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CubeSat.

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Oscillations of the gravity-stabilized tethered space system exposed to an aerodynamic moment in low Earth near-circular orbits are examined. The emphasis is on the study of the dynamics of small tethered space systems based on a triple CubeSat. This approach is validated by a need for the preparation of a full-scale experiment with an electrodynamic tethered space system. It is demonstrated that an aerodynamic moment can affect significantly the dynamics of the tethered space systems under consideration and result in resonances in oscillations of the space tethered systems, which are perpendicular to the orbit plane. To attain the gravitational stabilization, it is necessary that the parameters of the tethered space system should be corresponded to the desired computational values of an atmospheric density in an assumed orbit of a mass-center motion. The simple analytical expressions for estimating an amplitude of oscillations of the tethered space system relative to the mass center are derived. The study results can be employed to choose the parameters of an experimental tethered space system and the orbit of its motion or to estimate the aerodynamic effects on oscillations of the tethered space system with the selected parameters

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[2 – 6].

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 $550 - 750 \times 10^3$;
 $m_{KT C} = 3$;
 $m_1 = 0,8$;
 m_2 ;
 $1 \leq m_1/m_2 \leq 45$ (. . .)
 $m_1 = m_2 = 1,1$;
 $m_2 \approx 48$;
 $m_1 \approx 2,152$) .
 $d_i (i=1, 2)$,
 $V_i = \frac{1}{12} \pi d_i^3 = \frac{m_i}{\rho_{KT C}}$, $i=1, 2$, $\frac{d_1}{d_2} = \sqrt[3]{\frac{m_1}{m_2}}$,
 $V_i -$;
 $\rho_{KTS} = \frac{m_{KT C}}{V_{KT C}} = \frac{3}{0,1 \cdot 0,1 \cdot 0,3} = 10^3$ / $^3 - \ll \gg$ ($V_{KT C}$)
 CubSat) .
 $d_1 = d_2 \approx 16$; $d_1 \approx 20$, $d_2 \approx 6$.
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 ,
 φ ,
 θ (.
) . [1]

$$\begin{cases} \ddot{\theta} + (\dot{\phi} + \omega_0)^2 \sin \theta \cos \theta = -3\omega_0^2 l \cos^2 \theta \sin \theta + \frac{a_1 \rho V^2}{A} \times \\ \times (\tilde{V} \sin \phi \sin \theta + \varepsilon_V \cos \theta \cos u) \left(\sigma_a + \sqrt{1 - (\tilde{V} \sin \phi \cos \theta - \varepsilon_V \sin \theta \cos u)^2} \right), \\ \ddot{\phi} \cos \theta - 2(\dot{\phi} + \omega_0) \dot{\theta} \sin \theta = -3\omega_0^2 l \cos \phi \sin \phi \cos \theta - \frac{a_1 \rho V^2}{A} \times \\ \times \tilde{V} \cos \phi \left(\sigma_a + \sqrt{1 - (\tilde{V} \sin \phi \cos \theta - \varepsilon_V \sin \theta \cos u)^2} \right), \end{cases} \quad (1)$$

$\omega_0 -$; $l = (A - C)/B -$.
 $(A, B, C -$.
 $)$; $a_0, a_1, \sigma_a = a_0/a_1 -$.
 $V = |\vec{V}|$, $\vec{V} -$; $\rho -$;
 $\tilde{V} = (\omega_0 R - \omega_3 R \cos i)/V -$.
 $\omega_3 -$.

$$; i - ; R = |\vec{R}|, \vec{R} -$$

$$(), \varepsilon_V = (\omega_3/\omega_0) \sin i - ; u -$$

$$([7, 8]), [9, 10]$$

$$\rho = b_0 + \sum_{n=1}^4 b_n \cos(n\tau + f_n),$$

$$b_0, b_n, f_n -$$

$$; \tau = \omega_0 t - [11],$$

$$l,$$

$$\varphi = \varphi_0 + \tilde{\varphi}(t), \theta = \theta_0 + \tilde{\theta}(t),$$

$$\varphi_0, \theta_0 -$$

$$; \tilde{\varphi}(t), \tilde{\theta}(t)$$

$$\varphi_0, \theta_0.$$

$$\varphi_0, \theta_0$$

$$(1),$$

$$\left\{ \begin{aligned} \frac{1}{2} \omega_0^2 \sin 2\theta_0 &= -\frac{3}{2} \omega_0^2 l \cos^2 \varphi_0 \sin 2\theta_0 + \\ &+ \frac{a_1}{A} \tilde{V} \sin \varphi_0 \sin \theta_0 \left(\sigma_a + \sqrt{1 - \tilde{V}^2 \sin^2 \varphi_0 \cos^2 \theta_0} \right) \frac{b_0 V^2}{2}, \\ 0 &= -\frac{3}{2} \omega_0^2 l \sin 2\varphi_0 \cos \theta_0 - \\ &- \frac{a_1}{A} \tilde{V} \cos \varphi_0 \left(\sigma_a + \sqrt{1 - \tilde{V}^2 \sin^2 \varphi_0 \cos^2 \theta_0} \right) \frac{b_0 V^2}{2}. \end{aligned} \right. \quad (2)$$

$$(2),$$

$$\theta_0 = 0.$$

$$(\varphi_0 \approx 0, \theta_0 \approx 0)$$

$$\theta_0 \neq 0$$

$$(2) \quad \theta_0 = 0 \quad 1 - \tilde{V}^2 \sin^2 \varphi_0 \approx \tilde{V}^2 \cos^2 \varphi_0 \quad (\varepsilon_V^2),$$

$$\sin \varphi_0 = (\sigma_a + \tilde{V} \cos \varphi_0) \tilde{V} s, \quad (3)$$

$$s = -\frac{a_1 b_0 R^2}{6IA}$$

$$\sigma_a = \frac{a_0}{a_1}$$

$$\tilde{V} = \frac{1 - (\omega_3/\omega_0) \cos i}{\sqrt{1 - 2(\omega_3/\omega_0) \cos i}}$$

s -

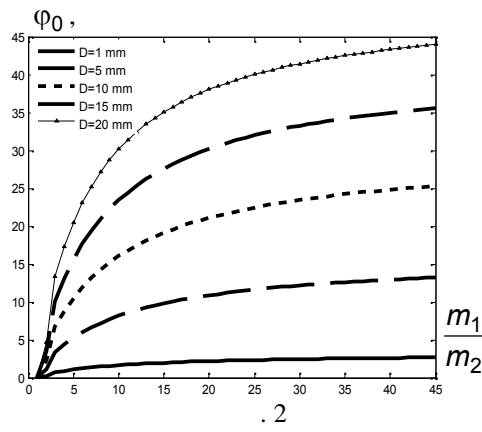
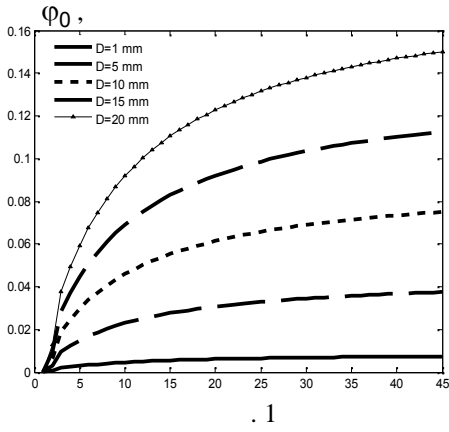
$$(\omega_3/\omega_0 < 0,07), \quad \tilde{V} \approx 0,005,$$

$$T_\infty = 1000, \quad T_r = 300, \quad \sigma_a = 0,18; \\ m_1/m_2 > 5, \quad \sigma_a = 0,08.$$

$$T_r = T_\infty = 1000, \quad [7, 12], \quad \sigma_a = 0,25.$$

$$b_0 R^2 \quad (F_0 = 75 \cdot 10^{-22} / ^2) \\ 0,4 / \quad 4,2 / , \\ F_0 = 250 \cdot 10^{-22} / ^2 \quad - \quad 8 / \quad 108 / . . . \\ 0,4 / \leq b_0 R^2 \leq 110 / .$$

$$(\dots .2), \quad (\dots .1), \quad \varphi_0$$



. 1, 2

φ_0

$T_\infty = 1000$

$T_r = 300$

(750 ,

$$F_0 = 75 \cdot 10^{-22} / \text{m}^2$$

(550 ,

$$F_0 = 250 \cdot 10^{-22} / \text{m}^2$$

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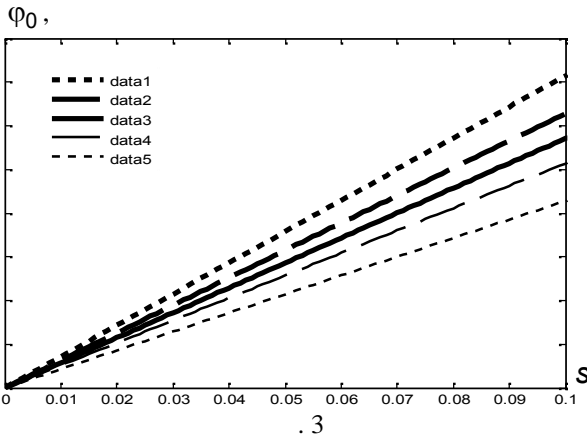
φ_0

$s < 0,1$,

φ_0

7,5° (. 3).

s



. 3

s

φ_0

s.

φ_0

(3)

0,25 %

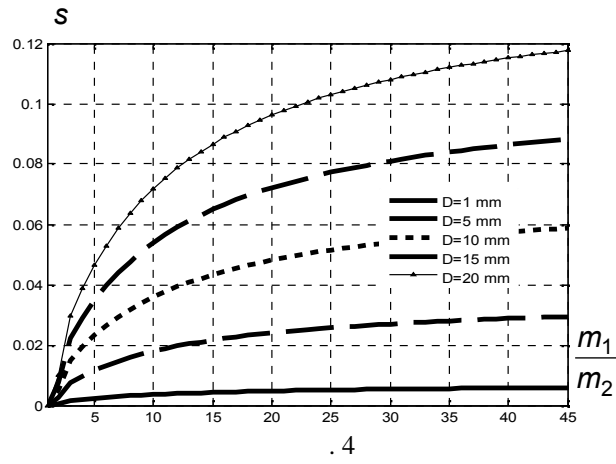
$$\varphi_0 = \arctg(s\tilde{V}^2) + \arcsin(s\sigma_a\tilde{V}) + 2\pi n, \quad n = 0, 1, 2, \dots$$

s

600

$$F_0 = 150 \cdot 10^{-22} / ^2,$$

« »



(3),

s phi_0

(1),

(1)

$$\varepsilon_V \cdot \varepsilon_V \tilde{\theta} \sim \varepsilon_V^2$$

$$\varphi_0, \quad \theta_0 = 0$$

$$1 - \tilde{V}^2 \sin^2 \varphi \approx \tilde{V}^2 \cos^2 \varphi,$$

$$\begin{cases} \ddot{\tilde{\theta}} + \omega_0^2 \tilde{\theta} = -3\omega_0^2 l \tilde{\theta} \cos^2 \varphi_0 + \frac{a_1 \sigma_a}{A} (\tilde{V} \sin \varphi_0 \tilde{\theta} + \varepsilon_V \cos u) q + \\ + \frac{a_1 \tilde{V} \varepsilon_V}{A} \cos u (\cos \varphi_0 - \tilde{\varphi} \sin \varphi_0) q + \frac{a_1 \tilde{V}^2}{A} \tilde{\theta} \sin \varphi_0 \cos \varphi_0 q, \\ \ddot{\tilde{\varphi}} = -3\omega_0^2 l (\sin \varphi_0 \cos \varphi_0 + \tilde{\varphi} \cos 2\varphi_0) - \frac{a_1 \tilde{V}}{A} \cos \varphi_0 (\sigma_a + \tilde{V} \cos \varphi_0) q + \\ + \frac{a_1 \tilde{V}}{A} \tilde{\varphi} \sin \varphi_0 (\sigma_a + 2\tilde{V} \cos \varphi_0) q. \end{cases} \quad (4)$$

phi_0

$$\tau = \omega_0 t, \quad (4)$$

$$\begin{cases} \tilde{\theta}'' + (k_\theta^2 + \delta_\theta \tilde{\rho}) \tilde{\theta} = -\varepsilon_V \cos u (1 + \tilde{\rho}) (c_1 - c_2 \tilde{\varphi}), \\ \tilde{\varphi}'' + (k_\varphi^2 + \delta_\varphi \tilde{\rho}) \tilde{\varphi} = d_\varphi \tilde{\rho}, \end{cases} \quad (5)$$

$$k_\theta^2 = 1 + 3l \cos^2 \varphi_0 + \delta_\theta, \quad \delta_\theta = d_\varphi \operatorname{tg} \varphi_0, \quad d_\varphi = 3ls \tilde{V} \cos \varphi_0 (\sigma_a + \tilde{V} \cos \varphi_0),$$

$$c_1 = \frac{d_\varphi}{\tilde{V} \cos \varphi_0}, \quad c_2 = 3ls \tilde{V} \sin \varphi_0, \quad k_\varphi^2 = 3l \cos 2\varphi_0 + \delta_\varphi,$$

$$\delta_\varphi = 3ls \tilde{V} \sin \varphi_0 (\sigma_a + 2\tilde{V} \cos \varphi_0), \quad \tilde{\rho} = \sum_{n=1}^4 \bar{b}_n \cos(n\tau + f_n).$$

(5)

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(3),

$$d_\varphi = 3l \cos \varphi_0 \sin \varphi_0,$$

$$\delta_\theta = 3l \sin^2 \varphi_0, \quad c_1 = 3 \frac{l}{\tilde{V}} \sin \varphi_0, \quad \delta_\varphi = 3l \sin^2 \varphi_0 + 3ls \tilde{V}^2 \sin \varphi_0 \cos \varphi_0,$$

$$k_\varphi^2 = 3l \cos^2 \varphi_0 + 3ls \tilde{V}^2 \sin \varphi_0 \cos \varphi_0, \quad k_\theta^2 = 1 + 3l, \quad (6)$$

..

) k_θ 2.

(.. [13]),

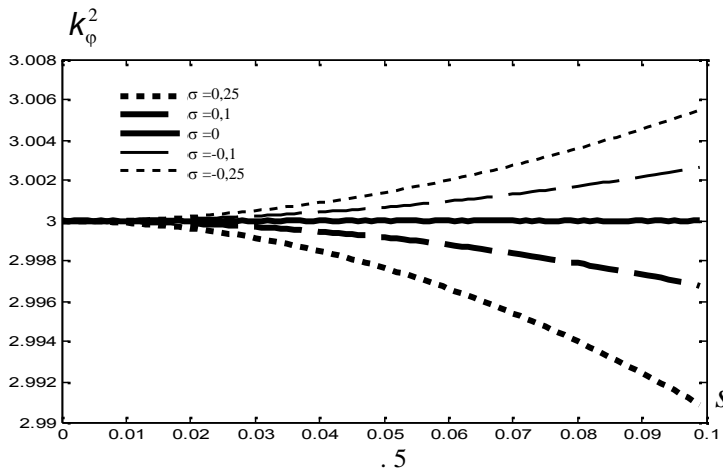
(.. [14, 15]).

φ_0

$$k_\varphi \approx \sqrt{3} \approx 1,73$$

(.5).

φ_0 (



(.. [16]),

$$\tilde{\varphi}^B = \sum_{n=1}^4 \frac{d_\varphi \bar{b}_n}{k_\varphi^2 - n^2} \cos(n\tau + f_n).$$

$\bar{b}_1 > \bar{b}_2 > \bar{b}_3$ ($\bar{b}_1 \leq 0,83; \bar{b}_2 \leq 0,23; \bar{b}_3 \leq 0,02$ [16]), $\varphi_0 = 0^\circ$ $k_\varphi^2 = 3$

$$A_\varphi \approx 3s \left(\frac{\bar{b}_1}{2} + \bar{b}_2 \right) (1 + \sigma_a). \quad (7)$$

φ_0 ($s < 0,1$)

14°.

(5),

$$\begin{aligned} \varepsilon_V \cos u(1 + \tilde{\rho})(c_1 + c_2 \tilde{\varphi}) = & \Phi(\tau) + \frac{1}{2} \varepsilon_V [(c_1 \bar{b}_1 + c_2 A_1) \cos(2\tau + u_0 + f_1) + \\ & + (c_1 \bar{b}_3 + c_2 A_3) \cos(2\tau - u_0 + f_3) + \frac{1}{2} (\bar{b}_1 A_2 + \bar{b}_2 A_1) \cos(2\tau - u_0 + f_1 + f_2) + \\ & + \frac{1}{2} \bar{b}_2 A_1 \cos(2\tau + u_0 + f_2 - f_1) + \frac{1}{2} (\bar{b}_3 A_2 + \bar{b}_2 A_3) \cos(2\tau + u_0 + f_3 - f_2)], \end{aligned} \quad (8)$$

$$A_n = d_\varphi \bar{b}_n / (k_\varphi^2 - n^2), \quad n = 1, 2, 3 -$$

, n ; $\Phi(\tau) -$

(5)

$2\tau.$

$2\tau.$

ε_V

$\sin i,$

$$y'' + a^2 y = A \cos(\omega \tau), \quad y -$$

; $a -$

A $\omega -$

($a = \omega$)

(.,

[17])

$$y = \frac{A}{2\omega} \sin(\omega\tau) \cdot \tau. \quad (8)$$

2τ,

$$A_{\theta_rez} \approx \frac{1}{2} \varepsilon_V c_1 \bar{b}_1 \cdot \frac{1}{2k_\theta} \approx \frac{3}{8} \varepsilon_V s \bar{b}_1 (1 + \sigma_a) \tau. \quad (9)$$

(,)

($\omega_3/\omega_0 < 0,07$).

$$\varepsilon_V = 0,07$$

$$s = 0,1 \quad \sigma_a = 0,25$$

$2,7 \cdot 10^{-3}$
1°

$$- 2,1083 \quad , \quad 0,0917 \quad (m_1/m_2 = 23),$$

$$. 4, \quad 10 \quad ($$

$$\varepsilon_V \approx 0,0107, \quad \bar{b}_1 \approx 0,6695, \quad s \approx 0,1005, \quad \sigma_a \approx 0,0761, \quad k_\varphi^2 \approx 2,9975,$$

$$\varphi_0 \approx 6,18^\circ, \quad A_\varphi \approx 9,5^\circ, \quad \dots \max(\varphi) \approx 15,7^\circ).$$

$$(\quad)$$

$$(1) \quad (4)$$

(. 6). ó

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$$(1) (4) \quad (. 7).$$

$$- 2 \quad , \quad 0,2 \quad (m_1/m_2 = 10)$$

$$. 4, ($$

$$s \approx 0,0359, \quad \sigma_a \approx 0,0761, \quad k_\varphi^2 \approx 2,9997, \quad \varphi_0 \approx 2,22^\circ,$$

$$A_\varphi \approx 3,4^\circ, \quad \dots \max(\varphi) \approx 5,66^\circ); N -$$

; 1 -

(1); 2 -

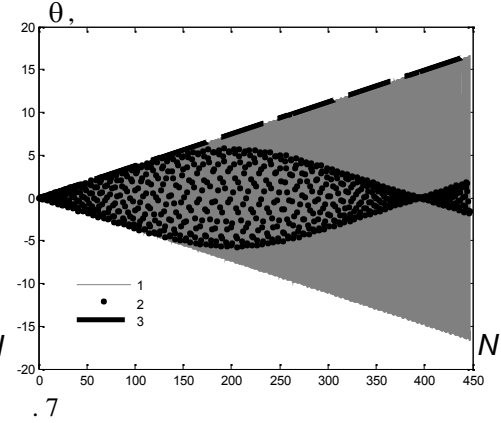
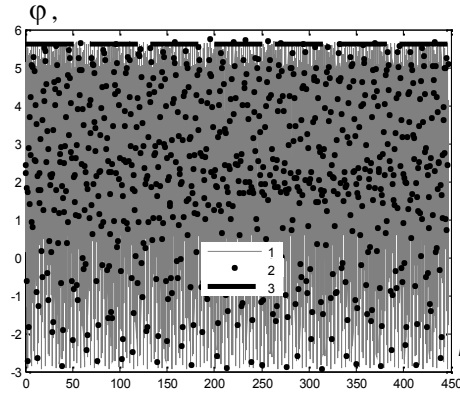
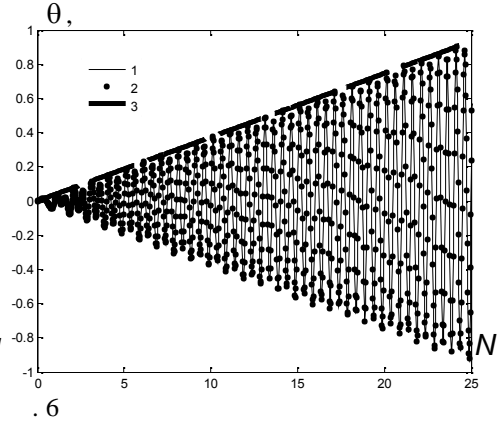
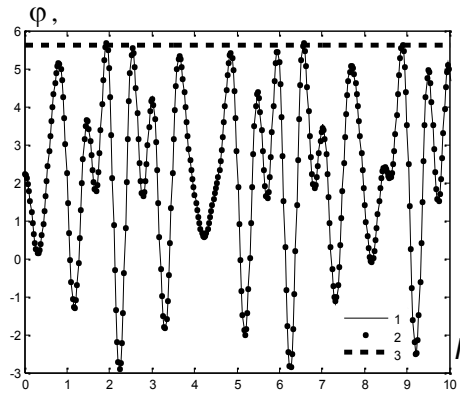
(4); 3 -

(7) (9)

$$T_r = 300 \quad , \quad T_\infty = 1000$$

($\sigma = 0$);

$$- \varphi(0) = \varphi_0, \quad \dot{\varphi}(0) = 0, \quad \theta(0) = 0, \quad \dot{\theta}(0) = 0.$$



$$\max(\varphi) = \varphi_0 + A_\varphi, \quad \varphi_0 \quad A_\varphi \quad (3)$$

$$(7) \quad \dot{\varphi} = 3^\circ \quad (9), \dots$$

$$\varepsilon_V, s, \bar{b}_1, \sigma_a \quad N$$

$$A_\theta = 1^\circ$$

$$N = \frac{8 \cdot A_\theta}{360 \cdot 3 \cdot \varepsilon_V s \bar{b}_1 (1 + \sigma_a)} = \frac{1}{135 \cdot \varepsilon_V s \bar{b}_1 (1 + \sigma_a)}$$

$$\left(\begin{array}{l} \varepsilon_V = 0,07, \quad s = 0,1, \quad \sigma_a = 0,25, \\ \bar{b}_1 = 0,83 \end{array} \right. \quad 1^\circ, \quad 1 ;$$

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2012–2016 ..

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