

# Dynamical Systems and Space Mission Design

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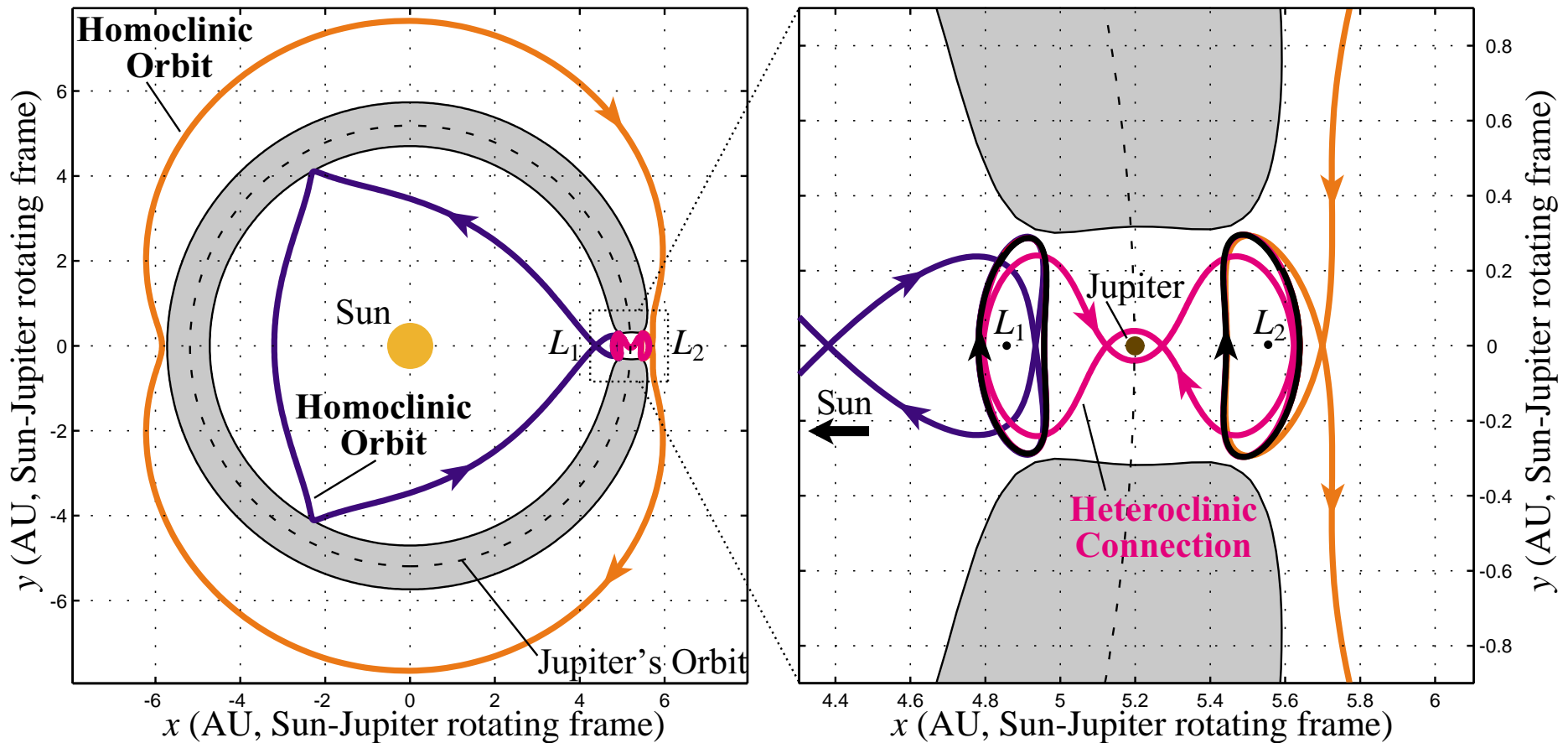
## ■ Global Orbit Structure: Outline

### ▶ Outline of Lecture 3B:

- Construction of Poincaré map.
- Review of Horseshoe Dynamics.
- Symbolic Dynamics for the PCR3BP.
- Main Theorem on Global Orbit Structure.

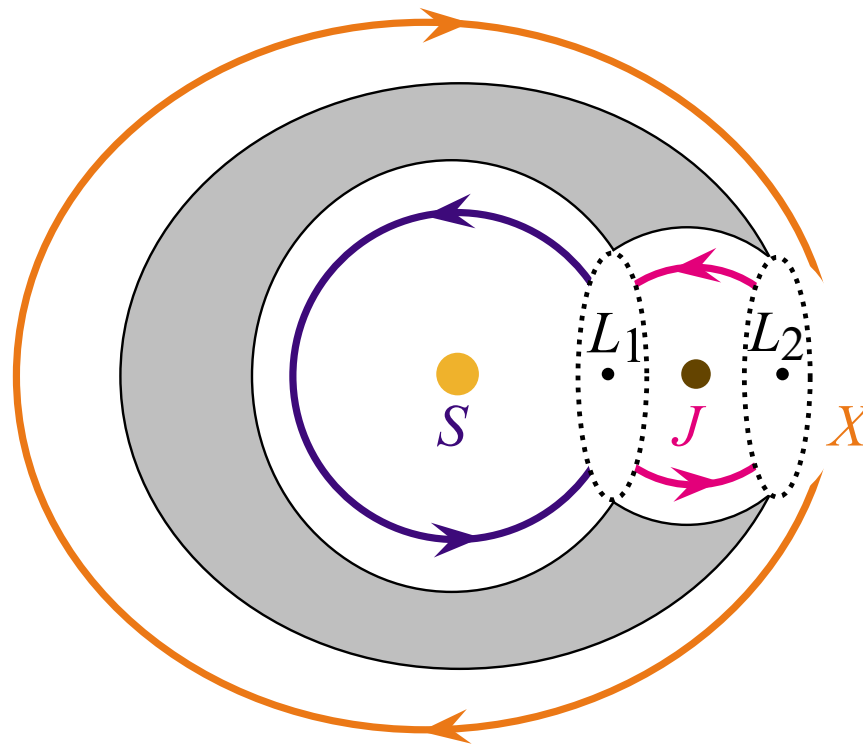
## Global Orbit Structure: Overview

- ▶ Found **heteroclinic connection** between pair of periodic orbits.
- ▶ Find a large class of **orbits** near this (homo/heteroclinic) **chain**.
- ▶ Comet can follow these **channels** in rapid transition.



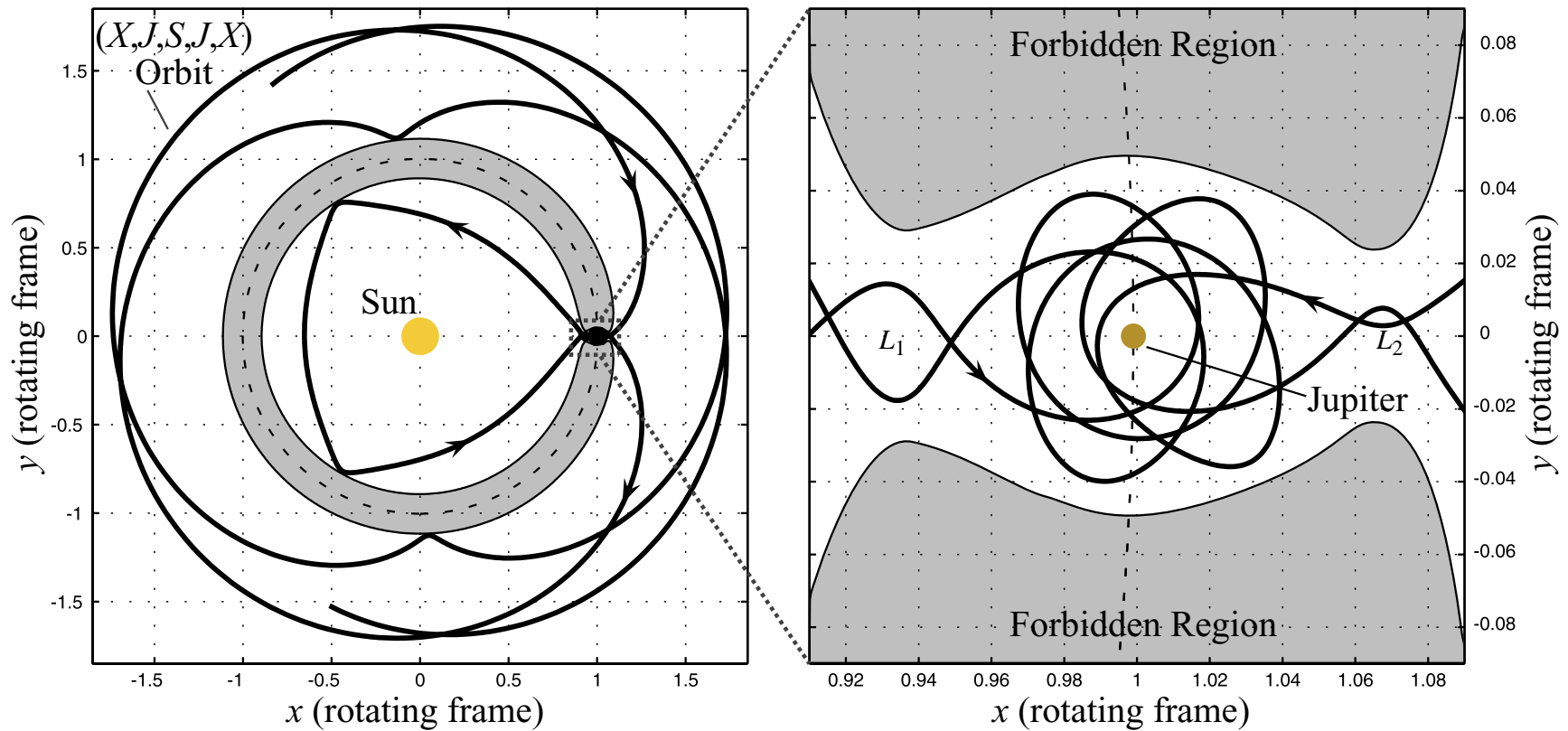
## ■ Global Orbit Structure: Overview

- ▶ **Symbolic sequence** used to label itinerary of each comet orbit.
- ▶ **Main Theorem:** For any admissible **itinerary**, e.g.,  $(\dots, \mathbf{X}, \mathbf{J}, \mathbf{S}, \mathbf{J}, \mathbf{X}, \dots)$ , there exists an orbit whose **whereabouts** matches this **itinerary**.
- ▶ Can even specify **number of revolutions** the comet makes around  $L_1$  &  $L_2$  as well as Sun & Jupiter.



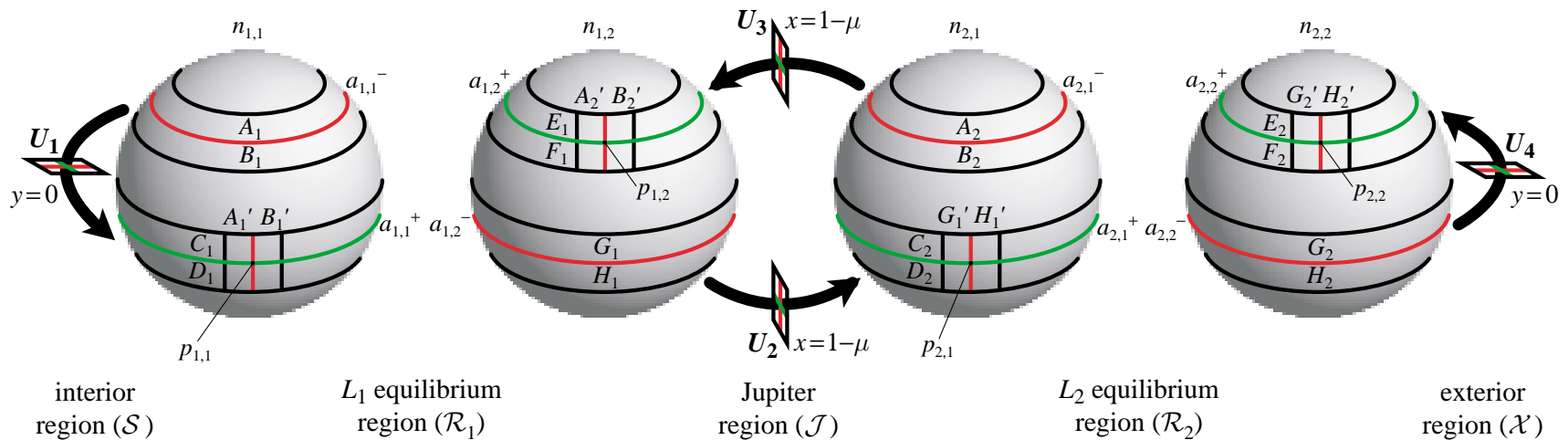
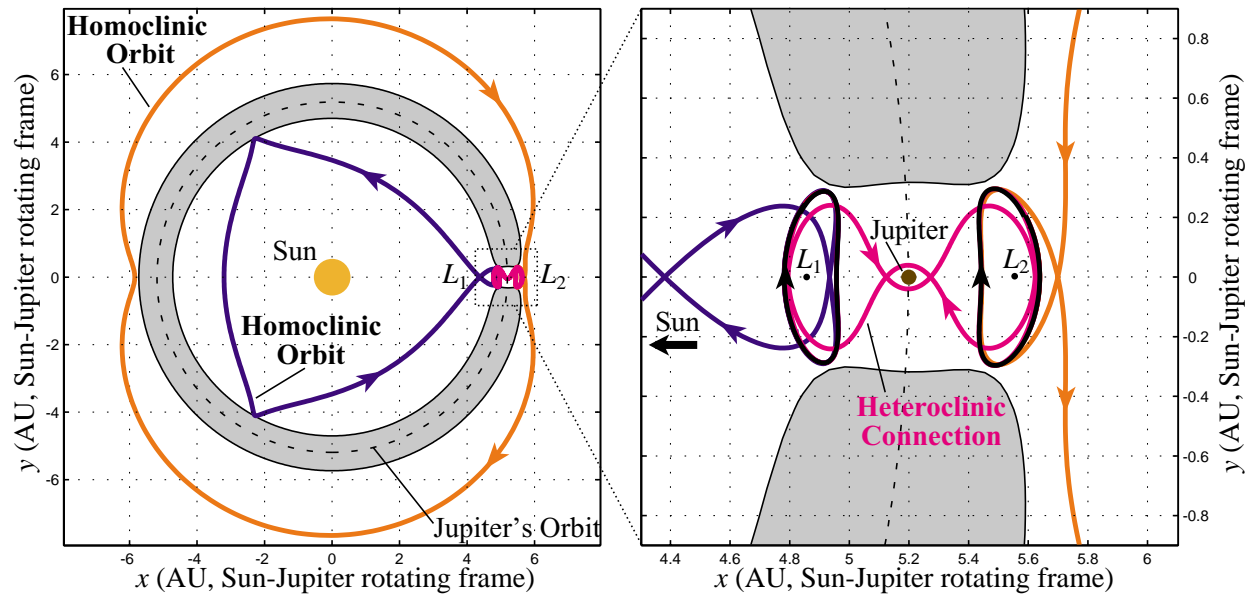
## ■ Global Orbit Structure: Overview

- ▶ Using the proof of **Main Theorem** as the guide, we develop procedure to construct orbit with **prescribed itinerary**.
- ▶ Example: An orbit with itinerary **(X, J; S, J, X)**.
- ▶ **Petit Grand Tour** of Jovian moons & **Shoot the Moon**.



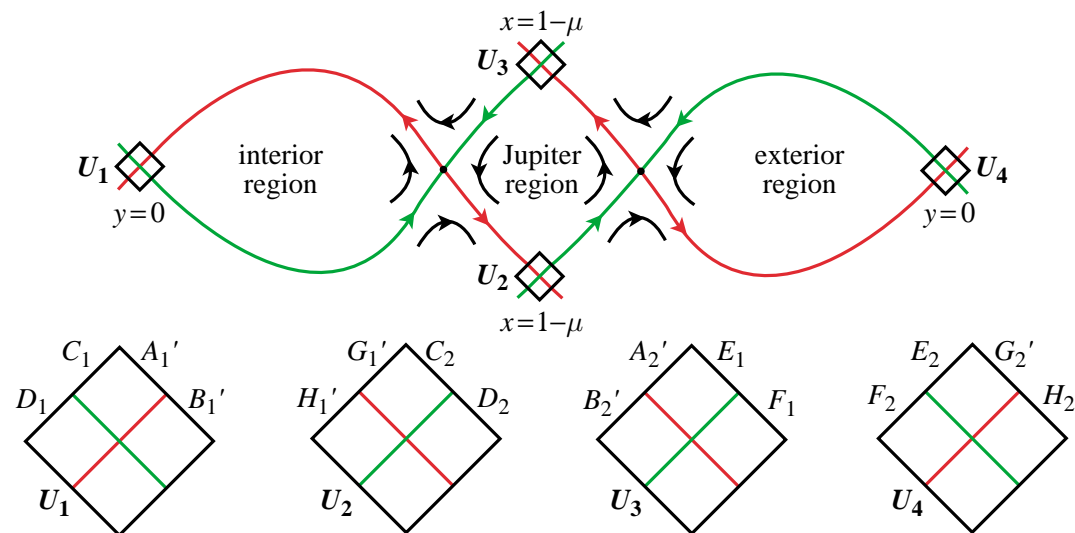
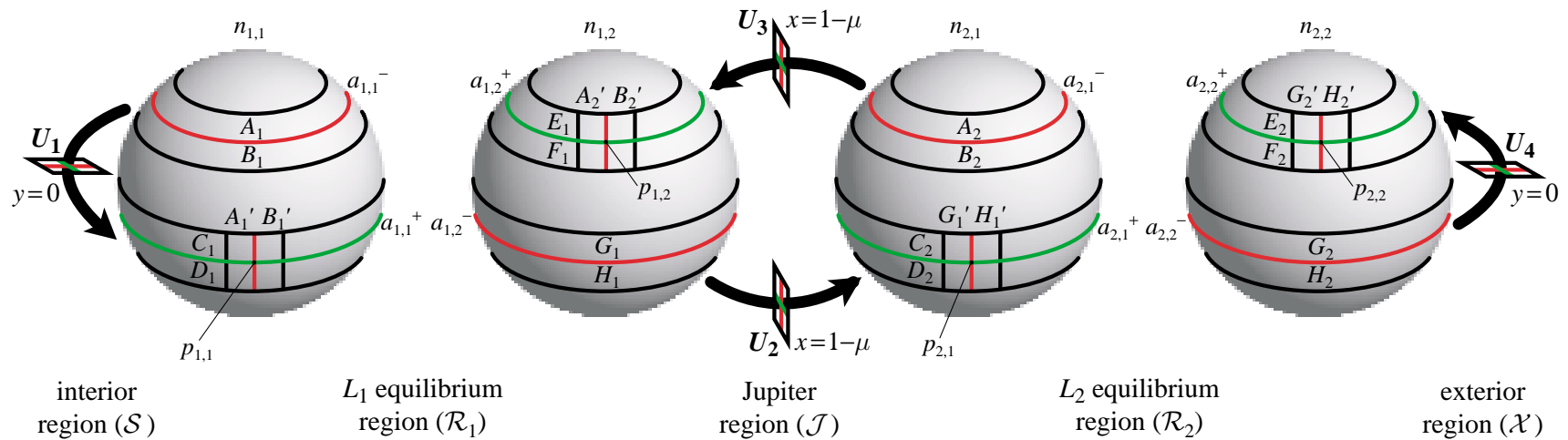
# Global Orbit Structure: Energy Manifold

► Schematic view of energy manifold.



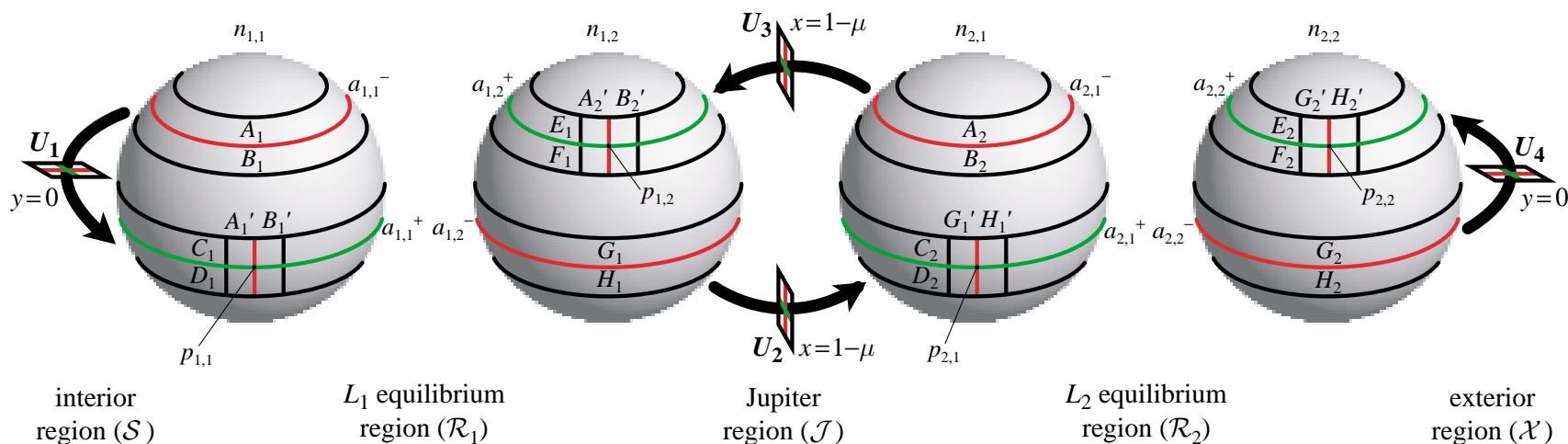
# Global Orbit Structure: Poincaré Map

- ▶ Reducing study of global orbit structure to study of discrete map.



## Construction of Poincaré Map

- ▶ Construct **Poincaré map**  $P$  (transversal to the flow) whose domain  $U$  consists of 4 squares  $U_i$ .
- ▶ Squares  $U_1$  and  $U_4$  contained in  $y = 0$ , each centers around a transversal **homoclinic** point.
- ▶ Squares  $U_2$  and  $U_3$  contained in  $x = 1 - \mu$ , each centers around a transversal **heteroclinic** point.





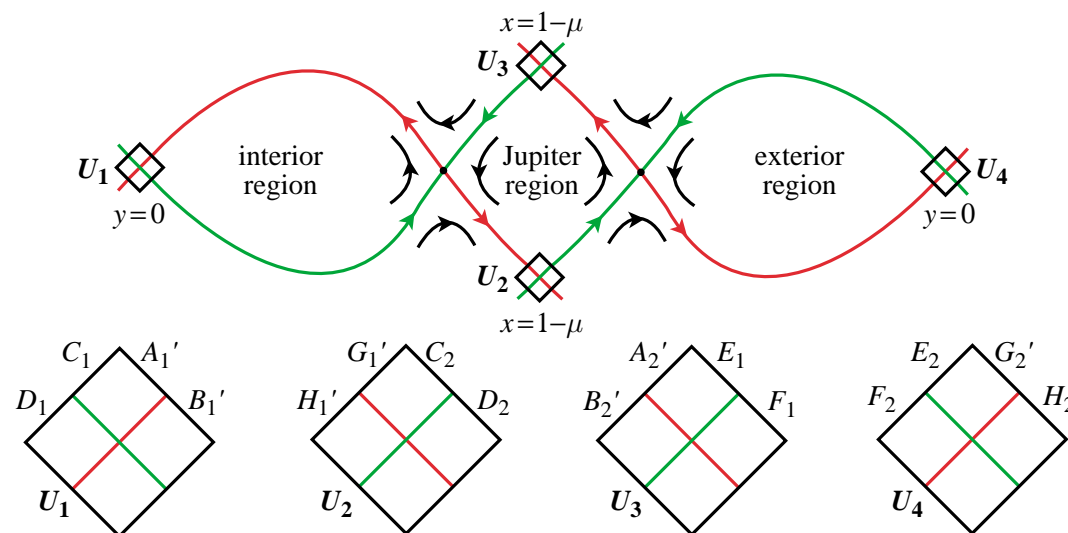
## Global Orbit Structure near the Chain

- Consider **invariant set**  $\Lambda$  of points in  $U$  whose images and pre-images under all iterations of  $P$  remain in  $U$ .

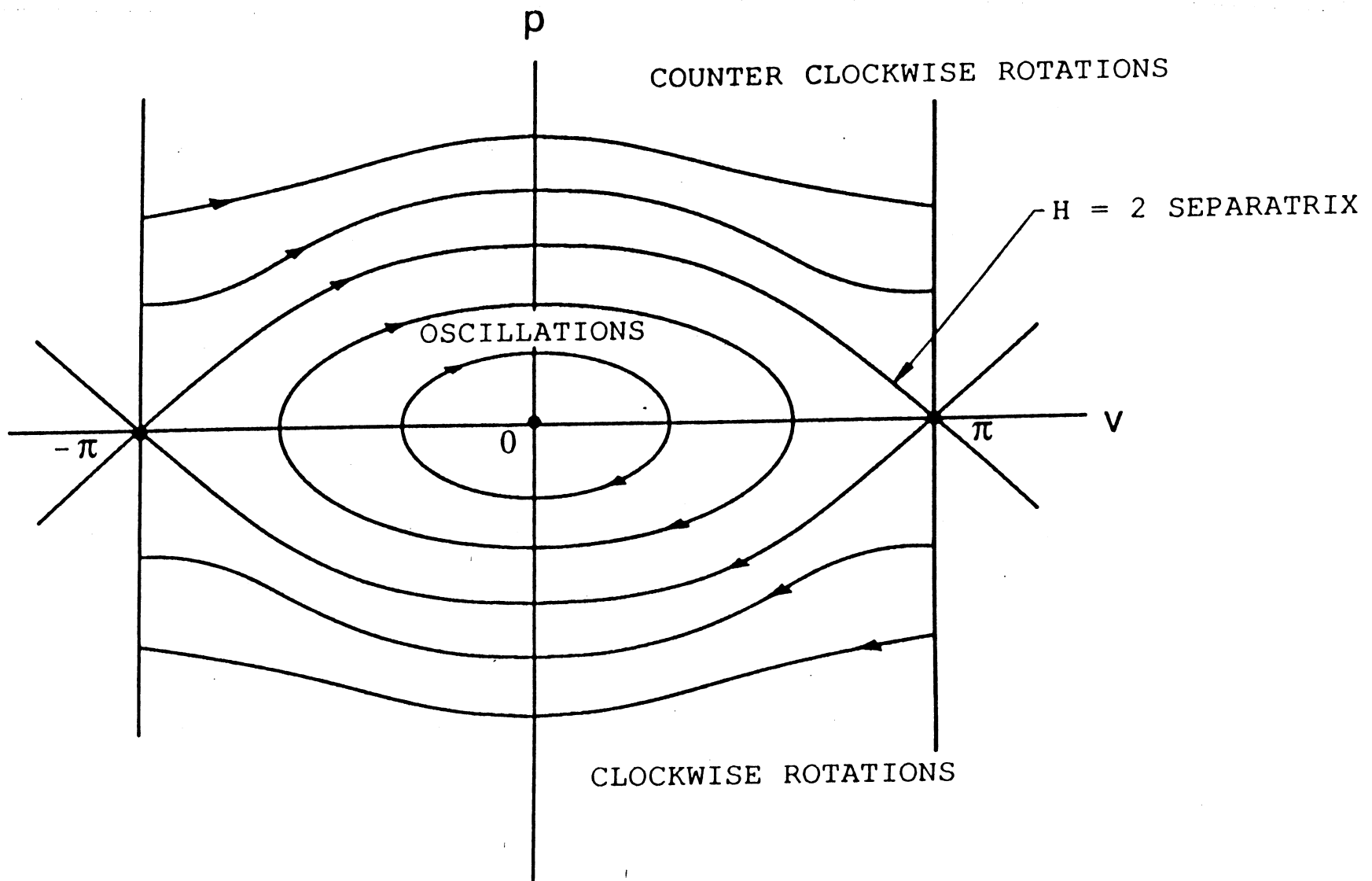
$$\Lambda = \bigcap_{n=-\infty}^{\infty} P^n(U).$$

- Invariant set  $\Lambda$  contains all **recurrent orbits** near the chain. It provides insight into the **global dynamics** around the chain.
- Chaos theory told us to first consider only the **first** forward and backward iterations:

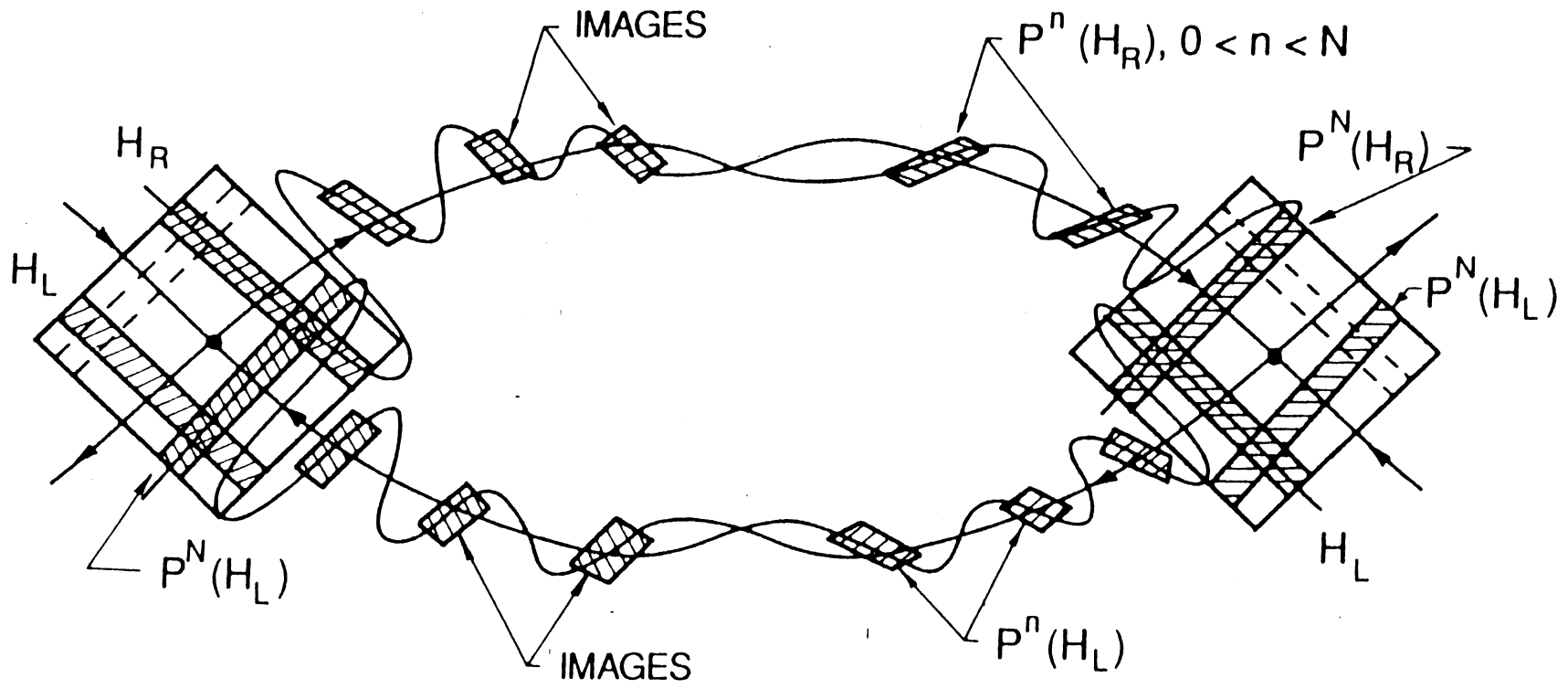
$$\Lambda^1 = P^{-1}(U) \cap U \cap P^1(U).$$



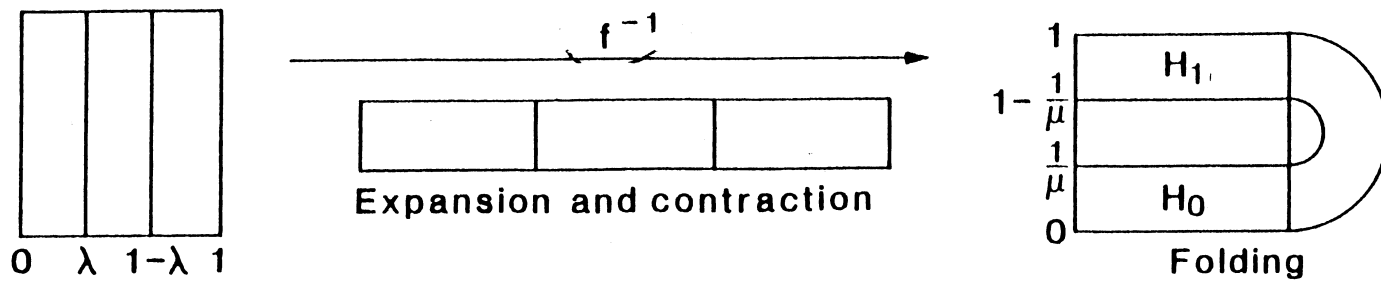
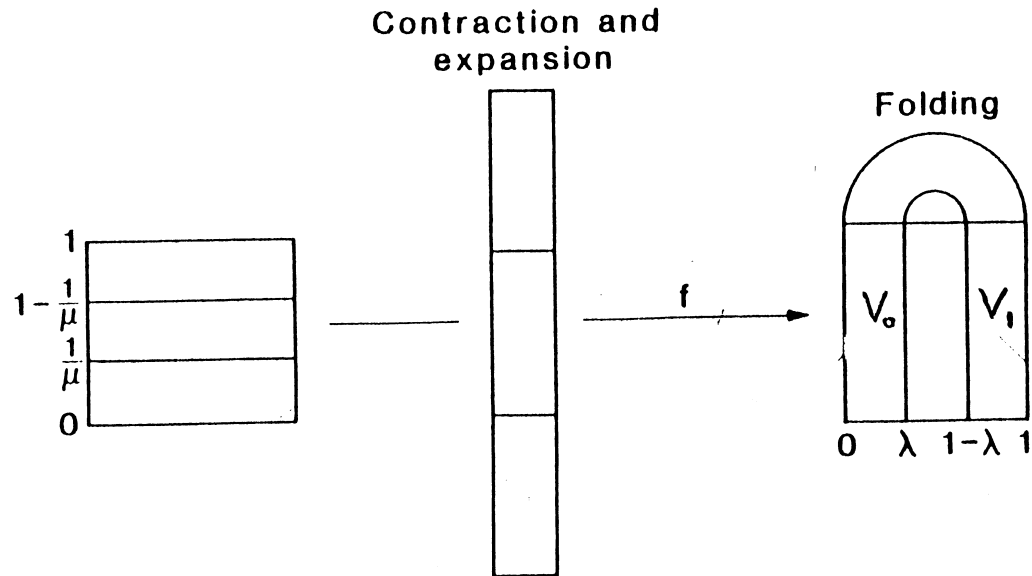
# ■ Review of Horseshoe Dynamics: Pendulum



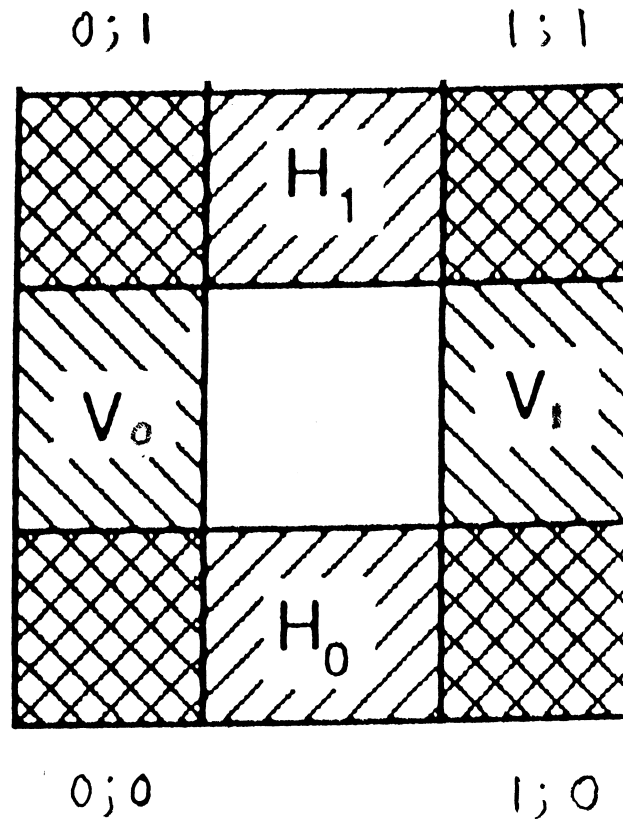
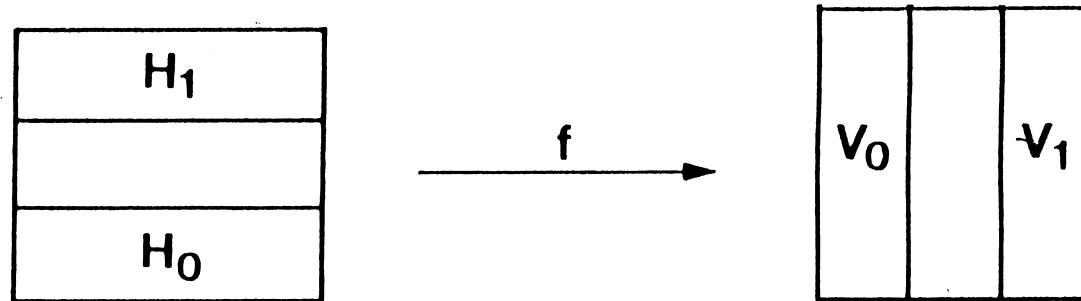
# Review of Horseshoe Dynamics: Forced Pendulum



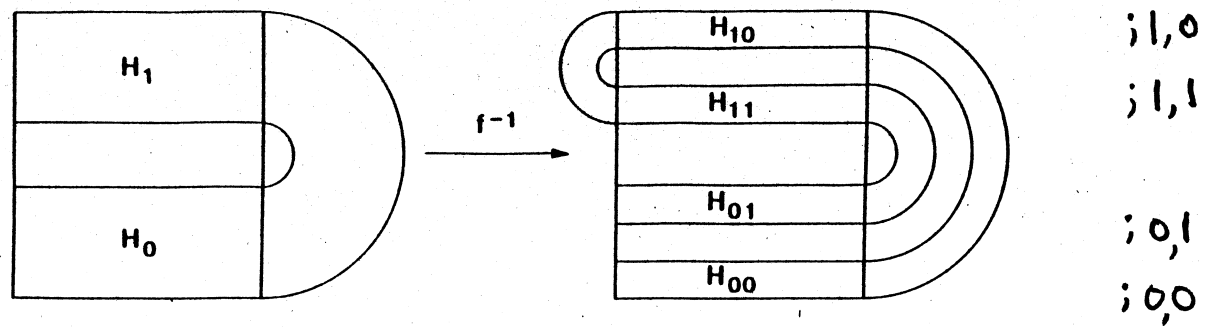
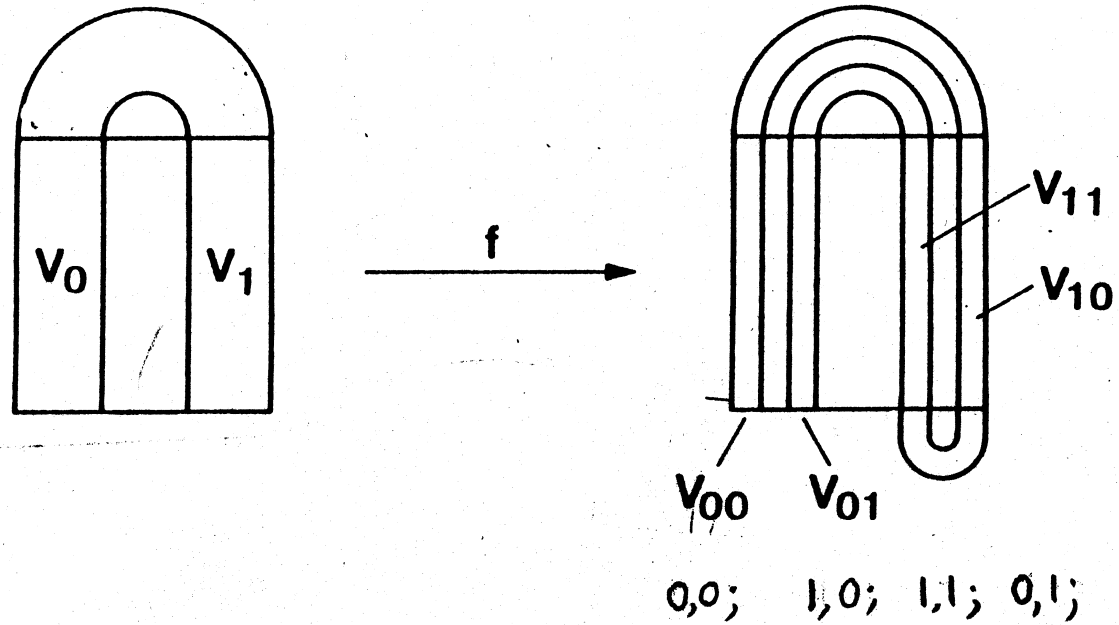
# Review of Horseshoe Dynamics: First Iteration



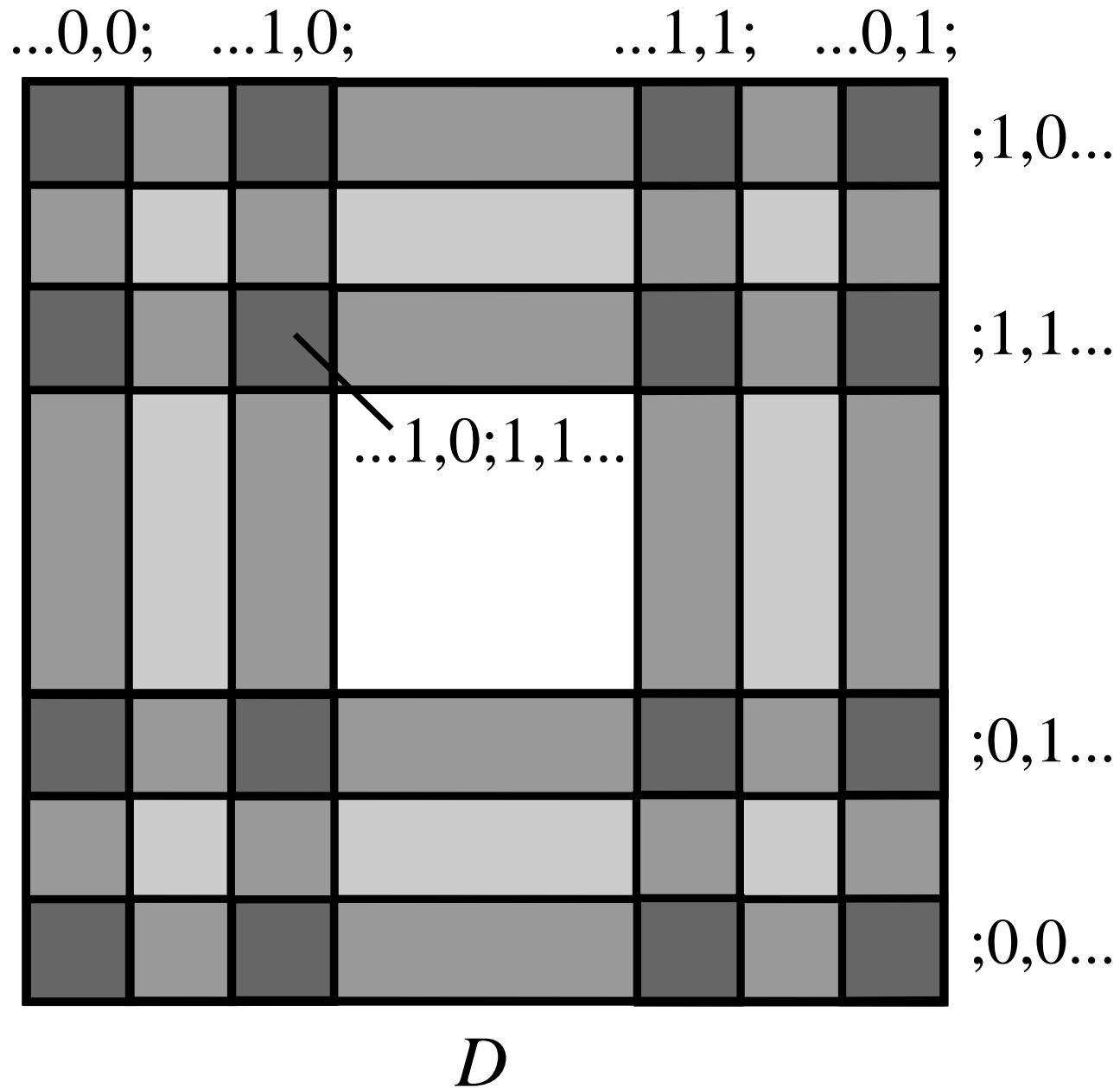
# Review of Horseshoe Dynamics: First Iteration



# Review of Horseshoe Dynamics: Second Iteration

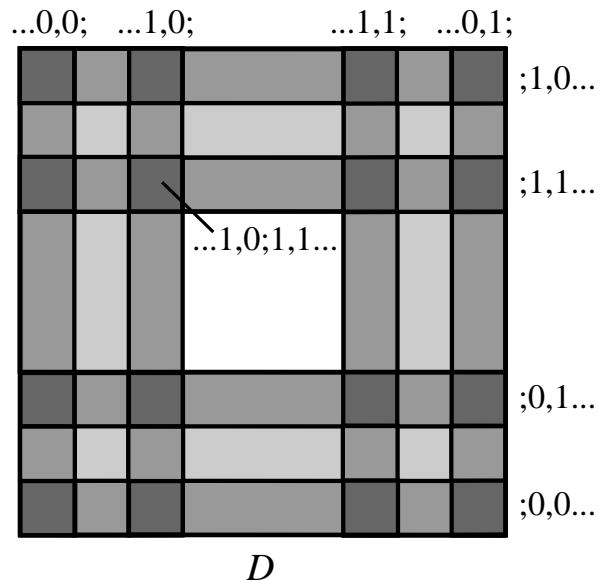


## ■ Review of Horseshoe Dynamics: Second Iteration



## ■ Conley-Moser Conditions: Horseshoe-type Map

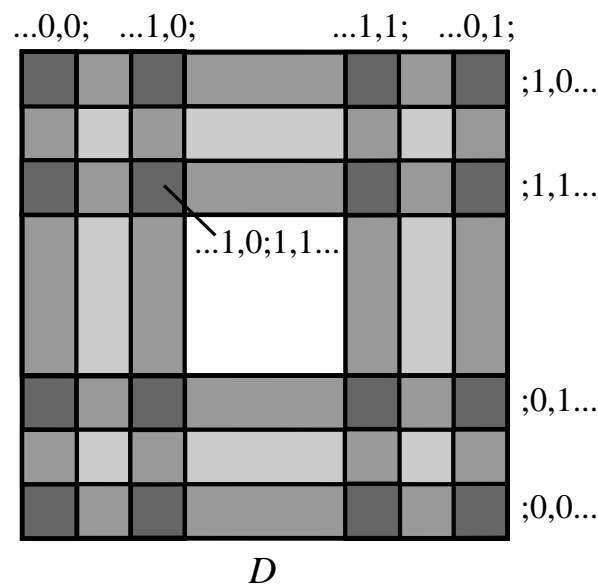
- For horseshoe-type map  $h$  satisfying **Conley-Moser conditions**, the **invariant set** of all iterations,  $\Lambda_h = \bigcap_{n=-\infty}^{\infty} h^n(Q)$ , can be constructed and visualized in a standard way.
- **Strip condition:**  $h$  maps “horizontal strips”  $H_0, H_1$  to “vertical strips”  $V_0, V_1$ , (with horizontal boundaries to horizontal boundaries and vertical boundaries to vertical boundaries).
  - **Hyperbolicity condition:**  $h$  has uniform contraction in horizontal direction and expansion in vertical direction.





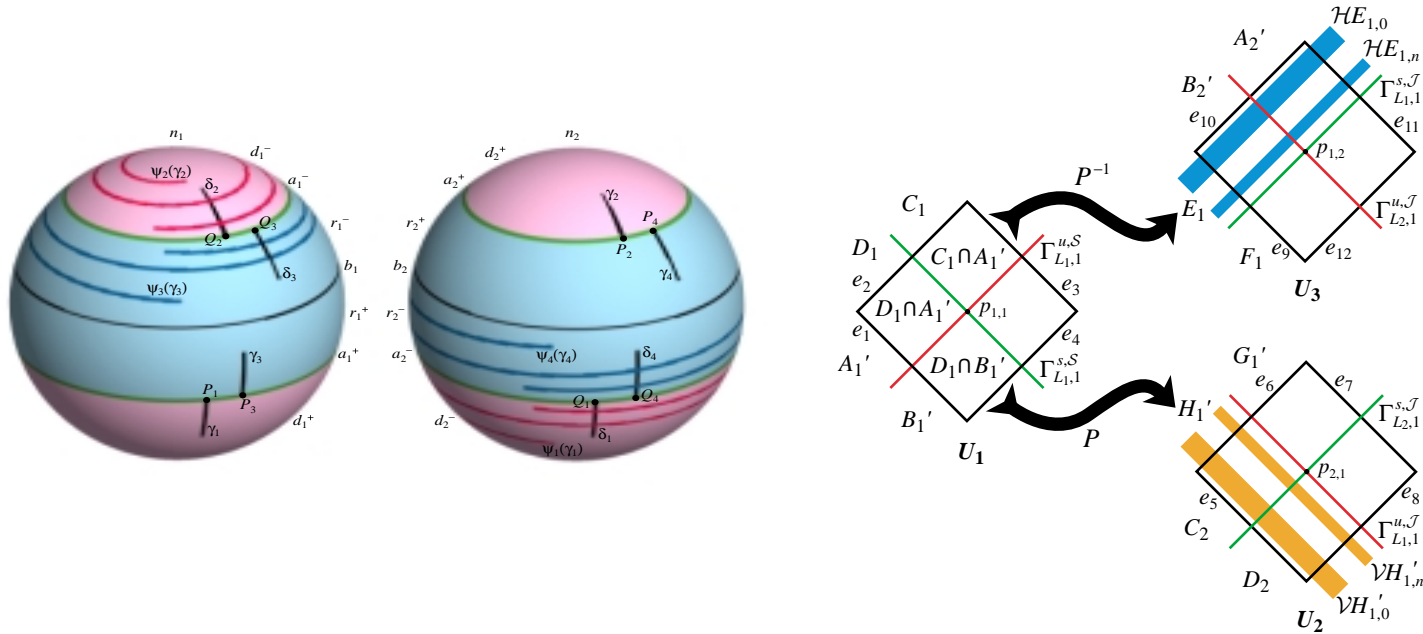
## ■ Conley-Moser Conditions: Horseshoe-type Map

- ▶ **Invariant set** of first iterations  $\Lambda_h^1 = h^{-1}(D) \cap D \cap h^1(D)$  has 4 squares, with addresses  $(0; 0), (1; 0), (1; 1), (0; 1)$ .
- ▶ **Invariant set** of second iterations has 16 squares **contained** in 4 squares of first stage.
- ▶ This process can be repeated **ad infinitum** due to **Conley-Moser Conditions**.
- ▶ What remains is **invariant set** of points  $\Lambda_h$  which are in 1-to-1 corr. with set of bi-infinite sequences of 2 symbols  $(\dots, 0; 1, \dots)$ .



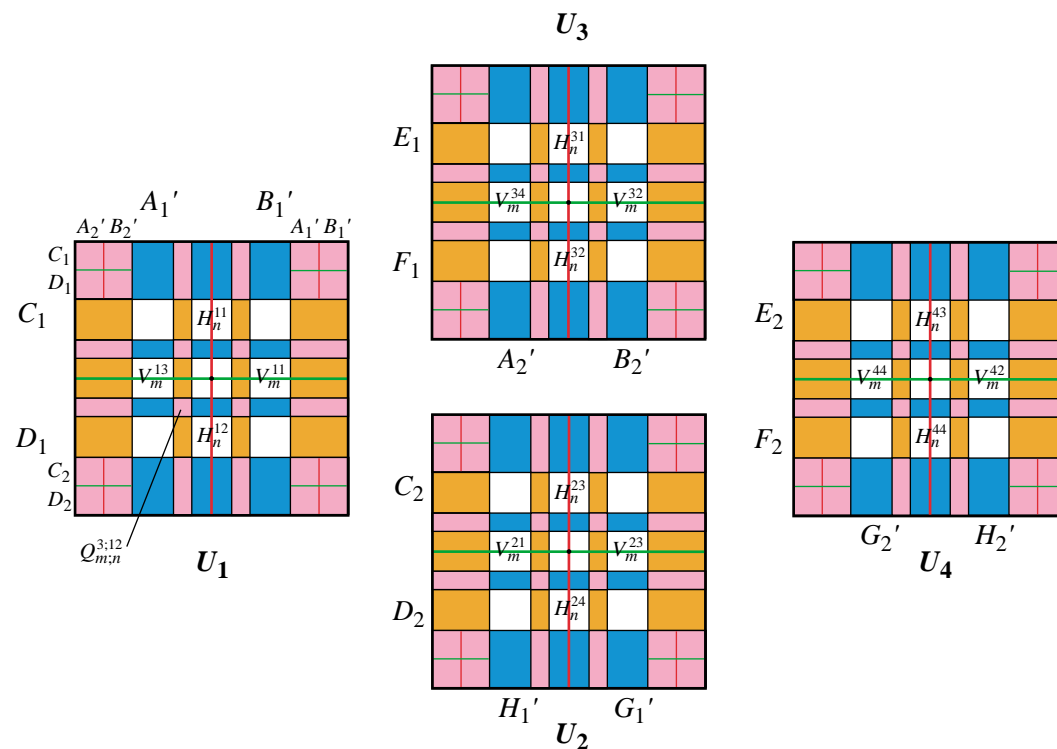
# Horizontal ( $H_n^{31}$ ) & Vertical ( $V_n^{21}$ ) Strips

- Recall: image of **abutting arc** of **stable manifold cut** spiral infinitely many times towards **unstable manifold cut**.



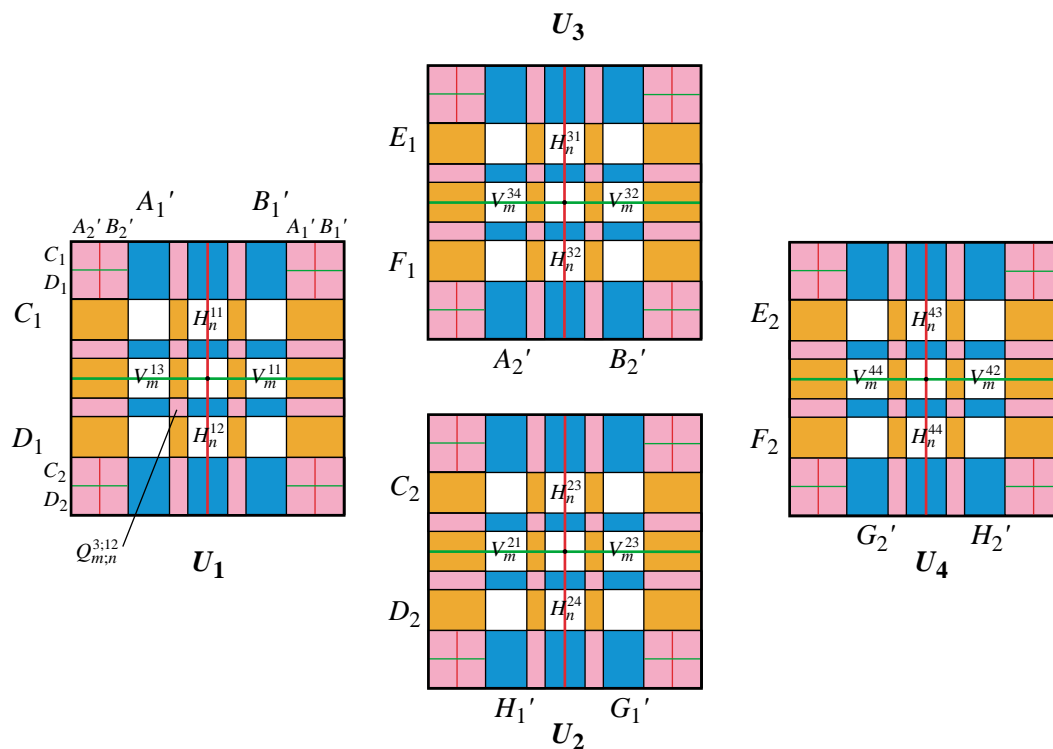
## ■ Horizontal ( $H_n^{ij}$ ) & Vertical ( $V_m^{ji}$ ) Strips

- Hence,  $U \cap P^{-1}(U)$  has 8 families of horizontal strips  $H_n^{ij}$ .
- Each point in **horizontal strip**  $H_n^{ij}$  is in  $U_i$  and will wind  $n$  times around an equilibrium point before reaching  $U_j$ .
  - We can associate each point in  $H_n^{ij}$  both an **address** in  $U$  and an **itinerary** ( $; u_i, n, u_j$ ).



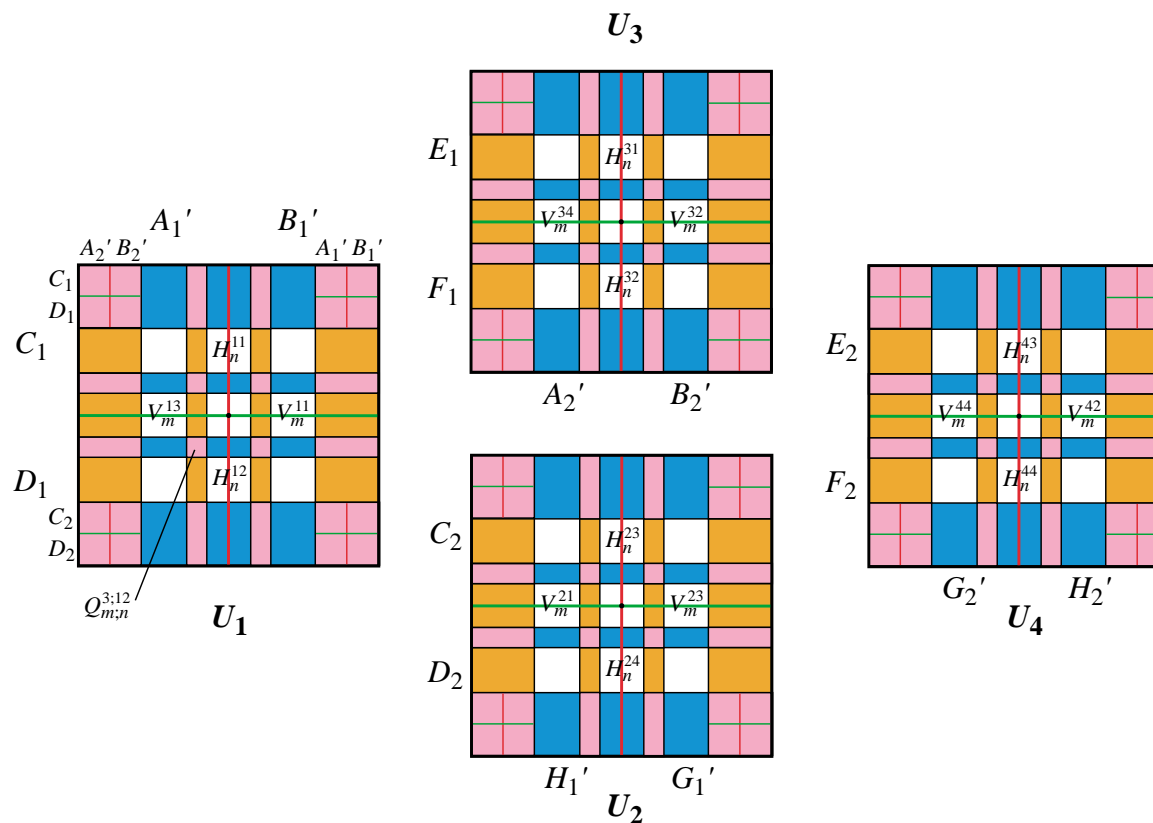
## ■ Horizontal ( $H_n^{ij}$ ) & Vertical ( $V_m^{ji}$ ) Strips

- Similarly,  $U \cap P^1(U)$  consists of 8 families of **vertical strips**  $V_m^{ji}$ .
- Each point in **vertical strip**  $V_m^{ji}$  came from  $U_i$  and has wound  $m$  times around an equilibrium point before arriving at  $U_j$ .
  - We can associate each point in  $V_m^{ji}$  both an **address** in  $U$  and an **itinerary**  $(u_i, m; u_j)$ .



## ■ Invariant Set $\Lambda^1$ under First Interations

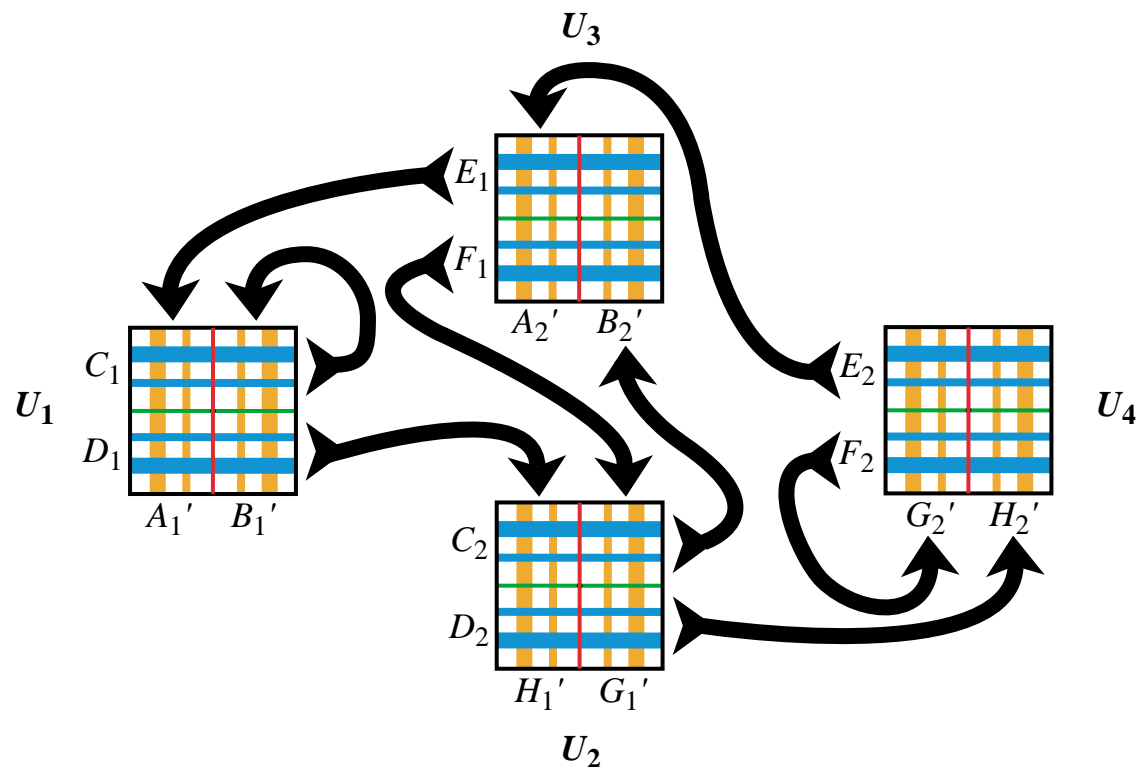
- ▶ The set  $\Lambda^1 = P^{-1}(U) \cap U \cap P^1(U)$  is intersections of all **horizontal** and **vertical** strips.
  - Each **point** of  $Q_{m;n}^{3;12} = H_n^{12} \cap V_m^{13}$  has an **itinerary**  $(u_3, m; u_1, n, u_2)$  which is a concatenation of  $(u_1; n, u_2)$  ( $H_n^{12}$ ) and  $(u_3, m; u_1)$  ( $V_m^{13}$ ).



## ■ Application of Symbolic Dynamics

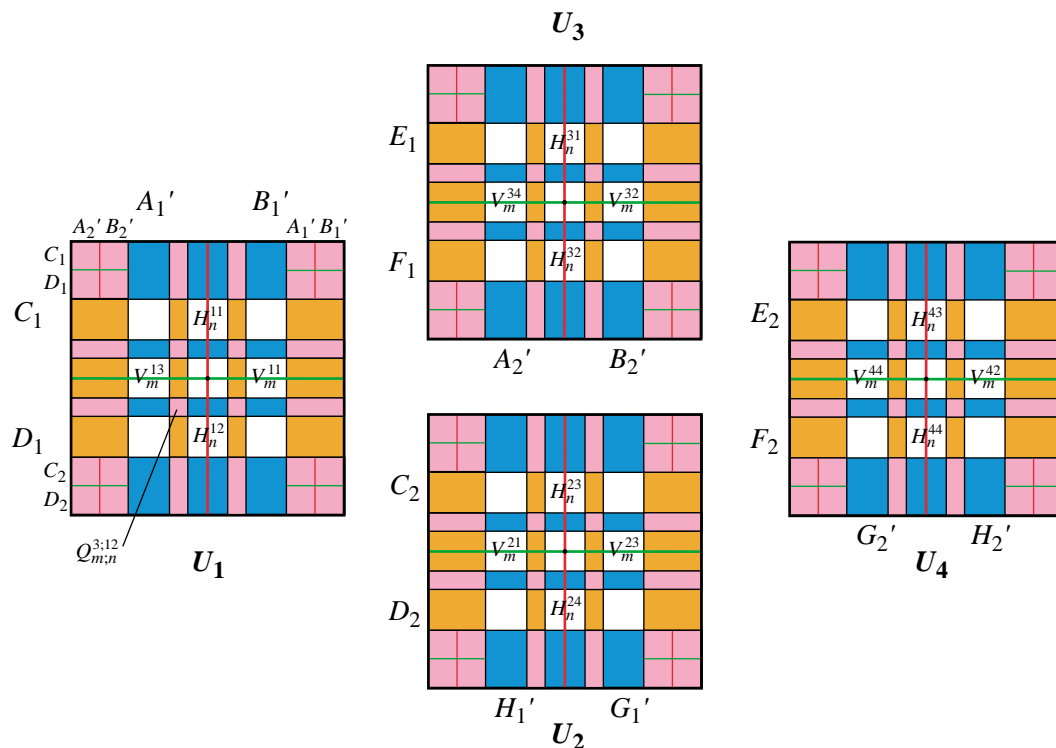
- ▶ Labeling “squares”  $Q_{m;n}^{3;12}$  with  $(u_3, m; u_1, n, u_2)$  is in line with characterizing orbits via bi-infinite sequences of “symbols”.
- ▶ To keep track of **itinerary** w.r.t. 4 squares  $U_i$ , we use **subshift** with 4 symbols  $u_i$ ,  $(\dots, u_3; u_1, u_2, \dots)$ , and a transition matrix

$$A = \begin{pmatrix} 1 & 1 & 0 & 0 \\ 0 & 0 & 1 & 1 \\ 1 & 1 & 0 & 0 \\ 0 & 0 & 1 & 1 \end{pmatrix}.$$



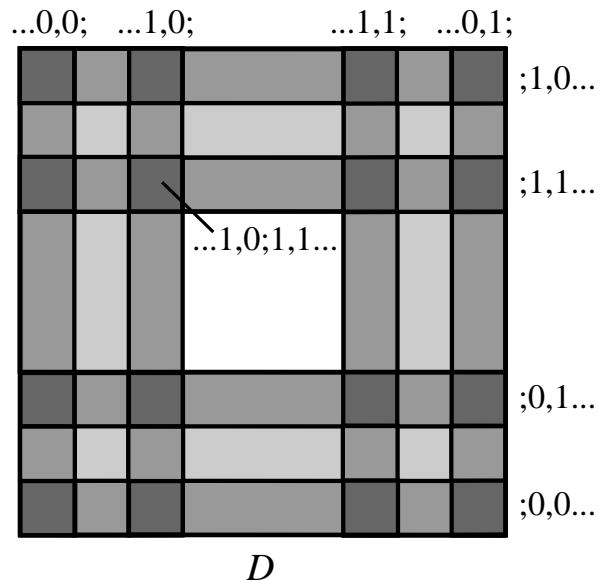
## Application of Symbolic Dynamics

- ▶ To keep track of **number of revolutions** around  $L_1$  or  $L_2$ , we use full shift with integer symbols,  $(\dots, m; n, \dots)$ .
- ▶ “Squares”  $Q_{m;n}^{i;jk}$  in 1-to-1 corr. with sequences  $(u_i, m; u_j, n, u_k)$ .
- ▶ **Symbolic sequence** is used to label **address** of each “square” and identifies **itinerary** of its orbits.
- ▶ To generalize beyond **first iteration**, need to review chaos theory.



## ■ Conley-Moser Conditions: Horseshoe-type Map

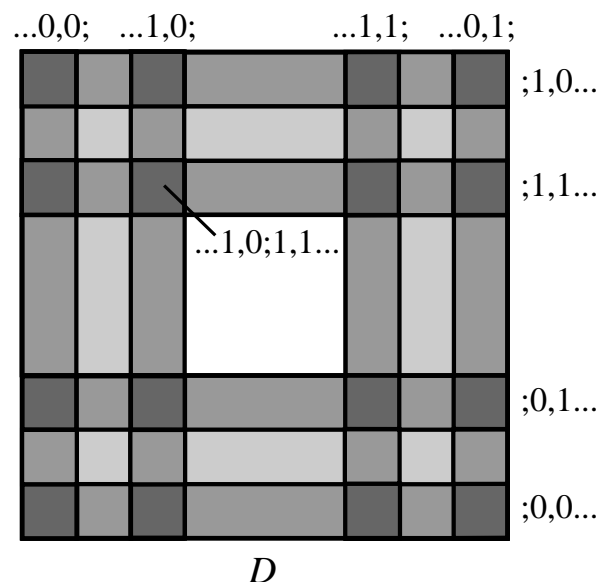
- For horseshoe-type map  $h$  satisfying **Conley-Moser conditions**, the **invariant set** of all iterations,  $\Lambda_h = \bigcap_{n=-\infty}^{\infty} h^n(Q)$ , can be constructed and visualized in a standard way.
- **Strip condition:**  $h$  maps “horizontal strips”  $H_0, H_1$  to “vertical strips”  $V_0, V_1$ , (with horizontal boundaries to horizontal boundaries and vertical boundaries to vertical boundaries).
  - **Hyperbolicity condition:**  $h$  has uniform contraction in horizontal direction and expansion in vertical direction.





## ■ Conley-Moser Conditions: Horseshoe-type Map

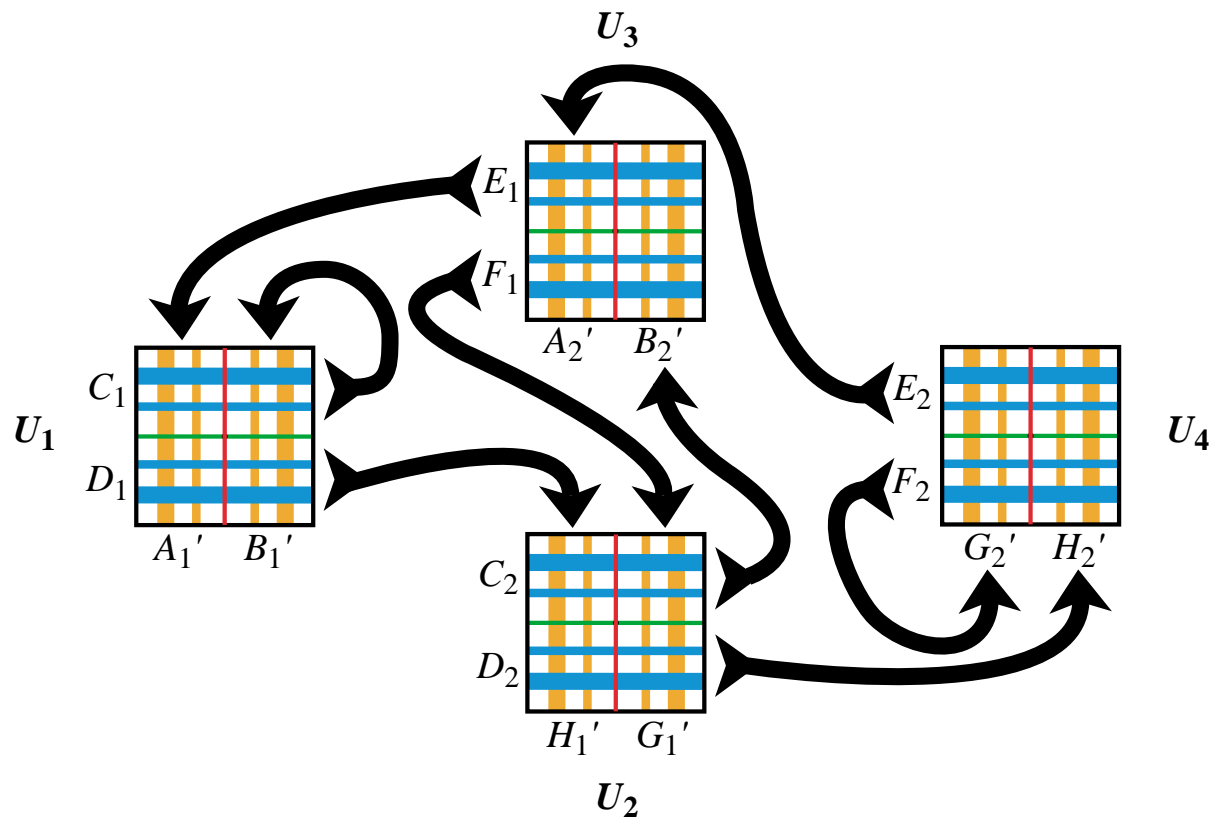
- ▶ **Invariant set** of first iterations  $\Lambda_h^1 = h^{-1}(D) \cap D \cap h^1(D)$  has 4 squares, with addresses  $(0; 0), (1; 0), (1; 1), (0; 1)$ .
- ▶ **Invariant set** of second iterations has 16 squares **contained** in 4 squares of first stage.
- ▶ This process can be repeated **ad infinitum** due to **Conley-Moser Conditions**.
- ▶ What remains is **invariant set** of points  $\Lambda_h$  which are in 1-to-1 corr. with set of bi-infinite sequences of 2 symbols  $(\dots, 0; 1, \dots)$ .



## ■ Generalized Conley-Moser Conditions

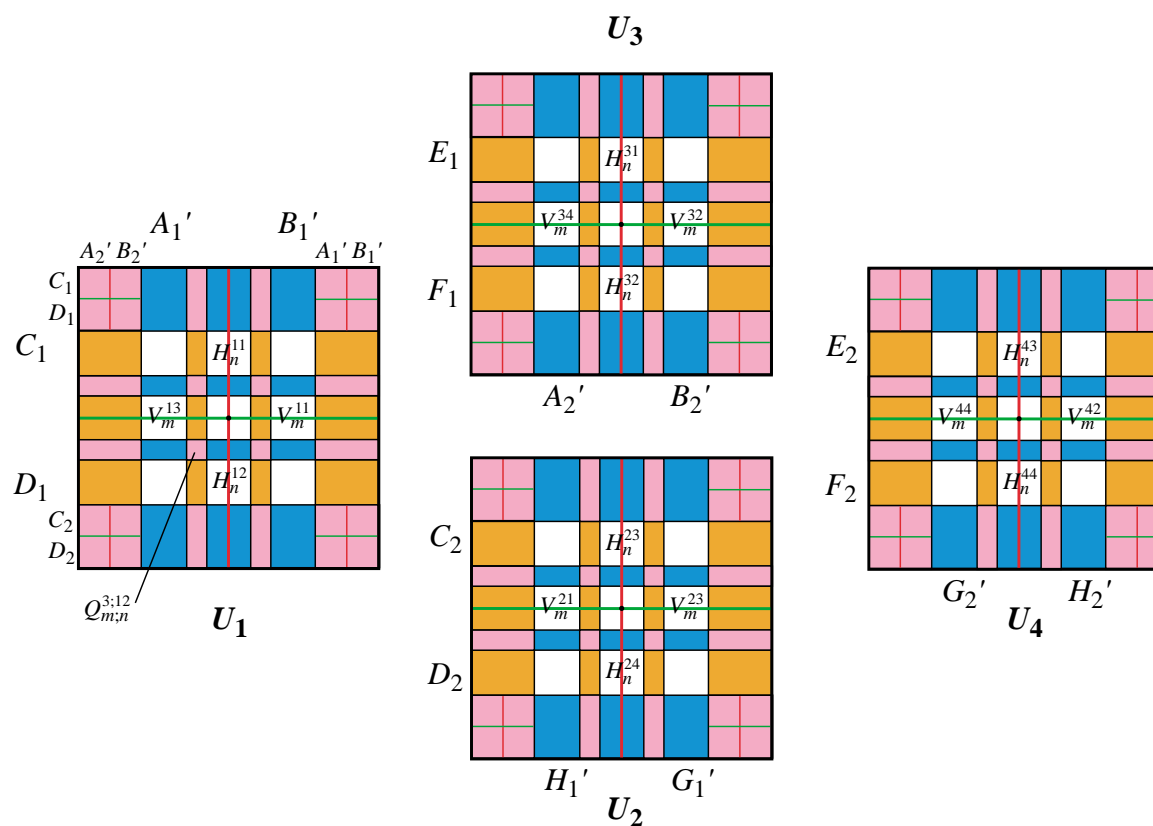
► Proved  $P$  satisfies **Generalized** Conley-Moser conditions:

- **Strip** condition: it maps “horizontal strips”  $H_n^{ij}$  to “vertical strips”  $V_n^{ji}$ .
- **Hyperbolicity** condition: it has uniform contraction in horizontal direction and expansion in vertical direction.



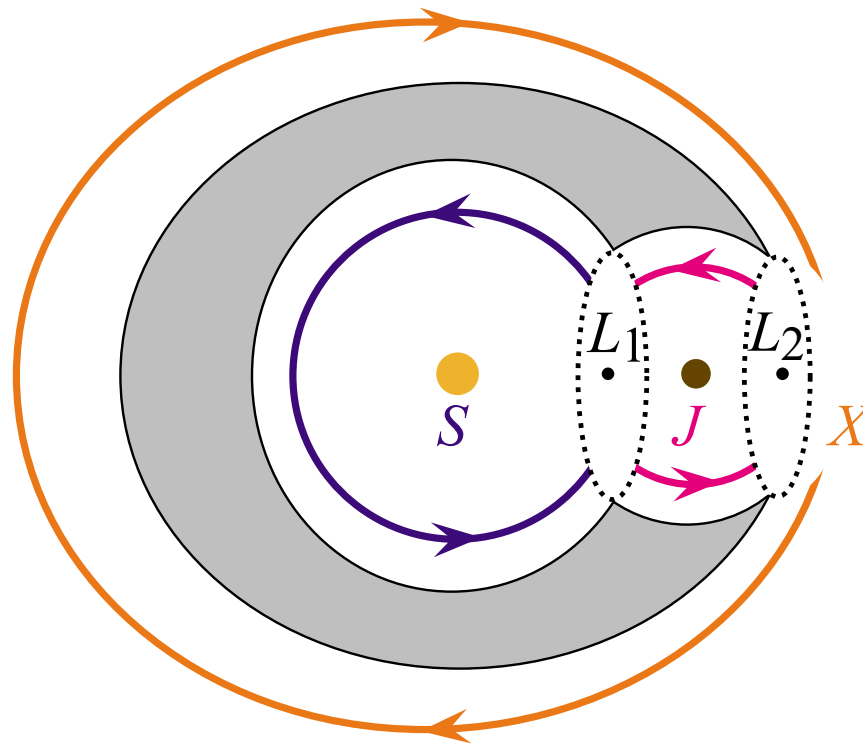
## ■ Generalized Conley-Moser Conditions

- ▶ Shown are invariant set  $\Lambda^1$  under **first iteration**.
- ▶ Since  $P$  satisfies Generalized Conley-Moser Conditions, this process can be repeated **ad infinitum**.
- ▶ What remains is **invariant set** of points  $\Lambda$  which are in 1-to-1 corr. with set of bi-infinite **sequences**  $(\dots, u_i, m; u_j, n, u_k, \dots)$ .



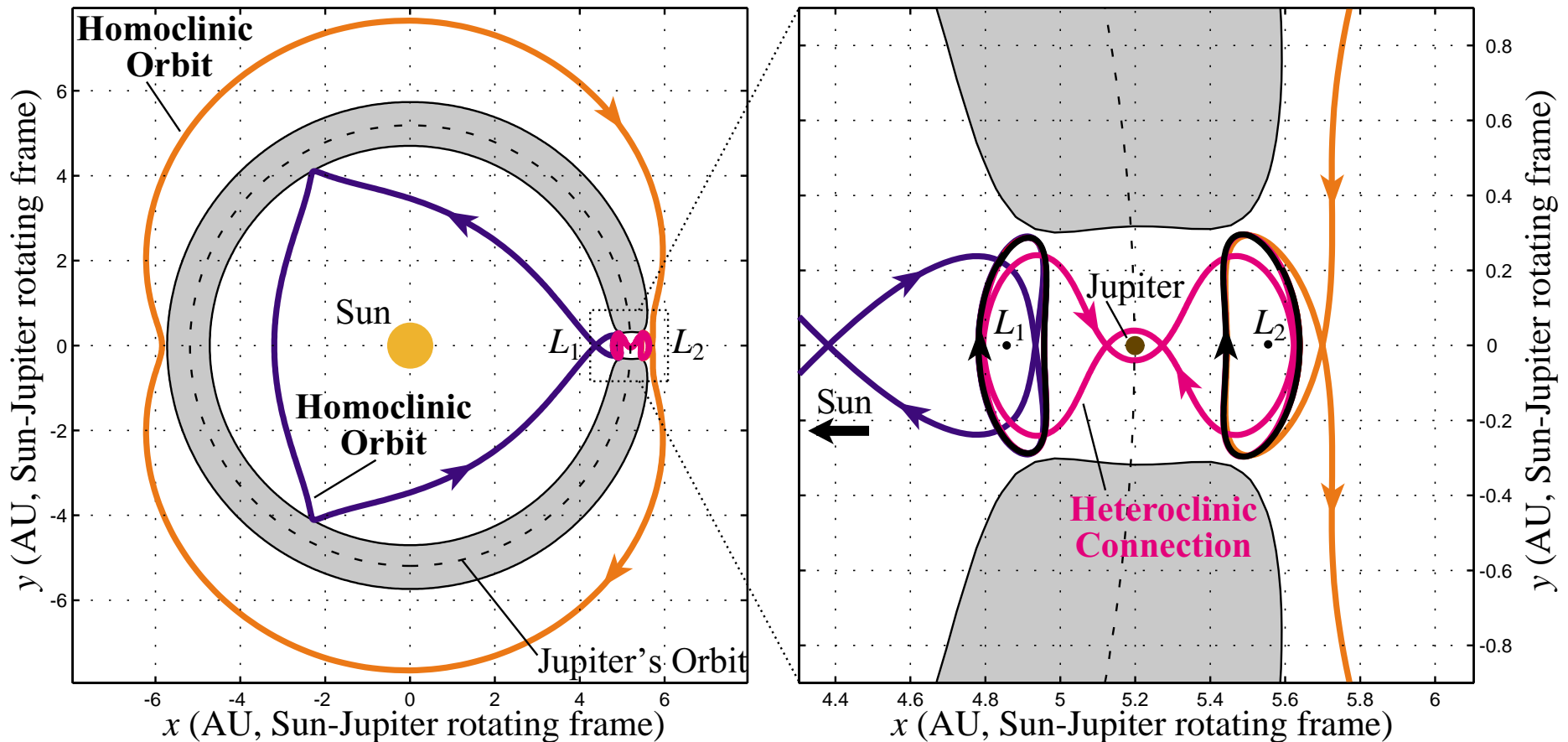
## ■ Global Orbit Structure: Main Theorem

- ▶ *Main Theorem:* For any admissible **itinerary**, e.g.,  $(\dots, \mathbf{X}, \mathbf{1}, \mathbf{J}, \mathbf{0}; \mathbf{S}, \mathbf{1}, \mathbf{J}, \mathbf{2}, \mathbf{X}, \dots)$ , there exists an orbit whose **whereabouts** matches this **itinerary**.
- ▶ Can even specify **number of revolutions** the comet makes around Sun & Jupiter.



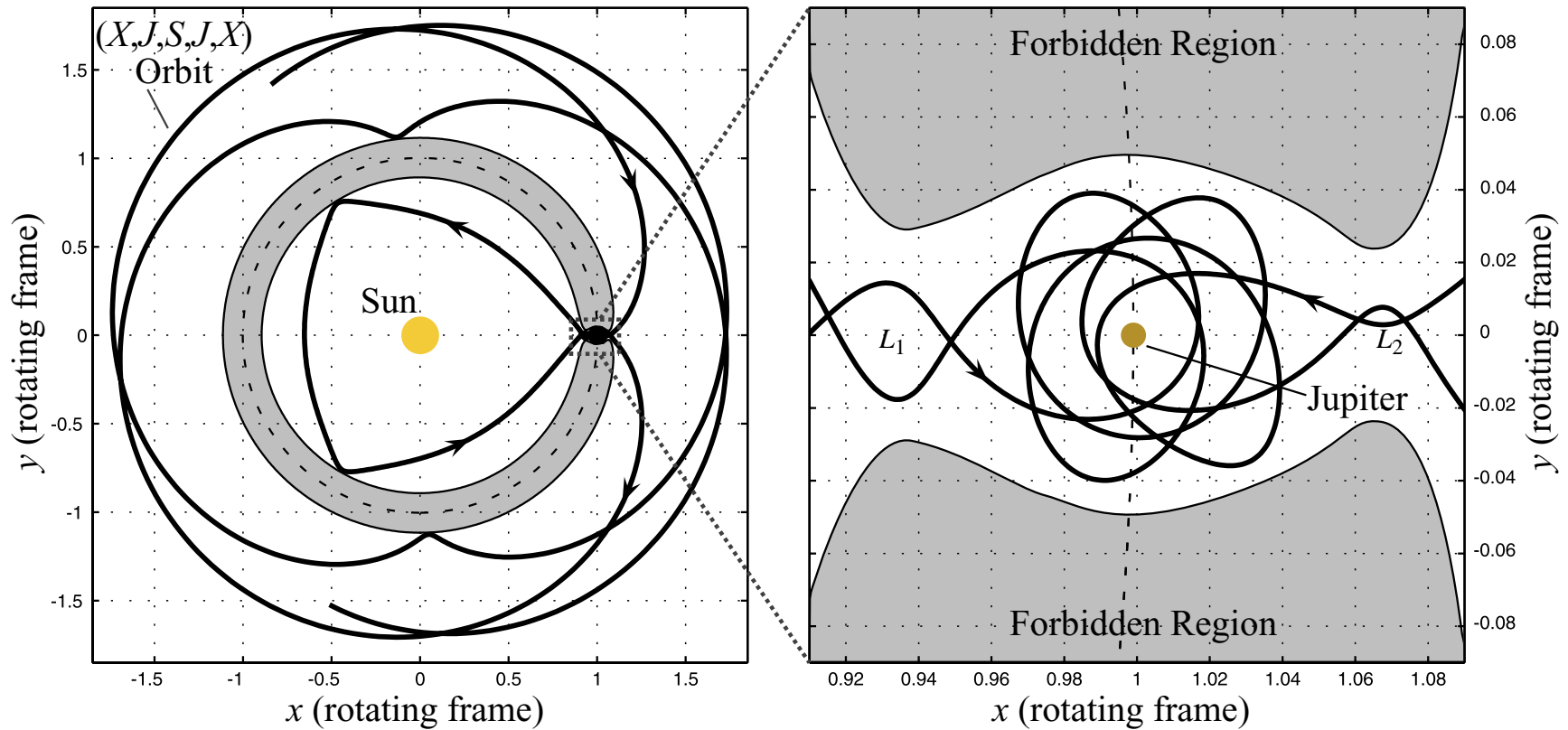
## Global Orbit Structure: Dynamical Channels

- ▶ Found a large class of **orbits** near homo/heteroclinic *chain*.
- ▶ Comet can follow these *channels* in rapid transition.

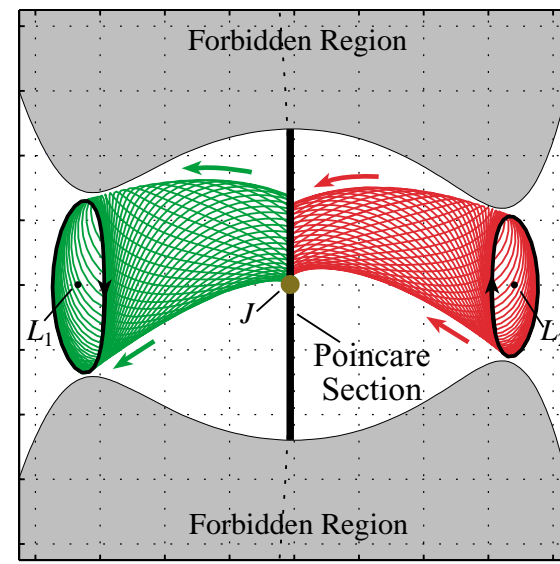
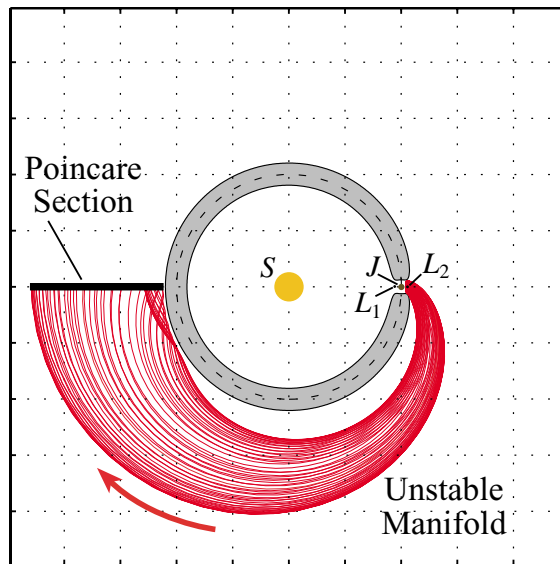
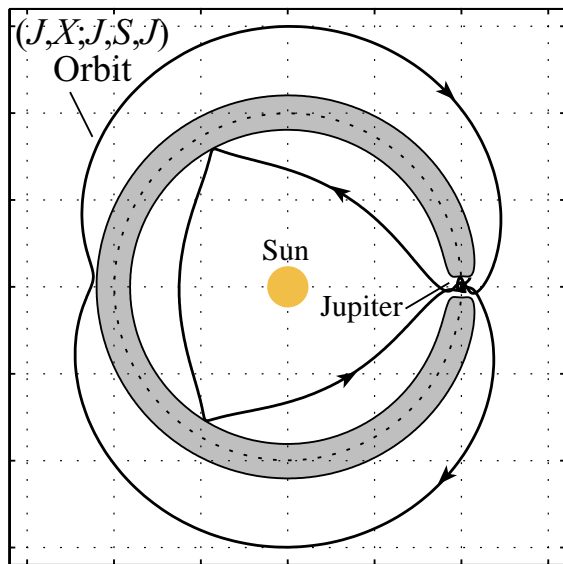


## ■ Construction of Orbits with Prescribed Itinerary

- ▶ Using the proof of **Main Theorem** as the guide, we develop procedure to construct orbit with **prescribed itinerary**.
- ▶ Example: An orbit with itinerary  $(\mathbf{X}, \mathbf{J}; \mathbf{S}, \mathbf{J}, \mathbf{X})$ .
- ▶ **Petit Grand Tour** of Jovian moons & **Shoot the Moon**.



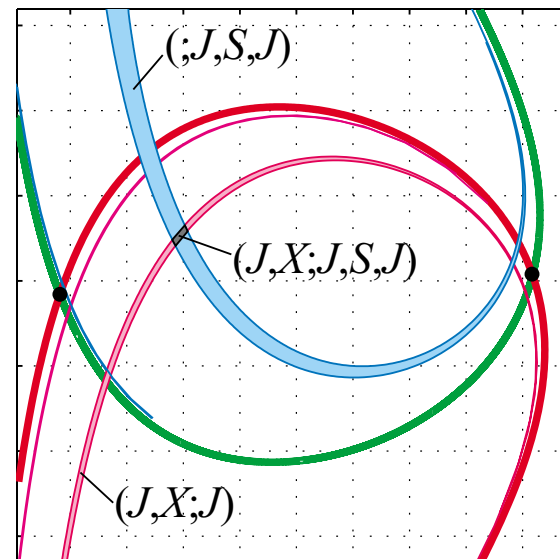
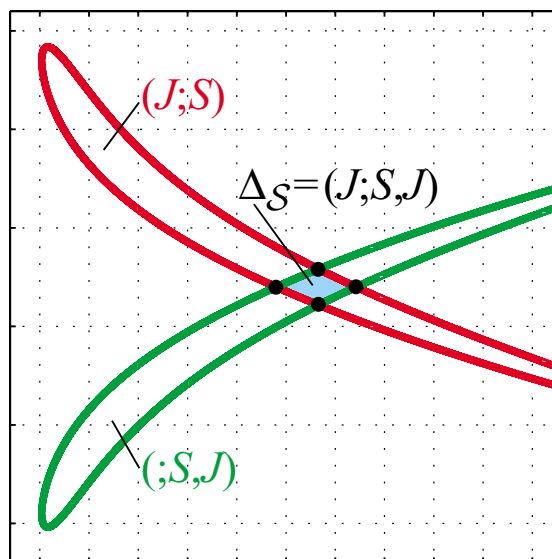
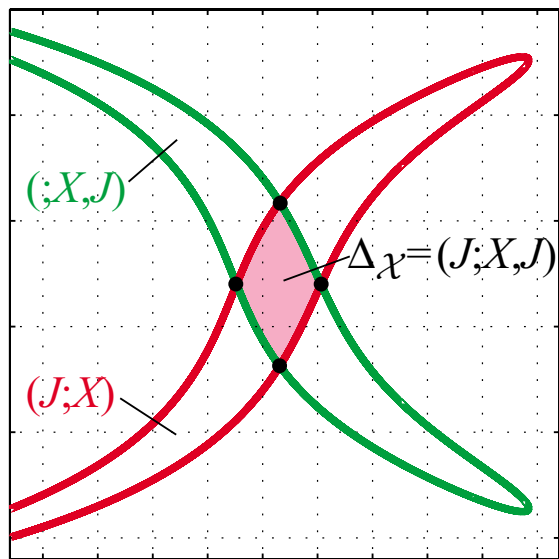
# Construction of $(J, X; J, S, J)$ Orbits



$$\Delta_{\mathcal{X}} = (J; X, J)$$

$$\Delta_{\mathcal{S}} = (J; S, J)$$

$$(J, X; J, S, J)$$



Exterior Region

Interior Region

Jupiter Region