# Rate and collision probability of tethers and sails against debris or spacecraft 

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- This presentation is available at https://sites.google.com/site/ricardogarciapelayo/

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- Computation of the collision probability of an encounter of a particular pair of objects whose probability density functions of the positions are known. This information is necessary to decide if an evasive maneuver is going to be performed or not.
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- Computation of the collision rate when the flux of one object (typically debris) with respect to the other object is known. This information is important when planning a mission.
- Computation of the collision probability of an encounter of a particular pair of objects whose probability density functions of the positions are known. This information is necessary to decide if an evasive maneuver is going to be performed or not.
- Contrary to the sphere-sphere case, attitude matters.


## Introduction


square sail + debris or spacecraft
tether $\quad+$ debris or spacecraft

round sail + debris or spacecraft


## Introduction

$\rho$ is the projection on the $b$-plane of the pdf of the relative position.


$$
\text { probability of collision }=\int_{M \oplus(-S)} d^{2} r \rho(\vec{r})
$$

$$
\text { rate of collision }=\frac{\bar{\rho} \mathrm{A}(M \oplus(-S))}{\text { time between encounters }} \rightarrow \phi \mathrm{A}(M \oplus(-S))
$$

prob. of $n$ collisions during a time $t=e^{-\phi \mathrm{A}(M \oplus(-S)) t} \frac{(\phi \mathrm{~A}(M \oplus(-S)))^{n}}{n!}$

## Collision rate

## Fixed attitude



$$
\mathrm{A}(M \oplus(-S))=\mathrm{A}(M \oplus S)=\mathrm{A}(M)+\operatorname{per}(M) R+\pi R^{2}
$$

## Collision rate

## Fixed attitude



## Collision rate

## Fixed attitude

$$
\mathrm{A}(M \oplus(-S))=
$$

## Collision rate

## Fixed attitude

$$
\mathrm{A}(M \oplus(-S))=
$$

- 

$$
a b \sqrt{-\cos \left(\theta_{a}+\theta_{b}\right) \cos \left(\theta_{a}-\theta_{b}\right)}+2\left(a \sin \theta_{a}+b \sin \theta_{b}\right) R+\pi R^{2}
$$

## Collision rate

## Fixed attitude

$$
\mathrm{A}(M \oplus(-S))=
$$

- 

$$
a b \sqrt{-\cos \left(\theta_{a}+\theta_{b}\right) \cos \left(\theta_{a}-\theta_{b}\right)}+2\left(a \sin \theta_{a}+b \sin \theta_{b}\right) R+\pi R^{2}
$$

$$
2(R+r) L \cos \alpha
$$

## Collision rate

Fixed attitude

$$
\mathrm{A}(M \oplus(-S))=
$$

0

$$
a b \sqrt{-\cos \left(\theta_{a}+\theta_{b}\right) \cos \left(\theta_{a}-\theta_{b}\right)}+2\left(a \sin \theta_{a}+b \sin \theta_{b}\right) R+\pi R^{2}
$$

- 

$$
2(R+r) L \cos \alpha
$$

- 

$$
2\left(\frac{w}{\pi}+R\right) L \cos \alpha
$$

## Collision rate

Fixed attitude

$$
A(M \oplus(-S))=
$$

- 

$$
a b \sqrt{-\cos \left(\theta_{a}+\theta_{b}\right) \cos \left(\theta_{a}-\theta_{b}\right)}+2\left(a \sin \theta_{a}+b \sin \theta_{b}\right) R+\pi R^{2}
$$

$$
2(R+r) L \cos \alpha
$$

- 

$$
2\left(\frac{w}{\pi}+R\right) L \cos \alpha
$$

$$
\pi R_{\text {sail }}^{2} \cos \theta_{M}+4 R_{\text {sail }} E\left(\sin ^{2} \theta_{M}\right) R+\pi R^{2}
$$

## Collision rate

## Random attitude

$$
\overline{\mathrm{A}(M \oplus(-S))}=
$$

## Collision rate

## Random attitude

$$
\overline{\mathrm{A}(M \oplus(-S))}=
$$

$$
\frac{a b}{2}+\frac{\pi(a+b) R}{2}+\pi R^{2}
$$

## Collision rate

## Random attitude

$$
\overline{\mathrm{A}(M \oplus(-S))}=
$$

$\bullet$

$$
\frac{a b}{2}+\frac{\pi(a+b) R}{2}+\pi R^{2}
$$

$$
\frac{\pi R_{\text {sail }}^{2}}{2}+\frac{\pi^{2} R_{\text {sail }} R}{2}+\pi R^{2}
$$

## Collision probability

## Rectangle

$$
\int_{M \oplus(-S)} d^{2} r \rho(\vec{r}) \leq \int_{\text {parallelogram }} d^{2} r \rho(\vec{r})
$$



## Collision probability

## Rectangle

The affine transformation of a parallelogram into a rectangle transforms the Gaussian into another Gaussian.


## Collision probability

## Rectangle

This allows the use of Genz's algorithm.

http://sdg.aero.upm.es/index.php/online-apps/ gaussian-over-parallelogram

G gaussian over parallelogram G

## Collision probability

Tether



## Collision probability

Tether

$$
\begin{aligned}
& \frac{1}{4}\left\{\operatorname{erf}\left[\frac{D^{2} L / 2+x \sigma_{y}^{2} \cos \Lambda+y \sigma_{x}^{2} \sin \Lambda}{\sqrt{2} D \sigma_{x} \sigma_{y}}\right]\right. \\
& \left.+\operatorname{erf}\left[\frac{D^{2} L / 2-x \sigma_{y}^{2} \cos \Lambda-y \sigma_{x}^{2} \sin \Lambda}{\sqrt{2} D \sigma_{x} \sigma_{y}}\right]\right\} \\
& \left\{\operatorname{erf}\left[\frac{\Delta / 2+|y \cos \Lambda-x \sin \Lambda|}{\sqrt{2} D}\right]+\operatorname{erf}\left[\frac{\Delta / 2-|y \cos \Lambda-x \sin \Lambda|}{\sqrt{2} D}\right]\right\}
\end{aligned}
$$

where:

$$
D \equiv \sqrt{\sigma_{x}^{2} \sin ^{2} \Lambda+\sigma_{y}^{2} \cos ^{2} \Lambda}
$$

## Collision probability

## Round sail



## Numerics

$\Lambda=45^{\circ}$ and $90^{\circ} ; L=2000 \mathrm{~m} ; \Delta=7 \mathrm{~cm}, 30 \mathrm{~cm}, 2 \mathrm{~m}$, and 8 m . $x, y, \sigma_{x}, \sigma_{y}$.


## Numerics

Tether


## Tether

The contribution to the overall probability of collision of the end masses is almost always negligible compared to the contribution of the tether. The reason is that the perimeter of the tether, $p_{t}$, is about 1,000 longer than the perimeter of any of the end masses, $p_{m}$.

## Conclusions

- For a tether of length $2 R$ and diameter $d$ the area of its average projection is $\pi d R / 2$, while the area of the projection of the circumscribing sphere is $\pi R^{2}$. For a disk of radius $R$ and its circumscribing sphere the average projected areas are, respectively, $\pi R^{2} / 2$ and $\pi R^{2}$.


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- Thus for these two cases the ratios of the area of the average projection to the area of the projection of the circumscribing sphere are $d /(2 R)$ (in reality less than 0.01 ) and $1 / 2$, respectively.
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- Thus for these two cases the ratios of the area of the average projection to the area of the projection of the circumscribing sphere are $d /(2 R)$ (in reality less than 0.01 ) and $1 / 2$, respectively.
- No additional computational cost, since the formulae are all analytical except for the case of the collision probability of a rectangle, for which a very fast algorithm, available as an app, is provided.


## Conclusions

In general one may decompose a complex aircraft in various pieces, and separately compute the probability of collision for each. When one of the pieces is a solar panel then the formulae for the rectangle can be used.

