

Index

- acceleration
 - and Earth oblateness, 281–303
 - and eccentric longitude, 304–326
 - and epoch eccentric longitude, 202–224
 - and epoch mean longitude, 154–178
 - higher-order harmonics in low-thrust orbit transfer, 328–357
 - in terms of the eccentric longitude, 180–200, 319–326
 - in terms of the equinoctial elements, 261–265
 - and thrust, 269–274
- acceleration (continuous constant), in six-element formulation, 83–87, 100
- acceleration (lunar gravity perturbation), in Euler–Hill frame, 370–374
- acceleration (solar gravity perturbation), in Euler–Hill frame, 362–370
- acceleration (zonal harmonics perturbation), and Euler–Lagrange equations, 330–332
- adjoint differential equations
 - for direct transfer trajectory, 204–213
 - for equinoctial elements, 429–431
 - in terms of eccentric longitude, 306–318
- arrival location in six-element formulation, 88–92
- augmented state in fundamental classic analysis, 27–31
- averaging technique
 - and continuous constant acceleration orbit transfer, 92–100
 - and costate differential equations for the thrust-constrained case, 10–13
 - fundamental classic analysis, 3–4
 - and orbit transfer, 92–100
 - and SECKSPOT, 40
- B matrix
 - and partial derivatives, 237–242
 - and partial derivatives for true longitude, 255–259
- Battin, R. H., 329
- Betts, J. T., 227, 328
- Broucke, R. A., 41, 50, 237, 304, 328
- Bryson, A. E., 305
- canonical transformations in epoch mean longitude formulation, 162–168
- Cefola, P. J., 41, 50, 237, 304, 328
- de Pontécoulant’s lunar theory, 374–377
- departure location, 88–92
- Earth oblateness
 - and acceleration, 281–303
 - equinoctial orbit elements, 260–279
 - in fundamental classic analysis, 25–27
 - low-thrust orbit transfer, 282–294
- Edelbaum, T. N., 1, 2, 40, 45, 50, 100, 138, 304, 328
- electrons and total flux, 36
- epoch eccentric longitude formulation, 202–220
- epoch mean longitude formulation, 185
- equations of motion, 8–9
- equinoctial orbit elements
 - and Earth oblateness, 260–279
 - in Euler–Hill frame, 362–370
 - multipliers system and simulations for luni-solar gravity, 410–423
 - nonsingular, 243–255
 - optimal low-thrust rendezvous, 102–125
 - and partial derivatives in epoch eccentric longitude formulation, 220–224
 - in polar coordinates for trajectory optimization, 227–237
 - and SECKSPOT, 40–41
 - in six-element formulation, 66–83
 - summary of mechanics, 4–7
 - in terms of the eccentric longitude, 184–185
 - with variable bounded thrust, 140–143
- Euler–Hill derivatives
 - lunar gravity perturbations, 370–374
 - solar gravity perturbations, 362–370
- Euler–Lagrange differential equations
 - multipliers system and simulations for luni-solar gravity, 392–399
 - in optimal low-thrust rendezvous, 106–109
 - for the seven state variables, 120–122
 - in six-element formulation, 81–83
 - and thrust, 271–274

- for trajectory optimization based on epoch
 - eccentric longitude formulation, 210–213
 - with variable bounded thrust, 140
 - and zonal harmonics perturbation acceleration, 330–332
- Feistel, B. S., 329
- flux model
 - and minimum-time transfer from LEO to GEO, 35–39
 - and SECKSPOT, 27–31
- fundamental classic analysis
 - and averaging technique, 3–4
 - and averaging technique and costate differential equations for thrust-constrained case, 10–13
 - and Earth oblateness, 25–27
 - and flux model for SECKSPOT, 27–31
 - low-thrust orbit transfer, 1–3
 - minimum-time transfers from LEO to GEO, 35–39
 - and SECKSPOT thrust, panel orientation angles, and spacecraft body, 31–35
 - in zero roll and zero pitch and free yaw, 16–25
 - in zero roll and zero pitch and maximization of solar panel power output, 13–16
- GEO (geostationary Earth orbit)
 - with continuous constant acceleration, 83
 - equinoctial orbit elements in polar coordinates, 236–237
 - minimum-time transfers from LEO, 35–39
 - with optimized departure and arrival locations, 90–92
 - and thrust, 274–279
 - using averaging technique, 96–100
- gravity (luni-solar)
 - and dynamic system for trajectory optimization, 361–385
 - higher-order expansions in rotating frame, 424–446
 - higher-order expansions in rotating frame numerics, 446–457
 - multipliers system and simulations, 391–410
- Hallman, W., 377
- Hamiltonian
 - in the epoch mean longitude formulation, 160–162
 - multipliers system and simulations for luni-solar gravity, 392–399
 - in terms of the eccentric longitude, 185–188
 - for trajectory optimization based on epoch
 - eccentric longitude formulation, 209–210
 - and true longitude for trajectory optimization, 247–254
- harmonics (higher order)
 - and eccentric longitude, 332–345
 - in low-thrust orbit transfer, 328–357
 - within true longitude formulation, 345–352
- higher order in low-thrust orbit transfer
 - and luni-solar gravity, 377–385
 - and rotating frame, 358–359, 424–446
- Ho, Y.-C., 305
- Lagrange multipliers, 41, 250–254
- LEO (low Earth orbit)
 - with continuous constant acceleration, 83
 - equinoctial orbit elements in polar coordinates, 236–237
 - minimum-time transfers to GEO, 35–39
 - with optimized departure and arrival locations, 90–92
 - and thrust, 274–279
 - using averaging technique, 96–100
- longitude formulation
 - eccentric, 180–192, 304–326, 332–345
 - epoch eccentric, 202–220
 - epoch mean, 154–174
 - and higher-order harmonics, 345–352
 - as sixth state variable, 283–284
- low-thrust orbit transfer
 - acceleration, 328–357
 - and Earth oblateness, 282–294
 - and Edelbaum, 51–59
 - fundamental classic analysis, 1–3
 - and higher-order harmonics, 319–326
 - higher order in, 358–359, 377–385, 424–446
 - minimum-fuel time-fixed rendezvous, 113–122
 - using eccentric longitude formulation, 180–192
 - and variable bounded thrust, 135–153
- low-thrust power-limited vehicles, in SECKSPOT, 44–46
- low-thrust rendezvous
 - boundary conditions for, 168–173
 - and equinoctial orbit elements, 102–125
 - minimum fuel time-fixed, 113–122
 - in near-circular orbit, 145–153
 - using epoch mean longitude formulation, 154–174
- lunar gravity perturbations
 - in Euler–Hill frame, 370–374
 - partial derivatives of, 401–404
- lunar theory (de Pontécoulant's), 374–377
- Marec, J.-P., 305
- minimum-time transfer
 - around the oblate Earth, 265–269
 - in the epoch mean longitude formulation, 168–173
 - from fixed initial state with continuous constant acceleration, 83–87
 - in optimal low-thrust rendezvous, 106–109
 - with optimized departure and arrival locations, 88–92

- transversality condition for, 213–220
- motion
 - in the epoch mean longitude formulation, 155–160
 - equations of, 8–9
 - nonzero partial derivatives, 311–318
 - nonzero partial derivatives of, 174–178, 192–197
 - partial derivatives of, 126–133, 197–200, 220–224
 - six-state differential equations of, 103–106
 - in terms of the eccentric longitude, 181–188
- nominal attitude, 2
- nonsingular orbital elements, 243–255
- oblateness (Earth)
 - in fundamental classic analysis, 25–27
 - minimum-time transfer and, 281–303
 - in trajectory optimization in equinoctial coordinates, 260–279
- optimal control theory, 59–64
- orbit transfer
 - with continuous constant acceleration, 83–100
 - and higher-order expansion of luni-solar gravity, 431–446
 - minimum-time with oblateness, 281–303
 - multipliers system and simulations for luni-solar gravity, 404–410
 - using averaging technique, 92–100
- orbital mechanics (nonsingular equinoctial elements), 66–83
- panel orientation angle in SECKSPOT, 31–35
- partial derivatives
 - B matrix, 237–242, 255–259
 - equinoctial orbit elements, 220–224
 - lunar gravity perturbations, 401–404
 - motion, 126–133
 - multipliers system and simulations for luni-solar gravity, 410–423
 - nonzero partials, 174–178, 192–197
 - solar gravity perturbations, 399–401
- polar coordinates and trajectory optimization mechanics, 227–237
- protons and total flux, 36
- rendezvous (low-thrust)
 - boundary conditions for, 168–173
 - and equinoctial orbit elements, 102–125
 - minimum-fuel time-fixed, 113–122
 - in near-circular orbit, 145–153
 - using epoch mean longitude formulation, 154–174
- rotating frame
 - dynamic system for luni-solar gravity perturbation, 361–385
 - and higher-order expansion of luni-solar gravity, 424–446
 - and higher-order harmonics inertial accelerations, 358–359
 - multipliers system and simulations for luni-solar gravity, 391–410
- SECKSPOT
 - capabilities and limitations, 39–49
 - flux model for, 27–31
 - minimum-time transfers from LEO to GEO, 35–39
 - thrust angle and panel orientation angle and spacecraft body, 31–35
- second zonal perturbation effect and Earth oblateness, 282–294
- seven state variables dynamic equations, 117–122
- six-element formulation
 - algorithm, 64–65
 - and Edelbaum low-thrust orbit transfer problem, 51–59
 - and optimal control theory, 59–64
 - and orbit transfer with continuous constant acceleration, 83–100
 - and true longitude for trajectory optimization, 244–250
 - using nonsingular equinoctial orbit elements, 66–83
- solar gravity perturbations
 - in Euler–Hill frame, 362–370
 - partial derivatives of, 399–401
- solar panel power
 - minimum-time transfers from LEO to GEO, 35–39
 - in zero roll and pitch, 13–16
- system differential equations, 204–213, 429–431
- three sides of the spacecraft body (SECKSPOT), 31–35
- thrust angle (SECKSPOT), 31–35
- thrust magnitude
 - optimization, 136–145
 - in SECKSPOT, 44–46
- thrust orientation
 - acceleration, 269–274
 - and averaged state, 10–13
 - in terms of nonsingular equinoctial orbit elements, 68
 - variable bounded, 135–153
 - and zero roll and zero pitch, 13–16
- trajectory optimization
 - based on epoch eccentric longitude formulation, 202–220
 - and dynamic system of luni-solar gravity perturbations, 361–385
 - in Earth oblateness, 260–279

- and higher-order expansion of luni-solar gravity, 424–446
- in terms of eccentric longitude, 304–326
- using eccentric longitude formulation, 180–192
- using nonsingular orbital elements and true longitude, 243–255
- using nonsingular variational equations in polar coordinates, 227–237
- true longitude
 - B matrix, 255–259
 - and higher-order harmonics, 345–352
 - in trajectory optimization, 243–255
- velocity, 76–81
- Walker, M. J. H., 328
- yaw, 16–25
- zero pitch
 - in the epoch mean longitude formulation, 168–173
 - and maximization of solar panel power, 13–16
 - for trajectory optimization based on epoch eccentric longitude formulation, 213–220
 - and zero roll constraint, 16–25
- zero roll
 - in the epoch mean longitude formulation, 168–173
 - and free pitch and yaw, 16–25
 - and maximization of solar panel power, 13–16
 - for trajectory optimization based on epoch eccentric longitude formulation, 213–220