The Consultative Committee for Space Data Systems

Recommendation for Space Data System Standards

ATTITUDE DATA MESSAGES

RECOMMENDED STANDARD

CCSDS 504.0-P-1.8~~CCSDS 504.0-P-1.6~~

PROPOSED PINK BOOK

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This document has been approved for publication by the Management Council of the Consultative Committee for Space ~~–~~Data Systems (CCSDS) and represents the consensus technical agreement of the participating CCSDS Member Agencies. ~~–~~The procedure for review and authorization of CCSDS Recommendations is detailed in the *Procedures Manual for the Consultative Committee for Space Data Systems* (reference [H1]~~[H3]~~), and the record of Agency participation in the authorization of this document can be obtained from the CCSDS Secretariat at the address below.

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STATEMENT OF INTENT

The Consultative Committee for Space Data Systems (CCSDS) is an organization officially established by the management of its members. The Committee meets periodically to address data systems problems that are common to all participants, and to formulate sound technical solutions to these problems. Inasmuch as participation in the CCSDS is completely voluntary, the results of Committee actions are termed **Recommended Standards** and are not considered binding on any Agency.

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  - The anticipated date of initial operational capability.
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No later than five years from its date of issuance, this **Recommended Standard** will be reviewed by the CCSDS to determine whether it should: (1) remain in effect without change; (2) be changed to reflect the impact of new technologies, new requirements, or new directions; or (3) be retired or canceled.

In those instances when a new version of a **Recommended Standard** is issued, existing CCSDS-related member standards and implementations are not negated or deemed to be non-CCSDS compatible.– It is the responsibility of each member to determine when such standards or implementations are to be modified.— Each member is, however, strongly encouraged to direct planning for its new standards and implementations towards the later version of the Recommended Standard.

FOREWORD

This document is a Recommended Standard for Attitude Data Messages (ADMs) and has been prepared by the Consultative Committee for Space Data Systems (CCSDS). The set of attitude data messages described in this Recommended Standard is the baseline concept for attitude representation in data interchange applications that are cross-supported between Agencies of the CCSDS.

This Recommended Standard establishes a common framework and provides a common basis for the interchange of attitude data. It allows implementing organizations within each Agency to proceed coherently with the development of compatible derived standards for the flight and ground systems that are within their cognizance. Derived Agency standards may implement only a subset of the optional features allowed by the Recommended Standard and may incorporate features not addressed by this Recommended Standard.

Through the process of normal evolution, it is expected that expansion, deletion or modification to this document may occur. This Recommended Standard is therefore subject to CCSDS document management and change control procedures, as defined in the *Procedures Manual for the Consultative Committee for Space Data Systems*. Current versions of CCSDS documents are maintained at the CCSDS Web site:

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CONTENTS

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1 INTRODUCTION

1.1 PURPOSE

This Attitude Data Message (ADM) Recommended Standard specifies ~~two~~ three standard message formats for use in transferring spacecraft attitude information between space agencies and commercial or governmental spacecraft operators: the Attitude Parameter Message (APM), ~~and~~ the Attitude Ephemeris Message (AEM), and the Attitude Comprehensive Message (ACM). Such exchanges are used for:

- preflight planning for tracking or attitude estimation support;
- scheduling attitude and data processing support;
- carrying out attitude operations;
- performing attitude comparisons;
- carrying out attitude propagations and/or sensor predictions;
- testing to initialize sub-system simulators (communications, power, etc.).

This Recommended Standard includes sets of requirements and criteria that the message formats have been designed to meet. For exchanges where these requirements do not capture the needs of the participating agencies, another mechanism may be selected.

1.2 SCOPE AND APPLICABILITY

This document contains ~~two~~ three attitude data messages designed for applications involving data interchange in space data systems. The rationale behind the design of each message is described in ANNEX E and may help the application engineer to select a suitable message. ~~Definition of the attitude accuracy underlying a particular attitude message is outside of the scope of this Recommended Standard and should be specified via Interface Control Document (ICD) between data exchange participants.~~ Applicability information specific to each Attitude Data Message format appears in sections 3, ~~and~~ 4, and 5 as well as in annex subsection E3.

This Recommended Standard is applicable only to the message format and content, but not to its transmission. The transmission of the message between agencies is outside the scope of this document and should be specified in an ICD or by following a CCSDS standard on transmission.

Description of the message formats based on the use of the eXtensible Markup Language (XML) is available. Agencies should specify, via ICD, the ASCII file format to be exchanged (Keyword Value Notation [KVN] or XML).

1.3 CONVENTIONS AND DEFINITIONS

The following conventions apply throughout this Recommended Standard:

a) the words ‘shall’ and ‘must’ imply a binding and verifiable specification;

b) the word ‘should’ implies an optional, but desirable, specification;

c) the word ‘may’ implies an optional specification; and

d) the words ‘is’, ‘are’, and ‘will’ imply statements of fact.

~~d)~~ As in some attitude dynamics references, in this document the term “nutation” is used to mean the motion of the spin axis of a body about an inertial axis. In many other references this motion is called “precession”.

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1.4 STRUCTURE OF THIS DOCUMENT

Section 2 provides a brief overview of the CCSDS-recommended Attitude Data Message types, the Attitude Parameter Message (APM) and Attitude Ephemeris Message (AEM).

Section 3 provides details about the structure and content of the APM.

Section 4 provides details about the structure and content of the AEM.

Section 5 provides details about the structure and content of the ACM.

Section 6 provides details about constructing an ADM/XML instance.

Section 7 provides details about ADM KVN syntax.

Section 8 provides details about ADM XML syntax.

ANNEX A provides the Implementation Conformance Statement (ICS) requirements list.

ANNEX B provides a list of approved values for selected keywords in the ADM metadata sections.

ANNEX C details the conventions relative to ADM data used in this document.

ANNEX D gives the complete list of changes between ADM versions 1 and 2.

ANNEX E lists a set of requirements that were taken into consideration in the design of the APM, ~~and~~ AEM, and ACM, along with tables and discussion regarding the applicability of the ~~two~~ three message types to various attitude estimation tasks and functions.

ANNEX F lists a number of items that should be covered in ICDs prior to exchanging ADMs on a regular basis.~~–~~ There are several statements throughout the document that refer to the desirability or necessity of such a document; this annex lists all the suggested ICD items in a single place in the document.

ANNEX G is a list of abbreviations and acronyms applicable to the ADM.

ANNEX H is a list of informative references.

ANNEX I is relative to security, SANA, and patents considerations.

1.5 REFERENCES

The following documents contain provisions which, through reference in this text, constitute provisions of this Recommended Standard.~~–~~ At the time of publication, the editions indicated were valid.~~–~~ All documents are subject to revision, and users of this Recommended Standard are encouraged to investigate the possibility of applying the most recent editions of the documents indicated below.~~—~~ The CCSDS Secretariat maintains a register of currently valid CCSDS Recommended Standards.

[1] *Information Technology—8-Bit Single-Byte Coded Graphic Character Sets—Part 1: Latin Alphabet No. 1*.~~–~~ International Standard, ISO/IEC 8859-1:1998. Geneva:~~–~~ ISO, 1998.

[2] *United Nations Office of Outer Space Affairs satellite designator/index, searchable at*~~–~~ <http://www.unoosa.org/oosa/osoindex>

[3] *JPL Solar System Dynamics*.~~———~~ Pasadena, CA, USA: JPL. <http://ssd.jpl.nasa.gov>

[4] *Time Code Formats*.~~—~~ Recommendation for Space Data System Standards, CCSDS 301.0-B-4.~~—~~ Blue Book.~~—~~ Issue 4.~~—~~ Washington, D.C.: CCSDS, November 2010.

[5] *XML Specification for Navigation Data Messages*.~~–~~ The XML Specification for Navigation Data Messages Recommended Standard describes an integrated XML schema set that is suited to interagency exchanges of navigation data messages, CCSDS 505.0-B-1.~~–~~ Blue Book.~~–~~ Issue 1.~~–~~ Washington, D.C.: CCSDS, December 2010.

[6] *IEEE Standard for Binary Floating-Point Arithmetic*.~~–~~ IEEE Std 754-1985.~~–~~ New York: IEEE, 1985.

[7] ~~[7]~~ *Orbit Data Messages*. Recommended standard, CCSDS 502.0-B-2. Blue Book, Issue 2. Washington, D.C.: CCSDS. November 2009 (with Technical Corrigendum 1, May 2012)~~*Orbit Data Messages*. Recommendation for Space Data System Standards, CCSDS 502.0-B-2. Blue Book. Issue 2. Washington, D.C.: CCSDS, November 2009~~.

[8] Henry S. Thompson, et al., eds. *XML Schema Part 1: Structures*. 2nd ed. W3C Recommendation. N.p.: W3C, October 2004.

[9] Paul V. Biron and Ashok Malhotra, eds. *XML Schema Part 2: Datatypes*. 2nd ed. W3C Recommendation. N.p.: W3C, October 2004.

NOTE: A list of informative references can be found in ANNEX H.

2 OVERVIEW

2.1 ATTITUDE DATA MESSAGE TYPES

~~Two~~ Three CCSDS-recommended Attitude Data Messages (ADMs) are described in this Recommended Standard: the Attitude Parameter Message (APM), ~~and~~ the Attitude Ephemeris Message (AEM), and the Attitude Comprehensive Message (ACM).

The recommended attitude data messages are ASCII text format. While binary-based attitude data message formats are computer efficient and minimize overhead on uplinked/downlinked data streams, there are ground-segment applications for which an ASCII character-based message is more appropriate. For example, when files or data objects are created using text editors or word processors, ASCII character-based attitude data format representations are necessary. They are also useful in transferring text files between heterogeneous computing systems, because the ASCII character set is nearly universally used and is interpretable by all popular systems. In addition, direct human-readable downloads of text files or objects to displays or printers are possible without preprocessing. The penalty for this convenience is inefficiency.

As currently specified, an APM, ~~or~~ AEM, or ACM file is to represent attitude data for a single vehicle.

2.2 ATTITUDE PARAMETER MESSAGE (APM)

An APM specifies the attitude state of a single object at a specified epoch. This message is suited to inter-agency exchanges that (1) involve automated interaction and/or human interaction, and (2) do not require high-fidelity dynamic modeling (for high-fidelity dynamic modeling, see 2.3, Attitude Ephemeris Message and 2.4 Attitude Comprehensive Message).

The APM requires the use of a propagation technique to determine the attitude state at times different from the specified epoch, leading to a higher level of effort for software implementation than for the AEM. When inertial frames are specified, the APM is fully self-contained and no additional information is required to specify the attitude; if local orbital frames are specified, then an APM must be accompanied by a corresponding Orbit Parameter Message (reference [7] ~~[7]~~).

The APM allows for modeling of any number of finite maneuvers ~~and simple modeling of solar radiation pressure and atmospheric torque~~. Note that an Orbit Parameter Message (OPM) is needed for proper solar radiation pressure modeling. The attributes of the APM also make it suitable for applications such as exchanges by FAX or voice, or applications where the message is to be frequently interpreted by humans.

2.3 ATTITUDE EPHEMERIS MESSAGE (AEM)

An AEM specifies the attitude state of a single object at multiple epochs, contained within a specified time range. The AEM is suited to inter-agency exchanges that (1) involve automated interaction (e.g., computer-to-computer communication where frequent, fast, automated time interpretation and processing are required), and (2) require higher fidelity or higher precision dynamic modeling than is possible with the APM (e.g., flexible structures, more complex attitude movement, etc.).

The AEM allows for dynamic modeling of any number of torques (solar pressure, atmospheric torques, magnetics, etc.). The AEM requires the use of an interpolation technique to interpret the attitude state at times different from the tabular epochs.

The AEM is fully self-contained; no additional information is required when inertial reference frames are specified. If local orbital reference frames are specified, then an AEM must be used in conjunction with an Orbit Ephemeris Message (reference [7] ~~[7]~~).

2.4 ATTITUDE COMPREHENSIVE MESSAGE (ACM)

An ACM specifies the attitude state of a single object at multiple epochs, contained within a specified time range. The ACM aggregates and extends APM and AEM content in a single comprehensive hybrid message and offers the following capabilities:

- Optional rate data elements
- Optional spacecraft physical properties
- Optional covariance matrix
- Optional maneuver parameters
- Optional estimator information

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The ACM is well-suited for inter-agency exchanges that (1) involve automated interaction (e.g., computer-to-computer communication where frequent, fast, automated time interpretation and processing are required), and (2) require more detailed information such as estimator type, additional estimator states (e.g., gyro bias), sensor details, and covariance data.

The ACM is fully self-contained; no additional information is required when inertial reference frames are specified. If local orbital reference frames are specified, then an ACM must be used in conjunction with an Orbit Ephemeris Message (reference [7] ~~[7]~~).

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~~2.4~~2.5 EXCHANGE OF MULTIPLE MESSAGES

For a given object, multiple APM, ~~or~~ AEM, or ACM messages may be provided in a message exchange session to achieve attitude fidelity requirements. ~~—~~ If attitude information for multiple objects is to be exchanged, then multiple APM, ~~or~~ AEM, or ACM files must be used.

~~2.5~~2.6 DEFINITIONS

Definitions of time systems, reference frames, attitude estimation and prediction methods and models are provided in reference ~~–~~ [H2]~~[H4]~~.

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3 ATTITUDE PARAMETER MESSAGE (APM)

3.1 OVERVIEW

Attitude information may be exchanged between two participants by sending the attitude state (see reference [H2]~~[H4]~~) for a specified epoch using an Attitude Parameter Message (APM).~~–~~ The message recipient must have an attitude propagator available that is able to propagate the APM state to compute the estimated attitude at other desired epochs.~~–~~ For this propagation, additional ancillary information (spacecraft properties such as inertia matrix, torque vectors, reaction wheel data, other data from momentum exchange devices,~~—~~ maneuver planning data, if applicable~~,–~~) shall be included with the message.

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The use of the APM shall be applicable under the following conditions:

- an attitude propagator shall be available at the receiver's location;
- the receiver's modeling of satellite attitude dynamics, atmospheric torque, other internal and external torques (e.g., magnetic, gravitational, etc.), thrust maneuvers, and attitude control (see reference [H2]~~[H4]~~) must fulfill accuracy requirements established via an ICD between the agencies.

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The APM shall be a text file consisting of attitude data for a single object.~~– It shall be easily readable by both humans and computers.~~

The APM file naming scheme ~~shall~~ should be agreed to on a case-by-case basis between the participating agencies, and should be documented in an Interface Control Document (ICD).~~–~~ The method of exchanging APMs shall be decided on a case-by-case basis by the participating agencies and documented in an ICD.

3.2 APM CONTENT

3.2.1 GENERAL

The APM shall be represented as a combination of the following:

a) a header;

b) metadata (data about the data);

c) optional comments (explanatory information); and

d) data.

3.2.2 APM HEADER

The header shall provide a CCSDS Attitude Data Message version number that identifies the format version; this is included to anticipate future changes. The version keyword shall be CCSDS_APM_VERS and the value shall have the form of ‘x.y’, where ‘y’ shall be incremented for corrections and minor changes, and ‘x’ shall be incremented for major changes. Version 1.0 shall be reserved for the initial version accepted by the CCSDS as an official Recommended Standard (‘Blue Book’). Testing shall be conducted using APM version numbers less than 1.0 (e.g., 0.x). Participating agencies should specify in the ICD the specific APM version numbers they will support.

The header shall include the CREATION_DATE keyword with the value set to the Coordinated Universal Time (UTC) when the file was created, formatted according to reference [4]. A description of APM header keywords and values is provided in table 3-1.

The first header line shall be the first non-blank line in the file.

~~3.2.2~~

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Table 3-1~~3-1~~ specifies for each header item:

a) the keyword to be used;

b) a short description of the item;

c) whether the values are normative (N) values or just examples (E);

d) values (either the list of all normative values or examples);

e) whether the item is mandatory or optional.

Only those keywords shown in table 3-1~~3-1~~ shall be used in an APM header.

Table 3-1:~~–~~ APM Header

Keyword	Description	N/E	Values	Mandatory
`CCSDS_APM_VERS`	Format version in the form of ‘x.y’, where ‘y’ is incremented for corrections and minor changes, and ‘x’ is incremented for major changes.	N	`2.0`	Yes
`COMMENT`	Comments (allowed at the beginning of the APM Header after the APM version number). Each comment line shall begin with this keyword.	E	`This is a comment`	No
`CREATION_DATE`	File creation date/time in UTC. For format specification, see 7.7. ~~one of the following formats:~~ ~~YYYY-MM-DDThh:mm:ss[.d→d] or~~ ~~YYYY-DDDThh:mm:ss[.d→d]~~ ~~where ‘YYYY’ is the year, ‘MM’ is the two-digit month, ‘DD’ is the two-digit day, ‘DDD’ is the three-digit day of year, ‘T’ is constant, ‘hh:mm:ss[.d→d]’ is the UTC time in hours, minutes, seconds, and optional fractional seconds. As many ‘d’ characters to the right of the period as required may be used to obtain the required precision. All fields require leading zeros.~~	E	`2001-11-06T11:17:33` `2001-101T11:17:33`	Yes

ORIGINATOR	Creating agency. The value for the "ORIGINATOR" keyword ~~"should" come from the SANA Registry~~should come from the 'Abbreviation' column in the 'Organizations' registry of the SANA Registry (https://sanaregistry.org/r/organizations).~~.~~	E	CNES ESOC GSFC GSOC JPL JAXA Other agency	Yes
MESSAGE_ID	ID that uniquely identifies a message from a given originator.~~–~~ The format and content of the message identifier value are at the discretion of the originator.	E ~~2011137 19185 ABC-12_34~~	201113719185 ABC-12_34~~No~~	No~~MESSAGE_ID~~

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3.2.3 APM METADATA

Table 3-2~~3-2~~ specifies for each metadata item:

a) the keyword to be used;

b) a short description of the item;

c) whether the values are normative (N) values or just examples (E);

d) values (either the list of all normative values or examples);

e) whether the item is mandatory or optional.

Only those keywords shown in table 3-2~~3-2~~ shall be used in APM metadata.~~–~~ For some keywords (OBJECT_NAME, OBJECT_ID, CENTER_NAME) there are no definitive lists of authorized values maintained by a control authority; the references listed in 1.5 and annex H are the best known sources for authorized values to date.

Table 3-2:~~–~~ APM Metadata

Keyword	Description	N/E	Values	Mandatory
COMMENT	Comments (allowed only at the beginning of the APM Metadata before OBJECT_NAME). Each comment line shall begin with this keyword.	E	This is a comment	No
OBJECT_NAME	Spacecraft name of the object corresponding to the attitude data to be given.~~–~~ There is no CCSDS-based restriction on the value for this keyword, but it is recommended to use names ~~international designators~~ from the UN Office of Outer Space Affairs (Ref. [2]).	E	EUTELSAT W1 MARS PATHFINDER	Yes
OBJECT_ID	Spacecraft identifier of the object corresponding to the attitude data to be given.~~–~~ While there is no CCSDS-based restriction on the value for this keyword, it is recommended to use international designators ~~names~~ from the UN Office of Outer Space Affairs (Ref. [2]).	E	2000-052A	Yes

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`CENTER_NAME`	Origin of reference frame, which may be a natural solar system body (planets, asteroids, comets, and natural satellites), including any planet barycenter or the solar system barycenter, or another spacecraft (in this the value for 'CENTER_NAME' is subject to the same rules as for 'OBJECT_NAME').~~–~~ There is no CCSDS-based restriction on the value for this keyword, but for natural bodies it is recommended to use names from the NASA/JPL Solar System Dynamics Group (~~r~~Ref.~~erence~~ [3]~~[3]~~).	E	EARTH EARTH BARYCENTER MOON	No
`TIME_SYSTEM`	Time system used for attitude and maneuver data (also see table 3-3~~3-3~~).~~–~~ The full set of allowed values is enumerated in annex B, with an excerpt provided in the 'Normative Values/Examples' column.~~–~~ Explanations of these time systems can be found in *Navigation Definitions and Conventions* (~~reference~~ Ref. [H2]~~[H4]~~).	E	UTC TAI	Yes

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3.2.4 APM DATA

Table 3-3~~3-3~~ provides an overview of the six logical blocks in the APM Data section (attitude quaternion, attitude Euler angles, angular velocity data, spin data, ~~angular velocity data,~~ spacecraft inertia parameters, maneuver parameters), and specifies for each data item:

a) the keyword to be used;

b) a short description of the item;

c) whether the values are normative (N) values or just examples (E);

d) values (either the list of all normative values or examples);

e) whether the item is mandatory or optional.

Only those keywords shown in table 3-3~~3-3~~ shall be used in APM data.~~—~~ Some remarks concerning the keywords in table 3-3~~3-3~~ appear immediately after the table.

~~There~~ The APM message shall contain at least ~~be as many~~one logical block~~s as necessary~~.

Any particular type of block may be repeated several times.

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Table 3-3:~~–~~ APM Data

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Keyword	Description	N/E	Values / units	Mandatory
`COMMENT`	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
`EPOCH`	Epoch of the attitude elements ~~&~~ and optional logical blocks.	E	`2001-11-06T11:17:33`	Yes

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Keyword	Description	N/E	Values / units	Mandatory
Block: Attitude Quaternion *All mandatory elements are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~COMMENT~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
QUAT_START	Indicator of start of data block	n/a	n/a	Yes
COMMENT	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
REF_FRAME_A	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~The full set of values is enumerated in annex B. For a definition of these various frames, the reader is directed to reference [H4].~~	E	ICRF INSTRUMENT_A	Yes
REF_FRAME_B	Name of the reference frame that defines the end point of the transformation. The full set of values is enumerated in annex B.~~–~~Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~For a definition of these various frames, the reader is directed to *Navigation Definitions and Conventions* (reference [H4]).~~	E	SC_BODY_1 STARTRACKER	Yes
Q1	e_1 * sin(θ/2) θ = rotation angle, e1 = 1st component of rotation axis	n/a	n/a	Yes
Q2	e_2 * sin(θ/2) θ = rotation angle, e2 = 2nd component of rotation axis	n/a	n/a	Yes
Q3	e_3 * sin(θ/2) θ = rotation angle, e3 = 3rd component of rotation axis	n/a	n/a	Yes
QC	cos(θ/2) θ = rotation angle	n/a	n/a	Yes
Q1_DOT	Derivative of Q_1	n/a	1/s	No
Q2_DOT	Derivative of Q_2	n/a	1/s	No
Q3_DOT	Derivative of Q_3	n/a	1/s	No
QC_DOT	Derivative of Q_C	n/a	1/s	No
QUAT_STOP	Indicator of end of data block	n/a	n/a	Yes
Block: Euler angle elements *All mandatory elements of the logical block are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~COMMENT~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
EULER_START	Indicator of start of data block	n/a	n/a	Yes
COMMENT	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No

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Keyword	Description	N/E	Values / units	Mandatory
REF_FRAME_A	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~Name of the reference frame that defines the starting point of the transformation. The full set of values is enumerated in annex B. For a definition of these various frames, the reader is directed to reference [H4].~~	E	SC_BODY_1 STARTRACKER_1	Yes
REF_FRAME_B	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~Name of the reference frame that defines the end point of the transformation. The full set of values is enumerated in annex B.~~	E	LVLH SC_BODY_1	Yes
EULER_ROT_SEQ	Rotation sequence that defines the REF_FRAME_A to REF_FRAME_B transformation.~~–~~ The order of the transformation is from left to right, where the leftmost letter represents the rotation axis of the first rotation.	E	XYZ ZXZ	Yes
ANGLE_1	Angle of the first rotation	n/a	deg	Yes
ANGLE_2	Angle of the second rotation	n/a	deg	Yes
ANGLE_3	Angle of the third rotation	n/a	deg	Yes
ANGLE_1_DOT	Time derivative of angle of the first rotation	n/a	deg/s	No
ANGLE_2_DOT	Time derivative of angle of the second rotation	n/a	deg/s	No
ANGLE_3_DOT	Time derivative of angle of the third rotation	n/a	deg/s	No
EULER_STOP	Indicator of end of data block	n/a	n/a	Yes
Block:~~–~~ angular velocity vector *All mandatory elements are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~COMMENT~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
ANGVEL_START	Indicator of start of data block	n/a	n/a	Yes
COMMENT	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
~~DATA_TYPE~~	~~Type of data~~	~~N~~	~~ANGVEL~~	~~Yes~~
REF_FRAME_A	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~Name of the reference frame that defines the starting point of the transformation. The full set of values is enumerated in annex B. For a definition of these various frames, the reader is directed to reference [H4].~~	E	SC_BODY_1 ICRF	Yes
REF_FRAME_B	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~Name of the reference frame that defines the end point of the transformation. The full set of values is enumerated in annex B.~~	E	ICRF INSTRUMENT_A	Yes

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Keyword	Description	N/E	Values / units	Mandatory
`ANGVEL_FRAME`	Reference frame in which the components of the angular velocity vector are given.	N	REF_FRAME_A REF_FRAME_B	Yes
`ANGVEL_X`	Component of the angular velocity vector on the X axis	n/a	deg/s	Yes
`ANGVEL_Y`	Component of the angular velocity vector on the Y axis	n/a	deg/s	Yes
`ANGVEL_Z`	Component of the angular velocity vector on the Z axis	n/a	deg/s	Yes
`ANGVEL_STOP`	Indicator of end of data block	n/a	n/a	Yes
Block: Spin *All mandatory elements are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~`COMMENT`~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
`SPIN_START`	Indicator of start of data block	n/a	n/a	Yes
`COMMENT`	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
`REF_FRAME_A`	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD. ~~The name of the reference frame that defines the starting point of the transformation. The full set of values is enumerated in annex B. For a definition of these various frames, the reader is directed to reference [H4].~~	E	SC_BODY_1 ICRF	Yes
`REF_FRAME_B`	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD.~~The name of the reference frame that defines the end point of the transformation. The full set of values is enumerated in annex B.~~	E	ICRF SC_BODY_1	Yes
`SPIN_ALPHA`	Right ascension of spin axis vector	n/a	deg	Yes
`SPIN_DELTA`	Declination of the spin axis vector	n/a	deg	Yes
`SPIN_ANGLE`	Phase of the satellite about the spin axis	n/a	deg	Yes
`SPIN_ANGLE_VEL`	Angular velocity of satellite around spin axis	n/a	deg/s	Yes
`NUTATION`	Nutation angle of spin axis	n/a	deg	Yes
`NUTATION_PER`	Body nutation period of the spin axis	n/a	s	Yes
`NUTATION_PHASE`	Inertial nutation phase	n/a	deg	Yes
`SPIN_STOP`	Indicator of end of data block	n/a	n/a	Yes
Block: Inertia *All mandatory elements are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~`COMMENT`~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
`INERTIA_START`	Indicator of start of data block	n/a	n/a	Yes
`COMMENT`	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
`INERTIA_REF_FRAME`	Coordinate system for the inertia tensor. Allowed values for this keyword are enumerated in annex B.	E	SC_BODY_1	Yes

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Keyword	Description	N/E	Values / units	Mandatory
`IXX`	Moment of Inertia about the X-axis	n/a	kg*m**2	Yes
`IYY`	Moment of Inertia about the Y-axis	n/a	kg*m**2	Yes
`IZZ`	Moment of Inertia about the Z-axis	n/a	kg*m**2	Yes
`IXY`	Inertia Cross Product of the X ~~&~~ and Y axes	n/a	kg*m**2	Yes
`IXZ`	Inertia Cross Product of the X ~~&~~ and Z axes	n/a	kg*m**2	Yes
`IYZ`	Inertia Cross Product of the Y ~~&~~ and Z axes	n/a	kg*m**2	Yes
`INERTIA_STOP`	Indicator of end of data block	n/a	n/a	Yes
Block: Maneuver Parameters *All ~~obligatory~~ mandatory elements are to be provided if the block is present.* *See ANNEX C for conventions and further detail.*				
~~COMMENT~~	~~One or more comment line(s). Each comment line shall begin with this keyword.~~	~~E~~	~~This is a comment~~	~~No~~
`MANEUVER_START`	Indicator of start of data block	n/a	n/a	Yes
`COMMENT`	One or more comment line(s). Each comment line shall begin with this keyword.	E	This is a comment	No
`MAN_EPOCH_START`	Epoch of start of maneuver	n/a	n/a	Yes
`MAN_DURATION`	Maneuver duration	n/a	s	Yes
`MAN_REF_FRAME`	Coordinate system for the torque vector. Allowed values for this keyword are enumerated in annex B.	n/a	n/a	Yes
`MAN_TOR_X`	1st component of the torque vector	n/a	N*m	Yes
`MAN_TOR_Y`	2nd component of the torque vector	n/a	N*m	Yes
`MAN_TOR_Z`	3rd component of the torque vector	n/a	N*m	Yes
`MANEUVER_STOP`	Indicator of end of data block	n/a	n/a	Yes

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3.2.5 REMARKS

3.2.5.1 DATA FORMAT

See ‘CREATION_DATE’ in table 3-1~~3-1~~ or see reference [4]~~[4]~~ for examples of how to format the EPOCH and MAN_EPOCH_START. Note that any epoch specified denotes a spacecraft event time.

In specifying the EPOCH of the message, care must be taken if UTC is used as the TIME_SYSTEM. If an APM message reports attitude during a time of leap seconds, the system making use of the message should be able to recognize 60 as a valid value for the seconds (e.g., 200x-xx-xxT23:59:58.000 .. 200x-xx-xxT23:59:59.000 .. 200x-xx-xxT23:59:60.000 .. 200x-xx-xxT00:00:00.000)

3.2.5.2 GENERAL

It may become necessary to utilize particular orbit information to process Euler angle elements or a local orbit frame (e.g., LVLH, QSW) properly. An approach to this is to add a ‘COMMENT’ block specifying a particular OPM message to use in conjunction with a particular APM.

Specification of Euler angle rotations around only one or two axes may be handled by entering the appropriate sequence for the desired one or two axis rotation and freely choosing the final axis of rotation and giving a value of zero for the rotation angle.

3.2.6 APM KEYWORD SET

~~The header shall provide a CCSDS Attitude Data Message version number that identifies the format version; this is included to anticipate future changes. The version keyword shall be CCSDS_APM_VERS and the value shall have the form of 'x.y', where 'y' shall be incremented for corrections and minor changes, and 'x' shall be incremented for major changes. Version 1.0 shall be reserved for the initial version accepted by the CCSDS as an official Recommended Standard ('Blue Book'). Testing shall be conducted using APM version numbers less than 1.0 (e.g., 0.x). Participating agencies should specify in the ICD the specific APM version numbers they will support.~~

~~The header shall include the CREATION_DATE keyword with the value set to the Coordinated Universal Time (UTC) when the file was created, formatted according to reference [4]. A description of APM header keywords and values is provided in table 3-1.~~

~~The first header line must be the first non-blank line in the file.~~

Only those keywords shown in tables 3-1~~3-1~~, 3-2~~3-2~~, and 3-3~~3-3~~ shall be used in an APM. Some keywords represent ~~obligatory~~ mandatory items and some are optional.~~ ~~ KVN assignments representing optional items may be omitted.

3.3 APM EXAMPLES

Figures 3-1~~3-1~~ through 3-3~~3-3~~ are examples of Attitude Parameter Messages.

```
CCSDS_APM_VERS = ~~1~~2.0
CREATION_DATE  = 2003-09-30T19:23:57
ORIGINATOR     = GSFC


COMMENT           GEOCENTRIC, CARTESIAN, EARTH FIXED
COMMENT           OBJECT_ID:  1997-009A
COMMENT $ITIM  = 1997 NOV 21 22:26:18.40000000, $ original launch time
OBJECT_NAME    = TRMM
OBJECT_ID      = 1997-009A
CENTER_NAME    = EARTH
TIME_SYSTEM    = UTC

COMMENT           Current attitude for orbit 335
COMMENT           Attitude state quaternion
COMMENT           Accuracy of this attitude is 0.02 deg RSS.

EPOCH             = 2003-09-30T14:28:15.1172

QUAT_START
REF_FRAME_A    = SC_BODY_1
REF_FRAME_B    = ITRF-97

Q1               = 0.00005
Q2               = 0.87543
Q3               = 0.40949
QC               = 0.25678
QUAT_STOP
```

Figure 3-1: APM File containing quaternion

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```
CCSDS_APM_VERS   = ~~1~~2.0
CREATION_DATE    = 2006-03-13T13:13:33
ORIGINATOR       = GSFC

OBJECT_NAME      = GOES-P
OBJECT_ID        = 2006-003A
CENTER_NAME      = EARTH
TIME_SYSTEM      = UTC
COMMENT            GEOSYNCHRONOUS, CARTESIAN, EARTH FIXED

COMMENT OBJECT_ID: 2006-003A
COMMENT $ITIM  = 2006 FEB 5 03:23:45.60000000, $ original launch time
COMMENT            Attitude given by Euler angles

EPOCH              = 2006-03-12T09:56:39.4987

~~COMMENT            Euler angles~~
EULER_START
COMMENT            Euler angles
~~DATA_TYPE        = SC_BODY_1~~
REF_FRAME_A      = EULER
REF_FRAME_B      = ITRF-97
EULER_ROT_SEQ    = YXY

ANGLE_1          = -26.78 [deg]
ANGLE_2          = 46.26 [deg]
ANGLE_3          = 144.10 [deg]
EULER_STOP
```

Figure 3-2:~~–~~ APM File Example with Euler Angles

```
CCSDS_APM_VERS    = ~~1~~2.0
CREATION_DATE     = 2004-02-14T19:23:57
ORIGINATOR        = JPL

OBJECT_NAME       = MARS SPIRIT
OBJECT_ID         = 2004-003A
CENTER_NAME       = EARTH
TIME_SYSTEM       = UTC
COMMENT             GEOCENTRIC, CARTESIAN, EARTH FIXED

COMMENT OBJECT_ID: 2004-003
COMMENT $ITIM = 2004 JAN 14 22:26:18.400000, $ original launch time 14:36

COMMENT             Generated by JPL
COMMENT             Current attitude for orbit 20 and attitude maneuver
COMMENT             planning data.

EPOCH               = 2004-02-14T14:28:15.1172

~~COMMENT                Attitude state quaternion~~
QUAT_START
COMMENT             Attitude state quaternion (ref frame = ITRF-97)
REF_FRAME_A       = ITRF-97 ~~INSTRUMENT_A~~
REF_FRAME_B       = INSTRUMENT_A ~~ITRF-97~~

Q1                  = 0.03123
Q2                  = 0.78543
Q3                  = 0.39158
QC                  = 0.47832
~~DATA~~QUAT_STOP

QUAT_START
COMMENT      Attitude state quaternion (ref frame = ICRF)
REF_FRAME_A    = ICRF
REF_FRAME_B    = INSTRUMENT_A

Q1        = 0.02478
Q2        = 0.78576
Q3        = 0.39552
QC        = 0.47491
QUAT_STOP

~~COMMENT                Spacecraft Parameters~~
~~DATA~~INERTIA_START
COMMENT             Spacecraft Inertia Parameters
~~DATA_TYPE          = INERTIA~~
IXX                 = 6080.0    [kg*m**2]
IYY                 = 5245.5    [kg*m**2]
IZZ                 = 8067.3    [kg*m**2]
IXY                 = -135.9    [kg*m**2]
IXZ                 = 89.3       [kg*m**2]
IYZ                 = -90.7      [kg*m**2]
INERTIA~~QUAT~~_STOP

~~COMMENT                Data follows for 1 planned maneuver.~~

~~COMMENT                First attitude maneuver for: MARS SPIRIT~~
~~COMMENT                Impulsive, torque direction fixed in body frame~~
MANEUVER_START
COMMENT             Data follows for 1 planned maneuver.
COMMENT             First attitude maneuver for: MARS SPIRIT
COMMENT             Impulsive, torque direction fixed in body frame
MAN_EPOCH_START = 2004-02-14T14:29:00.5098
MAN_DURATION    = 3          [s]
MAN_REF_FRAME   = ~~INSTRUMENT_A~~ICRF
MAN_TOR_X       = -1.25      [N*m]
MAN_TOR_Y       = -0.5       [N*m]
MAN_TOR_Z       = 0.5        [N*m]
MANEUVER_STOP
```

Figure 3-3:– APM File Example with various contents

4 ATTITUDE EPHEMERIS MESSAGE (AEM)

4.1 OVERVIEW

Attitude state information may be exchanged between participants by sending an ephemeris in the form of a series of attitude states using an Attitude Ephemeris Message (AEM).~~ ~~ The message recipient must have a suitable means of interpolating across these attitude states to obtain the attitude state at an arbitrary time contained within the span of the attitude ephemeris.

~~The AEM shall be a text file consisting of attitude data for a single object. It shall be easily readable by both humans and computers.~~

The file naming scheme ~~shall~~ should be agreed to on a case-by-case basis between the participating agencies, typically using an Interface Control Document (ICD).~~ ~~ The method of exchanging AEMs shall be decided on a case-by-case basis by the participating agencies and documented in an ICD.

4.2 AEM CONTENT

4.2.1 GENERAL

The AEM shall be represented as a combination of the following:

a) a header;

b) metadata (data about data);

c) optional comments (explanatory information); and

d) attitude data.

~~AEM files must have a set of minimum required sections; some may be repeated.~~

Table 4-1~~4-1~~ outlines the contents of an AEM.

Table 4-1:– AEM File Layout Specifications

Item			Mandatory ?
Header			Yes
Body	Segment 1	Metadata 1	Yes
		Data 1	
	Segment 2	Metadata 2	No
		Data 2	
	. . .	. . .	No
	Segment n	Metadata n	No
		Data n	

4.2.2 AEM HEADER

The header shall provide a CCSDS Attitude Data Message version number that identifies the format version; this is included to anticipate future changes.– The version keyword shall be CCSDS_AEM_VERS and the value shall have the form of ‘x.y’, where ‘y’ is incremented for corrections and minor changes, and ‘x’ is incremented for major changes.– Version 1.0 shall be reserved for the initial version accepted by the CCSDS as an official Recommended Standard (‘Blue Book’).– Testing shall be conducted using AEM version numbers less than 1.0 (e.g., 0.x).– Participating agencies should specify in the ICD the specific AEM version numbers they will support.

The header shall include the CREATION_DATE keyword with the value set to the Coordinated Universal Time (UTC) when the file was created, according to reference [4]~~[4]~~. A description of AEM header keywords and values is provided in table 4-2~~4-2~~.

The first header line must be the first non-blank line in the file.

~~4.2.2~~

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The AEM header assignments are shown in table 4-2~~4-2~~, which specifies for each item:

a) the keyword to be used;

b) a short description of the item;

c) whether the values are normative (N) values or just examples (E);

d) values (either the list of all normative values or examples);

e) whether the item is mandatory or optional.

Only those keywords shown shall be used in an AEM header.

Table 4-2:~~–~~ AEM Header

Keyword	Description	N/E	Values	Mandatory
`CCSDS_AEM_VERS`	Format version in the form of ‘x.y’, where ‘y’ is incremented for corrections and minor changes, and ‘x’ is incremented for major changes.	N	`2.0`	Yes
`COMMENT`	One or more comment lines. Each comment line shall begin with this keyword.	E	`This is a comment.`	No
`CREATION_DATE`	File creation date/time in UTC. For format specification, see 7.7. ~~File creation date/time in one of the following formats:~~ ~~YYYY-MM-DDThh:mm:ss[.d→d] or~~ ~~YYYY-DDDThh:mm:ss[.d→d]~~ ~~where ‘YYYY’ is the year, ‘MM’ is the two-digit month, ‘DD’ is the two-digit day, ‘DDD’ is the three-digit day of year, ‘T’ is constant, ‘hh:mm:ss[.d→d]’ is the UTC time in hours, minutes, seconds, and optional fractional seconds. As many ‘d’ characters to the right of the period as required may be used to obtain the required precision. All fields require leading zeros.~~	E	`2001-11-06T11:17:33`	Yes

`ORIGINATOR`	Creating agency.
	The value for the "ORIGINATOR" keyword should come from the 'Abbreviation' column in the 'Organizations' registry of the SANA Registry (https://sanaregistry.org/r/organizations).
		E	`CNES`
			`ESOC`
			`GSFC`
			`GSOC`
			`JPL`
			`JAXA`
				Yes

`MESSAGE_ID`~~`ORIGINATOR`~~	ID that uniquely identifies a message from a given originator. The format and content of the message identifier value are at the discretion of the originator.~~Creating agency.~~	E ~~E~~	`201113719185` `ABC-12_34`~~`CNES`~~ ~~`ESOC`~~ ~~`GSFC`~~ ~~`GSOC`~~ ~~`JPL`~~ ~~`JAXA`~~	No~~Yes~~

4.2.3 AEM METADATA

A single METADATA group shall precede each attitude ephemeris data block.— Multiple occurrences of a METADATA group followed by an attitude ephemeris data block may be used (e.g., METADATA, DATA, METADATA, DATA, etc.).

Before each METADATA group the string ‘META_START’ shall appear on a separate line and after each METADATA group (and before the associated DATA_START keyword) the string ‘META_STOP’ shall appear on a separate line.

~~4.2.3~~

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The AEM metadata assignments are shown in table 4-3~~4-3~~, which specifies for each item:

a) the keyword to be used;

b) a short description of the item;

c) whether the values are normative (N) values or just examples (E);

d) values (either the list of all normative values or examples);

e) whether the item is mandatory or optional.

Only those keywords shown shall be used in AEM metadata.~~—~~ For some keywords (OBJECT_NAME, OBJECT_ID, CENTER_NAME) there are no definitive lists of authorized values maintained by a control authority; the references listed in 1.5 are the best known sources for authorized values to date.

Table 4-3:~~–~~ AEM Metadata

Keyword	Description	N/E	Values	Mandatory
`META_START`	The AEM message contains both metadata and attitude ephemeris data; this keyword is used to delineate the start of a metadata block within the message (metadata are provided in a block, surrounded by ‘META_START’ and ‘META_STOP’ markers to facilitate file parsing).~~–~~ This keyword must appear on a line by itself.	n/a	n/a	Yes
`COMMENT`	Comments allowed only at the beginning of the Metadata section. Each comment line shall begin with this keyword.	E	`This is a comment.`	No
`OBJECT_NAME`	Spacecraft name of the object corresponding to the attitude data to be given.~~–~~ There is no CCSDS-based restriction on the value for this keyword, but it is recommended to use names ~~international designators~~ from the UN Office of Outer Space Affairs (Ref. [2]).	E	`EUTELSAT W1`	Yes
`OBJECT_ID`	Spacecraft identifier of the object corresponding to the attitude data to be given.~~–~~ While there is no CCSDS-based restriction on the value for this keyword, it is recommended to use international designators ~~names~~ from the UN Office of Outer Space Affairs (Ref. [2]).	E	`2000-052A`	Yes

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Keyword	Description	N/E	Values	Mandatory
`CENTER_NAME`	Origin of reference frame, which may be a natural solar system body (planets, asteroids, comets, and natural satellites), including any planet barycenter or the solar system barycenter, or another spacecraft (in this the value for ‘CENTER_NAME’ is subject to the same rules as for ‘OBJECT_NAME’).~~–~~ There is no CCSDS-based restriction on the value for this keyword, but for natural bodies it is recommended to use names from the NASA/JPL Solar System Dynamics Group (Ref.~~reference~~ [3]~~[3]~~).	E	`EARTH` `STS 106`	No

`REF_FRAME_A`	Name of the reference frame that defines the starting point of the transformation. The full set of values is enumerated in annex B.~~–~~ For a definition of these various frames, the reader is directed to *Navigation Definitions and Conventions* (reference [H2]~~[H4]~~).	E	`ICRF`
			`SC_BODY_1`
			`INSTRUMENT_A`
				Yes

`REF_FRAME_B`	Name of the reference frame that defines the end point of the transformation.~~–~~ The full set of values is enumerated in annex B.~~–~~ For a definition of these various frames, the reader is directed to reference [H2]~~[H4]~~.	E	`SC_BODY_1` `INSTRUMENT_A`	Yes
`TIME_SYSTEM`	Time system used for both attitude ephemeris data and metadata (also see tables 4-3~~4-3~~ and 4-4~~4-4~~).~~–~~ The full set of allowed values is enumerated in annex B.~~–~~ Explanations of these time systems can be found in *Navigation Data - Definitions and Conventions* ~~*Navigation Definitions and Conventions*~~ (reference [H2]~~[H4]~~).	E	`UTC` `TAI`	Yes
`START_TIME`	Start of TOTAL time span covered by attitude ephemeris data immediately following this metadata block.~~–~~ ~~The START_TIME time tag at a new block of attitude ephemeris data must be equal to or greater than the STOP_TIME time tag of the previous block.~~ For format specification, see 7.7.	E	`1996-12-18T14:28:15.1172`	Yes

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Keyword	Description	N/E	Values	Mandatory
USEABLE_ START_TIME, ~~USEABLE_ STOP_TIME~~	Optional start ~~and end~~ of USEABLE time span covered by attitude ephemeris data immediately following this metadata block. ~~-~~To allow for proper interpolation near the ~~ends~~ beginning/end of the attitude ephemeris data block, it may be necessary, ~~depending upon the interpolation method to be used,~~ to utilize this~~ese~~ keywords with values within the time span covered by the attitude ephemeris data records as denoted by the START / STOP_TIME time tags. The USEABLE_START_TIME time tag of a new block of ephemeris data must be greater than or equal to the USEABLE_STOP_TIME time tag of the previous block. For format specification, see 7.7.	E	1996-12-18T14:28:15.1172	No
USEABLE_STOP_ TIME	Optional stop of USEABLE time span covered by attitude ephemeris data immediately following this metadata block. See also USEABLE_START_TIME. For format specification, see 7.7.	E	1996-12-18T14:28:15.1172	No
STOP_TIME	End of TOTAL time span covered by the attitude ephemeris data immediately following this metadata block. ~~The STOP_TIME time tag for the block of attitude ephemeris data must be equal to or less than the START_TIME time tag of the next block.~~ For format specification, see 7.7.	E	1996-12-18T14:28:15.1172	Yes
ATTITUDE_TYPE	The format of the data lines in the message. This keyword must have a value from the set specified at the right.~~–~~ See 4.2.5 for details of the data contained in each line.	N	QUATERNION QUATERNION/DERIVATIVE QUATERNION/ANGVEL EULER_ANGLE EULER_ANGLE/DERIVATIVE EULER_ANGLE/ANGVEL SPIN SPIN/NUTATION	Yes
EULER_ROT_SEQ	The rotation sequence of the Euler angles that rotate from REF_FRAME_A to REF_FRAME_B.~~–~~ This keyword is applicable only if ATTITUDE_TYPE specifies the use of Euler angles.	E	ZXZ XYZ	No
~~RATE_FRAME~~ANGVEL_FRAME	The frame of reference in which ~~Euler rates~~angular velocity data are specified.~~–~~ The allowed values are shown at right.~~–~~ This keyword is applicable only if ATTITUDE_TYPE specifies the use of rates in conjunction with either quaternions or Euler angles.	N	REF_FRAME_A REF_FRAME_B	No

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Keyword	Description	N/E	Values	Mandatory
`INTERPOLATION_METHOD`	Recommended interpolation method for attitude ephemeris data in the block immediately following this metadata block.	E	~~LINEAR~~linear HERMITE LAGRANGE~~Lagrange~~	No
`INTERPOLATION_DEGREE`	Recommended interpolation degree for attitude ephemeris data in the block immediately following this metadata block. It must be an integer value. This keyword must be used if the ‘INTERPOLATION_METHOD’ keyword is used.	E	5 1	No
`META_STOP`	The end of a metadata block within the message. The AEM message contains both metadata and attitude ephemeris data; this keyword is used to delineate the end of a metadata block within the message (metadata are provided in a block, surrounded by ‘META_START’ and ‘META_STOP’ markers to facilitate file parsing). This keyword must appear on a line by itself.	n/a	n/a	Yes

~~Keywords START_TIME, USEABLE_START_TIME, USEABLE_STOP_TIME, and STOP_TIME all denote a spacecraft event time.~~

4.2.4 AEM DATA

~~See 4.2.5, Attitude Ephemeris Data Lines, for specifications regarding AEM data.~~

The Data section of the AEM shall be delineated by the ‘DATA_START’ and ‘DATA_STOP’ keywords. These keywords are intended to facilitate parsing, and will also serve to advise the recipient that all the attitude data records associated with the immediately preceding AEM Metadata section have been received (the rationale for including this is that data volumes can be very large, so knowing when the data begins and ends is desirable). The AEM recipient may process the ‘DATA_STOP’ keyword as a ‘local’ end-of-file marker.

4.2.5 ATTITUDE EPHEMERIS DATA LINES

For AEMs, each set of attitude ephemeris data, including the time tag, must be provided on a single line. Table 4-4~~4-4~~ lists the allowable combinations of data items, with each item following the same definition as given in table 3-3~~3-3~~. The order in which the data items are given shall be fixed as in table 4-4~~4-4~~, with the exception of Euler angle data for which the order of angle data must correspond with the sequence given by EULER_ROT_SEQ.

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The choice of one of the formats in table 4-4~~4-4~~ shall be specified via the ATTITUDE_TYPE keyword in the metadata.

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Table 4-4:– Types of Attitude Ephemeris Data Lines

Keyword	Value	Ephemeris Data Line
Quaternion Options (note that keywords and values appear only in Metadata)		
~~ATTITUDE_TYPE~~	~~QUATERNION~~	~~Epoch, QC, Q1, Q2, Q3~~
	~~QUATERNION/DERIVATIVE~~	~~Epoch, QC, Q1, Q2, Q3, QC_DOT, Q1_DOT, Q2_DOT, Q3_DOT~~
	~~QUATERNION/ANGVEL~~	~~Epoch, QC, Q1, Q2, Q3, ANGVEL_X, ANGVEL_Y, ANGVEL_Z~~
ATTITUDE_TYPE	QUATERNION	Epoch, Q1, Q2, Q3, QC
	QUATERNION/DERIVATIVE	Epoch, Q1, Q2, Q3, QC, Q1_DOT, Q2_DOT, Q3_DOT, QC_DOT
	QUATERNION/ANGVEL	Epoch, Q1, Q2, Q3, QC, ANGVEL_X, ANGVEL_Y, ANGVEL_Z
Euler Angle Options (note that keywords and values appear only in Metadata)		
ATTITUDE_TYPE	EULER_ANGLE	Epoch, ANGLE_1, ANGLE_2, ANGLE_3
	EULER_ANGLE/DERIVATIVE	Epoch, ANGLE_1, ANGLE_2, ANGLE_3, ANGLE_1_DOT, ANGLE_2_DOT, ANGLE_3_DOT
	EULER_ANGLE/ANGVEL	Epoch, ANGLE_1, ANGLE_2, ANGLE_3, ANGVEL_X, ANGVEL_Y, ANGVEL_Z
Spin Axis Options (note that keywords and values appear only in Metadata)		
ATTITUDE_TYPE	SPIN	Epoch, SPIN_ALPHA, SPIN_DELTA, SPIN_ANGLE, SPIN_ANGLE_VEL
	SPIN/NUTATION	Epoch, SPIN_ALPHA, SPIN_DELTA, SPIN_ANGLE, SPIN_ANGLE_VEL, NUTATION, NUTATION_PER, NUTATION_PHASE

The units used shall be the following:

- dimensionless:– EPOCH, Q1, Q2, Q3, QC;
- 1/s:– Q1_DOT, Q2_DOT, Q3_DOT, QC_DOT;
- deg: –ANGLE_1, ANGLE_2, ANGLE=_3, SPIN_ALPHA, SPIN_DELTA, SPIN_ANGLE, NUTATION, NUTATION_PHASE;
- deg/s: –ANGLE_1_DOT, ANGLE_2_DOT, ANGLE_3_DOT, ANGVEL_X, ANGVEL_Y, ANGVEL_Z, SPIN_ANGLE_VEL;

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– s:~~–~~ NUTATION_PER.

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– Note: The units do not appear in the AEM data lines. The data lines only contain values.

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4.2.5.1 FORMAT

At least one space character must be used to separate the items in each attitude ephemeris data line.

See ‘CREATION_DATE’ in table 3-1~~3-1~~ or see reference [4]~~[4]~~ for examples of how to format the EPOCH.~~–~~ Note that any epoch specified denotes spacecraft event time.

In specifying the EPOCH of the message, care must be taken if UTC is used as the TIME_SYSTEM.~~—~~ If an AEM message reports attitude during a time of leap seconds, the system making use of the message should be able to recognize 60 as a valid value for the seconds (e.g., ~~—~~200x-xx-xxT23:59:58.000 .. 200x-xx-xxT23:59:59.000~~—~~ ..~~—~~ 200x-xx-xxT23:59:60.000~~-~~ ..~~-~~ 200x-xx-xxT00:00:00.000).

4.2.5.2 TECHNICAL

It may become necessary to utilize particular orbit information to process Euler angle elements or a local orbit frame (e.g., LVLH, QSW) properly. An approach to this is to add a ‘COMMENT’ block specifying a particular OPM message to use in conjunction with a particular APM.

~~4.2.5.2~~ Specification of Euler angle rotations around only one or two axes may be handled by entering the appropriate sequence for the desired one or two axis rotation and freely choosing the final axis of rotation and giving a value of zero for the rotation angle.

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Attitude ephemeris data lines in a given data block must be ordered by increasing time, and time tags must not be repeated~~, except in the case where the STOP_TIME of a set of attitude ephemeris data lines is equal to the START_TIME of the following set of attitude ephemeris data lines.~~ . The time step duration may vary within a given AEM.

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The TIME_SYSTEM value must remain fixed within an AEM segment.

The occurrence of a second (or greater) metadata block after some attitude ephemeris data shall indicate that interpolation using succeeding attitude ephemeris data with attitude ephemeris data occurring prior to that metadata block shall not be done.~~–~~ This method may be used for proper modeling of propulsive maneuvers or any other source of a discontinuity such as eclipse entry or exit.

Details about the interpolation method should be specified using the INTERPOLATION_METHOD and INTERPOLATION_DEGREE keywords within the AEM.

All data blocks must contain a sufficient number of attitude ephemeris data records to allow the recommended interpolation method to be carried out consistently throughout the AEM.

Specification of Euler angle rotations around only one or two axes may be handled by entering the appropriate sequence for the desired one or two axis rotation and freely choosing the final axis of rotation and giving a value of zero for the rotation value.

~~4.2.6 AEM KEYWORD SET~~

~~The header shall provide a CCSDS Attitude Data Message version number that identifies the format version; this is included to anticipate future changes. The version keyword shall be CCSDS_AEM_VERS and the value shall have the form of 'x.y', where 'y' is incremented for corrections and minor changes, and 'x' is incremented for major changes. Version 1.0 shall be reserved for the initial version accepted by the CCSDS as an official Recommended Standard ('Blue Book'). Testing shall be conducted using AEM version numbers less than 1.0 (e.g., 0.x). Participating agencies should specify in the ICD the specific AEM version numbers they will support.~~

~~The header shall include the CREATION_DATE keyword with the value set to the Coordinated Universal Time (UTC) when the file was created, according to reference [4]. A description of AEM header keywords and values is provided in table 4-2.~~

~~The first header line must be the first non-blank line in the file.~~

~~Only those keywords shown in tables 4-2 and 4-3 shall be used in an AEM. Some keywords represent obligatory items and some are optional. KVN assignments representing optional items may be skipped. The two USEABLE_START/STOP_TIME keywords, marked as optional items, may not be necessary depending on the recommended interpolation method. (It is safer to use the USEABLE_START/STOP_TIME capability in all cases.)~~

~~A single METADATA group shall precede each attitude ephemeris data block. Multiple occurrences of a METADATA group followed by an attitude ephemeris data block may be used (e.g., METADATA, DATA, METADATA, DATA, etc.).~~

~~Before each METADATA group the string 'META_START' shall appear on a separate line and after each METADATA group (and before the associated DATA_START keyword) the string 'META_STOP' shall appear on a separate line.~~

4.3 AEM EXAMPLES

Figure 4-1~~4-1~~ is an example of an AEM.~~–~~ Note that some attitude ephemeris lines were omitted.

```
CCSDS_AEM_VERS = 2~~1~~.0
CREATION_DATE = 2002-11-04T17:22:31
ORIGINATOR = NASA/JPL

META_START
COMMENT This file was produced by M.R. Somebody, MSOO NAV/JPL, 2002 OCT 04.
COMMENT It is to be used for attitude reconstruction only. The relative accuracy of these
COMMENT  attitudes is 0.1 degrees per axis.
OBJECT_NAME         = MARS GLOBAL SURVEYOR
OBJECT_ID           = 1996-062A
CENTER_NAME         = mars barycenter
REF_FRAME_A         = EME2000
REF_FRAME_B         = SC_BODY_1
TIME_SYSTEM         = UTC
START_TIME          = 1996-11-28T21:29:07.2555
USEABLE_START_TIME  = 1996-11-28T22:08:02.5555
USEABLE_STOP_TIME   = 1996-11-30T01:18:02.5555
STOP_TIME           = 1996-11-30T01:28:02.5555
ATTITUDE_TYPE       = QUATERNION
INTERPOLATION_METHOD = hermite
INTERPOLATION_DEGREE = 7
META_STOP

DATA_START
1996-11-28T21:29:07.2555 0.56748  0.03146  0.45689  0.68427
1996-11-28T22:08:03.5555 0.42319  -0.45697 0.23784  0.74533
1996-11-28T22:08:04.5555 -0.84532 0.26974  -0.06532 0.45652
       < intervening data records omitted here >
1996-11-30T01:28:02.5555 0.74563  -0.45375  0.36875  0.31964
DATA_STOP

META_START
COMMENT  This block begins after trajectory correction maneuver TCM-3.
OBJECT_NAME         = mars global surveyor
OBJECT_ID           = 1996-062A
CENTER_NAME         = MARS BARYCENTER
REF_FRAME_A         = EME2000
REF_FRAME_B         = SC_BODY_1
TIME_SYSTEM         = UTC
START_TIME          = 1996-12-18T12:05:00.5555
USEABLE_START_TIME  = 1996-12-18T12:10:00.5555
USEABLE_STOP_TIME   = 1996-12-28T21:23:00.5555
STOP_TIME           = 1996-12-28T21:28:00.5555
ATTITUDE_TYPE       = QUATERNION
~~QUATERNION_TYPE     = LAST~~
META_STOP

DATA_START
1996-12-18T12:05:00.5555 -0.64585 0.018542 -0.23854 0.72501
1996-12-18T12:10:05.5555 0.87451  -0.43475  0.13458 -0.16767
1996-12-18T12:10:10.5555 0.03125  -0.65874  0.23458 -0.71418
       < intervening records omitted here >
1996-12-28T21:28:00.5555 -0.25485 0.58745  -0.36845  0.67394
DATA_STOP
```

Figure 4-1:~~–~~ AEM Example

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Figure 4-2~~4-2~~ is an example of an AEM describing a spinning spacecraft. Note that some attitude ephemeris lines were omitted.

```
CCSDS_AEM_VERS = ~~1~~2.0
CREATION_DATE = 2008-071T17:09:49
ORIGINATOR = GSFC FDF
MESSAGE_ID      = 7077456

META_START
OBJECT_NAME = ST5-224
OBJECT_ID = 2006224
CENTER_NAME = EARTH
REF_FRAME_A = J2000
REF_FRAME_B = SC_BODY_1
TIME_SYSTEM = UTC
START_TIME = 2006-090T05:00:00.071
USEABLE_START_TIME = 2006-090T05:00:00.071
USEABLE_STOP_TIME = 2006-090T05:00:00.946
STOP_TIME = 2006-090T05:00:00.946
ATTITUDE_TYPE = SPIN
META_STOP

DATA_START
COMMENT Spin KF ground solution, SPINKF rates
  2006-090T05:00:00.071  2.6862511e+002  6.8448486e+001  1.5969509e+002 -1.0996528e+002
  2006-090T05:00:00.196  2.6863990e+002  6.8432197e+001  1.4593720e+002 -1.0996493e+002
  2006-090T05:00:00.321  2.6864591e+002  6.8412960e+001  1.3218766e+002 -1.0996455e+002
  2006-090T05:00:00.446  2.6863697e+002  6.8392049e+001  1.1845280e+002 -1.0996402e+002
  2006-090T05:00:00.571  2.6861072e+002  6.8371266e+001  1.0473305e+002 -1.0996370e+002
  2006-090T05:00:00.696  2.6856625e+002  6.8353279e+001  9.1030304e+001 -1.0996339e+002
  2006-090T05:00:00.821  2.6850631e+002  6.8340398e+001  7.7341548e+001 -1.0996317e+002
  2006-090T05:00:00.946  2.6843571e+002  6.8332398e+001  6.3662262e+001 -1.0996304e+002
DATA_STOP
```

Figure 4-2: AEM Spinner Example

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5. ATTITUDE COMPREHENSIVE MESSAGE (ACM)

5.1 GENERAL

5.1.1 Comprehensive attitude information may be exchanged between two participants by sending attitude data/content for one or more epochs using an Attitude Comprehensive Message (ACM). The ACM aggregates and extends APM and AEM content in a single hybrid message. The ACM simultaneously emphasizes flexibility and message conciseness by offering extensive optional standardized content while minimizing mandatory content.

5.1.2 The ACM shall be a plain text file consisting of attitude data for a single space object, or in the case of a parent/child satellite deployment scenario, a single parent object. It shall be easily readable by both humans and computers.

5.1.3 The ACM file-naming scheme should be agreed to on a case-by-case basis between the exchange partners, and should be documented in an ICD. The method of exchanging ACMs should be decided on a case-by-case basis by the exchange partners and documented in an ICD.

5.1.4 Attitude information may be exchanged between two or more participants by sending an attitude ephemeris in the form of one or more time series of attitude states using an Atittude Comprehensive Message (ACM). If attitude states are desired at arbitrary time(s) contained within the span of the attitude ephemeris, the message recipient is encouraged to use a suitable interpolation or propagation method. For times outside of supplied attitude state time spans or if the step size between attitude states is too large to support interpolation or propagation, optional dynamic parameters should be included with this message and the recipient must have a suitably-compatible attitude dynamics propagator.

NOTE – Detailed syntax rules for the ACM are specified in section Section 7.

5.2 ACM CONTENT/STRUCTURE

5.2.1 GENERAL

The ACM shall be represented as a combination of the following as shown in Table 5-1. The ordering of these sections is mandatory. The order of occurrence of the ACM sections shall be fixed as shown in table 5-1.

1) one mandatory header;
2) a single mandatory metadata section (data about data);
3) optional data section(s), comprised of one or more data constituent types:
    a. one or more optional attitude state time histories
    b. one optional space object physical characteristics section
    c. one or more optional covariance time histories

d. one or more optional maneuver data section(s)

e. one optional attitude determination data section

f. one optional, user-defined data and supplemental comments (explanatory information).

Table 5-1: ACM File Layout and Ordering Specification

Section	**Content**
Mandatory Header	Header of message
Mandatory Metadata	Metadata (Informational comments recommended but not required.)
Attitude State Time History Section(s)	Optional: One or more attitude state time histories (each consisting of one or more attitude states)
Optional Space Object Physical Description	Optional space object physical characteristics.
Optional Covariance Data Section(s)	Optional: One or more covariance time histories (each consisting of one or more covariance matrices)
Optional Maneuver Section(s)	Optional maneuver specifications
Optional Attitude Determination Section	Optional attitude determination data section
Optional User Defined Data	Optional: One or more user-defined parameters

5.2.2 ACM HEADER

5.2.2.1 Table 5-2 specifies the keywords for each header item.

5.2.2.2 Only those keywords shown in table 5-2 shall be used in an ACM header.

5.2.2.3 The order of occurrence of these ACM header keywords shall be fixed as shown in table 5-2.

Table 5-2: ACM Header

Keyword	Description	Examples of Values	Mandatory
CCSDS_ACM_VERS	Format version in the form of ‘x.y’, where ‘y’ is incremented for corrections and minor changes, and ‘x’ is incremented for major changes.	1.0	**Yes**
COMMENT	Comments (allowed in the ACM Header only immediately after the ACM version number).	COMMENT This is a comment	No
CREATION_DATE	File creation date/time in UTC. (For format specification, see 7.7.)	2001-11-06T11:17:33 2002-204T15:56:23Z	**Yes**
ORIGINATOR	Creating agency. Value should come from the ‘Abbreviation’ column in the ‘Organizations’ registry of the SANA registry (https://sanaregistry.org/r/organizations).	CNES, ESOC, GSFC, GSOC, JPL, JAXA, Other Agency	**Yes**
MESSAGE_ID	ID that uniquely identifies a message from a given originator. The format and content of the message identifier value are at the discretion of the originator.	201113719185 ABC-12_34	**No**

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5.2.3 ACM METADATA

5.2.3.1 Table 5-3 specifies the metadata keywords. Only those keywords shown in table 5-3 shall be used in ACM metadata.

5.2.3.2 The “ACM Metadata” section is mandatory; “mandatory” in the context of Table 5-3 denotes those keywords which must be included in this section.

5.2.3.3 The order of occurrence of these ACM metadata keywords shall be fixed as shown in table 5-3.

5.2.3.4 The TIME_SYSTEM value must remain fixed within an ACM.

5.2.3.5 The ACM shall only contain a single metadata section in the entire scope of the message.

NOTE – For some keywords (OBJECT_NAME, OBJECT_ID) there are no definitive lists of authorized values maintained by a control authority; the references listed in 1.5 are the best known sources for authorized values to date.

NOTE 2 – Metadata fields which are relied upon by the subsequent optional ACM message subtypes (e.g. attitude state time histories, maneuver data, etc.) are designated as such in the right-hand column of Table 5-3.

Table 5-3: ACM Metadata

Keyword	**Description**	**Examples of Values**	**Mandatory**	**Any ACM sections relying upon this field ?**
COMMENT	Comments (allowed only at the beginning of the ACM Metadata). Each comment line shall begin with this keyword.	This is a comment.	No	
ORIGINATOR_ POC	Free text field containing Programmatic or Technical Point-of-Contact (PoC) for ACM	Ms. Rodgers	No	No
ORIGINATOR_ PHONE	Free text field containing PoC phone number	+49615130312	No	No
ORIGINATOR _POSITION	Free text field containing contact position of the PoC	GNC Engineer ACS Design Lead	No	No
ORIGINATOR_ADDRESS	Free text field containing Technical PoC information for ACM creator (suggest email, website, or physical address, etc.)	JANE.DOE@ SOMEWHERE.NET	No	No
OBJECT_NAME	Spacecraft name of the object corresponding to the attitude data to be given. There is no CCSDS-based restriction on the value for this keyword, but it is recommended to use names from the UN Office of Outer Space Affairs (Ref. [2]).	`SPOT, ENVISAT, IRIDIUM, INTELSAT`	Yes	No
OBJECT_ID	Spacecraft identifier of the object corresponding to the attitude data to be given. Wile there is no CCSDS-based restriction on the value for this keyword, it is recommended to use names from the UN Office of Outer Space Affairs (Ref. [2]).	`2000-052A`	Yes	No

CENTER_NAME	Origin of reference frame, which may be a natural solar system body (planets, asteroids, comets, and natural satellites), including any planet barycenter or the solar system barycenter, or another spacecraft (in this the value for 'CENTER_NAME' is subject to the same rules as 'OBJECT_NAME'). There is no CCSDS-based restriction on the value for this keyword, but for natural bodies it is recommended to use names from the Orbit Centers SANA Registry (link TBS).	`EARTH`
		`EARTH BARYCENTER`
		`MOON`
			No	No

TIME_SYSTEM	Time system used for metadata, attitude data, covariance data. The full set of allowed values is enumerated in TBD SANA Registry (link TBS).	`UTC` `TAI`	Yes	Yes
EPOCH_TZERO	Epoch from which all ACM relative times are referenced. (For format specification, see 7.7). The time scale for EPOCH_TZERO is the one specified by "TIME_SYSTEM" keyword in the metadata section.	2001-11-06T00:00:00	Yes	Yes
ACM_DATA_ELEMENTS	Comma-delimited list of elements of information data blocks included in this message.	ATT, PHYSCHAR,MNVR, COV, AD, USER	No	No
START_TIME	Relative time of the earliest of all time tags corresponding to maneuver, attitude state, covariance. Relative time is measured in seconds from EPOCH_TZERO.	100.0	No	No

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Keyword	**Description**	**Examples of Values**	**Mandatory**	**Any ACM sections relying upon this field ?**
STOP_TIME	Relative time of the end of TOTAL time span covered by ALL maneuver, attitude state, covariance contained in this message. Relative time is measured in seconds from EPOCH_TZERO.	1500.0	No	No
TAIMUTC_TZERO	Difference (TAI – UTC) in seconds (i.e. total # leap seconds elapsed since 1958) as modeled by the message originator at epoch "EPOCH_TZERO".	37 [s]	No	No

5.2.4 ACM DATA: ATTITUDE STATE TIME HISTORY

5.2.4.1 Table 5-4 provides an overview of the ACM attitude state time history section. Only those keywords shown in table 5-4 shall be used in ACM attitude state time history data specification.

5.2.4.2 Keyword values shall be provided in the units specified in the Units column of table 5-8.

5.2.4.3 The order of occurrence of these ACM Attitude State Time History keywords shall be fixed as shown in table 5-4.

5.2.4.4 The "ACM Data: Attitude State Time History" section is optional; "mandatory" in the context of table 5-4 denotes those keywords which must be included in this section if this section is included.

5.2.4.5 Each attitude state time history data block must begin with keyword ATT_START and end with keyword ATT_STOP.

5.2.4.6 Each of these keywords shall appear on a line by itself.

5.2.4.7 Multiple Attitude State Time History blocks shall appear in an ACM if:

5.2.4.7.1 They are delimited by separate ATT_START and ATT_STOP keywords;

5.2.4.7.2 Each data block is clearly differentiated from the others by one or more preceding comment(s) or by ICD agreement.

5.2.4.7.3 Each data block is unique from all others in at least one of the following respects:

1) The selected attitude state set (ATT_STATES) is unique
2) The Attitude State Time History is based upon a unique attitude determination solution
3) The transformations frames are unique (REF_FRAME_A, REF_FRAME_B)
4) The data interval timespan is unique (i.e., has no overlap with any other data interval(s)).

5.2.4.8 Each attitude state time history shall be time-ordered to be monotonically increasing, with the exception that the message creator may indicate a change in state over which interpolation or propagation should not be performed by providing exactly two consecutive lines containing a duplicate timestamp (e.g. following application of a maneuver or spacecraft or orbit event). In the case of such a duplicate timestamp, interpolation or propagation prior to the duplicate timestamp shall use the first of the two duplicate timestamp attitude states, and interpolation or propagation after the duplicate timestamp shall use the second of the two.

5.2.4.9 If the user includes attitude states at key mission event times, it is recommended that those mission event states be annotated as such by a descriptive comment line(s) immediately following the ATT_START keyword.

5.2.4.10 Time tags of consecutive attitude states within the ordered sequence may be separated by uniform or non-uniform step size(s).

5.2.4.11 Attitude state time tags may or may not match those of maneuver or covariance time histories.

5.2.4.12 All attitude state values in the ACM data shall be time-tagged by a relative time value measured with respect to the epoch time specified via the EPOCH_TZERO keyword.

5.2.4.13 At least one space character must be used to separate the items in each attitude data line.

Table 5-4: ACM Data: Attitude State Time History

Keyword	**Description**	**Units**	**Examples of Values**	**Mandatory**
ATT_START	Start of an attitude state time history section	n/a	n/a	Yes
COMMENT	Comments allowed only immediately after the ATT_START keyword	n/a	COMMENT This is a comment	No
ATT_ID	Optional alphanumeric free-text string containing the identification number for this attitude state time history.	n/a	ATT_20160402_XYZ	No
ATT_BASIS	Basis of this attitude state time history data, this is a text field with the following suggested values: 1. “PREDICTED” 2. “DETERMINED_GND” when estimated by post-processing attitude sensor data on the ground 3. “DETERMINED_OBC” when estimated onboard using onboard sensor data 4. “Simulated” for future mission design or other testing purposes	n/a	PREDICTED	No
REF_FRAME_A	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD.	n/a	J2000	Yes
REF_FRAME_B	Name of the reference frame that defines the starting point of the transformation. Use of values other than those present in ANNEX B, section B3 or B4 must be documented in an ICD.	n/a	SC_BODY	Yes
NUMBER_STATES	Number of data states included. States to be included are attitude states and rate states.	n/a	3,4,6,7	Yes
ATT_TYPE	Type of attitude data, selected per ANNEX B, section B5ANNEX B. Attitude states must always be listed before RATE_STATES. Attitude data must always be listed before rate data.	n/a, rad	QUATERNION EULER_ANGLES DCM	Yes
RATE_TYPE	Type of rate data, selected per ANNEX B, section B5. If rate data is included, NUMBER_STATES must be at least 6 to include both attitude and rate data.	rad/s	ANGVEL GYRO_BIAS, Q_DOT NONE	No
… < Insert attitude lines here>				Yes
ATT_STOP	End of an attitude state time history section	n/a	n/a	Yes

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5.2.5 ACM DATA: SPACE OBJECT PHYSICAL CHARACTERISTICS

5.2.5.1 Table 5-5 provides an overview of the ACM space object physical characteristics section. Only those keywords shown in table 5-5 shall be used in ACM space object physical characteristics data.

5.2.5.2 Keyword values shall be provided in the Units column of Table 5-5.

5.2.5.3 The order of occurrence of these ACM Space Objects Physical Characteristics keywords shall be fixed as shown in table 5-5.

5.2.5.4 The “ACM Data: Space Object Physical Characteristics” section is optional; “mandatory” in the context of table 5-5 denotes those keywords which must be included in this section if this section is included.

5.2.5.5 Only one space object physical characteristics section shall appear in an ACM.

5.2.5.6 The space object physical characteristics data section in the ACM shall be indicated by two keywords: PHYS_START and PHYS_STOP.

5.2.5.7 Further definition of Space Object Physical Characteristics parameters is provided in ANNEX X.

Table 5-5: ACM Data: Space Object Physical Characteristics

Keyword	Description	Units	Examples of Values	Mandatory
PHYS_START	Start of a Space Object Physical Characteristics specification	n/a		Yes
COMMENT	Comments allowed only immediately after the PHYS_START keyword.	n/a	COMMENT This is a comment	No
MASS	Total S/C Mass at the reference epoch "EPOCH_TZERO"	kg	500.0	No
IXX	Moment of Inertia about the X-axis of the spacecraft's primary body frame (e.g. SC_Body_1)	kg*m**2	1000.0	No
IYY	Moment of Inertia about the Y-axis	kg*m**2	800.0	No
IZZ	Moment of Inertia about the Z-axis	kg*m**2	400.0	No
IXY	Inertia Cross Product of the X & Y axes	kg*m**2	20.0	No
IXZ	Inertia Cross Product of the X & Z axes	kg*m**2	40.0	No
IYZ	Inertia Cross Product of the Y & Z axes	kg*m**2	60.0	No
CP	Vector location of spacecraft center of pressure for determining solar pressure torque, measured from the spacecraft center of mass in the spacecraft's primary body frame (e.g. SC_Body_1).	m	[0.02, 0.01, 0.2]	No
DRAG_COEF	Drag coefficient	n/a	2	No
FUEL_MASS	Fuel mass	kg	750.0	No
PHYS_STOP	End of a Space Object Physical Characteristics specification	n/a		Yes

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5.2.6 ACM DATA: ATTITUDE STATE COVARIANCE TIME HISTORY

5.2.6.1 Table 5-6 provides an overview of the ACM attitude state covariance time history section. Only those keywords shown in table 5-6 shall be used in ACM covariance time history data specification.

5.2.6.2 Keyword values shall be provided in the units specified in the Units column of table 5-10.

5.2.6.3 The order of occurrence of these ACM Attitude State Covariance Time History keywords shall be fixed as shown in table 5-6.

5.2.6.4 The "ACM Data: Attitude State Covariance Time History" section is optional; "mandatory" in the context of table 5-6 denotes those keywords which must be included in this section if this section is included.

5.2.6.5 Attitude State Covariance Time History data shall be indicated by two keywords: COV_START and COV_STOP.

5.2.6.6 Multiple covariance data blocks may appear in an ACM only if they are delimited by separate COV_START and COV_STOP keywords.

5.2.6.7 All covariance matrices in the ACM data shall be time-tagged by a relative time value measured with respect to the epoch time specified via the EPOCH_TZERO keyword.

5.2.6.8 Each covariance time history shall be time-ordered to be monotonically increasing, with the exception that the message creator may indicate a change in state over which interpolation or propagation should not be performed by providing exactly two consecutive covariance data blocks containing a duplicate timestamp (e.g. following application of an impulsive maneuver or spacecraft or orbit event). In the case of such a duplicate timestamp, interpolation or propagation prior to the duplicate timestamp shall use the first of the two duplicate timestamp covariance matrices, and interpolation or propagation after the duplicate timestamp shall use the second of the two.

5.2.6.9 If the user includes covariances at key mission event times, it is recommended that those mission event covariances be annotated as such by a preceding descriptive comment line.

5.2.6.10 Time tags of consecutive covariance information within the ordered sequence may be separated by uniform or non-uniform step size(s).

5.2.6.11 Covariance time tags may or may not match those of maneuver, attitude state, and/or sensor data time histories.

5.2.6.12 Values in the covariance matrix shall be only main diagonal elements provided on a single line. Off-diagonal elements could be defined in a USER defined block.

Table 5-6: ACM Data: Covariance Time History

Keyword	**Description**	**Units**	**Examples of Values**	**Mandatory**
COV_START	Start of a covariance time history section	n/a	n/a	Yes
COMMENT	Comments allowed only immediately after the COV_START keyword	n/a	COMMENT This is a comment	No
ATT_ID	Optional alphanumeric free-text string containing the identification number for this attitude covariance time history block	n/a	ATT_20160402_XYZ	No
ATT_BASIS	Basis of this covariance time history data, this is a text field with the following suggested values: 1. "PREDICTED" 2. "DETERMINED_GND" when estimated by post-processing attitude sensor data on the ground 3. "DETERMINED_OBC" when estimated onboard using onboard sensor data 4. "Simulated" for future mission design or other testing purposes			No
REF_FRAME	Reference frame of the covariance time history.	n/a	SC_BODY	No
NUMBER_COV_STATES	Number of covariance states included.	n/a	3,6	No
COV_ATT_STATES	Type of attitude error included in the covariance time history.	rad	ANGLES DELTA_QUAT	No
COV_RATE_STATES	Type of rate error included in the covariance time history. If rate error covariance data is included NUMBER_COV_STATES must be at least 6 to include both attitude error and rate error covariance data.	rad/s	ANGVEL GYRO_BIAS_ERROR	No
…< Insert covariance data here>				Yes
COV_STOP	End of a covariance time history section	n/a	n/a	Yes

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5.2.7 ACM DATA: MANEUVER SPECIFICATION

5.2.7.1 Table 5-7 provides an overview of the ACM maneuver specification section. Only those keywords shown in table 5-7 shall be used in the ACM maneuver specification.

5.2.7.2 Keyword values shall be provided in the units specified in the Units column of Table 5-7.

5.2.7.3 The order of occurrence of these ACM Maneuver Specification keywords shall be fixed as shown in table 5-7.

5.2.7.4 The "ACM Data: Maneuver Specification" section is optional; "mandatory" in the context of Table 5-7 denotes those keywords which must be included in this section if this section is included.

5.2.7.5 One or more ACM Maneuver Specification sections may appear in an ACM.

5.2.7.6 Maneuver data in the ACM shall be indicated by two keywords: MAN_START and MAN_STOP.

5.2.7.7 The 'MAN_TYPE' keyword must appear before the first line of any maneuver time history data.

5.2.7.8 Attitude maneuver data in the ACM data shall be time-tagged by a relative time value measured with respect to the epoch time specified via the EPOCH_TZERO keyword.

Table 5-7: ACM Data: Maneuver Specification

Keyword	**Description**	**Units**	**Examples of Values**	**Mandatory**
MAN_START	Start of a maneuver data interval specification	n/a		Yes
COMMENT	Comments allowed only immediately after the MAN_START keyword.	n/a	COMMENT This is a comment	No
MAN_ID	Optional alphanumeric free-text string containing the identification number for this maneuver	n/a	DH2018172	No
MAN_PURPOSE	The user can specify the intention(s) of the maneuver. Multiple maneuver purposes can be provided as a comma-delimited list. While there is no CCSDS-based restriction on the value for this keyword, it is suggested to use: Attitude adjust (ATT_ADJUST) Momentum desaturation (MOM_DESAT) Pointing Request Message (PRM_ID_xxxx) Science objective (SCI_OBJ) Spin rate adjust (SPIN_RATE_ADJUST)	n/a	ATT_ADJUST	No
MAN_ BEGIN	Start time of actual maneuver, measured as a relative time with respect to EPOCH_TZERO	sec	100.0	No
MAN_ END	End time of actual maneuver, measured as a relative time with respect to EPOCH_TZERO	sec	120.0	No
MAN_DURATION	Length of maneuver, should only specify MAN_END or MAN_DURATION, not both	s	20.0	No
ACTUATOR_USED	Specifies the type of actuator used for the maneuver	n/a	THR, RWA	No
TARGET_MOMENTUM	If MAN_PURPOSE=MOM_DESAT, TARGET_MOMENTUM in SC_BODY	N-m-s	[0, -10, 0]	No
TARGET_ATTITUDE	If MAN_PURPOSE=ATT_ADJUST, target quaternion	n/a	[0, 0, 0, 1]	No
TARGET_SPINRATE	If MAN_PURPOSE=SPIN_RATE_ADJUST, target spin rate	rad/s	0.31	No
MAN_STOP	End maneuver data interval specification	n/a		Yes

5.2.8 ACM DATA: ATTITUDE DETERMINATION DATA

5.2.8.1 Table 5-8 provides an overview of the ACM attitude determination section. Only those keywords shown in table 5-8 shall be used in ACM attitude determination data specification.

5.2.8.2 Keyword values shall be provided in the units specified in the Units column of table 5-8.

5.2.8.3 The order of occurrence of these ACM Estimator Description keywords shall be fixed as shown in table 5-8.

5.2.8.4 The Attitude Determination Data section is optional; “mandatory” in the context of table 5-8 denotes those keywords which must be included in this section if this section is included.

5.2.8.5 At most, only on Attitude Determination Data section shall appear in an ACM.

5.2.8.6 Attitude determination data in the ACM shall be indicated by two keywords: AD_START and AD_STOP.

5.2.8.7 This attitude determination parameters section should reflect the attitude determination settings used to generate all attitude and covariance matrix sections of the message.

Table 5-8: ACM Data: Attitude Determination Data

Keyword	**Description**	**Units**	**Examples of Values**	**Mandatory**
AD_START	Start of an attitude determination data section	n/a	n/a	Yes
COMMENT	Comments allowed only immediately after the EST_START keyword	n/a	COMMENT This is a comment	No
AD_ID	Optional identification number for this attitude determination.	n/a	AD_20190101	No
AD_METHOD	Type of estimator used. For further description see Annex C7.	n/a	EKF, TRIAD, QUEST, BATCH,Q METHOD, FILTER SMOOTHER	No
ATTITUDE_SOURCE	Source of attitude estimate, whether from a ground based estimator or onboard estimator	n/a	GND,OBC	No
NUMBER_STATES	Number of states if EKF, BATCH, or FILTER SMOOTHER is specified.	n/a	3, 6, 7	No
NUMBER_COV_STATES	Number of covariance states if EKF, BATCH, or FILTER SMOOTHER is specified	n/q	3, 6	No
NUMBER_STATES	Number of states if EKF, BATCH, or FILTER SMOOTHER is specified.	n/a	3, 6, 7	No
NUMBER_COV_STATES	Number of covariance states if EKF, BATCH, or FILTER SMOOTHER is specified	n/q	3, 6	No
REF_FRAME_A	Name of the reference frame that defines the starting point of the transformation described by the attitude state in the estimator.	n/a	J2000	Yes
REF_FRAME_B	Name of the reference frame that defines the ending point of the transformation described by the attitude state in the estimator.	n/a	SC_BODY	Yes
RATE_STATES	Type of rate state included in the estimator, if RATE_STATES are included NUMBER_STATES must be at least 6 to include both ATTITUDE_STATES and RATE_STATES	rad/s	ANGVEL GYRO_BIAS	No
COV_RATE_STATES	Type of rate error state included in the estimator, if COV_RATE_STATES are included NUMBER_COV_STATES must be at least 6 to include both COV_ATT_STATES and COV_RATE_STATES	rad/s	ANGVEL_ERROR GYRO_BIAS_ERROR	No
SIGMA_U	Rate random walk if RATE_STATES=GYRO_BIAS	rad/s**1.5	6.5e-9	No
SIGMA_V	Angle random walk if RATE_STATES=GYRO_BIAS	rad/s**0.5	2.3e-7	No

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Keyword	**Description**	**Units**	**Examples of Values**	**Mandatory**
NUMBER_SENSORS_USED	Number of sensors used to provide estimator measurements	n/a	2, 3	No
SENSORS_USED_i	Types of sensors used in estimation, i = 1 to NUMBER_SENSORS_USED	n/a	AST, DSS, GYRO	No
NUMBER_SENSOR_NOISE_COVARIANCE_i	Number of noise elements for sensor i. For example, noise along horizontal and vertical directions of a CCD, or noise along x, y, and z axes of a sensor.	n/a	2,3	No
SENSOR_NOISE_STDDEV_i	Standard deviation of sensor noise, size will be the same as NUMBER_SENSOR_NOISE_COVARIANCE_I	rad	0.00017, 0.00017	No
SENSOR_FREQUENCY_i	Frequency of sensor i data	Hz	5	No
RATE_PROCESS_NOISE_STDDEV	Process noise standard deviation if RATE_STATES=ANG_VEL	rad/s**1.5	9.0E-08	No
AD_STOP	End of an attitude determination data section	n/a		Yes

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5.2.9 ACM DATA: USER-DEFINED PARAMETERS

5.2.9.1 A section of User Defined Parameters may be provided if necessary. In principle, this provides flexibility, but also introduces complexity, non-standardization, potential ambiguity, and potential processing errors. Accordingly, if used, the keywords and their meanings must be described in an ICD. User Defined Parameters, if included in an ACM, should be used as sparingly as possible; their use is not encouraged.

5.2.9.2 The “ACM Data: User-Defined Parameters” section is optional; “mandatory” in the context of table 5-9 denotes those keywords which must be included in this section if this section is included.

5.2.9.3 At most, only one User-Defined Parameters section shall appear in an ACM.

5.2.9.4 Each user-defined parameter line may be preceded by one or more comment lines.

5.2.9.5 Table 5-9 provides an overview of the ACM user-defined data section. Only those keywords shown in table 5-9 shall be used in ACM user-defined data specification.

Table 5-9: ACM Data: User-Defined Parameters

Keyword	Description	Units	Examples of Values	Mandatory
USER_START	Start of a user-defined parameters data block	n/a		Yes
COMMENT	Comments (allowed at any point(s) throughout the ACM User-Defined Data section). (See 7.9**Error! Reference source not found.** for formatting rules.)	n/a	COMMENT This is a comment	No
USER_DEFINED_x	User defined parameter, where ‘x’ is replaced by a variable length user specified character string. Any number of user defined parameters may be included, if necessary to provide essential information that cannot be conveyed in standard ACM keywords or in COMMENT statements	n/a	USER_DEFINED_SENSOR = FINE_GUIDANCE_SENSOR	No
USER_STOP	End of a user-defined parameters data block	n/a		Yes

5.3 ACM EXAMPLES

Figures 5-1 through figure 5-5 are examples of Attitude Comprehensive Messages. The first has only a time history of attitude states and constitutes a minimal content ACM. The second includes space object characteristics, the third includes a maneuver with associated attitude history, the fourth contains an example sensor description block followed by sensor data, and the fifth includes a time series of covariance elements.

```
CCSDS_ACM_VERS   = 2.0
CREATION_DATE    = 1998-11-06T09:23:57
ORIGINATOR       = JAXA
OBJECT_NAME      = GODZILLA 5
OBJECT_ID        = 2000-052A
TIME_SYSTEM      = UTC
EPOCH_TZERO      = 1998-12-18T14:28:15.1172

ATT_START
REF_FRAME_A    = J2000
REF_FRAME_B    = SC_BODY
ATT_TYPE = QUATERNION

0.0     0.73566         -0.50547        0.41309         0.180707
0.25    0.73529         -0.50531        0.41375         0.181158
0.50    0.73492         -0.50515        0.41441         0.181610

< additional data records omitted here >
ATT_STOP
```

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Figure 5-1: Simple/Succinct ACM File example

```
CCSDS_ACM_VERS    = 2.0

CREATION_DATE     = 2017-12-01T00:00:00
ORIGINATOR        = NASA

OBJECT_NAME       = SDO
OBJECT_ID         = 2010-005A
TIME_SYSTEM       = UTC
EPOCH_TZERO       = 2017-12-26T19:40:00.000

MAN_START
COMMENT             Momentum management maneuver
MAN_PURPOSE       = MOM_DESAT
MAN_BEGIN         = 100.0
MAN_DURATION      = 450.0
ACTUATOR_USED     = THR
TARGET_MOMENTUM   = 1.30  -16.400  -11.350
MAN_STOP


AD_START
COMMENT             SDO Onboard Filter
AD_METHOD        = EKF
ATTITUDE_SOURCE   = OBC
NUMBER_SENSORS_USED = 4
SENSORS_USED_1    = AST1
SENSORS_USED_2    = AST2
SENSORS_USED_3    = DSS
SENSORS_USED_4    = IMU
AD_STOP



ATT_START
COMMENT            OBC Attitude and Bias during momentum management maneuver
REF_FRAME_A       = J2000
REF_FRAME_B       = SC_BODY
NUMBER_OF_STATES = 7
ATT_TYPE          = QUATERNION
RATE_TYPE         = GYRO_BIAS

0.000000 0.1153 -0.1424 0.8704 0.4571 2.271e-06 -4.405e-06 -3.785e-06
2.000000 0.1153 -0.1424 0.8704 0.4571 2.271e-06 -4.405e-06 -3.785e-06
< intervening data records omitted here >
99.80183  0.1017 -0.1332 0.8806 0.4433 2.587e-06 8.769e-06 5.436e-06
< intervening data records omitted here >
599.80275 0.1152 -0.1423 0.8704 0.4571 2.48e-06 -4.350e-06 -3.779e-06
ATT_STOP
```

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Figure 5-2: ACM example with Momentum Management Maneuver, Estimator Description, and Attitude State History During Manuever

```
CCSDS_ACM_VERS  = 2.0

CREATION_DATE          = 1998-11-06T09:23:57
ORIGINATOR             = JAXA
ORIGINATOR_POC         = Ms. Rodgers, (719)555-5555, email@email.XXX
TIME_SYSTEM            = TAI
EPOCH_TZERO            = 1998-12-18T14:28:15.1172

OBJECT_NAME            = GODZILLA 5
OBJECT_ID              = 1998-999ZZZ
TAIMUTC_TZERO          = 36       [s]


PHYS_START
COMMENT                 Spacecraft Physical Parameters
MASS               = 1916   [kg]
IXX                = 752    [kg*m**2]
IYY                = 1305   [kg*m**2]
IZZ                = 1490   [kg*m**2]
IXY                = 81.1   [kg*m**2]
IXZ                = -25.7  [kg*m**2]
IYZ                = 74.1   [kg*m**2]
CM                 = 0.04  -0.78  -0.023  [m]
PHYS_STOP
```

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Figure 5-3: Example Spacecraft Physical Characteristics

```
CCSDS_ACM_VERS   = 1.0

CREATION_DATE   = 2017-12-30T00:00:00
ORIGINATOR      = NASA

OBJECT_NAME     = LRO
OBJECT_ID       = 2009-031A
EPOCH_TZERO     = 2017-12-30T00:00:00.0
TIME_SYSTEM     = UTC

COMMENT  LRO Onboard Filter, A Multiplicative Extended Kalman Filter
AD_START
AD_METHOD         = EKF
ATTITUDE_SOURCE   = OBC
NUMBER_STATES     = 7
NUMBER_COV_STATES = 6
ATTITUDE_STATES   = QUATERNION
COV_ATT_STATES    = ANGLES
REF_FRAME_A       = EME2000
REF_FRAME_B       = SC_BODY
RATE_STATES       = GYRO_BIAS
COV_RATE_STATES   = GYRO_BIAS_ERROR
NUMBER_SENSORS_USED = 3
SENSORS_USED_1    = AST1
SENSORS_USED_2    = AST2
SENSORS_USED_3    = IMU
AD_END


COV_START
COMMENT  Diagonal Covariance for LRO Onboard Kalman Filter

0.0       6.74E-11 8.10E-11 9.22E-11 1.11E-15 1.11E-15 1.12E-15
1.096694  6.74E-11 8.10E-11 9.22E-11 1.11E-15 1.11E-15 1.12E-15
< intervening data records omitted here >
59.896697 6.74E-11 8.10E-11 9.22E-11 1.11E-15 1.11E-15 1.12E-15
COV_STOP
```

Figure 5-4: ACM example with Covariance Elements

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6 CONSTRUCTING AN ADM/XML INSTANCE

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6.1 OVERVIEW

This section provides more detailed instructions for the user on how to create an XML message based on one of the ASCII-text KVN-formatted messages described in Sections 3 through 5 of this document.

This section applies only to the XML representation of the ADM messages. The ADM/XML schemas are available on the SANA Web site. SANA is the registrar for the protocol registries created under CCSDS. The ADM XML schemas explicitly define the permitted data elements and values acceptable for the XML versions of the ADM messages. The location of the ADM/XML schemas is:

APM: https://sanaregistry.org/r/ndmxml/ndmxml-1.0-apm-2.0.xsd

AEM: https://sanaregistry.org/r/ndmxml/ndmxml-1.0-aem-2.0.xsd

ACM: https://sanaregistry.org/r/ndmxml/ndmxml-1.0-acm-2.0.xsd

Where possible these schemas use simple types and complex types used by the constituent schemas that make up Navigation Data Messages (see Reference [5]).

6.2 ADM/XML BASIC STRUCTURE

Each ADM shall consist of a `<header>` and a `<body>`.

The `<body>` shall consist of one or more `<segment>` constructs (one for the APM, one or more for the AEM, one for the ACM).

Each `<segment>` shall consist of one `<metadata>/<data>` pair, as shown in Figure 6-1.

NOTE: An AEM may have more than one segment, in which case the metadata/data pair is repeated in each segment.

```
<header>
</header>
<body>
      <segment>
            <metadata>
            </metadata>
            <data>
            </data>
      </segment>
</body>
```

Figure 6-1: ADM XML Basic Structure

6.3 ADM/XML TAGS

An ADM XML tag shall be all uppercase if it corresponds directly to a KVN keyword from the Header, Metadata, or Data sections.

The 'CCSDS_A*M_VERS' keyword and value shall appear as XML attributes of the root element rather than as XML elements. This is an exception where there is not a strict correspondence between keywords in the KVN and tags in the XML implementations, specifically, the 'CCSDS_A*M_VERS' keywords from the Headers for the APM, AEM, and ACM respectively.

ADM XML tags related to the XML message structure (i.e., that do not correspond directly to a KVN keyword) shall be in 'lowerCamelCase' (e.g., `<header>`, `<segment>`, `<metadata>`, `<attitudeStateType>`, etc.).

6.4 CONSTRUCTING AN ADM/XML INSTANCE

OVERVIEW

This subsection provides more detailed instructions for the user on how to create an XML message based on the ASCII-text KVN-formatted messages described in Sections 1 through 5**Error! Reference source not found.**.

XML VERSION

The first line in the instantiation shall specify the XML version:

```
<?xml version="1.0" encoding="UTF-8"?>
```

This line must appear on the first line of each instantiation, exactly as shown.

BEGINNING THE INSTANTIATION: root element TAG

Each instantiation shall have a 'root element tag' that identifies the message type and other information such as where to find the applicable schema, required attributes, etc.

The root element tag in an ADM/XML instantiation shall be one of those listed in Table 6-1.

Table 6-1: ADM/XML Root Element Tags

Root Element Tag	**Message Type**
`<apm></apm>`	Attitude Parameter Message
`<aem></aem>`	Attitude Ephemeris Message
`<acm></acm>`	Attitude Comprehensive Message

The XML Schema Instance namespace attribute must appear in the root element tag of all ADM/XML instantiations, exactly as shown:

```
xmlns:xsi="http://www.w3.org/2001/XMLSchema-instance"
```

If it is desired to validate an instantiation against the CCSDS Web-based schema, the xsi:noNamespaceSchemaLocation attribute must be coded as a single string of non-blank characters, with no line breaks, exactly as shown:

```
xsi:noNamespaceSchemaLocation="http://sanaregistry.org/r/ndmxml/ndmxml-
1.0-master.xsd"
```

NOTE – The length of the value associated with the xsi:noNamespaceSchemaLocation attribute can cause the string to wrap to a new line; however, the string itself contains no breaks.

There are two attributes that are required in the root element tag of an ADM/XML single message instantiation, specifically, the CCSDS_xxx_VERS keyword that is also part of the standard KVN header, and the Blue Book version number.

The final attributes of the root element tag shall be ‘id’ and ‘version’.

The ‘id’ attribute shall be ‘id="CCSDS_xxx_VERS"’, where xxx = AEM, APM, or ACM.

The ‘version’ attribute shall be ‘version="2.0"’.

NOTE – The following example root element tag for an APM instantiation combines all the directions in the preceding several subsections:

```
<?xml version="1.0" encoding="UTF-8"?>
<apm xmlns:xsi="http://www.w3.org/2001/XMLSchema-instance"
xsi:noNamespaceSchemaLocation=
"http://sanaregistry.org/r/ndmxml/ndmxml-1.0-master.xsd"
id="CCSDS_APM_VERS" version="2.0">
```

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THE ADM/XML HEADER SECTION

The ADMs (APM, AEM, ACM) shall share a standard header format, with tags `<header>` and `</header>` (see [5]).

Immediately following the <header> tag the message may have any number of `<COMMENT></COMMENT>` tag pairs.

The standard ADM header shall contain the following element tags:

a) `<CREATION_DATE>`

b) `<ORIGINATOR>`

c) `<MESSAGE_ID>`

NOTE – The rules for these keywords are specified in Tables 3-1, 4-2, 5-?. An example `<header>` section is shown immediately below:

```
<header>
   <COMMENT>This is the common ADM/XML Header.</COMMENT>
   <COMMENT>I can put as many comments here as I
want,</COMMENT>
   <COMMENT>including none.</COMMENT>
   <CREATION_DATE>2010-03-12T22:31:12.000</CREATION_DATE>
   <ORIGINATOR>AGENCYX</ORIGINATOR>
   <MESSAGE_ID>AGENCYX-1234</MESSAGE_ID>
</header>
```

THE ADM/XML BODY SECTION

After coding the `<header>`, the instantiation must include a `<body></body>` tag pair.

Inside the <body>`</body>` tag pair must appear at least one `<segment></segment>` tag pair, depending on the particular ADM (APM, AEM, ACM).

Each <segment> must be made up of one `<metadata></metadata>` tag pair and one `<data></data>` tag pair.

THE ADM/XML METADATA SECTION

All ADMs must have at least one Metadata section.

The Metadata Section shall be set off by the `<metadata></metadata>` tag combination.

Immediately following the `<metadata>` tag, the message may have any number of `<COMMENT></COMMENT>` tag pairs.

NOTE: The `<COMMENT></COMMENT>` placement is regulated by the XML schema. Standard XML comments, i.e. of the form `<!-- comment content -->` may be placed anywhere in the Metadata Section because they are ignored by the XML schema validator.

Between the <metadata> and </metadata> tags, the keywords shall be the same as those in the Metadata sections in Sections 3 through 5 of this document, with exceptions as noted in the subsections that discuss creating instantiations of the specific messages.

THE ADM/XML DATA SECTION

All ADMs must have at least one data section.

The Data Section shall follow the Metadata Section and shall be set off by the `<data></data>` tag combination.

Immediately following the `<data>` tag, the message may have any number of `<COMMENT></COMMENT>` tag pairs.

NOTE: The `<COMMENT></COMMENT>` placement is regulated by the XML schema. Standard XML comments, i.e. of the form `<!-- comment content -->` may be placed anywhere in the Data Section because they are ignored by the XML schema validator.

Between the `<data>` and `</data>` tags, the keywords shall be the same as those in the data sections in Sections 3 through 5 of this document, with exceptions as noted in the subsections that discuss creating instantiations of the specific messages.

6.5 LOCAL OPERATIONS

For use in a local operations environment, the NDM/XML schema set (which includes the ADM schemas) may be downloaded from the SANA web site to a local server that meets local requirements for operations robustness. See Reference [5].

If a local version is used, the value associated with the xsi:noNamespaceSchemaLocation attribute must be changed to a URL that is accessible to the local server.

6.6 CREATING AN APM INSTANTIATION

An APM instantiation shall be delimited by the `<apm></apm>` root element tags using the standard attributes documented in 0.

NOTE – Figures <<TBD>> provide example APM instantiations.

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The final attributes of the `<apm>` tag shall be ‘id’ and ‘version’; the order in which these attributes are specified is not significant.

The ‘id’ attribute shall be ‘`id="CCSDS_APM_VERS"`’.

The ‘`version`’ attribute for the version of the APM shall be ‘`version="2.0"`’.

The standard ADM/XML header shall follow the `<apm>` tag (see 0).

The APM `<body>` shall consist of a single `<segment>`.

The keywords in the `<metadata>` and `<data>` sections shall be those specified in Section 3.2.

Tags for keywords shall be all uppercase, as in Section 3.2.

Several of the APM/XML keywords may have a unit attribute, if desired by the APM producer, as illustrated in the following table:

Table 6-2 APM XML Units

Keyword	**Units**	**Example**
Q1_DOT	1/s	<Q1_DOT units="1/s">numeric-value</Q1_DOT>
Q2_DOT	1/s	<Q2_DOT units="1/s">numeric-value</Q2_DOT>
Q3_DOT	1/s	<Q3_DOT units="1/s">numeric-value</Q3_DOT>
QC_DOT	1/s	<QC_DOT units="1/s">numeric-value</QC_DOT>
ANGLE_1	deg	<ANGLE_1 units="deg">numeric-value</ANGLE_1>
ANGLE_2	deg	<ANGLE_2 units="deg">numeric-value</ANGLE_2>
ANGLE_3	deg	<ANGLE_3 units="deg">numeric-value</ANGLE_3>
ANGLE_1_DOT	deg/s	<ANGLE_1_DOT units="deg/s">numeric-value</ANGLE_1_DOT>
ANGLE_2_DOT	deg/s	<ANGLE_2_DOT units="deg/s">numeric-value</ANGLE_2_DOT>
ANGLE_3_DOT	deg/s	<ANGLE_3_DOT units="deg/s">numeric-value</ANGLE_3_DOT>
ANGVEL_X	deg/s	<ANGVEL_X units="deg/s">numeric-value</ANGVEL_X>
ANGVEL_Y	deg/s	<ANGVEL_Y units="deg/s">numeric-value</ANGVEL_Y>
ANGVEL_Z	deg/s	<ANGVEL_Z units="deg/s">numeric-value</ANGVEL_Z>
SPIN_ALPHA	deg	<SPIN_ALPHA units="deg">numeric-value</SPIN_ALPHA>
SPIN_DELTA	deg	<SPIN_DELTA units="deg">numeric-value</SPIN_DELTA>
SPIN_ANGLE	deg	<SPIN_ANGLE units="deg">numeric-value</SPIN_ANGLE>
SPIN_ANGLE_VEL	deg/s	<SPIN_ANGLE_VEL units="deg/s">numeric-value</SPIN_ANGLE_VEL>
NUTATION	deg	<NUTATION units="deg">numeric-value</NUTATION>
NUTATION_PER	s	<NUTATION_PER units="s">numeric-value</NUTATION_PER>
NUTATION_PHASE	deg	<NUTATION_PHASE units="deg">numeric-value</NUTATION_PHASE>
IXX	kg*m**2	<IXX units="kg*m**2">numeric-value</IXX>
IYY	kg*m**2	<IYY units="kg*m**2">numeric-value</IYY>
IZZ	kg*m**2	<IZZ units="kg*m**2">numeric-value</IZZ>
IXY	kg*m**2	<IXY units="kg*m**2">numeric-value</IXY>
IXZ	kg*m**2	<IXZ units="kg*m**2">numeric-value</IXZ>
IYZ	kg*m**2	<IYZ units="kg*m**2">numeric-value</IYZ>
MAN_DURATION	s	<MAN_DURATION units="s">numeric-value</MAN_DURATION>
MAN_TOR_X	N*m	<MAN_TOR_X units="N*m">numeric-value</MAN_TOR_X>
MAN_TOR_Y	N*m	<MAN_TOR_Y units="N*m">numeric-value</MAN_TOR_Y>
MAN_TOR_Z	N*m	<MAN_TOR_Z units="N*m">numeric-value</MAN_TOR_Z>

SPECIAL TAGS IN the APM/xml BODY

NOTE – In addition to the APM keywords specified in Section 3, there are several special tags associated with the APM body as described in the next few subsections. The information content in the APM is separated into constructs referred to as ‘logical blocks’. Special tags in the APM are used to encapsulate the information in the logical blocks of the APM.

The APM/XML tags used to delimit the logical blocks of the APM shall be drawn from the following table:

Table 6-3 Special Tags in the APM/XML Body

APM Logical Block	Associated APM/XML Tag

Attitude Quaternion	`<quaternionState>`
	`<quaternion>`
	`<quaternionDerivative>`
	
	The `<quaternionState>` consists of the `<quaternion>` tag that contains the components of the quaternion itself, and the `<quaternionDerivative>` tag that contains the rate of change of the quaternion components

Euler Angle Elements	`<eulerAngleElements>`
Angular Velocity Vector	`<angularVelocity>`
Spin	`<spin>`
Inertia	`<inertia>`
Maneuver Parameters	`<maneuverParameters>`

Between the begin tag and end tag (e.g., between `<eulerAngleElements>` and `</eulerAngleElements>`), the user shall place the keywords required by the specific logical block as specified in Section 3.

DISCUSSION

This non-normative subsection discusses and provides examples of the use of quaternion tags in the APM.

The XML representations of quaternions in the ADM constituent messages share a common quaternion definition. However, there are some differences in those definitions in the underlying KVN definitions of the APM and AEM. The following examples are meant to illustrate the standard for representing quaternions in the APM.

Here is an example APM quaternion construct:

```
      <quaternionState>
        <EPOCH>2004-100T00:00:00Z</EPOCH>
        <REF_FRAME_A>ICRF</REF_FRAME_A>
        <REF_FRAME_B>ICRF</REF_FRAME_B>
        <quaternion>
          <Q1>0.00005</Q1>
          <Q2>0.87543</Q2>
          <Q3>0.40949</Q3>
          <QC>0.25678</QC>
        </quaternion>
      </quaternionState>
```

Here is an example APM quaternion construct with the optional derivative:

```
      <quaternionState>
        <EPOCH>2004-100T00:00:00Z</EPOCH>
        <REF_FRAME_A>ICRF</REF_FRAME_A>
        <REF_FRAME_B>ICRF</REF_FRAME_B>
        <quaternion>
         <Q1>0.00005</Q1>
         <Q2>0.87543</Q2>
         <Q3>0.40949</Q3>
         <QC>0.25678</QC>
        </quaternion>
        <quaternionDerivative>
         <Q1_DOT>0.002</Q1_DOT>
         <Q2_DOT>0.003</Q2_DOT>
         <Q3_DOT>0.004</Q3_DOT>
         <QC_DOT>0.001</QC_DOT>
        </quaternionDerivative>
      </quaternionState>
```

6.7 CREATING AN AEM INSTANTIATION

An AEM instantiation shall be delimited with the `<aem></aem>` root element tags using the standard attributes documented in 0.

NOTE – Figures <<TBD>> provide example AEM instantiations.

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The final attributes of the `<aem>` tag shall be ‘id’ and ‘version’; the order in which these attributes are specified is not significant.

The ‘id’ attribute shall be ‘id="CCSDS_AEM_VERS"’.

The ‘version’ attribute for the version of the AEM shall be ‘version="2.0"’.

The standard ADM/XML header shall follow the `<aem>` tag (see 0).

The AEM `<body>` shall consist of one or more `<segment>` constructs (see [5], section 3.4).

The keywords in the `<metadata>` and `<data>` sections shall be those specified in Section 4.2ERROR! REFERENCE SOURCE NOT FOUND..

Tags for keywords shall be all uppercase as in Section 4.2.

Commented [LA25]: Number to be checked

Although units are not specified in the KVN representation of the AEM, several of the AEM/XML keywords may have a unit attribute, if desired by the AEM producer, as illustrated in the following table:

Table 6-4 AEM XML Units

Keyword	Units	Example
Q1_DOT	1/s	`<Q1_DOT units="1/s">numeric-value</Q1_DOT>`
Q2_DOT	1/s	`<Q2_DOT units="1/s">numeric-value</Q2_DOT>`
Q3_DOT	1/s	`<Q3_DOT units="1/s">numeric-value</Q3_DOT>`
QC_DOT	1/s	`<QC_DOT units="1/s">numeric-value</QC_DOT>`
ANGLE_1	deg	`<ANGLE_1 units="deg">numeric-value</ANGLE_1>`
ANGLE_2	deg	`<ANGLE_2 units="deg">numeric-value</ANGLE_2>`
ANGLE_3	deg	`<ANGLE_3 units="deg">numeric-value</ANGLE_3>`
ANGLE_1_DOT	deg/s	`<ANGLE_1_DOT units="deg/s">numeric-value</ANGLE_1_DOT>`
ANGLE_2_DOT	deg/s	`<ANGLE_2_DOT units="deg/s">numeric-value</ANGLE_2_DOT>`
ANGLE_3_DOT	deg/s	`<ANGLE_3_DOT units="deg/s">numeric-value</ANGLE_3_DOT>`
ANGVEL_X	deg/s	`<ANGVEL_X units="deg/s">numeric-value</ANGVEL_X>`
ANGVEL_Y	deg/s	`<ANGVEL_Y units="deg/s">numeric-value</ANGVEL_Y>`
ANGVEL_Z	deg/s	`<ANGVEL_Z units="deg/s">numeric-value</ANGVEL_Z>`
SPIN_ALPHA	deg	`<SPIN_ALPHA units="deg">numeric-value</SPIN_ALPHA>`
SPIN_DELTA	deg	`<SPIN_DELTA units="deg">numeric-value</SPIN_DELTA>`
SPIN_ANGLE	deg	`<SPIN_ANGLE units="deg">numeric-value</SPIN_ANGLE>`
SPIN_ANGLE_VEL	deg/s	`<SPIN_ANGLE_VEL units="deg/s">numeric-value</SPIN_ANGLE_VEL>`
NUTATION	deg	`<NUTATION units="deg">numeric-value</NUTATION>`
NUTATION_PER	s	`<NUTATION_PER units="s">numeric-value</NUTATION_PER>`
NUTATION_PHASE	deg	`<NUTATION_PHASE units="deg">numeric-value</NUTATION_PHASE>`

SPECIAL TAGS IN the AEM BODY

NOTE – In addition to the AEM keywords specified in Section 4.2, there are several special tags associated with the AEM body as described in the next few subsections.

The <attitudeState> tag shall be used to encapsulate the keywords associated with the structure of one of the attitude ephemeris data line types.

The ADM/XML tags used within the `<attitudeState>` structure shall be drawn from the following table:

Table 6-5 Special Tags in the AEM/XML Body

AEM 'ATTITUDE_TYPE' Metadata Value	**Associated ADM/XML Tag in the `<attitudeState>`**
QUATERNION	`<quaternionState>`
QUATERNION/DERIVATIVE	`<quaternionDerivative>`
QUATERNION/ANGVEL	`<quaternionAngvel>`
EULER_ANGLE	`<eulerAngle>`
EULER_ANGLE/DERIVATIVE	`<eulerAngleDerivative>`
EULER_ANGLE/ANGVEL	`<eulerAngleAngvel>`
SPIN	`<spin>`
SPIN/NUTATION	`<spinNutation>`

Between the begin tag and end tag (e.g., between `<quaternionState>` and `</quaternionState>`), the user shall place the values required by the specific ephemeris data line type as specified in Section 4.2.5, Table 4-4.

In the XML representation of the AEM, the components of the `<attitudeState>` ephemeris data line must be represented with keywords (i.e., a tag).

The `<attitudeState>` keywords shall be the same as those defined for the same construct in the APM.

NOTE – In the KVN representations of the ephemeris data lines, keywords are not used. Rather, the components of the ephemeris data line appear in an order defined by the specific ephemeris data line type. In the XML representation, the tags described are fundamental to the format.

DISCUSSION

This non-normative subsection discusses and provides examples of the use of quaternion tags in the AEM.

The XML representations of quaternions in the ADM constituent messages share a common quaternion definition. However, there are some differences in those definitions in the underlying KVN definitions of the APM and AEM. As in the KVN representation of the quaternion, it is possible to code the tags for the individual components of the quaternion (Q1, Q2, Q3, QC) in either of the standard orders (i.e., scalar component first or last). The following examples are meant to illustrate the standard for representing quaternions in the AEM.

Here is an example AEM quaternion for a 'QUATERNION' ephemeris data line:

```
      <attitudeState>
        <quaternionState>
         <EPOCH>2004-100T00:00:00</EPOCH>
         <quaternion>
           <Q1>0.00005</Q1>
           <Q2>0.87543</Q2>
           <Q3>0.40949</Q3>
```

```
           <QC>0.25678</QC>
         </quaternion>
        </quaternionState>
      </attitudeState>
```

Here is an example AEM quaternion for a ‘QUATERNION/DERIVATIVE’ ephemeris data line:

```
      <attitudeState>
        <quaternionDerivative>
         <EPOCH>2004-100T00:00:00</EPOCH>
         <quaternion>
           <Q1>0.00005</Q1>
           <Q2>0.87543</Q2>
           <Q3>0.40949</Q3>
           <QC>0.25678</QC>
         </quaternion>
         <quaternionDerivative>
           <Q1_DOT>0.002</Q1_DOT>
           <Q2_DOT>0.003</Q2_DOT>
           <Q3_DOT>0.004</Q3_DOT>
           <QC_DOT>0.001</QC_DOT>
         </quaternionDerivative>
        </quaternionDerivative>
      </attitudeState>
```

6.8 CREATING AN ACM INSTANTIATION

SECTION FORTHCOMING AS THE ACM IS DEFINED... NOTHING TO ADD AT THIS TIME.

~~5~~7 ATTITUDE DATA MESSAGES KVN SYNTAX

~~5.1~~7.1 INTRODUCTION

This section details the syntactic~~al~~ requirements for attitude messages. All APM and AEM messages shall observe the syntax described in subsections 5.2 through 5.8.

~~5.2~~7.2 APM

The APM shall be a plain text file, using keyword descriptions given in 3.2.1 through 3.2.6.

~~5.3~~7.3 AEM

The AEM shall be a plain text file, using the keyword descriptions given in 4.2.1 through ~~4.2.6~~ 4.2.5.

7.4 ACM

The ACM shall be a plain text file, using the keywords given in 5.2.1 through 5.2.7.

~~5.4~~7.5 LINES

Each APM, ~~and~~ AEM, or ACM line must not exceed 254 ASCII characters and spaces (excluding line termination character[s]).

Only printable ASCII characters and blanks shall be used. Control characters (such as TAB, etc.) shall not be used, except as indicated below for the termination of lines.

Blank lines may be used at any position within the file.

Comment lines shall be optional. See 7.9.2~~5.8.2~~ for details regarding the placement of comment lines in an APM. See 7.9.3~~5.8.3~~ for details regarding the placement of comment lines in an AEM. See 7.9.4 for details regarding the placement of comment lines in an ACM.

APM, ~~and~~ AEM, and ACM lines shall be terminated by a single Carriage Return or a single Line Feed, or a Carriage Return/Line Feed pair or a Line Feed/Carriage Return pair.

~~5.5~~7.6 KEYWORDS

All header, metadata, and APM data lines, with exceptions as noted in 0~~5.5.8~~, shall use ‘keyword = value’ notation, abbreviated as KVN.

Only a single ‘keyword = value’ assignment shall be made on a line.

Keywords must be uppercase and must not contain blanks.

Any white space immediately preceding or following the keyword shall not be significant.

Any white space immediately preceding or following the ‘equals’ sign shall not be significant.

Any white space immediately preceding the end of line shall not be significant.

The order of occurrence of ~~obligatory~~ mandatory and optional KVN assignments shall be fixed as shown in tables 3-1~~3-1~~, 3-2~~3-2~~, and 3-3~~3-3~~ for the APM, ~~and~~ as shown in tables 4-2~~4-2~~ and 4-3~~4-3~~ for the AEM, and as shown in tables 5-2 through 5-9 for the ACM.~~–~~ ~~Exceptions to this rule for the APM shall be for quaternion and Euler angle ordering, as described in 3.2.5.~~

The keywords COMMENT, META_START, META_STOP, DATA_START and DATA_STOP, QUAT_START, QUAT_STOP, EULER_START, EULER_STOP, ANGVEL_START, ANGVEL_STOP, SPIN_START, SPIN_STOP, INERTIA_START, INERTIA_STOP and AEM data lines are exceptions to the KVN syntax.

~~5.6~~7.7 VALUES

Angle measurements shall be given in degrees, with values between -360 and 360 degrees. ~~The range of values for angle measurements is -360 degrees <= x <= 360 degrees.~~ If agencies wish to exchange using radians, this must be specified in an ICD because it is nominally outside the standard.

Blanks shall not appear within numeric values and time values.

~~Integer values shall consist of a sequence of decimal digits with an optional leading sign (‘+’ or ‘-’). If the sign is omitted, ‘+’ shall be assumed. Leading zeros may be used. The range of values that may be expressed as an integer is:~~

~~-2 147 483 648 <= x <= +2 147 483 647 (i.e., -2^{31} <= x <= 2^{31}-1).~~Integer values shall consist of a sequence of decimal digits with an optional leading sign (‘+’ or ‘-’). If the sign is omitted, ‘+’ shall be assumed. Leading zeroes may be used. The range of values that may be expressed as an integer is:

−2,147,483,648 ≤ x ≤ +2,147,483,647 (i.e., -2^{31} <= x <= 2^{31}-1)

NOTE – The commas in the range of values above are thousands separators and are used only for readability. They should not appear in an actual message.

Non-integer numeric values may be expressed in either fixed-point or floating-point notation. Both representations may be used within an APM or an AEM.

Commented [LA26]: Comma not added because I found this :

Numbers consisting of long sequences of digits can be made more readable by separating them into groups, preferably groups of three, separated by a small space. For this reason, ISO 31-0 specifies that such groups of digits should never be separated by a comma or point, as these are reserved for use as the decimal sign.

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Non-integer numeric values expressed in fixed-point notation shall consist of a sequence of decimal digits separated by a period as a decimal point indicator, with an optional leading sign (‘+’ or ‘-’). If the sign is omitted, ‘+’ shall be assumed. Leading and trailing zeros may be used. At least 1 digit is required before and after a decimal point. The number of digits shall be 16 or fewer.

Non-integer numeric values expressed in floating-point notation shall consist of a sign, a mantissa, an alphabetic character indicating the division between the mantissa and exponent, and an exponent, constructed according to the following rules:

– The sign may be ‘+’ or ‘-’. If the sign is omitted, ‘+’ shall be assumed.

– The mantissa must be a string of no more than 16 decimal digits with a decimal point ‘.’ in the second position of the ASCII string, separating the integer portion of the mantissa from the fractional part of the mantissa.

– The character used to denote exponentiation shall be ‘E’ or ‘e’. If the character indicating the exponent and the following exponent are omitted, an exponent value of zero shall be assumed (essentially yielding a fixed-point value).

– The exponent must be an integer, and may have either a ‘+’ or ‘-’ sign (if the sign is omitted, then ‘+’ shall be assumed).

– The maximum positive floating-point value is approximately 1.798E+308, with precision of 16 significant decimal digits. The minimum positive floating-point value is approximately 4.94E-324, with precision of 16 significant decimal digits.

These specifications for integer, fixed-point, and floating-point values conform to the XML specifications for the data types four-byte integer ‘xsd:int’, ‘xsd:decimal’ and ‘xsd:double’ respectively. The specifications for floating-point values conform to the IEEE double precision type (reference [6]~~[6]~~). Floating-point numbers in IEEE extended-single or IEEE extended-double precision may be represented, but do require an ICD between participating agencies because of their implementation-specific attributes (reference [6]~~[6]~~). Note that NaN, +Inf, -Inf, and -0 are not supported values.

Text value fields must be constructed using only all uppercase or all lowercase.

A non-empty value field must be specified for each keyword provided, except as noted in 0~~5.5.8~~.

In value fields that are text, an underscore shall be equivalent to a single blank. Individual blanks between non-blank characters shall be retained (shall be significant) but multiple blanks shall be equivalent to a single blank.

In value fields that represent a timetag or epoch, one of the following two formats shall be used:

YYYY-MM-DD:Thh:mm:ss[.d→d][Z]

or

YYYY-DDDThh:mm:ss[.d→d][Z]

where ‘YYYY’ is the year, ‘MM’ is the two-digit month, ‘DD’ is the two-digit day, ‘DDD’ is the three-digit day of year, ‘T’ is constant, ‘hh:mm:ss[.d→d] is the time in hours, minutes seconds, and optional fractional seconds; ‘Z’ is an optional time code terminator (the only permitted value is ‘Z’ for Zulu, i.e., UTC).~~–~~ All fields shall have leading zeros.~~–~~ See reference [4]~~[4]~~, ASCII Time Code A and B.

~~5.7~~7.8 UNITS

~~5.7.1~~7.8.1 APM RESTRICTIONS

For clarity, units may be included as ASCII text after a value, but they must exactly match the units specified in table 3-3~~3-3~~ (including case).~~–~~ If units are displayed, then:

a) there must be at least one blank character between the value and the units text;

b) the units must be enclosed within square brackets (e.g., ‘[deg]’);

c) multiplication of units shall be denoted with a single asterisk ‘*’ (e.g., ‘[N*m]’).

d) exponents of units shall be denoted with a double asterisk ‘**’ (e.g., ‘[kg*m**2]’).

~~5.7.2~~7.8.2 AEM RESTRICTIONS

Units shall not be displayed; the applicable units are determined by the value set for the ATTITUDE_TYPE keyword. See 0.

~~5.8~~7.9 COMMENTS

~~5.8.1~~7.9.1 GENERAL

All comment lines shall begin with the ‘`COMMENT`’ keyword followed by at least one space. This keyword must appear on every comment line, not just the first such line.~~–~~ The remainder of the line shall be the comment value.~~–~~ White space shall be retained (shall be significant) in comment values.

Comments may be used to provide provenance information or to help describe dynamical events or other pertinent information associated with the data.~~–~~ This additional information is intended to aid in consistency checks and elaboration where needed, but shall not be required for successful processing of a file.

If accompanying descriptive text designed to clarify and/or remove ambiguities in provided ADM data does not fit well into the single comment line paradigm, it is recommended that the

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APM or AEM producer convey key elements of that information in comments and use an ICD to provide further details.

~~The following comment should be provided in an APM or AEM message: information regarding the genesis, history, interpretation, intended use, etc., of the attitude state and any additional information that may be of use to the receiver of the APM or AEM. Example:~~

```
~~COMMENT  Source: File created by GSFC Flight Dynamics Facility as part~~
~~COMMENT  of Launch Operations Readiness Test held on 15 July 2004.~~
```

~~5.8.2~~7.9.2 APM SPECIFIC

Comments are optional and may appear only at the beginning of the APM Header and APM Metadata sections, as shown in tables 3-1~~3-1~~ and 3-2~~3-2~~. In the APM Data section, comments shall appear only at the beginning of a logical block. Comments must not appear between the components of any logical block in the APM Data section. The logical blocks in the APM Data section are indicated in table 3-3~~3-3~~.

~~The following type of comment may be provided as part of the APM to provide information regarding the attitude estimation accuracy:~~

```
~~COMMENT  The 1-sigma accuracy determined by the GSFC Flight~~
~~COMMENT  Dynamics Facility for this attitude solution was~~
~~COMMENT  [0.02670  0.00945  0.00832] DEG.~~
```

~~The purpose of this comment is to enable some specification on the quality of the attitude estimate. The interpretation of the message or the values placed herein should be specified in an ICD.~~

~~5.8.3~~7.9.3 AEM SPECIFIC

~~5.8.3.1~~7.9.3.1 General

Comments are optional and may appear only after the specification of the keyword CCSDS_AEM_VERS, at the beginning of Metadata sections (only after META_START and before OBJECT_NAME), and immediately following the DATA_START keyword. Comments must not appear between attitude ephemeris data lines, nor after the DATA_STOP keyword.

7.9.4 ACM SPECIFIC

Comments are optional and may appear at the beginning of the ACM Header, ACM Metadata section, and after the start of each included ACM Data block as shown in tables 5-4 through 5-9.

8 ATTITUDE DATA MESSAGES XML SYNTAX

NOTE: Could be put in Section 7 also (i.e., one syntax section, divided between KVN and XML.

8.1 OVERVIEW

XML instantiations of an ADM shall observe the syntax described in this chapter.

8.2 ADM LINES IN XML

Each ADM file shall consist of a set of ADM lines. Each ADM line shall be one of the following:

- XML version line;
- an XML-formatted line; or
- a blank line.

Each ADM line must not exceed 254 ASCII characters and spaces (excluding line termination character[s]). [Question: Different limit for ACM?]

Only printable ASCII characters and blanks shall be used. Control characters (such as TAB, etc.) shall not be used, with the exception of the line termination characters specified below. [Note: Frank has recommended as statement/requirement regarding XML "escaped" characters such as & < > " ', but it is not yet clear what the statement/requirement should be.]

Blank lines may be used at any position within the file. Blank lines shall have no assignable meaning, and may be ignored.

All lines shall be terminated by a single Carriage Return or a single Line Feed, or a Carriage Return/Line Feed pair or a Line Feed/Carriage Return pair.

8.3 VALUES IN THE ADM/XML

Each mandatory XML tag must be present and contain a valid value.

Integer values shall follow the conventions of the integer data type per Reference [reference here to XML datatypes document [9] (see above)]. Additional restrictions on the allowable range of values permitted for any integer data element may also be defined in the ADM XML Schema.

NOTE – Examples of such restrictions may include a defined range (e.g., 0 - 100, 1 - 10, etc.), a set of enumerated values (e.g., 0,1,2,4,8), a pre-defined specific variation such as positiveInteger, or a user-defined data type variation.

Non-integer numeric values may be expressed in either fixed-point or floating-point notation. Numeric values shall follow the conventions of the double data type per Reference [reference here to XML datatypes document [9] (see above)]. Additional restrictions on the allowable range of values permitted for any numeric data element may also be defined in the ADM XML Schema.

NOTE – Examples of such restrictions may include a defined range (e.g., 0.0-100.0, etc.), or a user-defined data type variation.

Text values shall follow the conventions of the string data type per Reference [reference here to XML datatypes document [9] (see above)]. Additional restrictions on the allowable range or values permitted for any data element may also be defined in the ADM XML Schema.

NOTE – Examples of such restrictions may include a set of enumerated values (e.g., ‘YES’/‘NO’) or other user-defined data type variation.

Text values in ADM/XML instantiations (i.e., the values between the opening and closing tags), shall consist of either all uppercase or all lowercase characters; an exception is made for values between the `<COMMENT>` and `</COMMENT>` tags, which may be in any case desired by the user. Otherwise, instantiations shall not mix uppercase and lowercase characters in values.

In value fields that represent a time tag, values shall follow the conventions of the ndm:epochType data type used in all CCSDS NDM/XML schemas.

8.4 UNITS IN THE ADM/XML

The units in the ADM/XML shall be the same units used in the KVN-formatted ADM described in Sections 1 through **Error! Reference source not found.**. XML attributes shall be used to explicitly define the units or other important information associated with the given data element (see Annex C for examples).

8.5 COMMENTS IN ADM/XML

Comments are optional and must be displayed as values between the `<COMMENT>` and `</COMMENT>` tags. Comments may be in any case desired by the user.

NOTE to Alain: Examples forthcoming...

Commented [LA28]: Examples forthcoming

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~~5.8.3.2 AEM Accuracy vs. Efficiency~~

~~The producer of an AEM may optionally report in comment lines the expected accuracy of the attitude ephemeris. The user may then use this additional information to smooth or otherwise compress the data without affecting the accuracy of the attitude, but is not required to utilize~~

~~this information to successfully process the message. The AEM producer also should strive to achieve not only the best accuracy possible, taking into account prediction errors, but also consider the efficiency of the attitude representation (e.g., step sizes of fractional seconds between attitude ephemeris lines may be necessary for precision scientific reconstruction of an attitude, but may be excessive in some cases).~~

ANNEX A

IMPLEMENTATION CONFORMANCE STATEMENT (ICS) PROFORMA

(NORMATIVE)

A1 INTRODUCTION

A1.1 OVERVIEW

This annex provides the Implementation Conformance Statement (ICS) Requirements List (RL) for an implementation of the Attitude Data Message~~[Specification]~~.~~–~~ The ICS for an implementation is generated by completing the RL in accordance with the instructions below. An implementation claiming conformance must satisfy the mandatory requirements referenced in the RL.

A1.2 ABBREVIATIONS AND CONVENTIONS

The RL consists of information in tabular form.~~–~~ The status of features is indicated using the abbreviations and conventions described below.

Item Column

The item column contains sequential numbers for items in the table.

Feature Column

The feature column contains a brief descriptive name for a feature. It implicitly means “Is this feature supported by the implementation?”

Status Column

The status column uses the following notations:

– M	mandatory;
– O	optional;
– C	conditional;
– X	prohibited;
– I	out of scope;
– N/A	not applicable.

Support Column Symbols

The support column is to be used by the implementer to state whether a feature is supported by entering Y, N, or N/A, indicating:

Y	Yes, supported by the implementation.
N	No, not supported by the implementation.
N/A	Not applicable.

The support column should also be used, when appropriate, to enter values supported for a given capability.

A1.3 INSTRUCTIONS FOR COMPLETING THE RL

An implementer shows the extent of compliance to the Recommended Standard by completing the RL; that is, the state of compliance with all mandatory requirements and the options supported are shown. The resulting completed RL is called an ICS. The implementer shall complete the RL by entering appropriate responses in the support or values supported column, using the notation described in A1.2.~~–~~ If a conditional requirement is inapplicable, N/A should be used. If a mandatory requirement is not satisfied, exception information must be supplied by entering a reference X*i*, where *i* is a unique identifier, to an accompanying rationale for the noncompliance.

A2 ICS PROFORMA FOR THE ATTITUDE DATA MESSAGE~~[SPECIFICATION]~~

A2.1 GENERAL INFORMATION

A2.1.1 Identification of ICS

Date of Statement (DD/MM/YYYY)	
ICS serial number	
System Conformance statement cross-reference	

A2.1.2 Identification of Implementation Under Test

Implementation Name	
Implementation Version	
Special Configuration	
Other Information	

A2.1.3 Identification of Supplier

Supplier	
Contact Point for Queries	
Implementation Name(s) and Versions	
Other information necessary for full identification, e.g., name(s) and version(s) for machines and/or operating systems; System Name(s)	

A2.1.4 Identification of Specification

504.0-B-2 ~~[CCSDS Document Number]~~	
Have any exceptions been required? NOTE – A YES answer means that the implementation does not conform to the Recommended Standard. Non-supported mandatory capabilities are to be identified in the ICS, with an explanation of why the implementation is non-conforming.	Yes [ ] No [ ]

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A2.2 REQUIREMENTS LIST

[See CCSDS A20.1-Y-1, *CCSDS Implementation Conformance Statements* (Yellow Book, Issue 1, April 2014).]

ANNEX B

VALUES FOR SELECTED KEYWORDS

(NORMATIVE)

B1 OVERVIEW

The values in this annex represent the acceptable values for selected keywords. Each keyword’s values delineated here are present in either an APM or AEM message. For details and descriptions of the keyword interpretations, the reader is directed to reference [H2]~~[H4]~~. If exchange partners wish to use different settings, they should be documented in an ICD.

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Field Code Changed

B2 TIME_SYSTEM METADATA KEYWORD

TIME_SYSTEM Value	Meaning/Description
GMST	Greenwich Mean Sidereal Time
GPS	Global Positioning System
MET	Mission Elapsed Time
MRT	Mission Relative Time
SCLK	Spacecraft Clock (receiver)
TAI	International Atomic Time
TCB	Barycentric Coordinated Time
TDB	Barycentric Dynamical Time
TT	Terrestrial Time
UT1	Universal Time
UTC	Coordinated Universal Time

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Note that if MET or MRT are chosen as the TIME_SYSTEM, then the epoch of either the start of the mission for MET, or of the event for MRT, should either be given in a comment in the message, or provided in an ICD. The time system for the start of the mission or the event should also be provided in the comment or the ICD. If these values are used for the TIME_SYSTEM, then the times given in the file denote a duration from the mission start or event. However, for clarity, an ICD should be used to fully specify the interpretation of the times if these values are to be used. Note that the time format should only utilize three digit days from the MET or MRT epoch, not months and days of the months.

Note that if SCLK is chosen as a TIME_SYSTEM, the transformation of this time to one of the other specified time systems in B2 should be given in an ICD. The intent of this keyword is to allow for the use of SCLK as a TIME_SYSTEM, but there is currently no standard way to transform this time system to other time systems listed in B2.

B3 INERTIAL AND LOCAL ORBITAL FRAME KEYWORD VALUES

The following table enumerates the allowable keywords for ~~inertial~~ reference frames that can be used by ADM messages. They are valid for keywords~~:~~ REF_FRAME_* in the APM and AEM messages, where '*' denotes 'A' or 'B'.~~Q_FRAME_*, EULER_FRAME_*, and SPIN_FRAME_* in an APM, and REF_FRAME_* in an AEM, where '*' denotes 'A' or 'B'.~~

Keyword Value	Meaning/Description
EME2000	Earth Mean Equator and Equinox of J2000
GTOD	Greenwich True of Date
ICRF	International Celestial Reference Frame
ITRF2000	International Terrestrial Reference Frame 2000
ITRF-93	International Terrestrial Reference Frame 1993
ITRF-97	International Terrestrial Reference Frame 1997
ITRF	International Terrestrial Reference Frame
ITRFyyyy	International Terrestrial Reference Frame associated to year yyyy
J2000	Earth Mean Equator and Equinox of J2000
LVLH	Local Vertical Local Horizontal
RTN, QSW	Radial, Transverse, Normal Orbital Frame
TOD	True of Date
TNW, NTW	Tangential, Normal, Omega (W) Orbital Frame
RSW	Relative Orbit Frame describing the relative motion of two satellites (Clohessy-Wiltshire Equations)

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B4 LOCAL SPACECRAFT BODY REFERENCE FRAMES

The following table enumerates the allowed values for the keyword REF_FRAME_* in the APM and AEM messages, where ‘*’ denotes ‘A’ or ‘B’.~~–~~ These frames will vary from object to object, but provide a mechanism of denoting different reference frames than the object’s BODY axes to specify an orientation.~~—~~ ~~It is the responsibility of the end user to have an understanding of the location of these frames for their particular object,~~The exact specification of the frames (position of center, orientation) should be~~-~~ defined ~~typically via~~ in an ICD.

Keyword Value	Meaning/Description
ACTUATOR_x	Actuator reference frame (‘x’ = 0→9): could denote reaction wheels, solar arrays, thrusters, etc.
AST_x	Autonomous Star Tracker (‘x’ = 0-9)
CSS_xy	Coarse Sun Sensor (‘x’ = 0→9, ‘y’ = 0→9)
DSS_x	Digital Sun Sensor (‘x’ = 0→9)
GYRO_x	Gyroscope Reference Frame (‘x’ = 0→9)
INSTRUMENT_y	Instrument ‘y’ reference frame (‘y’ = A→Z, 0→9)
SC_BODY_x	Spacecraft Body Frame (‘x’ = 0→9)
SC_BODY_y	Spacecraft Body Frame of another object (‘y’ = A→Z)
SENSOR_x	Sensor ‘x’ reference frame (‘x’ = A→Z, 0→9)
STARTRACKER_x	Star Tracker Reference Frame (‘x’ = 0→9)
TAM_x	Three Axis Magnetometer Reference Frame (‘x’ = 0→9)

B5 ATTITUDE AND RATE TYPES

The following table enumerates the allowed values for the keywords associated with ATT_TYPE and RATE_TYPE in the ACM.

Keyword Value	Meaning/Description
QUATERNION	Coordinate transformation represented as a quaternion
EULER_ANGLES	Coordinate transformation represented with three successive rotations

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DCM	Coordinate transformation represented as a 3x3 matrix
ANGVEL	Angular velocity vector
Q_DOT	Rate of change of the quaternion
EULER_RATE	Time derivative of the Euler angles
GYRO_BIAS	Correction to gyro estimated angular velocity

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B6 ESTIMATOR TYPES

The following table enumerates the allowed values for the keyword AD_METHOD in the ACM:

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EKF	Extended Kalman Filter, a sequential estimation algorithm applied to spacecraft attitude determination. Often additional state vector components are included, such as gyro biases.
TRIAD	TRIAxial Attitude Determination, an algebraic method for determination of spacecraft attitude from a set of two vector observations.
QUEST	Quaternion ESTimator, an efficient, deterministic algorithm to estimate a spacecraft attitude quaternion.
BATCH	A batch least squares algorithm to estimate spacecraft attitude, and optionally additional sensor parameters such as alignments, biases, scale factors.
Q METHOD	Considered the best deterministic algorithm to estimate a spacecraft attitude quaternion. Requires use of an eigenvalue decomposition algorithm.
FILTER_SMOOTHER	A method to smooth noisy processes. Several smoothing approaches exist such as fixed-point, fixed-lag, and fixed-interval. Used in ground applications to produce fine attitude estimates for post-processing applications.

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B7 NORMATIVE REFERENCES FOR ATTITUDE AND SPACECRAFT CONVENTIONS

[B-1] SANA Registry of Attitude and Spacecraft Conventions: https://sanaregistry.org/r/attitude_and_spacecraft_conventions

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ANNEX C

CONVENTIONS FOR ADM DATA

(INFORMATIVE)

C1 OVERVIEW

This paragraph details the conventions used in this document for the definition of Attitude data.

C2 QUATERNIONS

The quaternion called "from frame A to frame B" is defined as the quaternion of the rotation that transforms the basis vectors of frame A into the basis vectors of frame B. That is to say that the basis vectors of frame B are the respective images of the basis vectors of frame A by the rotation.

The quaternion is defined by four components:

Q~~q~~1 = sin(ϕ/2) * e1

Q~~q~~2 = sin(ϕ/2) * e2

Q~~q~~3 = sin(ϕ/2) * e3

~~qc~~ QC = cos(ϕ/2)

Where:

ϕ is the rotation angle,

e1, e2 and e3 are the coordinates of the rotation axis in either frame A or frame B.

The quaternion is related to the frame transformation matrix in the following way:

Let X_A be the coordinates of some vector in frame A, and X_B the coordinates of the same vector in frame B.

The frame transformation matrix M_{BA} that transforms coordinates in frame A to coordinates in frame B is defined by:

$$X_B = M_{BA} * X_A$$

where M_{BA} is a function of the quaternion components:

$$M_{BA} = \begin{bmatrix} \cancel{q}Q_1^2 - Q\cancel{q}_2^2 - Q\cancel{q}_3^2 + Q\cancel{q}_c^2 & 2\,(Q_1\,Q_2\cancel{q_1\,q_2} + Q_3\cancel{q_3}\,Q_c\cancel{q_c}) & 2\,(Q_1\cancel{q_1}\,Q_3\cancel{q_3} - Q_2\cancel{q_2}\,Q_c\cancel{q_c}) \\ 2\,(Q\cancel{q}_1\,Q\cancel{q}_2 - Q\cancel{q}_3\,Q\cancel{q}_c) & -Q_1^2\cancel{q_1^2} + Q_2^2\cancel{q_2^2} - Q_3^2\cancel{q_3^2} + Q_c^2\cancel{q_c^2} & 2\,(Q_2\cancel{q_2}\,Q_3\cancel{q_3} + Q_1\cancel{q_1}\,Q_c\cancel{q_c}) \\ 2\,(Q_1\cancel{q_1}\,Q_3\cancel{q_3} + Q_2\cancel{q_2}\,Q_c\cancel{q_c}) & 2\,(Q_2\,\cancel{q_2}Q_3\cancel{q_3} - Q_c\cancel{q_1}\,Q_c\cancel{q_c}) & -Q_1^2\cancel{q_1^2} - Q_2^2\cancel{q_2^2} + Q_3^2\cancel{q_3^2} + Q_c^2\cancel{q_c^2} \end{bmatrix}$$

The real component (~~qc~~QC) of the quaternion ~~shall~~ should be made non negative by convention.

C3 EULER ANGLES

The Euler angles called "from frame A to frame B" are the rotation angles of the 3 successive rotations that transform frame A into frame B.

Let's call θ1, θ2, θ3 the 3 rotation angles, and a1, a2, a3 the respective rotation axes (X-axis, Y-axis, or Z-axis). The images of the basis vectors of frame A by the 3 successive rotations of angle θ1 and axis a1, angle θ2 and axis a2, angle θ3 and axis a3 are the respective basis vectors of frame B.

Example:

Let's consider the 3 successive rotations around axes a1=X, a2=Y, a3=Z of respective angles θ1, θ 2, θ3.

Let's define the frame transformation matrix M such that:

X_B = M_{BA}~~M~~ * X_A

where X_A denotes the coordinates of some vector in frame A, and X_B the coordinates of the same vector in frame B.

Then we have:

$$M_{BA}\cancel{M} = \begin{bmatrix} cos\theta_3 & sin\theta_3 & 0 \\ -sin\theta_3 & cos\theta_3 & 0 \\ 0 & 0 & 1 \end{bmatrix} . \begin{bmatrix} cos\theta_2 & 0 & -sin\theta_2 \\ 0 & 1 & 0 \\ sin\theta_2 & 0 & cos\theta_2 \end{bmatrix} . \begin{bmatrix} 1 & 0 & 0 \\ 0 & cos\theta_1 & sin\theta_1 \\ 0 & -sin\theta_1 & cos\theta_1 \end{bmatrix}$$

C4 ANGULAR VELOCITY VECTOR

The angular velocity vector from frame A to frame B represents the angular velocity vector of ~~FRAME~~ frame B with respect to frame A.

The components can be defined either in ~~F~~frame A or frame B.

C5 SPIN DATA

The spin data enable the user of the message to propagate the attitude of an object using a simple model.

The spin data from frame A to frame B are defined as follows:

The spin axis is the Z axis of frame B, a principal axis.

The initial attitude is defined as the result of 3 successive rotations of respective angles spin_alpha, spin_delta, spin_angle around the successive axes Z, Y, Z starting from frame A.

Nutation_angle is the angle between the principal axis (spin axis) and angular momentum.

Nutation_phase describes the initial orientation of the spin axis in his motion around the angular momentum vector.

The following ~~assumption~~ is assumed:

The angular momentum vector has components in the frame B:

- alpha, delta
- Pi/2 - delta is the nutation angle
- Alpha - pi is the offset angle

C6 INERTIA DATA

Inertia data consist of:

- Moments of inertia (diagonal terms)

- Inertial cross products (off diagonal terms)

$$I = \begin{bmatrix} IXX\sout{11} & -IXY\sout{12} & -IXZ\sout{13} \\ -IXY\sout{12} & \sout{-}IYY\sout{22} & -IYZ\sout{23} \\ -IXZ\sout{13} & -IYZ\sout{23} & \sout{-}IZZ\sout{33} \end{bmatrix}$$

The cross product terms are negative.

The inertia matrix is defined relative to a particular frame (defined by its axis and origin).

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ANNEX D

LIST OF CHANGES VERSUS ADM VERSION 1

(INFORMATIVE)

The present section gives the main changes between ADM 1.0 and ADM 2.

Changes relative to APM-:

Number	Description	See section
1~~2~~	The "*_DIR" keywords have been removed	
2~~3~~	The quaternion block is now optional.	
3~~4~~	Any block can now be present as many times as necessary.	
4~~5~~	The meaning of quaternion, Euler angles, spin data, ...is now clearly defined by the standard. Any changes in meaning with respect to the standard should be detailed in an ICD.	
5~~6~~	Euler rotation sequences ("EULER_ROT_SEQ" keyword) are specified by letter (X, Y, Z) instead of number, e.g. XYX instead of 121.	
6~~7~~	The logical block "Euler angles" now contains angle derivatives rather than components of the angular velocity vector.	
7~~8~~	A new block for the angular velocity vector has been added: ANGVEL.	
8~~9~~	The keywords for the moments of inertia have changed: IXY instead of I12, etc...	
9~~10~~	Data blocks have been added. Data types such as quaternion, Euler angles... are explicitly enclosed between ~~DATA~~QUAT_START__~~—~~...__~~—~~ ~~DATA~~QUAT_STOP, EULER_START … EULER_STOP, etc delimiters.	
10	A new keyword: “MESSAGE_ID” has been added.	
11	Frame related keywords have changed in APM version 2: keywords in version 1 such as Q_FRAME_*,	

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	SPIN_FRAME_*, etc… (where * denotes “A” or “B”) have been removed. The keywords in version 2 are REF_FRAME_*.	
12	The keywords defining attitude direction (Q_DIR, EULER_DIR, SPIN_DIR) have been removed. The direction is always from A to B.	

Changes relative to AEM:

Number	Description	See section
1	Euler rotation sequences ("EULER_ROT_SEQ" keyword) are specified by letter (X, Y, Z) instead of number, e.g. XYX instead of 121.	
2	A new value has been introduced for the "ATTITUDE_TYPE" keyword: EULER_ANGLE/DERIVATIVE	
3	The order for quaternion components (real part first or last) is now imposed by the standard.	
4	The ATTITUDE_DIR keyword has been removed.	
5	A new keyword: “MESSAGE_ID” has been added.	
6	The keyword “QUATERNION_TYPE” has been removed. The order in the AEM is the same as in the APM: Q1, Q2, Q3, QC by convention. This change also make the KVN and XML versions more consistent.	
7	Values for the “ATTITUDE_TYPE” keyword have changed: - QUATERNION/RATE and EULER_ANGLE/RATE have been removed - QUATERNION_ANGVEL and EULER_ANGLE/ANGVEL have been added	

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ANNEX E

RATIONALE FOR ATTITUDE DATA MESSAGES

(INFORMATIVE)

E1 OVERVIEW

This annex presents the rationale behind the design of each message. It may help the application engineer to select a suitable message. Corrections and/or additions to these requirements are expected during future updates.

A specification of requirements agreed to by all parties is essential to focus design and to ensure the product meets the needs of the Member Agencies. There are many ways of organizing requirements, but the categorization of requirements is not as important as the agreement to a sufficiently comprehensive set. In this annex the requirements are organized into three categories:

a) Primary Requirements: These are the most elementary and necessary requirements. They would exist no matter the context in which the CCSDS is operating, i.e., regardless of pre-existing conditions within the CCSDS or its Member Agencies.

b) Heritage Requirements: These are additional requirements that derive from pre-existing Member Agency requirements, conditions, or needs. Ultimately these carry the same weight as the Primary Requirements. This Recommended Standard reflects heritage requirements pertaining to some of the technical participants' home institutions collected during the preparation of the document; it does not speculate on heritage requirements that could arise from other Member Agencies.

c) Desirable Characteristics: These are not requirements, but they are felt to be important or useful features of the Recommended Standard.

E2 PRIMARY REQUIREMENTS ACCEPTED BY THE ATTITUDE DATA MESSAGES

Table E-1:~~–~~ Primary Requirements

~~Requirement~~		~~Accepted for APM?~~	~~Acc for AEM?~~
~~Data must be provided in digital form (computer file).~~		~~Y~~	~~Y~~
~~The file specification must not require of the receiving agency the separate application of, or modeling of, spacecraft dynamics or gravitational force models, or integration or propagation.~~		~~N~~	~~Y~~
~~The interface must facilitate the receiver of the message to generate an attitude state at any required epoch.~~		~~Y~~	~~Y~~

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~~Attitude state information must be provided in a reference frame that is clearly identified and unambiguous.~~		~~Y~~	~~Y~~
~~Identification of the object must be clearly identified and unambiguous.~~		~~Y~~	~~Y~~

~~Identification of the center of attitude motion must be clearly identified and unambiguous.~~ ~~NOTE – – The specification of a center name is not required~~		~~N~~	~~N~~

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~~for the unambiguous specification of attitude but may be provide~~			

~~if desired.~~			
~~Time measurements (time stamps, time tags, or epochs) must be provided in a commonly used, clearly specified system.~~		~~Y~~	~~Y~~
~~The time bounds of the attitude ephemeris must be unambiguously specified.~~		~~N~~	~~Y~~
~~The standard must provide for clear specification of units of measure.~~		~~Y~~	~~Y~~

~~Files must be readily ported between, and useable within, *all* Member Agency computational environments that could be used to exchange Attitude Data Messages.~~		~~Y~~	~~Y~~
~~Files must have means of being uniquely identified and clearly annotated. The file name alone is considered insufficient for this purpose.~~		~~Y~~	~~Y~~
~~File name syntax and length must not violate computer constraints for those Member Agency computing environments that could be used to exchange Attitude Data Messages.~~		~~Y~~	~~Y~~

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Number	**Requirement**	**Accepted for APM?**	**Accepted for AEM?**
1	Data must be provided in digital form (computer file).	Y	
2	The file specification must not require of the receiving agency the separate application of, or modeling of, spacecraft dynamics or gravitational force models, or integration or propagation.	N	
3	The interface must facilitate the receiver of the message to generate an attitude state at any required epoch.	Y	
4	Attitude state information must be provided in a reference frame that is clearly identified and unambiguous.	Y	
5	Identification of the object must be clearly identified and unambiguous.	Y	
5	The possibility to identify the center of the reference frame must be provided.	Y	
8	Time measurements (time stamps, time tags, or epochs) must be provided in a commonly used, clearly specified system.	N	
9	The time bounds of the attitude ephemeris must be unambiguously specified.	Y	
10	The standard must provide for clear specification of units of measure.	Y	
11	Files must be readily ported between, and useable within, all Member Agency computational environments that could be used to exchange Attitude Data Messages.	Y	
12	Files must have means of being uniquely identified and clearly annotated. The file name alone is considered insufficient for this purpose.	Y	

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Table E-2:~~–~~ Heritage Requirements

Number	Requirement	Accepted for APM?	Accepted for AEM?
1	A complete attitude ephemeris, not subject to integration or propagation by the customer, must be provided.	N	Y
2	The standard is, or includes, an ASCII format.	Y	Y
3	The standard does not require software supplied by other agencies.	Y	Y

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~~Requirement~~	~~Accepted for APM?~~	~~Accepted for AEM?~~
~~A complete attitude ephemeris, not subject to integration or propagation by the customer, must be provided.~~	~~N~~	~~Y~~
~~The standard is, or includes, an ASCII format.~~	~~Y~~	~~Y~~
~~The standard does not require software supplied by other agencies.~~	~~Y~~	~~Y~~

Table E-3:~~–~~ Desirable Characteristics

Number	Requirement	Accepted for APM?	Accepted for AEM?
1	The standard applies to non-traditional objects, such as landers, rovers, balloons, and natural bodies (asteroids, comets).	Y	Y
2	The standard allows attitude states to be provided in other than the traditional EME2000 inertial reference frame; one example is the International Astronomical Union (IAU) Mars body-fixed frame. (In such a case, provision or ready availability of supplemental information needed to transform data into a standard frame must be arranged.)	Y	Y
3	The standard is extensible with no disruption to existing users or uses.	Y	Y
4	The standard is consistent with, and ideally a part of, attitude products and processes used for other space science purposes.	N	N
5	The standard applies to non-traditional objects, such as landers, rovers, balloons, and natural bodies (asteroids, comets).	Y	Y

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~~Requirement~~	~~Accepted for APM?~~	~~Accepted for AEM?~~
~~The standard applies to non-traditional objects, such as landers, rovers, balloons, and natural bodies (asteroids, comets).~~	~~Y~~	~~Y~~
~~The standard allows attitude states to be provided in other than the traditional EME2000 inertial reference frame; one example is the International Astronomical Union (IAU) Mars body-fixed frame. (In such a case, provision or ready availability of supplemental information needed to transform data into a standard frame must be arranged.)~~	~~Y~~	~~Y~~
~~The standard is extensible with no disruption to existing users or uses.~~	~~Y~~	~~Y~~
~~The standard is consistent with, and ideally a part of, attitude products and processes used for other space science purposes.~~	~~N~~	~~N~~
~~The standard is as consistent as reasonable with any related CCSDS attitude standards used for earth-to-spacecraft or spacecraft-to-spacecraft applications.~~	~~Y~~	~~Y~~
~~The standard allows for the specification of the accuracy of the attitude solution.~~	~~Y~~	~~Y~~

E3 APPLICABILITY OF CRITERIA TO MESSAGE OPTIONS

The selection of one particular message will depend on the optimization criteria in the given application.~~–~~ Table E-4~~E-4~~ compares the two recommended messages in terms of the relevant selection criteria identified by the CCSDS:

Field Code Changed

Table E-4:~~–~~ Applicability of the Criteria to Attitude Data Messages

Criteria	Definition	Applicable to APM?	Applicable to AEM?
Modeling Fidelity	Permits modeling of any dynamic perturbation to the attitude.	N	Y
Human Readability	Provides easily readable message corresponding to widely used attitude representations.	Y	Y
Remote Body Extensibility	Permits use for assets on remote solar system bodies.	Y	Y
Lander/Rover Compatibility	Permits exchange of non-orbit attitudes.	Y	Y

E4 SERVICES RELATED TO THE DIFFERENT ATTITUDE DATA MESSAGE FORMATS

The different attitude data messages have been distinguished by their self-interpretability. Both attitude data messages provide for recognizing the boundaries of the attitude data fields and thus can transfer each field, as a block, to another location.~~–~~ The different services that can be achieved without special arrangements between users of the CCSDS attitude data messages are listed in table E-5~~E-5~~.

Field Code Changed

Table E-5:~~–~~ Services Available with Attitude Data Messages

Service	Definition	Applicable to APM?	Applicable to AEM?
Absolute Attitude Interpretation	State availability at specific times for use in additional computations (geometry, event detection, etc.).	Y	Y
Relative Attitude Interpretation	Trajectory comparison and differencing for events based on the same time source.	Only at time specified at Epoch	Y

ANNEX F

ITEMS FOR AN INTERFACE CONTROL DOCUMENT

(INFORMATIVE)

In several places in this document there are references to items which should be specified in an ICD between agencies participating in an exchange of attitude data.~~–~~ The ICD should be jointly produced by both agencies participating in a cross-support activity involving the transfer of attitude data.~~–~~ This annex compiles those recommendations into a single list.[1]

Table F-1:~~–~~ Items Recommended for an ICD

ICD Item		Section Trace
1	ADM, ~~M and~~ AEM, and ACM file naming conventions.	0~~3.1.4~~ 0~~4.1.3~~
2	Method of exchanging ADMs (transmission).	0~~1.2.2~~ 0~~3.1.4~~ 0~~4.1.3~~
3	Definition of attitude accuracy requirements pertaining to data in an ADM as well as attitude dynamics modeling.	0~~1.2.1~~ 0~~3.1.2~~ 0~~5.8.2.2~~
4	Specific APM, AEM and/or AC~~E~~M version numbers that will be exchanged.	0~~3.2.6.1~~ 0~~4.2.6.1~~
~~5~~	~~Format on values used for the ‘ORIGINATOR’ keyword.~~	~~table 3-1~~ ~~table 4-2~~
5~~6~~	Values used for the ‘OBJECT_ID’ keyword for cases when the value is not published in the international designators list by the UN Office of Outer Space Affairs (reference [2]~~[2]~~).	table 3-2~~3-2~~ table 4-3~~4-3~~
6~~7~~	Values and definition of the 'FRAME_*’ keywords to be used in ADM exchanges, if the value is not given in annex B.	3.2.4
7~~8~~	Convention for values of the ‘SPIN_ANGLE’ keyword if~~ not expressed in reference [H4]~~ different form that of ANNEX C, section C5.	**3.2.4**

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[1] The greater the amount of material specified via ICD, the lesser the utility/benefit of the ADM (custom programming will be required to tailor software for each ICD).

	ICD Item	Section Trace
8~~9~~	If floating-point numbers in extended-single or extended-double precision are to be used, then discussion of implementation-specific attributes is required.	0~~5.6.5~~
9~~10~~	Information which must appear in comments for any given ADM exchange.	0~~5.8.1.3~~
~~11~~ 10	Whether the format of the ADM will be KVN or XML~~[1]~~.	0~~1.2.3~~
11 ~~12~~	A reference orientation should be specified in an ICD if a body-fixed frame is to be used for the specification of Euler angles.~~–~~ For instance, demonstrating the alignment of the body axes with the local orbit frame or an inertial frame that gives a context to interpret the Euler angle data.	
~~13~~		
12	If the chosen angle units are radians (which is outside the standard).	
~~14~~ 13	Provisions that are made to ensure information security.	ANNEX I~~ANNEX I~~
~~15~~ 14	Values used for those keywords listed in annex B when those values are different from those given in annex B.	B
~~16~~ 15	Specification of interpretation of MET, MRT and SCLK, if to be exchanged, and how to transform it to a standardized time system such as UTC, TAI, etc.~~–~~ An ICD should specify that elapsed days are to be used for epochs, with year starting at zero.	B2
~~17~~ 16	Exact specification of reference frames used in messages, if different from those specified in annex B.	B4

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~~[1] XML implementation awaiting approval as a standard.~~

ANNEX G

ABBREVIATIONS AND ACRONYMS

(INFORMATIVE)

ASCII	American Standard Code for Information Interchange
ACM	Attitude Comprehensive Message
ADM	Attitude Data Message
AEM	Attitude Ephemeris Message
APM	Attitude Parameter Message
AST	Autonomous Star Tracker
~~CCIR~~	~~International Coordinating Committee for Radio Frequencies~~
CCSDS	Consultative Committee for Space Data Systems
CP	Center of Pressure
CSS	Coarse Sun Sensor
DSS	Digital Sun Sensor
EKF	Extended Kalman Filter
EME2000	Earth Mean Equator and Equinox of J2000 (Julian Date 2000)
GPS	Global Positioning System
IAU	International Astronomical Union
ICD	Interface Control Document
ICRF	International Celestial Reference Frame
IEC	International Electrotechnical Commission
IMU	Inertial Measurement Unit
ISO	International Organization for Standardization
ITRF	International Terrestrial Reference Frame
KVN	Keyword = Value Notation
LVLH	Local Vertical Local Horizontal
NTW	Normal, Tangential (to velocity vector) and Normal to Orbit Plane
ODM	Orbit Data Message
OEM	Orbit Ephemeris Message
OPM	Orbit Parameter Message
RWA	Reaction Wheel Assembly
TAI	International Atomic Time
TCB	Barycentric Coordinated Time

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TDB	Barycentric Dynamical Time
~~TDM~~	~~Tracking Data Message~~
TOD	True Equator and Equinox of Date
TT	Terrestrial Dynamical Time
UTC	Coordinated Universal Time
XML	eXtensible Markup Language

ANNEX H

INFORMATIVE REFERENCES

(INFORMATIVE)

~~[H1] *XML Schema Part 2: Datatypes*. 2nd ed. P. Biron and A. Malhotra, eds. W3C Recommendation 28. n.p.: W3C, 2004.~~

~~[H2] *Standard Frequencies and Time Signals*. Volume 7 of *Recommendations and Reports of the CCIR: XVIIth Plenary Assembly*. Geneva: CCIR, 1990.~~

[H1~~3~~] *Organization and Processes for the Consultative Committee for Space Data Systems*, CCSDS A02.1-Y-4. Yellow Book. Issue 4. Washington, D.C.: CCSDS, April 2014.

[H2~~4~~] *Navigation Data—Definitions and Conventions*.~~—~~ Report Concerning Space Data System Standards, CCSDS 500.0-G-2.~~—~~ Green Book.~~—~~ Issue 3.~~—~~ Washington, D.C.: CCSDS, May 2010.

NOTE – Normative references are provided in 1.5.

ANNEX I

SECURITY, SANA, AND PATENT CONSIDERATIONS

(INFORMATIVE)

A1 SECURITY CONSIDERATIONS

A1.1 ANALYSIS OF SECURITY CONSIDERATIONS

This subsection presents the results of an analysis of security considerations applied to the technologies specified in this Recommended Standard.

A1.2 CONSEQUENCES OF NOT APPLYING SECURITY TO THE TECHNOLOGY

The consequences of not applying security to the systems and networks on which this Recommended Standard is implemented could include potential loss, corruption, and theft of data. Because these messages are used in spacecraft ~~collision avoidance~~attitude analyses and potential maneuvers, the consequences of not applying security to the systems and networks on which this Recommended Standard is implemented could include compromise or loss of the mission if malicious tampering of a particularly severe nature occurs.

A1.3 POTENTIAL THREATS AND ATTACK SCENARIOS

Potential threats or attack scenarios include, but are not limited to, (a) unauthorized access to the programs/processes that generate and interpret the messages, and (b) unauthorized access to the messages during transmission between exchange partners. Protection from unauthorized access during transmission is especially important if the mission utilizes open ground networks, such as the Internet, to provide ground-station connectivity for the exchange of data formatted in compliance with this Recommended Standard. It is strongly recommended that potential threats or attack scenarios applicable to the systems and networks on which this Recommended Standard is implemented be addressed by the management of those systems and networks.

A1.4 DATA PRIVACY

Privacy of data formatted in compliance with the specifications of this Recommended Standard should be assured by the systems and networks on which this Recommended Standard is implemented.

A1.5 DATA INTEGRITY

Integrity of data formatted in compliance with the specifications of this Recommended Standard should be assured by the systems and networks on which this Recommended Standard is implemented.

A1.6 AUTHENTICATION OF COMMUNICATING ENTITIES

Authentication of communicating entities involved in the transport of data which complies with the specifications of this Recommended Standard should be provided by the systems and networks on which this Recommended Standard is implemented.

A1.7 DATA TRANSFER BETWEEN COMMUNICATING ENTITIES

The transfer of data formatted in compliance with this Recommended Standard between communicating entities should be accomplished via secure mechanisms approved by the Information Technology Security functionaries of exchange participants.

A1.8 CONTROL OF ACCESS TO RESOURCES

Control of access to resources should be managed by the systems upon which originator formatting and recipient processing are performed.

A1.9 AUDITING OF RESOURCE USAGE

Auditing of resource usage should be handled by the management of systems and networks on which this Recommended Standard is implemented.

A1.10 UNAUTHORIZED ACCESS

Unauthorized access to the programs/processes that generate and interpret the messages should be prohibited in order to minimize potential threats and attack scenarios.

A1.11 DATA SECURITY IMPLEMENTATION SPECIFICS

Specific information-security interoperability provisions that may apply between agencies and other independent users involved in an exchange of data formatted in compliance with this Recommended Standard could be specified in an ICD.

A2 SANA CONSIDERATIONS

The following ADM related items will be registered with the SANA Operator.~~–~~ The registration rule for new entries in the registry is the approval of new requests by the CCSDS

Area or Working Group responsible for maintenance of the ADM at the time of the request~~Navigation Working Group chair~~. New requests for this registry should be sent to SANA (mailto:info@sanaregistry.org).

- The ADM XML schema
- A transform from the ADM XML to the ADM KVN version
- Values for the originator keyword.

A3 PATENT CONSIDERATIONS

The recommendations of this document have no patent issues.