



Universidad de Granada

Máster en Soft Computing y Sistemas Inteligentes

Trabajo de Investigación Tutelada

Genetic Algorithm for Robotic Telescope Scheduling

Curso académico MMVII / MMVIII

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Acknowledgement I would like to acknowledge financial support from Spanish Ministry of Education and Science via grant BES-2006-11506. This work benefits from my experiences gained developing RTS2. RTS2 development was encouraged and supported by many persons, among them worth noting are Alberto Castro-Tirado, Martin Jelínek, Ronan Cunniffe, René Hudec and Victor Reglero. This work will never be produced without kindly help and assistance of professors Francisco Herrera and Antonio Gonzáles. And I am gratefull to Rocio Romero for providing me NSGA II description.

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Preface

This work was inspired by author experiences with a telescope scheduling. Author long time goal is to develop and further extend software for an autonomous observatory. The software shall provide users with all the facilities they need to take scientific images of the night sky, cooperate with other autonomous observatories, and possibly more. It shall provide support for as many devices coming from as many different vendors as possible, yet remains "plug and play" to setup and operate.

From thirty thousands feet view, telescope time scheduling looks simple. Take some entries, select the best one, and observe it as long as possible. If it is no more worth to observe this particular position, choose another. Do so every night from dusk to dawn, see results of the night runs, analyse acquired images and try to advance mankind knowledge of the astronomy, astrophysics or physics from the acquired images.

However, as we zoom closer to provide more details about scheduling, nice flat landscape become covered with various obstacles. Start with the definition what is the best target – is it the one which is currently rising or the one which is setting and so telescope will not have possibility to observe it again for some time. And what about future plans? Is it better to observe star A, and in a few weeks time star B, or shall the observatory pick star A and B at the same night?

No wonder that scheduling is one of the major issues of current world class observatories, both ground and space. Usual approach is to have some time allocation committee, which pick which observations proposals are worthy to observe, and then meets every day, week, month or year to discuss which objects will be observed during the next period. Rules are created for sharing risks between an observatory and the observation proposal authors – for example it has to be defined what shall happen if bad weather prevents observations on a ground observatory, or if data are lost during transmission from a satellite to the ground. And humans, which are member of time allocation committee, make sure that all observation constraints are obeyed and that users are happy with acquired data and do a lot of interesting and useful science based on the data acquired.

Autonomous observatories are by definition autonomous. They do not have any time allocation committee composed of smart people. They are destined to create observation strategy from inputs which human operators provided to them and/or from results of the previous observations. This works provides overview of the various constraints and objective of the observatory, and gives some solution to the scheduling problem.

The obvious question which can be asked is why we need the schedule at

all? Would not it be better to simply pick the best observation, and then the next one, as mentioned above? Is not this a principle of the queue scheduling, which is used on most of the human operated observatories today? There are various hints which gives us answer that this is not a desired operation for the autonomous operations.

The first one comes from possible network scheduling. Network nodes can of course be scheduled locally. But that will not exploit network advantages. Network can observe one star simultaneously over period longer than usual dark period at a single site. For this kind of observations some collaboration among schedulers is needed. One of the possibility is to let local scheduler collaborate and create a plan. Second possibility is to have possibility to centrally schedule network observations. Our experience shows that while first option is feasible, second is more easily controlled and monitored by a human operator.

The second case come from operation of a single instrument. Our experience shows that it is handy to have a schedule before start of the night to check what observatory will do during night. The system poses option to create an observing plan and then to execute it, but plan has to be created somehow. And as the scheduling process is annoying and can only distract person doing it from other work, plan creation has to be automated. With human experts possibly reviewing it and taking actions if they found something strange on the schedule.

Chapter 1

Introduction

RTS2[9] is an open-source software package for robotic observatory. Apart from a central server, device drivers and various other functions, it provides service for target selection - a selector.

Current selector uses a simple single merit function selection to select next observation from the list of the possible observations. The merit function, which measure how good is a target for observation, is hard-coded in selector code and cannot be easily modified. Moreover, current selector does not allow generation of an observing plan for a full night. Current design allows only selection of the next target. After the current target observation is finished, the target with the highest current merit function value is selected by the selector. Creating night schedule for telescope belongs to NP class of problems. Some heuristic might apply, but the problem will remain hard to solve.

This work describes design and implementation of a selector based on genetic algorithm. This selector allows generation of the full night plan. It must also keep an overview of which important targets remain to be observed, and allow to schedule them appropriately. The algorithm must be extensible for scheduling of the robotics telescope network. And it must be written so it can be easily integrated with the current RTS2 code.

1.1 Basic definitions

Target is an object on the sky telescope users would like to observe. It can have fixed coordinates (stars,..) or its coordinates can change with time (planets, solar system minor bodies,..). For given time and location, target altitude, zenith distance and azimuth can be easily calculated.

Observation is one visit to the target. During observation, target can be observed in different colours, using filters placed in optical path by some rotating mechanism. If an observation does not satisfy user needs (e.g. does point to clouds, instrument problems occurred during observing run,..) it shall be rescheduled. Observation usually consists of images acquired with different filters. For some targets the length of the observation can be modified, for others it must remain fixed.

1.2 Constrains

The following constrain might apply to a target:

- target must be **visible**, e.g. above local horizon
- various constraints based on **lunar distance** of the target, solar distance, moon phase (some targets cannot be observed with a full moon, etc..).
- **budget constraints** – time allocated to target/user can be limited, and target cannot exceed it
- **time** – some targets required observation in a given time, some can be observed anytime they are visible, some targets should be observed only once per night, week, .., as other observations will not lead to increase in the scientific return obtained from the acquired images
- when scheduling a network of autonomous observatories, some observations can be carried either simultaneously with two or more telescopes, or observation with one telescope must follow observation with another telescope

Constraints are formalised in the third chapter.

1.3 Selection of the best schedule

Astronomers would measure an observatory success by a number of the articles which reference the observatory (possibly weighted by the journal citation index). Because scheduling does not pose black magic it is unable to predict which targets observations will contribute to the most interesting discoveries and scientific papers. So some evaluation function has to be defined which compares targets. The goal would be to found a sequence with the highest sum of observation fitness values, while keeping the constrains outlined above. Evaluation can be based on:

- **height** of the target during observation (higher is usually better)
- **distance** of the target from the Moon or any other sky body
- **quality** of the proposal (some accepted targets may only fill the gap, other can be ranked as top priority by evaluation committee)

Formalisation of the various fitness measurements is described in the third chapter.

1.4 Genetic algorithms for robotic telescope scheduling

Aim of this work is to design, develop and tests various genetic algorithm for scheduling of the robotic observatories. Problem is similar to job shop scheduling, and thus belongs to NP-hard problems. Schedule for one telescope and scheduling of telescope network will be investigated.

1.4. GENETIC ALGORITHMS FOR ROBOTIC TELESCOPE SCHEDULING3

Problem input consists of targets and their characteristic. Target is location on the sky which can be visited by telescope to acquire data. Each target have constrain which specify when it can be observed.

Output is list of targets and their observations times on the telescope or on the telescope network.

Chapter 2

Autonomous robotic observatory

Autonomous robotic observatory is a complex environment of computers, networks and instruments. Aim of an autonomous robotic observatory is to carry observations of night sky and record the observations using CCD cameras or other instruments.

Most of the modern astronomical observatories are controlled by computer. But degree at which computer is in charge of the observatory varies significantly.

One extreme is a computer controlling only the telescope, and offering observer quick way how to enter target coordinates. Observer is then responsible for scheduling, acting as coordinator synchronising various instruments, recording data and processing them.

Other extreme end of observatory a complete autonomous observatory. Software is then responsible for observatory operations, opening and closing of the roof, assuring that observatory is protected from elements, and reducing data.

Only a few world observatories are operated in a fully autonomous mode, without night operator overseeing night operations. Full list of observatories which claims to be robotic is provided at [7]. It should be noted, that RTS2 operates at least 6 telescopes with others coming hopefully in near future. And at least 2 of those were run in fully autonomous mode over periods of years - FRAM and Watcher.

Major current projects which operates and further extend fully autonomous observatories ¹ are ”*Thinking Telescope/RAPTOR*” developed at LANL[17], AudeLA developed at Observatory de Haute Provance[8] and Las Cumbres Observatory Global Telescope Network[2] – eStar project[4], which operates Faulkes Telescopes. It should be noted, that from those only eStar is actively investigating telescope scheduling[5], and AudeLA is the only other project which provides observatory control system under open source license.

Majority of the world observatories operates in semi automatic mode. Scheduling is usually done by human in the loop, supported by tools to help him/her decide the best strategy. Following paragraphs provide review of the current practice at leading Spanish and European observatories.

¹of which author of this work is informed

2.1 CAHA

Calar Alto Hispano Aleman (CAHA) observatory currently operates two major instruments - 3.5m and 2.2m telescope. Both are remotely controlled by night operators. For troubleshooting, operators are equipped with a torch, two way radio and a car to drive to the instrument. Some scripting is provided for some observations, but it is a night assistant who is responsible for operating the instrument.

Scheduling on 2.2m is done on paper basis, with observer having printed observing proposal for a night and selecting two or three observations he will be performing during night. He is then responsibly to enter targets to the schedule and oversee that observations are performed as expected.

Scheduling of 3.5m is even more complicated. Night staff have printed observing proposals, pick up the one that will be observed and according to proposal text handle instrument setup and observation synchronisation.

2.2 OSN

Observatory de Sierra Nevada has three major instruments – 1.5m, 0.9m and 0.6m telescope. The 0.6m is controlled by RTS2, so it is designed to be fully autonomous. The other telescopes are controlled by night observer, who either carry all observations himself, picking targets from a prepared list, or enter current target to observatory control system and check that the observations are performed as expected.

2.3 ESO VLT

European South Observatory Very Large Telescopes are operated in queue scheduling[15]. Night observers have screen with preselected list of possible observations. Depending on observing conditions, their experience and mood they select and oversee progress of the observation they choose to perform.

2.4 GTC

Grand Telescopio de Canarias is now in commissioning phase. So far queue scheduling is envisioned once telescope will be open for scientific observations. Software for telescope operation posses similarities with ESO BOSS[15], mentioned above.

Chapter 3

Formalisation of the observation scheduling problem

The problem deals with distributing time on a single instrument. Night is time when observatory is operational and can take observations. Schedule is sequence of targets which will be observed during night. Each target have position where it will be observed, observation script which defines how the observations will be observed - for example which filters and exposures combinations will be used during observation. For each target, various properties are set, and other properties can be calculated.

In the following paragraphs are defined terms that will be used when dealing with scheduling problem.

3.1 Night

Night start at some time after sunset and ends at some time before sunrise. More complicated scheduling scenarios might include use of twilight period, when observation is possible on certain parts of the sky. To keep problem simply it is assumed that night runs from time N_s till time N_e . Night has then duration $N_d = N_e - N_s$.

Observatory operation can be disturbed by various factors. Those can be divided into predictable and unpredictable interruptions. Predictable interruptions are usually caused by maintenance work, which must be performed at given time at the observatory. Unpredictable is weather, which causes major observatory downtime, and technical issues with the observatory, which causes some downtime. Depending on various factors (location, season, ..) weather usually account for downtime between few percents up to 100%. But observatories are usually not build on sites where back weather account for more then 70% of available night time. Technical downtime is on tuned-up systems less then 1%.

Unless explicitly specified, a case of an ideal observatory without any downtime is considered.

3.2 Observing sequence

Observing sequence describes how the observation of a target is carried. It is a sequence of camera exposures, telescope operations and various modifications performed on instruments on light path. For some targets, observing sequence can be looped. For others, only single observation must be carried.

3.3 Target

Target is a position on sky which can be observed. Target has sky location, usually expressed in equatorial coordinate system as right ascension and declination. Each target has assigned observing sequence.

Observing sequence can change depending on various parameters. But that change will make problem even more complex. Unless explicitly stated, only case of a single observing sequence for a target is considered.

Targets are included in set TS . Size of target set is equal to $|TS|$.

3.4 Observation

Observation is a single visit of the telescope of a single target location. Data are acquired during observation. Observing sequence describes how the data shall be acquired.

3.5 Duration of target observation

Each target have three major duration values. When combined together they describe how much night time will be used by a single target observation. Slew time, T_s , describes how much time will be spend by slewing telescope on target. Shutter open time, T_o , gives total time of the exposures taken for a single observing sequence of target. Total observation time, T_t , gives time spend in a single observing sequence. If telescopes moves during observing sequence, T_t contributes to total observing time and not to slew time – slew time is only the time needed to perform first slew to target.

Observing sequence can be repeated l times, where $l \geq 1$. Dark time T_d , time when shutter is closed, is equal to

$$T_d = T_s + l * (T_t - T_o)$$

Target slew time depends on previous telescope position. For some targets, observing sequence can be looped and so total observing time can change in multiplies of observing sequence duration. For others targets, only single observing run must be performed, and so total observing time cannot change.

Total observation time TT is then calculated as

$$TT = T_s + l * T_t$$

3.6 Observation fitness

Observation fitness describes how good is it to observe a target at a given time. It is important to realize that the position of the target on the sky and its distance to various disturbing bodies depends on time. Hence observation fitness depends on time. So the observation fitness can be described as function:

$$f : \text{time} \Rightarrow \text{fitness}$$

where time is time variable and fitness is some arbitrary set which describes target fitness.

To make further explanation more understandable, we divide the fitness function into two parts. The first depends only on time, second depends on a target position. Following two paragraphs describes various fitness functions. The first paragraph describes those which depends primarily on time, the second those which depends on target position.

For algorithms to transform object coordinates to object position at a given time, and to calculate object position with respect to other bodies, please refer to [12]. Please see libnova ([11]) for their implementation.

3.7 Observation time fitness

To formalise observation time fitness binary logic is used. It is either interesting or uninteresting to observe target at a given time. So the fitness function is one returning either 0 or 1:

$$f_t(t) = 0 \vee 1$$

The f_t function can depend on various factors. Even through the author of this text gain some experience in the area, full list of those factors is beyond his current knowledge. The ones he can mention are: **time from last observations of the object, brightness of the object which show periodic brightness variations and special observing circumstances.**

Time dependent brightness variability of the objects observed by the astronomers can be separated into three classes: regular time variability in brightness, irregular time variability and brightness variability bellow detection limit of the instrument. The objects can also show regular time variability with superimposed irregular time variability.

Objects without any significant brightness variability have time fitness constant through whole night. Objects which shows regular time variability are usually worth observing at a certain time in the variability period. Hence those objects should have time fitness higher when it is worth observing them.

Objects showing irregular time variability can be observed anytime. However, if instrument or other astronomers detects that the object of interest is showing some interesting behaviour, usually increase in brightness, they shall be visited more frequently.

Time from the last observation of an object

This case can be used when astronomer would like to monitor the object behaviour in predefined intervals. If he/she is interested in variability of the object

at time scale of t_{var} seconds, then the observations shall usually be carried every $\frac{t_{var}}{2}$ seconds. So the $f_t()$ function will be written in form:

$$f_t(t) = 1 \iff now - T_s \geq \frac{t_{var}}{2}$$

where now is current time and T_s is time of start of the last observation of the target.

Phase of the object which show periodic brightness variations

Suppose that an object has periodicity P_l seconds. Suppose that one know period started at time P_s . Astronomer is interested in data taken in phase between H_s and H_e . Then time fitness function will then become:

$$f_t(t) = 1 \iff \exists h \in Z : now - P_s - h * P_l \in \langle H_s, H_e \rangle$$

Special observing circumstances

Special observing circumstances are some know circumstances which will occurs and which will make target observation interesting. For example, consider transit of some solar system body in of some bright background stars. The transiting body can be as big as the Moon and as small as some minor solar system body. If astronomers have precise timing of transit, they can calculate object size and others interesting parameters.

Of course not all targets shows this dependency. For them, the special time fitness function f_s is equal to 1. For those which have special time dependence, there is set of times when observation should start. The duration of observation is governed by observing sequence. To formalise this, we have a set TC of pairs T_s, T_e . Then fitness function f_s is defined as:

$$f_s(t) = 1 \iff \exists s \in TC : t \in s$$

3.8 Observation position fitness

Following paragraphs describes some of the time fitness functions, which depends on target position. As was mentioned in introduction to this chapter, position of the target can be calculated from time and target properties.

First some introduction to how target position can depend on a time is given. Then various factors which affect target fitness depending on its position are described.

Objects observed by astronomers are located on the stellar sphere. As earth rotates, those objects show apparent movement on the sky. Furthermore position of objects which are close enough to the Earth and moves significantly in respect to the Earth changes with regard to the stellar sphere. For example objects in the solar system – planets, dwarf planets and other solar system bodies – moves on the sky with comparison to more distant background stars. Satellites on the Earth orbit moves even more quickly then the solar system bodies.

Relation between object position and Moon position

Moon significantly increases sky brightness. Increased sky brightness can make some observations useless, and other more difficult to process. The targets can have following constraints:

- target cannot be observed if Moon height is above certain limit
- target cannot be observed if Moon phase is in certain interval and Moon height is above certain limit
- those which can be observed only if their distance to the Moon is above certain limit and Moon phase is above certain limit

As Moon sky position changes roughly by 13° in 24 hours, object distance to the Moon does not change significantly during night. Moon phase, if measured in range $< 9^\circ, 360^\circ >$, changes by same amount. This shows that fitness function based on moon position, f_m , will not show great variance during night if it depends only on distance of the object to the Moon. So f_m with only two possible values, 0 or 1, is used. So for a target with duration TT , f_m is defined as:

$$f_m(t) = \begin{cases} 1 & \text{if all moon constraints are valid in time } < t, t + TT > \\ 0 & \text{otherwise} \end{cases}$$

Object altitude

Object altitude changes during the night as it moves on the sky. For an object with *declination* δ and hour angle H , and observing site with latitude ϕ , the altitude h of the object is calculated as:

$$\sin(h) = \sin(\phi) * \sin(\delta) + \cos(\phi) * \cos(\delta) * \cos(H)$$

The minimal altitude of an object attained during 24 hours $A_{day_{min}}$ is for an observer on northern hemisphere calculated as

$$A_{day_{min}} = \phi - 90^\circ - \delta$$

The maximal altitude $A_{day_{max}}$ is equal to

$$A_{day_{max}} = 90^\circ - \phi + \delta$$

For an observer on southern hemisphere signs in the above formulas before ϕ and δ has to be swapped.

As objects can be observed only during night, more important are values of $A_{nigh_{min}}$ and $A_{nigh_{max}}$, the maximal and minimal altitudes of the object during night. Those are calculated as

$$A_{nigh_{min}} = \begin{cases} A_{day_{min}} & \text{if } t_{lowertransit} \in < N_s, N_e > \\ \min(A_{N_s}, A_{N_e}) & \text{otherwise} \end{cases}$$

$$Anight_{max} = \begin{cases} Aday_{max} & \text{if } t_{uppertransit} \in \langle N_s, N_e \rangle \\ \max(A_{N_s}, A_{N_e}) & \text{otherwise} \end{cases}$$

Those calculations reflect fact that minimal or maximal altitude is reached either during given interval or on one of its edges.

Each target T has low observing altitude TA_{min} . It is useless to observe the object bellow this altitude. So if h is target altitude, then position fitness function is equal to 0 if $h \leq TA_{min}$.

If we do not consider changes in weather, which might render target observation useless, then the best time for target observation is when its altitude is maximal. To formalise this, height fitness function f_h has range $[0,1]$ and is calculated as

$$f_h(h) = \begin{cases} 0 & \text{if } h \leq TA_{min} \\ \frac{h - \max(Anight_{min}, TA_{min})}{Anight_{max} - \max(Anight_{min}, TA_{min})} & \text{otherwise} \end{cases}$$

3.9 Observation accounting

Observatory time is usually shared by multiple groups. They contribute to capital and operational costs of the observatory. Based on their contribution they are allocated some fraction of the observatory time.

The time sums over given period and the fraction left for the observation is adjusted accordingly. Suppose that we have two groups sharing time on the telescope, both having equal share (50%) of the telescope time. Then if two nights are scheduled, and one group receives first night for its observations, the other group shall get remaining full night.

Time allocated to the groups is accounted, and compared with the share values. If some shared values drop bellow reasonable number, system must give higher preference to this group in order to successfully fill requested share fractions.

To formalise this mechanism consider a accounts. Vector A of length a holds fraction of time allocated to each account. It is clear that

$$\sum_{k=1}^a A[k] = 1$$

Vector OA of length a holds seconds accounted for various groups. Total time of all observations, OT , can then be calculated as

$$OT = \sum_{k=1}^a OA[k]$$

If $OT > 0$, current percentage for a given account, $OC[k]$, is calculated as

$$OC[k] = \frac{OA[k]}{OT}$$

3.10 Observation schedule

Observation schedule is an ordered sets of targets. For each target, starting time is provided. After target is selected for observation, telescope is slewed to target position and observing sequence is executed. Shutter open time and total observing time can be calculated for observing sequence provided with target.

Schedule is a set of three vectors of length s . Vectors are SS , ST and SL . Vector SS contains start time of observations. Vector ST contains targets which are scheduled for observation. And SL contains observation loop counts. For feasible schedule, following conditions must be fulfilled:

$$\forall_{k=1}^{s-1} SS[k+1] \geq SS[k] + T_s[ST[k]] + SL[k] * T_t[ST[k]]$$

$$\forall_{k=1}^s SL[k] \geq 1$$

$$SS[1] \geq N_s$$

$$SS[s] \leq N_e$$

3.11 Number of targets observed during night

Observing schedule should try to visit as much targets during night as possible. Schedule which contains only observations of two targets visited through whole night is most probably not better then schedule with three, four or more targets. That is because due to probability, more visited and observed targets can bring more opportunities to discover new science and hence write a good paper - and as mentioned at the beginning, the whole game is at the ultimate end about publications.

On the other hand, an excess fragmentation of night time is weighted good. Excess fragmentation will make long-duration observations highly improbable. Long-duration observations are necessary for planet transits and other science. The solution may be found in a careful examination of the possible schedules and picking sometimes ones with fewer targets, but more long-duration runs, and sometimes go for a large night fragmentation.

It must be also mentioned that big fragmentation naturally allows better time distribution and hence creating a schedule which will fill accounted time of various groups. So the system shall aim for a bigger fragmentation in order to be able to better distribute remaining time.

There should be an objective night fragmentation, expressed in number of targets visited during night. The better schedule is the one with number of targets visited closer to this number.

Chapter 4

Time-dependent objective functions

This section deals with problem of using various, usually time-dependent target fitness functions to calculate fitness of the whole schedule.

As two different schedules can hold different number of targets, using sum of observation fitness included in schedule will be useless. It is also important to note that observation fitness can be different during duration of the observation. For example value of observation position fitness calculated from object altitude will change with a daily and other movement of the object on the sky.

The first solution to those problems is to use average fitness calculated at the midpoint of the observation duration, which can be expressed as:

$$\frac{\sum_{k=1}^s f^{ST[k]}(SS[k] + T_s[ST[k]] + \frac{SL[k] * T_o[ST[k]]}{2})}{s}$$

where $f^T(t)$ is value of the fitness function for target T at time t , and there are s targets in the schedule. There are however still some problems associated with this approach:

- as there are multiple fitness functions, it does not present single objective, but rather multiple objectives
- fitness value at the various times can differ significantly from fitness value at the observation middle time
- the functions does not differentiate between schedules with higher number of observations and those with fewer observations

To handle differences due to time used for calculating observing fitness, minimum can be used. So the function then becomes:

$$\frac{\sum_{k=1}^s \min_{t \in \langle SS[k] + T_s[ST[k]], SS[k] + T_s[ST[k]] + SL[k] * T_o[ST[k]] \rangle} (f^{ST[k]}(t))}{s}$$

This function truly evaluates targets merit functions. Averaging will make sure that schedules with fewer observations will not be disadvantaged against schedules with more observations.

Most probably fitness functions shall be evaluated separately. As some objectives are contradicting it is impossible to construct schedule with only the best observations at the best times. There will be multiple paths to choose from, and the whole play is about sufficient balance between different objectives.

Chapter 5

Multiobjective scheduling optimisation

Multiobjective scheduling optimisation is discussed in great detail in [1]. Here are discussed various method to select best schedule in problems with multiple independent objective functions. The possible solutions are reviewed bellow.

5.1 Weighted single objective function

This is probably the simplest approach. Objective functions are multiplied with weighting factors and summed together to form a single objective function. Scheduling algorithm then search for schedule with highest single objective function.

The major disadvantage of this approach is necessity of finding correct weight factors.

5.2 Single objective function, move others objectives to constraints

This approach picks the most significant objective as the single objective. Other objectives are then used as schedule constraints.

Major disadvantage of this approach is in specifying correct constraints for objective functions which are not used as a single objective. When the constraint range is too narrow, there is a risk of loosing some good solution because they will slightly not fit inside the range. If the range is too wide, there is a risk of finding schedules way from the best one.

5.3 Searching Pareto optimal solutions

Pareto[14] optimality is named after Vilfred Pareto. This method search for all nondominant solutions. It overcomes disadvantages of both previous approaches by finding subsurface in the solution space with the best possible tradeoffs be-

tween various objective functions. It does not need any weight factor nor correctly picked constraints.

Genetics algorithms are very good in finding Pareto optimal subsurface. As the algorithm always operates with multiple solutions, they can represent multiple points on Pareto optimal subsurface. So the genetic algorithm naturally fits in Pareto search.

Following section describes one of the genetics algorithm variants, know as Nondominated Sorting Genetic Algorithm II - NSGA II.

Chapter 6

Nondominated Sorting Genetic Algorithm II

Scheduler uses Nondominated Sorting Genetic Algorithm II (NSGA-II) developed by Deb et al. A short description provided by Deb et. al. [3] is the following:

The step-by-step procedure shows that NSGA-II algorithm is simple and straightforward. First, a combined population $R_t = P_t \cup Q_t$ is formed. The population R_t is of size $2N$. Then, the population R_t is sorted according to non-domination. Since all previous and current population members are included in R_t , elitism is ensured. Now, solutions belonging to the best non-dominated set F_1 are of best solutions in the combined population and must be emphasised more than any other solution in the combined population. If the size of F_1 is smaller than N , we definitely choose all members of the set F_1 for the new population P_{t+1} . The remaining members of the population P_{t+1} are chosen from subsequent non-dominated fronts in the order of their ranking. Thus, solutions from the set F_2 are chosen next, followed by solutions from the set F_3 , and so on. This procedure is continued until no more sets can be accommodated. Say that the set F_i is the last non-dominated set beyond which no other set can be accommodated. In general, the count of solutions in all sets from F_1 to F_i would be larger than the population size. To choose exactly N population members, we sort the solutions of the *last* front F_i using the crowded-comparison operator \prec_n in descending order and choose the best solutions needed to fill all population slots. The NSGA-II procedure is also shown in Fig. 6.1. The new population P_{t+1} of size N is now used for selection, crossover, and mutation to create a new population Q_{t+1} of size N . It is important to note that we use a binary tournament selection operator but the selection criterion is now based on the crowded-comparison operator \prec_n . Since this operator requires both the rank and crowded distance of each solution in the population, we calculate these quantities while forming the population P_{t+1} , as shown in the above algorithm.

The components of the NSGA-II scheduling structure are described as follows:

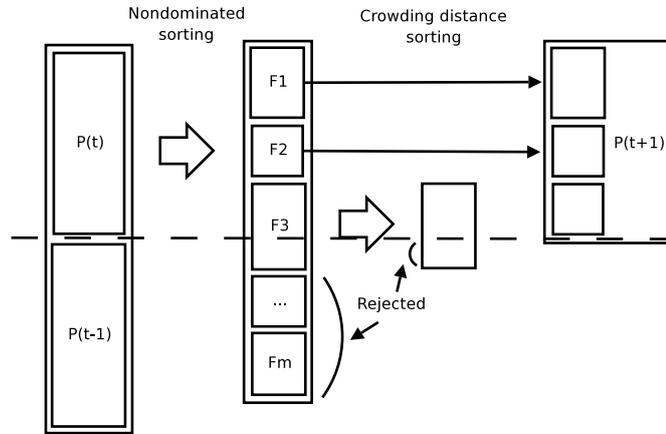


Figure 6.1: The NSGA-II algorithm [3].

6.1 Chromosome Representation

RTS2 NSGA-II scheduling encodes only feasible schedules in each chromosome. Chromosomes are implemented as an array of observing entries. The gene in chromosome is a record containing starting date, duration and pointer to ticket¹. The initial population consists of a set of random schedules, generated using random number generator. The set of all nondominant chromosomes of the final population represents an optimal schedules.

6.2 Genetic Operators

RTS2 NSGA-II scheduling applies crossover and mutation operators with a given probability over the chromosomes composing the GP population. The crossover operator consists of the following steps:

- pick a random time T_{cross} between night start and night end.
- construct beginning of the resulting schedule by using observations from first schedule till T_{cross}
- add schedules to the resulting schedule from second schedule, starting from T_{cross} .
- repair resulting schedule, so it is feasible - adjust schedule starting time, and schedules duration. If schedule duration cannot be adjusted, remove shortest schedule.

The mutation operators used in RTS2 NSGA-II scheduling implementation are those:

- Delete a random selected observation
- Change ticket entry of a random selected observation

¹which contains observation details - target, account etc.

- Adjust duration by a random time of a randomly selected observation

After the mutation is performed, resulting schedule is repaired by same algorithm used for repairs after crossover.

6.3 Selection

RTS2 NSGA-II scheduling employs a crowded binary tournament constraint – dominated selection operator [3]. Assuming that every individual in the population has three attributes: number of violated constraints ($i_{violation}$, nondomination rank (i_{rank}) and crowding distance ($i_{distance}$), the crowded constraint – dominated operator \prec_{cc} is defined as

$$i \prec_{cc} j \iff \begin{cases} (j_{violation} > 0 \text{ and } i_{violation} < j_{violation}) \\ \text{or } (i_{rank} < j_{rank}) \\ \text{or } (i_{rank} = j_{rank} \text{ and } i_{distance} > j_{distance}) \end{cases}$$

See [16] and [3] for a complete description.

6.4 Constraints

Selection of crowded constraint – dominated selection operator allows easy addition of new constraints. Constraint functions returns integer values, which tell how many constraints are violated. The objective of algorithm is to minimise this value, so there will be as few constraints as possible. The following constraints can be used:

- **Visibility.** Observation violates visibility constraint, if it is not visible during its scheduled time.
- **Schedule time.** Observing ticket might provide time during which observation should be carried. If observation is not carried in the specified time interval, it breaks schedule time constraint.
- **Unobserved tickets.** If time period during a ticket should be observed intersect with interval being scheduled and it is not selected for observation, it violates this constraint.
- **Number of observations per ticket.** Some tickets might provide number of observation required to be performed of the target. Schedule violates this consists if more observations of the ticket are schedule.

6.5 Fitness functions

One of the principal advantages of NSGA-II multi-objective algorithm is ability to easy add new fitness functions. Following fitness functions are used: *altitude*, *observation distance*, *account*, *target diversity*, *observation diversity*. The diversity functions conflicts with observation distance - if schedule has better diversity, it has worse observation distance and vice versa. The implementation works to maximalize fitness functions and minimalize constraints violations. In

the fitness functions description is provided note if target is to maximalize or minimalize its value. If not specified otherwise, it is assumed that if objective is to minimalize fitness value, inverted value is used in algorithm for maximalization.

- **Altitude merit.** Altitude merit is calculated as ratio of mid altitude to maximal possible altitude which target can have during night. For a given observing ticket it is calculated as:

$$f_h(h) = \begin{cases} 0 & \text{if } h \leq TA_{min} \\ \frac{h - \max(Anight_{min}, TA_{min})}{Anight_{max} - \max(Anight_{min}, TA_{min})} & \text{otherwise} \end{cases}$$

For final schedule merit is used average of those ticket functions. Objective is to maximalize this value.

- **Observation distance merit.** This merit is calculated as sum of distance of the telescope travelled. Its purpose is to minimalize time telescope will spend moving from one location to the other. For a single observation it is calculated as:

$$f_a() = \text{angularDistance}(Position_{end}^{previous}, Position_{start}^{current})$$

Sum of the individual values is used. Objective is to minimalize this value.

- **Account merit.** Account merit is calculated as ratio of observed schedule account use versus requested account use:

$$AD = \sum_{k=1}^a \frac{|OC[k] - OA[k]|}{OA[k]}$$

where AD is sum of proportional differences of requested and observed accounting.

Objective of the scheduling algorithm is to find schedule with minimal deviation from requested time share. Time share is accounted usually by longer intervals, months, semesters or year. So the scheduling algorithm shall give lower priority on fairness of the selection at the beginning of the accounting period then at the end of the accounting period.

- **Target diversity merit.** Target diversity merit is calculated as number of targets observed in the schedule. Objective is to maximalize this function.
- **Observation diversity merit.** Observation diversity merit simply counts observing entries in the schedule. Objective is to maximalize this function.

Chapter 7

Implementation

Because RTS2[10] is mostly coded in [6], choice of the language in which scheduler shall be written was pretty obvious. Coding was done in the Vim[13] editor. debugging was done using Valgrind and GDB: The GNU Project Debugger.

Code was documented using Doxygen. The design relies as much as possible on standard template library provided by GNU libstc++. LibNova was used for various astronomical calculations.

The implementation benefits from object oriented approach. It provides classes which holds list of schedules = *GA population* = **Rts2SchedBag**, schedules = *chromosomes* = **Rts2Schedule** and observation entries = *genes* = **Rts2SchedObs**. Observation targets are subclasses of **Target** class, created by a standard **createTarget** call. **Rts2SchedBag** provides methods for GA algorithms. **Rts2Schedule** provides methods for chromosome evaluation.

Interface for testing was written as subclass of the standard **Rts2AppDb** class. The interface provides few options, and prints out results in simple space separated format. The output can be feed directly to **GNUPlot** plotting program. It is expected that scheduling classes will be integrated to RTS2 as a standard library.

During development *iterative life cycle* was used. Small parts of the system were developed, tested and results checked. The following sections document progress of development.

Development was initially committed to **REL_0.8.0** branch. After firsts successful tests of GA code, branch was merged to trunk.

7.1 Simple test

First test was done on a simple genetics algorithm for selecting visible schedules. Target set consists of flat field targets used to obtain calibration observations. Plot of targets altitude as function of time observed from a site at 36° north latitude are show in figure 7.1. As targets are distributed along the celestial equator, it is possible to observe each target for 12 hours.

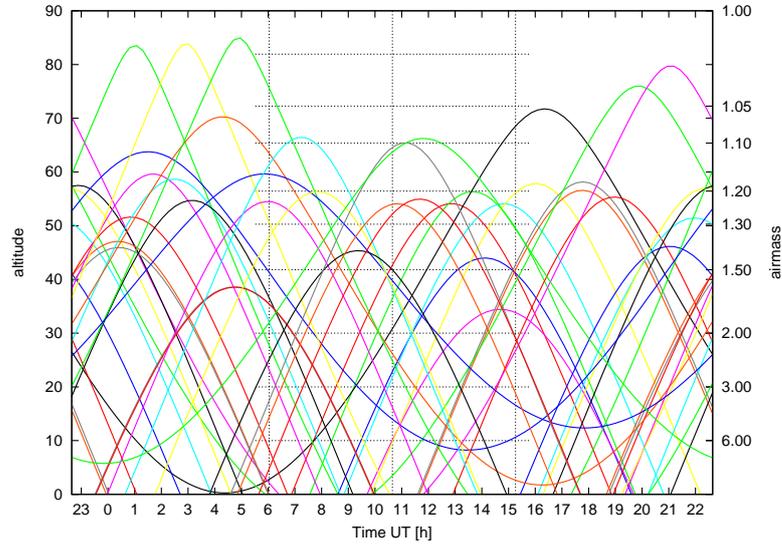


Figure 7.1: Altitude of targets used for first tests as function of time.

Schedule consists of observations with predefined total time. Valid schedule for this problem is any sequence of targets which fills requested time.

The algorithm work in the following steps:

- Initial random population is created
- Elite population is chosen. Only the most fit schedules are drawn for mating.
- Mating is performed using roulette wheel selection. Crossing operator is simple two fold crossing – random number r smaller then number of observations in a schedule is drawn. Two child are created – one with first r observations from the first parent and rest from second parent, the other with opposite parents chromosomes used.
- Mutation is performed. Random observation entry is picked and replaced by another random observation entry.
- Population number is increased
- If population number is bellow predefined population maxima, go to step 2.

Only schedule visibility ratio was used as fitness criteria. The results confirmed correctness of genetic algorithm implementation. Results for 30 test runs are presented in figures 7.2 and 7.3. It can be clearly seen that:

- it works - the visibility fitness converge towards 1

- the population converges pretty fast
- as targets are distributed along celestial equator, the average visibility fitness of a random observation schedule is 0.5.

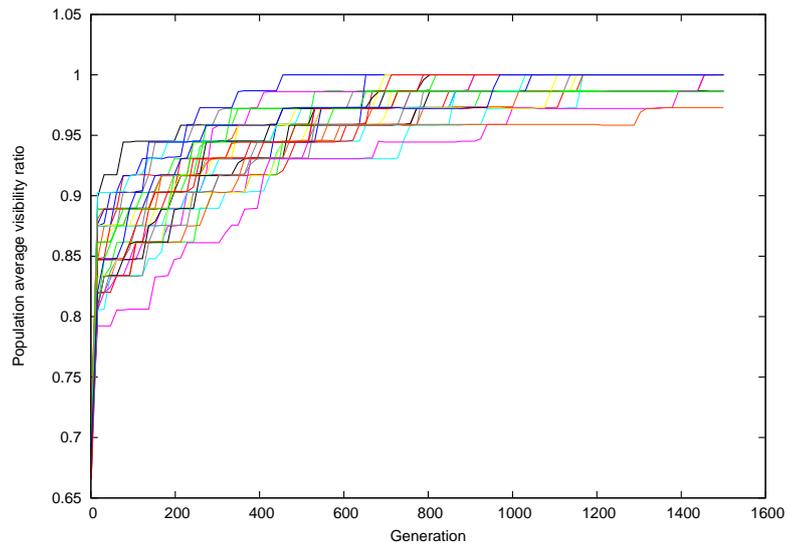


Figure 7.2: Convergence of the population average visibility ratio.

These tests confirm quick convergence of genetic algorithm. Quite nice results were a quick convergence of entire population to global maxima. Those results provided firm ground for further improvements.

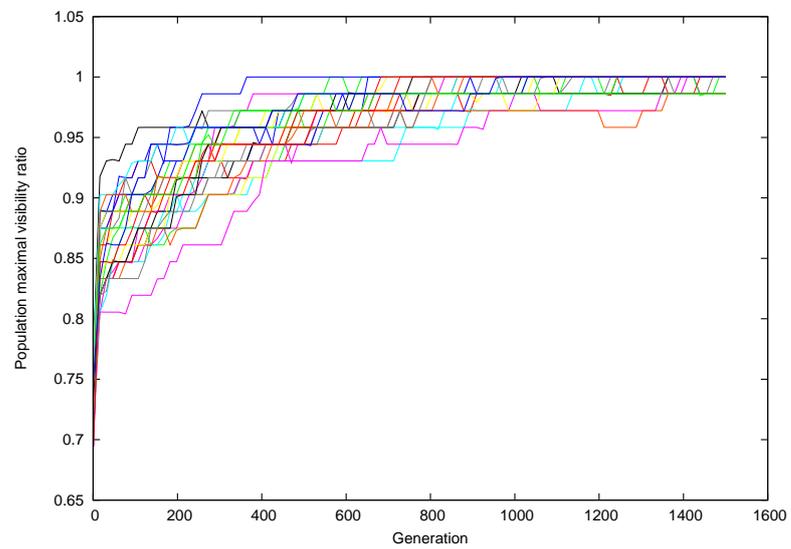


Figure 7.3: Convergence of the maximal visibility ratio.

Chapter 8

Results

The algorithm clearly identify Pareto optimal fronts. Figures 8.1, 8.2 and 8.3 shows altitude, observation distance and target diversity merits for different populations sizes.

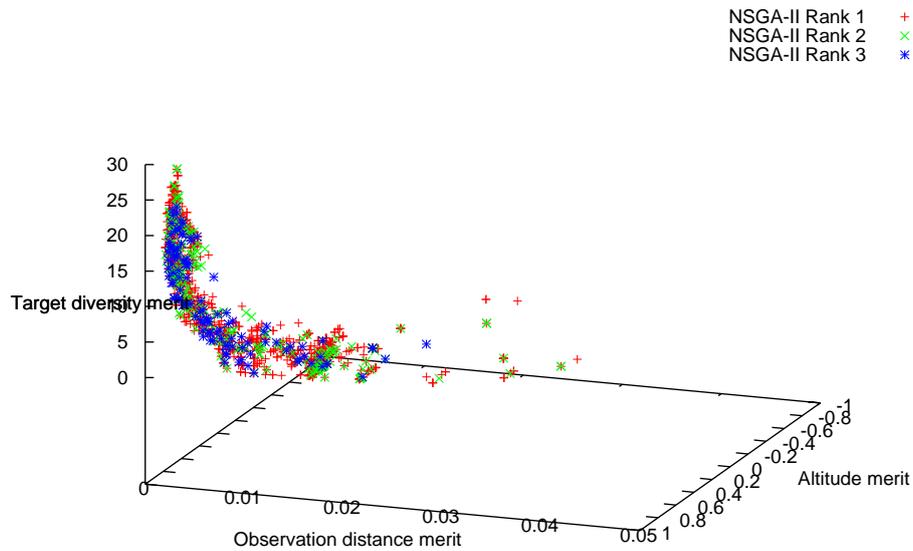


Figure 8.1: Pareto front, population = 1000, generations = 100

Tests against currently used single objective algorithm were carried. Figures 8.4 and 8.5 shows simulated altitude merit and distance merit functions versus

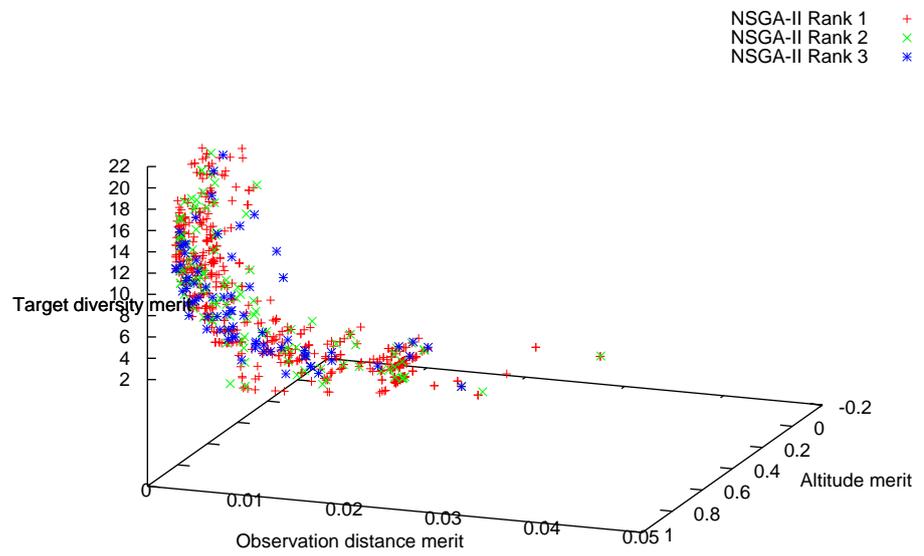


Figure 8.2: Pareto front, population = 500, generations = 100

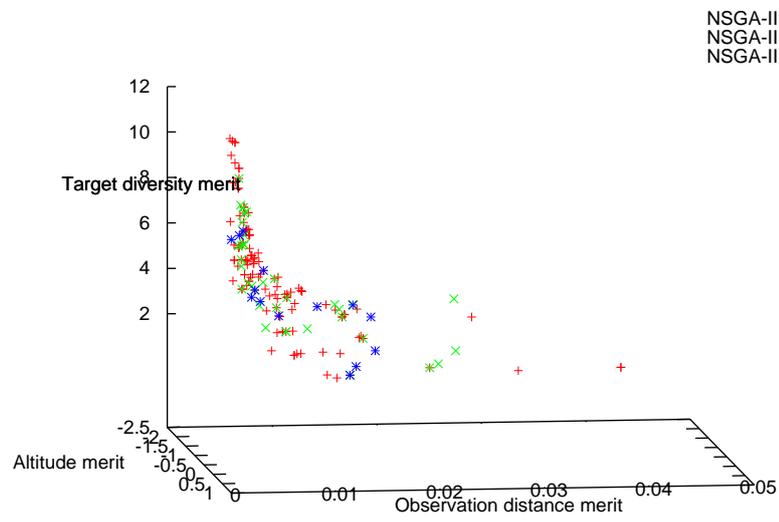


Figure 8.3: Pareto front, population = 100, generations = 100

observed merit and distance functions. Unfortunately account merit cannot be calculated, as this merit was recently introduced.

Altitude merit is in proportional units, where 1 means optimal altitude of the observations. Distance merit is in degrees - there lower value means lower slew times, and so better schedule. In both graphs, blue dots are difference between observed schedule and average of Pareto front schedules. There lower difference value means better NSGA-II scheduling simulation then current scheduler.

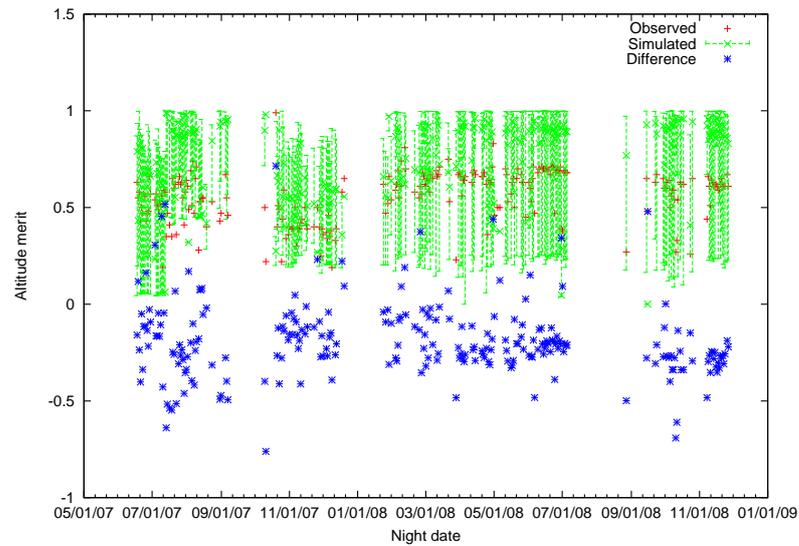


Figure 8.4: Altitude merits of a used single merit algorithm versus new NSGA-II scheduling

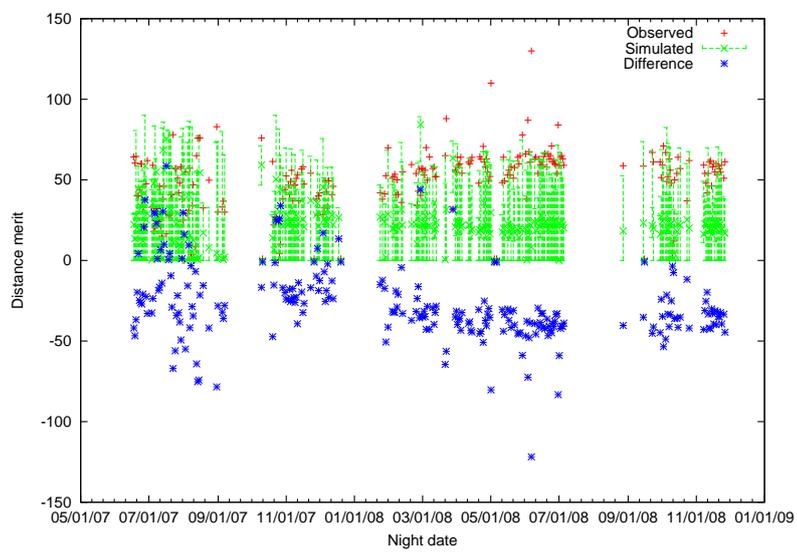


Figure 8.5: Distance merits of a used single merit algorithm versus new NSGA-II scheduling

Chapter 9

Conclusion

In this work was presented a novel approach to telescope scheduling, using Pareto optimal search genetic algorithm. Having Pareto optimum provides experienced observers with overview which observations are possible.

Complex autonomous telescope scheduling is a difficult task. It requires continuous adjustment of objectives, so the observatory remains productive for a various science goals. Also new observatory constraints can be introduced. Presented approach provides an easy and robust way how to add new objectives and constraints without a need to invest time and effort towards discovering heuristics and rules which will make scheduling working better.

Scheduling network of the autonomous observatories is a magnitude more difficult then scheduling of a single observatory. Yet the approach outlined in this work looks promising and provides solid base for a development of an algorithm for network scheduling.

The software is ready for live use on the telescopes of RTS2 network. It is expected that it will be used in production during first quarter of 2009.

Chapter 10

Further work

This work presents solid foundations for observatory and network scheduling. The expected further work is related to further development of the RTS2. This includes development of the central planning and monitoring facility, which will enable observers to continuously monitor network performance. This will also solve various operational issues and enables network scheduling. It is expected that the network scheduling functionality will be added to network in second quarter of 2009, at the time when Bootes 3 telescope, located on New Zealand, will start routine operations.

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