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The Editor *writes*

The idea of producing an algorithm for the detection of encounter is a useful one, but it is not clear why the author has chosen this particular form. It might have been preferable to have made some simple assumptions, such as taking the risk to be proportional to the relative velocity V_r, inversely proportional to the distance of closest point of approach D_{CPA}, and inversely proportional to the range $D(t)$. This would lead to an expression of the type:

$$\text{Risk} = k \cdot V_r / [D(t) \cdot D_{CPA}]$$

This could then be normalized and, if required, arranged to vary between the limits of zero and unity.