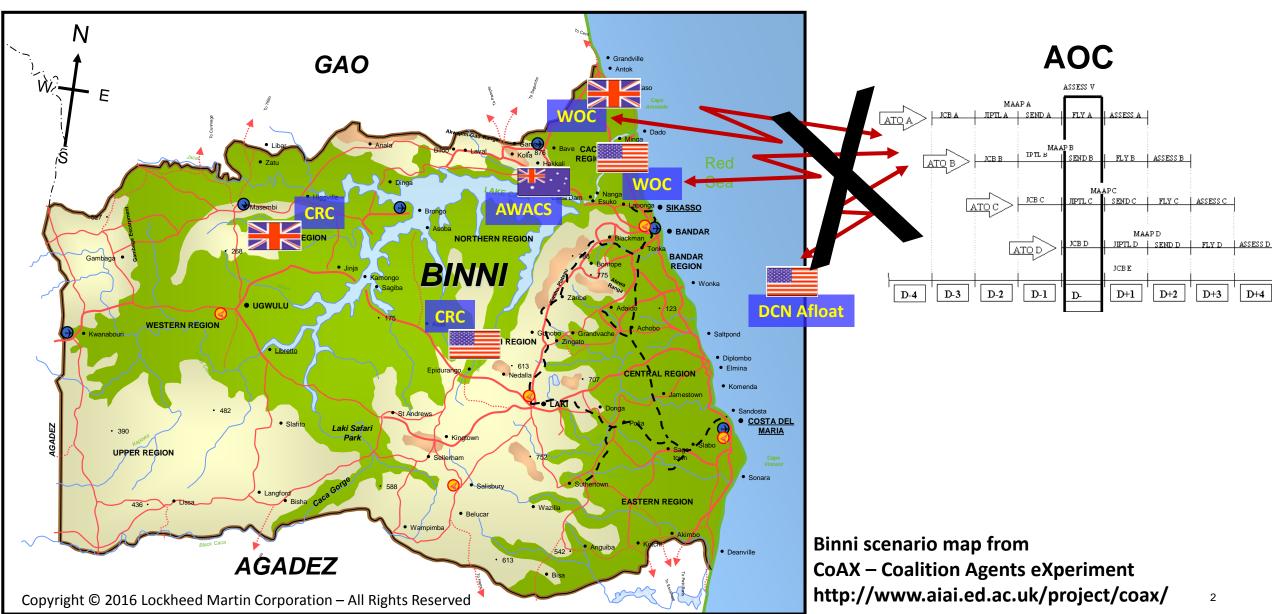
Resilient C2 in the A2/AD Environment

Martin O. Hofmann, Katherine Guo, Kevin Spivey, Rachel Hingst Lockheed Martin Advanced Technology Laboratories Cherry Hill, NJ 08002, USA

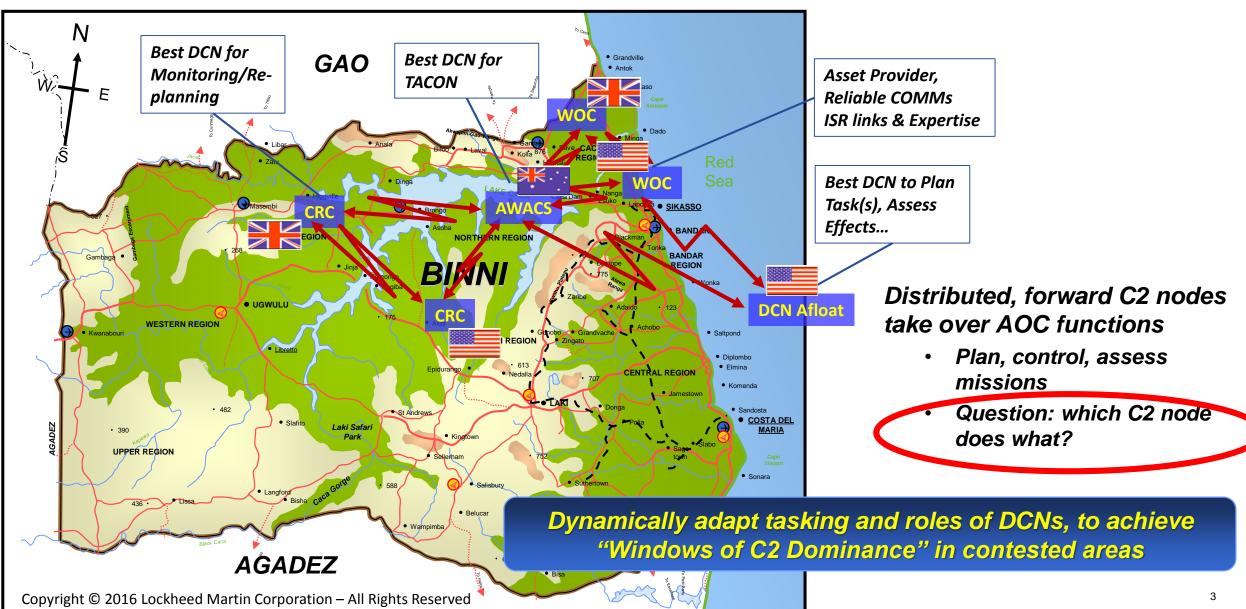
LOCKHEED MARTIN

Martin.Hofmann@Imco.com

Problem: Reachback to AOC is Threatened



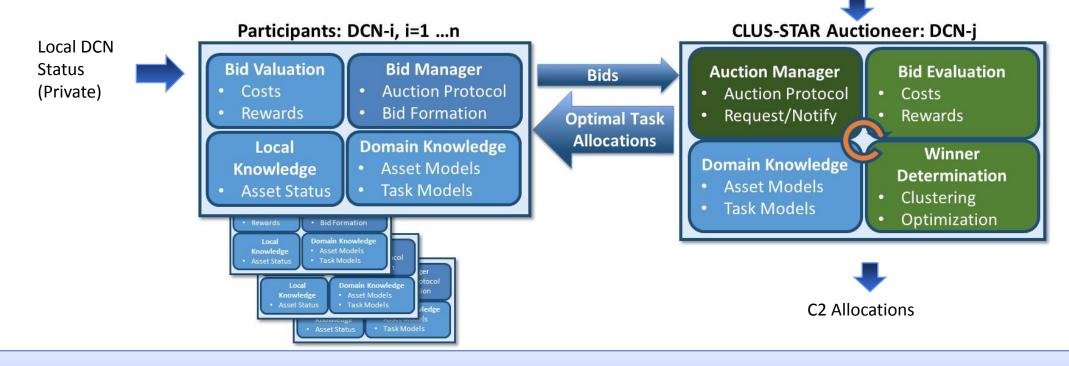
Solution: Distributed Control





Decision Support: Distributed Resource Allocation with C2 Nodes as Resources

- Optimizes the allocation of C2 tasks to the most appropriate DCN
- Dynamically re-allocates C2 tasks when needs/comms/capacities change



- "CLUS-STAR" Dynamic auction technique
- Result of IRAD and ONR investment
- Breaks allocation commitments in favor of higher-priority pop-up tasks
- Supports cooperation by multiple capabilities hosted on multiple platforms

Unallocated C2 Tasks

Low and very localized communications requirements

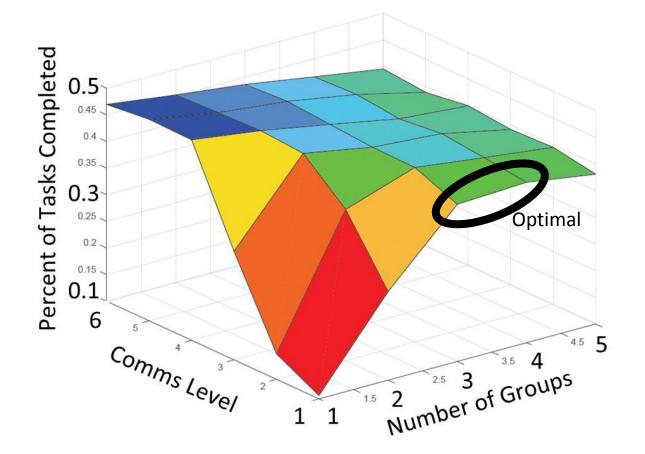
Domain Independent Models

- Tasks
- Assets
- Capabilities/ Proficiencies
- Rewards
- Priorities

- Task j is defined by $(\underline{t}_{j}, \underline{l}_{j}, \underline{req}_{j}, \underline{d}_{j}, \underline{p}_{j}, \underline{r}_{j}, \underline{Pr}_{j}, \underline{T}_{j}, T_{0j})$, where
 - $t_i \in \mathbb{R}_+$ is the release time of task j
 - $l_j \in G$ is the location of task j
 - $req_j \in \{0,1\}^k$ is a k-vector of 0 or 1 describing the requirements for performing task j along k dimensions
 - $d_j \in \mathbb{R}^k_+$ is a k-vector time duration needs of task j along its k dimension requirements req_i
 - $p_j \in \mathbb{R}_+$ is the penalty for not performing task j
 - $r_j \in \mathbb{R}_+$ is the revenue associated with the completion of task j
 - − $Pr_j \in \mathbb{R}_+$ is the priority of task j
 - $T_i \in \mathbb{R}_+$ is the deadline before task j has to be completed
 - $-T_{0i} \in \mathbb{R}_+$ is the time task j is schedule to begin

Easy to apply to a variety of problems: IRS asset allocation, C2 task allocation, etc.

Resilience to Intermittent Communications

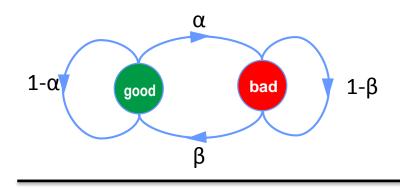


As communications degrade from perfect comms (Level 6) towards near total - 95% - loss (Level 1), the loss of SA and coordination messages favors the distributed algorithm over a centralized planner.

CLUS-STAR peer-to-peer solution is highly resilient to communications network degradation

Communications Model

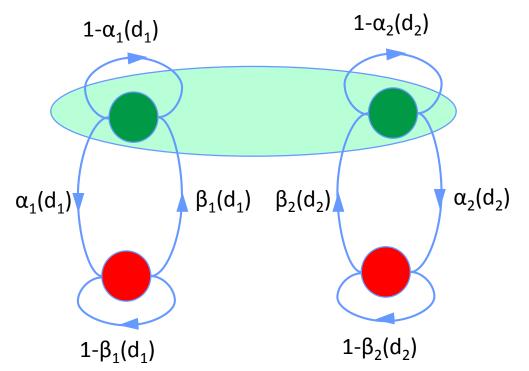
Two Stage Gilbert_Elliott Channel



α and β are parameterized by distance

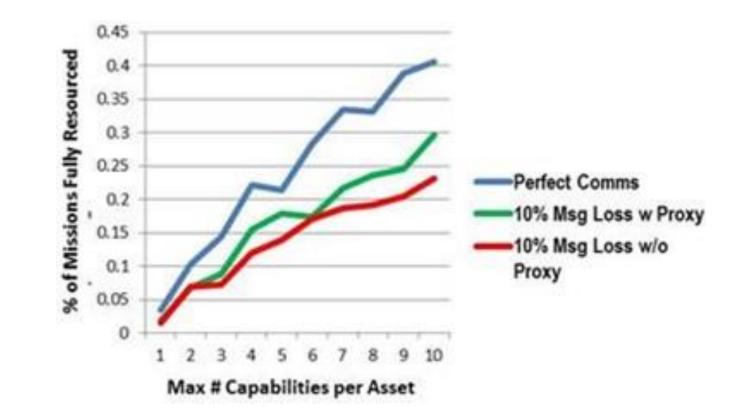
- Distance to the hot spots (d₁)
- Distance of communication (d₂)

To be able to communicate with its peer, the agent must be in an compound good state. The agent will keep trying to send until success (delay) or timeout (failure)



Algorithm Enhancements

- Anticipating change
 - Add a cost term that discounts the reward for assigning an asset to a task, if there is a high chance that the asset will be needed in the near future for a high priority mission
- Bidding Proxies bridge temporary disconnections
- Allocation by Percentage of a Resource



Modeling: Nodes and Tasks

- C2 Nodes ("Agents")
 - 1. Disctributed C2 Node (DCN)
 - 2. Wing Operations Center (WOC)
 - 3. Control and Reporting Center
 - 4. DCGS Reachback Unit
 - 5. Target Reachback Unit

Generic C2 Tasks

Plan TST	Plan Strike	Plan CAS	Plan DCA
Control TST	Control Strike	Control CAS	Control DCA
Asses TST	Assess Strike	Assess CAS	Assess DCA

TST: Time-Sensitive Target CAS: Close Air Support DCA: Defensive Counter Air



Capability Requirements Matrices

Task: Plan TST

Capability	Required?	% of Person		Capability	Required? (Y/N)	% of Person
Capability	nequireu:	70 UI FEISUII		Approving authority	Yes	
	/\//NI\			Ops Planner	Yes	
	(Y/N)		_	ISR Planner	Yes	
				Spectrum Planner Airspace Control	No Yes	
Approving authority	Yes	5		PED GEOINT	Yes	
<u> </u>				××××××××××××××××××××××××××××××××××××××	No	
Ops Planner	Yes	25		****	Yes	
Opsi laintei	103	23		*****	Yes Yes	
	Vac	20		xxxxxxxxxxxxxxxxxxxxxxxxx	Yes	
ISR Planner	Yes	30		XXXXXXXXXXXXXX	Yes	
				xxxxxxxxxxxx	No	
Spectrum Planner	No				Yes	
•				Weather	Yes	
Airspace Control	Yes	10			Yes	
	105	10		Link-16	Yes	
PED GEOINT	Voc	1 [×xxxxxxxxxxxx	No	
PED GEOINT	Yes	15		xxxxxxxxxxxxx	Yes	
				*****	Yes	
				****	No No	
				*****	No	
Weather	Yes	5		*****	No	
weather	103			****	No	
				****	No	
				*****	Yes	
				xxxxxxxxxxxx	Yes	
Link-16	Yes	10		*****	Yes	
				ROE	Yes	
				*****	Yes	
				xxxxxxxxxxxx	Yes	
ROE	Yes	5		****	Yes	
NUE	Tes	5		XXXXXXXXXXXXXX	Yes	



C2 Node Capabilities

Capability-People	#	Proficiency	Capability-Comms	Bool	Capability-Tools	Bool
Approving authority	2	1.0	VOIP	true	Chat	true
Ops Planner	2	1.0				
ISR Planner	0	1.0			AOI Coverage	
Spectrum Planner	0	1.0	Link-16	true	(Radar/COP/etc.)	false
Airspace Control	0	1.0	UpChannel – AOC	false		
PED GEOINT	0	1.0	Lateral - other C2	true	ROE	true
			DownChannel – unit	false		
					ATO	true
					No Strike List	True
			WOC (partia	l list)		

Scenario

Plan strike mission DAN – required by 1500 20 Oct 2020, typical C2 task duration 1 hour, priority 3 Control strike mission DAN – required by 1700 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Assess strike mission DAN – required by 2100 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Plan strike mission DBF – required by 1200 20 Oct 2020, typical C2 task duration 1 hour, priority 3 Control strike mission DBF – required by 1400 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Assess strike mission DBF – required by 1800 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Plan strike mission DBF – required by 1800 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Plan strike mission DDF – required by 1300 20 Oct 2020, typical C2 task duration 4 hours, priority 3 Control strike mission DDF – required by 1500 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Assess strike mission DDF – required by 1500 20 Oct 2020, typical C2 task duration 4 hours, priority 2

Plan strike mission DIF – required by 0930 20 Oct 2020, typical C2 task duration 1 hour, priority 3 Control strike mission DIF – required by 1130 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Assess strike mission DIF – required by 1530 20 Oct 2020, typical C2 task duration 4 hours, priority 2 Plan CAS mission 1 – required by 0200 20 Oct 2020, typical C2 task duration 2 hours, priority 3 Control CAS mission 1 – required by 0400 20 Oct 2020, typical C2 task duration 12 hours, priority 2 Assess CAS mission 1 – required by 1700 20 Oct 2020, typical C2 task duration 2 hours, priority 2

Plan DCA mission 1 – required by 0200 20 Oct 2020, typical C2 task duration 2 hours, priority 3 Control DCA mission 1 – required by 0400 20 Oct 2020, typical C2 task duration 12 hours, priority 2 Assess DCA mission 1 – required by 1700 20 Oct 2020, typical C2 task duration 2 hours, priority 2

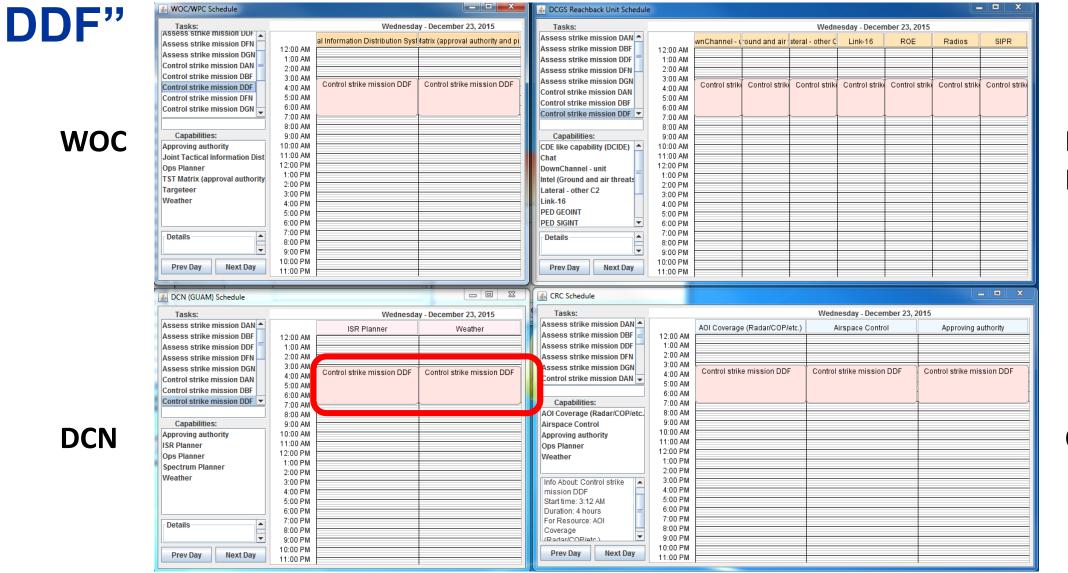
...

GUI: Allocations for one C2 Node

ScRC Schedule						_ 🗆 🗙
Tasks:			We	ednesday - Decembe	er 23, 2015	
Control strike mission DAN Control strike mission DBF	12:00 AM	overage (Radar/CO		Approving authority	Ops Planner	Weather
Control strike mission DDF Control strike mission DFN	1:00 AM 2:00 AM 3:00 AM	~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~~	Plan strike missio	Plan strike missio	Plan strike missio	Plan Cont
Control strike mission DGN Control strike mission DJF	4:00 AM 5:00 AM 6:00 AM			Control Control		Plan Cont
Capabilities:	7:00 AM					
AOI Coverage (Radar/COP/etc. Airspace Control Approving authority Ops Planner Weather	8:00 AM 9:00 AM 10:00 AM 11:00 AM 12:00 PM 1:00 PM 2:00 PM 3:00 PM			Control		Cont
Info About: Control strike mission DDF Start time: 3:12 AM Duration: 4 hours For Resource: Airspace Control	4:00 PM 5:00 PM 6:00 PM 7:00 PM 8:00 PM 9:00 PM 10:00 PM 11:00 PM					

CRC

Capabilities Allocated for "Control Strike



DCGS Reachback

CRC

Future Work



- Validate end user value proposition
 - Start by gathering SME feedback on the current design
 - Expose the concept to a set of operational users
 - Specify a richer set of user interaction beyond inspection of automated results
 - Prototype an interactive user interface
- Extensions
 - Design and implement conditional resource requirements, e.g., when allocation of a task across two nodes requires a higher level of communications capability between the two nodes.
 - Predictive modeling of denial actions (jamming, kinetic attack, cyber attack, spoofing, etc.) to enable proactive task re-allocation
 - Mixed-initiative allocation