf{P}_x$ matrices are non-linear and their region of numeric stability about the geodesic origin is small. Hence, for very accurate relative motion computations the difference equations of Equation 2.9 become a more reliable relationship on which to base computational algorithms. Equation 2.15 can be represented by the sum of two vectors,

$$\dot{\mathbf{v}}_{on} = \mathbf{A}_{1n} + \mathbf{A}_n, \quad (2.16)$$

where $\mathbf{A}_{1n}$ are the combined gravitational and inertial accelerations effecting the relative motion of the center of mass.

The $\mathbf{P}_x$ matrix reduces to (see Appendix C)

$$\mathbf{P}_x = -\mu R^{-3} \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & -2 \end{pmatrix} = -\mathbf{w} \cdot \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & -2 \end{pmatrix}. \quad (2.17)$$

In a spherical gravitational field, i.e., where all gravity harmonics are assumed zero,
\[
\overline{WW} = \begin{pmatrix}
0 & 0 & -\omega_o \\
0 & 0 & -\omega_o \\
\omega_o & 0 & 0 \\
\end{pmatrix}
\begin{pmatrix}
0 & 0 & -\omega_o \\
0 & 0 & 0 \\
\omega_o & 0 & 0 \\
\end{pmatrix}
= \begin{pmatrix}
-\omega_o^2 & 0 & 0 \\
0 & 0 & 0 \\
0 & 0 & -\omega_o^2 \\
\end{pmatrix}
\quad (2.18)
\]

and for uniform circular orbit motion

\[
\dot{\overline{W}} = 0.
\quad (2.19)
\]

However, in the "real world" small oscillatory motions do occur about the LVLH axes due to the gravity harmonics. Then Equation 2.15 reduces to

\[
\begin{cases}
\dot{v}_x = 2\omega_o \, v_z + \overline{A}_x = \overline{A}_{Ix} + \overline{A}_x \\
\dot{v}_y = -\omega_o^2 \, y + \overline{A}_y = \overline{A}_{Iy} + \overline{A}_y \\
\dot{v}_z = 3\omega_o^2 \, z - 2\omega_o \, v_x + \overline{A}_z = \overline{A}_{Iz} + \overline{A}_z
\end{cases}
\quad (2.20)
\]

which are recognized as the Clohessy-Wiltshire approximation for the differential equations of relative motion [as described in Reference 1.0]. The \(\overline{A}_I\) in Equation 2.20 are the combined relative gravitational and inertial acceleration effects in the LVLH system.
3.0 ROTATIONAL DYNAMICS

The vehicle angular momentum in body axis coordinates transforms into the inertial frame via

\[ L = a \bar{I} \]  \hspace{1cm} (3.1)

and \( \bar{I} \) for any rigid body is given by \( \bar{I} \dot{\omega} \) where \( \bar{I} \) is the body axis moment of inertia matrix and \( \omega \) is the body axis rotation rate vector. Equation 3.1 becomes

\[ L = a \bar{I} \dot{\omega}. \]  \hspace{1cm} (3.2)

Using Newton's Law;

\[ \frac{dL}{dt} = N. \]  \hspace{1cm} (3.3)

Equation (3.2) becomes

\[ \frac{dL}{dt} = a \bar{I} \dot{\omega} + a \bar{I} \dot{\omega} = N = a \bar{N} \]  \hspace{1cm} (3.4)

where \( N \) and \( \bar{N} \) are the applied torques in the inertial and body axis coordinate frames, respectively. Equation 3.4 yields Euler's Equation of motion for a rigid body,

\[ \bar{N} = \bar{W} \dot{\omega} + \bar{I} \ddot{\omega}, \]  \hspace{1cm} (3.5)

and solving for \( \dot{\omega} \), we have,
\[
\dot{\omega} = \bar{J} \left( \bar{N} - \bar{W} \bar{I} \bar{\omega} \right)
\]  \quad (3.6)

where \( \bar{J} = \bar{I}^{-1} \), is the inverse of the body axis moment of inertia matrix. The applied torques are composed of

\[
\bar{N} = \bar{N}_G + \bar{N}_T + \bar{N}_A + \bar{N}_P
\]  \quad (3.7)

gravity, thrusting, aerodynamic and plume impingement torques, respectively, and Equation 3.6 becomes

\[
\dot{\omega} = \bar{J} \left[ \bar{N}_G + \bar{N}_T + \bar{N}_A + \bar{N}_P + \bar{N}_I \right]
\]  \quad (3.8)

where the inertial torques are \( \bar{N}_I = -\bar{W} \bar{I} \bar{\omega} \), which results due to rotational motion of the vehicle itself. Integrals of this equation [see Reference 3.0] provide the body axis rotation rate vector as a function of time.
4.0 SIX DEGREES-OF-FREEDOM EQUATIONS OF MOTION

From Equation (2.20),

\[ \dot{\mathbf{v}}_n = \frac{g_0}{\mathbf{W}_n} \sum F_n + \mathbf{A}_{\text{In}} \]  \hspace{1cm} (4.1)

for translational dynamics and Euler's equation

\[ \dot{\mathbf{w}} = \mathbf{J}_n (\mathbf{N}_n - \mathbf{W}_n \mathbf{I}_n \ddot{\mathbf{a}}_n) \]  \hspace{1cm} (4.2)

for rotation dynamics, where;

\[ \frac{g_0}{\mathbf{W}_n} \sum F_n \] - Summation of contact forces acting on vehicle n (LVLH Ref)

\[ \mathbf{A}_{\text{In}} \] - Inertial and gravitational accelerations of CM of vehicle n (LVLH Ref)

\[ \mathbf{I}_n \] - Moment of inertia matrix of vehicle n

\[ \mathbf{J}_n \] - Inverse of moment of inertia matrix of vehicle n

\[ \mathbf{N}_n \] - Body axis torques about the CM of vehicle n

\[ \mathbf{W}_n \] - Skew symmetric angular velocity matrix (vehicle n)

\[ \mathbf{w} \] - Body axis rotation rate vector (vehicle n)

\[ \ddot{\mathbf{a}}_n \] - Body axis rotation rate acceleration vector for vehicle n.
For example an integrable set of differential equations could be represented as follows,

\[
\begin{align*}
\dot{\mathbf{v}}_1 &= \frac{g_0}{W_1} (-C_{D1} q S_1 u_{REL1} + T_1) + A_{I1} \\
\dot{\mathbf{v}}_2 &= \frac{g_0}{W_2} (-C_{D2} q S_2 u_{REL2}) + A_{I2}.
\end{align*}
\]

(4.3) (4.4)

Assume that vehicle one is active (with thrust) and that vehicle two is passive (no thrusting) and

\[
\begin{align*}
\dot{\mathbf{v}}_1 &= -B_1 g_0 \bar{q} u_{REL1} + \frac{g_0}{W_1} T_1 + A_{I1} \\
\dot{\mathbf{v}}_2 &= -B_2 g_0 \bar{q} u_{REL2} + A_{I2},
\end{align*}
\]

(4.5)

where \(u_{REL}\) is a unit vector in the LVLH geodesic system and is in the direction of the motion of the geodesic frame and,

\[
B_1 \text{ is the ballistic coefficient } \left( \frac{C_{D1} S_1}{W_1} \right)
\]

\(\bar{q}\) is the fluid dynamic pressure, \(\bar{q} = (1/2 \rho (V_R)^2)\) where,

\(V_R\) - relative velocity magnitude

\(\rho\) - fluid density
and the $\tilde{\mathbf{u}}_{\text{REL}}$ vector in the LVLH reference frame is approximately,

$$
\tilde{\mathbf{u}}_{\text{REL}} = \begin{bmatrix} 1.0 \\ 0.0 \\ 0.0 \end{bmatrix}.
$$

(4.7)

With the above example in mind, Appendix A shows a suggested integrable parameter list for a time-wise step solution to the problem. More precise equations of motion can be defined by computing the driving values for $\mathbf{F}_n$ and $\mathbf{N}_n$ in Equations 4.1 and 4.2, respectively, however, the same 6-DOF solution procedures will apply.
5.0 TRANSLATION CONTROL PARAMETERS

As in Figure 2-1, the geodesic center is the motion of an imaginary point falling along the local gravity geodesic arc. No drag or other contact forces are acting at the geodesic center. The rotating LVLH coordinate axes are attached to the geodesic center. The position vector in the inertial coordinate system to a point in space can be computed from each of the coordinate systems shown in the following figure.

Figure 5-1
The Cartesian equations relating the coordinates as shown in Figure 5.1 can be written as follows;

\[ x_0 = a_0 x_0 + x_0 \]  \hspace{1cm} (5.1)

from the geodesic frame and likewise,

\[ x_1 = a_1 x_1 + x_1 \]  \hspace{1cm} (5.2)

is from the center of mass of vehicle one. From coordinates \( x_1 \) on vehicle one,

\[ x_1 = c_1 \dot{x}_1 + \ddot{x}_1, \]  \hspace{1cm} (5.3)

is from the center of the docking port located on vehicle one. Similarly for vehicle two,

\[ x_2 = a_2 x_2 + x_2 \]  \hspace{1cm} (5.4)

from the center of mass of vehicle two

\[ x_2 = c_2 \dot{x}_2 + \ddot{x}_2 \]  \hspace{1cm} (5.5)

and from the center of the docking port located on vehicle two.
The following definitions apply to Equations 5.1 through 5.5.

\( a_0 \) - The LVLH to inertial transformation matrix attached to the geodesic coordinate center (a time varying matrix)

\( a_i \) - \( i \)th body axis to inertial transformation matrix (a varying matrix)

\( X_i \) - The inertial coordinates of the \( i \)th coordinate center (a dynamic vector in motion about the planet center)

\( c_i \) - \( i \)th docking port to body axis transform matrix (a constant matrix)

\( \bar{X}_i \) - Body axis coordinates of the \( i \)th body docking port coordinate center (a constant vector).

The target docking port inertial position is

\[
x_T = a_2 X_2 + X_2
\]

\[
x_T = a_2 (c_2 \bar{X}_2 + \bar{X}_2) + X_2
\]  \hspace{1cm} (5.6)

but

\[
\dot{X}_2 = 0,
\]

since the target is the docking port coordinate center and therefore Equation 5.6 reduces to

\[
x_T = a_2 \bar{X}_2 + X_2,
\]  \hspace{1cm} (5.7)

the target location in inertial coordinate. Hence, the position relative geometry in the inertial coordinate reference frame becomes
\[ a_2 \bar{x}_2 + \bar{x}_2 = a_1 (c_1 \bar{x}_1 + \bar{x}_1) + \bar{x}_1 \]  \hspace{1cm} (5.8)

from Equation 5.1

\[ X_1 = a_0 x_{o1} + x_o \quad \text{and} \quad X_2 = a_0 x_{o2} + x_o \]  \hspace{1cm} (5.9)

and substituting these into Equation 5.8

\[ a_2 \bar{x}_2 + a_0 x_{o2} = a_1 (c_1 \bar{x}_1 + \bar{x}_1) + a_0 x_{o1} \]  \hspace{1cm} (5.10)

where the \( x_{o2} \) and \( x_{o2} \) are the position vectors to the vehicle one and two center of mass measured in the LVLH geodesic coordinate frame of reference.

By multiplying Equation 5.10 by the transformation matrix \((a_0)^T\), the equation is transformed to the LVLH frame,

\[ (a_0)^T a_2 \bar{x}_2 + x_{o2} = (a_0)^T a_1 (c_1 \bar{x}_1 + \bar{x}_1) + x_{o2}. \]  \hspace{1cm} (5.11)

Now let \( b_1 = (a_0)^T a_1 \) and \( b_2 = (a_0)^T a_2 \), be the transformation matrices for the body axes to the LVLH reference frame. Then Equation 5.11 becomes

\[ (x_{o2} - x_{o1}) = b_1 (c_1 \bar{x}_1 + \bar{x}_1) - b_2 \bar{x}_2, \]  \hspace{1cm} (5.12)

the relative position vector between the two vehicles in the LVLH frame and solving for \( \bar{x}_1 \),

\[ \bar{x}_1 = (c_1)^T [(b_1)^T ((x_{o2} - x_{o1}) + b_2 \bar{x}_2) - \bar{x}_1]. \]  \hspace{1cm} (5.13)
We have the position control vector as seen from the vehicle one docking port coordinate center. The GN&C systems should drive this vector to zero for docking contact. Written in body axis coordinates we have,

\[ \vec{x}_1 = c_1 \vec{\dot{x}}_1 = (b_1)^T (b_2 \vec{X}_2 + (\vec{x}_{02} - \vec{x}_{01})) - \vec{X}_1, \quad (5.14) \]

the control vector as seen from the active vehicle (vehicle one). Hence, a candidate commanded velocity in the vehicle frame becomes,

\[ \vec{v}_c = K_R \vec{x}_1 \quad (5.15) \]

where the gain,

\[ K_R = -\left( \frac{k_R}{\Delta t} \right), \]

can be applied in a Flight Control System (FCS) with appropriate limiters for proper closing rates. For the velocity of the target docking port we differentiate Equation 5.9

\[ a_2 \vec{w}_2 \vec{x}_2 + a_0 \vec{w}_0 \vec{x}_{02} = a_1 \vec{w}_1 \left( c_1 \vec{\dot{x}}_1 + \vec{x}_1 \right) + a_1 c_1 \vec{v}_1 + a_0 \vec{w}_0 \vec{x}_{01} + a_0 \vec{v}_{01}. \quad (5.16) \]

Again by multiplying by \((a_0)^T\) the equation is reduced to LVLH coordinates,
\[(a_o)^T a_2 \vec{W}_2 \vec{X}_2 + \vec{W}_0 \vec{x}_0 + \vec{v}_o = (a_o)^T a_1 \vec{W}_1 (c_1 \vec{x}_1 + \vec{X}_1)\]

\[+ (a_o)^T a_1 c_1 \vec{v}_1 + \vec{W}_0 \vec{x}_0 + \vec{v}_o\]

(5.17)

and the relative velocity difference in the LVLH frame is,

\[(\vec{v}_{o2} - \vec{v}_{o1}) = b_1 \vec{W}_1 (c_1 \vec{x}_1 + \vec{X}_1) + b_1 c_1 \vec{v}_1 - b_2 \vec{W}_2 \vec{X}_2 - \vec{W}_0 (\vec{x}_{o2} - \vec{x}_{o1})\]

(5.18)

and the docking port relative velocity of the docking port coordinate center on vehicle two (the target) is

\[\vec{v}_1 = (c_1)^T ((b_1)^T ((\vec{v}_{o2} - \vec{v}_{o1}) + \vec{W}_0 (\vec{x}_{o2} - \vec{x}_{o1}) + b_2 \vec{W}_2 \vec{X}_2) - \vec{W}_1 (c_1 \vec{x}_1 + \vec{X}_1))\]

(5.19)

The control velocity vector in vehicle body axis coordinates becomes,

\[\vec{v}_1 = c_1 \vec{v}_1 = (b_1)^T (\vec{v}_{o2} - \vec{v}_{o1} + \vec{W}_0 (\vec{x}_{o2} - \vec{x}_{o1}) + b_2 \vec{W}_2 \vec{X}_2) - \vec{W}_1 (c_1 \vec{x}_1 + \vec{X}_1)\]

(5.20)

Using Equations 5.15 and 5.20, the \(\Delta V\) command for translation control becomes,

\[\Delta \vec{V}_c = \vec{v}_c - \vec{v}_1\]

(5.21)

and when applied with appropriate limiters or closing gates, the algorithm can be used to the control closing conditions for safe docking. The acceleration of the control vector is found by differentiation of Equation 5.16 and becomes
\[
\dot{\theta}_1 = (c_1)^T \left[ (b_1)^T b_2 (\ddot{w}_2 \dot{w}_2 + \ddot{\omega}_2) \dot{X}_2 + (b_1)^T \{(\ddot{w}_o \dot{w}_o + \ddot{\omega}_o) (x_{o2} - x_{o1}) \right.
\]
\[
+ 2 (\ddot{w}_o) (\theta_{o2} - \theta_{o1}) + (\dot{\theta}_{o2} - \dot{\theta}_{o1}) \right] \]
\[
- (\ddot{w}_1 \ddot{w}_1 + \ddot{\omega}_1) (c_1 \ddot{x}_1 + \dot{X}_1) - 2 \ddot{w}_1 c_1 \dot{\theta}_1 \]    

(5.22)

and in body axes coordinates

\[
(c_1 \dot{\theta}_1) = (b_1)^T b_2 (\ddot{w}_2 \dot{w}_2 + \ddot{\omega}_2) \dot{X}_2 + (b_1)^T \{(\ddot{w}_o \dot{w}_o + \ddot{\omega}_o) (x_{o2} - x_{o1}) \right.
\]
\[
+ 2 \ddot{w}_o (\theta_{o2} - \theta_{o1}) + (\dot{\theta}_{o2} - \dot{\theta}_{o1}) \right] \]
\[
- (\ddot{w}_1 \ddot{w}_1 + \ddot{\omega}_1) (c_1 \ddot{x}_1 + \dot{X}_1) - 2 \ddot{w}_1 c_1 \dot{\theta}_1. \]

(5.23)
6.0 ROTATION CONTROL PARAMETERS

The attitude control matrix may be derived as from rotation equations as follows

\[ x_1 = a_1 \dot{x}_1 \quad \quad x_2 = a_2 \dot{x}_2 \]

\[ \dot{x}_1 = c_1 x_1 \quad \quad \dot{x}_2 = c_2 \dot{x}_2 \]

\[ x_1 = [a_1 c_1] \dot{x}_1 \quad \quad x_2 = [a_2 c_2] \dot{x}_2 \]  \hspace{1cm} (6.1)

The desired attitude condition at docking is that the two systems have approximately the same orientation in inertial space and, therefore,

\[ a_1 c_1 \neq a_2 c_2. \]  \hspace{1cm} (6.2)

If vehicle number one is the active control vehicle,

\[ a_{1d} = a_2 c_2 (c_1)^T \]  \hspace{1cm} (6.3)

is the desired attitude matrix for vehicle number one. The control matrix becomes

\[ a_1 \dot{x}_1 = a_{1d} \dot{x}_{1d} \]

\[ \dot{x}_1 = [(a_1)^T a_{1d}] \dot{x}_{1d} \]

\[ \dot{x}_1 = [(a_1)^T a_2 c_2 (c_1)^T] \dot{x}_{1d} \]

\[ C_N = [(a_1)^T a_2 c_2 (c_1)^T] \text{ (Attitude Control Matrix)} \]  \hspace{1cm} (6.4)
That is, the $C_N$ matrix will become the unit matrix when the docking ports are aligned. By extracting the Hamilton Quaternion from the $C_N$ matrix a desired rotation can be found to align the docking ports as follows;

$$
\begin{bmatrix}
q_1 \\
q_2 \\
q_3 \\
q_4
\end{bmatrix} =
\begin{bmatrix}
\cos (\omega/2) \\
\sin (\omega/2) \cos \alpha \\
\sin (\omega/2) \cos \beta \\
\sin (\omega/2) \cos \gamma
\end{bmatrix}
$$

(6.5)

where

$$\omega = 2 \cos^{-1} (q_1),$$

(6.6)

is the instantaneous angular control rotation required to align the docking ports.

The eigen axis about which the controlled rotation of vehicle one must occur becomes

$$
\begin{bmatrix}
\cos \alpha \\
\cos \beta \\
\cos \gamma
\end{bmatrix} = 
\frac{1}{\sin (\omega/2)}
\begin{bmatrix}
q_2 \\
q_3 \\
q_4
\end{bmatrix}.
$$

(6.7)

Hence, as $\omega$ approaches zero, the $C_N$ matrix approaches the unit matrix and the desired attitude condition of Equation 6.4 can be reached. The vehicle one attitude GN&C functions must be designed to control the spacecraft to this desired attitude.

The soft singularity indicated in Equation 6.7 will not be reached since $\omega$ will fall into the control attitude deadband before $\omega = 0$. A candidate commanded body axis rate vector may be estimated by selecting a scaler quantity $\Omega$ for the desired angular closing rate for the control quaternion and the desired body axis rotation rate becomes
The candidate commanded body axis rotation rate change is

$$\Delta \omega_{1c} = \omega_{1d} - \omega_1,$$  \hspace{1cm} (6.9)

where $\omega_1$ is the instantaneous body axis rotation rate vector for the active vehicle (i.e., vehicle one).

The desired attitude rate constraint can also be derived by equating the two transformation matrices for docking port coordinates to the inertial coordinates as follows,

$$(a_0)^T a_1 c_1 = (a_0)^T a_2 c_2$$  \hspace{1cm} (6.10)

and then demanding that the rates of the changed resulting matrices be identical,

$$-\bar{W}_0 (a_0)^T a_1 c_1 + (a_0)^T a_1 \bar{W}_1 c_1 = -\bar{W}_0 (a_0)^T a_2 c_2 + (a_0)^T a_2 \bar{W}_2 c_2$$  \hspace{1cm} (6.11)

and

$$-a_0 \bar{W}_0 (a_0)^T a_1 c_1 + a_1 \bar{W}_1 c_1 = -a_0 \bar{W}_0 (a_0)^T a_2 c_2 + a_2 \bar{W}_2 c_2.$$  \hspace{1cm} (6.12)

Solving for the body axis rotation rate command matrix for vehicle one

$$\bar{W}_{1c} = (a_0)^T (a_0 \bar{W}_0 (a_0)^T (a_1 - a_{1d}) + a_2 \bar{W}_2 c_2 (c_1)^T).$$  \hspace{1cm} (6.13)
The $a_{1d}$ matrix is the desired attitude matrix given by Equation 6.3. Note that when the $a_1$ matrix approaches the $a_{1d}$ (desired attitude matrix) the steady state rotation rate command matrix for vehicle one becomes

$$\bar{W}_{1c} = (a_1)^T a_2 \bar{W}_2 c_2 (c_1)^T.$$ 

The candidate FCS could monitor the error signal, $(a_1-a_{1d})$ from Equation 6.13 above and apply appropriate gains and limiters to control the attitude of vehicle one during docking.
Detailed analysis of the Automatic Rendezvous and Capture problem indicate three different regions of mathematical description for the GN&C algorithms; (1) multi-vehicle orbital mechanics to the rendezvous interface point, i.e., within 100 NM, (2) relative motion solutions (such as Clohessy-Wiltshire type) from the far field to the near field interface, i.e., within 1 NM and (3) close proximity motion - the near field motion where relative differences in the gravitational and orbit inertial effects can be neglected from the equations of motion. Limit boundaries to these regions can be precisely defined by further analysis and will also be a function of the tracking measurement accuracies and the computer resources available to the solution algorithms.

The subjects of this paper analyze the regions (2) and (3) above and presents the derivation and discussion of the general case of gravitational perturbed relative motion. Mathematical deviations from the spherical gravity case of Clohessy-Wiltshire are presented in the analysis. Based upon the preliminary analysis of this work it is recommended that further efforts be used to assess the relative position and velocity differences in region (2) due to non-spherical effects (especially that of J₂) in the gravity perturbations. Future GN&C systems using relative motion measurements from either an onboard laser tracking systems or from the GPS will possibly be able to detect and predict these perturbations in the relative motion.

The docking port relative position and velocity target vectors as outlined in this work couples the effects of the translation and rotation control activity. Based on these preliminary control parameters it is recommended that guidance and control systems functions couple translation and attitude control in region (3) for safe docking maneuvers. In region (2) the relative range between the docking port targets is assumed large enough so that translation and rotation G&C functions can be independent of one another.
8.0 REFERENCES


The following list contains the fundamental parameters necessary to solve for the motion and attitudes of two vehicles relative to the geodesic LVLH frame and the body axis frame, respectively. A numerical process to perform the first order solution of this set of simultaneous differential equations is required. This process will perform the integral

\[ x(t+\Delta t) = x(t) + \int_{t}^{t+\Delta t} x(t') \, dt'. \]

The process of Runge-Kutta-Gill is recommended, however, in some applications requiring high frequencies (i.e., small \( \Delta t \)) the Cauchy-Euler solution method is adequate for an accurate solution.
In the event that the absolute inertial state is required, the following additions can be made to the integrable parameter list:

\[
\begin{align*}
\dot{x}(t) & \quad \dot{x}(t) \\
\hline \\
1. & x_0 \quad (\text{Position}) \\
2. & \mathbf{x}_0 \quad \mathbf{LVLH \ Ref.} \\
3. & \dot{\mathbf{x}}_0 \quad \mathbf{LVLH \ Ref.} \\
4. & \mathbf{v}_1 \quad \mathbf{Velocity} \\
5. & \mathbf{q}_1 \quad \mathbf{Quaternion} \\
6. & \mathbf{q}_1 \quad \mathbf{Body \ axis \ to} \\
7. & \mathbf{q}_1 \quad \mathbf{inertial} \\
8. & \dot{\mathbf{q}}_1 \quad \mathbf{Body \ Axis} \\
9. & \dot{\mathbf{q}}_1 \quad \mathbf{Rotation \ Rates} \\
10. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
11. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
12. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
13. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
14. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
15. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
16. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
17. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
18. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
19. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
20. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
21. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
22. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
23. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
24. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
25. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
26. & \mathbf{J}_1 \quad \mathbf{J}_1 (\mathbf{N}_1 - \mathbf{W}_1 \mathbf{I}_1 \mathbf{\omega}_1) \\
27. & \mathbf{X}_0 \quad \mathbf{V}_0 \\
28. & \mathbf{V}_0 \quad \mathbf{V}_0 \\
29. & \mathbf{V}_0 \quad \mathbf{V}_0 \\
30. & \mathbf{V}_0 \quad \mathbf{V}_0 \\
31. & \mathbf{V}_0 \quad \mathbf{V}_0 \\
32. & \mathbf{V}_0 \quad \mathbf{V}_0 \\
\end{align*}
\]

where \( \mathbf{v}_0 \) is the acceleration due to gravity at the point \( \mathbf{X}_0 \), the geodesic coordinate center (see Figure 2-1).
GRAVITATIONAL ACCELERATIONS

APPENDIX B

Using the Newtonian formulation of gravity the inertial gravitational acceleration vector in a spherical gravity field is

\[ G(x) = -\mu R^{-3} x \]  

(B.1)

where \( x \) is the column vector for position from the gravitating mass center, that is,

\[ x = \begin{pmatrix} x \\ y \\ z \end{pmatrix}. \]  

(B.2)

To transform B.1 into the LVLH coordinate frame use Equation 2.1 in B.1,

\[ G(\vec{x}) = -\mu R^{-3} a_0 \vec{x} - \mu R^{-3} x_0 \]  

(B.3)

and transform \( G(\vec{x}) \) to the LVLH frame,

\[ (a_0)^T G(\vec{x}) = \vec{G}(\vec{x}) = -\mu R^{-3}(\vec{x}) - \mu R^{-3}(a^T x_0) \]  

(B.4)

Since the LVLH coordinate axes are aligned with the Z-axis in the \(-R\) direction, Equation B.4 reduces to

\[ \vec{G}(\vec{x}) = -\mu R^{-3} \begin{pmatrix} \vec{x} \\ y \\ z-R_0 \end{pmatrix}. \]  

(B.5)
The gravitational acceleration vector in a field perturbed by non-spherical gravity harmonics, we write,

\[ G(x) = -\mu R^{-3} (I+\mathcal{A})x \]  \hspace{1cm} (B.6)

where \( I \) is the unit matrix and \( \mathcal{A} \) is a diagonal matrix,

\[
\mathcal{A} = \begin{pmatrix}
\mathcal{A}_x & 0 & 0 \\
0 & \mathcal{A}_y & 0 \\
0 & 0 & \mathcal{A}_z
\end{pmatrix}
\]  \hspace{1cm} (B.7)

For example, using the \( J_2 \) harmonic only as shown in Reference 2, Pages 50 and 51,

\[
\begin{pmatrix}
\mathcal{A}_x \\
\mathcal{A}_y \\
\mathcal{A}_z
\end{pmatrix} = \begin{pmatrix}
3/2 J_2 \left( \frac{R_E}{R} \right)^2 \left( 1 - \frac{5}{3} \left( \frac{Z}{R} \right)^2 \right) \\
3/2 J_2 \left( \frac{R_E}{R} \right)^2 \left( 1 - \frac{5}{3} \left( \frac{Z}{R} \right)^2 \right) \\
3/2 J_2 \left( \frac{R_E}{R} \right)^2 \left( 3 - \frac{5}{3} \left( \frac{Z}{R} \right)^2 \right)
\end{pmatrix}
\]  \hspace{1cm} (B.8)

Here, \( R_E \) is the reference planetary equatorial radius and \( J_2 \) is the first zonal harmonic. For instance, the \( J_2 \) harmonic for the earth is \(-1.0826271x10^{-2}\) (unitless) and has the most pronounced effect on the motion of the low earth orbit spacecraft.

Transforming \( G(x) \) in Equation B.6 into \( \bar{G}(\mathcal{A}) \) we have

\[
\bar{G}(\mathcal{A}) = -\mu R^{-3} (I+\mathcal{A}) \begin{pmatrix}
\mathcal{A} \\
\gamma \\
2-R_o
\end{pmatrix}
\]  \hspace{1cm} (B.9)

where \( I \) is the unit matrix and \( \mathcal{A} \) is given by the similarity transformation,
\( \bar{R} = a^T \bar{R} a, \quad \text{(B.10)} \)

and becomes a full matrix in the LVLH coordinate frame. Using the \( J_2 \) harmonic only from Equation B.8 and reducing to LVLH coordinates Equation B.9 becomes,

\[
\bar{G}(\vec{x}) = -\mu R^{-3} \left( I + \frac{3}{2} J_2 \left( \frac{R_E}{R} \right)^2 \right) \\
\left[ a^T [K] a - 5 \left( \frac{z}{R} \right)^2 I \right] \begin{pmatrix} \dot{x} \\ \dot{y} \\ z - R_o \end{pmatrix} \quad \text{(B.11)}
\]

where the matrix \([K]\) is a constant matrix given by

\[
[K] = \begin{pmatrix} 1.0 & 0 & 0 \\ 0 & 1.0 & 0 \\ 0 & 0 & 3.0 \end{pmatrix}. \quad \text{(B.12)}
\]
The $\bar{P}_x$ Matrix of Equation 2.15 for a spherical gravitational field is found by partial differentiation of Equation B.5 with respect to the $x$ coordinates and is

$$\bar{P}_x = \frac{\partial \bar{g}}{\partial x} = -\mu R^{-3}$$

\[
\begin{pmatrix}
1-3 \left( \frac{x}{R} \right)^2 & -3 \left( \frac{xy}{R^2} \right) & -3x(z-R_0) \\
-3 \left( \frac{xy}{R^2} \right) & 1-3 \left( \frac{y}{R} \right)^2 & -3y(z-R_0) \\
-3x(z-R_0) & -3y(z-R_0) & 1-3 \left( \frac{z-R_0}{R} \right)^2
\end{pmatrix}
\]  

(C.1)

The Clohessy-Wiltshire relative motion equations result when $x$, $y$, and $z$ are very small relative to the radius vector magnitude $R$ (thus $R$ approaches $R_0$) and Equation C.1 is approximated by

$$\bar{P}_x \approx -\mu R^{-3}$$

\[
\begin{pmatrix}
1.0 & 0.0 & 0.0 \\
0.0 & 1.0 & 0.0 \\
0.0 & 0.0 & -2.0
\end{pmatrix}
\]  

(C.2)

When the gravity field is perturbed due to non-spherical harmonics as in a real world situation the $P_x$ matrix is found by partial differentiation of Equation B.9 with respect to the $x$ coordinates and can be written out in component form as follows:
\[
\frac{\partial \overline{G}_x}{\partial x} = \mu R^{-3} \left( 1 + \overline{R}_{11} + \left( \frac{\partial \overline{R}}{\partial x} - 3 \frac{x}{R^2} \left( 1 + \overline{R}_{11} \right) \right) x \right.
\]
\[
+ \left( \frac{\partial \overline{R}_{12}}{\partial x} - 3 \frac{x}{R^2} \right) y + \left( \frac{\partial \overline{R}_{13}}{\partial x} - 3 \frac{x}{R^2} \right) (z - R_0) \right) \] (C.3)

\[
\frac{\partial \overline{G}_x}{\partial y} = \mu R^{-3} \left( \overline{R}_{12} + \left( - \overline{R}_{11} + 3 \frac{y}{R^2} \left( 1 + \overline{R}_{11} \right) \right) x \right.
\]
\[
+ \left( \frac{\partial \overline{R}_{12}}{\partial y} - 3 \frac{y}{R^2} \overline{R}_{12} \right) y + \left( \frac{\partial \overline{R}_{13}}{\partial y} - 3 \frac{y}{R^2} \overline{R}_{13} \right) (z - R_0) \right) \] (C.4)

\[
\frac{\partial \overline{G}_x}{\partial z} = \mu R^{-3} \left( \overline{R}_{13} + \left( - \overline{R}_{11} + 3 \frac{(z - R_0)}{R^2} \left( 1 + \overline{R}_{11} \right) \right) x \right.
\]
\[
+ \left( \frac{\partial \overline{R}_{12}}{\partial z} - 3 \frac{(z - R_0)}{R^2} \overline{R}_{12} \right) y + \left( \frac{\partial \overline{R}_{13}}{\partial z} - 3 \frac{(z - R_0)}{R^2} \overline{R}_{13} \right) (z - R_0) \right) \] (C.5)
\[
\frac{\partial G_y}{\partial x} = \mu R^{-3} \left( \frac{\partial \bar{R}_{21}}{\partial x} + \left( \frac{\partial \bar{R}_{21}}{\partial y} - 3 \frac{z}{R^2} \right) \bar{R}_{21} \right) x
\]
\[
+ \left( \frac{\partial \bar{R}_{22}}{\partial x} - 3 \frac{x}{R^2} \left( 1 + \bar{R}_{22} \right) \right) y
\]
\[
+ \left( \frac{\partial \bar{R}_{23}}{\partial x} - 3 \frac{z}{R^2} \bar{R}_{23} \right) \left( z - R_0 \right) \right) \]
\]
\[
\frac{\partial G_y}{\partial y} = \mu R^{-3} \left( 1 + \bar{R}_{22} + \left( \frac{\partial \bar{R}_{21}}{\partial y} - 3 \frac{y}{R^2} \bar{R}_{21} \right) x
\]
\[
+ \left( \frac{\partial \bar{R}_{22}}{\partial y} - 3 \frac{y}{R^2} \left( 1 + \bar{R}_{22} \right) \right) y
\]
\[
+ \left( \frac{\partial \bar{R}_{23}}{\partial y} - 3 \frac{y}{R^2} \bar{R}_{23} \right) \left( z - R_0 \right) \right) \]
\]
\[
\frac{\partial G_y}{\partial z} = \mu R^{-3} \left( \frac{\partial \bar{R}_{23}}{\partial z} + \left( \frac{\partial \bar{R}_{21}}{\partial z} - 3 \frac{(2-R_0)}{R^2} \left( 1 + \bar{R}_{21} \right) \right) \bar{R}_{23} \right) \]
\[
+ \left( \frac{\partial \bar{R}_{22}}{\partial z} - 3 \frac{(2-R_0)}{R^2} \left( 1 + \bar{R}_{22} \right) \right) \bar{R}_{23} \right) \left( z - R_0 \right) \right) \]
\]
\]
\]
\[
(C. 6)
\]
\[
(C. 7)
\]
\[
(C. 8)
\]
\[
\frac{\partial G_x}{\partial x} = \mu R^{-3} \left( \overline{R}_{31} + \left( \frac{\partial \overline{R}_{31}}{\partial x} - 3 \frac{x}{R^2} \overline{R}_{31} \right) x \right.
\]
\[
\left. + \left( \frac{\partial \overline{R}_{32}}{\partial x} - 3 \frac{x}{R^2} \overline{R}_{32} \right) y \right)
\]
\[
\left. + \left( \frac{\partial \overline{R}_{33}}{\partial x} - 3 \frac{x}{R^2} \left(1+\overline{R}_{33}\right) \right) \left(2-R_0\right) \right) \] (C. 9)

\[
\frac{\partial G_x}{\partial y} = \mu R^{-3} \left( \overline{R}_{32} + \left( \frac{\partial \overline{R}_{31}}{\partial y} - 3 \frac{y}{R^2} \overline{R}_{31} \right) x \right.
\]
\[
\left. + \left( \frac{\partial \overline{R}_{32}}{\partial y} - 3 \frac{y}{R^2} \overline{R}_{32} \right) y \right)
\]
\[
\left. + \left( \frac{\partial \overline{R}_{33}}{\partial y} - 3 \frac{y}{R^2} \left(1+\overline{R}_{33}\right) \right) \left(2-R_0\right) \right) \] (C. 10)

\[
\frac{\partial G_z}{\partial z} = \mu R^{-3} \left( 1 + \overline{R}_{33} + \left( \frac{\partial \overline{R}_{31}}{\partial z} - 3 \frac{(2-R_0)}{R^2} \overline{R}_{31} \right) x \right.
\]
\[
\left. + \left( \frac{\partial \overline{R}_{32}}{\partial z} - 3 \frac{(2-R_0)}{R^2} \overline{R}_{32} \right) y \right)
\]
\[
\left. + \left( \frac{\partial \overline{R}_{33}}{\partial z} - 3 \frac{(2-R_0)}{R^2} \left(1+\overline{R}_{33}\right) \right) \left(2-R_0\right) \right) \] (C. 11)
As \( x, y \) and \( z \) approach zero (\( R \) approaches \( R_0 \)) and Equations C.3 through C.11 form the \( \overline{P}_x \) matrix as in Equation C.2 but for non-spherical case,

\[
\overline{P}_x = -\mu R^{-3}
\begin{pmatrix}
\left( 1 + \overline{R}_{11} - R_0 \right) \frac{\partial \overline{R}_{13}}{\partial x} & \left( \overline{R}_{12} - R_0 \right) \frac{\partial \overline{R}_{13}}{\partial y} & \left( \overline{R}_{13} - R_0 \right) \frac{\partial \overline{R}_{13}}{\partial z} \\
\left( \overline{R}_{21} - R_0 \right) \frac{\partial \overline{R}_{23}}{\partial x} & \left( 1 + \overline{R}_{22} - R_0 \right) \frac{\partial \overline{R}_{23}}{\partial y} & \left( \overline{R}_{23} - R_0 \right) \frac{\partial \overline{R}_{23}}{\partial z} \\
\left( \overline{R}_{31} - R_0 \right) \frac{\partial \overline{R}_{33}}{\partial x} & \left( \overline{R}_{32} - R_0 \right) \frac{\partial \overline{R}_{33}}{\partial y} & \left( -2 + 2 \overline{R}_{33} - R_0 \right) \frac{\partial \overline{R}_{33}}{\partial z}
\end{pmatrix}
\] (C.12)

Typical values for the \( \overline{P}_x \) matrix in a 4x4 gravity field at 190 NM altitude (orbit inclination 28.5°) as a function of orbital longitude (\( L \)) are;

For \( L = 0.0^\circ \),

\[
\overline{P}_x = -\mu R^{-3}
\begin{pmatrix}
0.100211132E+1 & -0.127455301E-2 & 0.860795280E-4 \\
-0.127455552E-2 & 0.100374459E+1 & 0.141282142E-5 \\
0.441508313E-4 & -0.992324472E-4 & 0.141282142E-5
\end{pmatrix}
\] (C.13)

For \( L = 91.914^\circ \),

\[
\overline{P}_x = -\mu R^{-3}
\begin{pmatrix}
0.99755725E+0 & 0.656077200E-4 & -0.128398836E-3 \\
0.658219319E-4 & 0.100197258E+1 & -0.497582344E-2 \\
-0.780933175E-4 & -0.490363083E-2 & 0.200586443E+1
\end{pmatrix}
\] (C.14)

For \( L = 184.114^\circ \),

\[
\overline{P}_x = -\mu R^{-3}
\begin{pmatrix}
0.100217612E+1 & 0.119984812E-2 & 0.174780536E-3 \\
0.119982659E-2 & 0.100371725E+1 & 0.414833236E-3 \\
0.223653423E-3 & 0.303452941E-3 & -0.200189351E+1
\end{pmatrix}
\] (C.15)

For \( L = 276.309^\circ \),

\[
\overline{P}_x = -\mu R^{-3}
\begin{pmatrix}
0.999822606E+0 & -0.917771447E-4 & -0.183744890E-3 \\
-0.916192270E-4 & 0.100211408E+1 & 0.474542054E-2 \\
-0.217657097E-3 & 0.482754340E-2 & -0.200180233E+1
\end{pmatrix}
\] (C.16)
# Reference Equations of Motion for Automatic Rendezvous and Capture

The analysis presented in this paper defines the reference coordinate frames, equations of motion and control parameters necessary to model the relative motion and attitude of spacecraft in close proximity with another space system during the Automatic Rendezvous and Capture phase of an on-orbit operation.

The relative docking port target position vector and the attitude control matrix are defined based upon an arbitrary spacecraft design. These translation and rotation control parameters could be used to drive the error signal input to the vehicle flight control system. Measurements for these control parameters would become the bases for an autopilot or FCS design for a specific spacecraft.