MISSION ACTIVITIES PLANNING FOR A HERMES MISSION BY MEANS OF AI-TECHNOLOGY

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ABSTRACT

Mission Activities Planning is a complex task to be performed by mission control centers. AI technology can offer attractive solutions to the planning problem. This paper presents the use of a new AI-based Mission Planning System for crew activity planning which has been set up in the course of an ESA project in cooperation with an industrial consortium led by ERNO Raumfahrttechnik. Based on a HERMES servicing mission to the COLUMBUS Man Tended Free Flyer (MTFF) with complex time and resource constraints appr. 2000 activities with 50 different resources have been generated, processed and planned with parametric variation of operationally sensitive parameters. The architecture as well as the performance of the mission planning system is discussed. An outlook to future planning scenarios, the requirements and how a system like MARS can fulfill those requirements is given.

Key Words: crew activity planning, time- and resource constraints, distributed planning, rule based planning.

1. MISSION SCENARIO & OVERVIEW

The case study conducted is based on a HERMES servicing mission to the COLUMBUS Man Tended Free Flyer [ref 1]. The mission scenario includes a HERMES launch rate of 2 per year. The involved ground segment comprises a Hermes Flight Control Center (HFCC), an MTFF Control Center (MSCC), a coordinating Combined Mission Control Center (CMCC) as well as User and Engineering Support Centers.

Crew activity planning for such type of missions has to consider the following main aspects:

- the HERMES spaceplane system:
  - launched by an ARIANE 5 launcher
  - Mass of payload 3.0 metric tons

- nominal mission duration: 10 days (Free Flyer Servicing: 6 days)
- 3 crewmembers (commander, pilot, mission engineer)

- the Man Tended Free Flying Laboratory:
  - 2 segment Pressurized Module (PM) for accommodation of 16 P/L racks (12 m³)
  - Resource Module (RM) docked to PM
  - Propulsion subsystem for altitude and attitude control
  - ARIANE 5 launch vehicle

- MTFF servicing concept:
  - Corrective/Preventive Maintenance
  - Replenishment of consumables
  - Inspection and cleaning
  - Implementation of growth features
  - P/L Upgrading, repair, reconfiguration & replacement of payload facilities
  - P/L Resupply and collection of samples & consumables
  - P/L Checkout and set-up of P/L processes
  - Servicing by IVA, EVA, Remote Manipulation and combined EVA and Remote Manipulation activities.

- Mission Cargo Sets includes all serviceable items for a single servicing mission, including:
  - permanent travellers (to be flown each mission)
  - life limited items (to be exchanged at end of life)
  - stochastic items (corrective maintenance)
  - consumables (e.g. gases & fluids)
  - airborne support equipment (ASE) & tools

2. THE PLANNING APPROACH

Crew tasks like internal servicing of subsystems or payloads, external servicing of subsystems, crew sustaining operations, etc. can be broken down into subtasks and activities. The resulting
hierarchical structure of crew activities has to be converted into a planning database which can then be accessed by the planning system. The nodes of the planning database contain all the relevant planning information, like: earliest and latest start time, permissible time window, used resources (power, crew member, sun / eclipse phases, communication channels, etc.), antecedent links to other activities etc. Resources are specified: name, type, availability and max capacity.

The idea is first to build a generic planning database which can serve as a library of generic tasks, subtasks and activities to be copied for reuse and customization for a specific mission, thus to reduce significantly the effort for the compilation of planning data. The contents of the specific database depends totally on the Mission Cargo Sets.

Consistency checks of the specific DB (e.g. missing or inconsistent antecedent links) are supported by the planning system itself.

Such a system can be easily used as a valuable tool for quick assessment of design changes by planning with parametric variation of operational sensitive parameters.

3. THE PLANNING SYSTEM

3.1 The MARS Scheduling System

The scheduling of the activities selected for a specific mission was performed by means of the AI based mission planning tool MARS (Mission Activities and Resource Scheduler [ref 2]) developed by ERNO Raumfahrttechnik GmbH. The design of MARS explicitly takes into account the complexity aspects of current and future space missions. It has been steadily evolved in tight cooperation with operational users. Within the ESTEC contract NEPTUNE (New Expert System for Users in a Network Environment [ref 3]) MARS was enhanced by more general resource handling capabilities, a rule system, configuration management features and distributed planning capabilities. It now includes all features necessary to successfully apply it not only to space missions planning but to any kind of large project scheduling.

The main modules of MARS comprise the Database Editor and the Scheduler each of which will be briefly described in the following.

The Database Editor is a graphical interactive tool to allow the efficient creation and modification of activity and resource descriptions, rules to direct the scheduling process and constraints. Activities are hierarchically structured as explained in chapter 2 and handled by the Activity Editor [Fig. 1].

Activities are described by the following major attributes:

- Full activity name and abbreviation, position in the activity hierarchy.
- Earliest and latest possible start time and due date (if fixed by problem at hand).
- Minimum and maximum duration.
- Any number of antecedent activities and min-/max delay times to them (logical dependencies).
- Priority, keywords and comments by the user.
- Interdependencies to other activities (mutually exclusive set of activities).
- Any number of resource requests in the form of: resource-name and resource request profiles.

The Resource Editor allows the specification of resources as well as the generation of resource availability profiles. Any number of different resources can be introduced by the user. Each resource can be of one of the following types:

- Sharable resources represent system states. E.g. the execution of several activities can be restricted to happen during certain day or night periods (SUN-ECLIPSE Phases).
- Depletable resources can be used to describe incremental consumption of a given capacity, e.g. Battery or Storage Place.
- Reusable resources can only be used by one user at a time but are available afterwards, e.g. Tools and Energy. Conventional project planning tools only provide this single type of resource.
- Tri-state resources allow to specify mutually exclusive sets of activities (e.g. activities of one set cannot run in parallel with activities of another set). It is a combination of sharable and reusable.

Optionally resource requests can be defined that are used permanently even after termination of the given activity. Resources can also be generated by activities. Additionally a calendar defining the general working hours and off days can be defined as in any conventional project planning system.

For the generation of schedules and timelines adhering to all given constraints a set of rules (heuristics) can be specified using the Rule Editor. Those rules influence or direct the scheduling process. E.g. it is possible to schedule in
priority a selected set of activities or to schedule in priority the most resource consuming activities. Using this feature of MARS the user is very flexible in defining his/her own preferences or goals to be achieved by the scheduling process.

Four different rule types exist:

- **Scheduling Rules**, which select the set of activities for the next pass of the scheduling process.
- **Activity Selection Rules**, which influence the selection of the next to be scheduled activities.
- **Rescheduling Rules**, which influence the rescheduling process and
- **Backtracking Rules**, which direct the scheduling process during backtracking situations.

**Scheduler**

The basic problem in any scheduling process involving (limited) resources is defined by the requirement to satisfy both temporal and resource constraints simultaneously.

For MARS therefore a new method has been developed, called *Time Constraints Propagation Mechanism* (TCPM), that transforms all symbolic time constraints on and between activities into a computationally much more efficient algebraic representation covering all time relations defined between activities. At first "time constraint windows" are computed for each activity with respect to the totality of all temporal constraints imposed on the plan. Scheduling of activities only within these time windows guarantees that no temporal constraint conflicts will occur at any point in the scheduling process. Thus futile attempts to schedule activities outside these windows are avoided, thereby speeding up the scheduling process considerably and increasing the chance of generating a conflict-free schedule. It is the task of the TCPM to compute and dynamically update these permissible time windows after each scheduling step.

This separation between handling time and resource constraints leads to a scheduling strategy whereby at each point in time, starting from left to right on the time axis, only those activities which lie within their permissible time windows and whose resource and target requests are satisfied by the resource and target availability profiles for the total duration of the activity are identified. Obviously each of these activities individually represents a candidate for scheduling. However, usually not all candidates can be scheduled simultaneously, but only candidate
subsets. To influence which subset is assigned the highest priority for being scheduled the user can tailor the involved heuristics with the help of the rule system mentioned above. Activities whose resource requests cannot be met at that particular scheduling step are shifted in time to the beginning of their next "resource window", where their resource request can be fulfilled, but staying within their computed time window.

In this way generating timelines and schedules with MARS can proceed fully automatically, fully interactively where the operator selects each activity to be scheduled, or in a "mixed mode". In all modes the user can follow the dynamically unfolding scheduling process graphically on the "temporal level". At any point in the scheduling process one is able to re-edit activities or resource availability profiles, perform backtrack operations and call up conflict inspection displays, such as:

- Display of the schedule and composite timelines in the form barcharts and Gantt diagrams.
- Resource Usage, giving the percentage resource exploitation over the total mission time (as an indication of the schedule quality).
- Any type and duration of resource violations and involved activities are graphically displayed.
- The user can graphically shift an activity forward or backward in time and view the induced conflicts (or conflict-free areas for scheduling) dynamically displayed by the "co-moving" scheduler (on forward shift) or Backtrack Module (on backward shift).

A typical example of a schedule generated by MARS is depicted in Fig. 2.

3.2 The Mission Database

To demonstrate the ability of MARS to interact with different types of already existing or future mission specific data (e.g. configuration and planning data) and to support the concept of a generic planning database the mission planning data for this project has been stored in an external database whose structure reflects the foreseen COLUMBUS Mission Database Application (MDA). For this purpose the Mission Database Application Software (MIDAS) was developed based on the commercial ORACLE DBMS to provide MARS with the required data. The information maintained by MIDAS consists of:

![Fig. 2 MARS Scheduler](image-url)
3.3 The Toolset Architecture

Since the MARS system and the MIDAS application were intended to be used in a distributed environment running on different physical machines (for this project MARS ran on a Symbolics Ivory LISP coprocessor board residing in a SUN 4/330 with the Genera 8.0 operating system whereas MIDAS was running on a SUN 3 with SunOS 4.0.3) interface S/W was developed to allow communication between MARS and MIDAS in a client-server architecture.

The approach to generate planning data includes 3 main steps:

- Definition of generic crew activities library which can be reused for any mission cargo set.
- Definition/selection of the mission cargo set to be transported by HERMES and operated by the crew including all items for:
  - a selected nominal MTFF servicing mission
  - a selected MTFF contingency mission
- Definition of specific crew activities database based on generic data and the selected mission cargo set.

Only those crew activities were subject for planning which start with docking of HERMES to MTFF and ending with de-docking of HERMES.

4.1 Generic Operations Definitions

All generic crew activities have been structured hierarchically into phase, task, subtask and activity level. The 1st level of the resulting crew activities breakdown is shown in Fig. 4.

The complete breakdown resulted in a total of 80 subtasks and 431 generic activities. An example of the activities breakdown established for
the exchange of a failed video modulator (internal servicing of communication subsystem) is also given in Fig. 1.

4.2 Mission Cargo Sets

The required items/tasks to be installed/accomplished by the crew are determined by the HERMES and MTFF system capabilities as well as by the servicing concept, strategy and constraints (see chap.1). The 20 Mission Cargo Sets (MCS) for the first 10 years of operation have been generated by means of a Monte Carlo Simulation. Out of these a representative MCS has been selected for the detailed planning. For the 114 ORU's of the selected mission a rough accommodation analysis to derive the operational properties of the different ORU's has been performed including an Exchange Task Time Assessment as well as an ORU criticality analysis to derive priority information to be used by the planning system in case of conflicts.

4.3 Specific Operations Definition

Based on the generated MCS information a mission specific database has been set up. The major steps were:

- definition of a suitable task structure to allow the re-use of the existing substructures of the generic database to the extent possible,
- setup of the lower level task/activities structures by:
  - importing
  - modification
  - duplication
  as appropriate for the specific mission demands,
- tuning of the generic planning information imported from the generic database according to the mission specific constraints, e.g. time constraint information, resources and resource usage,
- specification of the resource availabilities,
- definition of the targets (orbital opportunities) in the form of time-histories.

The resulting mission specific database includes 32 Tasks, 399 Subtasks and 1741 Activities.

The same exercise was performed for a contingency mission which has been based on the nominal mission defined before. The assumptions for this mission have been:

- repair to be performed by means of EVA
- exact location and extent of the problem is not known a priori, thus requiring inspection activities with remote manipulator
- specific repair tools had to be included

The database for this mission includes 24 Tasks, 252 Subtasks and 966 Activities.

5. CREW WORKLOAD ANALYSIS

The generation of conflict free schedules of activities defined in the mission database has been performed for the nominal as well as for the contingency mission. Another important analysis was the variation of operationally sensitive parameters in order to investigate selected contingency scenarios and options to change mission rules.

For the nominal mission the following variations of operationally sensitive parameters have been performed:

- Crew Task Change
  The Mission Engineer has been removed from all subsystem servicing activities and the Pilot and Commander got the same priority to perform subsystem servicing.
- MCS Reduction
  Some cargo items could not be accommodated physically in HERMES. The corresponding crew activities have been removed from the schedule.
- Crew Sickness
  The Mission Engineer is not available on the first servicing day for about 4 hours due to space sickness.
- Communication Dropout
  RF - Communication between HERMES / MTFF and ground is interrupted for 3 hours on the 4th mission day.

The generated schedule for the nominal mission showed that with the a priori defined crew allocation to the mission activities only 35 % of the science payloads could be processed. Valuable statistical functions for exploitation of the available crew resources resulted in the following numbers:

- Commander = 61.6 %
- Pilot = 62.9 %
- Mission Engineer = 84.9 %

These numbers gave indications to assign more tasks in the science payload area to the Commander and to the Pilot, which resulted in
Tab. 1 Summary of Planning Results

<table>
<thead>
<tr>
<th>Planning Results Summary</th>
<th>Nominal Mission &quot;M4&quot;</th>
<th>M4 Planning Options</th>
<th>Contingency Mission &quot;M4C&quot;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Total Mission Time [d/h/m]</td>
<td>11 d 8 h 27 m</td>
<td>8d</td>
<td>10d 1h 48m</td>
</tr>
<tr>
<td>Database Size: Phases</td>
<td>N/A</td>
<td>-4827</td>
<td>-1239</td>
</tr>
<tr>
<td>Tasks</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>Subtasks</td>
<td>32</td>
<td>32</td>
<td>32</td>
</tr>
<tr>
<td>Activities</td>
<td>1741</td>
<td>1741</td>
<td>1676</td>
</tr>
<tr>
<td>Crew Usage: Commander</td>
<td>61.6%</td>
<td>89.4%</td>
<td>62.9%</td>
</tr>
<tr>
<td>Pilot</td>
<td>62.0%</td>
<td>87.2%</td>
<td>63.9%</td>
</tr>
<tr>
<td>Mission-E.</td>
<td>84.9%</td>
<td>84.6%</td>
<td>85.5%</td>
</tr>
<tr>
<td>Subsystem Servicing:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Start Time</td>
<td>1d 2h 30m</td>
<td>1d 2h 36m</td>
<td>1d 2h 36m</td>
</tr>
<tr>
<td>End Time</td>
<td>5d 1h 16m</td>
<td>5d 1h 16m</td>
<td>5d 1h 16m</td>
</tr>
<tr>
<td>Serviced ORUs</td>
<td>100%</td>
<td>100%</td>
<td>100%</td>
</tr>
<tr>
<td>Payload Servicing:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Start Time</td>
<td>5d 8h 16m</td>
<td>1d 2h 55m</td>
<td>1d 2h 55m</td>
</tr>
<tr>
<td>End Time</td>
<td>11d 2h 4m</td>
<td>1d 10h 18m</td>
<td>1d 10h 18m</td>
</tr>
<tr>
<td>Serviced ORUs</td>
<td>35%</td>
<td>100%</td>
<td>48%</td>
</tr>
</tbody>
</table>

a 100% accomplishment of all tasks. Table 1 indicates the results obtained by the other variations.

6. OTHER SYSTEM APPLICATIONS

MARS has shown its versatility and operational capabilities in a number of different application areas. The first important application field was the planning of manned and unmanned space missions on tactical as well as on executional level. This also covers the application as described in this paper. Furthermore, MARS was used to perform dynamic payload accommodation based on information contained in payload configuration databases (such as the COLUMBUS P/L Database CPDB) and to analyse alternative accommodations [ref 4].

In a study on future autonomous space systems MARS was used as a building block for autonomous scheduling and rescheduling. Complemented by a diagnosis system and spacecraft simulator the system was able to demonstrate the capabilities of a fully autonomous spacecraft that reacts to malfunctions by diagnosing its internal status, initiates appropriate recovery actions and finally replans the rest of its mission according to the new situation [ref 5].

Current activities comprise the development of interface software and the rework of planning data originally compiled for the MIPS (Mission Planning System) used to plan the next German Spacelab Mission (D2) to be launched early next year. For this application MARS is intended to be validated during the mission in terms of its performance and operational capabilities by comparing MARS with the built-in scheduler (ESP, Experiment Scheduling Program) of the MIPS system in replanning situations. For this purpose MARS is extended to be able to deal with the same input and output data formats as the ESP system. Former studies have already shown the advantages of MARS as an automatic and interactive scheduling tool wrt ESP, but this will have to be justified during that real mission.

Another recent project is the utilisation of MARS for the planning of the ARIANE4 second stage and booster production and integration that is performed at ERNO premises.

Under the product name PARS (for Project Activities and Resource Scheduler) the MARS system will also be made available commercially on SUN workstations until end of this year.

Distributed Planning

The COLUMBUS mission planning concept is currently still under definition. MARS can support an operational scenario which is based on two important principles:
According to the hierarchy of the distributed planning environment there will exist a tree structure of logical nodes each with its own MARS system, each responsible for the planning of a specific logical node or mission center in the hierarchy. Within a logical node the activities are structured itself in a tree hierarchy as described for the mission planning database editor. In a top-down procedure each center allocates resource envelopes to its lower level centers over the network, so that these can generate their own local schedules and timelines. Afterwards these local timelines will be integrated in a bottom up approach into the higher level timelines. This MARS features can also be applied to any type of project planning, where the problem at hand must be decomposed and solved by several planning teams, working closely together.

7. CONCLUSION

The results of the project have clearly shown that such a planning system can be an essential tool throughout the lifecycle of a space project, starting with the initial definition of the space infrastructure until and within the operational phase. In the very early project phases trade-offs can be performed to assist in the design of the spacecrafts and payloads. What-if scenarios can be worked out to identify bottlenecks in the system design by analysing operational scenarios (timelines).

The planning system used in this study compared to other commercially available systems, e.g. for project planning, has the ability to handle different kinds of resources, e.g. to handle stocking tasks by filling intermediate stores. It can be interfaced with other software and databases through its programming language interface and the possibility exists to extend its intrinsic functionality to implement any upcoming and very specialised requirements, e.g. for additional project specific resource types.

These features would allow the cost effective application of MARS in other very demanding scheduling domains where resources are a limiting factor and the timespan for execution of tasks is restricted, such as:

- Production planning, scheduling of production tasks, interleaving of multiple production lines
- Transportation planning
- Logistics planning

Future alternative hardware platforms for the planning tool MARS will be any UNIX based system that supports a Common Lisp environment with multitasking capability and X window system interface using CLIM and CLOS (e.g. SUN workstations). This will achieve the goal of principal hardware independence for MARS and derivatives (PARS) and will be finished in 1992.

8. ACKNOWLEDGEMENTS

The following organisations have contributed to the implementation and application of the described system:

SENER, Bilbao - Spain
CISET, Rome - Italy

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