ther the present LDPC-PPM scheme or
the prior SCPPM scheme. At the trans-
mitting terminal, the original data \((u)\)
are processed by an encoder into blocks
of bits \((a)\), and the encoded data are
mapped to PPM of an optical signal \((c)\).
For the purpose of design and analysis,
the optical channel in which the PPM
signal propagates is modeled as a Pois-
son point process. At the receiving ter-
minal, the arriving optical signal \((y)\)
is
demodulated to obtain an estimate \((\hat{a})\)
of the coded data, which is then
processed by a decoder to obtain an esti-
mate \((\hat{u})\) of the original data.

The demodulation and decoding sub-
processes are iterated to improve the
final estimates in an attempt to recon-
struct the original data stream \((u)\)
ex-
actly. The decoder implements a soft-
input/soft-output (SISO) algorithm.
This or any SISO decoder receives, as
soft inputs, noisy versions (estimates and
log-likelihoods of the estimates) of the
input and output of the encoder and
produces updated log-likelihoods of the
estimates of the input, the output, or
both. These estimates and their log-like-
lihoods may then be transmitted to
other SISO modules in the receiver,
where they are treated as noisy inputs.

In comparison with non-iterative alter-
natives, both the present LDPC-PPM
scheme and the prior SCPPM scheme
offer better performance. In comparison
with iterative alternatives, both schemes
afford better performance with less com-
plexity. In comparison of these schemes
with each other, each is partly advanta-
geous and partly disadvantageous: For ex-
ample, computational simulations have
shown that for a block length of about
8Kb, the performance of the prior
SCPPM scheme is about 0.8 dB away from
the theoretical channel capacity, while
the performance of the LDPC-PPM
scheme is expected to be about 1.2 dB
away from the theoretical channel capac-
ity at a bit-error rate of about \(2 \times 10^{-5}\) (see
Figure 2); in other words, the perform-
ance of the LDPC-PPM scheme is ex-
pected to be about 0.4 dB below that of
the prior SCPPM scheme. On the other
hand, unlike the prior SCPPM scheme,
the LDPC-PPM scheme is lends itself very
good to low-latency parallel processing. Ei-
ther scheme could serve as the basis of
design of an optical communication sys-
tem, depending on requirements per-
taining to the PPM order, latency, and ar-
chitecture of the system.

This work was done by Maged Barsoum,
Bruce Moision, Dariush Divsalar, and Jon
Hamkins of Caltech and Michael Fitz of
UCLA for NASA’s Jet Propulsion Laboratory.
Further information is contained in a TSP
(see page 1), NPO-44408

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**Complex Event Recognition Architecture**

*Lyndon B. Johnson Space Center, Houston, Texas*

“Complex Event Recognition Archi-
tecture” ("CERA") is the name of a
computational architecture, and soft-
ware that implements the architecture,
for recognizing complex event patterns
that may be spread across multiple
streams of input data. One of the main
components of CERA is an intuitive
event pattern language that simplifies
what would otherwise be the complex,
difficult tasks of creating logical de-
scriptions of combinations of temporal
events and defining rules for combin-
ing information from different sources
over time. In this language, recognition
patterns are defined in simple, declarative statements that combine point events from given input streams with those from other streams, using conjunction, disjunction, and negation. Patterns can be built on one another recursively to describe very rich, temporally extended combinations of events. Thereafter, a run-time matching algorithm in CERA efficiently matches these patterns against input data and signals when patterns are recognized.

CERA can be used to monitor complex systems and to signal operators or initiate corrective actions when anomalous conditions are recognized. CERA can be run as a stand-alone monitoring system, or it can be integrated into a larger system to automatically trigger responses to changing environments or problematic situations. This program was written by William A. Fitzgerald and R. James Firby of I/NET, Inc. for Johnson Space Center. Further information is contained in a TSP (see page 1).

TurboTech Technical Evaluation Automated System
Goddard Space Flight Center, Greenbelt, Maryland

TurboTech software is a Web-based process that simplifies and semiautomates technical evaluation of NASA proposals for Contracting Officer’s Technical Representatives (COTRs). At the time of this reporting, there have been no set standards or systems for training new COTRs in technical evaluations. This new process provides boilerplate text in response to “interview-style” questions. This text is collected into a Microsoft Word document that can then be further edited to conform to specific cases.

By providing technical language and a structured format, TurboTech allows the COTRs to concentrate more on the actual evaluation, and less on deciding what language would be most appropriate. Since the actual word choice is one of the more time-consuming parts of a COTRs’ job, this process should allow for an increase in quantity of proposals evaluated.

TurboTech is applicable to composing technical evaluations of contractor proposals, task and delivery orders, change order modifications, requests for proposals, new work modifications, task assignments, as well as any changes to existing contracts. This work was done by Dorothy J. Tiffany of Goddard Space Flight Center. Further information is contained in a TSP (see page 1). GSC-15554-1

Robot Vision Library
NASA’s Jet Propulsion Laboratory, Pasadena, California

The JPL Robot Vision Library (JPLV) provides real-time robot vision algorithms for developers who are not vision specialists. The package includes algorithms for stereo ranging, visual odometry and unsurveyed camera calibration, and has unique support for very wide-angle lenses (as used on the Mars Exploration Rover HazCams). JPLV gathers these algorithms into one uniform, documented, and tested package with a consistent C API (application programming interface). The software is designed for real-time execution (10–20 Hz) on COTS (commercial, off-the-shelf) workstations and embedded processors.

This package incorporates algorithms developed over more than ten years of research in ground and planetary robotics for NASA, DARPA (Defense Advanced Research Projects Agency) and the Army Research Labs, and is currently being used in applications as diverse as legged vehicle navigation and large-scale urban modeling. This work was done by Andrew B. Howard, Adnan I. Ansar, and Todd E. Litwin of Caltech and Steven B. Goldberg of Indelible Systems for NASA’s Jet Propulsion Laboratory.

This software is available for commercial licensing. Please contact Karina Edmonds of the California Institute of Technology at (626) 395-2322. Refer to NPO-46532.

Perl Modules for Constructing Iterators
Goddard Space Flight Center, Greenbelt, Maryland

The Iterator Perl Module provides a general-purpose framework for constructing iterator objects within Perl, and a standard API for interacting with those objects. Iterators are an object-oriented design pattern where a description of a series of values is used in a constructor. Subsequent queries can request values in that series. These Perl modules build on the standard Iterator framework and provide iterators for some other types of values. Iterator::DateTime constructs iterators from DateTime objects or Date::Parse descriptions and ICal/rfc 2445 style re-