**"Gyroskopiya i Navigatsiya" №2, 2004**

**CONTENTS**

|  |  |  |
| --- | --- | --- |
| **A.M. Alechetchkine, P.N. Ivanov, V.I. Kokorine, A.I. Yanovski** | **The High-Precision Radio-Navigation System for the Sea Users** | **5** |
| In the report represented there are discussed the constructive principles and the technical characteristics of the phase radio-navigation system (RNS) "Krabik-BM", developed in 2000-2002 years by the associations KSTU with FGUP NPP "Radiosvyaz". The RNS is intended for high-precision automatic definition, indication and registering the position coordinates and motion elements of above-water objects, it works in the range of frequencies of 320-332 MHz and ensures the determination of coordinates error 0.5-3 m. In 2002, the prototype of RNS "Krabik-BM" passed official tests according to results of which there was accepted a solution about its series production by FGUP NPP "Radiosvyaz" of Krasnoyarsk. | |  |

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| --- | --- | --- |
| **Zixing Cai, Hangen He, A.V. Timofeev** | **Navigation and Control of Mobile Robots in Unknown Environment: a Survey** | **13** |
| Theories and Methods for navigation control of mobile robots in unknown environments including main contents and recent developments relative to navigation have been surveyed and analyzed. The main contents deal with the Architecture, Environment Modeling, Localization Methods, Path Planning, Motion Control, Fault Diagnosis and Recovery and so on. Some learning and self-adaptive theories and approaches relative to the mobile robot navigation have been investigated, especially the kernel-based reinforcement learning, evolution-based learning and multiple-instance learning have been attracted much attention in recent years. Several existing problems have been presented, some issues of the future research have also been proposed in this paper. | |  |

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| **M. Mittnacht, E. Gottzein, M. Hartrampf, A. Konrad, M. Vasilyev** | **Real-Time Test Environment for a Space-Borne Attitude and Orbit Determination System for Earth Artificial satellites** | **25** |
| In the recent past GPS receivers for space applications have been used in different areas. Orbit determination for different kinds of missions from LEO (Low Earth Orbit) to GEO (Geostationary Orbit) [6] have been explored and used. For LEO satellites the usage of GPS receivers is becoming a standard. Navigation satellite systems are not only used for real-time absolute orbit determination, but also for relative navigation between multiple vehicles, attitude determination, precise orbit determination and a growing number of other areas of interest. The so-called MosaicAODS [5] is a space-borne Attitude & Orbit Determination System developed at Astrium GmbH. It is based on the MosaicGNSS receiver [3], extended by a star sensor and an optional INS. In order to validate the functionality of the MosaicAODS and to ensure its proper functionality in space a modular real-time test environment has been developed, where single AODS modules as well as the full system can easily be tested. Additional to these tests, the system provides the capability to test precise and relative navigation using GPS signals for rendezvous maneuver, formation flying or spacecraft co-positioning. This paper outlines the AODS test environment and the GPS precise and relative navigation test environment. | |  |

|  |  |  |
| --- | --- | --- |
| **V.B. Kostousov, A.V. Kostousov, I.G. Onuchin** | **Simulation of Moving Objects Guidance by Radar Images** | **37** |
| Current paper is devoted to simulation of guidance process on basis of radio-locating images of scenes. Models of radio-locating images and their use for moving object navigational parameters reconstruction are considered. Suggested model of radio-locator is based on the well-known back ray tracing technique. This method is a general-purpose one, that is it could be used for any scene under arbitrary observation conditions. Besides it allows various hardware-based sensor improvements to be easily added to the model; radio-locating images (RLI) resolution increase methods implementation demonstrates this. Simplicity of algorithm parallelization it the other advantage of this technique. The primary drawback of the suggested method is high computational laboriousness of the RLI construction procedure. Radar sensor parameters which specify accuracy characteristics of the system are discussed in this paper. Special attention is paid to software simulation complex of radar navigation system. | |  |

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| **V.A. Udaloy, N.M. Ivanov, N.L. Sokolov, V.U. Pazdnikov** | **Some Peculiarities of Operative Okean-O Spacecraft Control** | **48** |
| During "Okean-O" control Main Operative Group of Control (GOGU) had to support the spacecraft attitude by changing solar array position during communication session. In this paper basic peculiarities of "Okean-O" control in condition of great atmosphere parameters changes and methodic of atmosphere parameters changes calculating are submitted; process of "Okean-O" control during one of the hardest geomagnetic storms on July, 15, 2000 is described. | |  |

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| --- | --- | --- |
| **I. Flinsenberg** | **Using Turn Restrictions for Faster Route Planning with Partitioned Road Networks** | **55** |
| We investigate the planning of optimum routes in large real-world road networks, by using a graph partitioning approach. Very specific for real-world road networks is the presence of turn restrictions. We consider the problem of planning optimum routes in partitioned graphs, where the original graph, and thus the created reduced graph, contains turn restrictions. We discuss the consequences of the presence of turn restrictions for the creation of reduced graphs. Then we create a new reduced graph based on the original graph partition. When constructing this new reduced graph, we use the presence of turn restrictions in the original graph to our advantage. We develop a new planning algorithm to plan with the new reduced graph and the original graph partition. We compare the number of function evaluations of this algorithm for the old and new reduced graph, for several planning criteria on several real-world road networks. We conclude that our algorithm performs significantly better for the new reduced graph than for the old one. Our algorithm applied to the old reduced graph is, in turn, faster than the generalized *A*\*-algorithm for unpartitioned graphs. | |  |

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| **V.E.Dzhashitov, V.M.Pankratov, Yu.K.Pylaev, A.G.Gubanov** | **Mathematical simulation of three-dimensional nonuniform nonstationary temperature fields for electronic boards and multifunctional programmable controllers of spacecraft orientation systems** | **68** |
| Is designed and is built methodical, mathematical, algorithmic and software for realization of computer simulation of non-steady thermal processes in electronic printed circuit cards and multifunction pioes, keeping them, (MP) of onboard control systems. On the basis of the fundamental heat transfer laws, the ratio (l)-(8) and algorithms permitting to calculate of non-steady temperature on volume basis of composite comppund object for each member (design points) with allowance for of all possible kinds of heat transfer are obtained. Is designed mathematical and software by the way of complexes of the programs "MFC" and "PLT". The thermal model MP with fuel units on electronic printed circuit cards (fig. 1) is constructed. The computer experiments with the help of a programmatic complex "MPC" are conducted, are obtained qualitative and quantitative assessments of parameters of non-steady thermal processes (fig. 2) and steadied temperature fields of electronic printed circuit cards MP (fig. 3). The guidelines on improvement of a temperature situation in the multifunction pio are developed. The mathematical modeling of thermal processes not only in MP, but also autonomous simulation of thermal processes in separate plates of industrial controllers with the help of a specialized programmatic complex "PLT" is conducted. Thus the thermal model of a printed circuit card of the industrial controller (fig. 4) is constructed and the calculations and visual rendition of non-steady temperature fields of plate (fig. 5) are conducted. | |  |

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| --- | --- | --- |
| **O.A.Stepanov, D.A.Koshaev** | **Universal MATLAB Programs for Investigating a Potential Accuracy and Sensitivity of Linear Nonstationary Filtering Algorithms** | **81** |
| The presented programs are intended for analyzing accuracy of nonstationary Kalman filtering algorithms and investigating sensitivity of such algorithms to the disagreement between the calculated and real models of the state vector and measurements. The algorithm is proposed for the program that investigates sensitivity and need no dummy entries for different state vector lengths of the real and calculated models. The possibility of using the program for problems with random dimension without reprogramming has come its merit. The programs are turned to the specific tasks with the help of the user-friendly graphical interface with the developed menu and setup system. Their considerable peculiarity is that data about the state vector and vector of measurements are inserted directly in the form of equations for the components of the state vector and vector of measurements, and all the necessary matrixes are formed by the program itself. The provision is made for special writers permitting to add, copy, delete and remove components of the state vector and vector of measurements with automatical correction of indexing of the corresponding vector components in all equations. In the program of potential accuracy analysis the optimal filter RMS error values are calculated, and in the program of sensitivity - the investigated filter errors or additional errors besides. At the same time the prescribed quantity of error realizations can be simulated. The results are presented in the form of graphics drawn in process of calculation which fragments can be viewed scaled-up. The developed program has already been used for applied tasks of navigation data processing. | |  |

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| --- | --- | --- |
| **Ya.I.Binder, G.I.Emeliantsev** | **Bearing drift estimation method for the strapdown inertial measurement unit in conditions of vehicle maneuvering** | **93** |
| An integrated system based on strapdown inertial measurement unit (SIMU) using angular velocity transducers (AVT) and GPS/GLONASS receivers is considered. The problem of estimation is examined for nonstationary components of SIMU gyro heading drifts when integrated system is operating in the observation mode on a mobile vehicle. The peculiarity of the offered solution is formation at vehicle maneuvering of additional measurements representing the difference between the geographical heading value and gyro azimuth value calculated on the base of position coordinates and vehicle speed. Simulation results justifying the efficiency of the offered solution are presented. | |  |

|  |  |  |
| --- | --- | --- |
| **M.B.Bogdanov, V.V.Saveliev** | **Influence of the angular velocity transducer non-identity on the accuracy of strapdown position control system** | **100** |
| The influence of distinction characteristics of rate sensors (which composes measuring block) on accuracy of strapdown orientation system to research in this article. | |  |

|  |  |  |
| --- | --- | --- |
| **V.N.Narver, V.D.Prihodko, V.I.Stotyka** | **Fiber optic angular pickup for the gradiometer sensor** | **106** |
| The angular pickup is considered for gradiometer sensor cross-beam turning. The results are presented for the theoretical and experimental research of the angular pickup prototype with the fiber optic elements making possible guaranty of the limiting measurement error not exceeding 0.35 arc.sec within the range of ±2 arc.min. and 1 arc.sec within the range of up to 1 deg. Fine reading channel is realized on the base of an amplitude mask installed in the focus of the objective lens, fiber optic element, laser emitter and photodetector. The test element by way of a mirror surface is organized on the cross-beam (being an inertial actuating medium). The light from the laser emitter comes to the lighting mask via optical fiber. The mask image is reduced by the test element to the surface of receiving multislot mask and through the fiber bundle to the photodetector. Prototype specifications are presented. | |  |

**International Public Association   
The Academy of Navigation and Motion Control  
*Official information***

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| --- | --- |
| The 70th anniversary from the birth of the RAS Academician V.G.Peshekhonov - the President of the Academy of Navigation and Motion Control | **111** |

**History Pages**

|  |  |  |
| --- | --- | --- |
| **S.S.Rivkin** | **To the history of preparing and giving a course Theory of Gyroscopic and Stabilizing Devices of the Ship Armament** | **114** |
| Considered are the main stages of preparing and giving a course in which main attention is paid to devices and systems for ship artillery and missile armament. The materials on base of which the course is prepared are analyzed. Training aids created in process of giving a course are briefly characterized. | |  |

**Information**

|  |  |
| --- | --- |
| Materials of the joint scientific session of the Navigation Systems and Their Sensors Section and the Saint Petersburg Section of Precise Gyroscopy of the RAS Scientific Council on the problems of motion control and navigation | **127** |

|  |  |
| --- | --- |
| Russian and international conferences, symposiums and exhibitions | **129** |