

Colombia: Avances en Implementación del SMS y Programa del Estado.



A AERONÁUTICA CIVIL DE COLOMBIA



A Colombia: Avances en SMS





Colombia: Avances en SMS

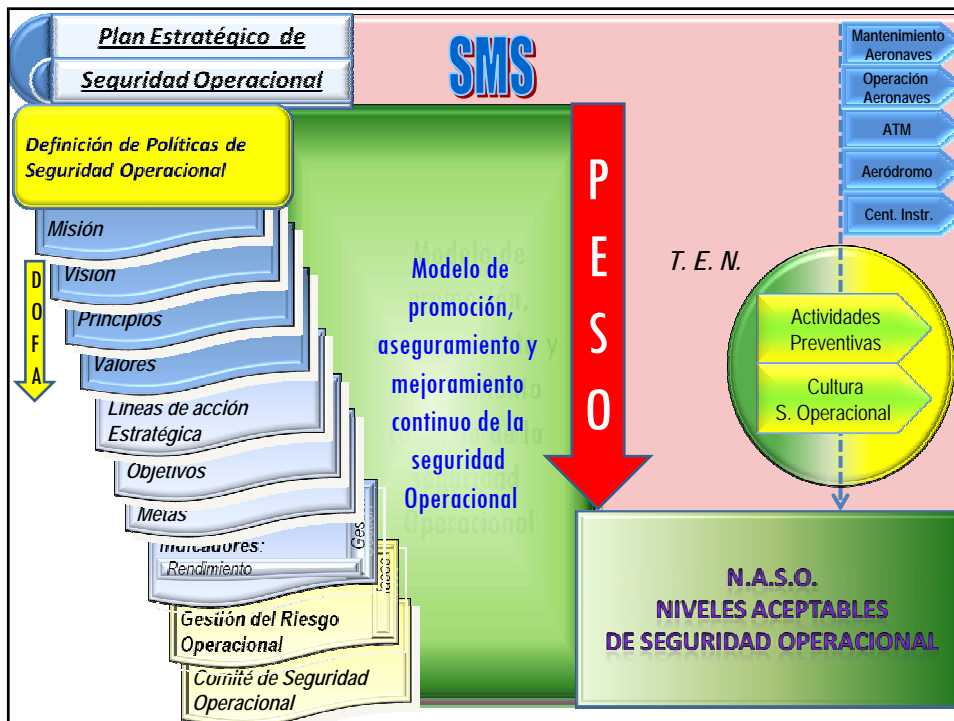


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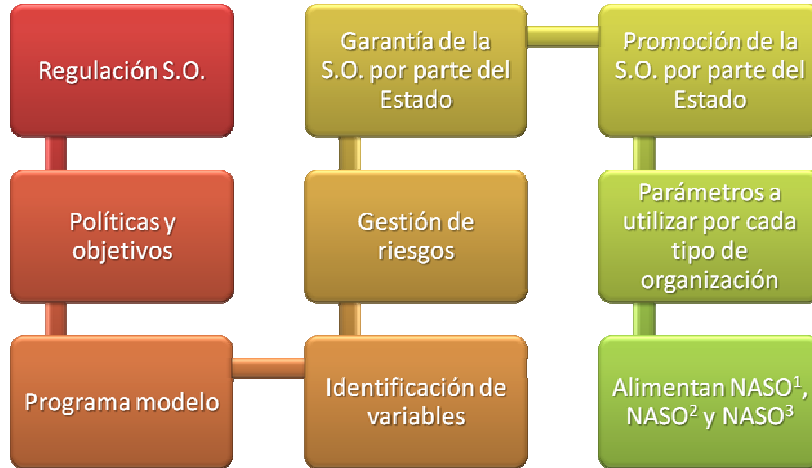
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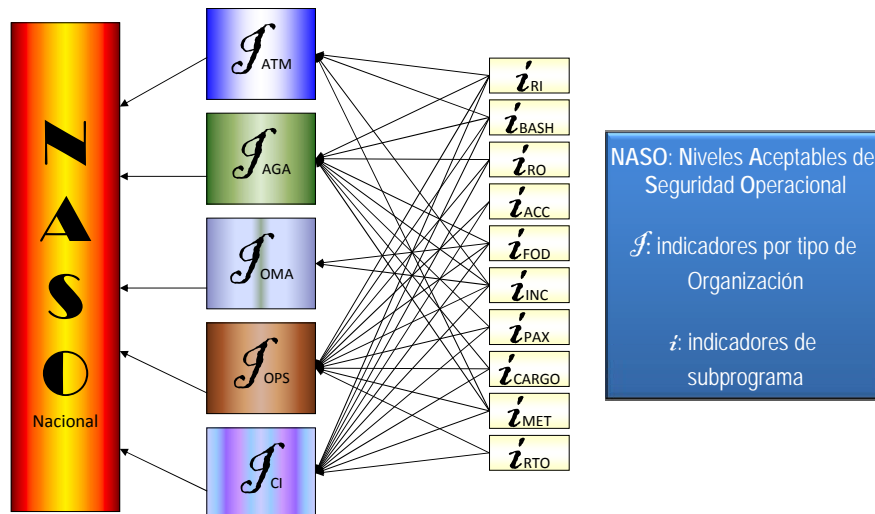
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Definición de Niveles aceptables de Seguridad Operacional





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Modelos matemáticos - NASO



- *Deben tener en cuenta:*

$$\text{NASO}_{\text{NaI}} = f(\mathcal{J}_{\text{ATM}}, \mathcal{J}_{\text{AGA}}, \mathcal{J}_{\text{OPS}}, \mathcal{J}_{\text{OMA}}, \mathcal{J}_{\text{CI}})$$



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Donde, por ejemplo:

$$\mathcal{J}_{\text{ATM}} = f(i_{\text{RI}}, i_{\text{BASH}}, i_{\text{GAP}}, i_{\text{MET}}, \dots)$$

$$\mathcal{J}_{\text{AGA}} = f(i_{\text{RI}}, i_{\text{FOD}}, i_{\text{GAP}}, i_{\text{MET}}, \dots)$$

$$\mathcal{J}_{\text{OMA}} = f(i_{\text{OPS}}, i_{\text{GAP}}, \dots)$$

$$\mathcal{J}_{\text{OPS}} = f(i_{\text{OPS}}, i_{\text{GAP}}, i_{\text{HL}}, \dots)$$

$$\mathcal{J}_{\text{CI}} = f(i_{\text{alumnos}}, i_{\text{categ entrenam}}, \dots)$$



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A su vez, de:

$$J_{ATM} = f(i_{RI}, i_{BASH}, i_{GAP}, i_{MET}, \dots)$$

Es necesario obtener:

$$i_{RI} = f(\# \text{ operaciones}, \text{ Horas pico}, \text{ Cat. aeródromo}, \dots)$$

$$i_{BASH} = f(\# \text{ operaciones x pista}, \text{ Horas pico}, \text{ categoría}, \dots)$$

$$i_{FFHH} = f(\text{duty}, \text{clasificación lenguaje proeficiency}, \dots)$$

$$i_{MET} = f(\# \text{ operaciones}, \text{ Cat. espacio aéreo}, \text{ radioayudas met}, \dots)$$



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$$i_{FFHH} = f(\text{duty}, \text{clasificación lenguaje proeficiency}, \dots)$$

Actores	Variación	Precusores de accidente					Otro agravante
		l: Language proficiency	c: Callsign mistake	f: fraseología no estándar	s: conciencia situacional	d: distracción / fatiga /stress	
p: Piloto	$\begin{pmatrix} \frac{\partial A_{p_i}}{\partial t} \\ \dots \\ \frac{\partial A_{p_j}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{pl}}{\partial t} \\ \dots \\ \frac{\partial X_{pj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{pc}}{\partial t} \\ \dots \\ \frac{\partial X_{pj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{pf}}{\partial t} \\ \dots \\ \frac{\partial X_{pj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{ps}}{\partial t} \\ \dots \\ \frac{\partial X_{ps}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{pd}}{\partial t} \\ \dots \\ \frac{\partial X_{pd}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial A_{p_i}}{\partial t} \\ \dots \\ \frac{\partial A_{p_j}}{\partial t} \end{pmatrix}$
a: Auxiliar	$\begin{pmatrix} \frac{\partial A_{a_i}}{\partial t} \\ \dots \\ \frac{\partial A_{a_j}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{al}}{\partial t} \\ \dots \\ \frac{\partial X_{aj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{ac}}{\partial t} \\ \dots \\ \frac{\partial X_{aj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{af}}{\partial t} \\ \dots \\ \frac{\partial X_{aj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{as}}{\partial t} \\ \dots \\ \frac{\partial X_{as}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{ad}}{\partial t} \\ \dots \\ \frac{\partial X_{ad}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial A_{a_i}}{\partial t} \\ \dots \\ \frac{\partial A_{a_j}}{\partial t} \end{pmatrix}$
t: técnico o mecánico	$\begin{pmatrix} \frac{\partial A_{t_i}}{\partial t} \\ \dots \\ \frac{\partial A_{t_j}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{tl}}{\partial t} \\ \dots \\ \frac{\partial X_{tj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{tc}}{\partial t} \\ \dots \\ \frac{\partial X_{tj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{tf}}{\partial t} \\ \dots \\ \frac{\partial X_{tj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{ts}}{\partial t} \\ \dots \\ \frac{\partial X_{ts}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{td}}{\partial t} \\ \dots \\ \frac{\partial X_{td}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial A_{t_i}}{\partial t} \\ \dots \\ \frac{\partial A_{t_j}}{\partial t} \end{pmatrix}$
r: Rampa	$\begin{pmatrix} \frac{\partial A_{r_i}}{\partial t} \\ \dots \\ \frac{\partial A_{r_j}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{rl}}{\partial t} \\ \dots \\ \frac{\partial X_{rj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{rc}}{\partial t} \\ \dots \\ \frac{\partial X_{rj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{rf}}{\partial t} \\ \dots \\ \frac{\partial X_{rj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{rs}}{\partial t} \\ \dots \\ \frac{\partial X_{rs}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{rd}}{\partial t} \\ \dots \\ \frac{\partial X_{rd}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial A_{r_i}}{\partial t} \\ \dots \\ \frac{\partial A_{r_j}}{\partial t} \end{pmatrix}$
c: Controlador	$\begin{pmatrix} \frac{\partial A_{c_i}}{\partial t} \\ \dots \\ \frac{\partial A_{c_j}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{cl}}{\partial t} \\ \dots \\ \frac{\partial X_{cj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{cc}}{\partial t} \\ \dots \\ \frac{\partial X_{cj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{cf}}{\partial t} \\ \dots \\ \frac{\partial X_{cj}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{cs}}{\partial t} \\ \dots \\ \frac{\partial X_{cs}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial X_{cd}}{\partial t} \\ \dots \\ \frac{\partial X_{cd}}{\partial t} \end{pmatrix}$	$\begin{pmatrix} \frac{\partial A_{c_i}}{\partial t} \\ \dots \\ \frac{\partial A_{c_j}}{\partial t} \end{pmatrix}$

