# **Telematics International Mission - TIM**

Alexander Kleinschrodt<sup>1</sup>, Iurii Motroniuk<sup>2</sup>, Anna Aumann<sup>2</sup>, Ilham Mammadov<sup>2</sup>, Maros Hladky<sup>1</sup>, Mohd Bilal<sup>1</sup>, Andreas Freimann<sup>1</sup>, Liu Minshi<sup>3</sup>, Jiang Lianxiang<sup>3</sup>, Francois Malan<sup>4</sup>, Hendrik Burger<sup>5</sup>, Giovanni Beltrame<sup>6</sup> and Klaus Schilling<sup>1,2</sup>

<sup>1</sup>University of Würzburg, Lehrstuhl für Informatik VII (Robotik und Telematik), Würzburg, Germany; <sup>2</sup>Zentrum für Telematik e. V., Würzburg, Germany; <sup>3</sup>Shandong Institute of Space Electronic Technology, Shandong, China; <sup>4</sup>Space Advisory Company, Somerset West, Cape Town, South Africa; <sup>5</sup>SCS Space, Somerset West, Cape Town, South Africa, and <sup>6</sup>Polytechnique Montreal, Montreal, Canada



## **Objectives**



## Visual Servoing

**Formation Control** 



#### Figure 1: TIM formation & tasks

- Create formation of cooperating nanosatellites for joint Earth observation.
- Establish large formation to provide increased coverage and shorter revisit times for monitoring dynamic events.
- Present solutions to cutting edge problems: 1) monitoring of height of ash clouds, 2) identification of sea vessels, 3) monitoring of thermal anomalies.
- Unify infrastructure from all partners for one joint mission.
- ► Modular design based on UNISEC.



Figure 2: UNISEC reference implementation

Figure 6: Example for a feature matching

- Satellites analyze area, process input, share data and provide input for attitude control to keep max. overlap of imaged areas.
- ► The method consists of three steps: (1) feature extraction, (2) description and (3) distributed matching.



Figure 7: Formation control for desired formation configuration

- Natural dynamics utilized for formation design.
- Projected circular orbit and in-track formation for Earth Observation.
- ► Traditional linear models for relative motion not sufficient here. Nonlinear control techniques need to be employed.



#### Satellite Design



trol

#### **Coordinated Attitude Control**

## Maximize overlapping area of



#### Communication

- Space Segment  $\triangleright$  UHF : Telemetry and low speed data transfer, ISL communication.
  - ▷ S-Band : high speed downlink.
  - ▷ OSIRIS : Experimental optical downlink.
- Ground Station Network



Figure 8: TIM communication concept

▷ Provides interface for heterogeneous software and hardware systems. ▷ Scheduling algorithms of available stations across the network.

### **Testing facilities**



images to ca. 80%.

► Stereo angle of ca. 10deg for photogrammetric measurements. ► Inter-satellite distances of ca. 100km.

Required pointing accuracy of ca. 1deg achieved by newly developed miniature reaction wheels (Wittenstein/ZfT Development: 20x20x20mm, 20g; 2 mNms Momentum Storage, 0.1 mNm max. torque).



Figure 4: Concept of Coordinated Attitude Con-



Figure 5: Reaction Wheels

Figure 9: Turntables at ZfT

# Simulation of Dynamic Observation. ► Geometries for Camera Testing. Sensor calibration.

# Acknowledgments

The authors thank all the collaborators for their contributions within the Telematics Earth Observation Mission – TOM, supported by the Bavarian Ministry of Economics and the RLS for the cooperation in TIM.



# https://www.rls-sciences.org