

## LIDARデータおよび形状モデルを組み合わせた「はやぶさ2」探査機軌道改良

### Improved Trajectory of Hayabusa2 by Combining LIDAR Data and a Shape Model

\*松本 晃治<sup>1</sup>、野田 寛大<sup>1</sup>、石原 吉明<sup>2</sup>、千秋 博紀<sup>3</sup>、山本 圭香<sup>1</sup>、平田 成<sup>4</sup>、平田 直之<sup>5</sup>、並木 則行<sup>1</sup>、大坪 俊通<sup>6</sup>、渡邊 誠一郎<sup>7</sup>、水野 貴秀<sup>8</sup>、山本 幸生<sup>8</sup>、池田 人<sup>8</sup>、尾川 順子<sup>8</sup>、菊地 翔太<sup>8</sup>、佐伯 孝尚<sup>8</sup>、津田 雄一<sup>8</sup>

\*Koji Matsumoto<sup>1</sup>, Hiroto Noda<sup>1</sup>, Yoshiaki Ishihara<sup>2</sup>, Hiroki Senshu<sup>3</sup>, Keiko Yamamoto<sup>1</sup>, Naru Hirata<sup>4</sup>, Naoyuki Hirata<sup>5</sup>, Noriyuki Namiki<sup>1</sup>, Toshimichi Otsubo<sup>6</sup>, Sei-ichiro WATANABE<sup>7</sup>, Takahide Mizuno<sup>8</sup>, Yukio Yamamoto<sup>8</sup>, Hitoshi Ikeda<sup>8</sup>, Naoko Ogawa<sup>8</sup>, Shota Kikuchi<sup>8</sup>, Takanao Saiki<sup>8</sup>, Yuichi Tsuda<sup>8</sup>

1. 国立天文台RISE月惑星探査検討室、2. 国立環境研究所、3. 千葉工業大学、4. 会津大学、5. 神戸大学、6. 一橋大学、7. 名古屋大学、8. 宇宙航空研究開発機構

1. RISE Project, National Astronomical Observatory of Japan, 2. National Institute for Environmental Studies, 3. Chiba Institute of Technology, 4. The University of Aizu, 5. Kobe University, 6. Hitotsubashi University, 7. Nagoya University, 8. JAXA

Hayabusa2 spacecraft successfully arrived at the target C-type asteroid 162173 Ryugu on 27 June, 2018, with its “home position” being about 20 km above the sub-Earth point. Soon after arrival, Hayabusa2’s remote sensing instruments started near-global observations. Because map products from these instruments depend on the spacecraft position with respect to the asteroid, it is necessary to provide precise spacecraft trajectory in a timely manner. The basic idea is to find a trajectory correction which makes “LIDAR-derived topography” fit to the reference shape model. The LIDAR-derived topography is, in other words, a sequence of LIDAR footprint positions expressed in asteroid-centered body-fixed rotating frame. The footprints can be computed by using the following information; spacecraft position with respect to the asteroid, spacecraft attitude, LIDAR range, rotational information of the asteroid (orientation and spin period). If all the information above was perfect, the collective footprints would delineate the shape of the asteroid. In reality, however, there are various errors affecting the footprint positions, among which the largest is generally the trajectory error, making the resultant LIDAR footprints deviate from the shape model. We call the deviation as residual. A shape model constructed by stereo photoclinometry (SPC) method is used as reference. We obtain trajectory correction by minimizing the residuals with polynomial functions. We made use of Markov chain Monte Carlo (MCMC) algorithm to explore better parameters. We compared the LIDAR-corrected trajectory with camera positions that are determined through SPC shape modeling. The two estimates agree with each other within about 40 m on 10 July 2018, and 20 m on 20 July 2018. LIDAR-derived topography with such an improved trajectory can be used for analysis of boulder height, crater shape, surface roughness, etc.

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